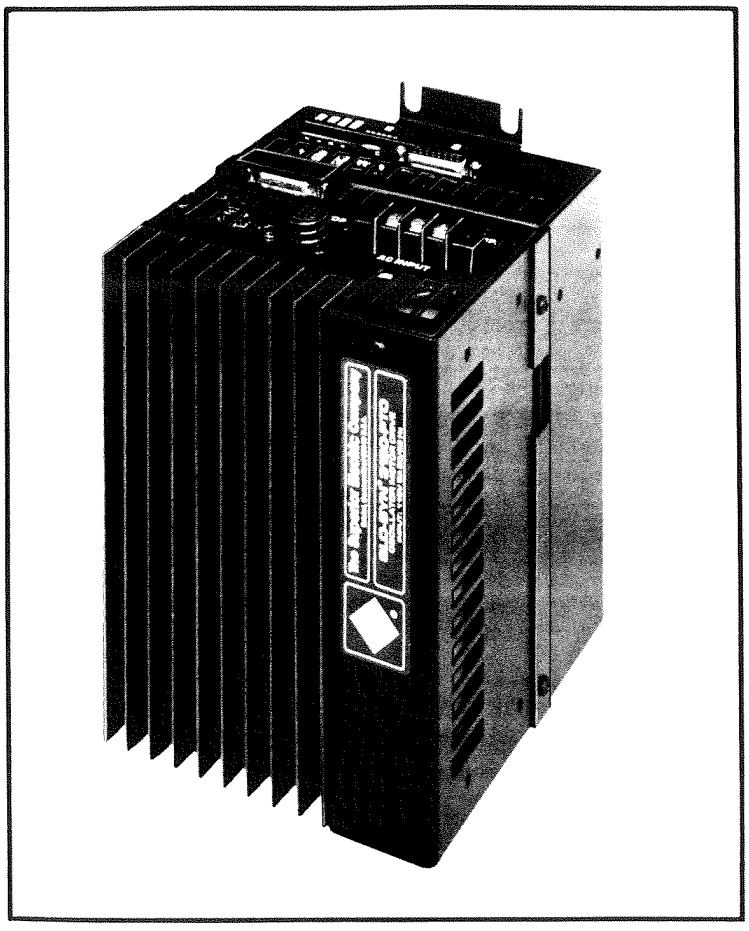
PRICE: $7.50

INSTRUCTIONS
for
SLO-SYN® MICRO-SERIES
MOTION CONTROLS
PACKAGED OSCILLATOR/DRIVES
TYPES 3180-PTO, 3180-PTO10, 3180-PTO125



WARNER ELECTRIC

DANA

QUALITY ASSURED FIRM ISO 9002 SGS

Manufactured under an ISO 9002 compliant manufacturing system

CONTENTS

EXPRESS START UP PROCEDURE

STEPS NECESSARY TO BECOME OPERATIONAL

This Express Start Up Procedure outlines the minimum steps necessary for the Oscillator/Drive to become operational. **FAILURE TO PERFORM THESE STEPS MAY RESULT IN DAMAGE TO THE UNIT.**

CAUTION: Never connect or disconnect anything from the unit with the power on.

I. DRIVE

Failure to properly perform the steps listed below will result in damage to the drive or injury to personnel.

1. Connect 120 volts ac, 50/60 Hz to the terminal strip. The terminal labeled "H" is hot, "C" is common and "G" is ground.

2. Check to see that the motor used is compatible with the drive. A list of compatible motors is given in Section 3.3.

3. Set the correct current level for the motor used per the instructions in Section 3.6.1.

4. Wire the motor per Section 2.2, "Motor Connections".

5. Caution: always disconnect the ac power to the unit when connecting or disconnecting the motor connector or leads. **Be certain the "PWR ON" LED is OFF before unplugging the motor connector, or the drive will be damaged.**

6. Caution: always run the motor and the drive **grounded**. Be sure to twist the wires for each motor phase; six twists per foot is a good guideline.

7. Connect the customer control logic to connector J4. Do not use J1 on the drive. Refer to Section 3.5.3 for connections and to Section 5 for descriptions of operation.

II OSCILLATOR

1. Set up switch S1 on the oscillator properly.

   a. Select a frequency range of operation for the oscillator as shown in the following chart. The pulse output is square waves.

S1-1	S1-2	S1-5	S1-6	Range Selected
X	X	off	off	no pulses out of oscillator
off	off	on	off	0 to 1 MHz
off	off	off	on	0 to 500 kHz
on	off	on	off	0 to 20 kHz
on	off	off	on	0 to 10 kHz
off	on	on	off	0 to 100 kHz
off	on	off	on	0 to 50 kHz

NOTE: X denotes either position.

   b. High Speed Adjustment select:

      If S1-3 is in the On position, the high speed is adjustable using "R3" on the oscillator board only.

      If S1-3 is in the Off position, the high speed is adjustable using an external potentiometer connected between J4-8 and J4-15. A 500k ohm multi-turn potentiometer is suggested.

   c. Translator Pulse Source select:

      If S1-4 is in the On position, the drive translator is connected to the oscillator output.

      If S1-4 is in the Off position, the drive translator input is J4-3.

2. Adjust the speed of the oscillator at a nonresonant starting speed, preferably above the mechanical resonance speed of the motor. This is accomplished by adjusting "R4" with the "RUN" (J4-6) and the "BASE SPEED ONLY" (J4-14) inputs tied to "SIGNAL COMMON" (J4-7 or J4-12).

3. Adjust the high speed of the oscillator to the desired high speed. Close position 3 of switch S1, or temporarily short J4-8 to J4-15, and adjust "R3" with the "RUN" input tied to SIGNAL COMMON (J4-7 or J4-12). If the motor stalls, adjust "R3" clockwise to lower the high speed limit. Remove the "RUN" input from SIGNAL COMMON and wait for the motor to stop. Then connect the "RUN" input to SIGNAL COMMON.

4. Adjust the Acceleration and Deceleration potentiometers on the oscillator board if you desire. The procedure is described in the manual. The factory preset value is 1 second for both the acceleration and deceleration rates.

FUSE AND MOTOR CONNECTOR NUMBERS FOR 3180 SERIES UNITS

FUSE: Littelfuse part number 225005
2AG, 5 amperes, 125 volts, fast acting

MOTOR CONNECTOR: (mates with female motor connector J2 on drive)
Male Connector Body: AMP part number 206434-1
Pins (5 required): AMP part number 66506-8
Cable Clamp: AMP part number 206062-1

INSTALLATION GUIDELINES FOR REDUCED NOISE

I General Comments

SLO-SYN Micro Series drives use modern solid-state electronics such as microprocessors to provide the features needed for advanced motion control applications. In some cases, these applications produce electromagnetic interference (EMI, or electrical "noise") that may cause inappropriate operation of the microprocessor logic used in the Micro Series product, or in any other computer-type equipment in the user's system.

This guide is aimed toward helping users avoid such problems by applying "good engineering practices" when designing their systems. Following these guidelines will usually prevent EMI noise from interfering with drive operation.

II Noise Sources

What causes electrical noise? In general, any equipment that causes arcs or sparks or that switches voltage or current at high frequencies can cause interference. In addition, ac utility lines are often "polluted" with electrical noise from sources outside a user's control (such as equipment in the factory next door).

The following are some of the more common causes of electrical interference:

- power from the utility ac line
- relays, contactors and solenoids
- light dimmers
- arc welders
- motors and motor starters
- induction heaters
- radio controls or transmitters
- switch-mode power supplies
- computer-based equipment
- high frequency lighting equipment
- dc servo and stepper motors and drives

III Mounting Location

When selecting a mounting location, it is preferable to keep the drive away from obvious noise sources, such as those listed above. If possible, locate the drive in its own metal enclosure to shield it and its wiring from noise sources. If this cannot be done, keep the drive at least three feet from any noise sources.

