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MODULAR APPROACH FOR AN ASIC INTEGRATION OF ELECTRICAL DRIVE CONTROLS

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Abstract VLSI circuits design allows today to consider new modes of implementation for electrical controls. However, design techniques require an adaptation effort that few designers, too accustomed to the software approach, provide. The authors of this article propose to develop a methodology to guide the electrical designers towards optimal performances of control algorithms implementation. Thus, they were based on two concepts: modular design and algorithm architecture adequation. An exemple of DTC control implemented in an ASIC circuit is presented and the results of the integration performances valid our methodology.

Keywords ASIC, FPGA, Electrical System Control, Modular Design, Algorithm Architecture Adequation, Direct Torque Control.

چکیده امروزه، طراحی مدارهای VLSI حالتی جدید برای راه اندازی کنترل های الکتریکی است. به هر حال، روش های طراحی به تلاشی تطابقی نیاز دارد که تعدادی از طراحان خوگرفته به روش های نرم افزاری، آن را ایجاد می کنند. نویسندگان این مقاله، توسعه روشی را برای هدایت طراحان الکتریکی به سمت عملکردهای انتخابی برای راه اندازی الگوریتم های کنترلی پیشنهاد می کنند. بنابراین، آنها بر پایه دو مفهوم هستند: طراحی مدولار و معماری الگوریتم. تمام نمونه های راه اندازی کنترل DTC در مدار ASIC نمایش داده شده است و نتایج عملکردهای یکپارچه، روش ما را معتبر ساخته است.

1. INTRODUCTION

Power electronics and electrical drive controls are generally implemented by microprocessors or digital signal processor (DSP) solutions. Specific microprocessor architectures, including dedicated control and calculation functions for motor applications, have been developed by processor manufacturing [1]. From these software solutions, we can take advantage of fixed hardware architecture and extensive software flexibility which reduces the development cost.

A very large scale integration (VLSI) application has improved control implementation performance [2]. Indeed, an application of specific integrated circuit (ASIC) solution can exploit efficiently specificities of the control algorithms that fixed hardware architecture can not do. For example, parallel calculation cannot be included in

a software solution based on sequential processing [3]. In addition, ASIC can reduce wire and electromagnetic field interference by a fully system on a chip (SoC) integration.

However, there are still two main drawbacks to an integrated circuit solution: design complexity and reuse difficulty. This is true even with programmable logic device (PLD) solutions. Conception aid developer (CAD) combined with hardware description languages (HDL) and VLSI design methodology have accelerated conception and reuse [4]. Nevertheless, the main problem of integrated circuit design is to define the hardware architecture; this is particularly true for heterogeneous algorithm structures such as electrical controllers.

2. ELECTRICAL DRIVES STRUCTURE

To succeed ASIC integration of electrical controllers, the designer should take into account the heterogeneous algorithmic structures of electrical system, power environment and also integrated circuit constraints.

Figure 1 presents the structure of electrical systems. In the figure, the power environment and analogue interface are given as power source supply, controlled power converter, electrical load, sensors, amplifications, drivers and analogue to digital converters. The control algorithm is decomposed on four main functional blocks. Each block is done according its function and the hierarchy in the control algorithm [5]. The blocks are composed of independent and specific sub-algorithms which can be described by:

- treatment block: including sub-algorithms of treatment and transformation models (as direct or reverse Concordia transformation, direct or reverse Park transformation, ...).
- estimation block : including sub-algorithms of system estimation models (as flux and torque estimations, ...).
- regulation block: including sub-algorithms of regulation and control models (as hysteresis controller, PI controller, ...).
- modulation block: including sub-algorithms of power modulation models (as three-phase sine function, space vector PWM, ...).

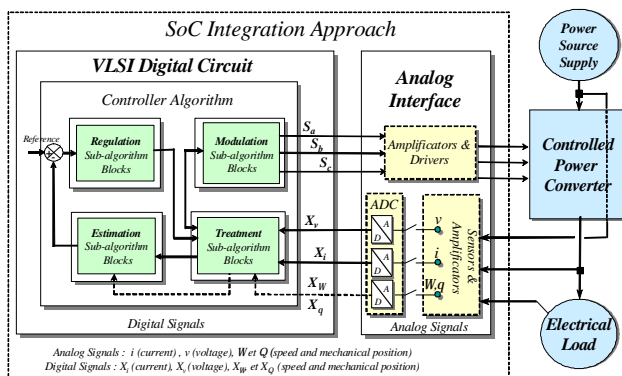


Figure 1. General structure of electrical system

3. MODULAR METHODOLOGY

3.1 Architectural Approach

IC architecture proposal is one of the most important hardware design steps. There are two main architecture approaches: the automatic and the dedicated approach.

