



TRINAMIC PD-1160 UNIQUE FEATURES Stepper Motor with Controller Driver User Manual

[Home](#) » [TRINAMIC](#) » TRINAMIC PD-1160 UNIQUE FEATURES Stepper Motor with Controller Driver User Manual

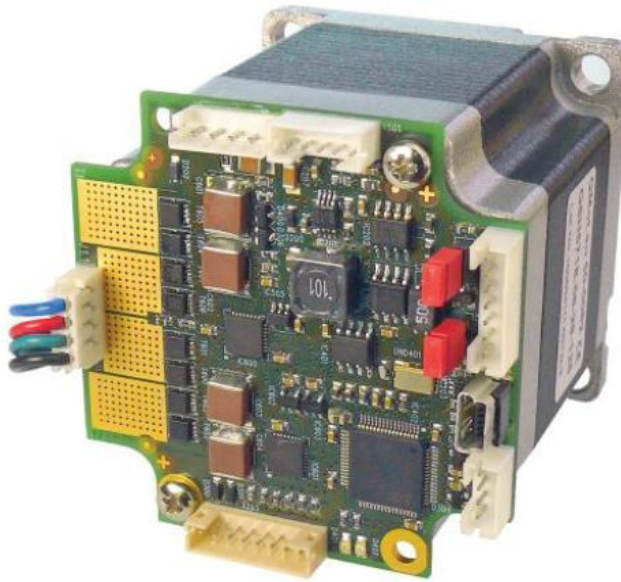


Contents

- [1 TRINAMIC PD-1160 UNIQUE FEATURES Stepper Motor with Controller Driver](#)
- [2 Features](#)
 - [2.1 MAIN CHARACTERISTICS](#)
- [3 Order Codes](#)
- [4 Mechanical and Electrical Interfacing](#)
- [5 Jumpers](#)
- [6 Reset to Factory Defaults](#)
- [7 On-board LEDs](#)
- [8 Operational Ratings](#)
- [9 Torque Curves](#)
- [10 Functional Description](#)
- [11 PD-1160 Operational Description](#)
- [12 Revision History](#)
 - [12.1 Hardware Revision](#)
- [13 Documents / Resources](#)
 - [13.1 References](#)



TRINAMIC PD-1160 UNIQUE FEATURES Stepper Motor with Controller Driver



Product Information

- **Product Name:** PANdrive Stepper Motor with Controller / Driver
- **Hardware Version:** V1.1
- **Manufacturer:** TRINAMIC Motion Control GmbH & Co. KG
- **Website:** www.trinamic.com

Unique Features

- Stepper motor with controller/driver
- 0.55 – 3.1 Nm torque
- 48V sensOstep™ Encoder
- USB, RS485, and CAN interfaces
- Step/Dir Interface

Order Codes

PD-1160

Mechanical and Electrical Interfacing

PD57-1160 Dimensions

Dimensions for PD57-1160 are available in the hardware manual.

PD60-1160 Dimensions

Dimensions for PD60-1160 are available in the hardware manual.

Jumpers

RS485 Bus Termination

Instructions for RS485 bus termination are available in the hardware manual.

CAN Bus Termination

Instructions for CAN bus termination are available in the hardware manual.

Curves

PD57-1160 Torque Curves

Torque curves for PD57-1160 are available in the hardware manual.

PD60-1160 Torque Curves

Torque curves for PD60-1160 are available in the hardware manual.

Functional Description

Detailed functional description is available in the hardware manual.

Operational Description

Operational description for PD-1160 is available in the hardware manual.

Life Support Policy

Information about the life support policy is available in the hardware manual.

Revision History

Revision history for PD-1160 is available in the hardware manual.

PD-1160

Stepper Motor with Controller / Driver 0.55 – 3.1 Nm / 48 V sensOstep™ Encoder USB, RS485, and CAN Step/Dir Interface

Features

The PANdrive™ PD-1160 is a full mechatronic solution with state of the art feature set. It is highly integrated and offers a convenient handling. The PD-1160 includes a stepper motor, controller/driver electronics, and TRINAMICs sensOstep™ encoder. It can be used in many decentralized applications and has been designed for 0.55... 3.1Nm max. holding torque and 24 or 48 V DC nominal supply voltage. With its high energy efficiency from TRINAMIC's coolStep technology cost for power consumption is kept down. The TMCL™ firmware allows for standalone operation and direct mode.

MAIN CHARACTERISTICS

Motion controller

- Motion profile calculation in real-time
- On the fly alteration of motor parameters (e.g. position, velocity, acceleration)
- High performance microcontroller for overall system control and serial communication protocol handling

Bipolar stepper motor driver

- Up to 256 microsteps per full step
- High- efficient operation, low power dissipation
- Dynamic current control
- Integrated protection

- stallGuard2 feature for stall detection
- coolStep feature for reduced power consumption and heat dissipation

Encoder

- sensOstep magnetic encoder (1024 increments per rotation) e.g. for step-loss detection under all operating conditions and positioning supervision
- Interface for connection of external incremental a/b/n encoder

Interfaces

- RS485 interface
- CAN (2.0B up to 1Mbit/s) interface
- USB full speed (12Mbit/s) interface
- Step/Direction interface (optically isolated)
- 3 inputs for stop switches and home switch (+24V compatible) with programmable pull-up
- 2 general purpose inputs (+24V compatible) and 2 general purpose outputs (open collector)
- Incremental a/b/n encoder interface (TTL and open-collector signals supported directly)

Safety features

- Shutdown input – driver will be disabled in hardware as long as this pin is left open or shorted to ground
- Separate supply voltage inputs for driver and digital logic – driver supply voltage may be switched off externally while supply for digital logic and therefore digital logic remains active

Software

- TMCL: standalone operation or remote controlled operation, program memory (non volatile) for up to 2048 TMCL commands, and PC-based application development software TMCL-IDE available for free.
- Ready for CANopen

Electrical and mechanical data

- Supply voltage: common supply voltages +12 V DC / +24 V DC / +48 V DC supported (+9 V... +51 V DC)
- Motor current: up to 2.8 A RMS (programmable)
- 0.55... 3.1Nm max. holding torque (depends on motor)
- With NEMA23 (57mm motor flange size) or NEMA24 (60mm motor flange size) stepper motor

Refer to separate TMCL Firmware Manual, too.

TRINAMICS UNIQUE FEATURES – EASY TO USE WITH TMCL

stallGuard2™ stallGuard2 is a high-precision sensorless load measurement using the back EMF on the coils. It can be used for stall detection as well as other uses at loads below those which stall the motor. The stallGuard2 measurement value changes linearly over a wide range of load, velocity, and current settings. At maximum motor

load, the value goes to zero or near to zero. This is the most energyefficient point of operation for the motor.

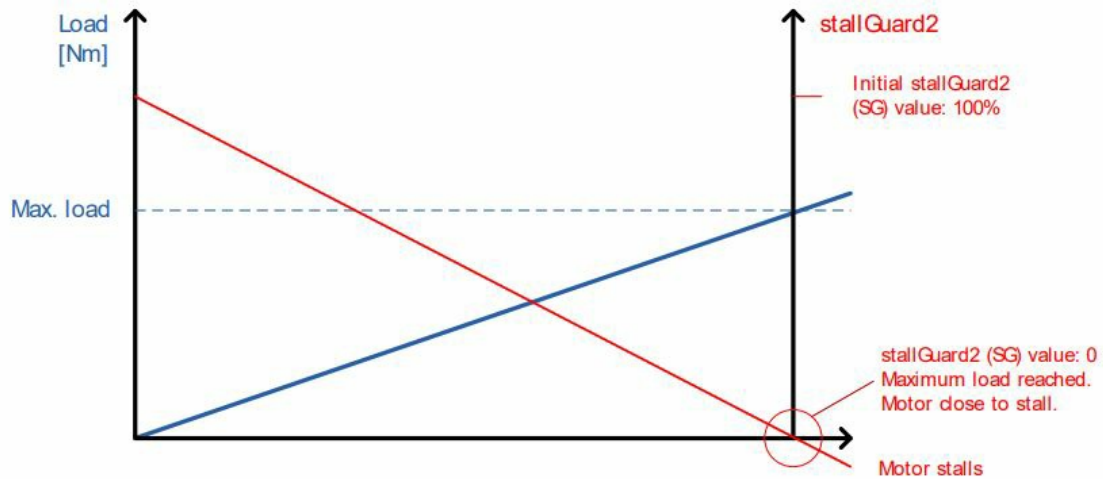


Figure 1.1 stallGuard2 load measurement SG as a function of load

coolStep™ coolStep is a load-adaptive automatic current scaling based on the load measurement via stallGuard2 adapting the required current to the load. Energy consumption can be reduced by as much as 75%. coolStep allows substantial energy savings, especially for motors which see varying loads or operate at a high duty cycle. Because a stepper motor application needs to work with a torque reserve of 30% to 50%, even a constant-load application allows significant energy savings because coolStep automatically enables torque reserve when required. Reducing power consumption keeps the system cooler, increases motor life, and allows reducing cost.

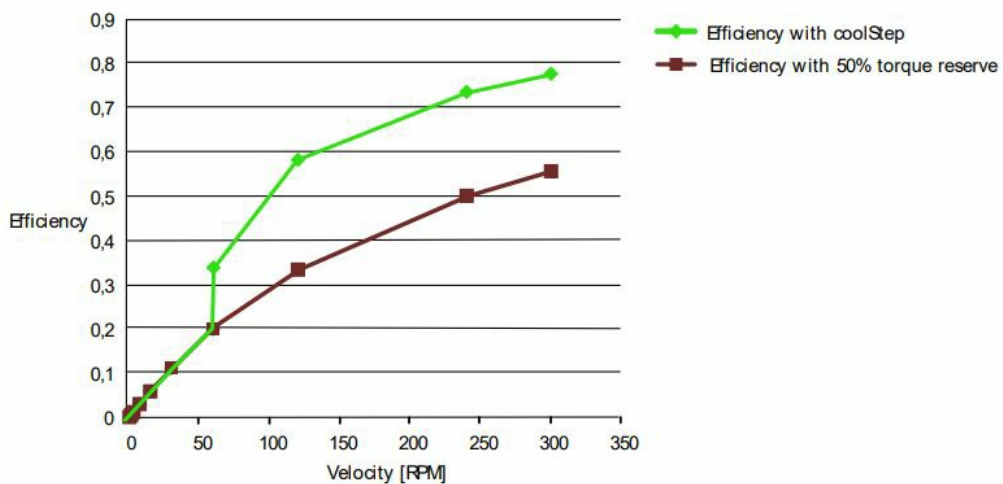


Figure 1.2 Energy efficiency example with coolStep

Order Codes

The PD-1160 is currently available with two different stepper motor series (NEMA23 / 57mm flange size or NEMA24 / 60mm flange size):

With NEMA 23 / 57mm flange size motor:

The length of the PANdrives is specified without the length of the axis. For the overall length of the product please add 24mm.