IV Wiring Practices - "Dos and Don'ts"

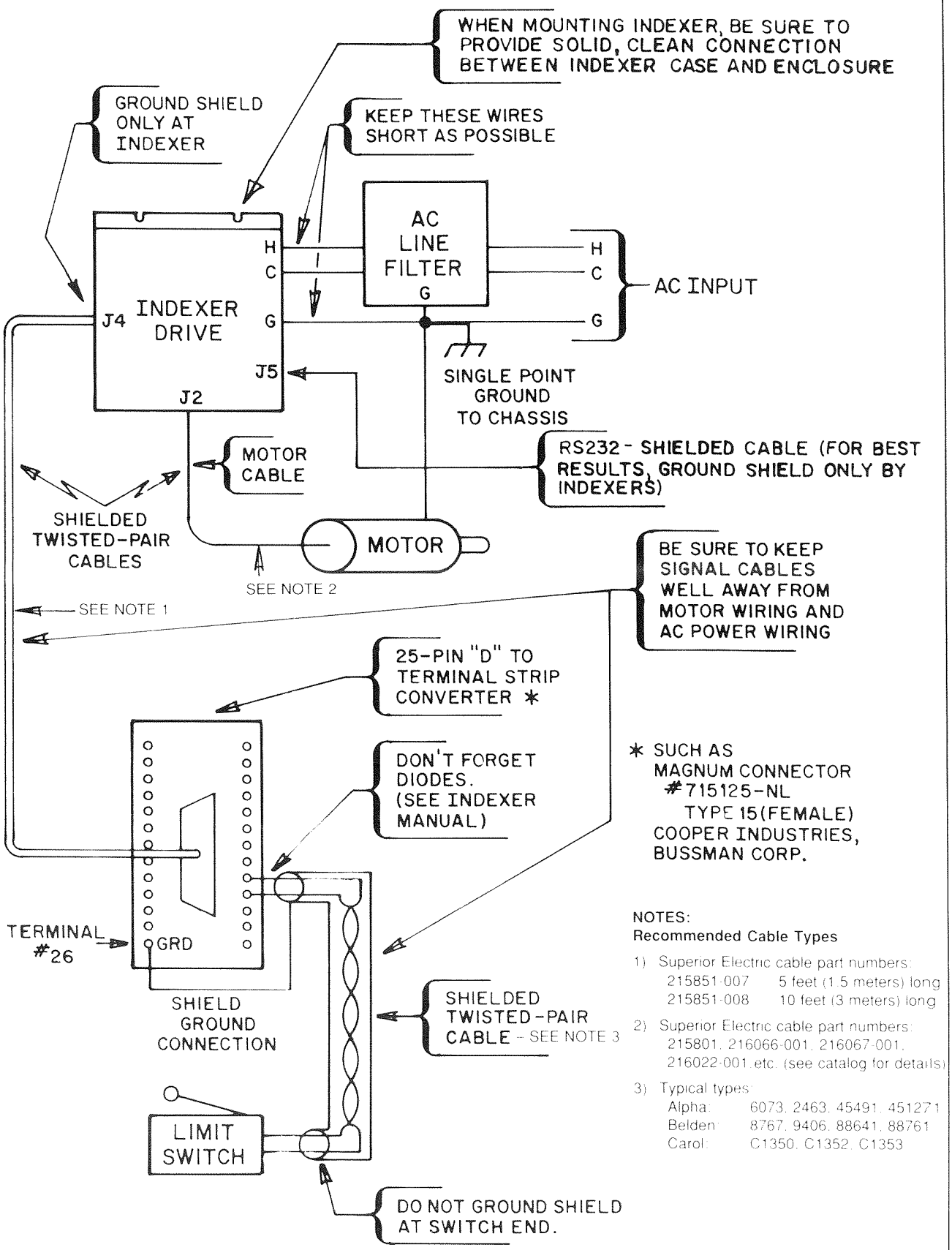
Do the following when installing or wiring your drive or indexer:

- **Do** keep the drive and its wiring as far away from noise sources as possible.
- **Do** provide a good, solid ground connection to the ac system earth ground conductor. Bond the drive case to the system enclosure.
- **Do** use a single-point grounding scheme for all related components of a system (this looks like a "hub and spokes" arrangement).
- **Do** keep the ground connection short and direct.
- **Do** use a line filter on the ac input (Corcom type 10B1, 10S1 or 10K1 or equivalent) for noisy ac lines. Particularly bad ac lines may need to be conditioned with a ferroresonant type isolation transformer to provide "clean" power to the drive or indexer.
- **Do** keep signal and drive wiring well separated. If the wires must cross, they should do so at right angles to minimize coupling. Power wiring includes ac wiring, motor wiring, etc. and signal wiring includes inputs and outputs (I/O), serial communications (RS232 lines), etc.
- **Do** use separate conduits or ducts for signal and I/O wiring. Keep all power wiring out of these signal line conduits.
- **Do** use shielded, twisted-pair cables for indexer I/O lines.
- **Do** ground shields only at one end, the indexer/drive end.
- **Do** use twisted-pair, shielded cable for the motor wiring.
- **Do** use solid-state relays instead of electromechanical contact types wherever possible to minimize noise generation.
- **Do** suppress all relays to prevent noise generation. Typical suppressors are capacitors or MOV's. See manufacturers literature for complete information.

Do not do the following when installing your drive or indexer:

- **Do not** install sensitive computer-based equipment (such as an indexer/drive) near a source of electromagnetic noise.
- **Do not** bundle power and signal lines together.
- **Do not** bundle motor cables and signal lines together.
- **Do not** fail to use shielded, twisted-pair cables for signals.
- **Do not** fail to properly connect the system grounds.
- **Do not** use "daisy-chained" grounds.
- **Do not** fail to ground signal cable shields at only one end.
- **Do not** assume that power from the ac line is adequately "clean".

Recommended Wiring Practices



NOTES:
Recommended Cable Types

1) Superior Electric cable part numbers:
   215851-007 5 feet (1.5 meters) long
   215851-008 10 feet (3 meters) long
2) Superior Electric cable part numbers:
   215801, 216066-001, 216067-001, 216022-001 etc. (see catalog for details)
3) Typical types:
   Alpha: 6073, 2463, 45491, 451271
   Belden: 8767, 9406, 88641, 88761
   Carol: C1350, C1352, C1353

V AC Line Filter

Use of an AC line filter on 3180 and 6180 Series drives **is recommended.**

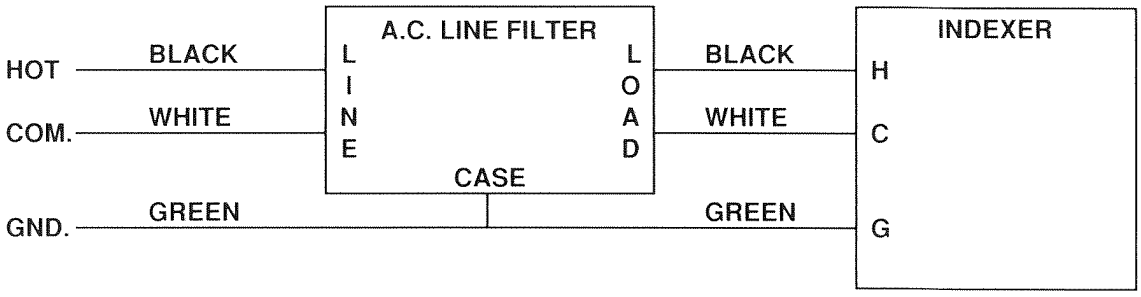
Proper installation of the AC Line Filter is essential

> **WARNING: Improper installation of the ac line filter may cause electrical shock, which could result in death, serious bodily injury or property damage. To avoid electrical shock:**
>
> **• The ac line filter must be installed by qualified personnel. Typical methods of locating and installing the line filter are shown in Figures 1and 2.**
>
> **• The ac line filter must be firmly fastened near the Indexer. Failure to do so may result in damage to the filter and system.**
>
> **• The installer must properly insulate and protect the ac connections to assure that the wires are not exposed. Exposed wires could cause electrical shock, resulting in death, bodily injury or property damage.**

If you have any questions regarding installation of the line filter, contact an electrician before installing the device.

For best performance:

• The wire between the Filter and the Drive should be less than two feet (0.61 meter) long.



Proper AC Line Filter Connections

VI Troubleshooting Guide

Electrical interference problems are common with today's computer-based controls, and such problems are often difficult to diagnose and cure. If such a problem occurs with your system, it is recommended that the following checks be made to locate the cause of the problem.

1. Check the quality of the ac line voltage using an oscilloscope and a line monitor, such as the Superior Electric VMS series. If line voltage problems exist, use appropriate line conditioning, such as line filters or isolation transformers.

2. Be certain all of the previous Do's and Don'ts are followed for location, grounding, wiring and relay suppression.

3. Double check the grounding connections to be sure they are good electrical connections and are as short and direct as possible.

4. Try operating the drive with all suspected noise sources switched off. If the drive functions properly, switch the noise sources on again, one at a time, and try to isolate which ones are causing the interference problems. When a noise source is located, try rerouting wiring, suppressing relays or other measures to eliminate the problem.

