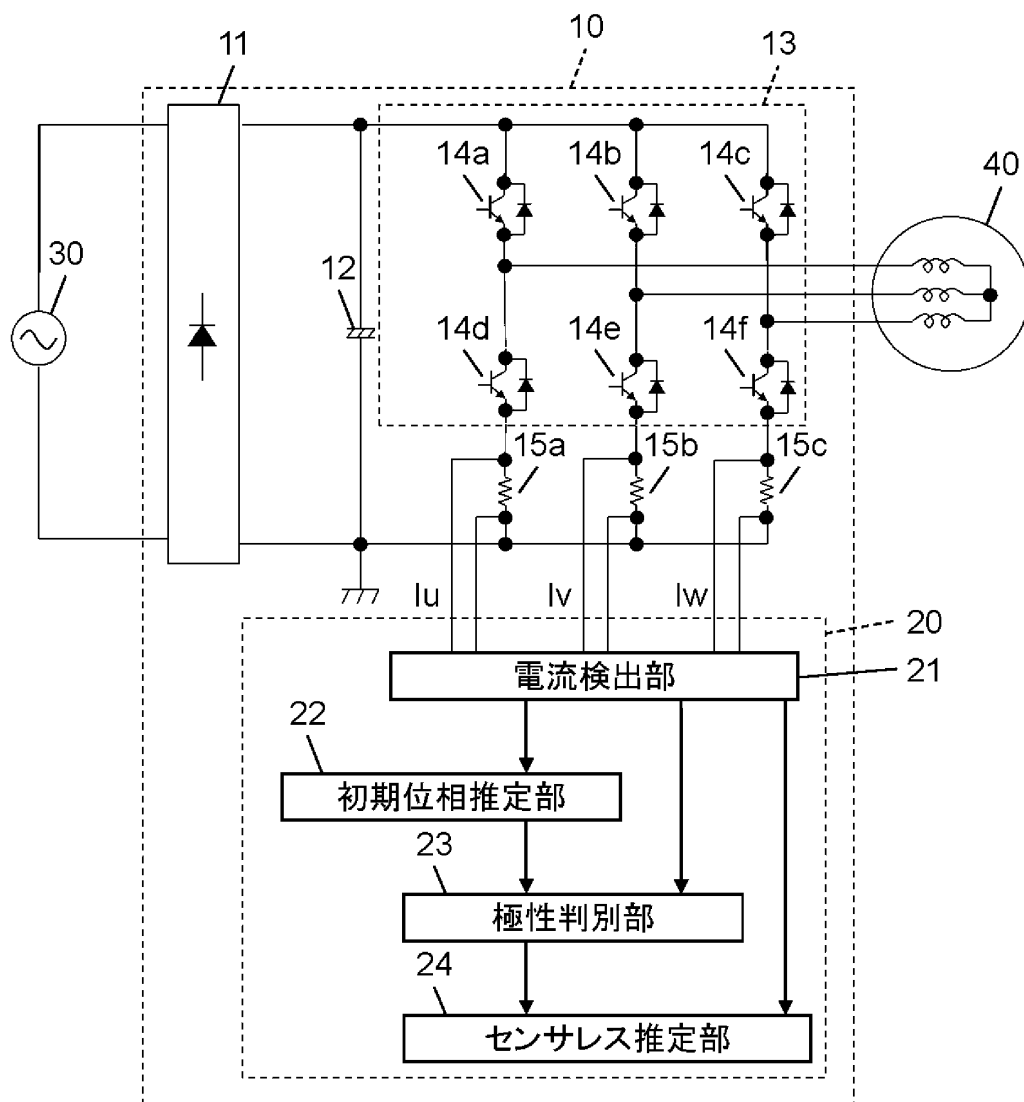
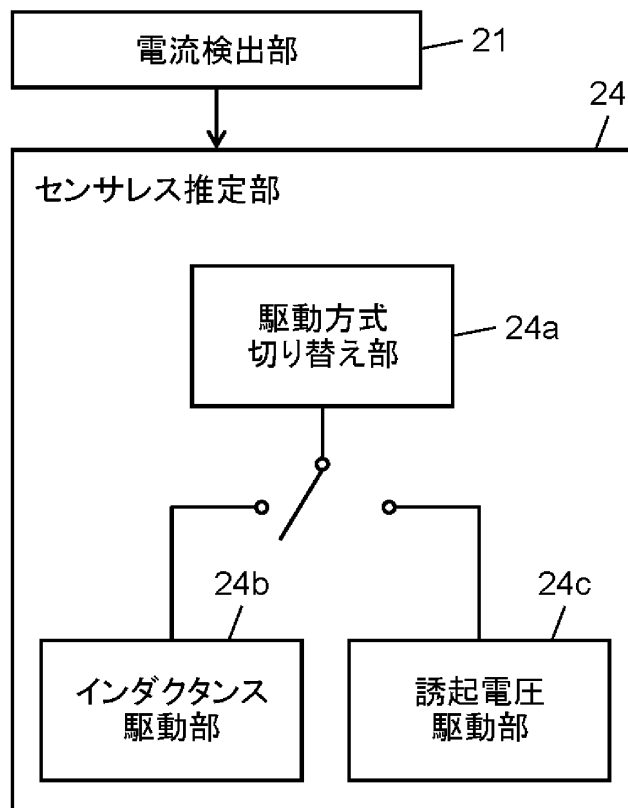