Nowadays, designers generally use methods

based on behavioral synthesis principles to automatically extract a controller and an operative part by allocating operators and by arranging operations according to architecture constraints [6]. Behavioral synthesis is particularly adapted to improve designer productivity and design quality, but is not considered universal for all applications and algorithms. Indeed, we can only generate optimized hardware amount and processing time for homogeneous algorithm structures. Consequently, the automatic approach is not a suitable solution for an IC-based electrical controller. Indeed, control algorithms used in most electrical drive applications are heterogeneous structures. All these technical restrictions can be resolved with a dedicated approach. However, it requires a longer development time and real designer know-how.

Finally, in order to generate an optimal architecture for an electrical controller and from electrical drives structure, we combined both approaches by applying modular principles generally used in IC conception.

3.2 Modular Principles

For very complex designs, modular conception is generally used to reduce design cycle. This methodology is based on hierarchy and regularity concepts. Hierarchy is used to divide a large or complex design into sub-parts that are more manageable. Regularity is aimed to maximize the reuse of already designed components and subsystems [7]. The modular partitioning is generally guided by precise rules that are resumed in three main steps in design-flow [6]:

- **Partitioning:** The partitioning can be applied in order to split the system into simpler modules. This step allows producing a hierarchical modular decomposition of the initial system.
- **Module design:** Each module generated can be designed independently using a specific library of components. It may include either existing functional units or specific modules that have been designed during previous steps for example, arithmetic operators as multiplier, divider ... etc.
- **Module abstraction:** The abstraction of the module has to be done in order to enable its reuse as a complex library element.

The result of such a design flow is a modular architecture made up of control unit (called the top

controller) managing a set of modules (functional units FU) and linked by a communication network as illustrated in Figure 2. This architecture may be hierarchical and the composition of each functional unit may consist of another control unit and another set of functional units, and so on. The hierarchy ends with functional unit without local control, such as a basic arithmetic operator.

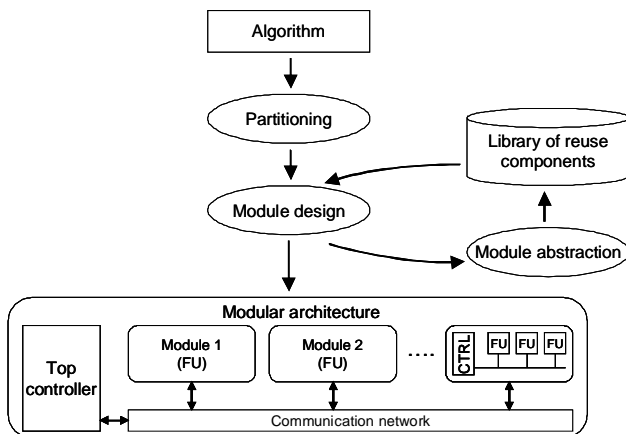


Figure 2. Modular design flow

4. MODULAR DESIGN FOR ELECTRICAL CONTROLLER

Like presented earlier, the idea of the modular methodology is to decompose the algorithm into modules that are separately designed, tested and included in the architecture. It means to reduce the development cost of complex algorithms as electrical controller. However, it is necessary to adapt the methodology to particular constraints of this application. To show the specificity of electrical controller, we will introduce an algorithmic partitioning how to structure the algorithm of electrical drives and after we will apply the modular principles to define a suitable architecture.

4.2 Modular Principles for Electrical Controller

4.2.1 Partitioning

For the electrical controller, the partitioning step is split into two stages called algorithmic and architectural partitioning.

4.2.1.1 Algorithmic partitioning

The most current approach, used by VLSI IC designers to describe an algorithm before to propose the suitable architecture, is to apply Data Flow Graph DFG principles [8]. We briefly present the DFG representation mode, then

provide specific rules used for describe general electrical controller algorithms. Finally, a DFG-based algorithm example will be studied.

Data Flow Graph approach

In the basic version of a DFG, each node represents an operation which consumes data before its execution and produces data after its execution. This approach introduces an order between the reading of data's on all inputs and the writing of resulting data's on all output. An algorithm description of an electrical controller depends obviously on a very large variety of DFG. Indeed, the choice of the granularity is not without consequence on the controller performances. The thicker granularity (thick granularity) enjoys the facilities for an algorithm implementation and the design should be improved in terms of time to market. However, this approach not only increases the execution time but also the hardware amount. On the other hand, a thin granularity offers a good implementation potential in terms of low cost and control performances, but naturally complicates strongly the design.

DFG description rules

From previous considerations, and to help the designer to describe the suitable DFG of his algorithm, we elaborated five DFG description rules, as given by:

- Rule 1: First, give a DFG description of each sub-algorithm block as referenced in the general structure of electrical controller, according to the following rules 2, 3 and 4.
- Rule 2: The nodes of the final DFG will exclusively correspond to:
 - basic arithmetic operators (thin granularity),
 - complex operators (thick granularity), existing in library,
 - complex operators not in library, if those represent a homogeneous iterative algorithm (for example, an integration by accumulation...) and can be easily evolved.
- Rule 3: Between an existing thick grain and its representation in thin granularity, the existing one should always be considered first. Moreover, when the constraints on execution time (delay) or integration density (hardware amount) are strong, the development in thin granularity is used. Thus, not only the hardware amount is reduced by sharing common hardware resources but also

execution time by increasing parallelisms of the algorithm.