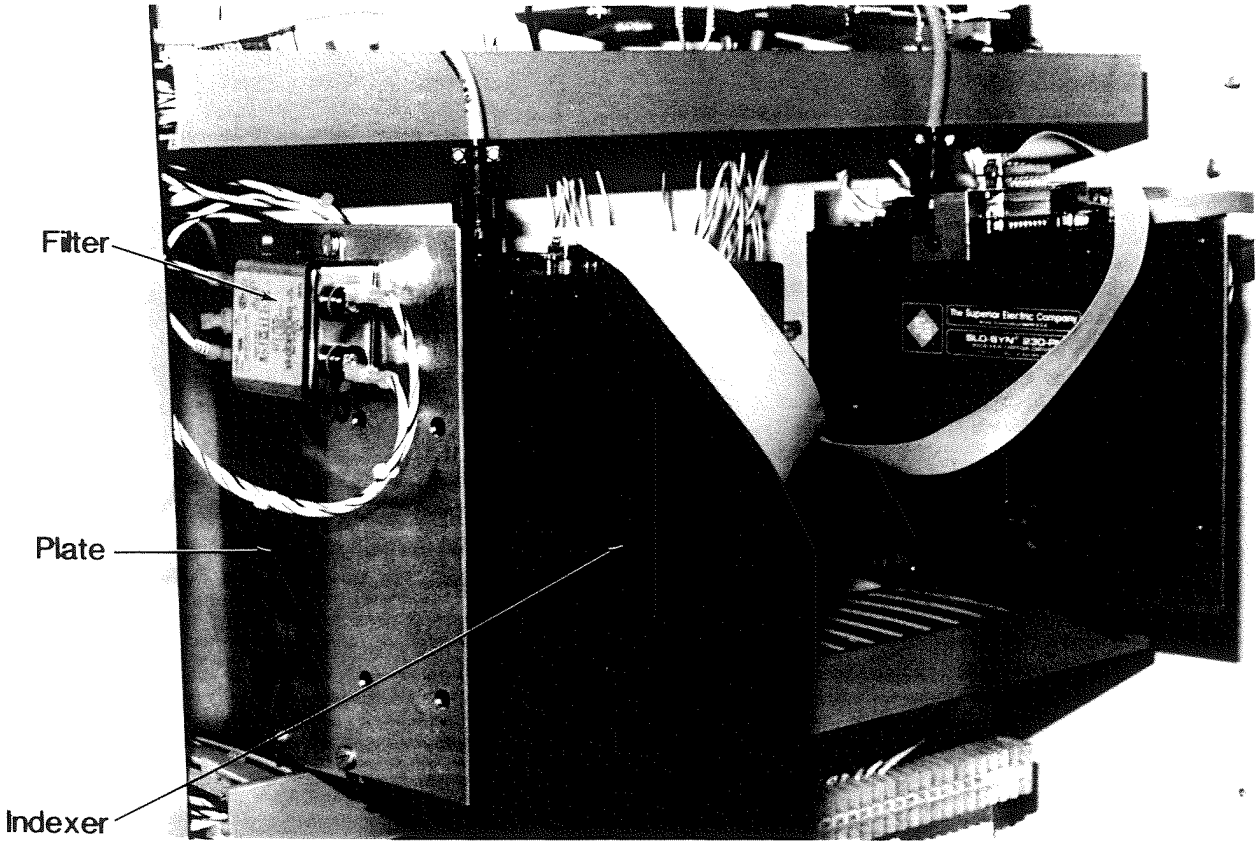


FIGURE 1
Filter Installed On Fabricated Plate Mounted On Indexer

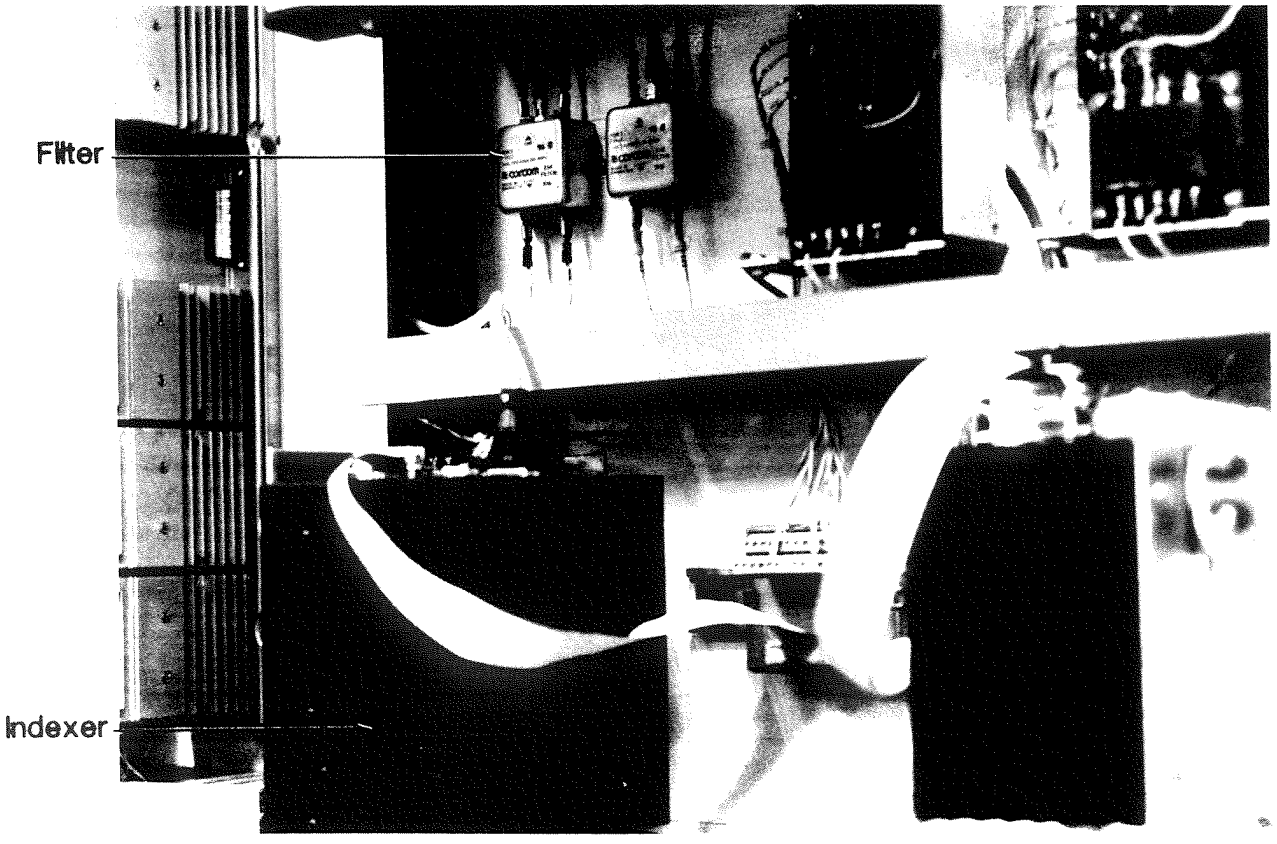


FIGURE 2
Filter Mounted Adjacent To Indexer

WARNINGS:

- **Voltages present in this unit can cause serious or fatal injury. Only qualified personnel should install or perform servicing procedures on this equipment.**
- **Voltage is present on unprotected pins when unit is operational.**
- **No short circuit protection for motor outputs is provided in this unit. The AC input is internally fused.**
- **Before making changes to the motor or control wiring, turn off all power to the unit, and disconnect its AC power source.**
- **When power is applied, all parts of the drive circuit should be considered hazardous.**
- **Allow at least ten minutes for capacitors to discharge as they will remain at high voltages for several minutes after power is removed.**

CAUTIONS:

- Assure motor compatibility before using the unit.
- Observe all cooling and temperature limitations. Heat sink temperature must be maintained between 0 and 80 degrees C. (32 and 176 degrees F). Unit must not be operated in ambient temperature below 0 degrees C (32 degrees F) or above 50 degrees C (122 degrees F).
- All Windings Off should be used with caution, as all holding torque is lost.
- Do not connect or disconnect motor or signal cables while AC power is applied.
- Do not apply AC power until all connections have been made correctly.
- Do not exceed specified input voltage.
- Do not operate unit without the enclosures in place, as high voltages are present.

LIMITS OF USE:

- Reconfiguration of the circuit in any fashion not shown in this manual will void the warranty.

NOTE:

1. **Clockwise and counterclockwise directions are properly oriented when viewing the motor from the label end.**

SECTION 1: INTRODUCTION

1.1 FEATURES OVERVIEW

The 3180-PTO provides the following output capability:

	MOTOR CURRENT PER PHASE	VA PER PHASE
3180-PTO	3 Amps Peak	500 VA nominal

The 3180-PTO motor drive/translator/oscillator package is a line-operated, energy efficient, self-contained motor drive module. An integral power supply provides the necessary DC voltages required to operate the drive. This module is capable of driving a wide range of Superior Electric Slo-Syn stepper motors, and has several features, including:

- Integral multi-range ramped oscillator for speed control
- Full/half, 1/10, or 1/125 step resolution, depending on model.
- Speeds up to 10,000 full steps per second.
- Motor current adjustable from 0.5 to 3.0 amperes per phase.
- Reduce-current and boost-current functions.
- Power-On and fault LED indicators.
- Over-temperature protection.

1.2 INSPECTION PARTS LIST

The drive comes fully assembled as a single unit and is marked with the part number, either 3180-PTO (full/half step), 3180-PTO10 (1/10 microstep), or 3180-PTO125 (1/125 microstep).

1.3 USING THIS MANUAL

This manual is an installation and operating guide to the 3180-PTO motor drive. All the necessary information is provided for using the 3180-PTO successfully.

We strongly recommend that this manual be read thoroughly and completely before attempting to install and operate the equipment.

1.3.1 ORGANIZATION

This manual is organized for the convenience of the operator. Section 2, "Mounting, Connections, and Pin Assignments," provides diagrams and reminders that are necessary for even the experienced user and installer.

Complete specifications, listed in Section 3, will provide easily referenced information concerning all aspects of installation, power and interface requirements, as well as performance specifications.

Section 4 gives a functional description of the drive, and Section 5 explains in detail each of the input/output signals.

The remaining sections contain additional drawings and information useful for setting up and operating the drive.