[図1]



[図2]



[図3]

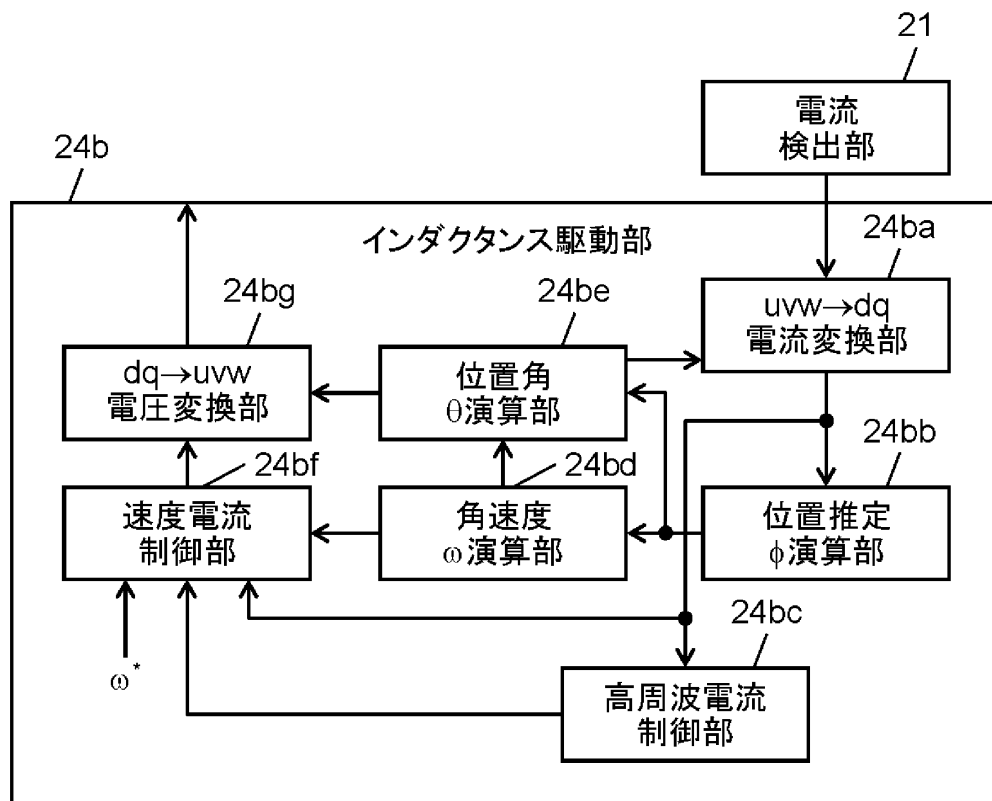
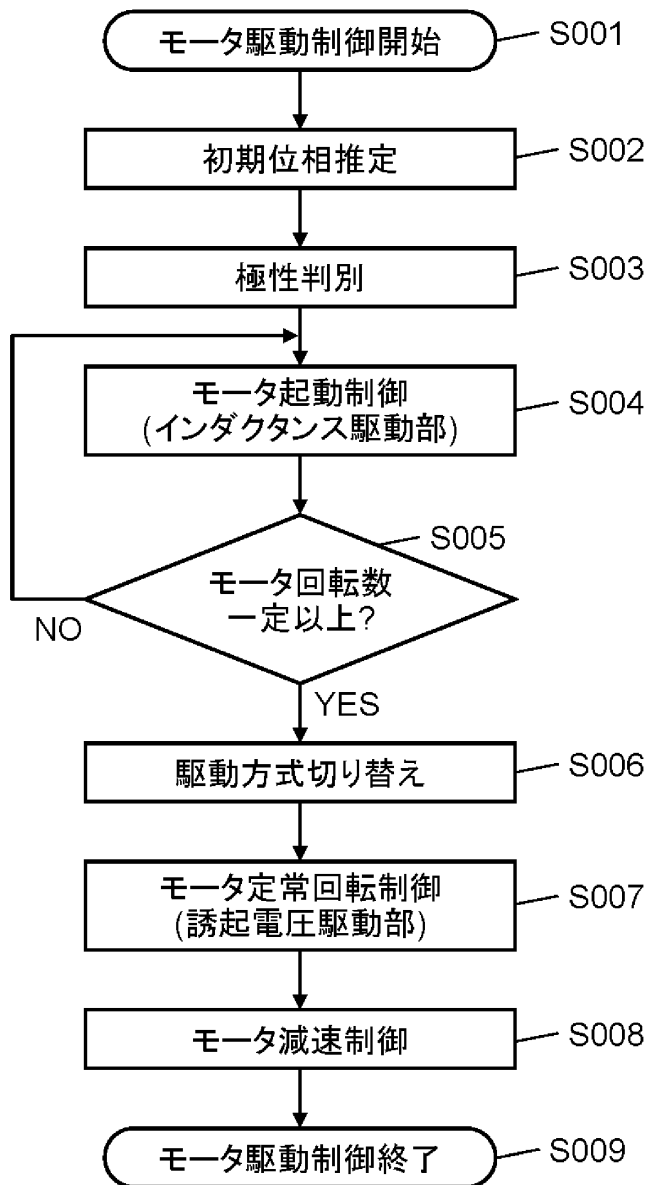


