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6 4 2 0 I n d e x e r / D r i v e

User Manual

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Table of Contents

1 Overview of 6420 Indexer/Drive

In this chapter

This chapter introduces the 6420 Indexer/Drive. Topics covered are:

- 6420 definition
- System diagram
- Warranty information

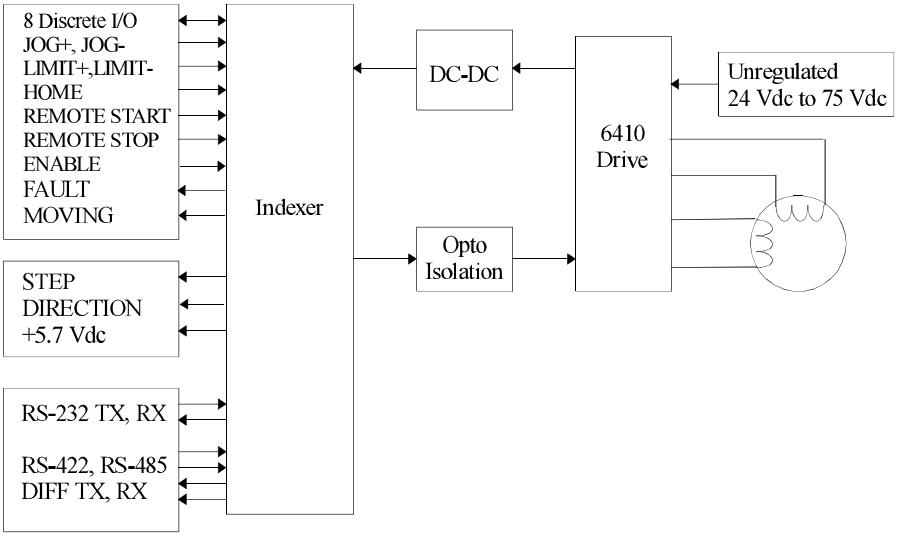
1.1 6420 Definition

Introduction

The 6420 Microstepping Indexer/Drive provides economical microstepping control with a simple mnemonic programming interface. Operation is programmed via the serial communications port. A combination of dedicated and user-programmable I/O provides motor control, status indication and sensor feedback.

Simple, single-letter mnemonics are used to specify a wide variety of motion commands. A terminal or PC with terminal software can be used to familiarize oneself with 6420 operation. Various motion parameters can be modified and motion executed immediately from the command line or from on-board non-volatile memory. Many applications can take advantage of the simplicity of developing programs for on-board execution. If more versatility is required, the user can write a custom program running on a host computer issuing immediate motion commands to the 6420.

Block diagram



The 6420 can communicate with RS-232, RS-422 or RS-485 serial protocols. Discrete I/O lines provide external start/stop and motor enable control, home and limit switch testing, motor jogging, slave drive interface and eight programmable bi-directional discrete I/O lines. The eight programmable bi-directional discrete I/O lines are individually jumper configurable for input or output. Immediate command line instructions can read back and write all eight bits.

Fixed resolution mode

The unit operates in one of two modes, either Fixed Resolution Mode or Variable Resolution Mode. In Fixed Resolution Mode with binary steps the resolution can be set from 200 steps/rev to 51,200 steps/rev and with decimal resolution 200 steps/rev to 50,000 steps/rev. The minimum and maximum step rate range in value from 0.08 to 19,000 steps/sec and vary depending on the resolution.. Of course, the finer step sizes result in high shaft resolution at the expense of shaft speed. The motion profile is trapezoidal with programmable initial and final speeds. The acceleration and deceleration rates are specified by a single command in terms of acceleration and deceleration factors ranging in value from 1 to 255.

Variable resolution mode

Variable Resolution Mode is the recommended alternative where micro-stepping is desired without compromising speed. This mode allows for positioning at a resolution of 1/100 of a step at effective full step speeds of 20-19,000 steps/second.

Drive features

Internal power supply - Single power supply

Bipolar chopper drive - Patented for superior current regulation and low ripple current.

Output current - adjustable from 0.625 A to 5 A RMS with 3 position DIP switch.

Microstepping - for smooth operation and increased resolution.

Fixed Resolution microstepping - Binary Steps: Full, 1/2, 1/4, 1/8, 1/16, 1/32, 1/64, 1/128, 1/256. Decimal Steps: Full, 1/2, 1/5, 1/10, 1/25, 1/50, 1/125, 1/250

Variable Resolution microstepping - Decimal step resolution 0.01 steps at effective full step speeds of 20-19,000 steps/second

Optical isolation - Indexer optically isolated from drive

Digital Electronic Damping - Patented circuit reduces instability at speeds in middle of operating range.

Idle current reduction (ICR) - to reduce motor heating in many applications

Fault protection - Line-to-line and line-to-neutral shorts, Internal power supply under-voltage, Bus overvoltage

Small size - Only 7.5 square inches of panel space.

UL Recognized - 508C (Type R) - File E-137798. This also complies with CSA Standard for Process Control Equipment, C22.2 No. 142-M1987.

Vibration - IEC Standard 68-2-6.

Indexer features

Simple mnemonic command set - may be executed from internal NVRAM or from a more powerful host.

Serial port communications - supporting RS-232, RS-422 and RS-485 multi-drop.

Multi-axis - Single 6420 can control two independent or synchronous axes with an additional drive and no glue logic.

Input/Output ports - Eight general purpose bi-directional user programmable input/output ports.

Internal Memory - Approximately 1792 bytes of non-volatile memory are available for user programs.

1.2 System Components

The other components that, along with the drive comprise a complete motor control system are:

- Single Power Supply (24 - 75 Vdc)
- Motor

Installation guidelines for these components are described in Chapter 2, “Installing the 6420 Indexer/Drive.”

1.3 Warranty

The Pacific Scientific 6420 Indexer/Drive has a two year warranty against defects in material and assembly. Products that have been modified by the customer, physically mishandled or otherwise abused through miswiring, incorrect switch settings and so on, are exempt from the warranty plan.

2 Installing the 6420 Indexer/Drive

In this chapter

This chapter explains how to install the 6420 Indexer/Drive. Topics covered are:

- Unpacking and inspecting the 6420
- Installation of motor, power, discrete I/O and serial communications cables
- Configuration of drive and Indexer jumpers and DIP switch
- Attention to details such as heat sink requirements and power supply filter capacitor

2.1 Unpacking and Inspecting the 6420

Unpacking procedure

1. Remove the 6420 from the shipping carton. Make sure all packing materials are removed from the unit.
2. Check the items against the packing list. A label located on the unit identifies the unit by model number, serial number and date code.

Inspection procedure

Check items for any damage. If you find damage, either concealed or obvious, promptly contact your buyer to make a claim with the shipper.

Storing the unit

Store the 6420 in a clean, dry place, preferably in the original shipping carton.

2.2 Mounting the 6420 in Your Installation

Cabinet selection

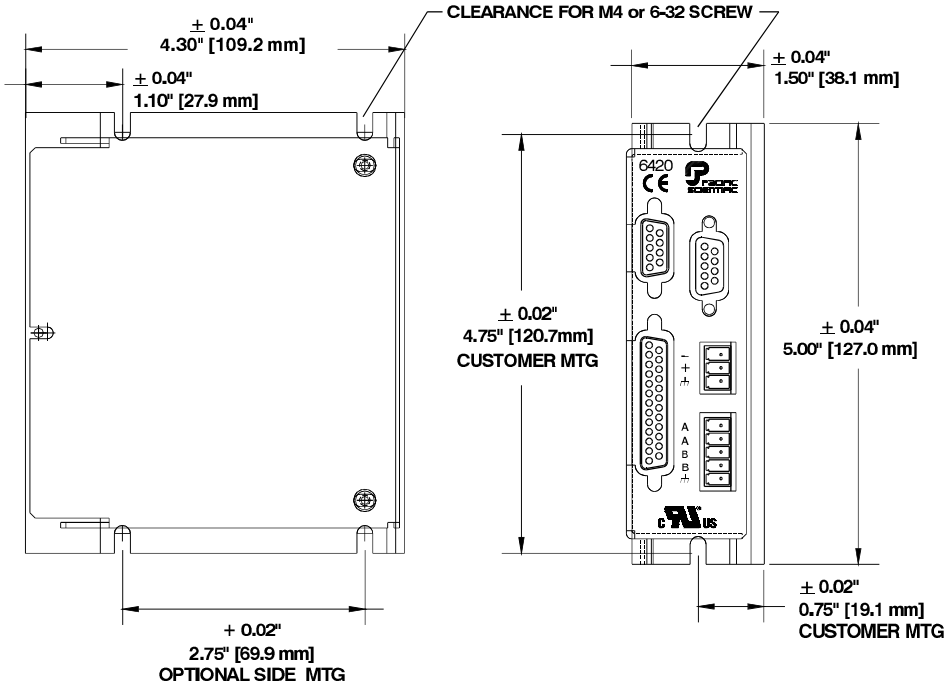
Select a standard 8-inch (205 mm) deep NEMA (National Electrical Manufacturers Association) enclosure appropriate for industrial applications.

Caution

The internal operating temperature should not exceed 50° C. If the cabinet is ventilated by filtered or conditioned air, make sure to prevent the accumulation of dust and dirt on the unit's electronic components. The air should also be free of corrosive or electrically conductive contaminants.

Mounting dimensions

The 6420 can be mounted in the two orientations shown below. Refer to Appendix A, "Specifications - Environmental Requirements," for additional information.



2.3 Connecting the Four Input/Output Cables

Introduction

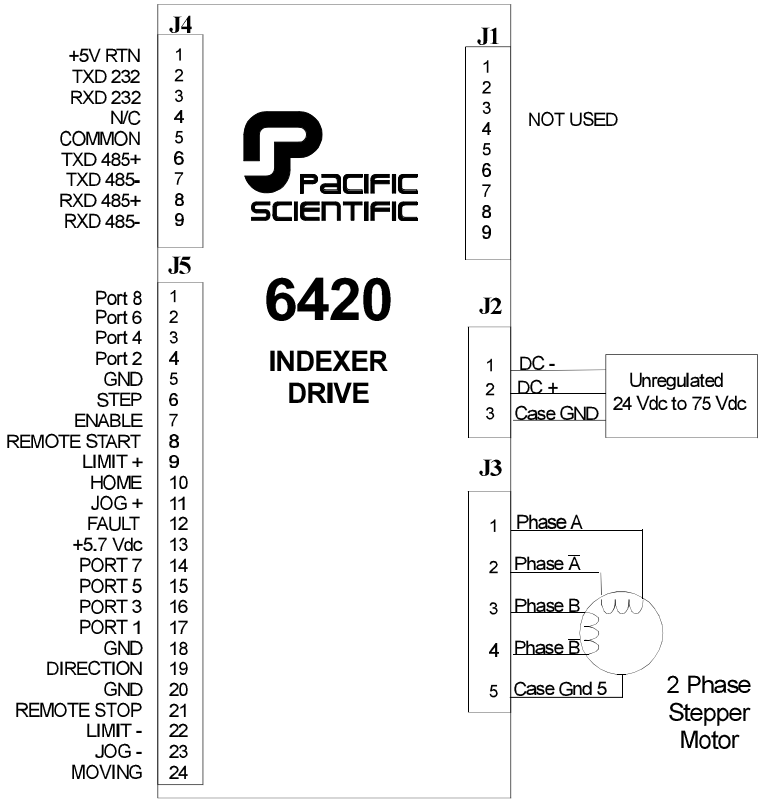
The four input/output cables are:

- J3 - Motor
- J2 - Power
- J4 - Serial port
- J5 - Discrete inputs and outputs

Note: *J1 Connector is **NOT USED**.*

Connection diagram

These inputs and outputs are shown as follows:



2.3.1 J3 - Motor Connection

Introduction The J3 motor cable connects the drive to the motor windings. Motor cables are available from Pacific Scientific, or you can make your own.

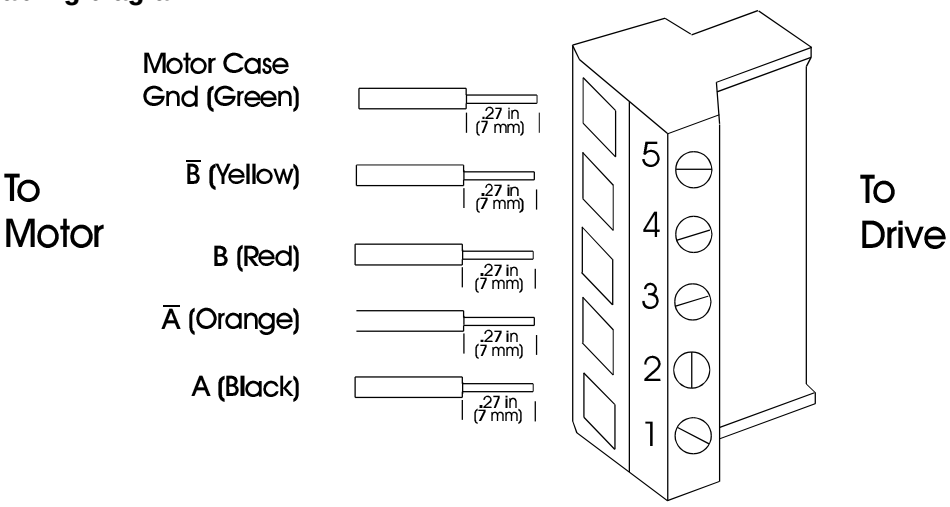
Mating connector The J3 motor connector is for a PCD 5-pin screw mating connector. The mating connector, supplied with the unit, is type ELVP05100.

2.3.1.1 4-Lead Motor

Cable requirements Use 18- to 16- gauge stranded wire, twisted at approximately 3 to 4 turns per inch for each motor phase.

Building a 4-lead motor cable The motor cable assembly uses a 5-pin PCD connector at the 6420. Pacific Scientific motors commonly use a MS style connector at the motor end. The cable assembly using standard Pacific Scientific stepper motor color coding is shown below:

Cabling diagram



Procedure

1. Strip the wires to 0.27 inch (7 mm).
2. Attach the wire to the connector as indicated in the diagram.

Note: *Make sure the screws on the PCD connector are tightened down firmly to the wiring.*

Caution

Do not pre-tin (solder) the tops of the cables going into the PCD connector. This can result in a loose connection.

3. Remove power from the 6420.

Warning

Always remove power before making or removing connections to the unit. The motor terminals have high voltage present when the 6420 is On.

4. Plug the mating connector firmly into the 6420.
5. Connect the cable shield to 6420 ground, if applicable.
6. Plug the other mating connector into the motor.
7. Switch On the 6420.

2.3.1.2 8-Lead Motor, Series Connected

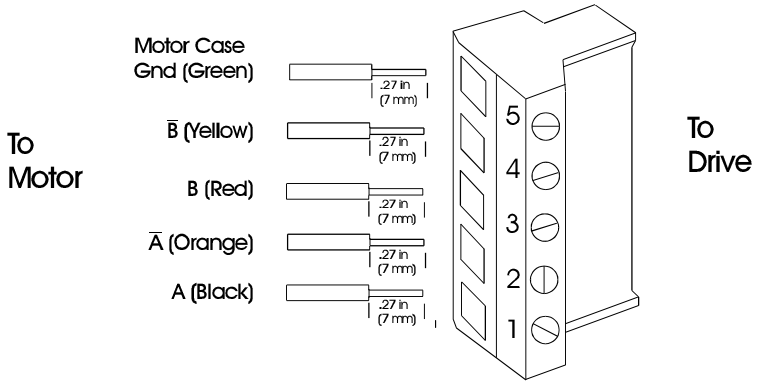
Introduction

For an 8-lead motor to be wired in series, build and install the cable as follows:

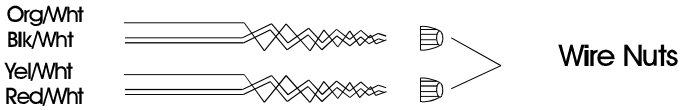
Building an 8-lead series motor cable

The connector assembly using standard Pacific Scientific stepper motor color coding is shown below:

Cabling diagram



In addition, make the following connections at the motor:

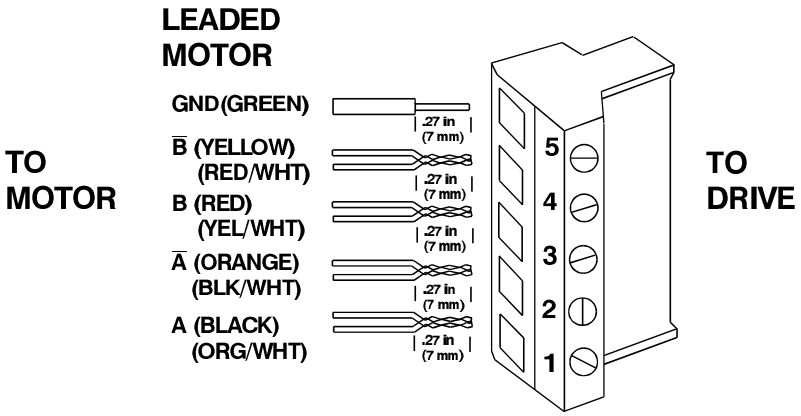


2.3.1.3 8-Lead Motor, Parallel Connected

Introduction For an 8-lead motor to be wired in parallel, build and install the cable as follows:

Building an 8-lead parallel motor cable The connector assembly using standard Pacific Scientific stepper motor color coding is shown below:

Cabling diagram

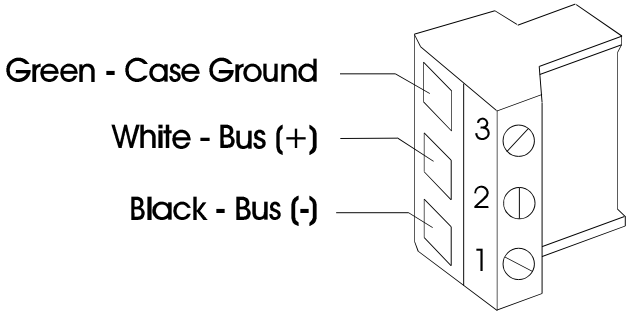


2.3.2 J2 - Power Connection

Introduction Bus power is applied to the 6420 J2 with a 3-pin PCD connector as shown on the following page.

Mating connector The J2 power input is for a PCD 3-pin mating connector. The connector, supplied with the unit, is type ELVP03100.

Cabling diagram



2.3.3 J4 - Serial Port Connection

Introduction

The serial port transmits and receives RS-232 communication for the user interface of your unit.

Mating connector

The J4 serial port mating connector, supplied with the unit, is an ITT Cannon DE-9S 9-pin plug-in female D connector.

Port connections

These are the RS-232 transmit (TXD) and receive (RXD) terminals.

Pin Number	Connection
J4-2	RS-232 TXD (output)
J4-3	RS-232 RXD (input)
J4-5	RS-232 Common

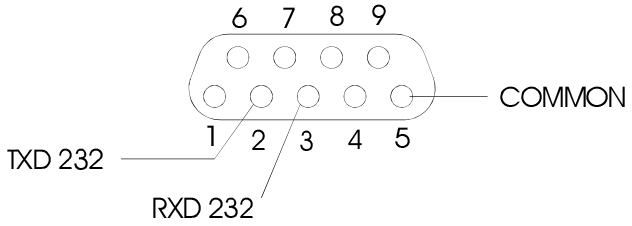
Baud rate

The 6420 supports single-unit RS-232, RS-422 and multi-unit RS-485 communication protocols running at 9600 bps, 1 start bit, 1 stop bit. RS-232 and RS-422 mode selection is automatic dependent upon whether connections are made to the single-ended RS-232 TX and RX lines or to the differential TX and RX lines. RS-485 mode is jumper selected and allows up to 32 units on a single differential RS-485 communications link. The host computer is the bus master and always initiates packet transfers. External termination may be required in some installations. The unit is factory configured for RS-232 protocol. The table below shows the Serial Port pin designations.

Input/Output	Pin Number	Description
+ 5 Vdc RTN/Shield	J4-1	RS-232 Transmit data (output)
TXD_232	J4-2	
RXD_232	J4-3	RS-232 Receive Data (input)
COMMON	J4-5	
TXD_485 +	J4-6	Differential Transmit Data (output)
TXD_485 -	J4-7	Differential Transmit Data (input)
RXD_485 +	J4-8	Differential Receive Data (output)
RXD_485 -	J4-9	Differential Receive Data (input)

2.3.3.1 Single-unit RS-232 Connection

Solder connections to TXD_232 (output), RXD_232 (input) and COMMON. After installing the power and serial communications cable you can quickly test the unit by applying power and pressing <Esc> and then the space bar. You should see the Pacific Scientific sign-on message and copyright notice.



2.3.3.2 Single-unit RS-422 Connection

Solder connections to TXD_485± and RXD_485 ± differential lines. After installing the power and serial communications cable you can quickly test the unit by applying power and pressing <Esc> and then the space bar. You should see the Pacific Scientific sign-on message and copyright notice.

Build the cable to connect to your computer or terminal by referring to the documentation for the device.

