

PWM Frequenz = 20kHz, Speed = 300, Verschiebung Winkelberechnung = 0

SinusU = pM->dV;

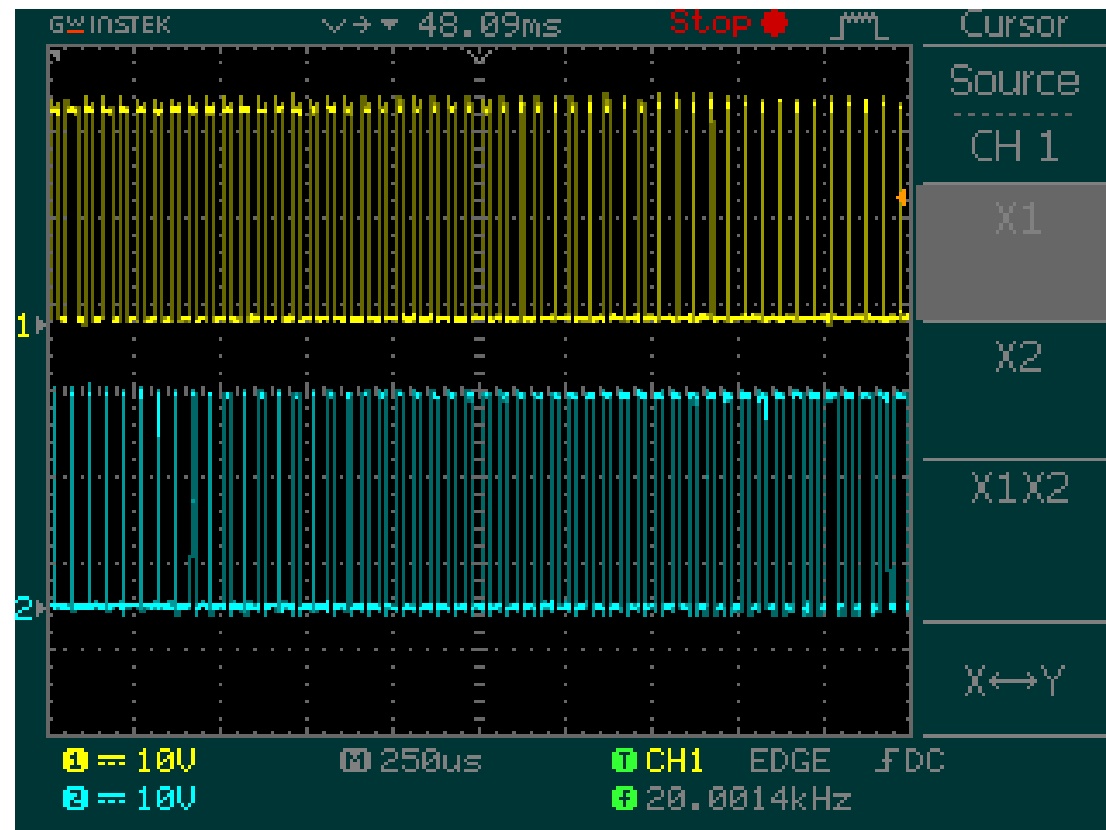
SinusV = pM->dW;

SinusW = pM->dU;