- Rule 4: Analyze the parallelism of the algorithm from its DFG representation. It often generates periodic repetitions of identical motifs operating on different data. These motifs give the possibility of a hardware optimization by sharing the datapath, i.e. Functional Units (FU).

Case of the three-phases to two-phases transformation algorithm

To illustrate these description rules previously defined, we propose to compose from an algorithm commonly applied in electrical systems to transform a model expressed in three-phases (X_1, X_2, X_3) to two-phases (X_α, X_β), as given by the relation (1):

$$\begin{bmatrix} X_a \\ X_b \end{bmatrix} = \begin{bmatrix} C_{11} & C_{12} & C_{13} \\ C_{21} & C_{22} & C_{23} \end{bmatrix} * \begin{bmatrix} X_1 \\ X_2 \\ X_3 \end{bmatrix} \quad (1)$$

This algorithm can be described at different levels of granularity according to the existing modules and to the conception constraints. So as seen in Figure 3, using the proceeding rules 2 & 3, the relationship (1) can be represented by a unique top. This top is the biggest existing operator in our library, i.e. the matrix product PM_{ij} (i: row, j: column) with $i=2$ and $j=3$, as given by the relation (2):

$$PM_{23} = \begin{bmatrix} C_{11} & C_{12} & C_{13} \\ C_{21} & C_{22} & C_{23} \end{bmatrix} \quad (2)$$

However, to respect the delay and resource constraints, it could be necessary to decompose the operator in thinner granularity as multipliers and adders. At this new granularity level, respecting rules 2 and 4, we first try to parallelize the algorithm as much as possible. We can see such in the graph (a) of the Figure 3, which uses 6 parallel branches of multipliers and adders. Afterwards, by factorizing this repetitive pattern we obtain the graph (b) of the Figure 3, which reduces the hardware amount but in other hand increase the execution time. We can note that it is naturally possible to go down to lower level (i.e. logic gates). The final graph is thus a compromise between calculation time and resource amount, between factorization and dyfactorization (without factorization).

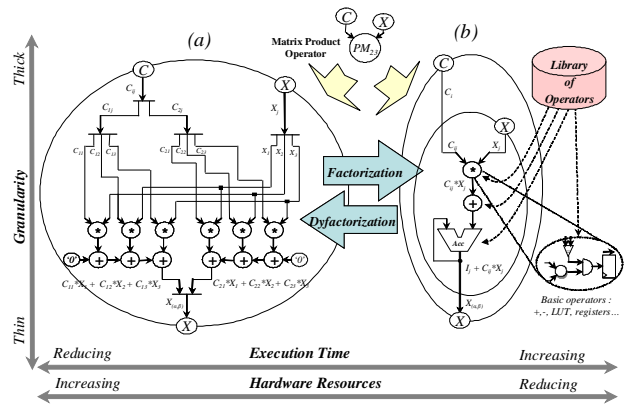


Figure 3. DFG representation of the relation (1)

4.2.1.2 Architectural partitioning

At the architectural partitioning stage the hardware amount of modules is allowed. Thus, independent modules, which compose final modular architecture, are extracted by regrouping the different sub-algorithms previously identified in algorithmic partitioning. Five rules are proposed to define architectural partitioning. These rules take into account the main constraints of the final IC: processing time, chip size, control performance, design flexibility, integration perspective and reusability.

Finally, the five rules are:

- regrouping in the same module sub-algorithms obtained from the similar functional block. The module thus developed can be proposed as a reused component of a design library.
- regrouping in the same module, sub-algorithms using the most constrained hardware amount or processing time.
- regrouping in the same module, sub-algorithms involve in analogue to digital and digital to analogue signal treatments, in a perspective of mixed analogue/digital integrated circuit.
- regrouping in the same module, sub-algorithms which can be applied to improve control performance.
- regrouping in the same module, sub-algorithms with homogeneous DFG. The aim is to use behavior synthesis to generate the architecture of this module.

Generally, these rules can not be used in same time because they are contradictory. In fact, the designer chooses the right one according to design constraints.

4.2.2 Module design Partitioning and module design are closely inter-related. The hierarchical decomposition may be influenced by the set of already existing modules in the library of reuse components (regularity concept). On the other side, the selection of the modules is influenced by the hierarchical decomposition of the design. The power and flexibility of such scheme depend on the range of components that may be used in the library. For the electrical designer, the problem is summed up to initialize the design flow by defining an appropriate library of reuse components.