Note: *Pinouts vary among computer manufacturers. Check your computer's hardware reference manual before wiring.*

2.3.3.3 Multi-unit RS-485 Connection

Solder connections to TXD_485± and RXD_485 ± differential lines. This mode requires each 6420 to be initialized with a single-letter node address to be used with each subsequent command. This node address must be setup in Single-Unit mode before the RS-485 mode operation is attempted. To set this address, perform the following:

Procedure

1. Apply power and press a key (a-z, A-Z) **NOT the Spacebar**, to be used as the address followed by a single space. Execute the P command to program the node address into non-volatile memory.
2. Power-down the unit and insert jumper E11 to configure the unit for RS-485 mode. There is no sign-on procedure while in RS-485 multi-unit mode. This mode is designed to be used with a host computer, but can be tested using a terminal.
3. Type in the node address. The character should be echoed if the unit recognizes the address.
4. Type a simple motion command, **R 500** followed by a <LF> (line feed) terminating character (press <**Ctrl**> <**J**>). The motor should now run.

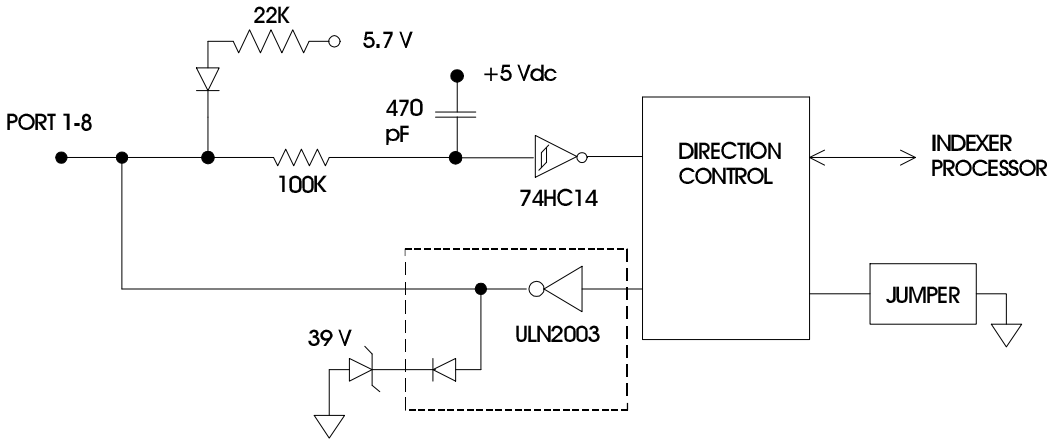
Note: *Units configured for single-unit RS-232 or RS-422 always have the serial drive lines enabled. Therefore, avoid connecting one of these units into a chain of RS-485 configured units.*

2.3.4 J5 - Discrete Inputs/Outputs Connection

Introduction

The 6420 features 8 user-programmable discrete input/output lines. Input/output selection for Port 1 to 8 is configured by jumpers E3 to E10 respectively. To enable a port as an input, remove the respective jumper. To enable as an output, install the jumper. Always remove the external cabling when making I/O configuration changes to ensure that an external low impedance input is not driving a I/O Port configured as an output The block diagram of a single I/O bit is shown below.

Block diagram



Note: *Inputs accept 0-30 VDC max, where $V_{in} \leq .8V$ is a logic low and $V_{in} \geq 3.7V$ is a logic high. All outputs are Open Collector 30 VDC, 70 ma sink, $V_{sat} \leq 1.0V$. All I/O signals are active low.*

Note: *If a bit is desired to be an input, the jumper must be out and an inactive level (low) written to the bit using the Y command. Otherwise, as a consequence of the wired "AND" design of the indexer, a logic "1" written to a bit configured as an input will always be read back as a "1." Programs executing from non-volatile memory can only output to these discrete bits, reading is not allowed.*

J5 port designations

The J5 connector pin designations are shown below:

Port	Pin Number	Jumper	I/O
1	J5-17	E3	Input 1 OR Output 1
2	J5-4	E4	Input 2 OR Output 2
3	J5-16	E5	Input 3 OR Output 3
4	J5-3	E6	Input 4 OR Output 4
5	J5-15	E7	Input 5 OR Output 5
6	J5-2	E8	Input 6 OR Output 6
7	J5-14	E9	Input 7 OR Output 7
8	J5-1	E10	Input 8 OR Output 8
GND	J5-5	N/A	Ground return for I/O signals.
GND	J5-18		
GND	J5-20		

Note: *The Discrete I/O connector has its own ground points, completely isolated from the unit's bus power.*

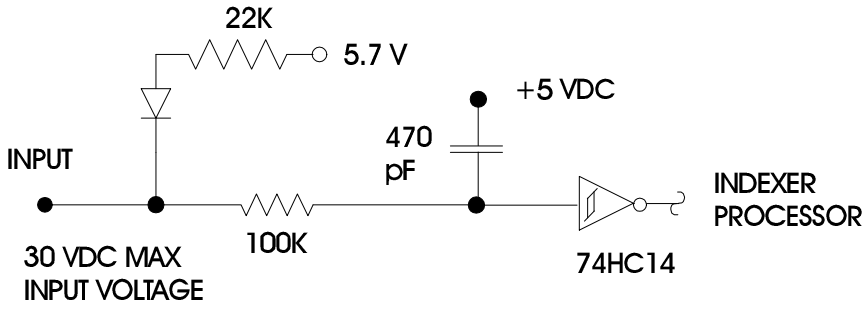
The minimum requirement to operate the unit is to enable motor current by connecting J5-7 (ENABLE) to one of the three J5 ground points (J5-5, J5-18, or J5-20).

2.3.4.1 Dedicated Discrete Input/Output Lines

Introduction

The 6420's operation is controlled by several input lines. These lines are active low. Input lines are RC filtered and passed to a 74HC14 Schmidt Trigger. The block diagram of input and output lines are shown below.

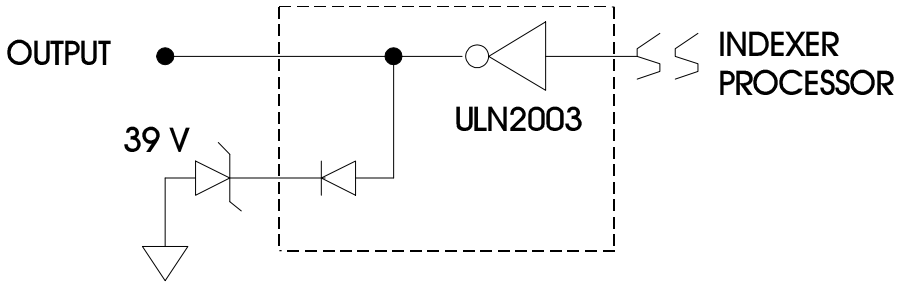
Input



Note: *Inputs accept 0-30 VDC max, where $V_{in} \leq .8V$ is a logic low and $V_{in} \geq 3.7V$ is a logic high.*

The 6420's outputs are open-collector Darlington ULN2003 drives. Inductive kick-back protection is provided by the built-in diode and 39 V Zener diode.

Outputs



Note: *All outputs are Open Collector 30 VDC, 70 ma sink, $V_{sat} \leq 1.0V$. All I/O signals are active low.*

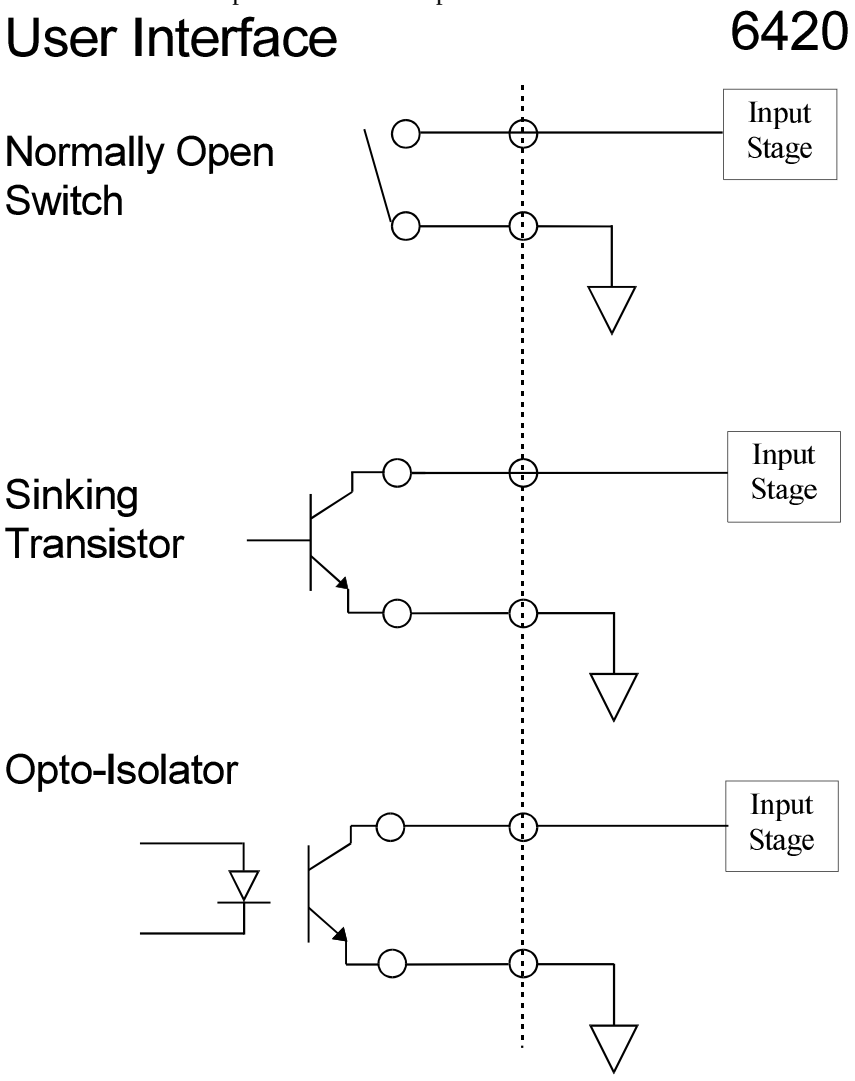
2.3.4.2 Dedicated Input/Output Pin Designations - J5

Introduction The pin definitions for all 6420 control lines are shown below:

Input/Output	Pin Number	Description
Remote Start	J5-8	This input activates program at location zero.
Remote Stop	J5-21	This input halts 6420 program and motion.
LIMIT +/LIMIT -	J5-9, J5-22	Activation of Limit + prohibits motion in CW direction. Activation of Limit - prohibits motion in CCW direction.
Home	J5-10	A transition at this input defines the electrical home position.
JOG +/JOG -	J5-11, J5-23	These inputs manually step the motor in the CW and CCW direction.
ENABLE	J5-7	This input is an active-low motor drive enable.
STEP	J5-6	This output is an active-low step pulse to slave drive approximately 400-600 ns in duration. Only in Fixed Resolution Mode.
DIR	J5-19	This output provides direction to slave drive. CCW is a logic low, CW is a logic high. Only in Fixed Resolution Mode.
+5.7 V	J5-13	This output provides power for slave STEP and DIR when used with a 6410 drive.
FAULT	J5-12	The output is an active-low fault indicator. It must be cleared by powering down.
MOVING	J5-24	This output is an active-low motion indicator.
GND	J5-20	Indexer ground, isolated from drive ground.

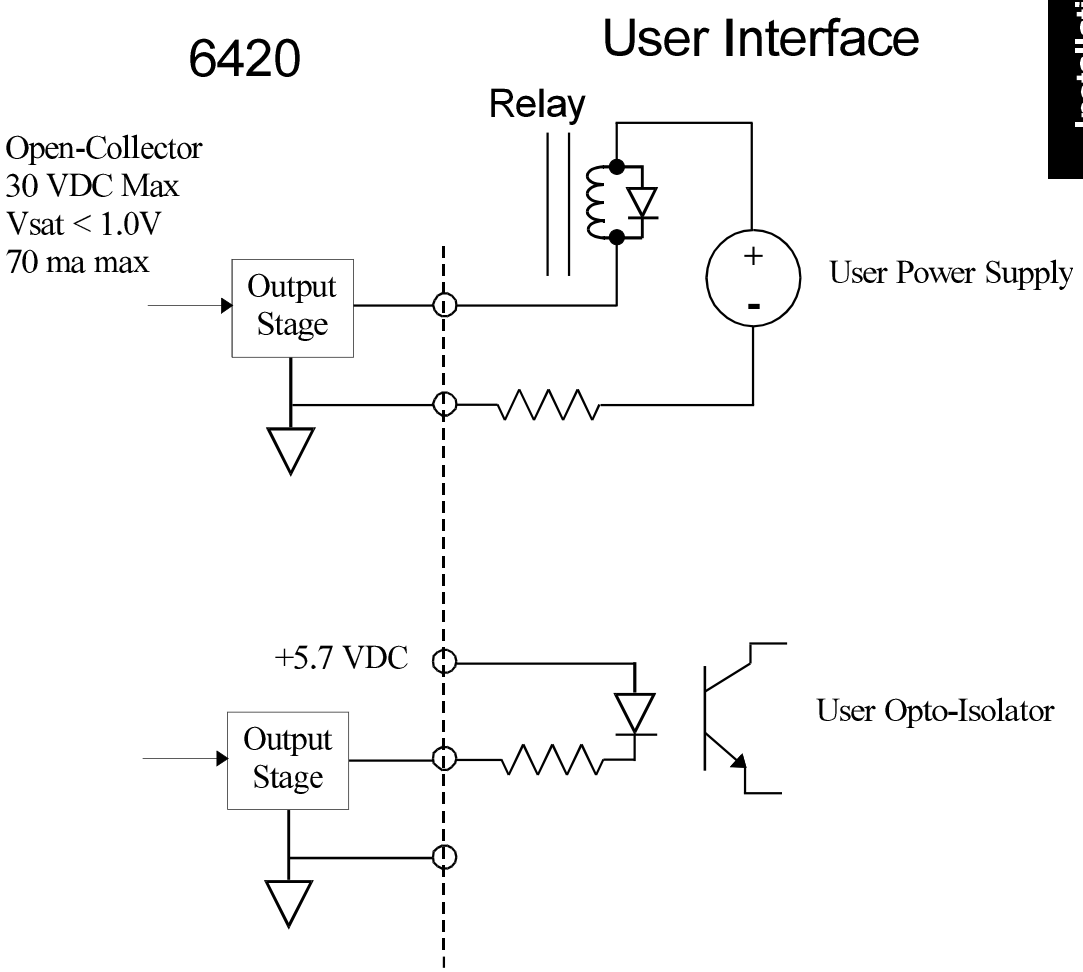
2.3.4.3 Input Interface Suggestions

These are examples of driving regular inputs and I/O pins configured as inputs. The input lines pull down to ground and the internal 22k ohm resistor through a 1N914 diode pulls up to 5.7 Vdc. The input is designed such that the user can actively drive the inputs with a low impedance source from 0 to 30 Vdc.



2.3.4.4 Output Interface Suggestions

The output stage is a Darlington sink to ground. The user generally supplies the +V power. However, the 6420 can provide upto 200 ma from the 5.7 Vdc intended for the slave 6410 interface, for applications such as driving 5 Volt nominal Opto 22 devices.



2.4 Using the 6420 to Control a 6410 Drive

Introduction

A single 6420 can be used to control two axes in either synchronous or alternating fashion. The 6420 Indexer/Drive must be in Fixed Resolution mode. The slave 6410 drive is usually set for the same step resolution but doesn't necessarily have to be. Jumpers E12 and E13 are used to configure these modes.

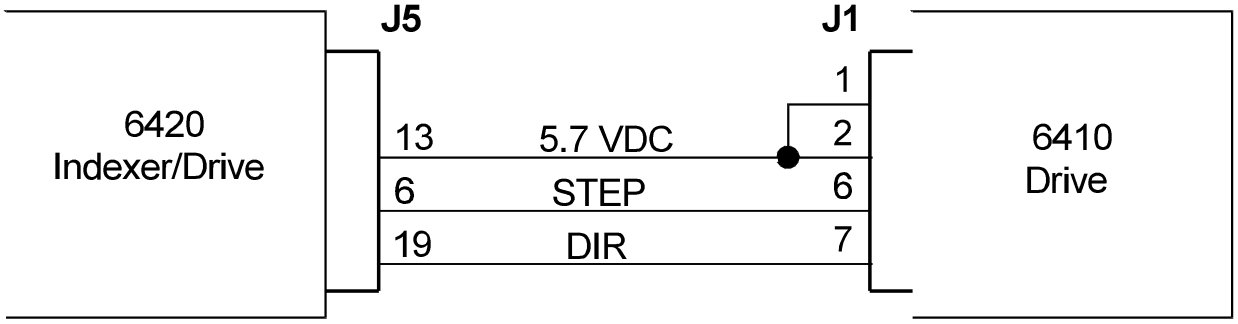
2.4.1 Synchronous Operation - E12 OUT, E13 IN

The T command, with enb = 1 enables step pulses to both master and slave. Issuing T with enb = 0 disables step pulses to both master and slave.

2.4.2 Alternating Operation - E12 IN, E13 OUT

The T command, with enb = 1 enables step pulses to the master and disables the slave. Issuing T with enb = 0 disables the master and enables slave.

Note: *Do not insert both E12 and E13 at the same time.*



Note: *All slave 6410 jumpers and DIP switches must be properly set. See the 6410 Data Sheet for additional information.*

2.5 Factory Default Settings

Introduction

The 6420 unit is a two board assembly incorporating a drive and an Indexer card set. With the cover removed, the topmost visible board is the Indexer. The Indexer mounts on the drive board and is separated by standoffs.

Drive

The drive has an eight position DIP switch (S1) and a group of four jumpers (J6) controlling drive current, digital electronic damping, idle current reduction and binary or decimal step size. The DIP switch (S1) is easily accessible without removing the Indexer card. The default factory set jumpers are usually suitable for most applications but can be modified if necessary. The jumpers (J6) may be removed using needle-nose pliers. To reinstall the jumper, loosen the screws on the indexer board. If the indexer board must be removed, it must be re-aligned properly before tightening the screws.

Warning

When installing the indexer board, make sure the 20 pin connector is aligned properly. Misalignment will seriously damge the drive.

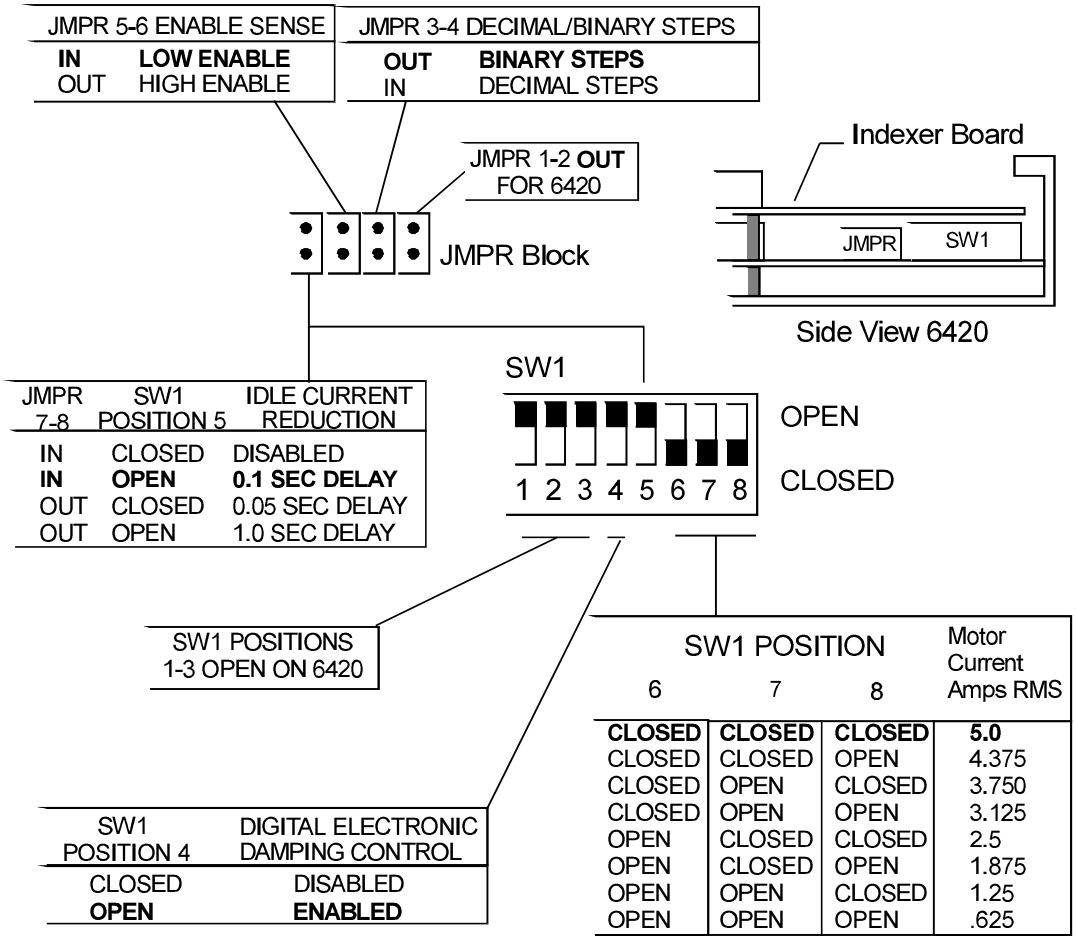
Indexer

The Indexer has thirteen plug on jumpers (E1 through E13) controlling RS Communications, Synchronous or Alternating Operation, and I/O Configuration.