Table 2.1 Order codes (PD57-1160)

Order code	Description	Size (mm3)
PD57-1-1160	PANdrive with 0.55Nm max./holding torque	60 x 60 x 58
PD57-2-1160	PANdrive with 1.01Nm max./holding torque	60 x 60 x 68

With NEMA 24 / 60mm flange size motor:

The length of the PANdrives is specified without the length of the axis. For the total length of the product add 24mm.

Table 2.2 Order codes (PD60-1160)

Order code	Description	Size (mm3)
PD60-3-1160	PANdrive with 2.10Nm max./holding torque	60 x 60 x 82
PD60-4-1160	PANdrive with 3.10Nm max./holding torque	60 x 60 x 103

A cable loom set is available for this module:

Table 2.3 Cable loom order codes

Order code	Description
PD-1160-CABLE	<p>Cable loom for PD-1160:</p> <ul style="list-style-type: none"> – 1x cable loom for power connector (length 200mm) – 1x cable loom for communication connector (length 200mm) – 1x cable loom for multipurpose I/O connector (length 200mm) – 1x cable loom for S/D connector (length 200mm) – 1x cable loom for encoder connector (length 200mm) – 1x USB type A connector to mini-USB type B connector cable (length 1.5m)

Mechanical and Electrical Interfacing

PD57-1160 and PD60-1160 Dimensions

1. PD57-1160 Dimensions

The PD57-1160 includes the TMCM-1160 stepper motor controller/driver module, the magnetic encoder based on sensOstep technology and a NEMA23 bipolar stepper motor. Currently, there is a choice between two NEMA 23/57mm bipolar stepper motors with different lengths and different holding torques.

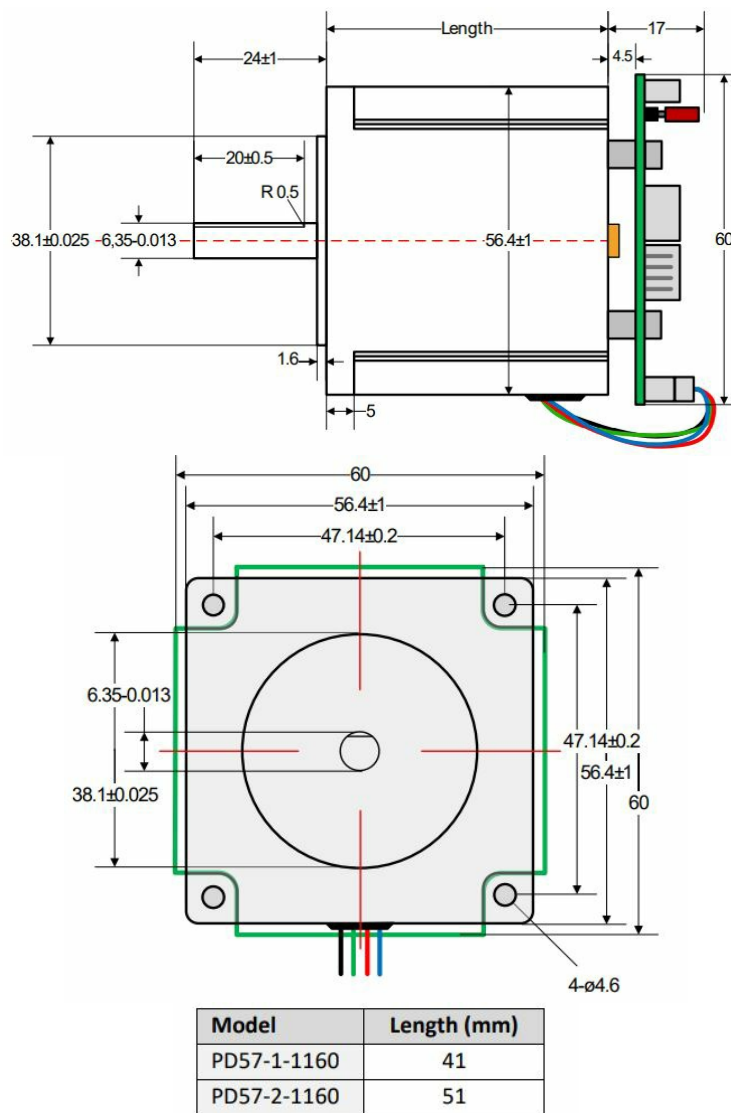
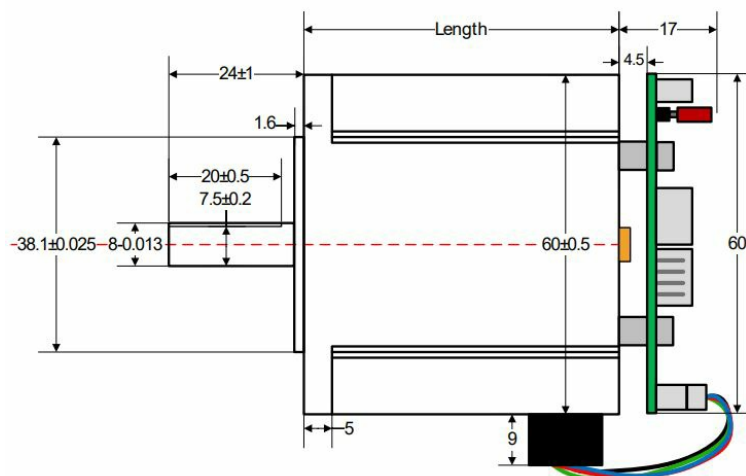
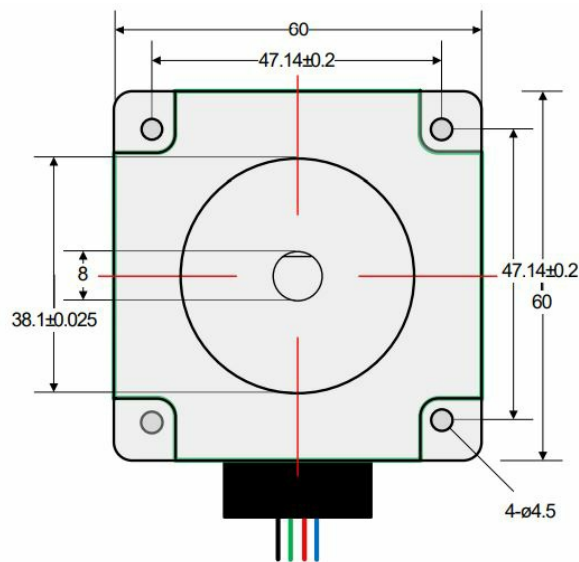


Figure 3.1 Dimensions of PD57-1160

2. PD60-1160 Dimensions

Currently, there is a choice between two NEMA 24/60mm bipolar stepper motors with different lengths and different holding torques.





Model	Length (mm)
PD60-3-1160	65
PD60-4-1160	86

Figure 3.2 Dimensions of PD60-1160

Connectors of PD-1160

The PD-1160 offers seven connectors including the motor connector which is used for attaching the motor coils to the electronics. In addition to the power connector there are two connectors for serial communication (mini-USB connector and 5pin connector for RS485 and CAN) and three connectors for Step/Direction, multipurpose input/output signals, and for an external encoder.

The multipurpose connector offers two general purpose outputs, two general purpose inputs, two inputs for stop switches and one for an additional home switch.

The power supply connector offers separate inputs for driver and for logic power supply plus hardware shutdown input. Leaving the shutdown input open or tying it to ground will disable the motor driver stage in hardware. For operation, this input should be tied to supply voltage.

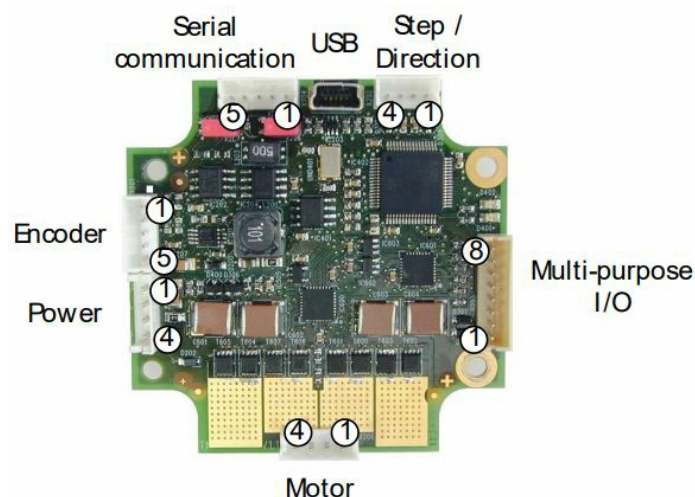


Figure 3.3 Overview connectors

Table 3.1 Connectors and mating connectors, contacts and applicable wire

Label	Connector type	Mating connector type
Power Connector	JST B4B-EH-A (JST EH series, 4pins, 2.5mm pitch)	Connector housing: JST EHR-4 Contacts: JST SEH-001T-P0.6 Wire: 0.33mm ² , AWG 22
Serial communication Connector	JST B5B-PH-K-S (JST PH series, 5pins, 2mm pitch)	Connector housing: JST PHR-5 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
Multi-purpose I/O Connector	JST B8B-PH-K-S (JST PH series, 8pins, 2mm pitch)	Connector housing: JST PHR-8 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
Step/Direction Connector	JST B4B-PH-K-S (JST EH series, 4pins, 2mm pitch)	Connector housing: JST PHR-4 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
Encoder Connector	JST B5B-PH-K-S (JST EH series, 5pins, 2mm pitch)	Connector housing: JST PHR-5 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
Motor Connector	JST B4B-EH-A (JST PH series, 4pins, 2.5mm pitch)	Connector housing: JST EHR-4 Contacts: JST SEH-001T-P0.6 Wire: 0.33mm ² , AWG 22
Mini-USB Connector	Molex 500075-1517 Mini USB Type B vertical receptacle	Any standard mini-USB plug

Power Connector

This PANdrive offers separate power supply inputs for digital logic (pin 2) and driver/power stage (pin 1). Both supply inputs use common ground connections (pin 4). This way, power supply for the driver stage may be switched off while still maintaining position and status information when keeping digital logic supply active. Due to internal diode the digital logic supply has to be equal or higher than the driver/power stage supply. Otherwise the diode between driver/power stage supply and digital logic supply might short the separate supplies.

+UDRIVER SUPPLY ONLY


In case power supply is provided only to the power section (pin 1) an internal diode will distribute power to the logic section. So, when separate power supplies are not required it is possible to just use pin 1 and 4 for powering the module. If so, pin 2 (logic supply) and pin 3 (/SHUTDOWN input) can be connected together in order to enable the driver stage.

ENABLING THE DRIVER STAGE

Connect /SHUTDOWN input to +UDriver or +ULogic in order to activate the driver stage. Leaving this input open or connecting it to ground will disable driver stage.

A 4-pin JST EH series B4B-EH connector is used as power connector on-board.

Table 3.2 Connector for power supply

	Pin	Label	Description
	1	+VDriver	Module + driver stage power supply input
	2	+VLogic	(Optional) separate digital logic power supply input
	3	/SHUTDOWN	Shutdown input. Connect this input to +V _{Driver} or +V _{Logic} in order to activate driver stage. Leaving this input open or connecting it to ground
			will disable driver stage
	4	GND	Module ground (power supply and signal ground)



Power Supply



For proper operation care has to be taken with regard to the power supply concept and design. Due to space restrictions the TMCM-1160 module includes about 20 μF / 100 V of supply filter capacitors. These are ceramic capacitors which have been selected for high reliability and long life time.