1.3.2 LOGIC CONVENTIONS, INDICATOR LAMPS, AND AC FUSE

- All logic is LOW TRUE. This means that a logic function is active when low and inactive when high. The low true condition is designated by a bar. For example, in the case of $\overline{AWO}$ (All Windings Off), the windings are OFF when the input is low.
- A red "PWR ON" LED indicator shows the presence of the +5 Vdc drive logic power supply; this shows the unit is energized.
- A red "TEMP" LED indicator detects a drive over-temperature condition. During this condition, the power is removed from the motor windings so that no holding torque is being applied. Recovery from this condition necessitates removing and then re-applying the AC power source.
- The unit's AC input is internally fused. A blown AC input fuse will prevent the power supply from energizing any of its outputs, hence, the unit will not operate. Usually, the only reason this fuse will open ("blow") is if an internal failure occurs. If an open fuse occurs, return the unit to the factory for service. **DO NOT REPLACE THE FUSE OR THE UNIT MAY BE FURTHER DAMAGED.**

SECTION 2: MOUNTING, CONNECTIONS AND PIN ASSIGNMENTS

2.1 MOUNTING

The 3180-PTO is mounted by affixing its enclosure to a flat surface in one of two possible configurations. Figure 2.1 shows the mounting hole locations and diameters. It is important to leave at least two inches (50.8mm) or space between the drive's top, bottom, and sides to allow proper airflow for cooling.

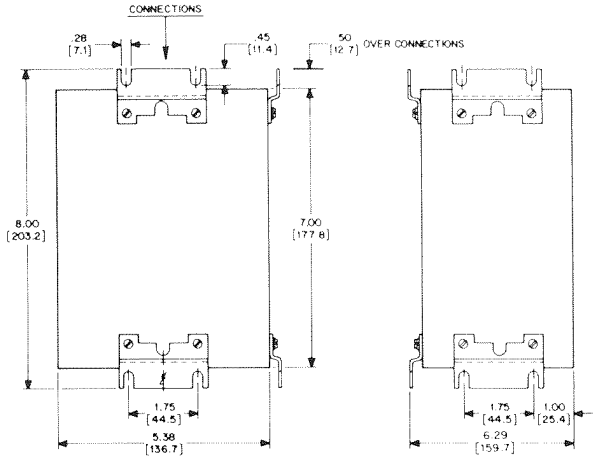
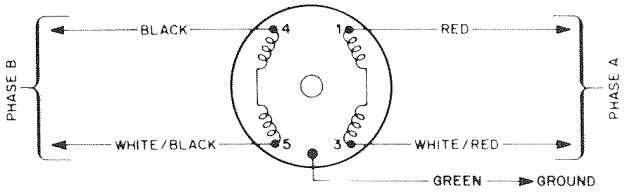


Figure 2.1: Mounting Diagram

The heat sink should always be mounted with the fins oriented vertically, or proper cooling will not occur. Air flow should not be obstructed. The maximum heat sink temperature must be held below 176 degrees F (80 degrees C).

2.2 MOTOR CONNECTIONS

All motor connections are made via the 8-pin circular AMP connector. Figure 2.2 shows the possible motor wiring configurations. The diagrams in Figures 2.2.1 through 2.2.6 show the connections for each combination of cable and motor type.



4-LEAD MOTORS, SERIES CONNECTION

Figure 2.2, Motor Connections

J2: Motor Connections

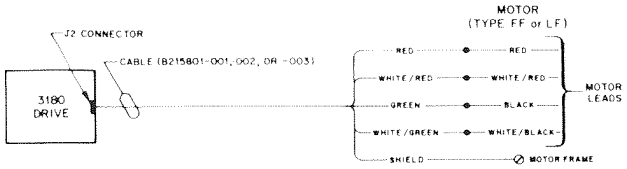
Cabling: Shielded, twisted-pair cable is highly recommended. Twist together the wires for each motor phase; six twists per foot is a good guideline.

Superior Electric Motor cables are available as follows:

	(Unterminated Leads on Motor End)	(Plug on Motor End)*
Length	Part Number	Part Number
10 ft. (3m)	B215801-001	B216066-001
25 ft. (7.6m)	B215801-002	B216066-002
50 ft. (15.2m)	B215801-003	B216066-003

*Mates with receptacles on M061, M062 and M063 motors that have receptacles.

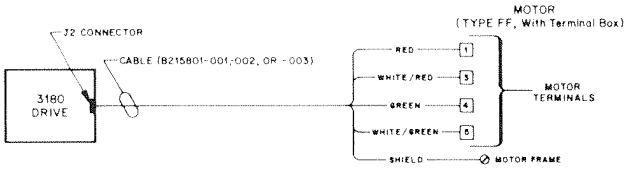
2.2.1 Connections Using LF or FF Type Motors (with Leads) and Superior Electric B215801-001, -002 or -003 Cables



3180 DRIVE / B215801-001, -002, or -003 CABLE / TYPE FF or LF MOTOR

Figure 2.2.1

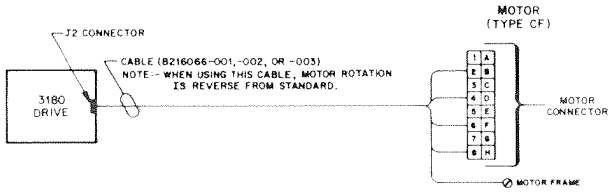
2.2.2 Connections Using FF Type Motors (with Terminal Boxes) and Superior Electric B215801-001, -002 or -003 Cables



3180 DRIVE / B215801-001, -002, or -003 CABLE / TYPE FF (With Term. Box) MOTOR

Figure 2.2.2

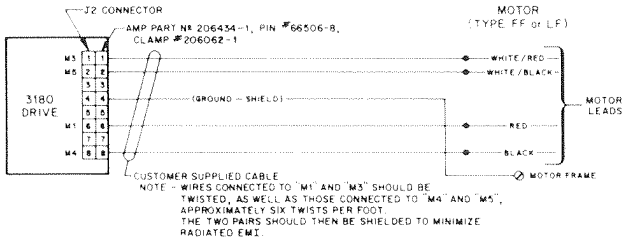
2.2.3 Connections Using CF Type Motors (with Connectors) and Superior Electric B216066-001, -002 or -003 Cables



3180 DRIVE / B216066-001, -002, or -003 CABLE / TYPE CF MOTOR

Figure 2.2.3

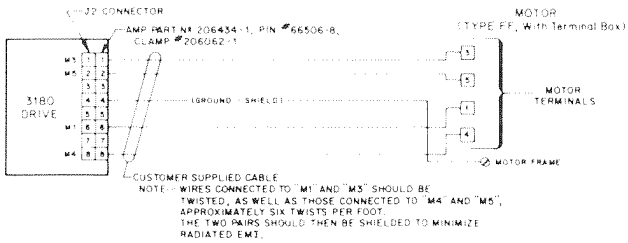
2.2.4 Connections Using LF or FF Type Motors (with Leads) and Customer Supplied Cables



3180 DRIVE / CUSTOMER SUPPLIED CABLE / TYPE FF or LF MOTOR

Figure 2.2.4

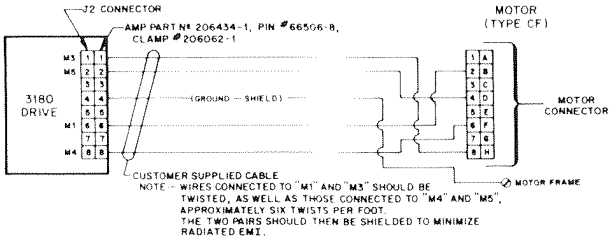
2.2.5 Connections Using FF Type Motors (with Terminal Boxes) and Customer Supplied Cables



3180 DRIVE / CUSTOMER SUPPLIED CABLE / TYPE FF (With Term. Box) MOTOR

Figure 2.2.5

2.2.6 Connections Using CF Type Motors (with Connectors) and Customer Supplied Cables



3180 DRIVE / CUSTOMER SUPPLIED CABLE / TYPE CF MOTOR

Figure 2.2.6

2.3 CONNECTORS

2.3.1 J1: Do Not Use

2.3.2 J2: Motor (see 3.5.2.1 for pin assignments)

2.3.3 J3: AC Power Input (see 3.5.1.2 for screw assignments)

2.3.4 J4: Signal I/O Connections (15-pin "D" type connector, female) (see 3.5.3.2 for pin assignments)

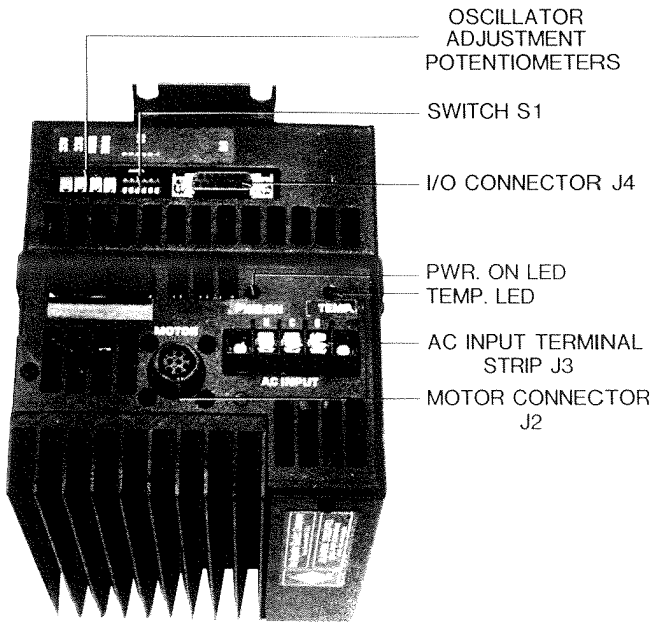


FIGURE 2.3 3180-PTO Connectors and Adjustments

SECTION 3: SPECIFICATIONS

3.1 DRIVE DESCRIPTION

Bipolar, speed adjustable, 2-phase, line operated chopper drive with translator, oscillator, and all power supplies.

