

DG3S series

DC Servo drive

User's Manual and Installation Guide

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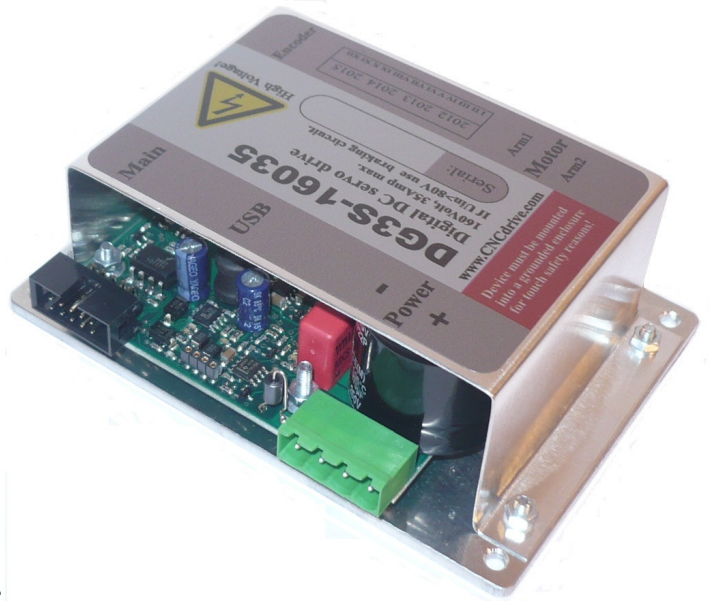
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1. Safety, policy and warranty.

1.1. Safety Notes

Please read through this documentation before operating the device. The devices can operate on low and medium DC bus Voltages the model -08020 operates upto 80VDC and the model -16035 operates upto 160VDC. Above 50VDC, the drive's metal case must be connected to safety ground for safety purpose. Above 80VDC motor supply Voltage an external braking circuit must be used on the powersupply.

Moving objects, like machine axis can be hazardous, avoid touching and keep distance from mechanic moving parts of the machine while the motor power supply is on and connected to the drives.

The device should not be used where it can cause personal injury, death or high financial loss. Never open the drive's chassis and never touch inner circuitry even if it's unpowered. Take care of power supply's correct polarity connection, wrong polarity connection of the Motor Power supply will cause permanent damage to the device.

Never disconnect the motor from the drive when power supply is connected to the drive and is under Voltage.

Do not short the motor output terminals, it may cause permanent damage to the device. The drives are in enclosure, but this metal case is not meant to protect the drive from dust and falling chips, liquid or other moisture material. Please take care to protect the drives from taint damage.

1.2. Policy

CNCdrive cannot take responsibility for any personal injury and/or financial loss caused by their drives' failure or caused by following an error in this documentation.

1.3. Warranty

We give 12 months of standard warranty period with our DG3S series drives. Customers may send back the drives within 15 days from reception date if they are not satisfied with the performance. Using the drive outside of the specified electrical ranges may cause permanent damage to the device and void warranty. Opening the drive's metal frame and making any modification in it voids warranty.

2. Electric specifications and limitations.

2.1.Operation ranges.

Property	Min	Typ	Max	Unit	Notes
Motor supply voltage (model 08020)	12	-	80	VDC	Optimal U=rated+10..20%
Motor supply voltage (model 16035 without using braking circuit)	12	-	80	VDC	Optimal U=rated+10..20%
Motor supply voltage (model 16035 with using braking circuit)	12	-	160	VDC	1.) Optimal U=rated+10..20% 2.) >160VDC input Voltage may cause permanent damage to the device!
Motor current (model 08020)	0	-	20	A	Limited by drive at software set threshold, maximum at 20A
Motor current (model 16035)	0	-	35	A	Limited by drive at software set threshold, maximum at 35A
Logic supply voltage	11.5	12	14	VDC	>20VDC input Voltage may cause permanent damage to the device!
Logic supply current	150	200	250	mA	
Operating temperature	0		65	°C	Automatic shutdown at 65°C
Opto-isolator input Voltage	3	-	-		Use external series resistor in case of input Voltage>5VDC For 12V input use 1kOhm For 24V input use 2.2kOhm
Opto-isolator current	3	5	10	mA	
Step input frequency	0		400	kHz	
Direction signal stabile state minimum allowed valid time after step signal active edge	1	1	1	usec	Step signal active and inactive edges can be configured in software by user.
Encoder maximum frequency	1	1	1	MHz	With 4x decoding
Error line output current	0	50	100	mA	100mA continiously output current is destructive
Switching frequency	20	20	20	kHz	
PID loop sampling time	1		65535	*60usec	User setable in 60usec steps

Minimum allowed motor coil resistance	0.4	-	-	Ohm	If resistance is lower it should be extended with inductor or with resistor/resistor wire.
Minimum allowed motor coil's inductance	200	-	-	uH	If inductance of the motor coil is lower, it should be extended with series coil for correct operation.