HINTS FOR POWER SUPPLY CABLES

- Keep power supply cables as short as possible.
- Use large diameters for power supply cables.

CAUTION!

	<p>Add external power supply capacitors!</p> <p>It is recommended to connect an electrolytic capacitor of significant size (e.g. 2200 μF / 63 V) to the power supply lines next to the PD-1160 especially if the distance to the power supply is large (i.e. more than 2-3m)!</p> <p>μF</p> <p>Rule of thumb for size of electrolytic capacitor: $c = 1000 \times \text{IMOT}$</p> <p>A</p> <p>In addition to power stabilization (buffer) and filtering this added capacitor will also reduce any voltage spikes which might otherwise occur from a combination of high inductance power supply wires and the ceramic capacitors. In addition it will limit slew-rate of power supply voltage at the module. The low ESR of ceramic-only filter capacitors may cause stability problems with some switching power supplies.</p>
	<p>Do not connect or disconnect motor during operation!</p> <p>Motor cable and motor inductivity might lead to voltage spikes when the motor is disconnected / connected while energized. These voltage spikes might exceed voltage limits of the driver MOSFETs</p>

	<p>and might permanently damage them. Therefore, always disconnect power supply before connecting / disconnecting the motor.</p>
	<p>Keep the power supply voltage below the upper limit of 51V!</p> <p>Otherwise the driver electronics will seriously be damaged! Especially, when the selected operating voltage is near the upper limit a regulated power supply is highly recommended. Please see also chapter Fehler! Verweisquelle konnte nicht gefunden werden.Fehler! Verweisquelle konnte nicht gefunden werden. (operating values).</p>
	<p>There is no reverse polarity protection!</p> <p>The module will short any reversed supply voltage due to internal diodes of the driver transistors.</p>


Serial Communication Connector

The module supports RS485 and CAN communication via this connector.

CAN interface will be de-activated in case USB is connected due to internal sharing of hardware resources.

A 2mm pitch 5-pin JST B5B-PH-K connector is used for serial communication.

Table 3.3 Connector for serial communication

	Pin	Label	Description
	1	CAN_H	CAN bus signal (dominant high)
	2	CAN_L	CAN bus signal (dominant low)
	3	GND	Module ground (system and signal ground)
	4	RS485+	RS485 bus signal (non inverted)
	5	RS485-	RS485 bus signal (inverted)

RS485

For remote control and communication with a host system the PD-1160 provides a two wire RS485 bus interface. For proper operation the following items should be taken into account when setting up an RS485 network:

1. BUS STRUCTURE:

The network topology should follow a bus structure as closely as possible. That is, the connection between each node and the bus itself should be as short as possible. Basically, it should be short compared to the length of the bus.

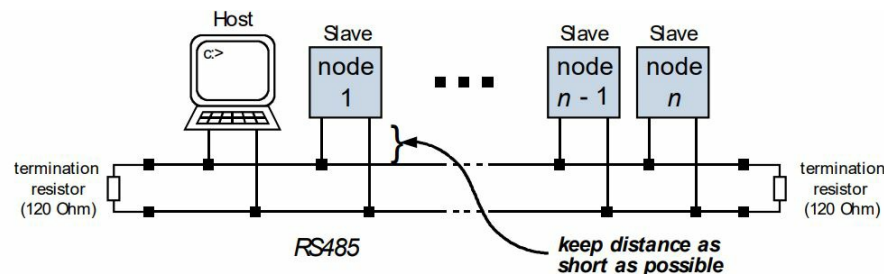


Figure 6.4: Bus structure

2. BUS TERMINATION:

Especially for longer busses and/or multiple nodes connected to the bus and/or high communication speeds, the bus should be properly terminated at both ends. The PD-1160 does offer on-board termination resistors which can be activated with the help of a jumper. The jumper has to be removed for units not connected to one end of the bus!

3. NUMBER OF NODES:

The RS485 electrical interface standard (EIA-485) allows up to 32 nodes to be connected to a single bus. The bus transceiver used on the PD-1160 units (SN65HVD485ED) has 1/2 of the standard bus load and allows a maximum of 64 units to be connected to a single RS485 bus.

4. NO FLOATING BUS LINES:

Avoid floating bus lines while neither the host/master nor one of the slaves along the bus line is transmitting data (all bus nodes switched to receive mode). Floating bus lines may lead to communication errors. In order to ensure valid signals on the bus it is recommended to use a resistor network connecting both bus lines to well defined logic levels. In contrast to the termination resistors this network is normally required just once per bus. Certain RS485 interface converters available for PCs already include these additional resistors (e.g. USB-2-485).

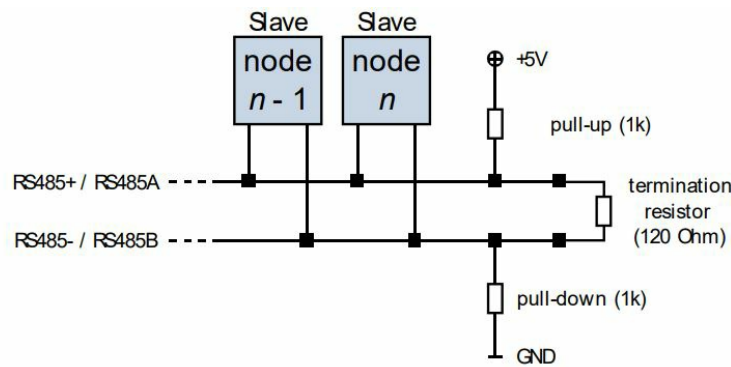


Figure 3.5 Bus lines with resistor network

CAN

For remote control and communication with a host system the PD-1160 provides a CAN bus interface. Please note that the CAN interface is not available in case USB is connected. For proper operation the following items should be taken into account when setting up a CAN network:

1. BUS STRUCTURE:

The network topology should follow a bus structure as closely as possible. That is, the connection between each node and the bus itself should be as short as possible. Basically, it should be short compared to the length of the bus.

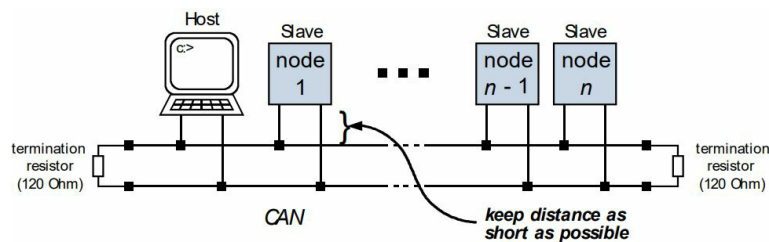


Figure 3.6 CAN bus structure

2. BUS TERMINATION:

Especially for longer busses and/or multiple nodes connected to the bus and/or high communication speeds, the bus should be properly terminated at both ends. The PD-1160 does offer on-board termination resistors which can be activated with the help of a jumper (see chapter 7). The jumper has to be removed for units not connected to one end of the bus!


3. NUMBER OF NODES:

The bus transceiver used on the PD-1160 units (TJA1050T or similar) supports at least 110 nodes under optimum conditions. Practically achievable number of nodes per CAN bus highly depends on bus length (longer bus -> less nodes) and communication speed (higher speed -> less nodes).

Multipurpose I/O Connector

A 2mm pitch 8-pin JST B8B-PH-K connector is used for connecting general purpose inputs, home and stop switches and outputs to the unit:

Table 3.4 Multipurpose I/O connector

	Pin	Label	Description
	1	OUT_0	General purpose output, open drain (max. 1A) Integrated freewheeling diode connected to +V _{Logic}
	2	OUT_1	General purpose output, open drain (max. 1A) Integrated freewheeling diode connected to +V _{Logic}
	3	IN_0	General purpose input (analog and digital), +24V compatible Resolution when used as analog input: 12bit (0..4095)
	4	IN_1	General purpose input (analog and digital), +24V compatible Resolution when used as analog input: 12bit (0..4095)
	5	STOP_L	Left stop switch input (digital input), +24V compatible, programmable internal pull-up to +5V
	6	STOP_R	Right stop switch input (digital input), +24V compatible, programmable internal pull-up to +5V
	7	HOME	Home switch input (digital input), +24V compatible, programmable internal pull-up to +5V
	8	GND	Module ground (system and signal ground)

Note:

All inputs have resistor based voltage dividers with protection diodes. These resistors also ensure a valid GND level when left unconnected.

For reference switch inputs (STOP_L, STOP_R, HOME) a 1k pull-up resistor to +5V can be activated (separately for each input). Then these inputs have a default (unconnected) logic level of “1” and an external switch to GND can be connected.

1. Digital Inputs STOP_L, STOP_R, and HOME

The eight pin connector of the PD-1160 provides three reference switch digital inputs STOP_L, STOP_R and HOME.

All three inputs accept up to +24 V input signals. They are protected against these higher voltages using voltage resistor dividers together with limiting diodes against voltages below 0 V (GND) and above +3.3 V DC.

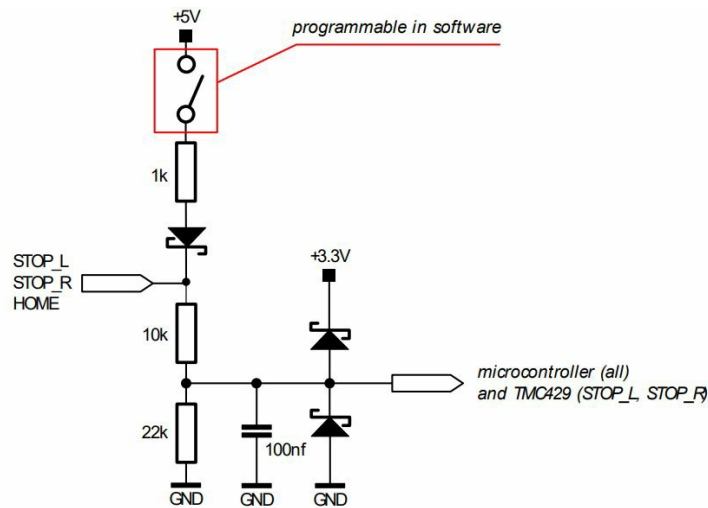


Figure 3.6 STOP_L, STOP_R and HOME inputs (simplified input circuit)

All three digital inputs are connected to the on-board processor and can be used as general purpose digital inputs!

2. General Purpose Inputs IN_0 and IN_1

The eight pin connector of the PD-1160 provides two general purpose inputs which may be used as either digital or analog inputs.

GENERAL PURPOSE INPUTS AS ANALOG INPUTS

As analog input they offer a full scale input range of 0... +10 V with a resolution of the internal analog-to-digital converter of the microcontroller of 12bit (0... 4095). The input is protected against higher voltages up to +24 V using voltage resistor dividers together with limiting diodes against voltages below 0 V (GND) and above +3.3 V DC.