Full, half, 1/10, or 1/125 step (Step resolution dependent on model type).

Power semiconductor type: N-channel FET

Chopping frequency: 20 kHz.

Control signals are optically isolated from the internal motor drive circuit.

3.2 DRIVE PERFORMANCE

Resolution: Half-step or full-step (3180-PTO)
1/10 microstep (3180-PTO10)
1/125 microstep (3180-PTO125)

Step Rate: 0 to 10,000 full-steps/sec. (3180-PTO)
0 to 20,000 half-steps/sec. (3180-PTO)
0 to 100,000 1/10 microsteps/sec. (3180-PTO10)
0 to 1,250,000 1/125 microsteps/sec. (3180-PTO125)

Oscillator base-speed frequency range: 0-150 kHz in 6 ranges

Oscillator high-speed frequency range: 0-1 mHz in 6 ranges

Accel/Decel adjustable range: 50ms to 2 seconds

Oscillator stability: Velocity and Accel/Decel, plus/minus 5% over full range of temperature and input power

Speed/Torque: See Section 7 for typical Speed/Torque curves.

3.3 MOTOR COMPATIBILITY

	3180-PTO
Motor types:	Superior Electric F Series motors are recommended
Frame Sizes:	61 to 112
No. of Leads:	4
Min. Inductance:	8.0 mH
Max. Inductance:	64 mH
Voltage to Motor:	170-190 Volts
Max. Motor Cable Length:	100 ft (30.5m)

MOTORS FOR USE WITH 3180-PTO

Superior Electric Type Number	3180 CURRENT SETTING (AMPERES)*
M061-CF408 M061-LF408	0.5
M062-CF402 M062-LF402	1.0
M063-CF401 M063-LF401	1.0
M091-FF401	1.0
M092-FF402	2.0
M093-FF402	3.0
M112-FF401	3.0
MH112-FJ4201	3.0

*Use this number to set the drive's "nominal" current as described in Section 3.6.1.

3.4 MECHANICAL SPECIFICATIONS

Size
(inches): 6.29 L x 5.67 W x 7.69 H (Height over connectors, excluding mounting flanges. Height with flanges is 8.0 inches)

(mm): 159.7 L x 144.0 W x 195.3 H

Weight:	lbs	kg
3180-PTO:	7	3.2

3.5 ELECTRICAL SPECIFICATIONS

3.5.1 AC INPUT

3.5.1.1 Power and Voltages

AC Input Range: 102 – 132 Vac, 50/60 Hz
Fuse Rating: 125 volts, 5 amps

Drive power dissipation (worst case)
3180-PTO: 90 watts

3.5.1.2 AC Input Connections

J3: 3-pin screw terminal strip

Pin	Assignment
"H"	Hot (black)
"C"	Common or Neutral (white)
"G"	Ground (green)

3.5.2 OUTPUT TO MOTOR

3.5.2.1 Motor Connections

J2: 8-pin twist-lock circular female AMP connector.

Pin	Assignment
1	M3
2	M5
3	No connection
4	Ground
5	No connection
6	M1
7	No connection
8	M4

NOTE: Motor phase A is M1 and M3, and phase B is M4 and M5.

Mates to male connector, AMP part number 206434-1 (AMP pin part number 66506-8 and AMP cable clamp part number 206062-1).

3.5.3 CONTROL SIGNAL INTERFACE

3.5.3.1 Signal Requirements

All connections are made via the J4 15-pin female "D" type connector. Optical isolation is used internally to separate all oscillator control signals from the motor drive circuitry. However, the J4 connector signals are not optically isolated from the user's circuitry; these signal characteristics are described below:

NOTE: Do not use the J1 connector for any purpose.

$\overline{\text{PULSE IN}}$ input characteristics:

Current sink from +5 Vdc internal source
Min. pulse width, low: 250 nanoseconds
Low level input current: 7 to 10 mA
Min. pulse width, high: 250 nanoseconds
High level input current: less than 1 mA

$\overline{\text{RUN}}$, $\overline{\text{BASE SPEED ONLY}}$ input characteristics:

High level voltage: +5.5 Vdc to +15 Vdc
High level current: 600 microamperes max.
Low level voltage: 0 Vdc to +4.5 Vdc
Low level current: 1.8 milliamperes max.

$\overline{\text{AWO}}$, CW/$\overline{\text{CCW}}$, HALF/$\overline{\text{FULL}}$, $\overline{\text{REDUCE CURRENT}}$, $\overline{\text{BOOST CURRENT}}$ input characteristics:

Current sink from +5Vdc internal source

High level input current: less than 1 mA
Low level input current: 10 mA to 20 mA

$\overline{\text{PULSE OUT}}$ output characteristics:

High level output voltage
(open collector): +24Vdc max.
Low level output voltage: +.7Vdc at 40 mA max.

Wire Size: 28 AWG minimum

Run length: 50 feet (15 meters) max.; 15 feet (4.6 meters) max. for HI SPEED POT 1 and HI SPEED POT 2. Shielded cable must be used for highest noise immunity. Be sure to ground the shield only at one end of the cable.

3.5.3.2 Pin Assignments for J4

Pin #	Assignment
1	All Windings Off (AWO)
2	CW/CCW (Direction)
3	PULSE IN (PU)
4	Reduce Current
5	(N.C.)
6	Run
7	Signal Common (Vo)
8	High Speed Pot 1
9	Half/Full (H/F)
10	PULSE OUT
11	Boost Current
12	Signal Common (Vo)
13	(N.C.)
14	Base Speed Only
15	High Speed Pot 2

Notes:

1. **N.C. = No Connection**
2. **The bar denotes "active low" logic. These inputs are tied to Signal Common to activate (low level) and open-circuited to deactivate (high level).**

3.6 SWITCHES AND POTENTIOMETERS

3.6.1 CURRENT SETTINGS

The current applied per motor phase is switch-selectable by a "DIP" switch (S2) accessible through an opening on the side of the indexer-drive (see Fig. 3.1 for switch location).

NOTE: Before making this adjustment, be sure to disconnect the drive's 120 volt AC power source and wait 10 minutes for the power supply capacitors to discharge. Set the switch as follows for the appropriate current, based on the motor's rating:

CURRENT (AMPS)			SWITCH POSITION			
NOMINAL	REDUCE	BOOST	S1	S2	S3	S4
2.0	1.0	3.0	OFF	OFF	OFF	OFF
1.5	0.75	2.25	ON	OFF	OFF	OFF
1.0	0.5	1.5	OFF	ON	OFF	OFF
0.5	0.25	0.75	OFF	OFF	ON	OFF
3.0	1.5	3.0	OFF	OFF	OFF	ON

Boost and Reduce functions are controlled via the appropriate input signals.

Note: When using BOOST, be sure that the motor maximum shell temperature is not exceeded. In some cases, it may be necessary to limit boost duty cycle to keep the motor below its maximum shell temperature, which is 105 degrees C (221 degrees F) for "M"-type motors and 125 degrees C (257 degrees F) for "MH"-type motors.

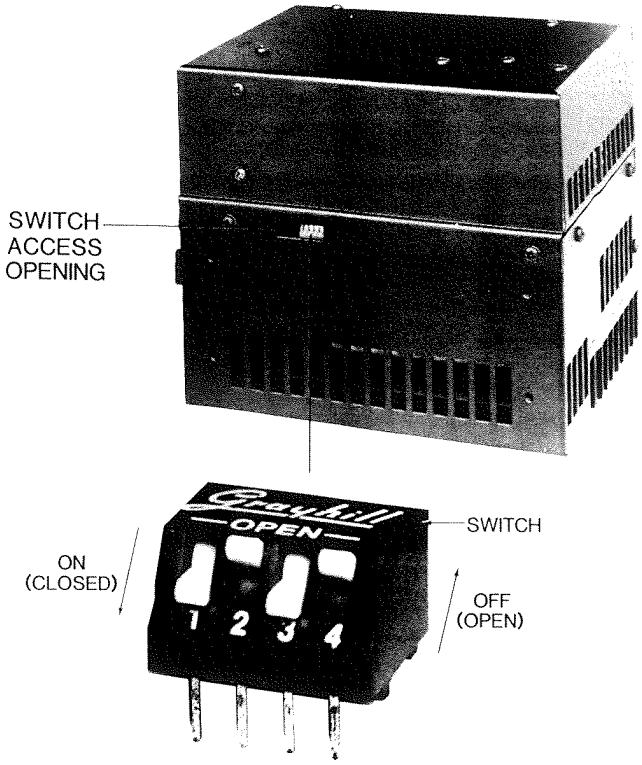


FIGURE 3.1 Current Setting Dip Switch For 3180 Series Drive

3.6.2 POTENTIOMETERS (See Figure 2.3 for potentiometer locations)

R1 Deceleration
R2 Acceleration
R3 High Speed
R4 Base Speed

The potentiometers are accessible from the top of the unit and a label identifies the function of each potentiometer. See Section 6 for adjustment procedures.