From the sub-algorithms order defined at algorithmic partitioning, we have built a library of reuse components with two main categories as shown in Figure 4.

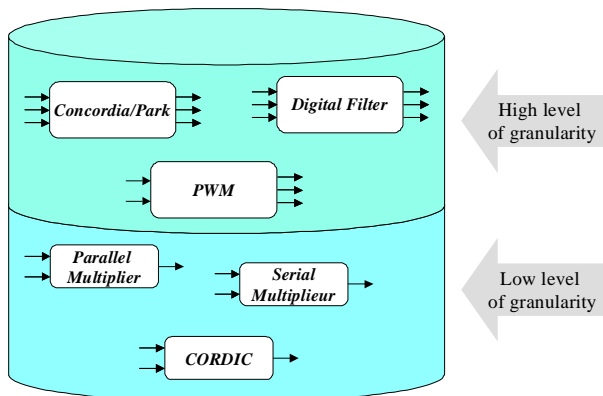


Figure 4. Library of reuse components

The first category is dedicated to complexes electrical controller sub-algorithms (thick grain) [9]. In our case, we have defined three components for standard electrical sub-algorithms of each algorithmic block, defined in electrical drives structure, as:

- Concordia/Park component corresponding to treatment block.
- Digital filter component corresponding to estimation and regulation blocks.
- PWM (Pulse Width Modulation) component corresponding to modulation block.

The second category is dedicated to arithmetic operators (thin grain) [10] as:

- Parallel multiplier based on Booth2 algorithm. This algorithm allows reducing multiplier execution time but increase hardware amount.
- Serial multiplier based on Baught-Wooley algorithm. The serial multiplier has an optimized area rather than execution time.

- CORDIC (COordinate Rotational Integrated Circuit) operator which execute rotational operation, dividing operation, logarithmic operation, ...

In order to validate each component of the library, an ASIC or FPGA integration of a prototype was made and results were resumed in Table 1 here after.

TABLE 1. The hardware integration results of reuse components

Component	Technology	Data Format (bits)	Hardware amount (mm ²)
Concordia/Park	ASIC AMS 0.6 μ m	16	2.2
PWM	ASIC AMS 0.6 μ m	12	2.5
Digital Filter	FPGA EPF10k250AGC5 99-1	16	6799 LCs
Parallel Multiplier	ASIC AMS 0.6 μ m	16	1.5
Serial Multiplier	ASIC AMS 0.6 μ m	16	0.43
CORDIC	ASIC AMS 0.6 μ m	16	1.25

LC : Logic Cell

To reduce development cost, the library also includes a set of basic reused components as: storage units (memories, registers ...) and communication units (multiplexers, switches ...). All of the reuse components are described in VHDL language at register transfer level.

4.2.3 Module abstraction The design reuse consists to reuse components of any degree of complexity. In our case, these components are developed in VHDL at register transfer level. Thus; they can be reused as black boxes or macro-blocks such a design situation is illustrated in Figure 5.

Starting from a main algorithm and partitioning steps, the designer use a set of components instances to build the modular architecture. From this design scheme, reused components with thick granularity are used as coprocessors in order to execute operations of main algorithm. In fact for the modular architecture, the synchronization is much less rigid than in the flat architecture as each module may run independently and in parallel with any other

module of the architecture. Communication between modules and the top controller allows exchanging data according to predefined protocols. We assume that all modules share a common clock. However, each module may have other local clocks. For a reused components with thin granularity (arithmetic operators), these components are used as a macro-blocks because they are defined as a functional unit without controller.

From this design flow, the main pieces of information necessary for the abstraction of a module for its reuse are:

- the operations it can execute,
- the communication protocol: control signals, clock, ...
- the timing scheme,
- the synthesis constraints.

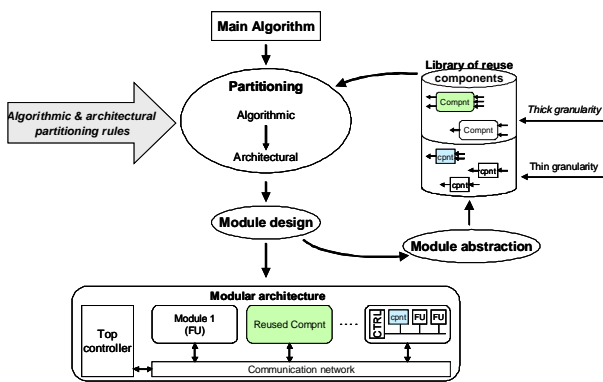


Figure 5. Modular design flow for electrical controller

5. MODULAR DESIGN VALIDATION

5.1 DTC Modular Decomposition To validate modular design flow for electrical controllers, we developed a modular architecture for an ASIC-based DTC (Direct Torque Control) algorithm of an asynchronous motor. Since, DTC structure is simple; it can be used to several AC motor types (asynchronous, synchronous ...). This control method insures excellent speed or torque control without any mechanical information. Moreover, sensitivity to machine parameters is lower for the DTC in comparison with classic vector control structures [11].