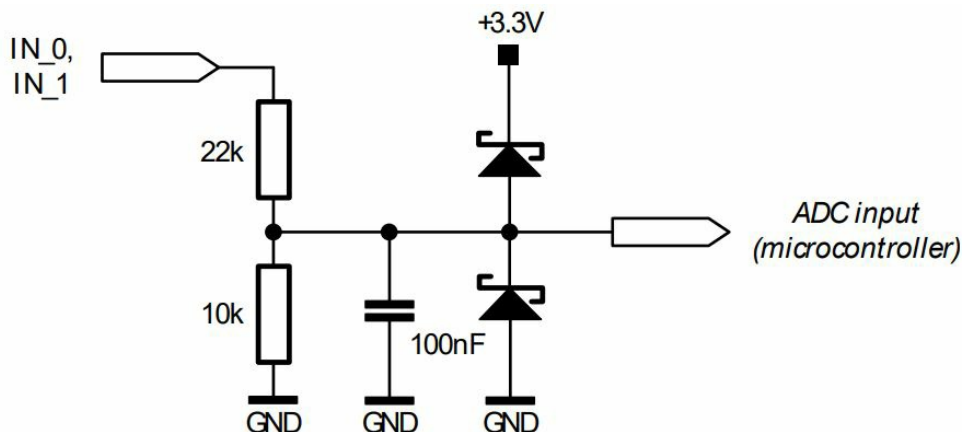


Figure 3.7 General purpose inputs (simplified input circuit)

3. Outputs OUT_0, OUT_1

The eight pin connector of the PD-1160 offers two general purpose outputs OUT_0 and OUT_1. These two outputs are open-drain outputs and can sink up to 1 A each. The outputs of the N-channel MOSFET transistors are connected to freewheeling diodes each for protection against voltage spikes especially from inductive loads (relays etc.) above supply voltage.

- In case free-wheeling diodes are connected to VDD supply voltage:
None of the two outputs should be connected to any voltage above supply voltage of the module.
- It is recommended to connect +Vlogic of the power connector to the power supply output in case the outputs OUT_0/1 are used to switch inductive loads (e.g. relays etc.).

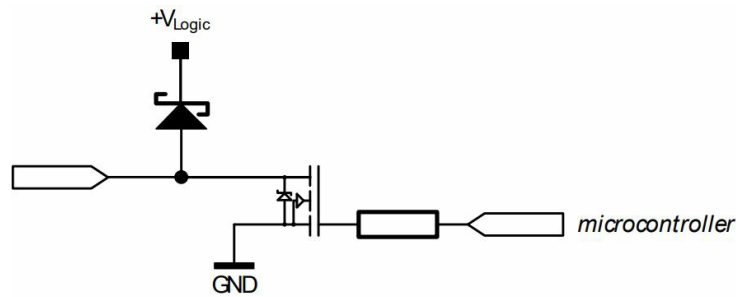


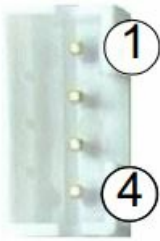
Figure 3.8 General purpose outputs

Step/Direction Connector

A 2mm pitch 4-pin JST B4B-PH-K connector is used for step and direction input signals. This is an option in case the on-board controller is used for configuration of the driver stage, only. The Step/Direction input is optically isolated and will allow direct control of the driver stage.

Please do not attach any signal to this input if the on-board motion controller is used! Otherwise step or direction signal connected here might interfere with signals generated on-board.

Table 3.4 Connector for step/direction signals

	Pin	Label	Description
	1	COM	Common supply for the opto-coupler inputs (+5V... +24V)
	2	ENABLE	Enable signal input (function depends on firmware)
	3	STEP	Step signal input (connected to step input of TMC262 driver IC)
	4	DIRECTION	Direction signal (connected to direction input of TMC262 driver IC)

Step / Direction / Enable Inputs

The inputs Step, Direction and Enable are electrically (optically) isolated from the power supply and all other signals of the module. These inputs have one common reference input COMMON.

The COMMON input should be connected to a positive supply voltage between +5 V and +24 V. Step / Direction / Enable signals might be driven either by open-collector / open-drain outputs or by push-pull outputs.

In case of push-pull outputs the COMMON supply voltage should be equal / similar to the high signal voltage level of the push-pull drivers.

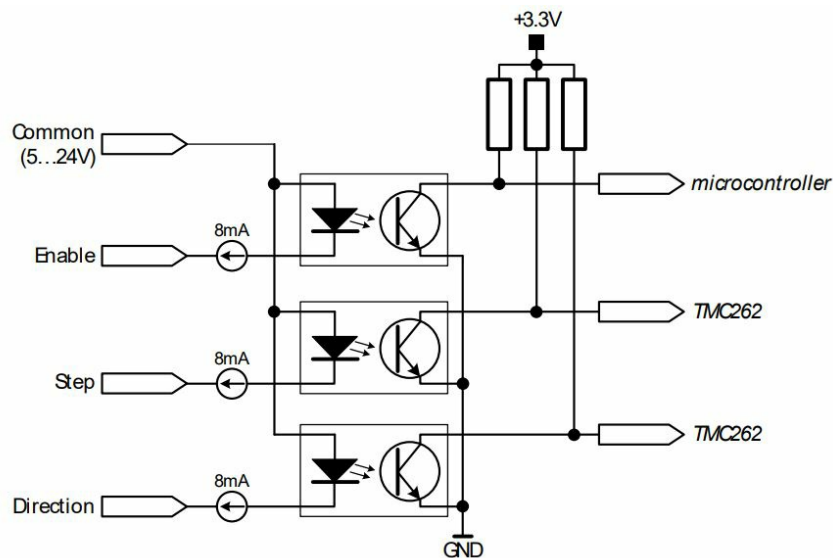



Figure 3.9 Step / Direction / Enable inputs

Encoder Connector

The module supports an external incremental a/b/n encoder via this connector. The external encoder may be used in addition or as an alternative to the internal / on-board sensOstep encoder.

A 2mm pitch 5-pin JST B5B-PH-K connector is used for connecting an external encoder with TTL (+5 V push-pull) or open-collector signals directly:

Table 3.5 Connector for an external incremental encoder

	Pin	Label	Description
	1	GND	Module ground (system and signal ground)
	2	+5V	+5V supply output for external encoder circuit (100 mA max.)
	3	ENC_A	Encoder a channel input (internal pull-up)
	4	ENC_B	Encoder b channel input (internal pull-up)
	5	ENC_N	Optional encoder n / index channel input (internal pull-up)

Encoder Inputs

The PD-1160 offers a dedicated encoder input for incremental a/b encoders with optional n / index-channel. Encoders with +5 V push-pull (TTL) signals or open-collector signals (on-board pull-ups) might be connected directly.

This connector offers a +5 V supply output for supply of the encoder circuit. Up to 100mA might be drawn from this output.

Connecting an external encoder is an option. An external encoder might be used in addition or as alternative to the internal sensOstep encoder.

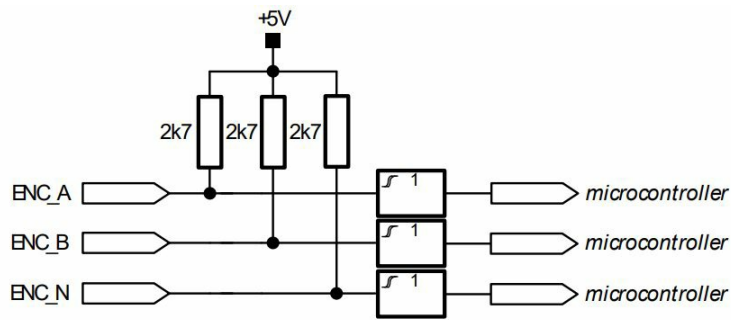
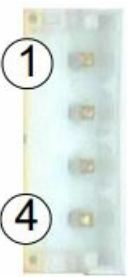


Figure 3.9 Encoder a/b/n inputs

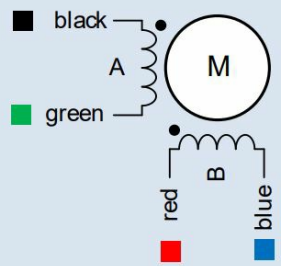
Motor Connector

Both motor coil windings (bipolar stepper motor) are connected to the motor connector.

Figure 3.4 Motor connector

	Pin	Label	Description
	1	OA1	Motor coil A
	2	OA2	Motor coil A
	3	OB1	Motor coil B
	4	OB2	Motor coil B

TMCM-1160		Q5718 motor	
Motor connector pin	Cable colour	Coil	Description
1	Black	A	Motor coil A pin 1
2	Green	A-	Motor coil A pin 2
3	Red	B	Motor coil B pin 1
4	Blue	B-	Motor coil B pin 2



CAUTION!

Keep the electronics free of (metal) particles!

The integrated sensOstep™ encoder uses a magnet at the end of the motor axis in order to monitor position. The magnet naturally attracts especially tiny metal particles. These particles might be held on the top side of the PCB and even worse – start moving in accordance with the rotating magnetic field as soon as the motor starts moving. This might lead to shorts of electronic contacts / wires on the board and totally erratic behavior of the module! Use compressed air for cleaning the module if necessary.


Mini-USB Connector

A 5-pin standard mini-USB connector is available on board. This module supports USB 2.0 full-speed (12Mbit/s) connections.

Please note:

- On-board digital core logic (mainly processor and EEPROM) will be powered via USB in case no other supply is connected. The USB connection might be used to set parameters / download TMCL programs or perform firmware updates while power supply for the module (and the rest of the machine) has been switched off or is not connected.
- CAN interface will be de-activated as soon as USB is connected due to internal sharing of hardware resources.

Table 3.6 Mini USB connector

	Pin	Label	Description
	1	VBUS	+5V supply from host
	2	D-	Data –
	3	D+	Data +
	4	ID	Not connected
	5	GND	Module ground (system and signal ground)

For remote control and communication with a host system the PD-1160 provides a USB 2.0 full-speed (12Mbit/s) interface (mini-USB connector). As soon as a USB-Host is connected the module will accept commands via USB.

USB BUS POWERED OPERATION MODE

The PD-1160 supports both, USB self powered operation (when an external power is supplied via the power supply connector) and USB bus powered operation, (no external power supply via power supply connector). On-board digital core logic will be powered via USB in case no other supply is connected (USB bus powered operation). The digital core logic comprehends the microcontroller itself and also the EEPROM. The USB bus powered operation mode has been implemented to enable configuration, parameter settings, read-outs, firmware updates, etc. by just connecting an USB cable between module and host PC. No additional cabling or external devices (e.g. power supply) are required.

Please note that the module might draw current from the USB +5 V bus supply even in USB self powered operation depending on the voltage level of this supply.

Motor movements are not possible in this operation mode. Therefore, connect the power connector and change to USB self powered operation mode.

Jumpers

Most settings of the board are done through the software. Nevertheless, two jumpers are available for configuration.