2.5.1 Drive Board Settings - Switch S1 & Jumper J6

Drive switch settings

Note: *Default settings are in **bold**.*



2.5.1.1 Digital Electronic Damping Control

Definition

Mid-speed instability and the resulting loss of torque occurs in any step motor/drive system due to the motor back EMF modulating the motor winding currents at certain speeds. Mid-speed instability can be explained as a region of potential instability that occurs as a result of the electronic, magnetic, and mechanical characteristics of any stepping motor system. The circuitry used to control this phenomenon does so by advancing or delaying the switching of the output current with respect to the incoming pulse train. This should be taken into account if the user is attempting to employ pulse placement techniques.

Enable the digital electronic damping function by placing DIP switch S1 position 4 in the open position as shown. This is the default position and should be used for most applications if your application is affected by loss of torque at mid-range speeds. If pulse placement techniques are being used, disable the digital electronic damping function by placing DIP switch S1 position 4 in the open position.

Benefit

This feature controls torque loss at mid-range speeds. When enabled, the motor maintains torque at mid-range operation, provided the torque load does not exceed motor torque ratings.

Maximum delay from input step to change in motor excitation:
Step frequency < 500 full steps/sec: 500 µs
Step frequency > 500 full steps/sec: 270° of step period

2.5.1.2 Idle Current Reduction

Definition

The Idle Current Reduction (ICR) function reduces the phase current at times when no motion is commanded. Motor current is reduced when no step commands are received for a given time. This time can be set to 0.05 seconds, 0.1 seconds or 1.0 second. Current to both motor windings is reduced by one-half.

The ICR function can be enabled/disabled and the time delay between the last step command and current reduction can be set to 50 ms, 0.1 seconds, or 1.0 second using DIP switch S1 position 5 and Jumper J6 position 7-8. With the jumper installed (factory default), ICR is disabled when DIP Switch S1 position 5 is in the closed position and enabled with a delay of 0.1 second (current is reduced by 50% when no step command is received for 0.1 second when the switch is open. With the jumper removed, ICR is enabled and the delay can be set to 0.05 second or 1.0 second by placing DIP Switch S1 position 5 in the closed or open position respectively.

Note: *When ICR is active, both the holding torque generated by the motor and the motor stiffness around the holding position are reduced by approximately 50%.*

Benefits

The ICR function:

- Reduces motor and drive heating during stand-by operation

3.1.3 Setting Motor Current

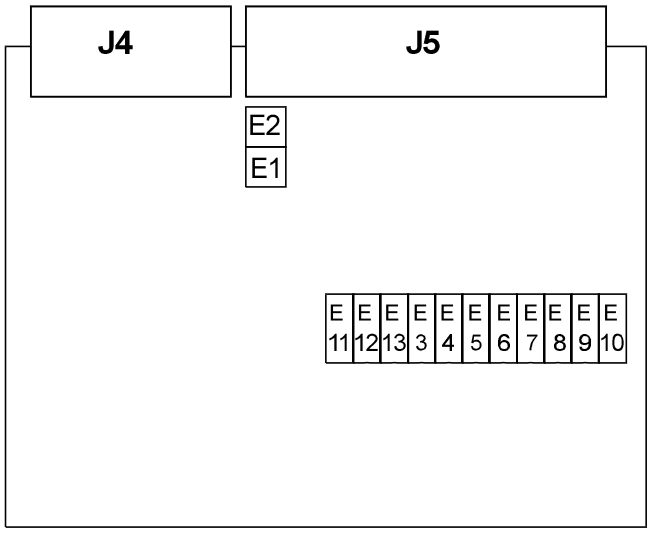
Motor current can be set using DIP Switch S1 positions 6, 7, and 8 as shown on page 3-2. Current should be compatible with motor current ratings.

2.5.2 Indexer Board Settings

Indexer

The Indexer has thirteen plug on jumpers (E1 through E13) controlling RS Communications, Synchronous or Alternating Operation, and I/O Configuration.

Jumper location



2.5.2.1 Jumper Settings

E1 and E2

Configuration	E1	E2
	IN	OUT

Note: *These jumpers **should NOT** be modified by user.*

E11

E11	RS Communication Configuration
IN	RS-485 Communications
OUT	RS-232/RS-422 Communications

Note: *The factory default is Jumper OUT enabling RS-232 and RS-422 communications.*

E12 and E13

E12	E13	Synchronous or Alternating Operation Configuration
IN	OUT	Alternating Operation
OUT	IN	Synchronous Operation

Note: *Factory default setting is E12 IN, E13 OUT.*

E3 to E10

Jumpers E3 to E10 control discrete I/O bit directions.

E3 to E10	I/O Configuration
IN	Output
OUT	Input

Note: *Factory default settings are all jumpers OUT configuring all lines as INPUTS.*

3 Powering up the 6420

In this chapter This chapter explains how to power up the 6420 after installation.

3.1 Testing the Installation

Background Perform the following test procedure to verify that the 6420 is installed properly and that is was not damaged internally during shipment.

Configuration The installation and power-up procedure requires a motor and computer or terminal to test the basic functionality of the 6420.

Procedure After performing the installation per the guidelines given in Chapter 2, “Installing the 6420,” test your installation as follows.

Warning

Perform this initial power-up with the motor shaft disconnected from the load. Improper wiring or undiscovered shipping damage can result in undesired motor motion. Be prepared to remove power if excessive motion occurs.

3.1.1 Connections test

Introduction Before beginning the connections test, please check the following:

- all wiring and mounting to verify correct installation
- specifications to ensure that voltages being applied do not exceed the voltages specified.

Procedure

1. Connect only J2 (unregulated 24 Vdc to 75 Vdc input) to the 6420 then apply power.
2. Verify +5.7 Vdc at the 6420 J5-13 to J5-5 (voltage should be 5.2V to 5.9V). If it is not, refer to "Troubleshooting section."
3. Switch power OFF.
4. Connect the J3 motor connector.
5. Switch power ON again.
6. Verify that the motor has holding torque by attempting to rotate the motor shaft. The energized shaft is either immovable or very resistant to rotation when the drive is enabled.
7. Connect the J4 RS-232 connector. Cycle power to the controller. If using a PC, use the 6420 Dialogue disk to set up your PC as a dumb terminal as described in Section 6.
8. Type ESC and then a single space character. The controller should respond with a pre-defined sign-on message:

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   v1.10

9. Enable the 6420 by connecting J5-7 (Enable1) to J5-5 (GNDA).
10. From the terminal or computer type, **R100<enter>**.

    This will move the motor at a velocity of 100 steps per second clockwise.

11. Type **R-100<enter>**. This will change the direction of the motor rotation.
12. Type **S <enter>**. The motor should stop rotating.

    If the controller passes all of the above, then you may start exercising the unit on your own. If the 6420 does not pass all of the above steps, refer to Section 4.2, "Troubleshooting."

4 Maintaining\Troubleshooting

In this chapter This chapter covers maintenance and troubleshooting of the 6420.

4.1 Maintaining the 6420

Introduction The 6420 module is designed for minimum maintenance. The following cleaning procedure as needed will minimize problems due to dust and dirt build up.

Procedure Remove superficial dust and dirt from the module using clean, dry, low-pressure air.

4.2 Troubleshooting the 6420

Introduction Use the following table to diagnose and correct most problems. If you are unable to achieve satisfactory operation, contact your local Pacific Scientific distributor or Applications Engineering Dept.

Symptom	Corrective Action
No RS-232 Communication	Verify that the 6420 E11 jumper is OUT, placing the 6420 into single-unit, RS-232/RS-422 mode. Verify that the transmit of the host terminal is wired to the 6420 receive and vice-versa. Normally DTE (Data Terminal Equipment) devices transmit data on pin 2 and receive data on pin 3. Verify the serial port settings to be 9600, N, 1. Make sure your host is working properly. Disconnect the D-9 connector from the 6420 unit. Wire pins 2 and 3 of this connector together. Try typing characters on the keyboard, each character should be echoed back to the screen. If not, check your cabling and connectors and refer to your host reference guide.

Table (cont'd)

Symptom	Corrective Action
Motor doesn't spin	Verify that the motor is properly connected with no open wires or shorts. With the 6420 energized, try twisting the motor shaft. If you're able to easily spin the shaft, especially at the higher motor current levels, chances are the motor is disabled. The Drive board J6 pins 5-6 (Enable sense) should be IN and J5 pin 7 (ENABLE) should be wired to a ground pin on the J5 connector. Verify that some motor problem has not created a Fault condition. A FAULT has occured if J5 pin 12 is low or the Read HW status command returns with Bit 7 high. If so, correct the condition that created the fault. If you issued the T command with Indexer jumpers E12 and E13 set for alternating operation, you may have disabled step pulses to the motor. Double check your jumper configuration and usage of the T command.
Motor spins, but tends to stall	Experiment with the M command by issuing M 255 255 which results in the slowest possible acceleration and deceleration. Possibly your motor cannot generate enough torque for your application. Try resizing.
Unit will not respond to commands	If the power supply is not adequate for the load, a momentary drop in power may reset the unit, and require that the sign-on procedure be repeated. It is possible a maximum velocity value, well above the specified range may have been executed. Try cycling power and resetting any erroneous parameters before issuing another motion command. If the error occurs in an AUTOSTART program, try ESCaping as soon as possible before the maximum velocity is attained. Cycle power.

If the 6420 is defective

If you cannot correct the drive problem, or if it is defective, return it to Pacific Scientific for repair or replacement.

Return procedure

1. Call Pacific Scientific at (815) 226-3100 from 8 am to 6 pm Eastern Standard Time to get a Returned Materials Authorization Number (RMA#).

   Note: *Do not attempt to return the 6420 or any other equipment without a valid RMA#. Returns received without a valid RMA# will not be accepted and will be returned to the sender.*

2. Pack the drive in its original shipping carton. Pacific Scientific is not responsible or liable for damage resulting from improper packaging or shipment.

3. Ship the drive to:

   Pacific Scientific
   Motion Technology Division
   110 Fordham Road
   Wilmington, MA 01887
   Attn: Repair Department, RMA# _____

   Note: *Do not ship Pacific Scientific motors to the above address. The correct address for motors is:*

   Pacific Scientific
   Motor Products Division
   4301 Kishwaukee Street
   Rockford, IL 61105
   Attn: Repair Department, RMA# _____

Shipment of your drive or motor to Pacific Scientific constitutes authorization to repair the unit. Refer to Pacific Scientific's repair policy for standard repair charges. Your repaired unit will be shipped via UPS Ground delivery. If another means of shipping is desired, please specify this at the time of receiving an RMA#.

5 Programming Overview and Instruction Set Description

5.1 Modes of Operation

Introduction

The 6420 can operate in Immediate or Execution Mode. Immediate Mode is an interactive, command line mode where commands are entered and immediately executed. Immediate Mode is used during program development or when controlling the unit with a host computer. Execution Mode is used when the 6420 is executing a program out of its non-volatile memory, usually when used as a standalone Indexer. During power-up if the AUTOSTART program is found at location 1600 in non-volatile memory, execution will begin at 1600. If the REMOTE START line is activated (LOW) in Immediate Mode, the unit will start executing the program at location 0 in memory.

5.1.1 Immediate Mode

After power-up, providing that neither REMOTE START nor the AUTOSTART are active, the 6420 will be in Immediate Mode. If the 6420 is configured for RS-232/RS-422 serial communications, it will wait for one ESC and one space character and then respond with the Pacific Scientific sign-on message and copyright notice. Commands are sent via the serial link and are terminated with a carriage return <CR>. The 6420 responds with any requested data followed by a <CR><LF>. Only one command can be sent at a time. Motion commands will immediately echo a <CR><LF> and carry out the motion in the background. If a second motion command is sent to the 6420 while another is in progress, the <CR><LF> response will be delayed until the original command is complete.

Programs can be entered into non-volatile memory while in Immediate Mode. Either a terminal emulator program or the Pacific Scientific “6420 Dialogue” can be used to facilitate program development. The E address command allows you to edit a program starting at the location specified by address. The starting address is echoed indicating where the command will go in memory. You can continue to enter successive commands line by line. If an entry error occurs before <CR>, the backspace or delete key can be used to correct the error. If the error is noticed sometime later, leave the edit mode by entering E <CR> and start editing at the line where the error was made by entering E error_address followed by <CR> . If you want to selectively change only the line where the error was made, enter the new command followed by <CR> as you normally would do, but leave the edit mode by pressing the ESC key instead of E <CR>. If you inadvertently enter the E <CR> combination, the next command in the program will be over-written with an invisible program termination code and you will have to go back and selectively replace this line. If you want to continue editing the program from this point on, continue to do so and conclude editing with E <CR>. You can test the program by using the G address command to execute the code. The program will continue to execute until it completes or you press the ESC key.

If the 6420 is configured for multi-unit RS-485 communication, no sign-on message will appear. Commands are sent to individual units based on a pre-assigned node address (assigned in single-unit mode as described in the “Serial Communications Port - J4” section) followed by the command, terminated by a line feed <LF> character. Once a unit recognizes it’s single-letter node address, that address character and commands entered up to the <LF> will be echoed back to the user.

5.1.2 Execution Mode

Once the program starts it will continue to execute until it is done, aborted with the S0 command embedded in the program, is aborted by the ESC or S keys or by the REMOTE STOP line.

5.1.3 The AUTOSTART Program

During power-up if a program is found at location 1600 in non-volatile memory, that program (the AUTOSTART program) will be executed. This program can be aborted by pressing the ESC or S keys, both forcing the unit back to the power-up state, waiting for the ESC and space character sign-on sequence.

5.2 Instruction Overview

Introduction The 6420 offers a variety of instructions for motion and program control in addition to several utility instructions. All instructions can be entered on a command line basis in immediate mode with many, but not all available for use within programs executed from on-board non-volatile memory. The instruction categories include:

Motion Control Incremental and absolute indexes, run at constant velocity and home to a known position. All the motion commands immediately echo <CR><LF> and carry out their motion in the background. The incremental and absolute indexes execute a trapezoidal velocity profile, accelerating from the initial velocity, accelerating to the final velocity, decelerating back to the initial velocity ending at zero velocity.

Program Control Such as P for program mode, G for executing programs and jumping within a program, J and B for executing interative loops, U for conditional branches based in the input ports.

Parameter Initialization Such as F to set the initial velocity, V to set the final velocity, M to set the acceleration and deceleration profiles, O to setup for a position trip point.

Initialization and Utility Commands Such as A to initialize memory, P to store current parameter values, E to edit a program.

5.3 Memory Map

User programs Approximately 1792 bytes are available for user programs. The maximum size of a program in terms of number of command lines is dependent on the actual commands used since each command is composed of 1 to 5 bytes. In general, programs can be entered into the entire 1792 byte range of "User Programs" memory, however, certain commands when utilized, require specific areas of memory to be reserved for their use.

Fast RAM In addition, there is a 64 byte segment, extending between locations 128 to 191 marked as "Fast Ram." This area is fast static RAM inside the microprocessor used when a specific command (the Trip and Output) requires it and when higher response or looping speed is necessary in an application. As the name implies, this area is NOT saved when the unit is powered-down. To save the program(s) in this area to non-volatile memory, you must issue the P command. Upon power-up the contents will be restored automatically.

Memory Map Details

Address	Description
0-255	User Programs. Location 0 is the starting location when the REMOTE START input is activiated. Locations 128-192 are FAST RAM locations and are not saved when the unit is powered down until **P** (Store parameters) is issued.
256-511	User programs and G 2048 Indexed jump
512-767	User Programs
768-1023	User Programs
1024-1279	User Programs
1280-1535	User Programs
1536-1791	User Programs. Location 1600 is starting address for AUTOSTART.
1792-1893	RESERVED: Variable resolution fraction look-up table.
1894-2047	RESERVED: Motion parameter storage, may be read by the Read Memory command >.

6 6420 Dialogue

6.1 Description of 6420 Dialogue

Introduction

6420 Dialogue is a menu driven software package that contains several software utilities to aid in the use of Pacific Scientific Digital Motion Control Products. These utilities are designed to run on an IBM compatible PC and interface to the Pacific Scientific motion control hardware via an RS-232 serial link. The Main Menu summarizes the tools available:

1) Terminal Emulator

- The Terminal Emulator utility allows the PC to be used as a dumb terminal. In this mode, the PC is acting as a terminal and allows the generation and editing of programs directly on the hardware (i.e. on-line).

2) Upload Utility

- The Upload Utility allows files to be read out of the controller's memory into a file on the PC's floppy or hard disk drive.

3) Download Utility

- The Download Utility allows files to be taken from the PC's disk drive and transferred into the position controller's memory.

4) Syntax Checker

- The Syntax Checker allows programs to be checked for errors before transferring them to the controller.

5) Editor

- The Editor allows the creation and editing of programs. Programs can be created and edited without the controller being connected to the PC (i.e. off-line). The resulting program can be stored on the PC's disk drive for downloading to the controller at a convenient time. Also, programs can be read from the hardware using the Upload Utility and be modified using the Editor.

6) Init Serial Port

- The Init Serial Port option allows the user to select a COM Port for serial communication.

6420 Dialogue is contained on a single 3-1/2 inch diskette.

6.2 Getting Started

6420 Dialogue can be executed directly from the 6420 Dialogue disk supplied or it can be installed on the PC's hard disk. If 6420 Dialogue is to be executed directly off the disk supplied, it is recommended that a backup copy be made and stored in a safe place.

6.2.1 Using the 6420 Dialogue Floppy Disk

Follow the steps below to use the 6420 Dialogue floppy disk:

1. Boot up the PC
2. Set the PC to directory A:
3. Insert the 6420 Dialogue floppy disk into drive A
4. Type 6420 **<enter>**

6420 Dialogue will be loaded and the Main Menu screen will appear. 6420 Dialogue is now running and you can select the tool desired.

6.2.2 Installing 6420 Dialogue on a Hard Drive

The 6420 Dialogue disk is supplied with an installation program. This program will create a sub-directory named \6420 on the hard drive and copy the 6420 Dialogue files from the floppy disk into the sub-directory. The installation program assumes that the hard drive is designated C:.

To install 6420 Dialogue on the PC's hard drive, follow the steps below:

1. Boot up the PC
2. Insert 6420 Dialogue disk in drive A
3. Type A: INSTALL **<Enter**>

6420 Dialogue is now installed on the hard disk. To run 6420 Dialogue get to the 6420 directory, and type 6420 **< Enter** >.

6.2.3 Serial Port Connections

6420 Dialogue can be used to generate programs off-line. However at some point programs have to be downloaded or uploaded between the PC and the motion control hardware. The RS-232 serial link is used to communicate between the PC and the hardware.

Many PCs have two serial communication ports, COM1 and COM2. One of these must be wired to the motion control hardware. Refer to the PC's Hardware Reference Manual and the Instruction Manual provided with the motion control hardware for wiring information. Use the Init Serial Port tool on the Main Menu to select the correct COM port and to set the serial link parameters.

Note: *Default Serial Link Parameters for the 6420 are displayed.*

6.3 Keyboard Commands

The choices from a main menu are highlighted by typing the **<Up >** or **<Down>** arrow keys. Selection of the highlighted item is made by entering the choice with the **<Enter >** key. This selection will bring up a prompt, a list and/or a sub-menu. Choices are made from a sub-menu or list using the **<Up>** key to move up, or the **<Down >** key to move down, then entering a choice with the **<Enter >** key.

Typing the **<Esc>** key will abort the current operation, and return to the previous menu, or exit the program. The **<Esc>** key is also used to exit from the Editor. To exit from a Terminal Emulator session, type **<Ctrl><E>**.

The keyboard command definitions are displayed in appropriate places on the screen to assist the user.

6.3.1 Terminal Emulator

The PC can be used as a dumb terminal to communicate with the selected controller. The PC's serial port is initialized when 6420 Dialogue is started. The parameters can be changed with the Init Serial Port utility.

To exit the Terminal Emulator at any time, type **<Ctrl><E>**, which returns to the Main Menu.

6.3.2 Upload Utility

After selecting this utility, the user is prompted for what filename to name the uploaded file. By default, the uploaded file will be created in the current directory. If the user selects a filename that already exists, then it will be overwritten, thus it is good practice to use a different extension or filename for the uploaded file. In particular, the filename.ext of the source file that was downloaded should not have the same filename.ext as the uploaded file, or the source file contents will be replaced with the uploaded file. When choosing extensions for filenames, the use of ".LST" should be avoided. The ".LST" extension is used by the 6420 Dialogue program for the listing files created by the Syntax Checker.

Note: *The Upload Utility will not function properly if voids (empty addresses) exist between sections of code in the memory. Contact the factory for additional information.*

After a file has been successfully uploaded, the message "Upload completed" is displayed. If the **<Path>**\filename.ext is unacceptable, then the message "Couldn't open file" is displayed.

When uploading a file, labels will be generated for any branch to address command. Note that for a program that has been downloaded, the symbolic labels and references are stripped out and replaced with numeric addresses. At uploading, these have been replaced with numeric sequential labels. It is good practice to use a different extension or filename for uploaded files. Label generation for Pacific Scientific Indexer Language is covered in Section 6.7, "Upload Utility."