3.1. Connectors

3.1.1. Motor and encoder connectors

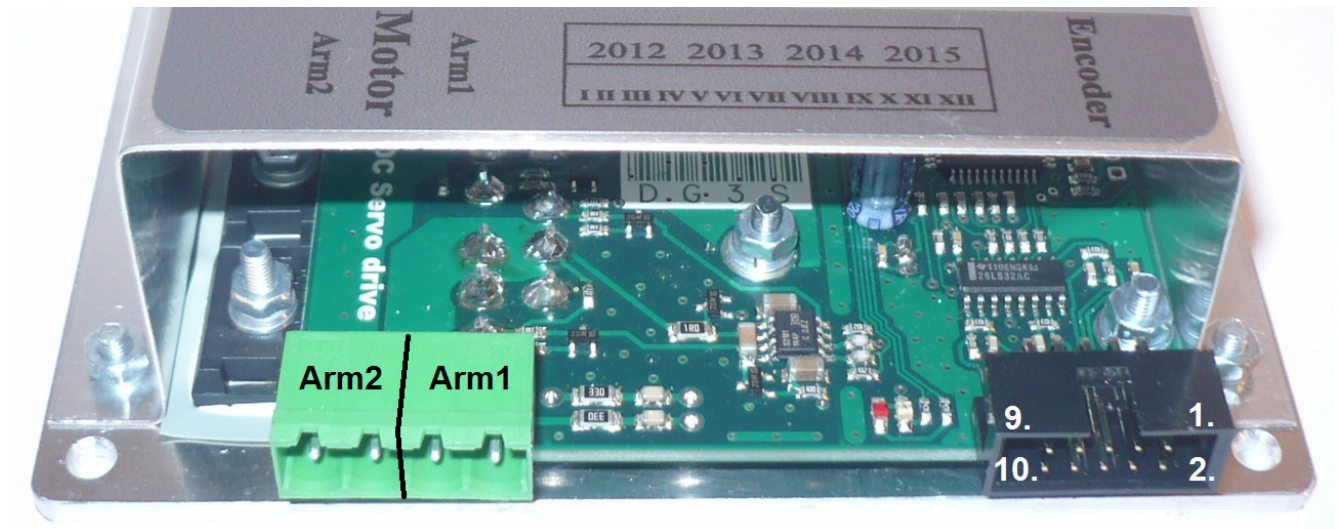


Figure 1. Motor and encoder connectors

Description of the Motor connector:

Connect the DC servomotor terminal wires to Motor Arm1 and Motor Arm2 screw terminals. There are 2 connection terminals for motor Arm1 and also 2 connections for Arm2. For low power motors (peak current rating < 20A) enough to connect 1-1 terminals. If using higher current rated motors connect the terminal pairs together to make the output pins higher diameter in summary for higher current capability.

Description of the encoder connector:

Connect the encoder to the IDC-10 input jack pins.
The pinout of this connector is listed below.
The connection can be made the following ways:

- 1.) Connect with an IDC ribbon female connector crimped onto a 10 wire ribbon cable, the other end of this cable may be a DSUB connector on the control box's frontpanel.
- 2.) Plug the RJ45E encoder IDC to RJ45 connector translator module to the IDC jack and make the connection to the encoder with a standard patch cable. The connection can be done the same way and with the same pinout as with our earlier servo drives.

Pinout of the of the encoder IDC-10 connector:

- 1.) No internal connection (do not connect.)
- 2.) Cable shield connection.
- 3.) Index- signal input
- 4.) Index+ signal input
- 5.) B- signal input
- 6.) B+ signal input
- 7.) A+ signal input
- 8.) A- signal input
- 9.) 5Volts (output from the drive to the encoder)
- 10.) Ground

Pinout of the of the encoder connector with using the RJ45E translator connector panel:

- 1.) Ground
- 2.) 5Volts (output from the drive to the encoder)
- 3.) Index+ signal input
- 4.) Index- signal input
- 5.) A+ signal input
- 6.) A- signal input
- 7.) B+ signal input
- 8.) B- signal input

3.1.2. Main, USB and Power in connectors

The socket labeled **Main** is a standard IDC-10 socket and contains the following connections, as show in Figure 2.



Figure 2. Control Connections

Pinout of the Main IDC-10 connector:

- 1.) No internal connection. (do not connect)
- 2.) No internal connection. (do not connect)
- 3.) DC power – (ground for the 12V DC power supply)
- 4.) DC power + (12V DC input for digital processor)
- 5.) Error (output) and Stop input
- 6.) Reset (input) and Stop input
- 7.) Direction signal ground (NOT for power)
- 8.) Direction signal input
- 9.) Step signal ground (NOT for power)
- 10.) Step signal input

Pinout of the Main connector with using the RJ45M translator connector panel:

- 1) Step signal input
- 2) Direction signal input
- 3) Ground for Step and Direction signals (NOT for power)
- 4) No internal connection. (do not connect)
- 5) Reset (input) and Stop input
- 6) Error (output) and Stop input
- 7) DC power + (12V DC input for digital processor)
- 8) DC power – (ground for the 12V DC power supply)

Descriptions of Main connector signals:

The **DC Power** must be smoothed with capacitor. An example is a typical low power universal power supply set to 12VDC voltage.