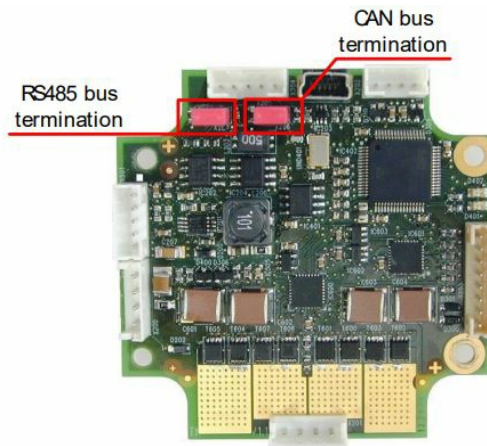


Figure 4.1 RS485 and CAN bus termination

1. RS485 Bus Termination

The board includes a 120 Ohm resistor for proper bus termination of the RS485 interface. When this jumper is closed, the resistor will be placed between the two differential bus lines RS485+ and RS485-.

2. CAN Bus Termination

The board includes a 120 Ohm resistor for proper bus termination of the CAN interface. When this jumper is closed, the resistor will be placed between the two differential bus lines CAN_H and CAN_L.

Reset to Factory Defaults

It is possible to reset the PD-1160 to factory default settings without establishing a communication link. This might be helpful in case communication parameters of the preferred interface have been set to unknown values or got accidentally lost.

For this procedure two pads on the bottom side of the board have to be shorted (see Figure 5.1).

Short these two pads.



Figure 5.1 Reset to factory default settings

PERFORM THE FOLLOWING STEPS:

1. Power supply off and USB cable disconnected
2. Short two pads as marked in Figure 5.1
3. Power up board (power via USB is sufficient for this purpose)

4. Wait until the on-board red and green LEDs start flashing fast (this might take a while)
5. Power-off board (disconnect USB cable)
6. Remove short between pads
7. After switching on power-supply/connecting USB cable all permanent settings have been restored to factory defaults

On-board LEDs

The board offers two LEDs in order to indicate board status. The function of both LEDs is dependent on the firmware version. With standard TMCL firmware the green LED should be flashing during operation and the red LED should be off.

When there is no valid firmware programmed into the board or during firmware update the red and green LEDs are permanently on.

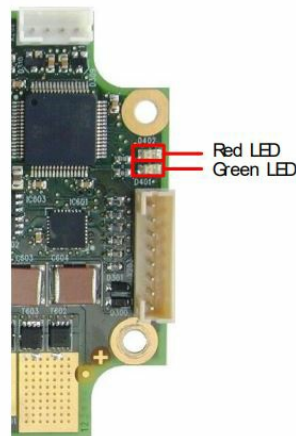


Figure 6.1 on-board LEDs

BEHAVIOR OF LEDS WITH STANDARD TMCL FIRMWARE

Status	Label	Description
Heartbeat	Run	The green LED flashes during operation.
Error	Error	The red LED lights up if an error occurs.

Operational Ratings

The operational ratings show the intended or the characteristic ranges and should be used as design values. In no case shall the maximum values be exceeded!

GENERAL OPERATIONAL RATINGS OF THE MODULE

Table 7.1 General operational ratings of module

Symbol	Parameter	Min	Typ	Max	Unit
+VDriver / +V Logic	Power supply voltage for operation	9	12, 24, 48	51	V DC *)
IUSB	USB supply current when USB bus powered (+5 V USB supply)		70		mA
ICOIL_peak	Motor coil current for sine wave peak (chopper regulated, adjustable via software)	0		4	A
ICOIL_RMS	Continuous motor current (RMS)	0		2.8	A
ISUPPLY	Power supply current		<< ICOIL	$1.4 \cdot I_{COIL}$	A
TENV	Environment temperature at +48V supply and rated current (100% duty-cycle, no forced cooling required)			40	°C
TENV	Environment temperature at +24V supply and rated current (100% duty-cycle, no forced cooling required)			50	°C

Attention: due to the internal diode between VDriver and VLogic VLogic should be always equal or higher than VDriver.

GENERAL OPERATIONAL RATINGS OF STEP/DIRECTION INPUT

Table 7.2 Operational ratings of Step/Dir input

Symbol	Parameter	Min	Type	Max	Unit
VCOMMON	Supply voltage for common supply input for step, direction and enable (inputs have negative logic)		5... 24	27	V
VSTEP/DIR/ENABLE_ON	Signal voltage at step, direction and enable input (active, opto-coupler on)	3.5	4.5... 24	30	V
VSTEP/DIR/ENABLE_OFF	Signal voltage at step, direction and enable input (inactive, opto-coupler off)	-5.5	0	2	V
VSTEP/DIR/ENABLE_ON	Opto-coupler current when switched on (internally regulated)		6... 8		mA
fSTEP	Step frequency			1 *)	MHz

Maximum frequency for +5 V TTL level step signals is with 50 % duty cycle.

OPERATIONAL RATINGS OF THE GENERAL PURPOSE INPUTS/OUTPUTS

Table 7.3 Operational ratings of the general purpose inputs/outputs

Symbol	Parameter	Min	Type	Max	Unit
VSTOP_L/R/HOME	Input voltage for STOP_L/R/HOME	0		24	V
VSTOP_L/R/HOME_L	Low level voltage for STOP_L/R/HOME	0		1.3	V
VSTOPL/R/HOME_H	High level voltage for STOP_L/R/HOME (internal programmable 1k pull-up to +5V)	3		24	V
VIN_0/1_digital	Input voltage for IN_0 and IN_1 when used as digital input	0		24	V
VIN_0/1_analog	Full range input voltage for IN_0 and IN_1 when used as analog input	0		10	V
VIN_0/1_L	Low level voltage for IN_0 and IN_1 when used as digital input (internal 10k pull-down)	0		1.3 *)	V
VIN_0/1_H	High level voltage for IN_0 and IN_1 when used as digital input	3 *)		24	V
VOOUT_0/1	Voltage at open collector output	0		VLOGIC + 0.5 **)	V
IOOUT_0/1	Output sink current at open collector outputs			1	A

- this voltage is programmable (internal 12bit ADC)
- limited to module supply voltage + 0.5V due to integrated freewheeling diode between general purpose output and module supply voltage

Torque Curves

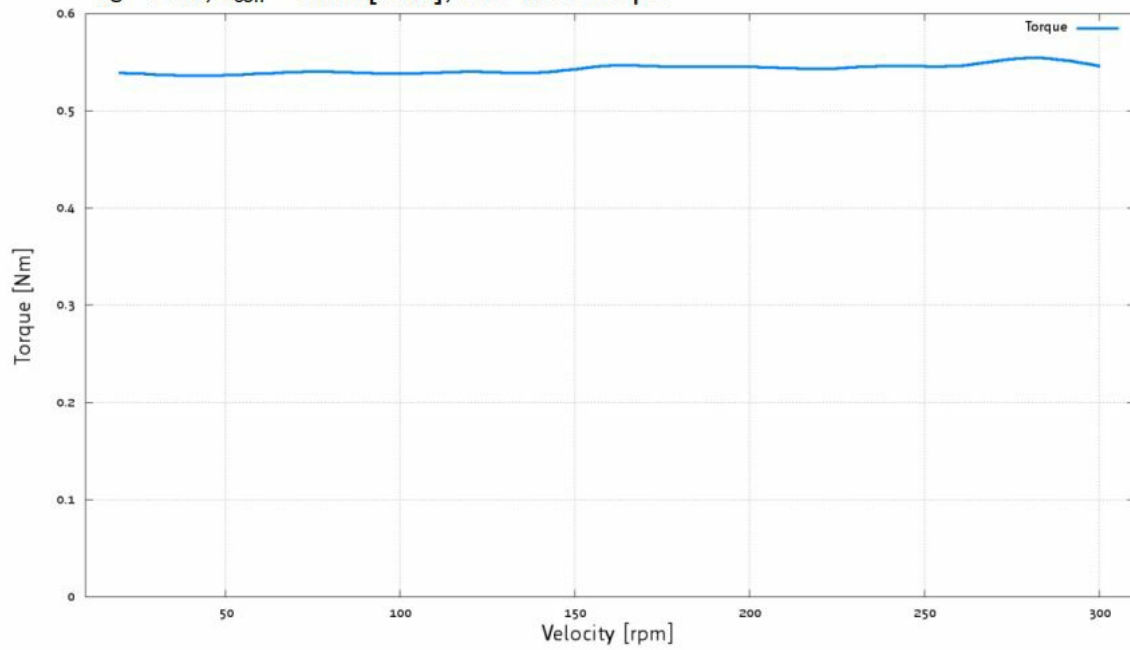
TRINAMIC offers the TMCM-1160 in combination with two different stepper motor series: QSH5718 and QSH6018. The following paragraphs will show you the curves of each PANdrive.