6.3.3 Download Utility

After selecting this utility, the user is prompted for a **<Path>**\filename.ext which can be typed in or selected from the current directory list. If the download is successful, the message "Download completed" is displayed.

6.3.4 Syntax Checker

By using the Syntax Checker, programs can be checked for syntax validity, prior to downloading or running.

Syntax Checker creates a listing file with the extension ".LST" given to the file that was sent to Syntax Checker or sent to the Download Utility (which automatically calls the Syntax Checker). If the syntax check is successful, the message "No syntax error(s) detected" is displayed and the listing file with the message "NO ERRORS FOUND" is sent to the display. If errors are found, then the message "Syntax error(s) detected" is displayed, and the listing file, containing the program code and syntax error messages, is displayed. The Editor can be used to review the syntax errors listed in the .LST file. The syntax checking for Pacific Scientific Indexer Language is discussed in Section 6.4.

To reposition the syntax error dialog box, press **F2** and then use the arrow keys to move to the desired position. Once the dialog box is positioned, press **F2** or <**Enter**> to see errors. To edit a line, you must return to the editor.

6.3.5 Editor

After selecting this utility, the user is prompted for a<**Path**>\filename.ext which can be typed in or selected from the current directory's file listing. If the filename does not exist, the user is prompted with "Create?" to which the response is **Y** (yes) or **N** (no). If answering "no", the system responds with the message "can't load file" (it doesn't exist), after which, a <**Enter**> returns to the Main Menu level. If answering "yes" to the prompt, the user is put into the Editor.

When exiting the Editor (typing <**Esc**>), the user is prompted with the question, "Save file (y/n) ?" Answering n <**Enter** > , returns to the Main Menu, without saving the file, and any edits are lost. Answering y <**Enter**> will bring up a prompt for the filename. The current file being edited can then be saved under the existing filename by typing <**Enter**> , or, the name can be changed by typing over the current filename, followed with <**Enter**>.

While using the Editor, many operations such as justify, cut, paste, etc. are available. These operations are assigned to various keys:

ESC	Exit the Editor.
INSERT	Toggles insert and typeover mode, (**default: typeover mode**).
F7	Attach file to the end of current file (**default: off**).
F8	Toggles whether hard and soft carriage returns are symbolically displayed in the edit window, (default: not displayed)
F9	Toggles editor display from 128 ASCII characters to 256 IBM characters, (**default: ASCII characters**).
F10	Reformats a paragraph.
UP ARROW	Moves cursor up a line.
DOWN ARROW	Moves cursor down a line.
LEFT ARROW	Moves cursor left a space.
RIGHT ARROW	Moves cursor right a space.
CTRL-A	Move cursor one word to the left.
CTRL-F	Move cursor one word to the right.
CTRL-Y	Delete line cursor is on.
CTRL-Z	Scroll up a line.
CTRL-W	Scroll down a line.
HOME	Move cursor to beginning of line.
END	Move cursor to the end of line.
PGUP	Previous Page.
PGDN	Move to top of screen.
CTRL-END	Move to bottom of screen.
CTRL-PGUP	Move to beginning of file.
CTRL-PGDN	Move to end of file.
TAB	Tab.

ALT-M	Begin marking a block of text, use cursor arrows to mark rest of block.
ALT-C	Copy marked block to scrap.
ALT-X	Cut marked block to scrap.
ALT-P	Paste scrap at cursor position.
ALT-S	Search for pattern (target); starts search, cancels search.

6.3.6 Init Serial Port

After selecting this utility, the serial port parameters can be initialized or changed. If the parameters do not need to be changed, then type **<Esc>.** Typing **<Esc>** at any point in the Init Serial Port menu will exit without saving any changes to the parameters.

The parameters are selected by using the up or down arrow keys. As each parameter is highlighted, its sub-menu displays the list of each parameter's values. The choices can be selected with the **<Up>** and **<Down>** keys. A parameter and its value are entered with a **<Enter>**.

To exit the Init Serial Port menu after making changes to any parameters, type **<Enter>** after the last parameter in the menu. Any changes made to the parameters are saved to a disk file in the current directory after exiting the Init Serial Port menu, and thus are used as the default settings, upon the next invocation of 6420 Dialogue. These default settings are stored in a binary data file named 'PORT.CFG'.

6.4 Indexer Language for the 6420 Series

Introduction

Pacific Scientific Indexer Language is a modified form of the program language of the Pacific Scientific Model 5240 Stepping Motor Indexer/Drive.

The language for the 6420 has been modified so that symbolic labels can be used as the operand for branch to address commands, for example “J”, the JUMP command. Syntax checking is done on the Indexer Language, and labels are translated to their target address by the Syntax Checker before a program is downloaded. When a program is uploaded, labels are generated for the operands of branch to address commands.

6.4.1 Use of Symbolic Labels in Programming

A line of program code has this format:

<LABEL> COMMAND OPERAND1 OPERAND2

where LABEL is optional, and OPERAND2 exists for some commands. One or more blanks must be used between a label and a command, or between operands, but blanks are not necessary between the command and OPERAND1. Tabs may be used in place of blanks. The branch to address commands, “G” (GOTO), “J” (JUMP) and “U” (LOOP), may have a label or an address for OPERAND1. The label reference in OPERAND1 must have a matching label somewhere in the program, or a syntax error is generated. Duplicate label names are not allowed and will cause a syntax error to be generated.

The format for a label is:

$ < STRING >

where there are no blanks between the dollar sign ($) and the string. The string is limited to eight characters composed of any sequence of digits and letters (including the underscore). Any variation from this format will generate a syntax error. The maximum number of labels allowed for any program is 200.

Note: *Labels are only used in the Editor Mode.*

Example Here is an example program that uses labels:

```
$ begin     k
            j $ begin 1
$ loop      +1000
            u $ loop 5
            g $ end
$ end       s
```

The labels in this program are “begin”, “loop”, and “end.”

6.5 Syntax Checker

The Syntax Checker checks for valid syntax for each line of code. If no syntax errors are found, the Syntax Checker takes out all symbolic labels and label references, and inserts the target address for each label reference, (a label reference is a label used as the operand for a branch to an address command).

If an error is found, the program and error messages are put into a listing file which is displayed. The possible error messages are listed below:

1. “invalid input; label or program command expected”
2. “invalid label; expecting alphanumeric after delimiter”
3. “invalid label or, expecting valid command after label”
4. “invalid operand; digit ‘1’ expected”
5. “invalid operand; expecting digit”
6. “EOL encountered; expecting operand”
7. “invalid input;no operand required”
8. “invalid input; expecting EOL character”
9. “invalid input; expecting valid number or label”
10. “illegal for this command to have a label reference”

Messages (cont'd)

11. "invalid operand; +,- character not allowed after +,- command"
12. "invalid number; input number is out of range"
13. "invalid operand; reference to nonexistent label"
14. "invalid label; duplicate label name exists"

Note: *The end of line character (EOL), which is defined as the linefeed character, is expected at the end of each line of code.*

6.6 Download Utility - Address Translation of Labels

Before a 6420 program is downloaded, it is automatically syntax checked. If there are no syntax errors, the Syntax Checker takes out all labels from the program and translates the label references to address. The program thus contains only commands and numeric operands, and is downloaded to the controller.

6.7 Upload Utility - Label Generation for Addresses

When a 6420 program is uploaded, labels are generated for the operands of branch to address commands. The labels are then inserted in the appropriate places in the program. The labels generated have the form $Lxxx, where the labels are sequentially generated starting with $L000.

Note: *If a 6420 program is written off-line on the PC with labels and then downloaded, when the program is uploaded the labels will take the form described above. The labels used in the program prior to downloading will exist only in the original file on the PC.*

To avoid confusion when developing 6420 programs, it is recommended that the labeling scheme used by the Upload Utility be followed. That is, when writing a 6420 program on the PC, use labels of the form $Lxxx starting with $L000 and progressing sequentially through the program. By following this practice, a program will not change labels when downloaded and then uploaded.

7 6420 Programming Instructions

In this chapter

This chapter contains detailed descriptions of the 6420 commands. The command and the mode of operation where it can be used is listed at the top of the page. Commands are then described using the following format:

Purpose - purpose of the instruction

Syntax - exact format of the command

Programming guidelines - pertinent information about using the command

Example - showing use of the instruction in a program segment

A (Clear and Restore)

A *opcode*

Immediate

Purpose

This command is used to initialize a portion of non-volatile memory. Non-volatile memory is segmented into 8 pages. The specified *opcode* determines precisely the page to be erased, reloaded or initialized.

Syntax

A *opcode*

Arguments

A0	Reloads the last saved parameters from NVRAM
A1 to A7	Erase the corresponding page in NVRAM
A8	Completely initializes NVRAM to default values.
A9	Initializes variable resolution fraction look-up table to default values. List of 100 eight-bit values starting at location 1792 in NVRAM

Programming guidelines

Memory Map Details:

Erase Cmmd	Address	Notes
A1	0-255	User programs. Location 0 for REMOTE START input. Locations 128-192 are Fast RAM locations.
A2	256-511	User programs and G 2048 Indexed jump
A3	512-767	User programs
A4	768-1023	User programs
A5	1024-1279	User programs
A6	1280-1535	User programs
A7	1536-1791	User programs. Location 1600 for AUTOSTART.
XX	1792-1893	RESERVED: Variable resolution fraction look-up-table
XX	1894-2047	RESERVED: Motion parameter storage, can be read by the Read Memory command

C (Read Position Counter)

C *arg*

Immediate

Purpose

Displays current position counter value. In Fixed Resolution Mode the value is an integer. In Variable Resolution Mode, a mixed integer/fractional value in range of ± 8,388,607.99 to steps. Specifying *arg* = 1, enables continuous echoing of position via the serial interface only in single-unit mode.

Syntax

C *arg*

Arguments

arg is 0, 1

Programming guidelines

This command is normally used when the 6420 is controlled by a host computer or with a terminal emulator.

Type **Z <Enter>** followed by **C <Enter>**. The value 0 should be displayed. Index incrementally by typing **+200 <Enter>**. Type **C <Enter>** again and 200 should now be displayed.

E (Edit Program)

E *addr*

Immediate

Purpose

Allows entry of user programs for subsequent execution by the G (GO) command or execution of a program at location 0 with activation of the Remote Start input or AUTOSTART at power-up. The *addr* argument specifies the address at which to edit a new or existing program.

Syntax

E *addr*

Programming guidelines

Example

Program line	**Explanantion**
E 100	Edit a program starting at location 100
M 10 10	
F 400	
V 1200	
+ 1000	
E	

Edit Program mode is entered by the E 100. Various commands are entered and terminated by <Enter>. When completed, the last E inserts a terminator byte at the end of the program, over-writing any pre-existing data. The ESC key instead of the last E will prevent over-writing the next command, which is useful for patching in corrections to an existing program when using a terminal emulator.

Program execution can be interrupted by Remote Stop, ESC, or the S key. After interruption of an AUTOSTART program, the sign-on procedure must be carried out.

F (Initial Velocity)

F *vel*

Immediate, Execution

Purpose

Sets the initial velocity to *vel* pulses/second. In Fixed Resolution Mode the actual speed in steps per second is determined by the current step size.

Example

If vel = 1000 and the step resolution is set for Full Steps (200 pulses/rev), then the shaft spins at 1,000 full steps/sec or 300 RPM. If vel = 1,000 and the step resolution is set for 1/8 Steps (1,600 pulses/rev), then the shaft spins at 125 full steps/sec (37.5 RPM)

In Variable Resolution Mode, the speed is determined by the VelScale factor.

Example

If VelScale has been set by issuing \ 0 (the nominal value), and vel = 1000, then the shaft spins at 1,000 full steps/sec (300 RPM). If VelScale has been set by issuing \ 2, and vel = 1000 then the shaft spins at 250 full steps/sec (300 RPM * .25 = 75 RPM).

Syntax

F *vel*

Arguments

$0 \leq vel \leq 19{,}000$

Related Commands

V — Set final velocity

Programming guidelines

Program line	Explanation
F 300	set the initial velocity
V 3000	

G (Go)

G *addr* [*trace*]

Immediate, Execution

Purpose

Executes a user program at a specified *addr*. The optional trace argument allows execution tracing. The *addr* specifies the starting address of a program in the range of 0 to 1791. A special case is where *addr* = 2048, which executes an “indexed” jump based on the lower 4 I/O port bits to 16 locations within address locations 256 to 496.

Syntax

G [*trace*

Arguments

0 ≤

0 M 10 10

3 F 300

execute Indexed Jump

Jump Table

The following jump table is used for an indexed jump which might be used for a rotary switch used to select 1 of 16 different operations.

Jump Loc	P4	P3	P2	P1
256	1	1	1	1
272	1	1	1	0
288	1	1	0	1
304	1	1	0	0
320	1	0	1	1
336	1	0	1	0
352	1	0	0	1
368	1	0	0	0
384	0	1	1	1
400	0	1	1	0
416	0	1	0	1
432	0	1	0	0
448	0	0	1	1
464	0	0	1	0
480	0	0	0	1
496	0	0	0	0

H (Home)

H *speed dir*

Immediate, Execution

Purpose

The Home instruction initiates a search for the home position. Home is executed with *dir* set for motion that will move the assembly towards the home switch at *speed* steps/second. When the home position is reached and the home input switch is activated, the motor will reverse direction and move at a speed equal to the Initial Velocity parameter until the home switch is de-activated. The activated level should be a logic "0," and the de-activated level a logic "1."

Syntax

H *speed dir*

Arguments

20 ≤ *speed* ≤ 19,000 steps/second

dir must be 1 for CCW or 0 for CW

Related Commands

F — set Initial Velocity

Programming guidelines

Example 1

The system is designed so that CW motion advances toward Home. The Home switch is not active and H 250 0 is executed: Motion will be CW at 250 steps/second until switch is activated, then motion flips to CCW at the Initial Vel (50 steps/second) until switch is de-activated and then motion stops.

Program line	**Explanation**
M 10 10	set accel/decel factors
F 50	set initial velocity
H 250 0	home

Example 2

The system is designed so that CCW motion advances toward Home. The Home switch is not active and H 250 1 is executed: Motion will be CCW at *speed* until switch is activated, then motion flips to CW at the Initial Vel (F) until switch is de-activated and then motion stops.

Program line	**Explanation**
M 10 10	set accel/decel factors
F 50	set initial velocity
H 250 1	home

mode

Immediate

Purpose

This instruction selects Fixed or Variable Resolution Modes. Fixed Resolution Mode allows a fixed step size to be selected by the \ (Step Size) command. Of course, fine step sizes result in proportionately slower stepping rates. Variable Resolution Mode allows high-speed, high-resolution indexes to be executed without compromising speed.

A mode value of 0 selects Fixed Resolution Mode. Stepping proceeds at fixed resolution selected by Step Size command (\).

A mode value of 1 selects Variable Resolution Mode. Step resolution is automatically adjusted during an index dependent upon Initial and Final Velocity parameters. Step resolution is 20,000 pulses/rev.

The Q command displays the resulting Initial and Final Velocity parameters and range of step sizes to be used in subsequent absolute and incremental indexes.

Syntax

I

Arguments

mode = 0 selects Fixed Resolution Mode

mode = 1 selects Variable Resolution Mode

Programming guidelines

Note: *Normally a preset operating parameter. Should not be incorporated into a non-volatile memory based program. Issue the P command to save changes to the operating mode.*

J, B (Jump Loop, Nested)

J *addr cntr*

B *addr cntr*

Execution

Purpose

These two commands allow implementation of a doubly nested loop structure. The primary "J" command and secondary "B" command can be nested. However, "J" is for jump outer loop while "B" is for jump inner loop. The *addr* specifies the loop's destination address. The *cntr* value plus 1 is the actual number of iterations. Therefore, *cntr* value must be set to the desired iterations minus 1. Either command can be used if only a single loop is required.

Syntax

J *addr cntr*

B *addr cntr*

Arguments

$0 \leq addr \leq 1791$

$0 \leq cntr \leq 255$ for 1 to 256 iterations

Programming guidelines

The following example illustrates a 2 axis system, where a master 6420 controls one axis and a slave 6410 drives the other axis. The program indexes the master axis a total of 4 times; and for each of these indexes, the slave axis 8 times.

Program line		Explanation
E0		
0	F 100	
3	T 1	Outer loop begins, use J
5	+ 1000	
10	W 0	
13	T 0	enable slave axis
		Inner loop begins, use B
15	+ 1500	index 1500 steps along slave axis
20	W 0	till complete
23	W 100	wait 1 second
26	B 15 7	Repeat slave axis motion 8 iterations
		End of inner loop
30	J 3 3	for every master index, repeated 4 times
		End of outer loop

K (Read Input Port)

K

Immediate

Purpose

Reads user defined I/O ports. The bits are active low, so a logic "0" applied to the input port reads back as a "1."

Syntax

K

Arguments

None. The bit weightings are:

Port 1 = 1	Port 5 = 16
Port 2 = 2	Port 6 = 32
Port 3 = 4	Port 7 = 64
Port 4 = 8	Port 8 = 128

Related Commands

Y — Write Port

Programming guidelines

To program an I/O port bit as an input, the respective I/O configuration jumper must be removed. Ports 1 through Port 8 are configured by jumpers E3 to E10 respectively. Remember, as a consequence of the internal processor wired "AND" design of the I/O port, a logic "1" inadvertently written to an I/O port configured as an input will over-ride the actual input state and hence will always be read back as a logic "1." Therefore, an inactive level (logic "0") must be written to input bits.

Type **K <Enter>**. The value of P8-P1 should be displayed, with the least significant bit representing P1.

L (List Program)

L *addr*

Immediate

Purpose

Produces a listing of instructions starting from the specified *addr* returning upto 20 command lines. Programs will be listed until a program terminator byte is encountered.

Syntax

L *addr*

Arguments

$0 \leq addr \leq 1791$

Programming guidelines

Enter a program starting at location 0 in memory. Type **L 0.** The program should now be listed on the screen.

M (Accel/Decel Factor)

M *accel decel*

Immediate, Execution

Purpose

The *accel* and *decel* values determine acceleration and deceleration profiles respectively. Accel/Decel ramps are determined by lookup table and are NOT specified in terms of dv/dt. The Initial and Final Velocity parameters are used as indicies into a lookup table to determine a range of step speeds to be applied to the drive. The time spent at any given step speed within the range is determined by the *accel* and *decel* values, and hence, determine how quickly the drive ramps up or down in speed. The arguments must be in the range of 5 to 255. Values towards the low end result in high acceleration rates and conversely, values towards the upper end result in lower acceleration rates. The current *accel* and *decel* values can be saved in non-volatile memory by issuing the P (store Parameters) command.

accel ≤ 255

1 ≤ *decel* ≤ 255

Related Commands

F — Set Initial Velocity

V — Set Final Velocity

Programming guidelines

Program line		Explanation
M	100 50	accel factor 100, decel factor 50

O (Trip Point)

O *position vaddr*

Execution

Purpose

Allows program to vector to the location specified by *vaddr* when the position counter equals the specified position value. The *vaddr* must be in the range of 0 to 255 and *position* in range of ±8,388,607. The *position* must be a whole integer value in both Fixed and Variable Resolution modes.

Trip Point service routines generally contain I/O instructions and new trip point specifications and should not contain index, wait or other time consuming instructions. A *position = 0* disables this function. For the trip to occur, the main program must be still actively running and not in idle mode.

Syntax

O *position vaddr*

Arguments

-8,388,607 ≤ *position* ≤ +8,388,607

0 ≤ *vaddr* ≤ 255

Related Commands

T — Set Trip Point

Programming guidelines

Program line	Explanation
E0	
0 Z	
1 O 5000 128	Trip at position 5000 to location 128
6 + 18000	
11 W 0	
14 G 0	Program still running
E	
E128	
128 Y 1	Activate P1 LOW
130 E	

P (Store Parameters)

P

Immediate

Purpose

Stores parameters to non-volatile memory. Values are restored to working memory upon power-up and by issuing the A0 command.

Syntax

P

Arguments

none

Programming guidelines

Type **P <Enter>**. All paramters and fast memory locations 128-191 will be saved to non-volatile memory in addition to the following parameters:

Initial Velocity (F)
Final Velocity (V)
Ramp slope (M)
Jog Speed (^)
Trip Point (O)
Resolution Mode
Limit Switch Polarity
RS-485 Node Address
User Programs

The default mode after memory initialization is Variable Resolution Mode at Full Speed.

Note: *Whenever a change in any of these parameters or code in Fast RAM locations 128-191 is to be saved during power cycling, the* ***P command must be executed****.*

Q (Examine Parameters)

Q

Immediate

Purpose

Displays current parameters and system settings. Returns a variable number of lines depending on mode of operation. Only in Single-User Mode.