Step and **Direction** source signals are fed to the DG3S drive through built in high speed 10Mbit/sec optoisolators. The step and direction inputs interface includes an analog and also a digital filter, these filters out short pulses and noise spikes.

Reset (and **Stop**) signal is referenced to the digital power supply ground (pin8). This is a dual purpose signal which is 'active low', which means the drive normally keeps the signal high and the drive is stopped by pulling the line low (grounding the pin). After the pin is pulled low, releasing the pin initiates a reset.

Note: The drive is also reset by turning the digital power off and back on. Error conditions must be cleared and an encoder must be connected and functioning properly before the drive will start working successfully.

Error (and **Stop**) See Chapter 4.2 for features and function of the Error line.
See Chapter 5.4 for Error line connection options.

Note: A **Stop** signal can be sent on the **Reset** line or on the **Error** line. Grounding either of these pins will stop the drive, but in different ways. See Chapter 4.2 for Error line function.

Description of the USB interface connector:

A 4-pin RM2.0 socket connector is provided for tuning and for making diagnostics on the drive. This connector plugs directly into our PRG01 USB programming stick and this cable contains the USB driver electronics. For tuning connect the drive's 4-pin socket to the PRG1 programming cable's 4-pin socket with the cables supplied with the programming cable. And connect the PRG1 circuit to the PC USB port via a standard USB A-B cable.

The USB connection is provided for configuration and monitoring purposes. These lines are optically isolated from the device's other parts and from the PC.

Note: The PRG01 USB programming stick is not the part of the D3GS drive package. This product must ordered separately. One programming stick can be used to configure any number of drives, but not in the same time.

The drives can be configured/tuned with our Servoconfigurator3 software which can be downloaded from our website for free of charge.

The software documentation can be found in the software package.

Download the latest tuning software from our website.

Descriptions of Power in connector:

The 'power in' connector is for the power supply connection, this source powering the motors through the drive. This connector has a positive and a negative connector section.

Each connection polarity has 2 pins for a 4 pins plug type screw terminal attachment.

For low power motors where the peak current rating of the motor is lower than 20 Amperes 1-1 pin of the terminals can be used for connecting the power supply to the drive. For motors where the rated peak current is greater than 20 Amperes the 2 positive input terminals should be linked together and also the 2 negative input terminals should be linked together for higher current throughput capability. The terminals can be linked together simply with a short piece of wire directly at the plugged screw terminals.

When making this connection take care of the correct polarity, because reverse polarity connection of the power supply may cause a permanent damage to the device!

For more informations on the power supply please see chapter 6. in this product manual.

3.1.3 Using external braking circuit

The background: When a DC motor is rapidly decelerating it acts as a generator. The generated energy pumps back into the drive, possibly higher the voltage in the motor power supply. Therefore if the used power supply rated voltage is greater than 80VDC, it is strongly recommended to use an external braking circuit which dumps and dissipates the generated extra Voltage and energy.

Working of braking circuits:

A braking circuit monitors the motor power supply voltage. If the voltage level rises above a set level the braking circuit activates and powers a braking resistor. The braking resistor is used to dissipate the generated extra energy.

We supply braking circuit products which fits our drives and can be used to protect the drives and the system from regenerative overvoltage events. For more information please check our BRKC-xxx braking circuit devices datasheet.

4.1 LED indicators

Indicator lights are visible on the edge of the board to give visual feedback on the drive operation. There are 2 pieces of LEDs, one with green and one with red with color.

The LED states and the combination of the states gives clear information about the drive operation. Please read section 4.2 below for more information about the possible LED states.

4.2 Fault conditions and Error handling

Error line is pin number 6 in the Main connector and is a dual purpose, bi directional line.

This pin is '*active low*', meaning that the line is normally *high* indicating no problems and normal operation. The drive will stop if this pin is pulled *low* (grounded) by one of these sources:

EXTERNAL activation; The line can be pulled low by an external source (CNC software, E-stop, etc). In this case, the drive will stop and remain stopped. When the pin is released, the drive will remain stopped, but can then be reset. CNC software should be set for 'active low' to use the Error line to stop the drive.

INTERNAL activation; The line is pulled low by the drive itself due to a fault condition. Once stopped by an internal fault condition, the drive will remain stopped until the fault is cleared and the drive is reset. This line may be monitored by your CNC software to trigger an e-stop in the event of a fault. See Chapter 5.4 for details on Error line connection options.