3.6.3 SWITCH S1, a 6-position DIP switch, is provided for setting speed ranges and for other functions. See Section 6 for proper set up. This switch is adjacent to J4 (see Figure 2.3).

3.7 ENVIRONMENTAL SPECIFICATIONS

Operating Temp:	+32 F to 122 F (0 C to +50 C) Free Air Ambient
Storage Temp:	−40 F to +167 F (−40 C to +75 C)
Humidity:	95% max., noncondensing
Altitude:	10,000 feet max. (3048 meters)
Cooling:	Will operate up to 122 degrees F (50 degrees C) so long as maximum heat sink temperature of 176 degrees F (80 degrees C) is maintained; forced-air (fan) cooling may be required.

SECTION 4: FUNCTIONAL DESCRIPTION

4.1 OVERVIEW

The 3180-PTO Oscillator/drives can be functionally divided into four components:

1. Motor drive circuitry
2. Translator circuitry
3. Oscillator/pulse generator circuits
4. Logic control functions

The 3180-PTO drives electronically convert input pulses into drive signals of the proper sequence and power required to operate a stepping motor: one input pulse being "translated" into one motor step. To drive the motor, a technique called **"chopping"** is used. Compared to older drive techniques, chopping gives improved motor performance while allowing the drive circuitry to dissipate less power. The voltage applied to the motor windings is turned on and off very rapidly, or **chopped** so that the desired current is produced.

The translator circuitry accepts a single pulse at a time as an input and determines which windings (phases) of the motor must be turned on and off in order to advance the motor shaft one step. The translator circuit is fully self-contained and is not accessible through any of the function pins.

The pulse input to the translator is internally generated by the oscillator. **This is accomplished by setting switch S1, position 4 to the "on" (closed) state, unless an external pulse source is utilized.** The oscillator circuitry controls the frequency of the pulse train for acceleration, deceleration, high and base speeds in accordance with the settings of the appropriate potentiometers.

The logic control circuitry accepts high or low logic levels through the pins on connector J4 and adjusts the motor operational parameters as described in Section 5.

The user may remotely control the high speed rate by connecting a 500k ohm potentiometer between pins 8 & 15 on connector J4. **If no external potentiometer is required, set position 3 of switch S1 to the "on" (closed) state.**

4.2 SIGNAL FUNCTIONS

Input pulses, one for each desired motor step, are received by the translator circuit on the PULSE IN (PU) pin.

Two input control signals alter the sequence of motor windings which will be energized. The CW/CCW pin controls which direction the motor will move and the HALF/FULL (H/F) pin determines whether a half or full step is taken. (Note: H/F is only active on the 3180-PTO; the microstepping versions, 3180-PTO10 and 3180-PTO125 do not use this signal.)

Even when the motor is stationary, current is flowing through one or two of the windings. The magnetic field produced by this current holds the shaft firmly with a force specified as the "holding torque." The input control signal, ALL WINDINGS OFF (AWO), turns off all current to the motor, thus allowing the shaft to be turned manually.

Additional motor torque for acceleration may be obtained by using the BOOST input. This increases current per phase by 50%, up to a maximum of 3 amperes.

If desired, current may be decreased by 50% using the REDUCE input. This function allows for cooler motor operation at standstill in cases where the resulting lower holding torque can be accommodated.

SECTION 5: CONTROL SIGNAL DESCRIPTIONS (Reference Figure 2.3)

Connector J4, 15-pin "D" type connector, female

5.1 AWO (ALL WINDINGS OFF) – Pin 1

A logical low turns off all power to the motor windings.

WARNING:

Holding torque is eliminated when this signal is active. Insure that the motor load, when released by this command, will not injure property or personnel.

5.2 CW/CCW (DIRECTION) – Pin 2

A logical high or an open connection causes the motor shaft to step in the clockwise direction as viewed from the label end of the motor. A logical low results in counterclockwise rotation.

5.3 PU (PULSE IN) – Pin 3

A low to high (positive going edge) transition on this pin causes the motor to take one step. Maximum frequency is 1.25 MHz.

5.4 REDUCE CURRENT – Pin 4

A logical low decreases motor current to 50% of the value set by the current-set "DIP" switch S2.

5.5 NOT CONNECTED – Pin 5

5.6 RUN – Pin 6

When connected to "SIGNAL COMMON" (logic low) enables the oscillator.

If BASE SPEED ONLY is open (logic high) when RUN is activated (logic low), the motor will accelerate according to the set rate, to the predetermined high speed. When RUN is open (logic high), the motor will decelerate according to the set rate until base speed is reached, and will then stop.

5.7 SIGNAL COMMON (Vo) – Pin 7

Reference point for all inputs and outputs.

5.8 HI SPEED POT 1 — Pin 8

Allows for control of high speed by means of an external 500k ohm potentiometer (ten-turn audio taper), when used in conjunction with HI SPEED POT 2 (pin #15). This is also a test point for acceleration and deceleration.

5.9 H/F (HALF/FULL) – Pin 9

A logical low causes the motor to step the full step angle indicated in its specifications. A logical high (open) causes the motor to take a "half step" equal to half of its specified step angle. When operated in half-step mode the motor provides smoother motion with finer resolution, but at approximately 30% less torque.

Note: This input is only used on the 3180-PTO full-step, half-step translator drives. It is inactive on the 3180-PTO10 and 3180-PTO125 microstepping drives.

5.10 PULSE OUT – Pin 10

Produces a pulse (square wave output) from oscillator. Connect to "PULSE IN" by placing position 4 of switch S1 in the "on" (closed) state if an external source is not required.

This is also a test point for monitoring base speed and high speed. This output is an open collector output and should be connected to PULSE IN if used for monitoring purposes.

5.11 BOOST CURRENT – Pin 11

A logical low increases current to 1.5 times the value set by the current-set "DIP" switch S2, up to 3.0 amperes maximum.

HIGH SPEED (%)	POTENTIOMETER R3 SETTING (APPROX # OF TURNS CCW FROM FULLY CW POSITION)		
	FREQUENCY RANGES		
	0-20 HKZ	0-100 KHZ	0-1 MEG HZ
0	2 1/4	2 1/4	2 1/4
10	3 1/2	3 1/2	3 1/8
20	4 1/2	4 1/2	3 5/8
30	5 1/2	5 1/4	4 1/8
40	6 3/4	6	4 1/2
50	7 3/4	7	5 1/8
60	9	8	5 3/4
70	10 1/4	9 1/4	6 1/4
80	11 3/4	10 1/4	6 7/8
90	13 1/2	11 1/2	7 1/2
100	14 3/4	13	8 1/4

Setting High Speed using chart:

1. Connect RUN (J4, pin #6) to SIGNAL COMMON (J4, pir
2. Adjust R3 potentiometer CW until motor is running at b
3. Adjust R3 potentiometer CCW until motor is just a Speed; this is approximately the 0% setting on the cha
4. Adjust R3 potentiometer CCW. The number of turns req difference between the desired speed and the 0% spee

Example:

The desired High Speed on the 0-20K HZ range is 10 k The 50% setting is 7 3/4 turns from the fully CW positio setting is 2 1/4 turns fom the fully CW position. Thus, F adjusted 5 1/2 turns CCW from the 0% setting.

HIGH SPEED (%)	APPROXIMATE VOLTAGE INPUT ON J4 – 15		
	FREQUENCY RANGES		
	0 – 20 KHZ	0 – 100 KHZ	0 – 1 MEG HZ
0	+ 5.43 V	+ 5.43 V	+ 5.43 V
10	+ 5.82 V	+ 5.78 V	+ 5.69 V
20	+ 6.08 V	+ 5.99 V	+ 5.82 V
30	+ 6.34 V	+ 6.21 V	+ 5.95 V
40	+ 6.62 V	+ 6.44 V	+ 6.08 V
50	+ 6.92 V	+ 6.68 V	+ 6.22 V
60	+ 7.24 V	+ 6.94 V	+ 6.37 V
70	+ 7.60 V	+ 7.22 V	+ 6.52 V
80	+ 7.98 V	+ 7.52 V	+ 6.69 V
90	+ 8.41 V	+ 7.84 V	+ 6.87 V
100	+ 8.89 V	+ 8.20 V	+ 7.06 V

NOTE: Because of the oscillator design, the high speed set lower than the speed set on the base speed potentio example, if base speed is set to 200 Hz, the high speed no lower than 200 Hz.