Syntax

Q

Programming guidelines

Type **Q <Enter>**. The screen should show the following parameter information:

M accel, decel, I = *VR* or *FR*, na = axis name, O = *trip pos* / *trip addr*

F = *initial vel* (*vel/stepsize*), V = *final vel* (*vel/stepsize*), (rl = *accel length*)

The *initial vel* and *final vel* are the programmed initial and final velocity values set by the F and V commands. The actual velocities also depend on the selected StepSize and Resolution Mode. For instance in Fixed Resolution Mode with Half Step Size (\ 1), F=400, V=1000, the second line would appear as:

F = 400 (400/2) V = 1001 (1001/2) rl = 2

Notice that the displayed velocities may not be exactly those that where specified. This is a result of truncation and roundoff errors during integer division calculations. The values within the parentheses (400/2) and (1001/2) indicate the actual velocity values are 200 and 500.5 full steps/second because of the half step size selected.

Programming guidelines

In Variable Resolution Mode, Full Step Size (\ 0), F=400 and V=1000, the second line would appear as:

F = 400 (12800/32) V = 1001 (16168/16) rl = 2

The values (12800/32) and (16168/16) indicate the actual velocity values are 400 and 1000 full steps/second and the automatically chosen step sizes are fine as 1/32 step. The \ 1 command scales velocity and the choosen automatic step sizes producing the expressions (12800/64) and (16168/32) resulting in actual velocity values of 200 and 500 full steps/second.

R (Run at Constant Velocity)

R *vel*

Immediate, Execution

Purpose

The Run instruction ramps up or down to the specified *vel*, expressed in pulses/second. In Fixed Resolution Mode the actual speed in steps per second is determined by the current StepSize. So, if vel = 1000 and the step resolution is set for Full Steps (200 pulses /rev), then the shaft spins at 1000 full steps/sec or 300 RPM. If vel = 1000 and the step resolution is set for 1/8 Steps (1600 pulses/rev), then the shaft spins at 125 full steps/sec (37.5 RPM).

In Variable Resolution Mode, the speed is determined by the VelScale factor. So, if VelScale has been set by issuing \ 0 (the nominal value), and vel = 1000 then the shaft spins at 1000 full steps/sec or 300 RPM. If VelScale has been set by issuing \ 2, and vel = 1000 then the shaft spins at 250 full steps/sec or 75 RPM.

Note: *In Variable Resolution Mode, direction is determined by the sign of velocity.*

Syntax

R *vel*

Arguments

$20 \leq |vel| \leq 19{,}000$

Related Commands

M — set acceleration/deceleration factors

Programming guidelines

Program line	Explanation
M 10 10	set accel/decel factors
F 300	set initial velocity
R 100	accelerate to 100 steps/sec (CW)
W 1000	wait for 10 seconds
R -100	accelerate to 100 steps/sec (CCW)
W 1000	wait for 10 seconds
R 0	ramp down to 0 steps/sec

S (Stop)

S [*arg*]

Immediate, Execution

Purpose

Stops motion with ramping deceleration specified by the M instruction. If the Indexer is currently running a program in execution mode or a motion command, motion will cease with ramping deceleration. If embedded in a program an optional argument can be supplied to abort the current program in addition to stopping all motion. If *arg* = 1 , motion will cease but the program will continue, otherwise with *arg* = 0 the program will terminate, placing the indexer into immediate mode.

Syntax

S [*arg*]

Arguments

None

Programming guidelines

Embedded in a program, will stop motion and abort, returning to idle mode.

Program line	**Explanation**
S 0	or S to stop motion and abort program

Typing S while a program is running will abort the program and return to idle mode.

T (Master/Slave Control)

T *enb*

Immediate, Execution

Purpose

This command is used when one 6420 Indexer/Drive controls motion of two axes, both at Fixed Resolution only. The 6420 is the master unit controlling a slave 6410 Drive. Jumpers E12 and E13 determine if the slave unit is running synchronous with the master, that is, identically executing index commands or in alternating fashion where motion is executed on one axis and then the other independently. Power-up state is T 1.

Syntax

T *enb*

Arguments

Synchronous Operation: E12 OUT, E13 IN

enb = 1 enables step pulses to both master and slave.

enb = 0 disables step pulses to both master and slave.

Alternating Operation: E12 IN, E13 OUT

enb = 1 enables master, disables slave.

enb = 0 disables master, enables slave.

Programming guidelines

The unit is configured for alternating operation. We alternately index each axis by :

Program line	**Explanation**
T 1	enable master indexing
+ 1000	index 1000 steps at current resolution
W 0	wait till done
T 0	enable slave indexing
- 2000	index at current resolution
W 0	wait till done

Note: To be meaningful, both units must be in Fixed Resolution mode.

U (Loop on Port)

U *addr cond*

Immediate, Execution

Purpose

This command tests a single I/O port bit, P1 to P8 and jumps to the specified address *addr* if *cond* is true.

Syntax

U *addr cond*

Arguments

$0 \leq addr \leq 1791$

The *cond* codes are:

0 => Jump if Port 1 high	1 => Jump if Port 1 low
2 => Jump if Port 2 high	3 => Jump if Port 2 low
4 => Jump if Port 3 high	5 => Jump if Port 3 low
6 => Jump if Port 4 high	7 => Jump if Port 4 low
8 => Jump if Port 5 high	9 => Jump if Port 5 low
10 => Jump if Port 6 high	11 => Jump if Port 6 low
12 => Jump if Port 7 high	13 => Jump if Port 7 low
14 => Jump if Port 8 high	15 => Jump if Port 8 low

Programming guidelines

Program line	Explanation
E0	
0 M 10 10	
3 F 300	
6 V 1000	
9 U 40 1	jump if Port 1 Low
13 U 100 3	jump if Port 2 Low
17 G 9	
E	
E40	
40 + 1000	CW 1000 steps
45 W 0	till done
48 U 48 1	wait for release
E	
E100	
100 - 1000	
105 W 0	
108 U 108 3	
E	

V (Final Velocity)

V *vel*

Immediate, Execution

Purpose

Sets the final velocity of an @ (absolute position) or (+ -) incremental move to vel pulses/sec. In Fixed Resolution Mode the actual speed is determined by the current StepSize. So, if *vel* = 1000 and the step resolution is set for Full Steps (200 pulses /rev), then the shaft spins at 1000 full steps/sec or 300 RPM. If *vel* = 1000 and the step resolution is set for 1/8 Steps (1600 pulses/rev), then the shaft spins at 125 full steps/sec (37.5 RPM).

In Variable Resolution Mode, the speed is determined by the VelScale factor. So, if VelScale has been set by issuing \ 0 (the nominal value), and *vel* = 1000 then the shaft spins at 1000 full steps/sec or 300 RPM. If VelScale has been set by issuing \ 2, and *vel* = 1000 then the shaft spins at 250 full steps/sec or 75 RPM.

This parameter does not affect the velocity supplied in the R (Run at constant Velocity), or that programmed for Jog or Home operations.

Syntax

V *vel*

Arguments

$0 \leq vel \leq 19{,}000$

Related Commands

F — Set Initial Velocity

Programming guidelines

Program line	Explanation
V 1000	set final velocity for +, - and @ indexes

W (Wait)

W *period*

Immediate, Execution

Purpose

Waits for a specified period of time. The argument *period* specifies the wait in terms of 10 millisecond periods, hence, the actual wait time is the *period* multiplied by 10 milliseconds. **Specifying *period* to be 0 is a special case that delays completion of the wait instruction until the end of the current motion command, such as an absolute or incremental index.**

Syntax

W *period*

Arguments

0 ≤ *period* ≤ 65,535

Related Commands

+, - and @ indexes

Programming guidelines

Note: *A non-zero wait period executed after issuing a motion command such as absolute or incremental index will immediately start counting down, in parallel to the motion command. Therefore, if the wait period is desired after the motion is completed, use a W 0 followed by the actual wait command.*

Program line	**Explanation**
W 100	wait 1 second
+ 100000	
W 0	wait till index complete

X (Read Limits)

X *arg*

Immediate

Purpose

This command returns the status of the limit, home and jog switches and the Drive Fault status. The value of *arg* specifies whether limit switch or input line information is returned.

Syntax

X *arg*

Arguments

Specifying *arg* = 0, returns 1 for Limit + active, 2 for Limit - active and 3 for both active. Bit 7 is active high if the drive has faulted.

Specifying *arg* = 1, returns a binary weighted value corresponding to the level of these signals:

1 => Home Input

32 => Jog - Input

64 => Jog + Input

128 => Drive Fault

Y (Write Output Port)

Y *port*

Immediate, Execution

Purpose

Writes to user defined I/O ports where the *port* specifies a binary-weighted port selection bit. The port bits are active LOW, e.g. Y 1 activates Port 1.

Syntax

Y *port*

Arguments

$0 \leq port \leq 255$

Y 0 deactivates all bits producing Logic HIGHs

Y 255 activates all bits producing Logic LOWs

Related Commands

K — Read Input Port

Programming guidelines

To program an I/O bit as an output, the respective jumper must be inserted. Ports1 to Port 8 are configured by jumpers E3 to E10 respectively. The bit weightings are as follows:

Port 1 = 1	Port 5 = 16
Port 2 = 2	Port 6 = 32
Port 3 = 4	Port 7 = 64
Port 4 = 8	Port 8 = 128

Note: *Avoid driving a port configured as an output by a low impedance input.*

Program line	Explanation
Y 0	Port 1 to 8 outputs off (open, pulled up)
Y 2	Port 2 output ON (sinking to ground)

Z (Zero Origin)

Z

Immediate, Execution

Purpose

Zeros position counter. This is normally done before a sequence of absolute moves and/or trip sequences.

Syntax

Z

Arguments

None

Related Commands

@ — Absoloute Indexes

Programming guidelines

Program line		Explanation
0	Z	zero origin
1	@ 200	index 1 revolution
6	W 0	wait till done
9	W 100	wait 1 second
12	@ 0	index back to position 0
17	W 0	
20	G 0	loop

^ (Set Jog Speed)

^ *speed*

Immediate, Execution

Purpose

Sets jog speed. This value is multiplied by 30 to determine speed in pulses/second. Acceleration is ramped. Deceleration is normally not ramped except in the case of activating both JOG inputs and releasing one. Jog inputs are active in idle mode, that is, when not in middle in entering a command and while not running a program.

Syntax

^ *speed*

Arguments

$0 \leq speed \leq 255$

@ (Absolute Move)

@ position

Immediate, Execution

Purpose

Indexes the motor to an absolute position given by the internal position counter. In Fixed Resolution mode, the *position* specifies ±8,388,607 pulses. So, if *position* = 200 and StepSize is set for Full steps, the shaft spins 1 revolution. If *position* = 1600 and StepSize is set for 1/8 step (1600 pulses/rev) then the shaft also spins 1 revolution.

In Variable Resolution Mode, the *position* specifies ± 8,388,607.99 Full steps with 0.01 step size resolution (20,000 pulses/rev). If *position* = 200.00 then the shaft spins 1 revolution.

Syntax

@ position

Arguments

- 8,388,607≤ *position* ≤ + 8,388,607 In Fixed Resolution

- 8,388,607.99 ≤ *position* ≤ + 8,388,607.99 In Variable Resolution

Related Commands

M — set acceleration/deceleration profile

F — set initial velocity

V — set final velocity

I — set Resolution Mode

\ — set StepSize

Z — Zero Position Counter

Programming guidelines

Program line	Explanation
M 10 10	
F 300	
V 1000	
Z	zero the position counter
@ 2000	index to position 2000
W 0	wait till index done
W 150	wait 1.5 seconds
Y 1	activate Port 1 (output LOW)
@ 0	index back to initial position
W 150	wait 1.5 seconds
Y 0	de-activate Port 1 (output HIGH)

+ (Positive Incremental Move)

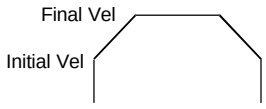
+ *steps*

Immediate, Execution

Purpose

Moves the motor a total of *steps* in the CW direction with a trapezoidal velocity profile shown below. In Fixed Resolution mode, the *steps* specifies ± 8,388,607 pulses. So, if *steps* = 200 and StepSize is set for Full steps, the shaft spins 1 revolution. If *steps* = 1600 and StepSize is set for 1/8 step (1600 pulses/rev) then the shaft also spins 1 revolution.

In Variable Resolution Mode, the *steps* specifies ± 8,388,607.99 Full steps with 0.01 step size resolution (20,000 pulses/rev). If *steps* = 200.00 then the shaft spins 1 revolution.



Syntax

+ *steps*

Arguments

0 ≤ *steps* ≤ + 8,388,607 (Fixed Resolution)

0.00 ≤ *steps* ≤ + 8,388,607.99 (Variable Resolution)

Related Commands

M — set accel/decel

F — set initial velocity

V — set final velocity

I — set resolution mode

\ — set StepSize

Programming guidelines

Program line	Explanation
M 10 10	set accel/decel factors
F 300	set initial velocity
V 1000	set final velocity
+ 1000.52	index 1000.52 steps

- (Negative Incremental Move)

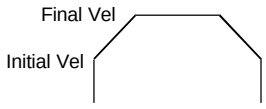
- steps

Immediate, Execution

Purpose

Moves the motor a total of *steps* in the CCW direction with a trapezoidal velocity profile shown below. In Fixed Resolution mode, the steps specifies ± 8,388,607 pulses. So, if *steps* = 200 and StepSize is set for Full steps, the shaft spins 1 revolution. If *steps* = 1600 and StepSize is set for 1/8 step (1600 pulses/rev) then the shaft also spins 1 revolution.

In Variable Resolution Mode, the *steps* specifies ± 8,388,607.99 Full steps with 0.01 step size resolution (20,000 pulses/rev). If *steps* = 200.00 then the shaft spins 1 revolution.



Syntax

- *steps*

Arguments

0 ≤ *steps* ≤ + 8,388,607 (Fixed Resolution)

0.00 ≤ *steps* ≤ + 8,388,607.99 (Variable Resolution)

Related Commands

M — set accel/decel

F — set initial velocity

V — set final velocity

I — set resolution mode

\ — set StepSize

Programming guidelines

Program line	**Explanation**
M 10 10	set accel/decel factors
F 300	set initial velocity
V 1000	set final velocity
- 1000	index 1000 steps at current resolution

\ (StepSize, VelScale)

\ *arg*

Immediate, Execution

Purpose

In Fixed Resolution Mode sets the StepSize. In Variable Resolution Mode determines VelScale to scale actual shaft speed.

Syntax

\ *arg*

The resolution settings also depend on the drive settings, which, for this instruction select either binary or decimal step sizes. The factory default is binary step sizes.

Arguments

Fixed Binary	Fixed Decimal	VR Speed
0 = Full	Not allowed	Full speed
1 = 1/2	Full	1/2
2 = 1/4	1/2	1/4
3 = 1/8	1/5	1/8
4 = 1/16	1/10	1/16
5 = 1/32	1/25	1/32
6 = 1/64	1/50	1/64
7 = 1/128	1/125	1/128
8 = 1/256	1/250	1/256

Programming guidelines

In the following program, assume the unit is set for Fixed Resolution Mode.

Program line		**Explanation**
E0		
0	\0	Full steps (200 steps/rev)
2	+ 1000	spin CW 5 revolutions
7	W 0	
10	W 100	
13	\2	Quarter steps (800 steps/rev)
15	- 1200	spin CCW 1.5 revolutions
20	W 0	
23	W 50	

In Variable Resolution Mode:

0	\0	Full speed
2	+ 1000	spin CW 5 revolutions
7	W 0	
10	W 100	
13	\2	1/4 speed
15	- 1200	spin CCW 6 revolutions
20	W 0	
23	W 50	

ESC (Abort)

ESC

Immediate

Purpose

Terminates any active operation and returns Indexer to the immediate or idle mode. If motor is in motion, it will be immediately stopped without ramping deceleration. Output ports will not be affected. In RS-485 multi-unit mode motion on all axes is stopped.

Syntax

Arguments

None

^C (Software Reset)

^C

Immediate

Purpose

Stops all axes, loads default parameter values, zeros origin, executes any user program (AUTOPROGRAM) at location 1600. Indexer will wait for the spacebar sign-on or external REMOTE START or JOG+ or JOG- inputs.

Syntax

Arguments

None

> (Read Memory)

> *addr size*

Immediate

Purpose

Displays a specified block of non-volatile memory starting at *addr*, returning a total of *size* bytes. The value of *addr* must be in the range of 0 to 2047 and block *size* 0 - 255. Displayed values are in decimal format.

Syntax

> *addr size*

Arguments

$0 \leq addr \leq 2047$ and $0 \leq size \leq 255$

< (Write Memory)

< addr data

Immediate

Purpose

Writes a *data* byte to an address specified by *addr* in non-volatile memory. The *addr* must be in range of 0 to 2047 and *data* must be in range of 0 to 255.

Syntax

< *addr data*

Arguments

0 ≤ *addr* ≤ 2047 and 0 ≤ *size* ≤ 255

] (Read Moving Status)

]

Immediate

Purpose

Returns an integer number representing the current move status. Bit weights:

1 => Indexing

2 => Constant Speed

128 => Drive Fault

Syntax

]

Arguments

None

‘ (Trip and Output)

‘nextpos port

Execution

Purpose

This instruction is designed to be used within a Trip Point Service Routine (TPSR) and provides the capability of setting or clearing user I/O lines as a function of current position. To use this instruction, set up a Trip Point (O command) in the normal fashion, but with an entry address in fast RAM locations 128 to 191, such that the entire TPSR resides within the fast RAM range. When the Trip and Output instruction is executed, the port parameter is sent out to the bi-directional ports. The position parameter nextpos sets the next trip point position. The Q command always shows the next trip point. Trip and Output instructions must be embedded within the TPSR in contiguous locations. At end of sequence, a new Trip Point can be specified.

Syntax

‘ *nextpos port*

Arguments

None

Programming guidelines

The following example activates ports P1, P2, P3, P4 in sequence as successive positions are traversed. The O command sets the initial trip point to position 1000 and vector address to 128. When this position is encountered, execution vectors to location 128. The Trip and Output instruction at location 128 writes a 1 to the bi-directional ports and sets the next trip point to position 5000 and the vector address 133. Subsequent execution continues in a similar manner.

Note: *Only the E command at the conclusion of editing is necessary to end the trip point service routine.*

Program line	**Explanation**
E0	
0 Z	zero position
1 O 1000 128	trip at pos 1000
6 + 50000	index
11 W 0	till done
14 W 100	wait 1 sec
17 G 0	loop
E128	
128 ‘ 5000 1	
133 ‘ 10000 2	
138 ‘ 15000 4	
143 ‘ 20000 8	
148 ‘ 25000 4	
153 ‘ 30000 2	
158 ‘ 35000 1	
E	

= (Limit Switch Polarity)

= *polarity*

Immediate

Purpose

Sets the limit switch polarity. The default limit input upon power up is active LOW.

Syntax

= *polarity*

Arguments

1 = Active Low

0 = Active High

: (Selective Termination)

: *axis*

Immediate

Purpose Aborts operations on a particular axis when configured for RS-485 communications mode.

Syntax : *axis*

Arguments Where *axis* is the single-letter axis designation.

Appendix A Specifications

Fixed Resolution Mode

Fixed resolution mode offers either binary or decimal step sizes. Binary step sizes range from 200 to 51,200 pulses/rev. Decimal sizes range from 200 to 50,000 pulses/rev. All indexing is specified in terms of an integer number of step pulses at the specified resolution. This mode must be used if a single 6420 indexer controls its own drive and a slave(s) 6410 drive.

Step size	Minimum Speed RPM (full steps/sec)	Maximum Speed RPM (full steps/sec)	Resolution Pulses/revolution
Binary Steps			
Full	6 (20)	5,700 (19,000)	200
1/2	3 (10)	3,000 (10,000)	400
1/4	1.5 (5)	1,500 (5,000)	800
1/8	.75 (2.5)	750 (2,500)	1,600
1/16	.37 (1.25)	375 (1,250)	3,200
1/32	.19 (.625)	188 (625)	6,400
1/64	.09 (.312)	93.75 (312)	12,800
1/128	.05 (.156)	46.87 (156)	25,600
1/256	.02 (.078)	23.43 (78)	51,200
Decimal Steps			
Full	6 (20)	5,700 (19,000)	200
1/2	3 (10)	3,000 (10,000)	400
1/5	1.2 (4)	1,200 (4,000)	1,000
1/10	.60 (2)	600 (2,000)	2,000
1/25	.24 (.8)	240 (800)	5,000
1/50	.12 (.4)	120 (400)	10,000
1/125	.048 (.16)	48 (160)	25,000
1/250	.024 (.08)	24 (80)	50,000

Variable Resolution Mode

The indexer varies the step size from Full to 1/256 as a function of the specified velocity/position profile. All indexing is specified in terms of a mixed integer/fractional number, with the integer portion specifying the full number of steps and the fractional portion specifying 0.01 to 0.99 decimal step resolution carried out to within 8 binary bits of precision.

Step Size	Minimum Speed, RPM (full steps/sec)	Minimum Speed, RPM (full steps/sec)	Resolution Pulses/revolution
Variable, automatically chosen. User specifies position to within 1/100 of a step.	.02 (.078)	5,700 (19,000)	20,000

Communications

RS-232 or RS-422/RS-485 at 9600 bits per second, 1 stop bit and no parity. The RS-485 mode supports both single axis and multi-drop, multi-axis operation.