Fault handling by the DG3S series drives:

The possible operation states and their indications are as follows:

1.) **Controller running** - indicates normal operation of the controller.

Red LED *off*.

Green LED *Flashing*.

Description: This is the indication when there is no fault and the drive is up and running.

2.) **Limit override** - indicates that the set servo error limit is reached.

Red LED *blinking*.

Green LED *blinking*.

Description: This is a fault condition and occurs if the following servo error gets greater than the user set value.

3.) **Unconnected or faulty encoder** – indicates that the encoder is not working properly

Green LED *off*

Red LED *blinking rapidly*

Description: This is a fault condition. The drive detects unconnected and faulty encoder signals if it sensing an encoder fault it stops operation.

4.) **Overheat** – indicates that the drive's metal case reached 65 °C

Green LED *on*

Red LED *blinking*

Description: This is a fault condition and indicates an overtemperature of the drive's metal case. When this fault happens the drive cannot be reset until it cools down to under 65 °C.

5.) **Overcurrent** – indicates that the current on the motor outputs cannot be limited

Green LED *off*

Red LED *off*

Description: This is a fault condition and indicates a short circuit on the motor output or a too low resistance/inductance of the motor coil.

Note1.: Point 2 to 5 are error conditions and the error line of the drive activates in these cases.

Note2.: Point 5. is a critical type of fault which cannot be reset using the error/reset lines.

For safety reasons if this type of fault happens the device can be reset only with toggling the 12V power supply to the drive.

5.1 Installation of drive and physical dimensions

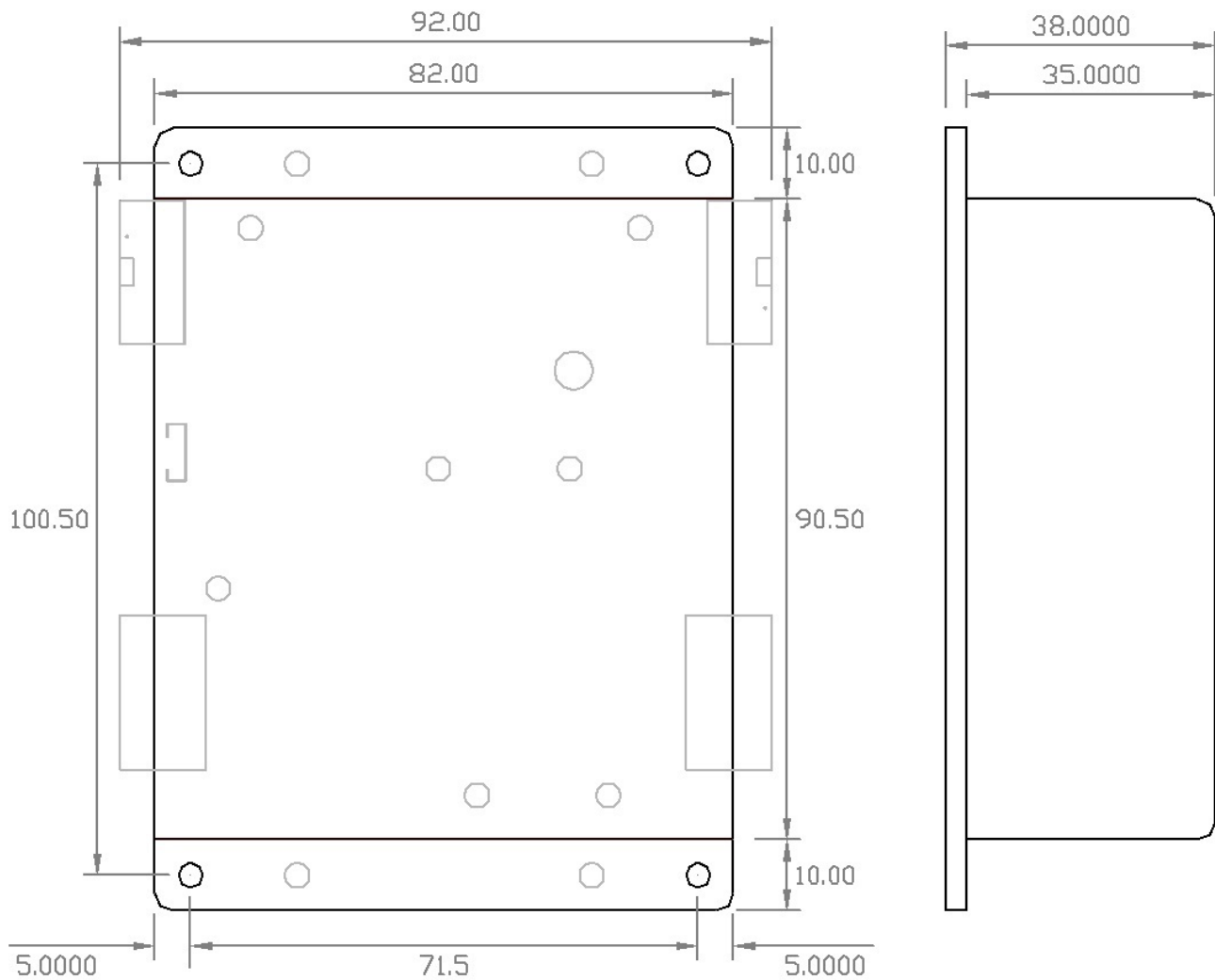


Figure 4. Drive mounting dimensions

All dimensions in mm.