To make the validation, we consider a set of integration constraints such as:

- Integrate DTC controller into ASIC target in a perspective of mixed analogue/digital integrated circuit.

- Increase the DTC control performances using the specificity of hardware integration.
- Improve development time

From the DTC algorithm and DFG description rules previously presented (paragraph 3.2.1.1), we define at algorithmic partitioning step 4 sub-algorithm blocks as illustrated in data flow graph of Figure 6.

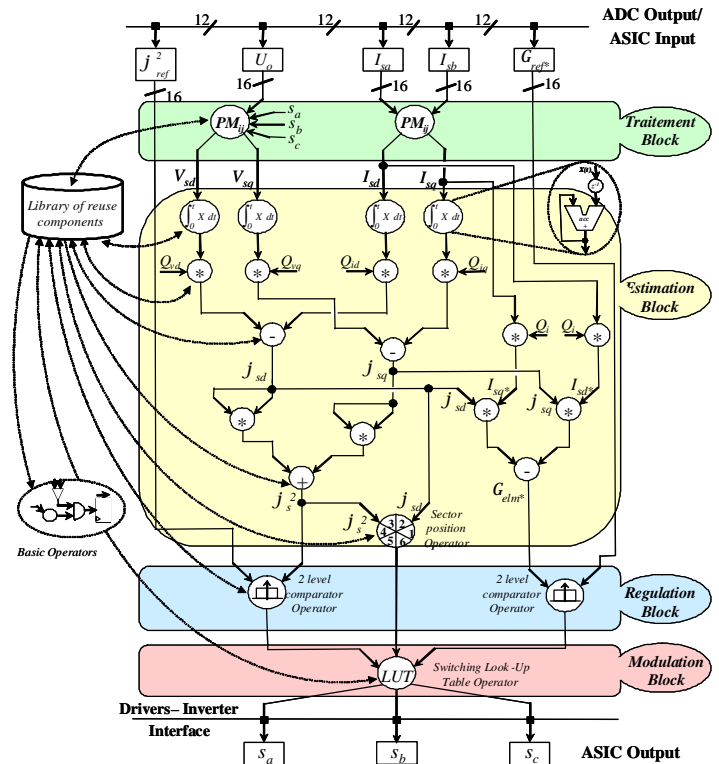


Figure 6. Data flow graph of DTC algorithm

The treatment block encloses two Concordia transformations which are represented with thick grain operators. These operators correspond to the matrix product of Concordia.

The estimation block includes sub-algorithms which compute flux ($j_s, j_{sd,q}$), torque (G_{elm}) and flux sector position (d). The DFG of this block is defined with thin grain arithmetic operators as: adder, multiplier...

The regulation block contains two similar sub-algorithms, torque and flux hysteresis comparators, characterized with thick grain operators called 2 level comparator operator.

The modulation block includes drivers switching table. It represented with thick grain operator named switching look-up table operator.

The DTC algorithm is implemented with 16 bits data format. We choose this format following previous study presented in [12, 13].

Now, the design constrains and DFG of DTC algorithm are fixed, we regroup, at architectural partitioning step, the four sub-algorithm blocks in three modules according to the rules presented in paragraph 3.2.1.2.

- **Interface module:** the direct Concordia transformation sub-algorithm is proposed to build a unique module called the interface module. Indeed, this sub-algorithms is involved, via the sensors/amplifiers and the ADC of the control system, in an analogue to digital signal treatment. Thus, the module can be considered in a viewpoint of mixed analogue/digital integrated circuit. Moreover, in reuse perspective, the sub-algorithm can be included in a generic module regrouping other transformation algorithms used in electrical control algorithms as Clarke or Park transformations. The architecture of the module contains a functional unit and a local control unit. The functional unit is composed by a look-up table (LUT) and a set of reuse thin grain components as: adder/subtractor, shift register Thus, the hardware amount of the architecture is optimized. In fact, the LUT and shift register avoid using the multiplier operator to compute the matrix product. The local control unit is employed to manage the ADC and the data in the FU.
- **Computation module:** motor model sub-algorithms require the most important hardware operator resource in opposite to the others controller sub-systems. Therefore, we choose to regroup all these sub-systems in one module, called computation module, in order to optimize the hardware amount of the final chip. To design this module, only one functional unit describes the architecture of the computation module which is composed by: an Arithmetic Logic Unit ALU (32-bit/32-bit Adder/Subtractor, a 32*16-bit Multiplier based on reuse parallel multiplier and a transmission operator to transfer data's between registers), a specific register-file (8 registers of 16-bit and 4 registers of 32-bit), and finally a ROM of constants.
- **Control module:** output data's of the switching logic table sub-algorithm are involved, via the amplifiers and inverter drivers, in a digital to analogue signal treatment. Furthermore, the two simple hysteresis controllers are similar

sub-algorithms. They can be regrouped with the flux zone position and the switching logic table sub-systems in a same module in order to improve control performances of DTC algorithm such as presented here. The architecture is built with a functional unit without control and composed of 3 operators: a position estimator, a hysteresis controller and a LUT.