Multi-axis capability

Multiple 6420 units may be connected to a single RS-485 bus for multi-axis operation. Another alternative is to use the Step and Direction outputs to control additional drives such as 6410s. The 6420 is designed to directly drive another 6410 drive with no glue logic. However, if desired, the user can implement external logic controlled by any number of the user bi-directional I/O lines to control more than one drive.

Programming

The 6420 is programmed with a simple mnemonic programming language. The unit operates in Immediate and Execution Modes. In Immediate, command line entry mode, the user can interactively specify motor commands, read back status information or enter programs with an ASCII terminal or terminal emulator. The host can also read back the status of both dedicated and user-defined I/O lines connected to external switches and sensors. In Execution Mode, previously entered programs may be executed on the 6420 to control the motor. On-board non-volatile memory offers approximately 1792 bytes for user programs. Program mnemonics vary from 1 to 5 bytes in length. Within the 1792 range there exists a 64 byte region from 128 to 191 designated as "FAST" memory for time critical code sections.

Electrical

Input Power

24 Vdc to 75 Vdc. Current is motor and load dependent, usually less than motor phase current.

Note: *A 2000 uf capacitor mounted within 3 feet of the 6420 is recommended to absorb the motor regen energy.*

Output Motor Phase Current

5 A RMS max, % A peak full step, 7.1 A peak microstepping

Discrete Input Voltage

0-30 Vdc max, $V_{in} \leq 0.8$ V is a logic low and $V_{in} \geq 3.7$ V is a logic high

Discrete Output Voltage

Open collector Darlington, 0-30 Vdc max, 70 mA sink, $V_{sat} \leq 1.0$ Vdc.

Electrical isolation

Indexer option power and interface signals to 6410 completely isolated. All other external inputs and outputs referenced to Indexer ground, unless otherwise specified.

Environmental Requirements

Storage temperature	-55° C to +70° C
Operating temperature	0° to 50° C ambient air
Maximum chassis operating temperature	60° C
	Note: *For optimal thermal performance, mount the 6420 chassis back or side to a cooling plate or heatsink. Use a thermal pad or grease if surface is irregular. A fan or idle current reduction may be employed to keep chassis below 60° C.*
Convection Cooling	
with optional heatsink	Full rating (5A) at 25°C Ambient 2.5A max at 45°C Ambient
without optional heatsink	2.5A max at 25°C Ambient 1.25A max at 45°C Ambient
Humidity Range	10 to 90%, non-condensing
	Note: *Adhere to the specified bus voltage range and power ratings; a heat sink may be required to prevent exceeding the temperature limit otherwise unit may be damaged.*

Mechanical

Dimensions 5” x 1.5” x 4.3”

Weight 1 lb nominal

Connectors

Discrete I/O	25 pin male D connector
Serial Port	9 pin male D connector
Power	3 pin PCD ELVP03100
Motor	5 pin PCD ELVP05100

Appendix B Ordering Information

Background

This appendix lists 6420 part numbers and gives information on ordering.

6420 part number table

Part	Pacific Scientific Order #	Comment
Stepper Drive	6420	
Connector Kit	CK6420	25-pin D connector
		9-pin D connector
		5-pin PCD
		3-pin PCD
6420 Dialogue	904-008101-00	3 1/2 inch
User Manual	MA6420	
Motor Cable	SPC-xxx-6420	xxx represents length in feet; for example, SPC-005 is a cable 5 feet long. For lengths over 50 feet contact Pacific Scientific. The connectors are MS on the motor end and PCD on the drive end to connect to Pacific Scientific motors.
Heatsink	HS6420	Optional heatsink.

How to order	Contact Pacific Scientific to order these parts.
Call	815-225-3100 from 8am to 6pm Eastern Standard Time.
Write	Pacific Scientific 4301 Kishwaukee Street Rockford, IL 61105
Fax	(815) 226-3048

Appendix C Quick Reference

In this chapter This section contains an alphabetized list of 6420 programming commands including a brief description and the operating modes where they apply. Detailed descriptions of each command are given on the page indicated in Chapter 7.

Command	Description	Mode	Page #
+ steps	Incremental move +	Immediate/Execution	7-40
- steps	Incremental move-	Immediate/Execution	7-42
:axis	Selective Termination	Immediate	7-54
<addr data	Write Non-volatile Memory	Immediate	7-49
=polarity	Limit Polarity	Immediate	7-53
>addr size	Read Non-volatile Memory	Immediate	7-48
@position	Absolute move	Immediate/Execution	7-38
\step size	Stepsize VelScale	Immediate/Execution	7-44
]	Read Moving Status	Immediate	7-50
^speed	Set Jog Speed	Immediate/Execution	7-37
^C	Software Reset	Immediate	7-47
‘nextpos port	Special Trip	Execution	7-51
A opcode	Clear and Restore	Immediate	7-2
B addr cntr	Jump inner loop	Execution	7-13
C arg	Read Position Counter	Immediate	7-4
E addr	Program Mode	Immediate	7-5
ESC	Abort or Terminate	Immediate	7-46
F vel	Initial Velocity	Immediate/Execution	7-6
G addr [trace]	Go	Immediate/Execution	7-8
H speed dir	Home	Immediate/ Execution	7-10

Table cont'd

Command	Description	Mode	Page #
I mode	Resolution Mode	Immediate	7-12
J addr cntr	Jump outer loop	Execution	7-13
K	Read Input Port	Immediate	7-15
L addr	List program	Immediate	7-16
M accel decel	Ramp Slope	Immediate/Execution	7-17
O position vaddr	Trip Point	Execution	7-19
P	Store Parameters	Immediate	7-21
Q	Examine Parameters	Immediate	7-22
R vel	Run at constant velocity	Immediate/Execution	7-24
S [arg]	Stop	Immediate/Execution	7-26
T enb	Master/Slave Control	Immediate/Execution	7-27
U addr cnd	Loop on Port	Immediate/Execution	7-29
V vel	Final Velocity	Immediate/Execution	7-31
W period	Wait	Immediate/Execution	7-32
X arg	Read Limits	Immediate	7-33
Y port	Write Output Port	Immediate/Execution	7-34
Z	Zero Origin	Immediate/Execution	7-36

Appendix D Ramp Algorithm & Lookup Table

Introduction

The 6420 Indexer/Drive uses a lookup table to determine the number of steps in the velocity ramp that occur from the initial (start/stop speed) velocity to the final velocity. The lookup table contents are included at the end of this appendix.

The velocity profile is a quantized linear ramp with discrete velocities stored in a lookup table. The velocity commands are in pulses per second.

The algorithm begins at the exact start/stop velocity entered, then runs at the next highest velocity in the lookup table. The velocity increments until it reaches the value immediately before the final velocity entered. The next velocity will be the final velocity.

The number of pulses output at each velocity is determined by the **M**(slope) command. The **M** value sets the number of pulses at each velocity.

For example:

M5

F300

V3000

The start/stop velocity and table velocities are:

155	562	820	1036	1227	1407	1581	1742	1905	2058
2190	2340	2472	2620	2736	2864	3004			

Five pulses will be generated at each of these rates as set by the **M** 5 command. The total ramp time from initial to final velocity is given by the sum of the times at each velocity during ramp up.

$$\text{Ramp time} = M * \sum_{V = \text{start/stop velocity}}^{V = \text{Last table entry before final velocity}} \frac{1}{V}$$

For example, ramp time for the above is:

$$\text{Ramp time} = 5 * \left[\frac{1}{300} + \frac{1}{562} + \frac{1}{820} + \frac{1}{1036} + \frac{1}{1227} + \frac{1}{1407} + \frac{1}{1581} + \frac{1}{1742} \right.$$
$$\left. \frac{1}{1905} + \frac{1}{2058} + \frac{1}{2190} + \frac{1}{2340} + \frac{1}{2472} + \frac{1}{2620} + \frac{1}{2736} + \frac{1}{2864}\right]$$

Divide command

The divide command (\n) can be used to modify the ramp profile. The divide command allows you to add more points to the velocity ramp, resulting in smaller velocity increments and smoother ramping.

All commanded velocities are divided by the (\n) command. When using the (\2) command with the previous example, the actual output pulse rate would be divided by 2. The initial velocity (Fnn) will be 150 pulses per second and the final velocity (Vnn) will be 1500 pulses per second. The new, modified ramp time will be:

$$\text{Ramp time} = 5*2\left[\frac{1}{300} + \frac{1}{562} + \frac{1}{820} + \frac{1}{1036} + \frac{1}{1227} + \frac{1}{1407} + \frac{1}{1581} + \frac{1}{1742} \right.$$
$$\left. \frac{1}{1905} + \frac{1}{2058} + \frac{1}{2190} + \frac{1}{2340} + \frac{1}{2472} + \frac{1}{2620} + \frac{1}{2736} + \frac{1}{2864}\right]$$

To run between the same start and final velocities as the original example (300 to 3000) with (\2) command, the program parameters will be:

\2

M 5

F 600

V 6000

Velocities are found from the lookup table:

155	562	820	1036	1227	1407	1581	1742	1905	2058
2190	2340	2472	2620	2736	2864	3004	3126	3225	3348
3461	3582	3690	3804	3925	4028	4137	4251	4342	4468
4568	4672	4744	4856	4974	5056	5141	5273	5365	5461
5560	5610	5715	5823	5936	5994				

The velocity ramp now consists of 46 points compared to the initial 14 without the (\2) command.

$$\text{Ramp time} = 5 * \left[\frac{1}{300} + \frac{1}{721} + \frac{1}{1054} + \ldots + \frac{1}{5994}\right]$$

Note: *If the final velocity is below 721 sps (the second speed in the lookup table) there will be NO ramping associated with that move. Instead, the move is completed in one step.*

Example

If Initial Velocity were specified at 100 steps/sec, Final Velocity at 1000 steps/sec, acceleration factor 120, deceleration factor 20, referring to the Profile Generator Table shown on the following page, the intermediate velocity points would be 155, 562 and 820 steps/sec. During acceleration 120 steps at 100 steps/sec, followed by 120 steps each at 155 steps/sec, 562 steps/sec, 820 steps/sec, concluding with the Final Velocity at 1000 steps/sec for the duration of the index until deceleration commences. One exception to this would be if the specified duration of the index (in steps) were not long enough to allow the motor to reach the Final Velocity; then the profile would top out at some intermediate point followed by the deceleration interval.

Profile Generator Look-up Table

155	562	820	1036	1227	1407	1581	1742	1905	2058
2190	2340	2472	2620	2736	2864	3004	3126	3225	3348
3461	3582	3690	3804	3925	4028	4137	4251	4342	4468
4568	4672	4744	4856	4974	5056	5141	5273	5365	5461
5560	5610	5715	5823	5936	5994	6113	6174	6301	6366
6433	6501	6606	6678	6788	6864	6942	7021	7271	7358
7447	7538	7585	7680	7777	7826	7927	7979	8084	8137
8246	8302	8416	8474	8533	8593	8714	8777	8840	8904
8969	9035	9170	9239	9309	9380	9452	9525	9600	9675
9752	9752	9830	9909	9990	10072	10155	10240	10240	10326
10413	10502	10593	10593	10685	10778	10778	10874	10971	10971
11070	11170	11170	11273	11377	11377	11592	11702	11702	11815
11815	11930	11930	12047	12166	12166	12288	12288	12412	12412
12538	12538	12538	12668	12668	12800	12800	12934	12934	13072
13072	13072	13212	13212	13356	13356	13356	13503	13503	13653
13653	13653	13806	13806	13806	13963	13963	14124	14124	14124
14288	14288	14288	14456	14456	14456	14456	14628	14628	14628
14804	14804	14804	14985	14985	15170	15170	15170	15360	15360
15360	15360	15554	15554	15554	15554	15753	15753	15753	15753
15958	15958	15958	15958	16168	16168	16168	16168	16168	16384
16384	16384	16384	16605	16605	16605	16605	16605	16832	16832
16832	16832	16832	17066	17066	17066	17066	17066	17307	17307
17307	17307	17307	17307	17554	17554	17554	17554	17554	17554
17808	17808	17808	17808	18070	18070	18070	18070	18070	18070
18340	18340	18340	18340	18340	18340	18340	18618	18618	18618
18618	18618	18618	18618	18618	18904	18904	18904	18904	18904
18904	18904	19200	19200	19200	19200	19200	19200	19200	19200
19200	19504	19504	19504	19504	19504	19504	19504	19504	19819

19819	19819	19819	19819	19819	19819	19819	19819	19819	20144
20144	20144	20144	20144	20144	20144	20144	20480	20480	20480
20480	20480	20480	20480	20480	20480	20480	20480	20480	20827
20827	20827	20827	20827	20827	20827	20827	20827	20827	20827
20827	21186	21186	21186	21186	21186	21186	21186	21186	21186
21186	21186	21186	21186	21186	21557	21557	21557	21557	21557
21557	21557	21557	21557	21557	21557	21557	21557	21557	21942
21942	21942	21942	21942	21942	21942	21942	21942	21942	21942
21942	21942	21942	21942	21942	21942	21942	21942	22341	22341
22341	22341	22341	22341	22341	22341	22341	22341	22341	22341
22341	22341	22341	22341	22341	22341	22341	22341	22341	22341
22341	22755	22755	22755	22755	22755	22755	22755	22755	22755
22755	22755	22755	22755	22755	22755	22755	22755	22755	22755
22755	22755	22755	22755	22755	22755	22755	22755	22755	22755
22755	23184	23184	23184	23184	23184	23184	23184	23184	23184
23184	23184	23184	23184	23184	23184	23184	23184	23184	23184
23184	23184	23184	23184	23184	23184	23184	23184	23184	23184
23184	23184	23184	23184	23184	23184	23184	23184	23184	23184
23184	23184	23184	23184						

D.2 Speed Accuracy

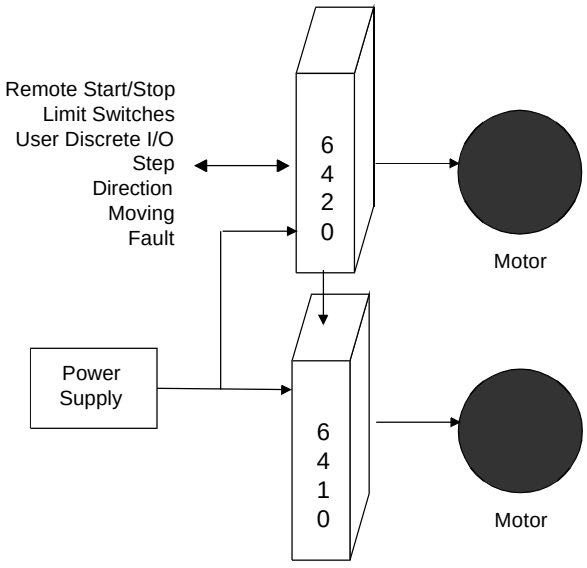
The 6420 Indexer generates step pulses by initializing a counter with a value that generates interrupts at approximately the desired step rate. The counter runs at a frequency of 1.2288 Mhz. This value is divided by the desired step rate to yield the integer counter initialization value. Consequently, the rounding process results in reduced accuracy as speeds increase. For example, step rates from 2498 to 2502 steps/second yield a 491 count value and result in an actual speed of 2503 steps/second. Likewise, 2503 to 2507 steps/second yield a 490 count and result in an actual speed of 2508 steps/second. In summary, speed accuracy over the full 20-19,000 step/second range is approximately 0.72 %.

Appendix E Application Examples

Introduction The following examples give a flavor of just a few of the myriad applications for the 6420.

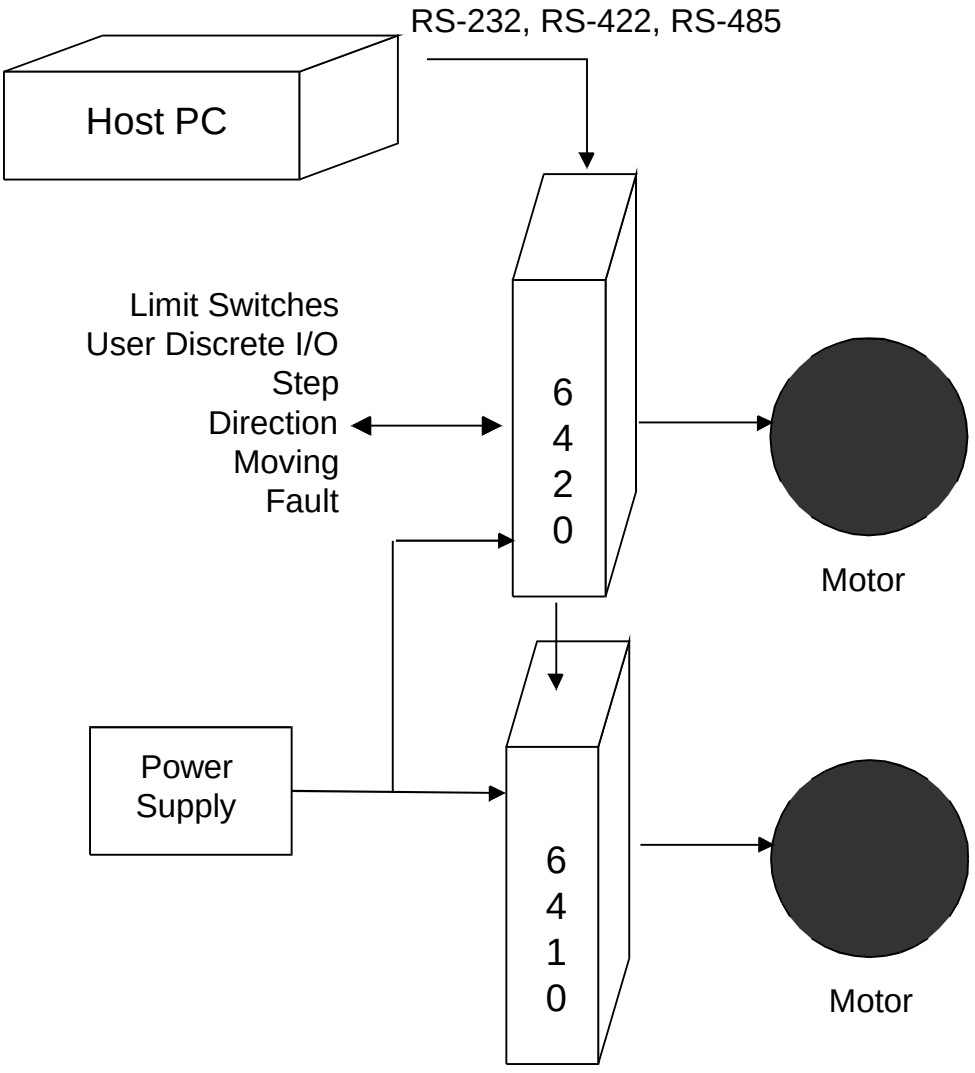
E.1 Standalone Operation

The 6420 has approximately 1792 bytes of internal, non-volatile memory for user programs. Internal programs can set initial and final velocities, acceleration and deceleration rates, execute incremental, absolute and constant velocity moves, program loops, branches based on the state of an input port and also write to the output port(s). In addition, a special case of the G instruction allows up to 16 different motion routines to be executed based on the state of the lower 4 port lines. Programs are entered with the E command and parameters saved with the P command in immediate mode. The external Remote Start and Stop can be used to start and stop program execution. Limit switches attached to the assembly can be used as safeguards for over-motion. A slave 6410 can be controlled by the Direction and Step lines, the Moving line can be polled for motion and the Fault line can be polled for fault conditions.



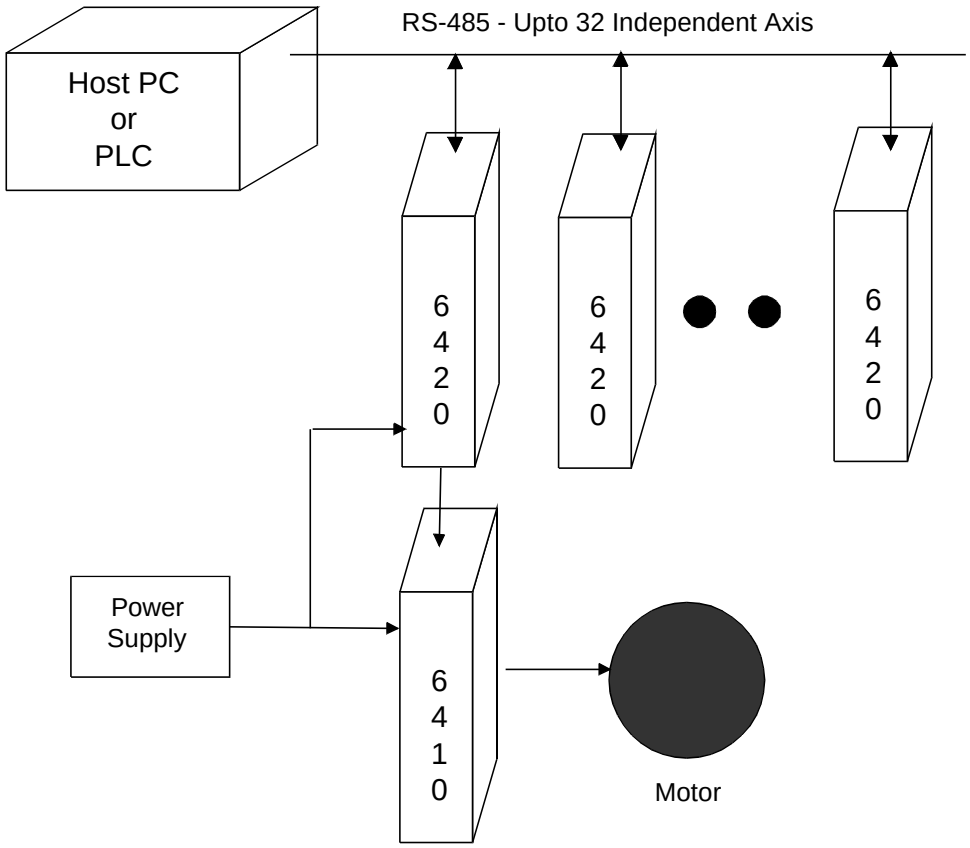
E.2 Host Operation Single Unit

In this configuration a custom host computer program issues immediate mode commands controlling all motion and parameter settings. All operations normally embodied in an on-board non-volatile program are executed on the host with only default motion parameters stored in non-volatile memory. This approach allows the programming freedom and flexibility afforded by the host programming language and development environment.