The drive has four 3.5mm mounting holes in the 3mm thick aluminium backplate.

The drive's metal base plate acts as a heat sink for the drive and can become hot under heavy current operation. It is recommended to install the drive on a thermally conductive frame, for example an aluminum plate of at least 1.5mm thickness, to improve cooling and power dissipation.

Use heat transfer paste or a silicon heat transfer sheet to get the best thermal connection between the drive's metal backplate and external mounting metal frame.

The drive has builtin thermal protection, but it is adviced to keep the metal frame as cool as possible to avoid overheating and unexpected shutdowns.

5.2. Motor wiring.

If possible use twisted pair of wires to connect motors to the drives to minimize radiated EMI from the wires. Use as high gauge wire as possible to minimize wire resistance.

5.3. Encoder wiring.

The DG3S drive has a 10 pin IDC male connector for the encoder connection, this connector is labeled as “encoder” and is shown on figure 1. in this manual.

There are some different ways connecting the encoder to the DG3S drive.

The most common ways of the encoder to drive connections:

- a.) If a differential encoder is used with A, _A and B, _B channels then connect it directly with a patch cable to the RJ45E module plugged into the the DG3S drive's IDC-10 encoder connector.
- b.) If single ended encoder is used with A and B channels then connect these channels to the DRVE differential line driver module, this translates the signals to A, _A and B, _B lines. Place the DRVE module close to the motor, keep the single ended A and B wires as short as possible and route the converted differential lines to the drive with a standard patch cable. Plug the patch cable's one end to the DRVE module's RJ45 jack and the other cable end goes to the RJ45E module plugged into the DG3S drive's encoder IDC-10 connector.
- c.) Using a DSUB9 cable assembly the encoder can be wired directly to the control box's (which contains the drive(s)) front panel and route the encoder to this DSUB connector. Using a soldered DSUB-9 male connector on the cable end the encoder is unpluggable at the control box's front panel.

5.4. Shielding techniques in general.

The drive has 'isolated' motor power supply and digital power supply sections. This means the digital power supply ground and motor power supply's ground are 'floating' to each other (not connected inside the drive) to avoid ground loops and therefore noise problems in communication. Do not use the same power supply for the motor power and the digital control power, for example a high voltage power supply that also has a low voltage output included which takes its primary power from the high voltage side.

To protect your new drives and also for the most reliable communications between the computer and the CNC electronics, always use separated Power Supplies for the digital power and the motor power and do not connect the two GND points together, keep them separated and run the ground lines back to their respective power supplies.

Use shielded cables for the **Main** connector and **Encoder** connector if possible. Connect the cable shields to an earth GROUND point (PE) at one end only, preferably at the Control box and not at the machine tool.

If connecting both ends of a cable shield to ground, then current can flow thru the shield creating noise problems and also can carry high voltage back to your control box electronics in the event of a short circuit at the machine tool.

5.5. Error Line wiring

The Error line is a bidirectional line and when looking to it as an output it acts as an open-collector output.

While the drive is running in normal operation the error line is released by the drive and only the internal $\sim 100\text{k}\Omega$ pullup resistors pulling the line to the internal 5 Volts potential.

The error line acts as an open collector output means that any number of error lines can be paralleled (connected together) which allows the user to create a "common error line".

When paralleling the error lines of all drives in a setup, if any of the drive has an internal fault, it pulls the error line low indicating the fault and stopping all other drives.

An external optical isolator may be used to interface the error line to the control computer or to a PLC or to any type of external control circuit. The external optical isolator may be connected as drawn on Figure 5.

An external pushbutton or NPN transistor may be used to trigger the error line by external circuits.

Take care to not to overstress the Error line output and never connect the error line to any other potential than GND (0 Volts of the digital powersupply).

The error line can sink a maximum 50mAmps of current and can live throu 100mA in peaks. Overstressing the error line may cause permanent damage to the device!