Curves of PD57-1160

PD57-1-1160 Torque Curves

TMC1160 – QSH5718-41-28-055 – Torque versus Velocity

$V_S = 24V$; $I_{coil} = 2.8A$ [RMS]; 256 Microsteps



TMC1160 – QSH5718-41-28-055 – Torque versus Velocity

$V_S = 24V$; $I_{coil} = 2.8A$ [RMS]; 256 Microsteps

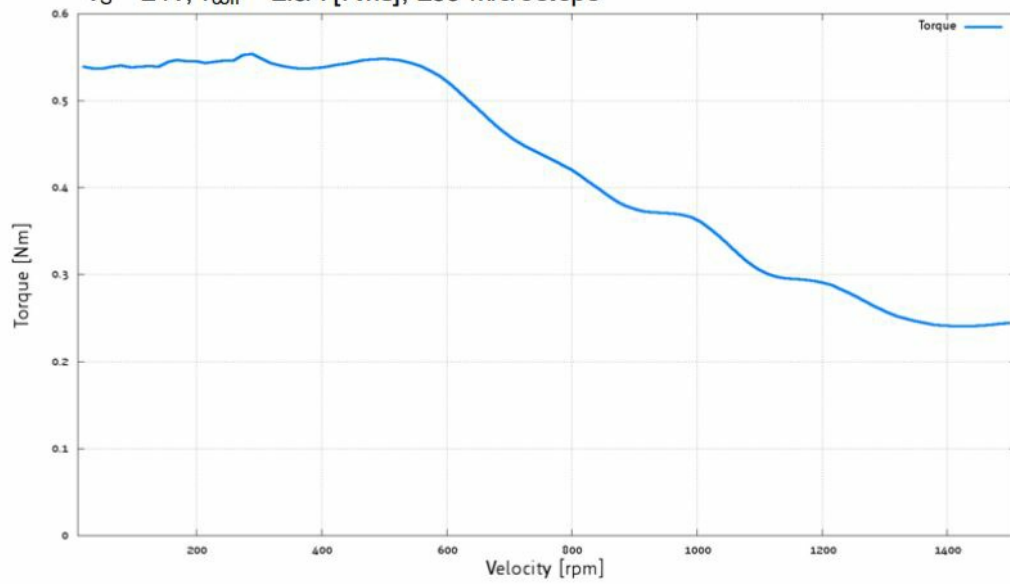


Figure 8.1 Torque curves PD57-1-1160, $V_S = 24 V$ DC

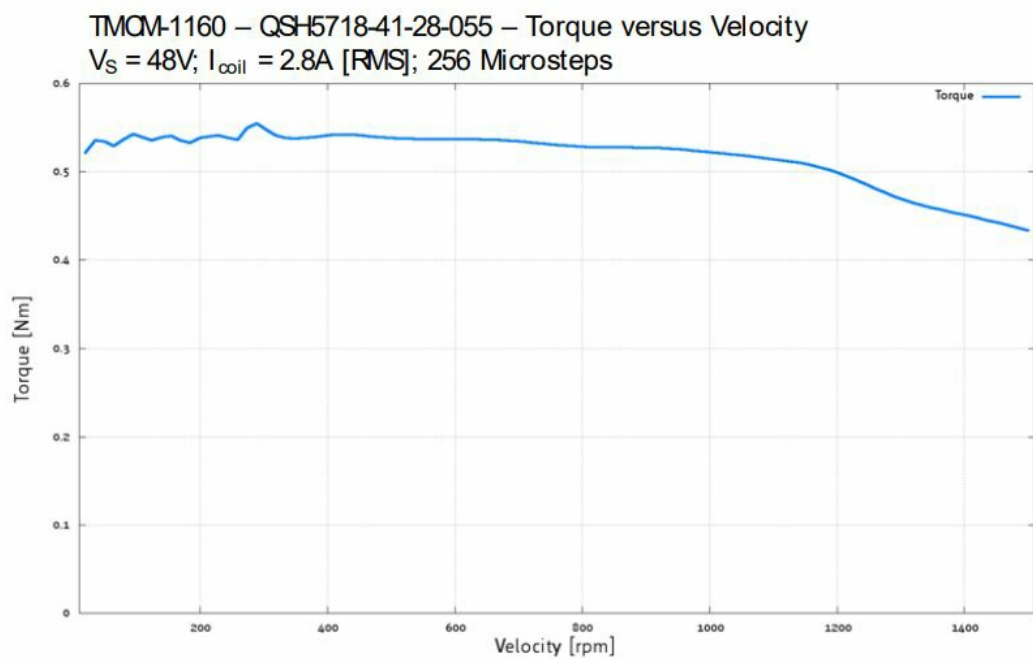
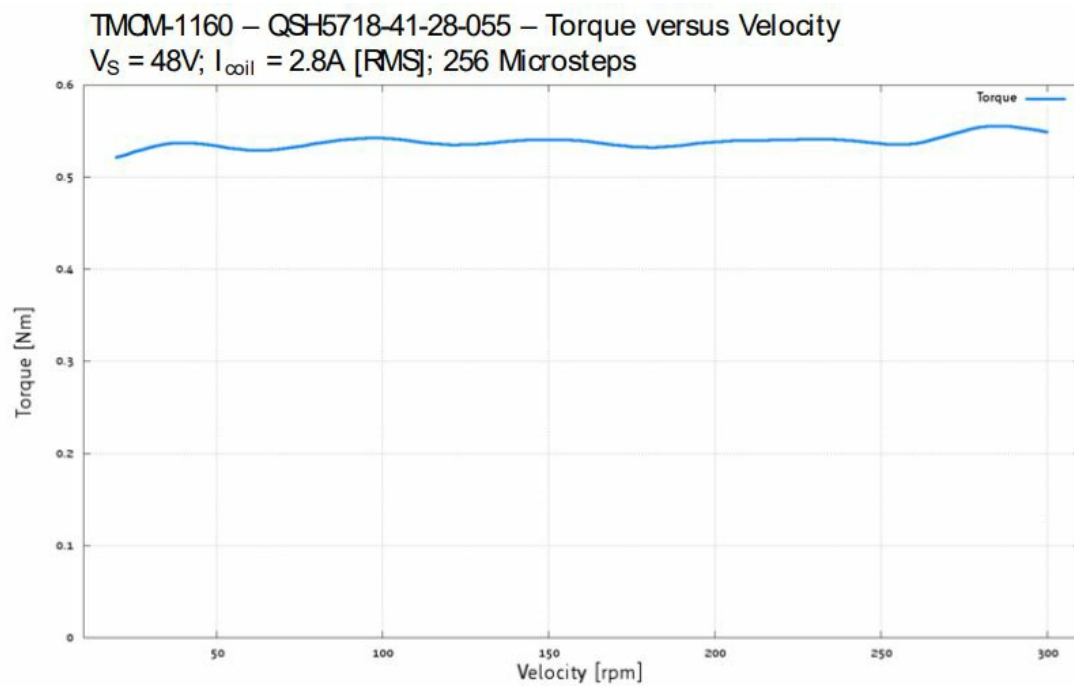
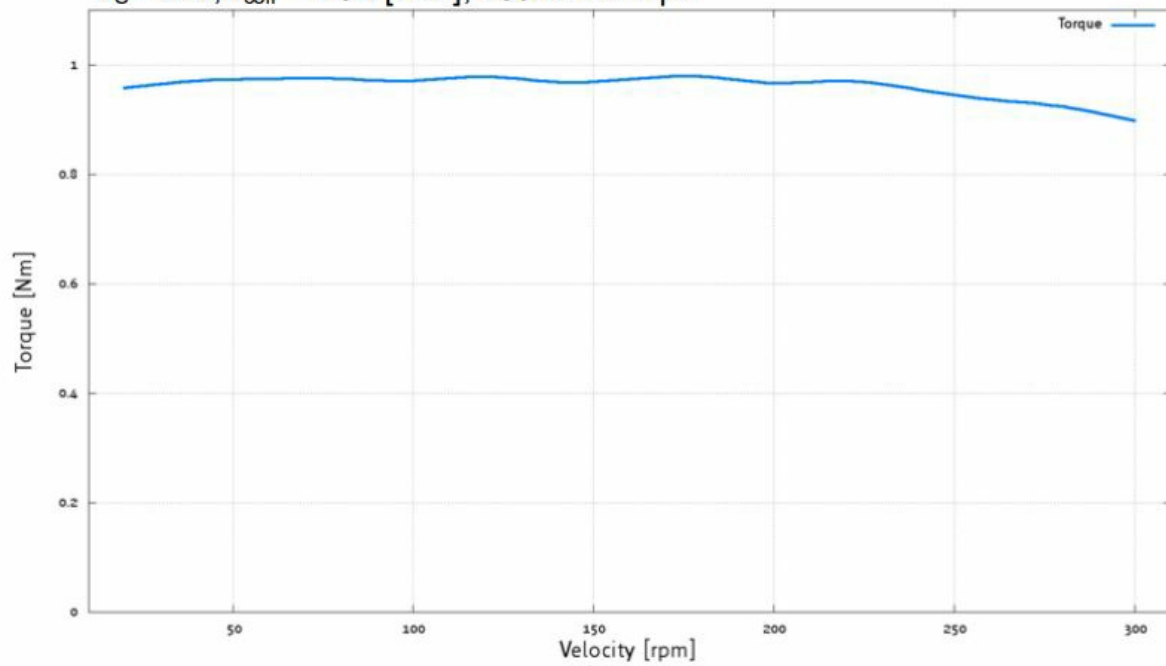


Figure 8.2 Torque curves PD57-1-1160, $V_S = 48$ V DC

PD57-2-1160 Torque Curves

TMC1160 – QSH5718-51-28-101 – Torque versus Velocity

$V_S = 24V$; $I_{coil} = 2.8A$ [RMS]; 256 Microsteps



TMC1160 – QSH5718-51-28-101 – Torque versus Velocity

$V_S = 24V$; $I_{coil} = 2.8A$ [RMS]; 256 Microsteps

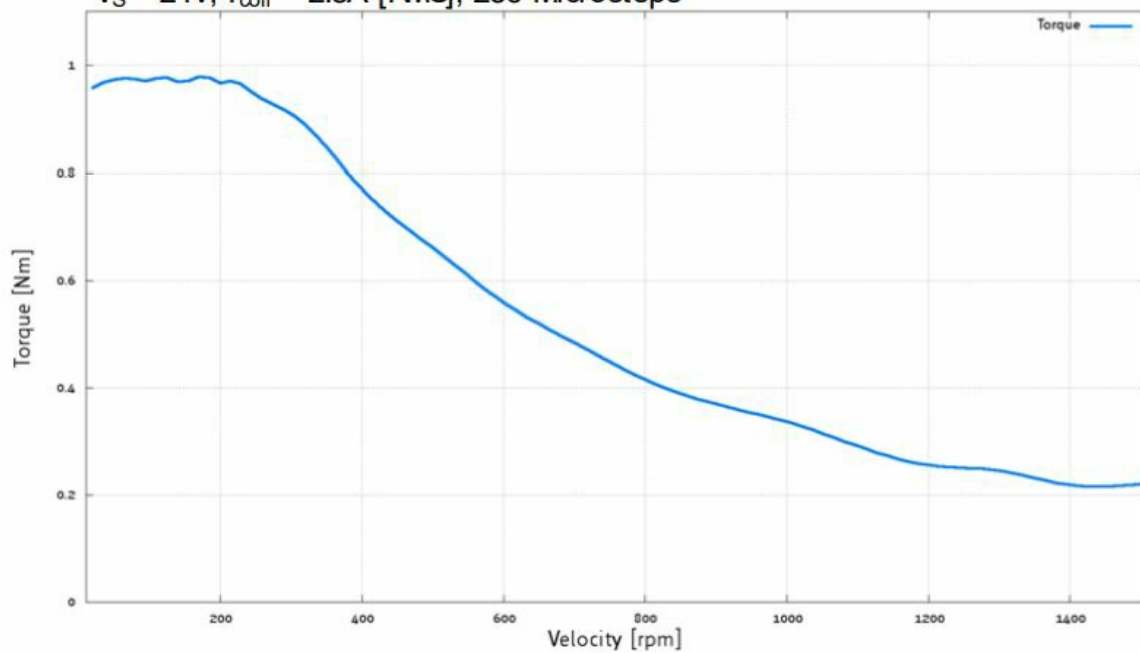
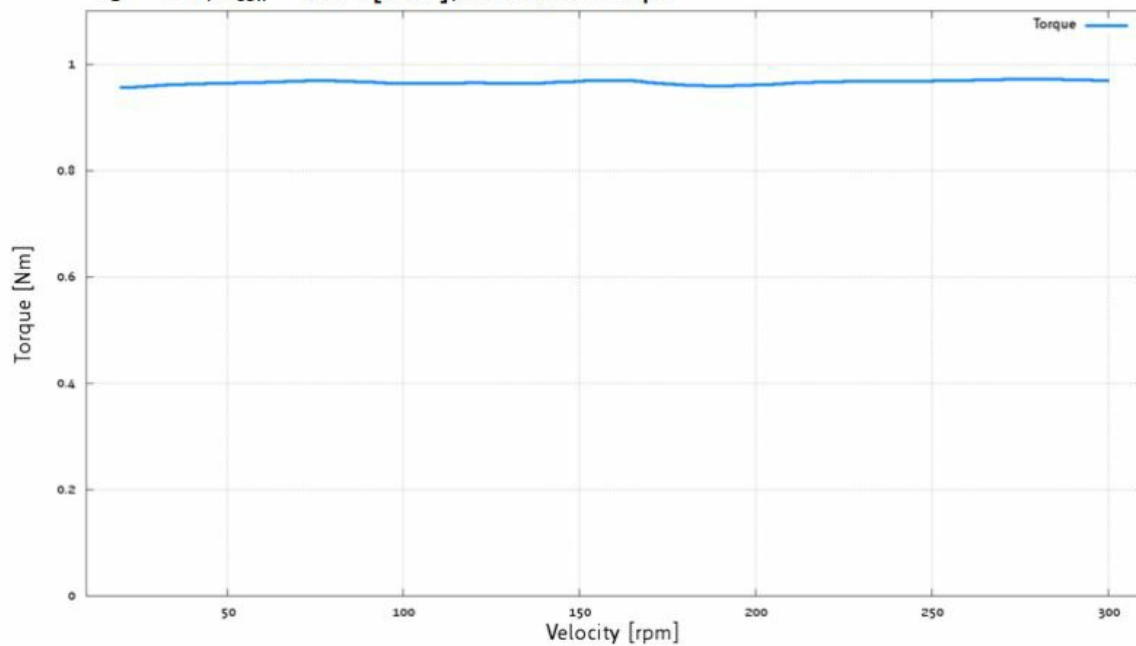