The top controller of the modular architecture is applied to control the FU of computation module. It also used to manage data transmission with the two other modules (Interface and Control). In order to optimize the top controller architecture and circuit debugging, a programming approach by microcode is proposed [14]. Also in order to compare the performances of the architecture, two kinds of controller were developed: controller with finite state machine (FSM) and controller with pipeline. The pipeline controller works at 25 MHz (1 instruction/40ns clock cycle). The figure 7 shows the modular architecture of DTC algorithm.

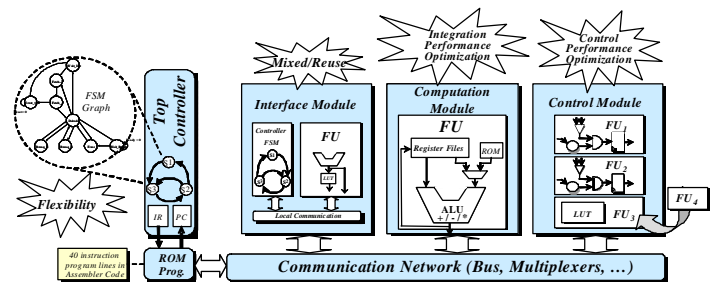


Figure 7. DTC modular architecture

5.2 DTC Validation To validate the DTC modular architecture, we have developed a mixed analogue/digital simulation based on HDL languages for the DTC controller and its electrical environment [15]. In fact, the power environment and analogue interface (sensors, analogue to digital converter, load...) are described in SpectreHDL and DTC architecture in VHDL.

5.2.1 Improving Torque Control by DTC architecture modification

Identification of DTC control defaults

In order to respect technical constraints of power inverter, the sample period of the controller should never exceed the switching limit given by the manufacturer. However, it is well-known that in

those sampling conditions, precision of control and stability are not satisfactory. It is particular true in the case of the DTC which used hysteresis controllers to correct torque regulation. Thus, ripples can be observed on the controlled torque which can be reflected on the driving shaft and caused damage on the structure [16]. Many researches in literature propose several control strategies or new structures to limit those effects [17- 19]. However, the proposed solutions always increase the controller algorithm complexity which is restricting for ASIC integration in terms of hardware amount and execution time.

New DTC strategy based on hardware solution

To improve DTC regulation and decrease torque ripples, we propose to reduce the sampling period of the controller, as much as possible. Thus, torque derivation could change faster than previously, avoiding consequently important torque overtaking. In the other hand, latency of electrical systems, using power inverter, is not low enough to justify high sampling frequency. However, by including an authorization mode in the original DTC strategy, only suitable and required signals will be propose to control switches of the inverter associated to the induction motor. Thus, a minimal sampling period (T_{com}) should be fixed and never be shorter than a sampling period multiple ($k T_e$). In the opposite case, the control signal transmission would not be authorized, as shown in the Figure 8.

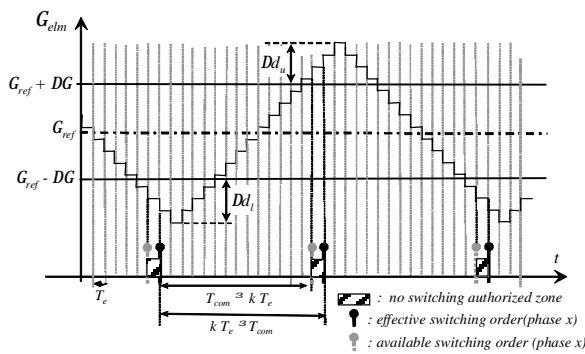


Figure 8. Torque response based on new DTC strategy

New control module architecture

Control Module architecture must be composed in part with elements of the previous DTC architecture, as torque and flux hysteresis comparators, position flux estimator and switching control Look-Up Table (LUT). And in another

part with elements of the new architecture which can be carried out from rudimentary components, as shown in the Figure 9.