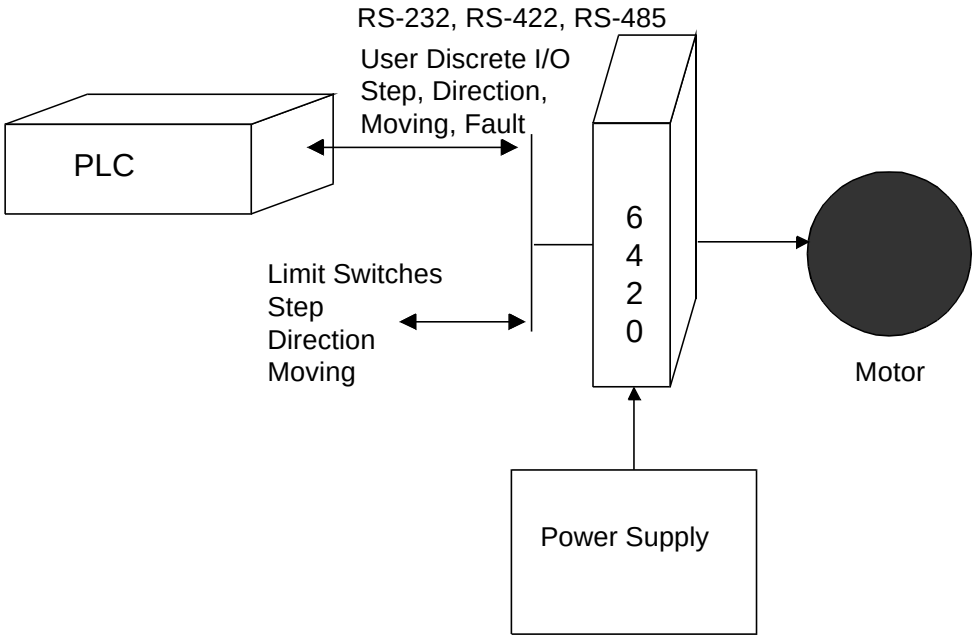
E.3 Host Operation Multiple Units

This configuration allows up to 32 independent axes to be controlled in immediate mode from a host computer or PLC. Normally all the units operate in immediate mode, but can also execute from on-board non-volatile memory. Remember, the RS-485 implementation is designed as a bus for the host computer to send commands to individual 6420s. The host can issue commands to read ports on individual units, but individual 6420s cannot initiate transfers back to the host. Only the host is the bus master. As in other configurations, an individual 6420 can also control a slave 6410.



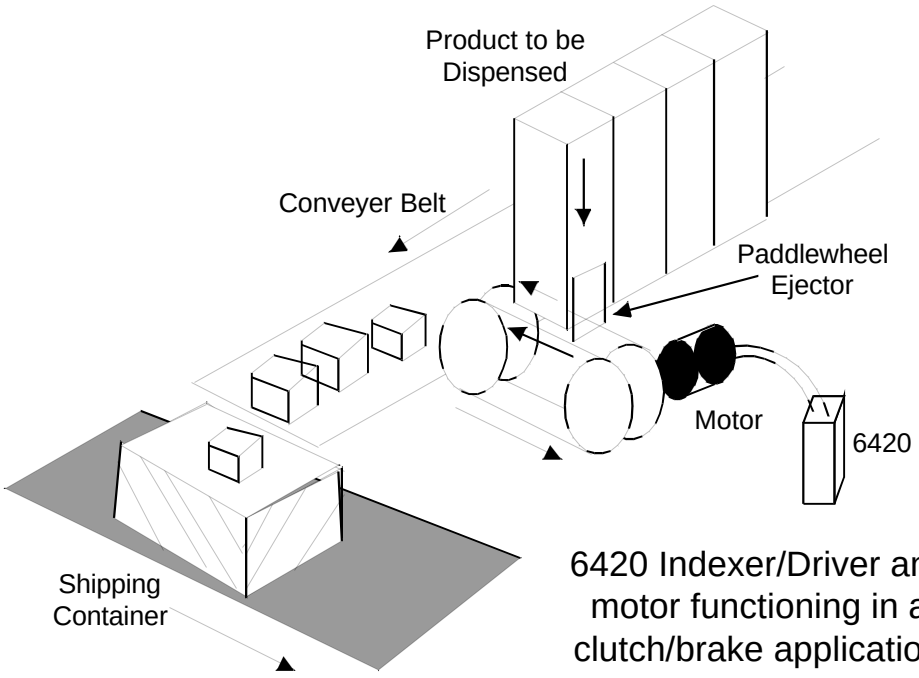
E.4 PLC Based Control

This configuration is similar to the others described above with the PLC acting as the host computer. The PLC can interface to the parallel port lines via a RS-232, RS-422 or RS-485 interface.



E.5 6420 Dispensing Product onto Conveyer Belt

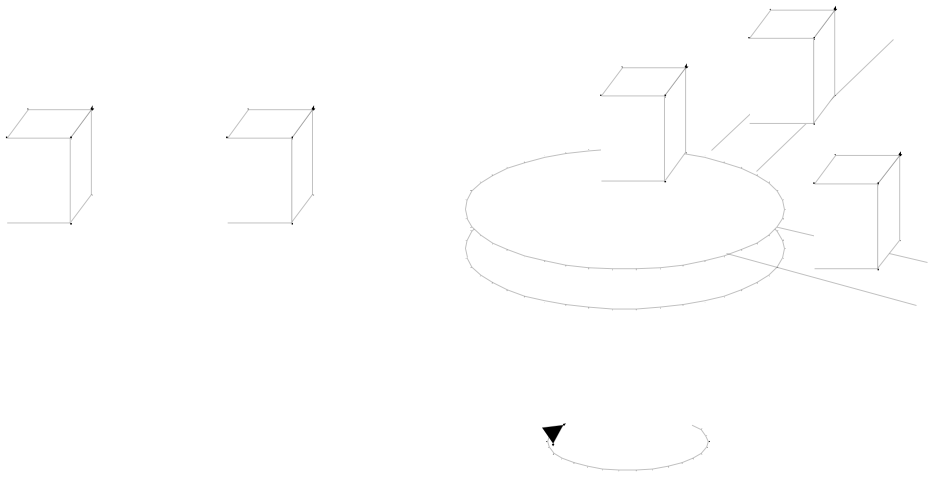
This example shows the 6420 Indexer/Drive and motor dispensing products onto a conveyor belt and into a shipping container. The stepper motor supplies start-stop motion to a paddlewheel ejector to dispense the product. An optic sensor is used to advance the paddlewheel to the starting point. An external Start signal initiates motion to eject the product, the motion continues for one revolution until the paddlewheel is aligned for the next cycle. A host computer or an on-board non-volatile program sets the acceleration, deceleration and velocity parameters and the 6420 executes the motion.



6420 Indexer/Driver and motor functioning in a clutch/brake application

E.6 6420 Controlling Indexer Table

The 6420 Indexer/Drive and motor combination easily drives an Indexing Table. The motor can drive the table directly, with a belt, or through a worm gear. An optic sensor can be used to indicate the starting or home position of the table and motion can be executed with open-loop stepping commands.



Incremental Indexing Table

E.7 Miscellaneous Application Notes

Start-Stop Program

The following is a start-stop motion program example. The program starting at location 128 in "FAST" memory spins the motor until an optic sensor wired to Port 8 goes HIGH. Once this stop point is detected, the motor decelerates until coming to a stop. The program is written such that the wait command executes in parallel with the deceleration. If the deceleration factor is set for maximum deceleration rate (0), motion stops very quickly and dead time will be about 1 second. If deceleration is set for the minimum rate (255), depending on the velocities involved the stopping time may be several seconds possibly over-shooting the stopping point substantially and eliminating the 1 second wait command. The optic design, be it a reflecting or slotted type may require some moving distance to disengage or deactivate its output. The program below runs at a constant slower speed until the sensor is cleared and then loops back to the beginning. This continuous running program can easily be modified to start up with an external input applied to an I/O port.

```
128   R 1200        ;  spin the motor
131   U 140 14      ;  jump to location 140 when stop point
                       is detected by the optic sensor.
135   G 131         ; continue polling Port 8
140   R 0           ; decelerate to 0
143   W 100         ; 1 second wait in parallel to R 0
146   U 146 14      ; loop till optics deactivated
150   G 128         ; back to beginning
```

Input Port Polling Times

Some applications may require estimates of branching times. The program below in "FAST" memory takes between 200 us to 1 ms to respond to an input line. The same program in "SLOW" memory requires approximately 1 ms to 12 ms to respond to an input line change.

```
128     U 140 14
132     G 128
140     W 100
143     G 128
```

Using the Input Port to Select 1 of 16 Different Profiles

An external thumbwheel switch can be used to select 1 of 16 different motion profiles. There are several different approaches to implementing this capability, but the easiest approach uses the G instruction to execute an indexed jump based upon the state of the lower 4 input port lines. This example initiates the indexed jump when the Remote Start input is activated low. Each jump executes a particular motion and then terminates, returning the 6420 to immediate mode waiting for the next Remote Start activation. At the end of motion either a termination byte (put there by the E command) or a branch to another location (G instruction) must occur. Remember that only 16 locations are available for instructions, including the program termination character or G instruction.

Example

```
E 0
    0
    Any initialization code

    G 2048          ; execute indexed jump


E   End of program here
```

This is the first profile to HOME the unit, where P[4-1] = Logic 1, 1, 1, 1.

```
E 256
    256             H 200 1
E
```

This is the 2nd profile, where P[4-1] = Logic 1, 1, 1, 0.

```
E 272
    272             M 40 40
                    + 800
E
```

This is the 3rd profile, where P[4-1] = Logic 1, 1, 0, 1.

```
E 288
    288             M 100 40
                    - 200
E
```

Here's another example where an AUTOSTART program waits for Port 8 to activate the program.

```
E 1600
    1600            *
    Any initialization code
    LoopU Loop 14   ; don't continue until Port 8 inactive
                    ; Port 8 must now be inactive high
    WlowU Wlow 14   ; don't continue until Port 8 active low
    G 2048          ; execute indexed jump
E                   End of program here
```

This is the first profile to HOME the unit, where P[4-1] = Logic 1, 1, 1, 1.

```
E 256
    256             H 200 1
                    W 0
                    G Loop
E
```

This is the 2nd profile, where P[4-1] = Logic 1, 1, 1, 0.

```
E 272
    272             M 40 40
                    + 800
                    W 0
                    G Loop
E
```

This is the 3rd profile, where P[4-1] = Logic 1, 1, 0, 1.

```
E 288

    288             M 100 40
                    - 200
                    W 0
                    G Loop

E
```

Note: *Since the jump table is encoded as straight binary rather than grey-coded, the 4 lower bits should be set first followed by a separate activation signal as is done above. Otherwise, if you attempt to set up a continuous loop where the 4 input lines may change state while the G instruction is executing, the program may not jump to the desired profile.*

Appendix F ASCII Codes

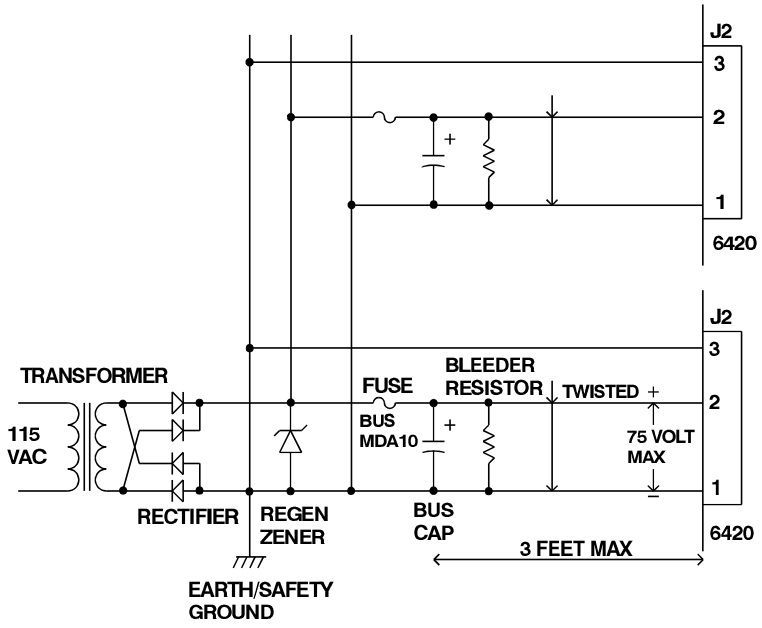
ASCII Code Result			ASCII Code Result		ASCII Code Result		ASCII Code Result	
0	^@	NUL	32		64	@	96	‘
1	^A	SOH	33	!	65	A	97	a
2	^B	STX	34	\	66	B	98	b
3	^C	ETX	35	#	67	C	99	c
4	^D	EOT	36	$	68	D	100	d
5	^E	ENQ	37	%	69	E	101	e
6	^F	ACK	38	&	70	F	102	f
7	^G	BEL	39	‘	71	G	103	g
8	^H	BS	40	(	72	H	104	h
9	^I	HT	41	)	73	I	105	i
10	^J	LF	42	*	74	J	106	j
11	^K	VT	43	+	75	K	107	k
12	^L	FF	44	,	76	L	108	l
13	^M	CR	45	-	77	M	109	m
14	^N	SO	46	.	78	N	110	n
15	^O	SI	47	/	79	O	111	o
16	^P	DLE	48	0	80	P	112	p
17	^Q	DC1	49	1	81	Q	113	q
18	^R	DC2	50	2	82	R	114	r
19	^S	DC3	51	3	83	S	115	s
20	^T	DC4	52	4	84	T	116	t
21	^U	NAK	53	5	85	U	117	u
22	^V	SYN	54	6	86	V	118	v
23	^W	ETB	55	7	87	W	119	w
24	^X	CAN	56	8	88	X	120	x
25	^Y	EM	57	9	89	Y	121	y
26	^Z	SUB	58	:	90	Z	122	z
27	^[	ESC	59	;	91	[	123	{
28	^\	FS	60	<	92	\	124	|
29	^]	GS	61	=	93	]	125	}
30	^^	RS	62	>	94	^	126	~
31	^_	US	63	?	95	_	127	

Appendix G Power Supply Considerations

G.1 Bridge, Capacitor Power Supply

The figure below shows the full-wave-bridge, capacitor-input configuration most commonly used to power one or more 6420 drive modules. A single transformer provides isolation and transforms the AC input voltage to a level that, when rectified, provides the desired DC bus voltage. Fusing should be between the rectifier and individual bus capacitors. This allows fuse size to be based upon the current requirements of a single module to provide the greatest protection. The capacitors must be connected to the 6420 DC+ and DC- inputs using twisted pairs no longer than three feet in length as shown to control winding inductive effects. A regen clamp to absorb power transferred from the motor to the 6420(s) is sometimes required. This section provides selection guidelines for the power supply components.

Block diagram



Warning

Power supply design must insure that the voltage between J2-2 and J2-1 never exceeds 75 volts under any operating conditions. These conditions include high line voltage, transformer regulation effects, voltage spiking due to current switching within the module and regeneration. Failure to do this can result in permanent damage to the 6420.

G.1.1 Line Transformer Selection

Primary voltage and frequency rating

Make sure that the transformer is guaranteed to operate at the highest line voltage combined with the lowest line frequency that will ever be used to power your system. Failure to do so can result in saturation, large current increases and winding failure.

Secondary voltage rating

Maximum motor speed performance will be achieved by using as high a motor supply voltage as possible without ever exceeding 75 volts. Of course lower voltages can also be used (so long as the voltage is greater than the minimum specified value of 24 volts) but motor torque will drop more rapidly as speed increases.

The peak bus voltage (excluding any spiking due to current switching in the drive module or any regeneration effects) is approximately equal to:

(1.414 * **Actual** Secondary rms voltage) - 1.5

Note: *This assumes a 0.75 volt drop across each rectifier diode. To insure this, as well as to discharge the bus capacitor when AC power is removed, it is recommended that a bleed resistor be placed across each bus capacitor as shown.*

Example

If, for example, the secondary rms voltage is 40 Vac, the peak bus voltage will be 1.414 * 40 - 1.5 = 55 volts. A transformer with 115 Vac primary and 40 Vac secondary would produce 55 volts peak bus voltage under nominal line conditions and at rated loading.

However, if the line voltage increases 10% the peak bus voltage increases to:

(1.414 * 1.1 * 40) - 1.5 = 60.7 volts

at rated transformer loading.

Load regulation must also be accounted for when selecting the transformer. Transformers are designed to produce their specified secondary voltage when loaded by their rated current. **For currents less than rated, the secondary voltage will increase**. Signal Transformer gives the following load regulation data for its line of rectifier transformers:[1]

VA Rating	Load Regulation
1 - 100	10%
100 - 350	8%
> 500	5% or less

This means that the secondary voltage of a 100 VA transformer will increase 10% over the specified voltage if the load current is reduced from rated current to zero. Since the stepper drive(s) might sometimes be disabled, the full regulation effect as well as maximum line voltage should be considered when selecting the transformer.

1 The VA product is obtained by multiplying the specified secondary voltage (Volts rms) by the rated secondary current (Amps rms). For example, a 24 Vac transformer with a rated secondary current of 1 Amp has a VA of 24.

Based upon these considerations, the table below gives the highest allowable rated secondary voltage when using a line with +10% voltage tolerance:

Transformer VA Rating	Maximum Rated Secondary Voltage
1 - 100	44.7 Vac
100 - 350	45.5 Vac
> 500	46.8 Vac

Current Rating

The average current load of the 6420 is a function of the motor used as well as motor speed and torque. To optimize the power supply design, the supply current can be measured using a DC current meter when the motor is producing the highest shaft power. If it is difficult to make this measurement, assume the maximum average load current equals the selected phase current. Thus, if the DIP switch is set for 5 Amps RMS, assume the maximum average power supply current is 5 amps.

The average transformer secondary current equals the sum of the average currents for all 6420s powered by the supply. Because the transformer supplies pulses of current to charge the “bus” capacitor(s) on the other side of the diode bridge, the rms current is higher than the average current. The transformer should have a rated secondary rms current of at least 1.8 times the average current.

Example

The transformer used to supply three 6420 drive modules, each set for 5 Amps rms should have a rated secondary rms current of 1.8 * (5 + 5 + 5) = 27 amps or greater.

Note: *It is generally not advisable to significantly oversize the transformer because this will increase rectifier surge current during turn on, as well as capacitor ripple current.*

G.1.2 Rectifier Diode Selection

Voltage rating

For the bridge rectifier configuration shown, the peak inverse voltage (PIV) equals 1.414 times the secondary rms voltage. For example, a 40 Vrms secondary will develop 1.414 * 40 = 56.6 PIV across the rectifier diodes. To allow for line variation and spiking, allow at least a 50% safety factor in the diode rating. Therefore, **the PIV rating of the rectifier diodes should be at least twice the rated secondary rms voltage.**

Current Rating

Since each diode conducts only on alternate cycles, the average diode current will be half the supply's average DC current load on the supply. When power is first applied, there is a surge of current to charge the capacitor(s) which must be less than the diode's peak one cycle surge current (I_{FSM}) rating. Typically, diodes are chosen with an average current rating of at least twice the average current load of the supply. It is often advisable to select diodes with an even greater average current rating because they have lower thermal resistance between junction and case and hence ease heat sinking requirements. It is good design practice to limit the maximum junction temperature to 125°C. Testing should be done to insure the power-on surge current is within the diode's I_{FSM} rating.

G.1.3 Capacitor Selection

The table below gives the minimum bus capacitance value for a single 6420 as a function of the current setting and bus voltage. These values give approximately 10% peak-to-peak ripple voltage with a 60 Hz line (increase capacitor values by 20% for use with a 50 Hz line).

Current Setting	30 Volt Bus	50 Volt Bus	70 Volt Bus
5.0	14,000	8300	6000
4.375	12,000	7300	5200
3.75	10,000	6300	4500
3.125	8700	5200	3700
2.5	6900	4200	3000
1.875	5200	3100	2200
1.25	3500	2100	1500
0.625	1700	1000	740

Bus Capacitance in Micro farads

Ripple current rating

The bus capacitor's 120 Hz ripple current rating should equal or exceed the 6420's current setting. The capacitor's working voltage rating must exceed the maximum bus voltage under all line, load, and regen conditions. Select a capacitor rated for at least 1.3 times the nominal bus voltage.