Figure 8.3 Torque curves PD57-2-1160, $V_S = 24 V$ DC

TMCM-1160 – QSH5718-51-28-101 – Torque versus Velocity
 $V_S = 48V$; $I_{coil} = 2.8A$ [RMS]; 256 Microsteps



TMCM-1160 – QSH5718-51-28-101 – Torque versus Velocity
 $V_S = 48V$; $I_{coil} = 2.8A$ [RMS]; 256 Microsteps

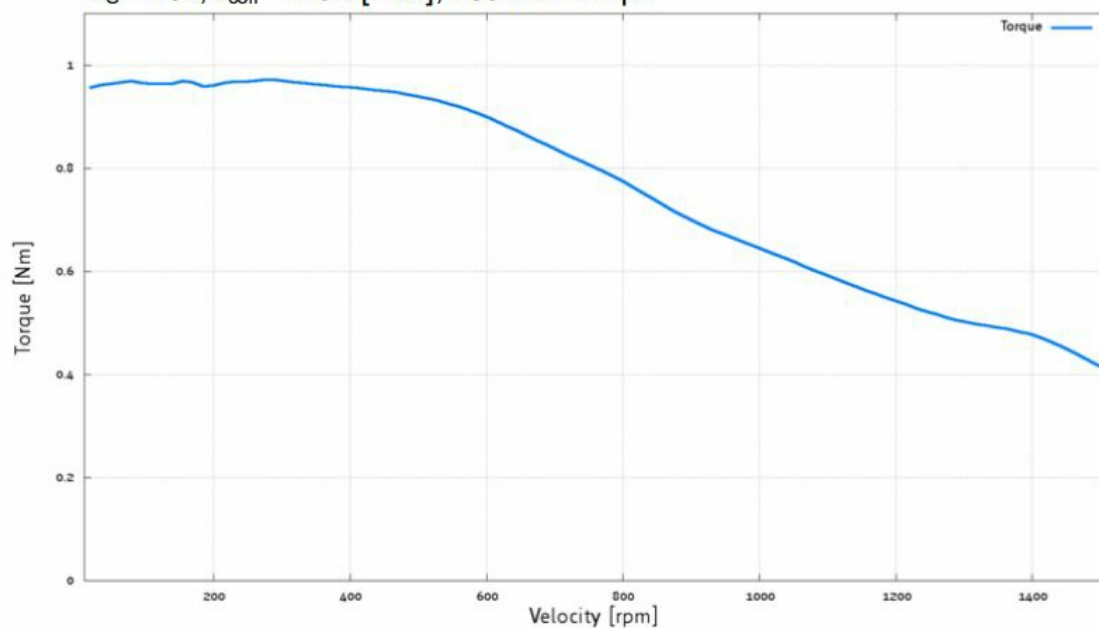


Figure 8.4 Torque curves PD57-2-1160, $V_S = 48$ V DC

Curves of PD60-1160

PD60-3-1160 Torque Curves

TMCM-1160 – QSH6018-65-28-210 – Torque versus Velocity

$V_S = 24V$; $I_{coil} = 2.8A$ [RMS]

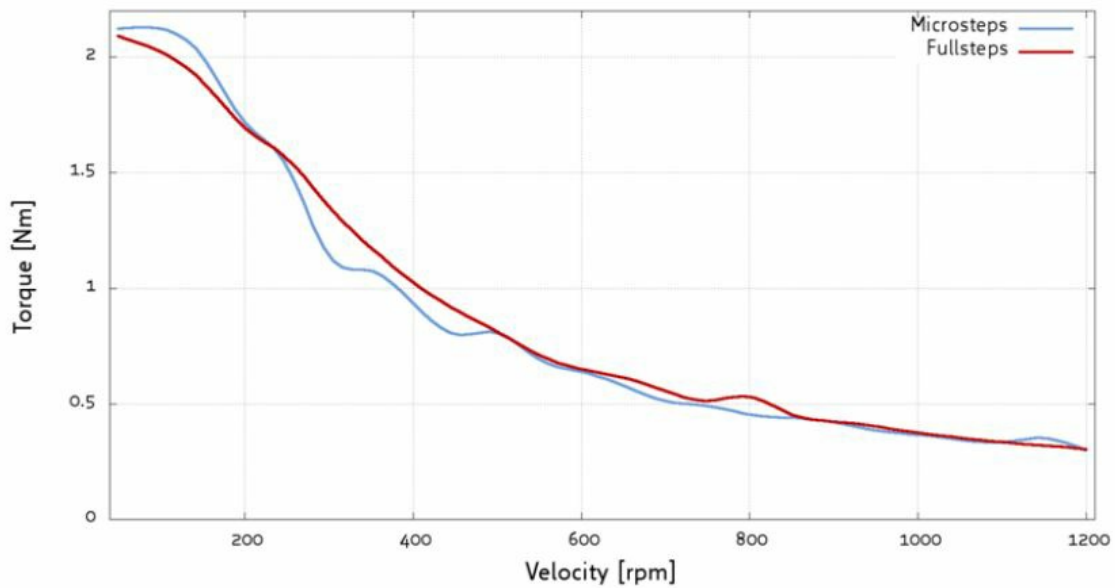


Figure 8.5 Torque curves PD60-3-1160, $V_S = 24$ V DC

TMCM-1160 – QSH6018-65-28-210 – Torque versus Velocity

$V_S = 48V$; $I_{coil} = 2.8A$ [RMS]

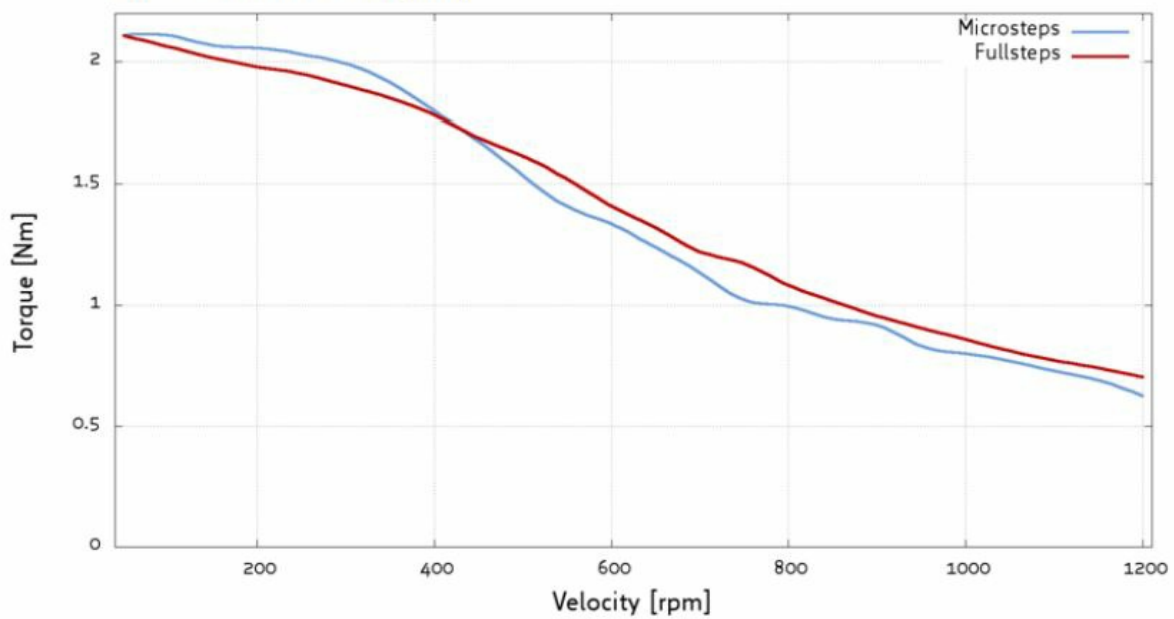


Figure 8.6 Torque curves PD60-3-1160, $V_S = 48$ V DC

PD60-4-1160 Torque Curves

TMC1160 – QSH6018-86-28-310 – Torque versus Velocity
 $V_S = 24V$; $I_{coil} = 2.8A$ [RMS]

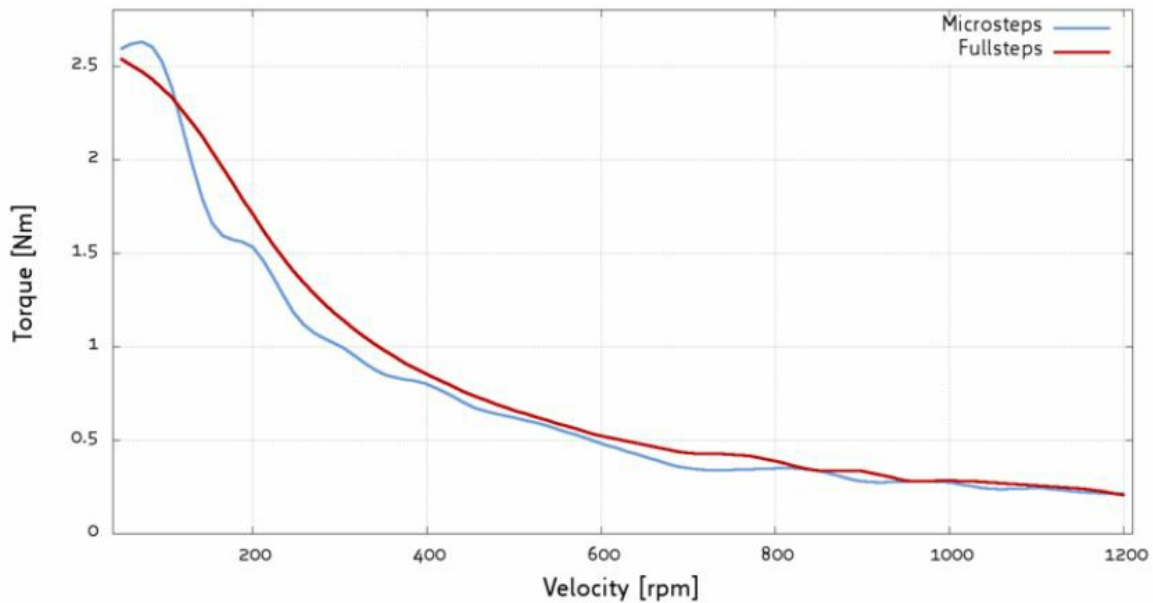


Figure 8.7 Torque curves PD60-4-1160, $V_S = 24$ V DC

TMC1160 – QSH6018-86-28-310 – Torque versus Velocity
 $V_S = 48V$; $I_{coil} = 2.8A$ [RMS]; Fullsteps