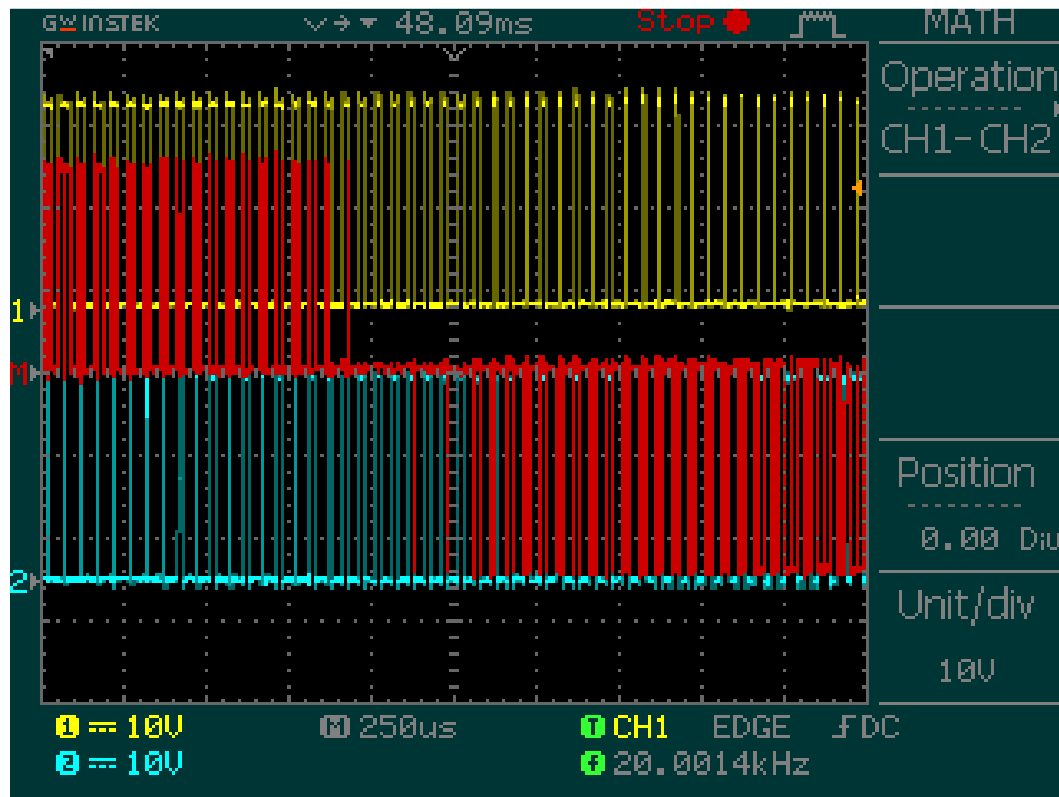
CH1 = Phase U

CH2 = Phase V

#define UI\_PARAM\_SENSOR\_POLARITY SENSOR\_POLARITY\_LOW



Das gleiche Bild mit dem math Kanal CH1-CH2.



PWM Frequenz = 2kHz, Speed = 300, Verschiebung Winkelberechnung = 0

SinusU = pM->dV;

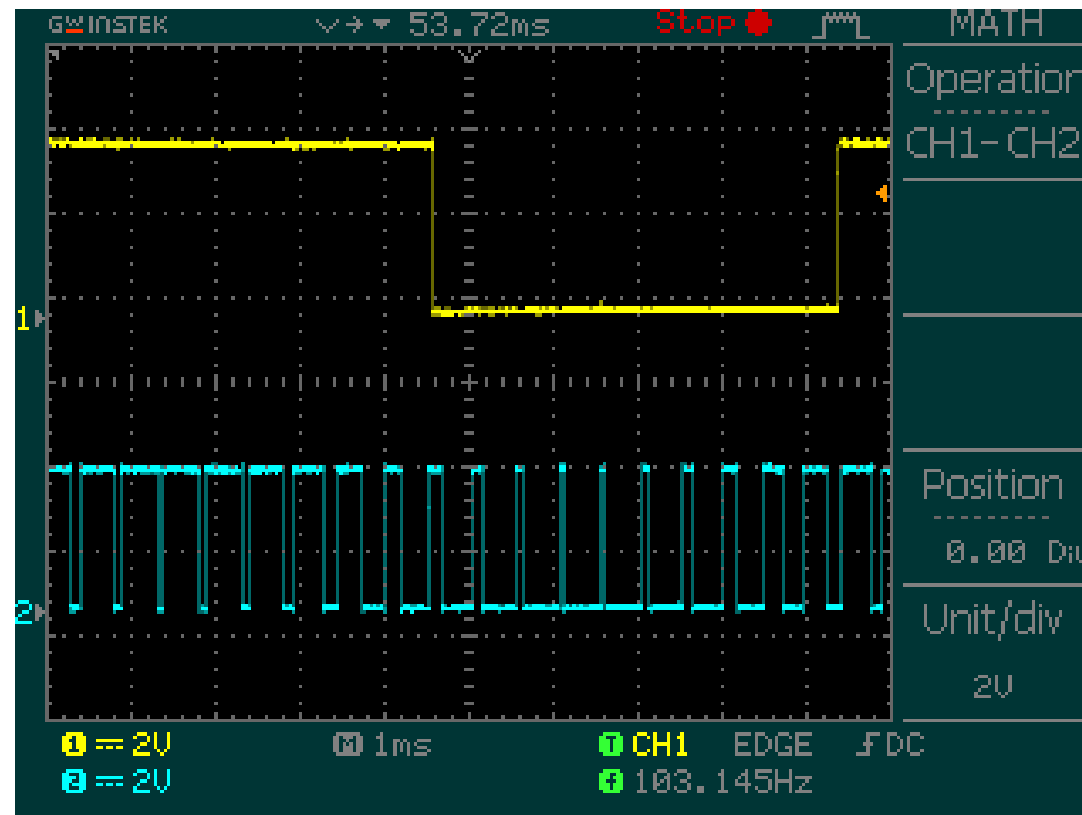
SinusV = pM->dW;

SinusW = pM->dU;

CH1 = HallB

CH2 = GateB High Side

#define UI\_PARAM\_SENSOR\_POLARITY SENSOR\_POLARITY\_LOW



PWM Frequenz = 2kHz, Speed = 300, Verschiebung Winkelberechnung = 0

SinusU = pM->dV;

SinusV = pM->dW;

SinusW = pM->dU;

CH1 = GateB High Side

CH2 = GateC High Side

#define UI\_PARAM\_SENSOR\_POLARITY SENSOR\_POLARITY\_LOW