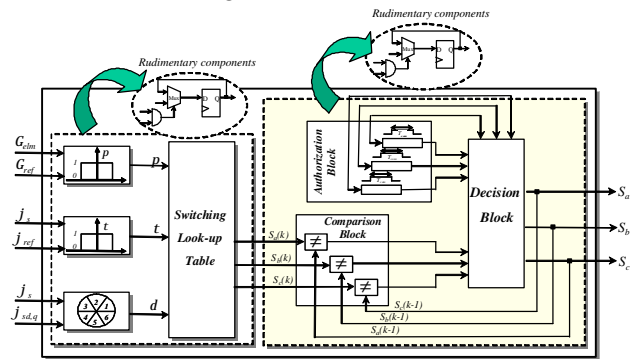


Figure 9. Control Module architecture

Three new elements will be added to the previous Control Module architecture, so called decision block, authorization blocks, and difference blocks. The decision block receives information from authorization blocks and difference blocks. Thus, difference blocks allow to detect difference between switching control signals $S_{a,b,c}$ at sampling periods $(k-1)$ and (k) . In case of difference, the decision block will applied the new control signal, on condition that authorization blocks authorize signal generation. In the opposite, the control decision will be reported at the next sampling period $(k+1)$. Once switching control signal sent, authorization blocks is fixed to prevent any new sending during a minimal switching period (T_{com}) which is given in specification of the control system.

Validation results

Figures 10(a) and 10(b) show torque regulation performances with previous and new DTC strategy. The torque is controlled around its reference 10 N.m with a simple hysteresis correction: ± 0.25 N.m for a flux reference: 0.8 Wb. In case of new control method, sampling and minimal switching periods are respectively given by $T_e = 2\mu s$ and $T_{com} = 30\mu s$.

To validate contribution of new DTC strategy in torque control performances, a torque resultant value was estimated. Thus, a significant reduction of torque overtaking can be observed since it reaches only 0.25 % instead of 6.75 % with classic DTC method.

Finally, the modular structure allows improving performances of the whole modular architecture by a simple local modification. In a perspective, many applications can be considered with the modular approach as predict control.

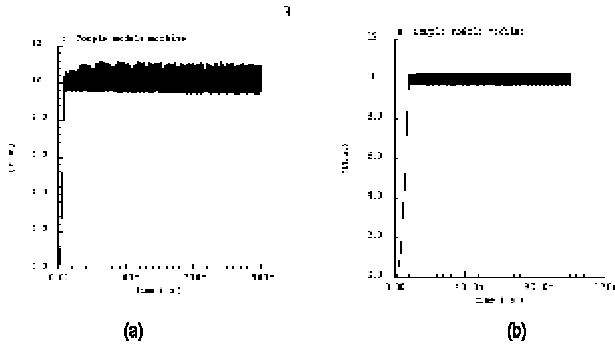


Figure 10. Instantaneous torque response obtained from HDL models

(a) classic DTC method ; (b) DTC with new control strategy

Experimental validation

The architecture was validated by using the test-bench engine of the Figure 11-a. This bench is mainly constituted by an asynchronous engine (Figure 11-c) and an in-house card based on ALTERA Flex 10K100A RC240-1 FPGA (Figure 11-b).

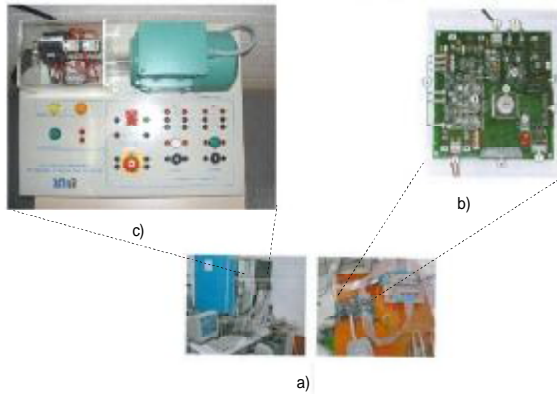


Figure 11. Experimental test-bench

(a)test-bench ; (b) in-house FPGA electronic card ; (c) engine

The Figure 12 presents experimental results. Figures 12-a and 12-b show the starting up until the established phase, the evolution of torque and rotor flux constituents φ_q and φ_d , respectively. The Figure 12-c presents $\varphi_q = fct(\varphi_d)$

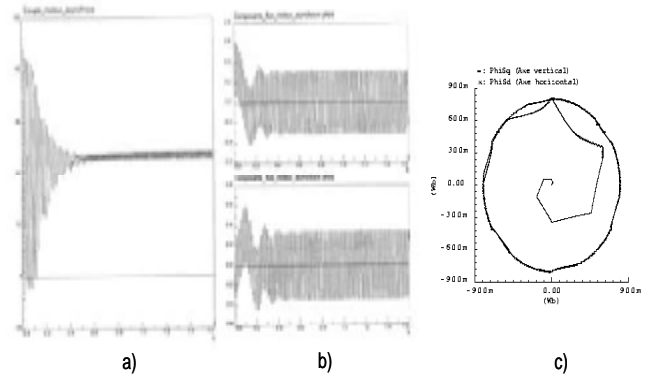


Figure 12. Experimental results

(a) torque ; (b) rotor flux φ_q and φ_d ; (c) $\varphi_q = fct(\varphi_d)$

5.2.2 Hardware Implementation Results

The Table 2 compares FPGA and ASIC hardware solutions by implementing modular DTC architecture on an Altera Flex 10K100 FPGA (3V, 25 MHz) and on a AMS 0.6 μm ASIC (3.3V, 25 MHz). In the case of FPGA target, we also compare, for computation module, the performances obtained with LPM multiplier from Altera’s library of parameterized modules and our reuse multiplier based on Booth2 algorithm.