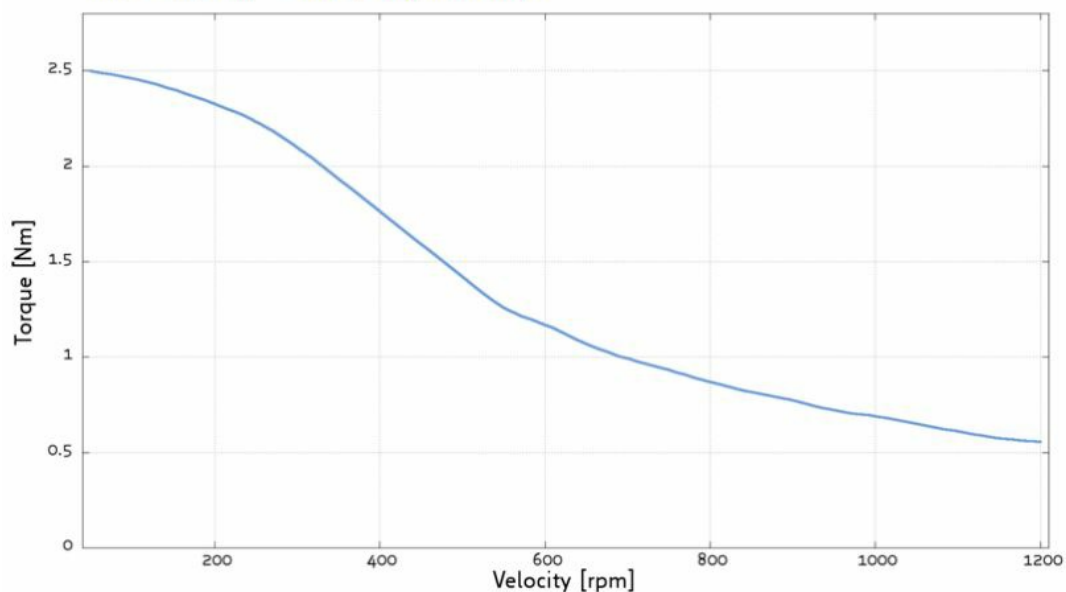


Figure 8.8 Torque curves PD60-4-1160, $V_S = 48$ V DC

Functional Description

The PD-1160 is a highly integrated mechatronic device which can be controlled via several serial interfaces. Communication traffic is kept low since all time critical operations, e.g. ramp calculations are performed on board. Common supply voltages are +12VDC / +24VDC / +48VDC. The PANdrive is designed for both: direct mode and standalone operation. Full remote control of device with feedback is possible. The firmware of the module can be updated via any of the serial interfaces.

In Figure 9.1 the main parts of the PD-1160 are shown:

- the microprocessor, which runs the TMCL operating system (connected to TMCL memory),

- the motion controller, which calculates ramps and speed profiles internally by hardware,
- the power driver with stallGuard2 and its energy efficient coolStep feature,
- the MOSFET driver stage,
- the QSH stepper motor, and
- the sensOstep encoder with resolutions of 10bit (1024 steps) per revolution.

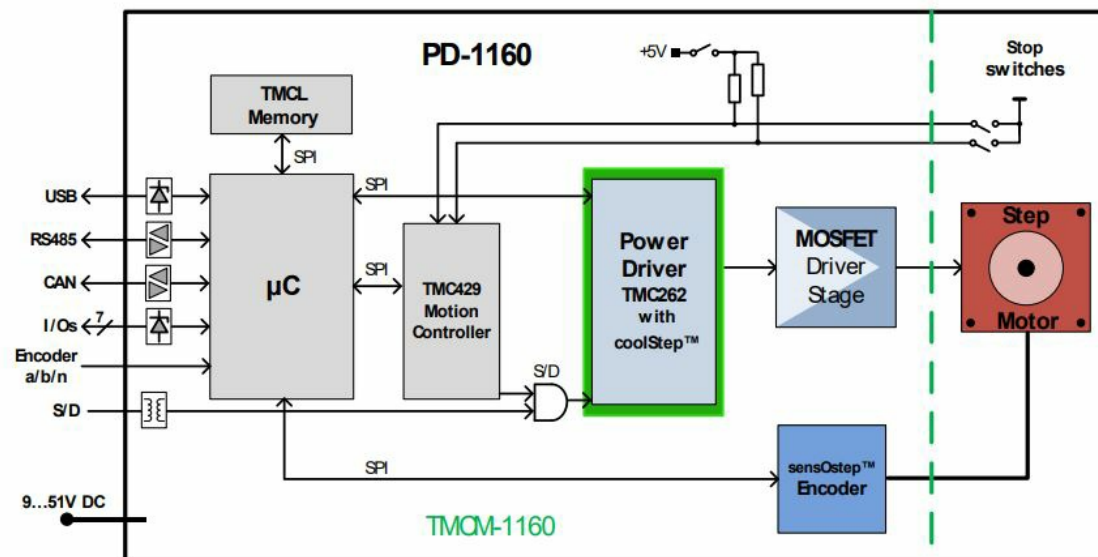


Figure 9.1 Main parts of the PD-1160

The PD-1160 comes with the PC based software development environment TMCL-IDE for the Trinamic Motion Control Language (TMCL). Using predefined TMCL high level commands like move to position a rapid and fast development of motion control applications is guaranteed.

Please refer to the PD-1160 Firmware Manual for more information about TMCL commands.

PD-1160 Operational Description

Calculation: Velocity and Acceleration vs. Microstep and Fullstep Frequency

The values of the parameters sent to the TMC429 do not have typical motor values like rotations per second as velocity. But these values can be calculated from the TMC429 parameters as shown in this section.

PARAMETERS OF TMC429

Table 10.1 TMC429 velocity parameters

Signal	Description	Range
fCLK	clock-frequency	16 MHz
velocity	–	0... 2047
a_max	maximum acceleration	0... 2047
pulse_div	divider for the velocity. The higher the value is, the less is the maximum velocity default value = 0	0... 13
ramp_div	divider for the acceleration. The higher the value is, the less is the maximum acceleration default value = 0	0... 13
Usrs	microstep-resolution (microsteps per fullstep = 2usrs)	0... 8

MICROSTEP FREQUENCY

The microstep frequency of the stepper motor is calculated with

$$usf[Hz] = \frac{f_{CLK}[Hz] \cdot velocity}{2^{pulse_div} \cdot 2048 \cdot 32} \quad \text{with usf: microstep-frequency}$$

FULLSTEP FREQUENCY

To calculate the fullstep frequency from the microstep frequency, the microstep frequency must be divided by the number of microsteps per fullstep.

$$fsf[Hz] = \frac{usf[Hz]}{2^{usrs}} \quad \text{with fsf: fullstep-frequency}$$

The change in the pulse rate per time unit (pulse frequency change per second – the acceleration a) is given by

$$a = \frac{f_{CLK}^2 \cdot a_{max}}{2^{pulse_div + ramp_div + 29}}$$

This results in acceleration in fullsteps of:

$$af = \frac{a}{2^{usrs}} \quad \text{with af: acceleration in fullsteps}$$

EXAMPLE:

Signal	value
f_CLK	16 MHz
velocity	1000
a_max	1000
pulse_div	1
ramp_div	1
usrs	6

$$msf = \frac{16 \text{ MHz} \cdot 1000}{2^1 \cdot 2048 \cdot 32} = \underline{\underline{122070.31 \text{ Hz}}}$$

$$fsf[\text{Hz}] = \frac{122070.31}{2^6} = \underline{\underline{1907.34 \text{ Hz}}}$$

$$a = \frac{(16 \text{ MHz})^2 \cdot 1000}{2^{1+1+29}} = \underline{\underline{119.21 \frac{\text{MHz}}{\text{s}}}}$$

$$af = \frac{119.21 \frac{\text{MHz}}{\text{s}}}{2^6} = \underline{\underline{1.863 \frac{\text{MHz}}{\text{s}}}}$$

CALCULATION OF THE NUMBER OF ROTATIONS

A stepper motor has e.g. 72 fullsteps per rotation

$$RPS = \frac{fsf}{\text{fullsteps per rotation}} = \frac{1907.34}{72} = 26.49$$

$$RPM = \frac{fsf \cdot 60}{\text{fullsteps per rotation}} = \frac{1907.34 \cdot 60}{72} = 1589.46$$

Life Support Policy

TRINAMIC Motion Control GmbH & Co. KG does not authorize or warrant any of its products for use in life support systems, without the specific written consent of TRINAMIC Motion Control GmbH & Co. KG.

Life support systems are equipment intended to support or sustain life, and whose failure to perform, when properly used in accordance with instructions provided, can be reasonably expected to result in personal injury or death.

© TRINAMIC Motion Control GmbH & Co. KG 2013

Information given in this data sheet is believed to be accurate and reliable. However neither responsibility is assumed for the consequences of its use nor for any infringement of patents or other rights of third parties, which may result from its use.

Specifications are subject to change without notice.

All trademarks used are property of their respective owners.

Revision History

Document Revision

Table 12.1 Document revision

Version	Date	Author	Description
		GE – Göran Eggers SD – Sonja Dwersteg	
0.91	2012-MAY-03	GE	Initial version
1.00	2012-JUN-12	SD	First complete version including the following chapters: <ul style="list-style-type: none"> – Reset to factory defaults, – LEDs
1.01	2012-JUL-30	SD	General purpose inputs corrected.
1.02	2013-JUL-08	SD	Chapter 3.2.1 updated.

Hardware Revision**Table 12.2** Hardware revision

Version	Date	Description
TMCM-1160_V10	2011-JUL-20	Initial version
TMCM-1160_V11	2012-JAN-24	– Inputs IN_0 and IN_1 can be used as analog inputs, also


References

[PD-1160 TMCL] PD-1160 TMCL Firmware Manual
[TMCL-IDE] TMCL-IDE User Manual
[QSH5718] QSH5718 Manual
[QSH5718] QSH5718 Manual

Please refer to www.trinamic.com.

Downloaded from Arrow.com.

Documents / Resources

	<p>TRINAMIC PD-1160 UNIQUE FEATURES Stepper Motor with Controller Driver [pdf] User Manual</p> <p>PD-1160 UNIQUE FEATURES Stepper Motor with Controller Driver, PD-1160, UNIQUE FEATURES Stepper Motor with Controller Driver, Motor with Controller Driver, Controller Driver, Driver</p>
---	---

References

- [▶ Trinamic Motion Control - Trinamic](#)

Manuals+.