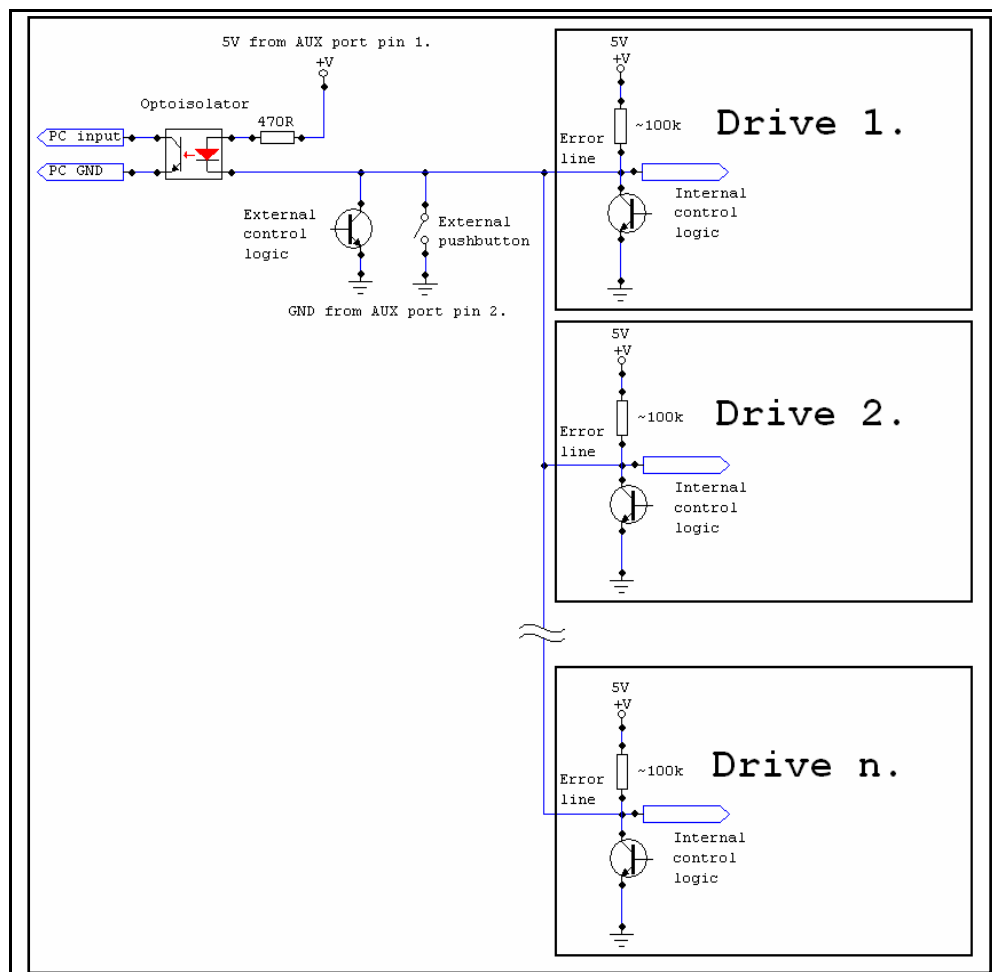


Figure 5. Interfacing the error line

5.6. Reset Line wiring

The reset line is a TTL level input. The line is held on 5Volts potential (referenced to the digital powersupply ground) by internal weak pullup resistors with an approximate value of 100kOhm. The reset line can be activated by external logic with pulling the line low. Releasing the line returns the line to a high (5V) state. It is only allowed to pull the error line low (GND potential) externally. Pulling the line high with any external logic may cause the output Mosfet transistor to overheat and damage!

5.7. Mixing the Reset and Error lines

The error line acts as an opencollector output which means that many error lines can be connected together (paralleled or in other words OR wired).

The reset line is an input and therefor any number of reset lines may be also wired together.

It is also allowed to wire the error lines and the reset lines together. With making this connection we get a "common error/reset line" for a drive or for any number of drives in the setup.

If this common error/reset line is pulled to GND potential by external logic, it works as if it was just a reset line and the drive stops operation. If the line is released by the external logic, the drive(s) automaticly resets and starts operation again.

If an internal fault occurs in any of the drives in this chain, the commoned error/reset line is pulled to GND potential by the drive which got the fault, but because the reset line is also connected to the same wire, the drive automaticly resets itself. In this automatic reset procedure a short approximately 300msec long low pulse is generated on the common error/reset line which an external logic may read and may do the required steps of operation.

As mentioned the drives automaticly resets with this mixed connection of the error and reset lines and with this connection there is no need to use any external logic to force the drives to reset after a fault.

Ofcourse individual reset and error line handling is also possible, it is only an option to mix the error and reset lines. It depends on the application if this connection mode is useful or not.

6. Power Supply selection and filtering

The drive needs 2 power supplies for operation, one to feed the digital circuit and one to feed the motor. The digital power supply can be typically a 12V DC voltage source with that has smoothed and regulated output and meets the other electrical requirements.

The motor power supply should be a 'linear' power transformer with continuous current capability at least of motor's rated continuous current rating.