6.4 HIGH SPEED

HIGH SPEED POTS 1 AND 2 TERMINALS ARE EITHER C(TOGETHER (BY CLOSING POSITION 3 OF S1 FOR ON-BOAF TION) OR ARE CONNECTED TO A REMOTE POTENT (Potentiometer set at minimum resistance.)

1. Make sure that BASE SPEED ONLY (J4 pin #14) is OP
2. Connect RUN (J4 pin #6) to SIGNAL COMMON.
3. Turn HIGH SPEED POT (R3) **counterclockwise** t velocity to desired maximum limit.

Speed (pulse frequency) can be monitored at J4, pin #1 OUT). Position 4 of switch S1 should be "on" (closed).

The settings of "DIP" switch S1, described in 6.3, also High Speed Range as noted in 6.3.

6.5 ACCELERATION

Acceleration time to high speed, with the Accel potentiometer (R2) fully counterclockwise is approximately 50 milliseconds. Range is from 50 milliseconds to 2 seconds (approximately).

Measure acceleration with an oscilloscope connected between HI SPEED POT 1 and SIGNAL COMMON. Oscilloscope should be triggered when RUN (J4 pin #6) goes low.

Then make the following settings:

1) Make sure BASE SPEED ONLY is Open.
2) Set RUN to Open.
   This signal must be open circuited long enough to allow complete deceleration.
3) Connect RUN to SIGNAL COMMON (logic low).
4) Measure acceleration time.
5) Adjust Acceleration potentiometer (R2) clockwise to increase acceleration time.
6) Repeat steps 2 – 5 until acceleration is attained.

The following table gives approximate settings for the Acceleration Potentiometer (R2).

The acceleration times are essentially unaffected by any p ter or switch settings.

ACCELERATION TIME (milliseconds)	POTENTIOMETER R2 SETT (number of turns CW from fully CCW position
22	0
60	1/2
100	1
200	2
300	3
400	4
500	5
600	6
800	8
1000	10
1250	12 1/2
1500	15
1750	17 1/2
2000	20
2200	22

6.6 DECELERATION

Deceleration time from high speed to base speed, with the Deceleration potentiometer (R1) fully counterclockwise is 50 milliseconds. Range is from 50 milliseconds to 2 seconds. **Measure deceleration with an oscilloscope connected to HI SPEED POT 1 and SIGNAL COMMON.** Oscilloscope should trigger when RUN (J4 pin #6) goes high.

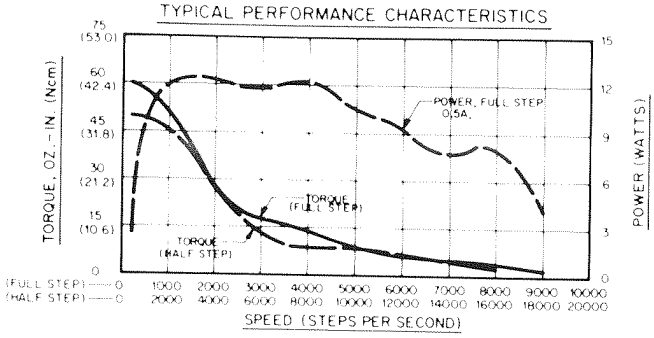
Then make the following settings:

1. Make sure $\overline{\text{BASE SPEED ONLY}}$ is Open.
2. Connect $\overline{\text{RUN}}$ (J4 pin #6) to SIGNAL COMMON (low). Maintain low until high speed is achieved.
3. Remove $\overline{\text{RUN}}$ connection to SIGNAL COMMON. Maintain until measurement is complete.
   (Oscilloscope will be triggered when $\overline{\text{RUN}}$ is open. This signal must be open circuited long enough to allow complete deceleration.)
4. Measure deceleration time.
5. Adjust Deceleration potentiometer (R1). Clockwise movement increases deceleration time.
6. Repeat steps 2 – 5 until desired deceleration is reached.

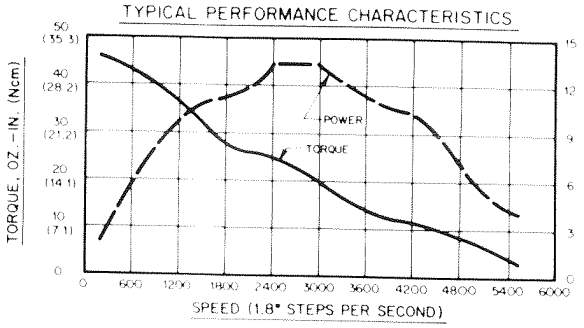
The following table gives approximate settings for the Deceler Potentiometer (R1).

DECELERATION TIME (milliseconds)	POTENTIOMETER R1 SETTING (number of turns CW from fully CCW position)
22	0
60	1/2
100	1
200	2
300	3
400	4
500	5
600	6
800	8
1000	10
1250	13
1500	15 1/2
1750	18
2000	20

SECTION 7: SPEED/TORQUE CURVES

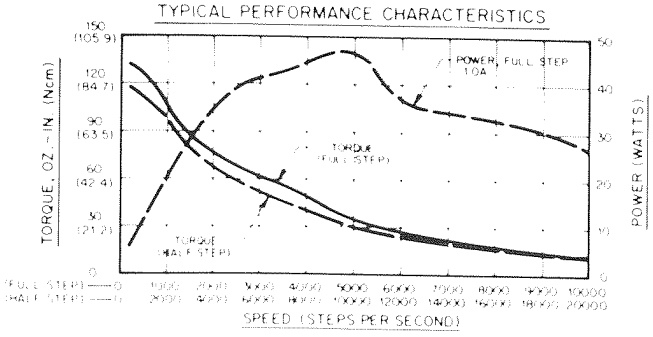


FULL/HALF STEP



MICROSTEP

M061-CF408 AND M061-LF408 MOTORS



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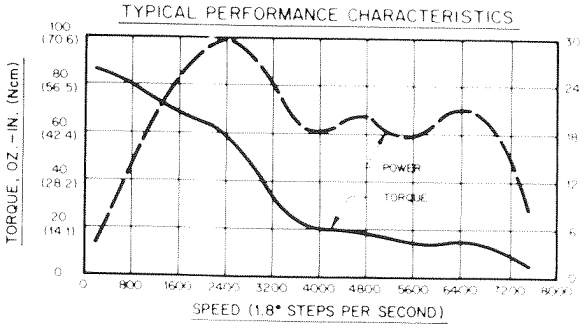

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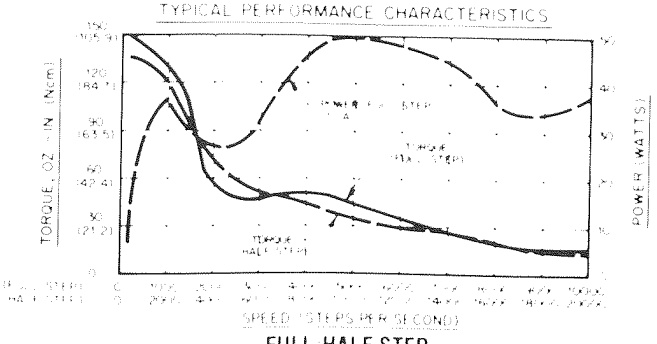
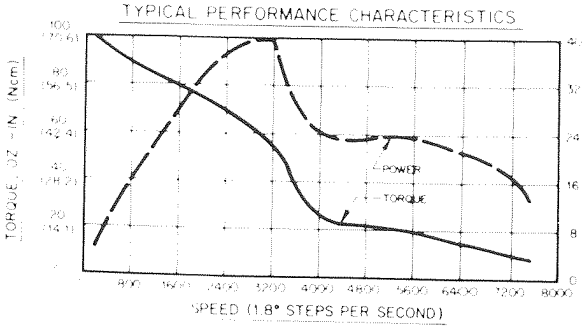
M062-CF402 AND M062-LF402 MOTORS



FULL/HALF STEP



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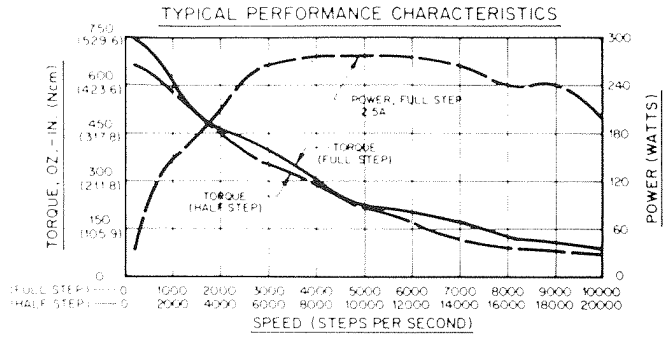
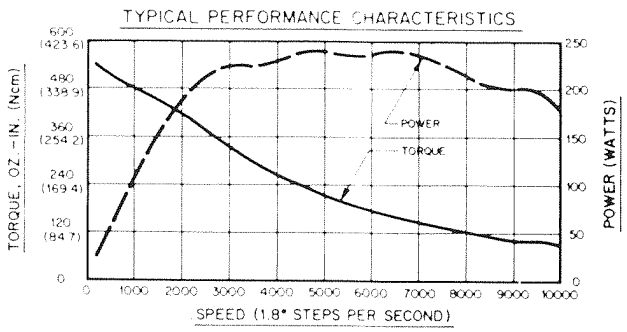
M063-CF401 AND M063-LF401 MOTORS