Example

Suppose a 6420 is operating at 70 volts and is set for 5 A rms motor current. Assuming a 60 Hz line, a bus capacitor of 6000 micro farads should be used. The capacitor should have a 120 Hz ripple current rating of at least 5 amps rms and a working voltage of at least 1.3 * 70 = 91 volts.

The bus capacitor should be connected to the 6420 using a twisted pair, no longer than 3 feet in length.

G.1.4 Fuse Selection

The BUS MDA 10 slow blow fuse or equivalent is recommended when the 6420 is set for 5 Amps. Fuses from the same family but with proportionally lower current rating can be used with lower current settings.

G.1.5 Regeneration Considerations

The motor power supply voltage can be "pumped up" when the motor and load are decelerated by the drive. In effect, the motor becomes a generator converting mechanical energy stored in the spinning motor and load inertia into electrical energy. If the mechanical energy is less than the losses in the drive and motor, the supply voltage does not increase. If the mechanical energy is greater than these losses, the supply voltage will increase (be pumped up).

The mechanical energy of a spinning inertia is given by:

$$E = 3.87 * 10^{-5} * J * S^2$$

where: E = kinetic energy (joules)

J = inertia in oz-in-sec^2

S = speed in rpm

Final voltage

If this energy is converted to electrical energy in the form of charge on the bus capacitor(s), the voltage will be:

$$V = \sqrt{Vo^2 + \frac{2E}{C}}$$

where: V is the final voltage (after energy transferred to capacitor(s)

Vo is the initial voltage

C is the total capacitance in farads

E is the initial kinetic energy in joules

Example

If an unloaded E34 motor (rotor inertia = .035 oz-in-sec^2) is rotating at 1500 rpm, the stored energy is:

$$3.87 * 10^{-5} * .035 * 15002 = 3.0 \text{ joules}$$

If all this energy is transferred to a 6800 mf capacitor, initially charged to 70 volts, the voltage on the capacitor after the transfer is equal to 76 volts.

Note: *This exceeds the volt maximum specification of the 6420 drive.*

In practice, most or all the kinetic energy is dissipated in the motor windings or in the drive power circuitry so that voltage pump-up is often not a problem. However, in systems running at high speeds and having large load inertia, the voltage might be pumped up significantly and circuitry must be added to insure that the 75 volt limit is never exceeded.

Note: *Regeneration effects should be considered in the presence of high line conditions.*

To find out if regenerative energy is a problem, run the system while monitoring the supply voltage with a storage oscilloscope. Alternatively, a simple peak detector made form a diode and a capacitor can be attached to the bus and the peak voltage measured using a digital voltmeter. Start the system with slow deceleration rates and monitor the motor power supply to see if the voltage rises during deceleration. Slowly increase the deceleration rate (shorten the deceleration time) while monitoring the voltage. If regeneration causes the supply voltage to exceed 75 Vdc peak, a clamping circuit is required.

Note: *Be sure to consider the effect of high line voltage when evaluating this test.*

Clamping Circuit

If a clamp is required, a power zener diode can be used as shown in the figure. The maximum zener clamp voltage must not exceed 75 volts.

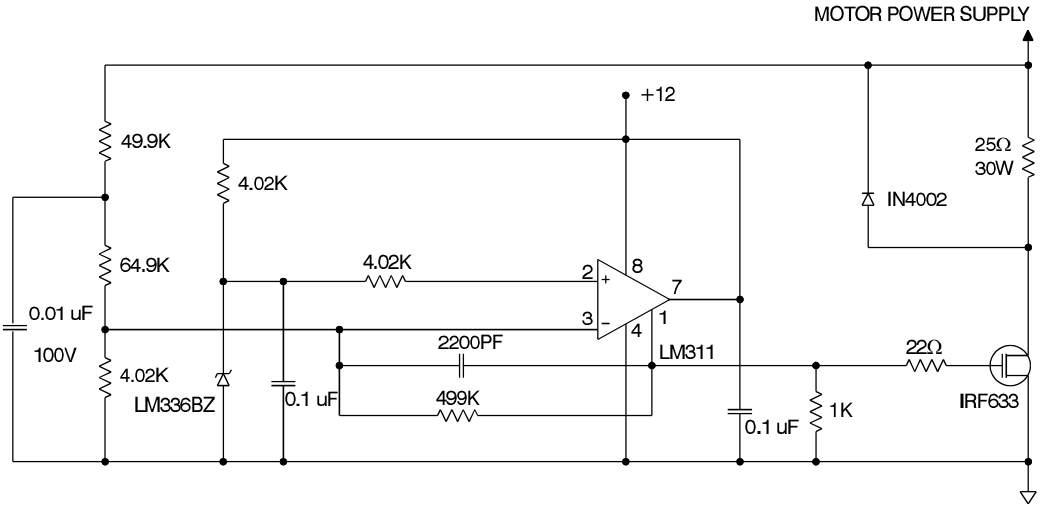
Caution

If a clamp is required, the transformer secondary voltage must be re-checked to insure that the minimum clamp voltage is not exceeded under high line and low load conditions when there is no regeneration. Otherwise, the zener might overheat and fail.

To determine the required diode power rating, start with a 5W device and monitor the zener current with a current probe. Power (in watts) is the average current (in amps) times the zener voltage. Estimate the average current from the oscilloscope trace and compute the power. Select a zener rated slightly higher than the measured power.

If the average power is too high to be conveniently dissipated in a zener diode, the active voltage clamp circuit shown below can be used instead. Power is dissipated in the 25Ω, 30W resistor if the Motor Power Supply voltage exceeds 75 volts.

Active clamp circuit



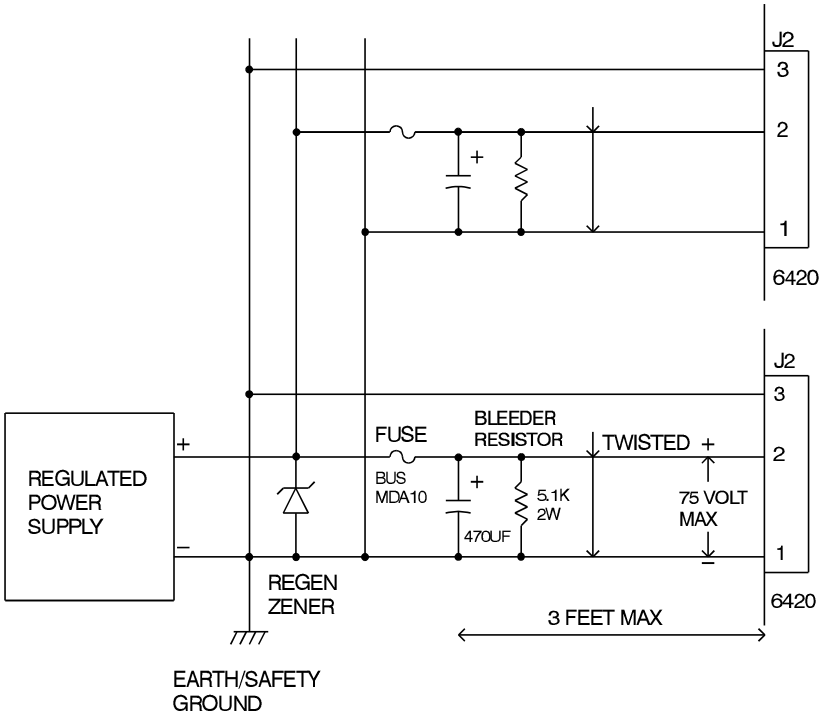
G.2 Powering the 6420 from a Regulated Supply

Certain precautions should be taken when powering the 6420 drive from a regulated power supply. The 6420's bipolar chopper output stage draws current from the DC supply in the form of pulses with fast rise and fall times. This may be a problem for some regulated supplies designed to drive loads having relatively constant or slowly varying current drain. If a regulated supply is used and problems are encountered, a 470uf capacitor should be placed across the DC+ and DC-lines between the power supply and 6420. Ideally this capacitor is located close to the 6420 drive but it can be located near the power supply and connected to the 6420 with a twisted pair no longer than 3 feet in length. The capacitor should have a 20KHz ripple current rating of at least the 6420's current setting and a voltage rating of 1.3 times the nominal bus voltage.

A second precaution involves regenerated power (see section G.1.5). Regulated supplies are usually not designed to absorb power. This might cause their output voltage to rise during regeneration and lead to power supply and/or 6420 damage. The same considerations and solutions described in section G.1.5 apply.

6420(s) powered by regulated supply

The figure below illustrates powering the 6420 from a regulated supply where both an external capacitor and regenerated power dump circuit are required. The recommended fusing is also shown.



Appendix H CE Installation Guide

Introduction

The information contained in this appendix applies to the 6420 ONLY. The 6420 is designed for use within machines that require compliance with European Safety and EMC Directives. The standards that the 6420 complies with are described in the Declaration of Conformity on the following page.

Note: *The information contained in this appendix supplements the material in the MA6420.*

Customer Responsibility

This appendix, supplied with all 6420 series drives, provides detailed information on installation. This appendix must be closely followed if EMC compliance is to be maintained. It covers details such as mechanical mounting, safety earth connections and motor wiring.

The 6420's input voltage is provided by a user supplied dc power supply. System harmonics and conducted emissions are dependent on the system chosen. Therefore, the machine builder is responsible to properly filter the installation thereby preventing unwanted conducted line noise.

EN 61800-3 also puts the responsibility of filtering on the machine builder. For additional information please see the "Assessment of Compatability" section in EN 61800-3.

CE Declaration of Conformity

This is to certify that:

Pacific Scientific
Motion Technology Division
110 Fordham Road
Wilmington, MA 01887 USA

Declares that the product(s):	
Designation	*STEPPER DRIVE*
Type	*6410, 6415, 6420*

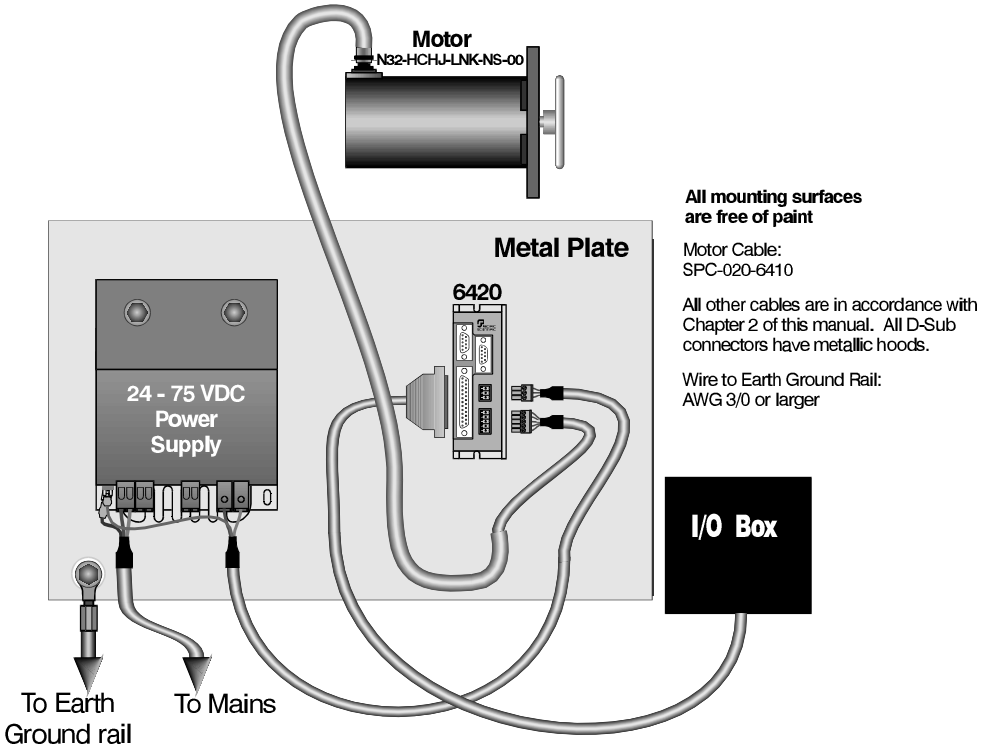
comply with the following relevant regulations:		
CE Guideline	*89/336/EEC*	*EMC Directive*
Applied harmonized standards:		EN 61800-3: 1996

Manufacturer's Contact:	Peter Deneault Compliance Engineer

Issued By:	Pacific Scientific, Motion Technology Division President, William T. Fejes
Place, Date:	Wilmington, MA, USA, 10-29-98

Legally binding Signature

CE Test Set Up The 6420 was determined to be the noisiest configuration for the 64xx family. Therefore it was used for all EMC testing.



Safety

In addition to the safety guidelines given in Section 2.2, observe the following:

- Electronic drives contain electrostatic sensitive devices which can be damaged when handled improperly. Qualified personnel must follow ESD protection measures. For example: wear grounded heel and wrist straps when contacting drive.
- Follow IEC 536-2 and IEC 1140 for installation protection against electric shock.
- Installation shall be performed in accordance with local electric codes, local accident prevention rules, and EN 61800-3.
- All covers shall be closed during operation.
- Braided cable shields should be connected to protective earth ground.

Drive mounting

Mount the drive to a conductive surface of the machine chassis, to ensure a good high frequency ground. If the chassis is painted or coated with another nonconductive coating, remove the coating from the mounting location prior to mounting the drive.

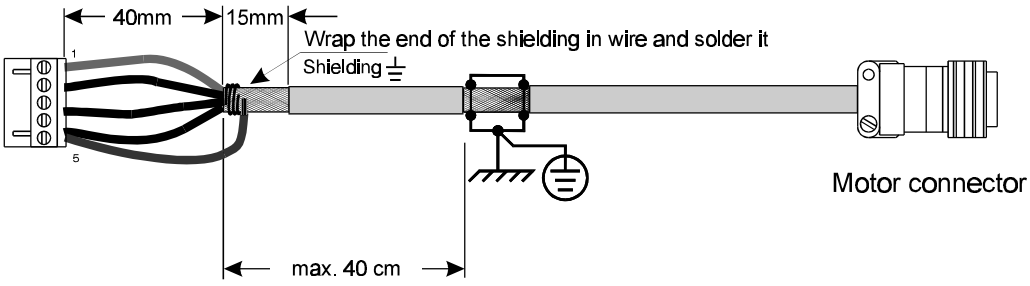
Cable Routing

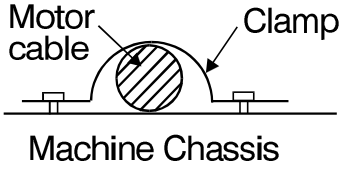
To avoid the risk of crosstalk, motor and command I/O cables should be kept away from sensitive signal cables such as telephone and intercommunication lines.

Cable shielding and grounding

The following information is not required for CE compliance of a single axis installation. When planning a multi-axis installation, or if extra high frequency noise reduction is required, Pacific Scientific suggests:

- In addition to the cable requirements given in this manual the motor and signal interface cables should have a braided shield which can be grounded to reduce high frequency disturbances.
- The motor cable shield must be grounded near the drive with a suitable high frequency ground. Such a ground connection is made by removing the cable's outer insulation, to expose the braided shield, then clamping the exposed braid to a conductive surface of the machine chassis. If the chassis is painted or coated with another nonconductive coating, remove the coating from the clamping location prior to clamping the shield. It is important that the clamp chosen be conductive and provide a full 360 degree connection.





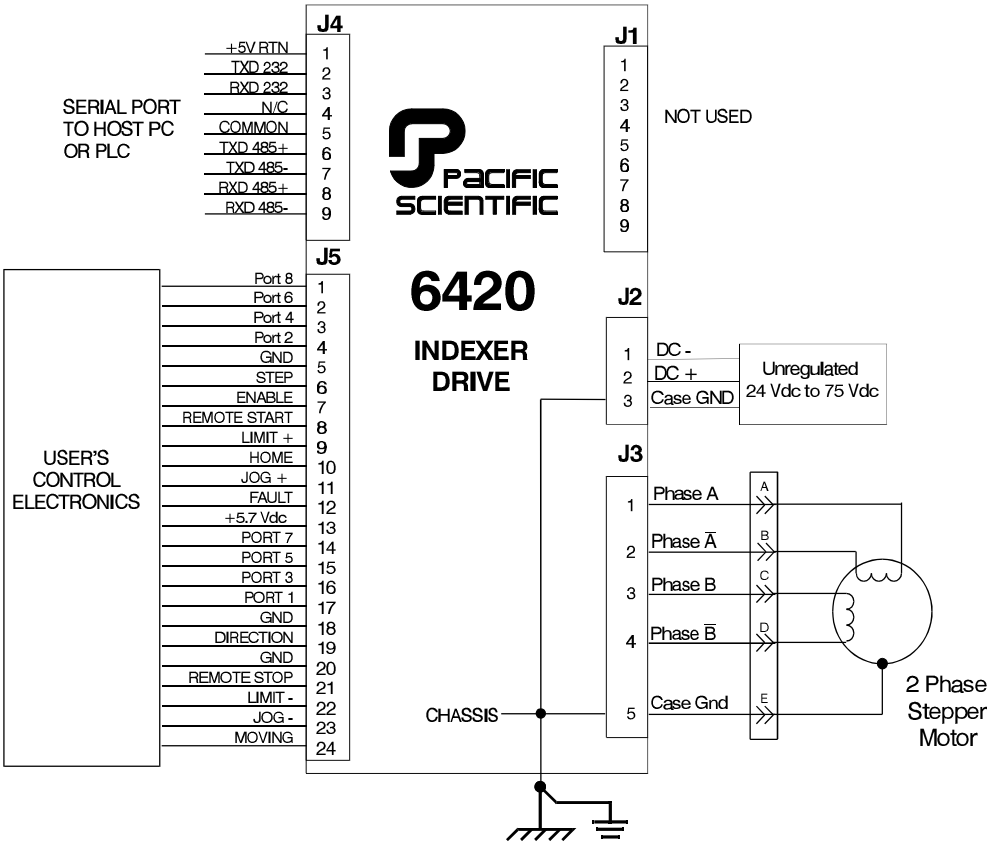
Note: *Ground shield to machine chassis with a metal clamp providing a 360 degree termination cable.*

The signal interface cable shield should be grounded to the drive through the 9 pin D-sub connector's conductive hood. If the cable connector does not provide a 360 degree ground connection to the shield, the signal interface cable should be grounded in accordance with the instructions given in the previous paragraph for the motor cable.

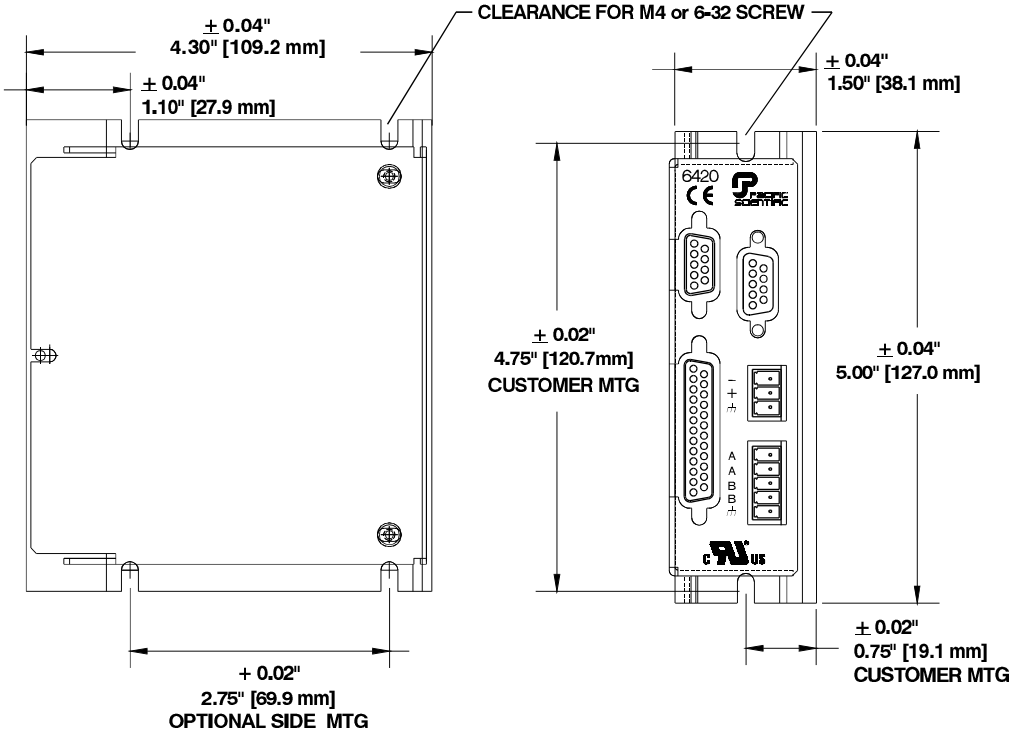
For additional information please contact the factory to request:

- Application Note 106 - Reducing Motor Drive Line Noise
- Application Note 107 - Reducing Motor Drive Radiated Emissions.

Connection Diagram



Mechanical Outline



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