The FPGA hardware resources rate is nearly 56% with approximately 2496 logic cells used for 4992 available. The execution time of the circuit can reach 2.3 μs (pipeline controller) for at least 4,48 μs (FSM controller). As expected, ASIC implementation results are much better in term of speed processing with 1.8 μs (pipeline controller) for at least 3.44 μs (FSM controller). In term of integration density, a useful integrated surface reaches 4.5 mm^2 .

As planned, size of the computation module of the DTC architecture is much bigger than Interface Module and Control Module. In detail, adder/subtraction and multiplier operators used in the Computation module are respectively based on Carry Look-Ahead and Booth2 algorithms which constitute respectively 10% and 75% of the size chip. Moreover, the execution time of the computation module given in Table 2 represents the time for a multiplication operation with the result stored in the register file.

TABLE 2. FPGA and ASIC Integration results for DTC implementation

Architecture		Execution Time (ms)		Integration Density		
Modules	Types	FPGA	ASIC	FPGA -amount resources- (%)	ASIC -useful surface- (mm ²)	
Interface Module	Multiplexer data-path type with FSM controller	1.2	0.8	8.57	0.7	
Control Module	Multiplexer data-path type	0.3	0.24	4.5	0.4	
Computation Module	Multiplexer data-path type	Mult. LPM	-	38.6	-	
		Mult. Booth 2	0.87	0.08	33.31	3
DTC Modular Architecture	Multiplexer data-path type with FSM controller	Mult. Booth 2	4.48	3.44	56	4.5
	Multiplexer data-path type with pipeline controller		2.3	1.8	56	4.5

The different hardware results show that the developed architecture is in excellent appropriateness with the modular partitioning applied to DTC algorithm. The Figure 11 shows the final DTC ASIC layout with the new control strategy for AMS 0,6µm technology. Benefit of the modular approach is shown.

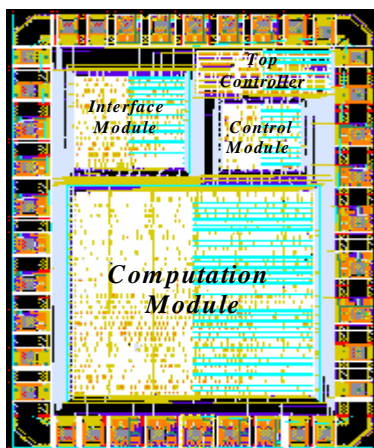


Figure 11. Final ASIC Layout of DTC modular architecture

5.2.3 Reuse results In order to prove the interest of the modular method to reduce conception time, we have developed a DTC architecture based on reuse Concordia/Park component (thick grain in the library of reuse components). Thus, the interface module was replaced with Concordia/Park component without modification of the other modules. In order to measure the profit in conception time, we use the simple relation (3) given by:

$$\text{Profit} = \frac{(\text{Number of modules} * 100)}{\text{Number of reused modules}} \quad (3)$$

In the case of DTC controller, the profit reaches 33%.

Table 3 compares the ASIC results for both DTC architectures.

TABLE 3. ASIC integration results for DTC architecture based on with/without reuse Concordia/Park component.

DTC	Technology	Data (bits)	Clk (ns)	Execution Time (μ s)	Hardware Amount (mm^2)
Without thick grain	AMS 0.6 μ m	16	20	1.8	8.7
With thick grain	AMS 0.6 μ m	16	20	1.8	11

The results are in accordance with the granularity effect developed in 3.2.1.1. In fact, the thicker Concordia/Park component allows reducing design time but increasing the hardware amount of the final architecture.

6. CONCLUSION

In this paper, the authors develop a new architecture approach for electrical controllers. They propose to apply modular design principles quite well-known nowadays in microelectronic industry. Specific modular partitioning principles were defined, and then these modules are regrouped into a modular architecture. The methodology developed is principally based on a library of reuse components. In fact, we have developed library of reuse components in two categories: high and low level of granularity. This approach was then used to design an ASIC integrated solution for a vector control structure called DTC. Three modules are identified and the architecture of each of them described. In order to reduce debugging time and improve design flexibility, a specific programmable architecture based on a microcode is proposed. Finally, the modular architecture optimized both hardware amount and processing time, making easier design reuse of circuit was presented. This example of modular development is shown to prove the contribution of the proposed approach in improving hardware results, controller performances and conception time that reach 33% compared with classic design.

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