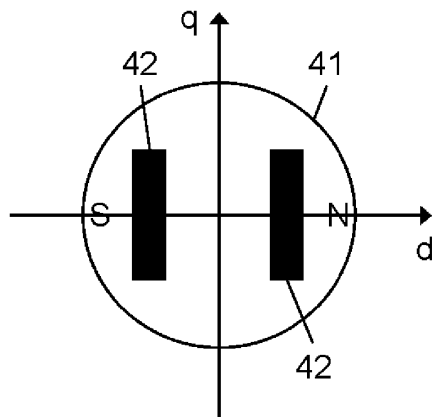
Figure 10 is a block diagram of a motor control system. The system includes the following components and signal flows:

- 電流検出部 (Current Detection Unit, 21)**: Outputs a signal (24ca) to the **uvw→dq 電流変換部**.
- uvw→dq 電流変換部 (uvw to dq Current Conversion Unit, 24cd)**: Receives signal 24ca and a reference signal (24cb) from the **位置推定 εγ 演算部**. It outputs a signal to the **速度電流制御部**.
- 速度電流制御部 (Speed Current Control Unit, 24ce)**: Receives the signal from the current conversion unit and outputs a signal (24cf) to the **dq→uvw 電圧変換部**.
- dq→uvw 電圧変換部 (dq to uvw Voltage Conversion Unit, 24c)**: Receives signal 24cf and outputs a signal (24c) to the motor.
- 位置推定 εγ 演算部 (Position Estimation εγ Calculation Unit, 24cc)**: Receives feedback signals from the motor and the **角速度 ω 演算部**. It outputs a reference signal (24cb) to the current conversion unit and a signal (24cd) to the **位置角 θ 演算部**.
- 位置角 θ 演算部 (Position Angle θ Calculation Unit, 24cd)**: Receives signal 24cd from the position estimation unit and outputs a signal (24cd) to the current conversion unit.
- 角速度 ω 演算部 (Angular Velocity ω Calculation Unit, 24cd)**: Receives feedback signals from the motor and the position angle calculation unit. It outputs a signal (24cd) to the position estimation unit.