FULL/HALF STEP



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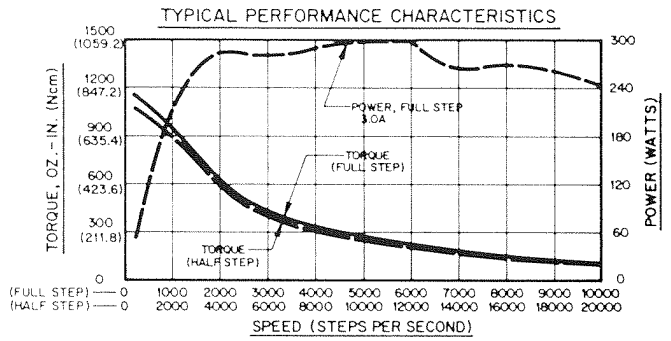
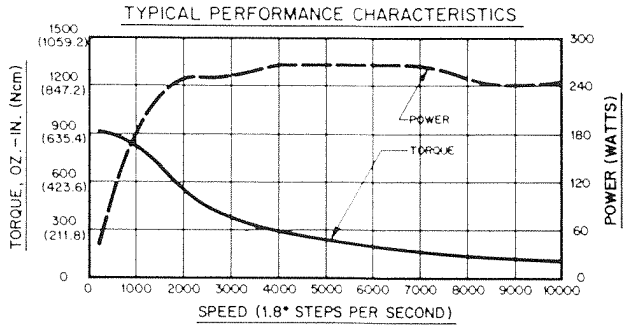
M112-FF401 MOTOR



FULL/HALF STEP



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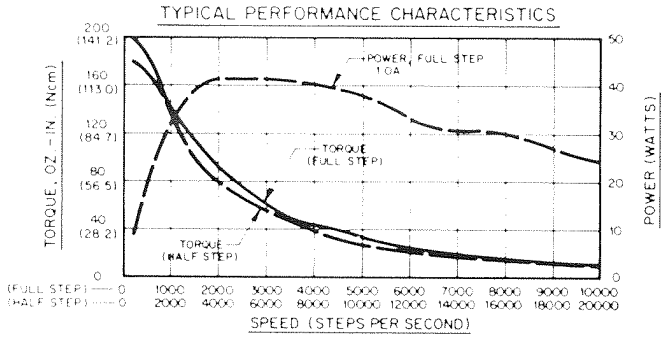
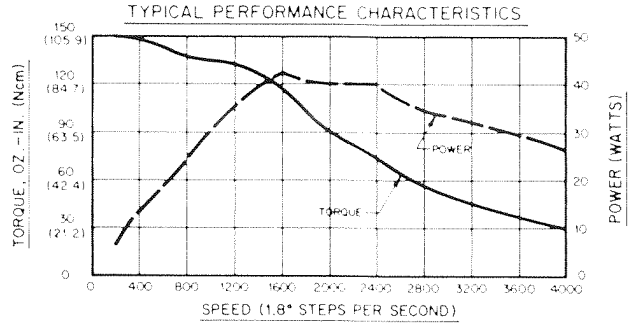
MH112-FJ4201 MOTOR



FULL/HALF STEP



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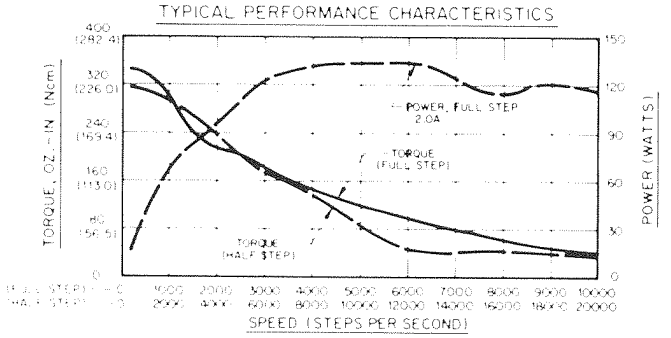
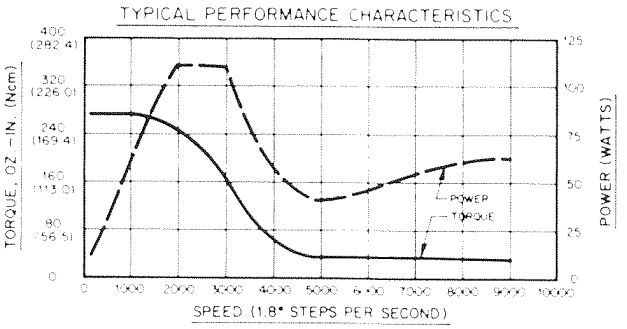
M091-FF401 MOTOR



FULL/HALF STEP



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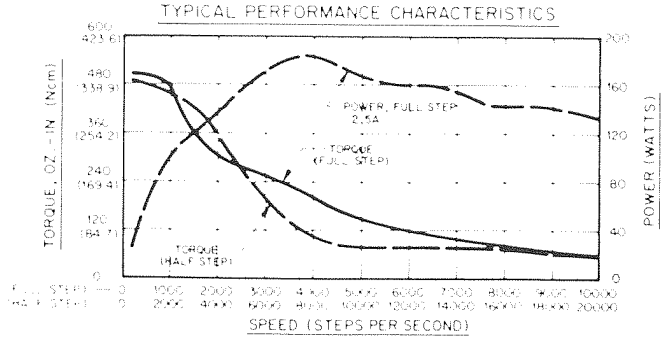
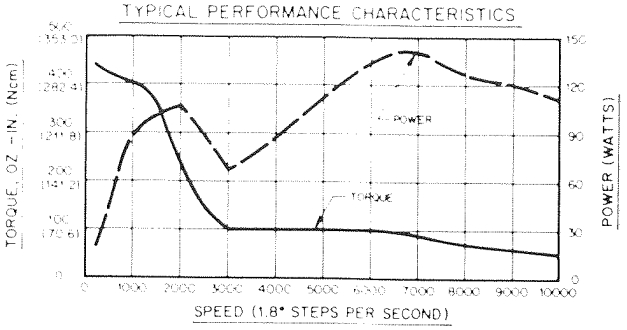
M092-FF402 MOTOR



FULL/HALF STEP



MICROSTEP

M093-FF402 MOTOR

7.1 MOTOR PERFORMANCE

All stepping motors exhibit instability at their natural frequency and harmonics of that frequency. Typically, this instability will occur at speeds between 50 and 500 full steps per second and, depending on the dynamic motor load parameters, can cause excessive velocity modulation or improper positioning.

There are also other instabilities which may cause a loss of torque at stepping rates outside the range of natural resonance frequencies. One such instability is broadly identified as mid-range instability. This is identified by the dotted area (....) on the speed torque curves.

Usually, the dampening of the system and acceleration/deceleration through the resonance areas aid in reducing instability to a level that provides smooth shaft velocity and accurate positioning. If instability does cause unacceptable performance under actual operating conditions, the following techniques can be used to reduce velocity modulation.

1. Avoid constant speed operation at the motor's unstable frequencies. Select a base speed that is above the motor's resonant frequencies and adjust acceleration and deceleration to move the motor through unstable regions quickly.
2. The motor winding current can be reduced as discussed in Section 3.6. Lowering the current will reduce torque proportionally. The reduced energy delivered to the motor can decrease velocity modulation.
3. Use half-step mode of operation (3180-PTO only). Note that this also halves the shaft speed for a given input pulse rate. Microstepping (3180-PTO10 and 3180-PTO125) inherently provides smoother operation, and reduces the effects of instability.

SECTION 8: TROUBLESHOOTING

WARNING:

Motors connected to this drive can develop high torque and large amounts of mechanical energy.

Keep clear of the motor shaft, and all parts mechanically linked to the motor shaft.

Turn off the power to the drive before performing work on parts mechanically coupled to the motor.

If installation and operation instructions have been followed carefully, this unit should perform correctly. If motor fails to step properly, the following checklist will be helpful.

In General:

- Check all installation wiring carefully for wiring errors or poor connections.
- Check to see that the proper AC voltage level is being supplied to the unit.
- Be sure the motor is compatible for use with this unit.

8.1 IF MOTOR DIRECTION (CW, CCW) IS REVERSED, Check:

Connections between the drive and the motor. Motor wires may have been reversed accidentally on one phase. For example, swap the positions of the M1 and M3 (red and white/red wires).

8.2 IF THE MOTOR MOTION IS ERRATIC, Check:

Input pulses not of proper level or width.
Supply voltage out of tolerance.
Operation in area of motor instability (dotted portion of torque/speed curve).

8.3 IF TORQUE IS LOW, Check:

$\overline{\text{AWO}}$ (All Windings Off) active or $\overline{\text{REDUCED CURRENT}}$ active.
Improper supply voltage.
Operation in area of motor instability (dotted portion of torque/speed curve).

If a malfunction occurs that cannot be corrected by making these corrections, contact The Superior Electric Company.

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