The DC output should be smoothed with capacitors downstream of the rectifier using the following sizing rules;

1000uF per amp up to 80V
2000uF per amp over 80V

Connect each drive with separate feed wires from these main capacitors. Do not 'daisy chain' the drives to the power supply.

Keep the wires from the power supply to the drives under 30cm (12 inches) in length. If that is not possible, then install an additional 1000uf (or greater) capacitor directly across the power terminals on the drive.

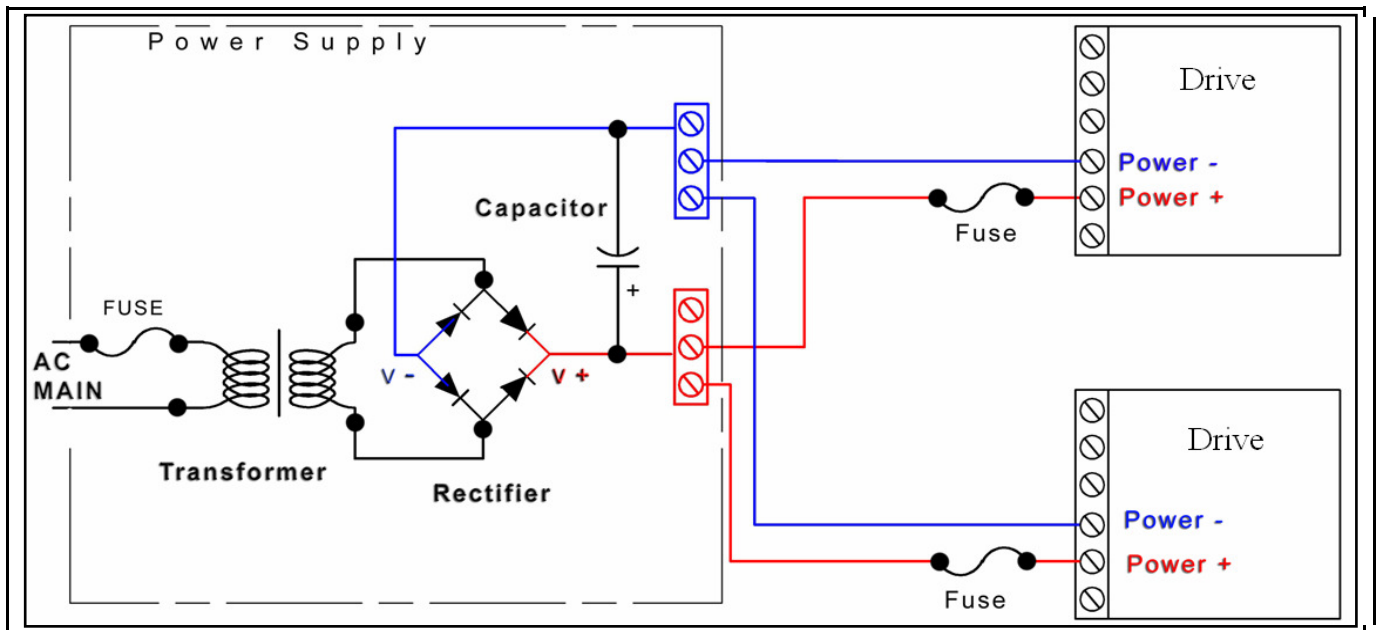


Figure 6. Ideal basic motor power supply configuration

Using a switching mode power supply (SMPS)

If using not a linear, but switching mode power supplies then do not connect the SMPS outputs directly to the drives, but connect a diode with it's anode to the power supply positive output and place a capacitor to between the diode's cathode and the negative (GND) output of the SMPS. When sizing the capacitor follow the rules described above in point 6. in this manual.

The reason this extension circuit is needed is because most of the switching power supplies are not designed to power highly inductive loads (like motors). The problem is that the power supplies having too low capacitance on the outputs and the inductive kickback from the motors may rise the power supply Voltage and this could damage the drive and/or the power supply.

The diode in the extension circuit blocks the reverse Voltage from the motor/drive to the power supply and the added external capacitor keeps the charge and the Voltage on the desired level and suppressing Voltage fluctuation on the DC bus.