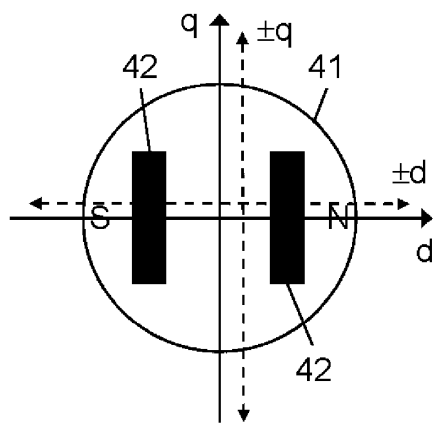
[図5]



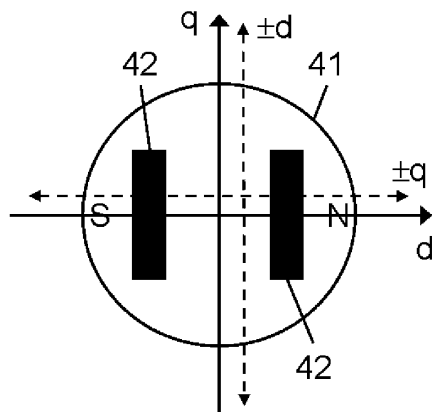
[図6A]



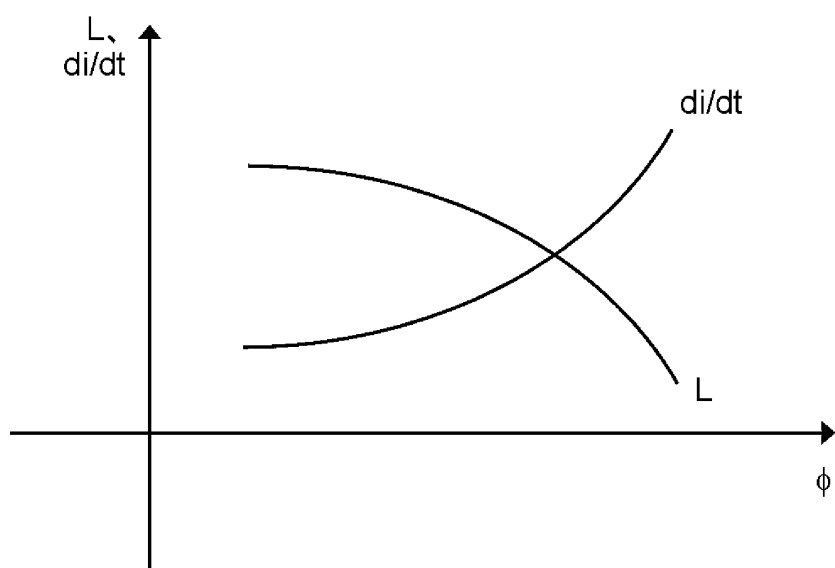
[図6B]



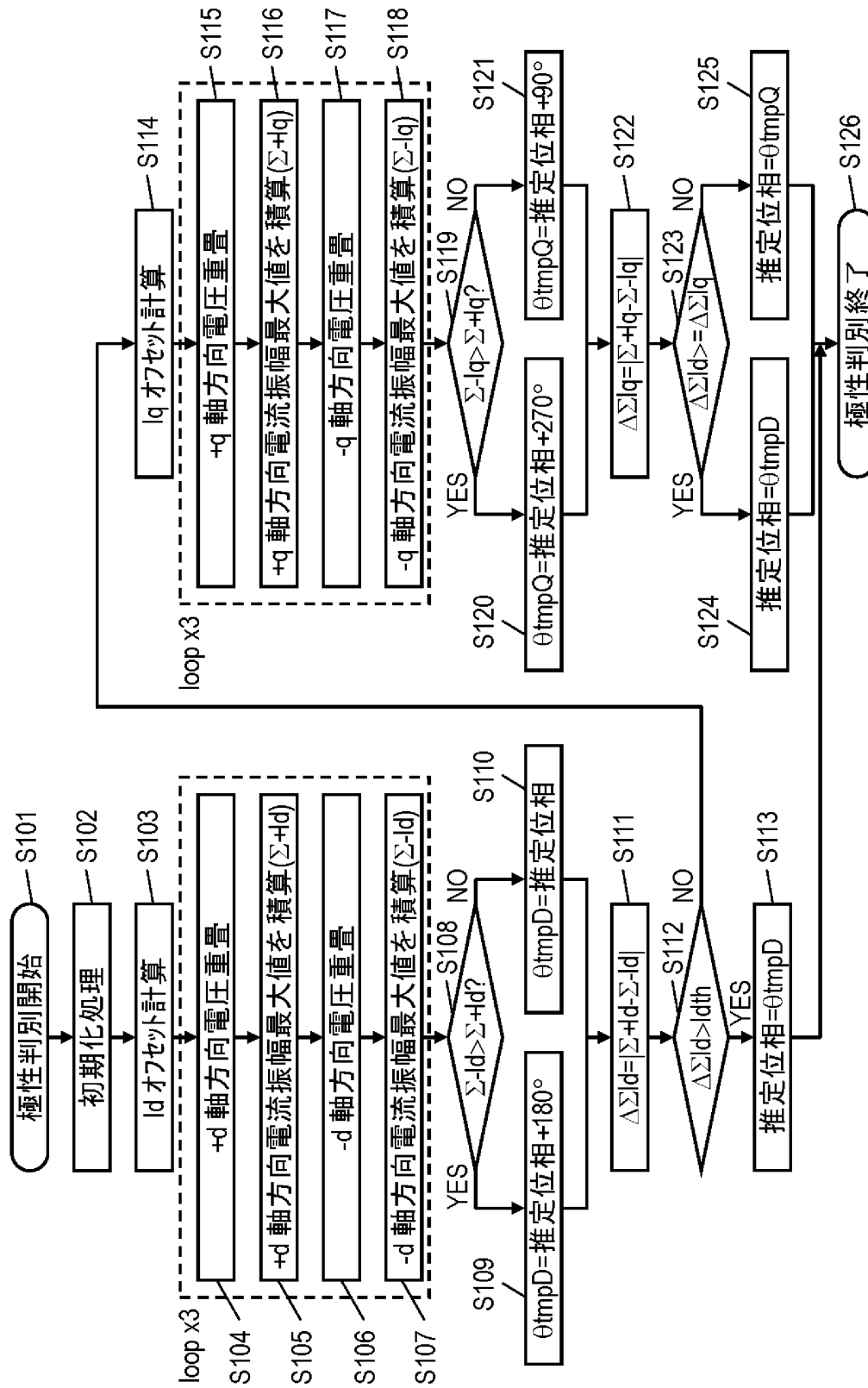
[図6C]



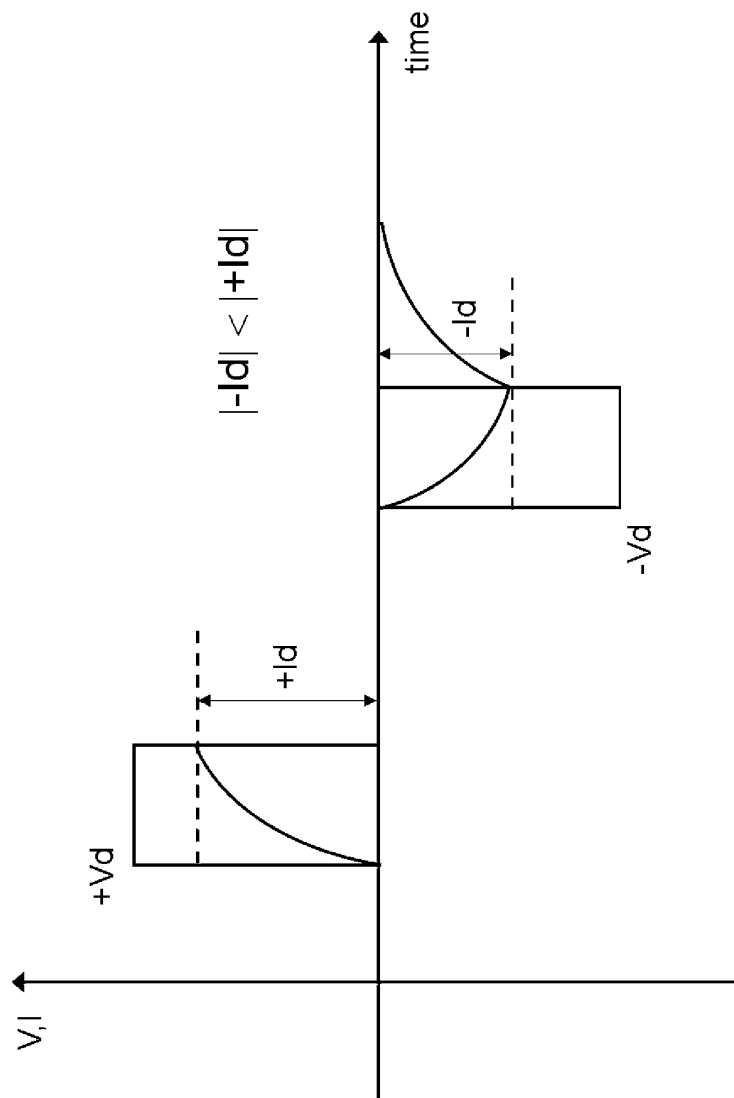
[図7]



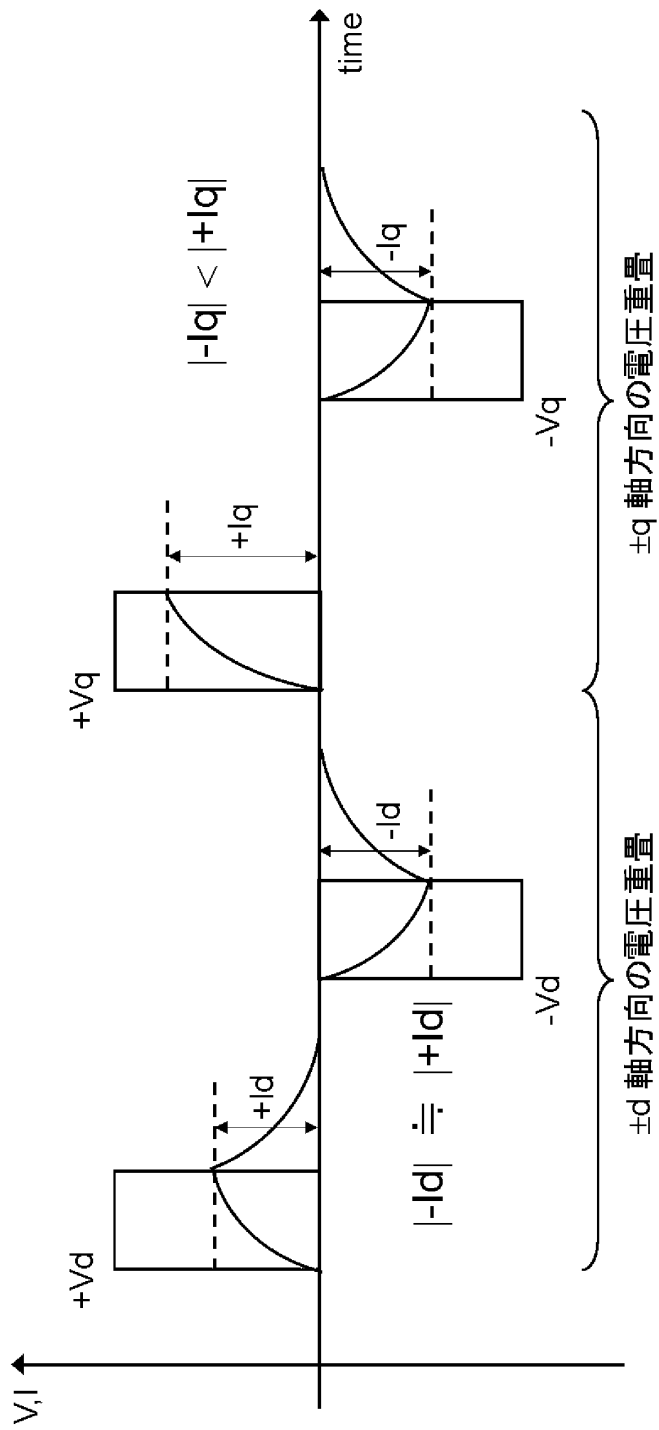
[図8]



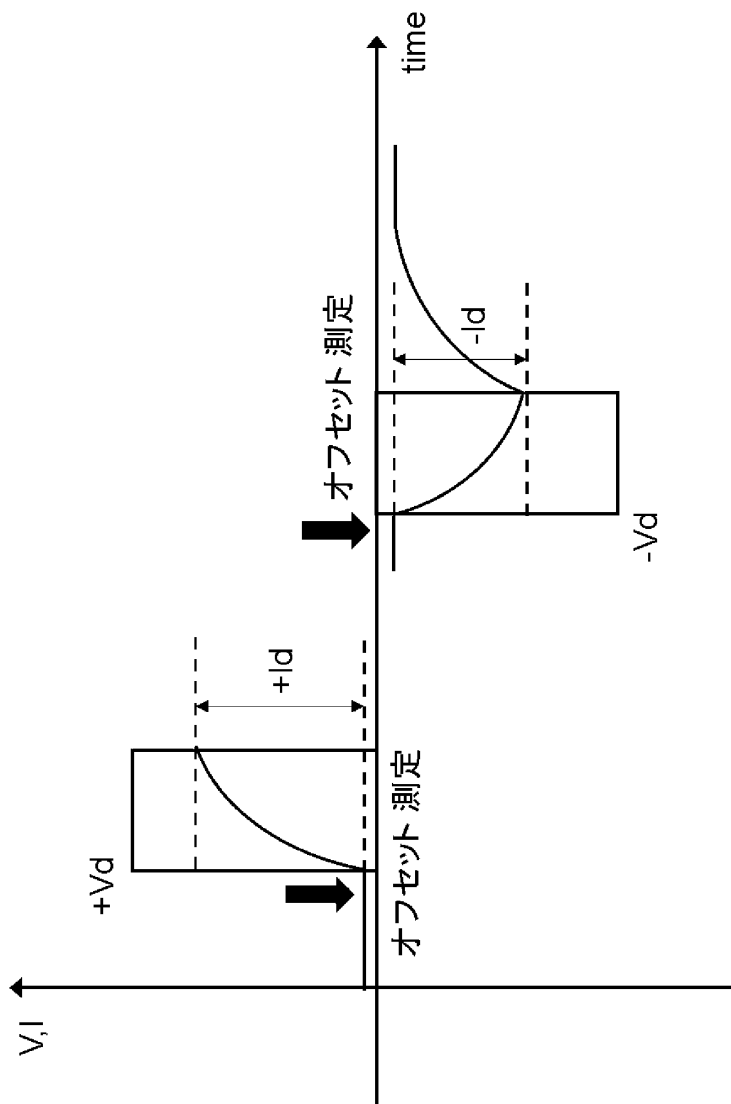
[図9]



[図10]



[図11]



[図12]