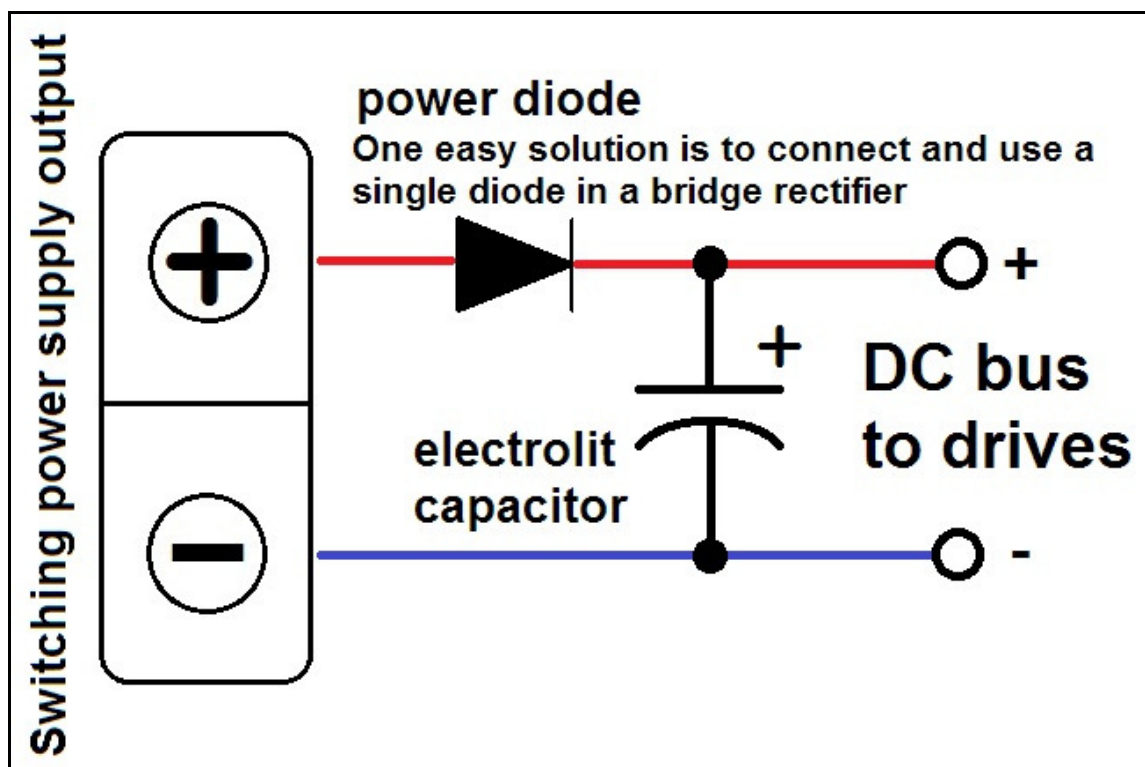


Figure 7. Extension circuit if using Switchind mode powersupply

7. Accessories (not parts of the drive, may be ordered separately!)

DRVE Differential line driver module

Pinout:

- 1.) Ground
- 2.) **5V** DC power for encoder
- 3.) Not used
- 4.) Not used
- 5.) **A**
- 6.) **A₋**
- 7.) **B**
- 8.) **B₋**

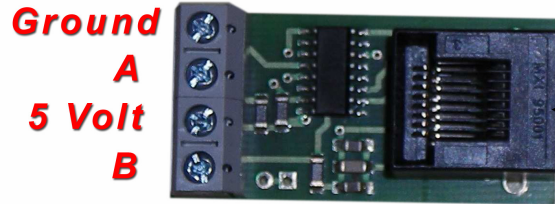


Figure 8. DRVE module

The Encoder must be an incremental and TTL level type with square waves. Absolute encoders are not supported.

An encoder with differential A , A₋ and B , B₋ channels must be used for position feedback from the motor to the drive.

A single ended encoder can be converted to differential by using our differential line driver module. Mount the interface board near the encoder and connect the encoder wires to the interface **screw terminals** as shown.

RJ45M , IDC-10 to RJ45 translator module

The RJ45M module contains an IDC-10 female connector on one end and an RJ45 connector on the other end of the board. The module can be plugged directly into the drive's 'Main' labeled IDC-10 male signal connector and connects the signals to the RJ45 jack on the other end of the module.

Using the module makes the connection easy 'plug and play like" to our breakout boards.

Using these modules is not absolutely necessary in all installations, the user should decide if it is needed for his application.

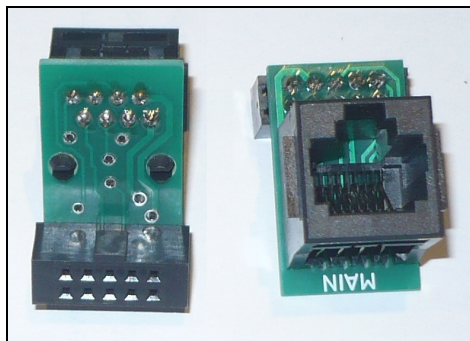


Figure 9. shows the Main and Encoder IDC-10 to RJ45 modules. Both modules look the same, but have different pinouts and a silkscreen label on the PCB with text of "Main" and "Encoder" help the identification of them.

Pinout of the RJ45M module:

Pin number	Signal in the IDC-10 connector	Signal in the RJ45 connector
1.	No internal connection. (do not connect)	Step signal input
2.	No internal connection. (do not connect)	Direction signal input
3.	12V DC power supply GND	Ground for Step and Direction signals
4.	12V DC power positive	NC
5.	Error (output) and Stop input	Reset (input) and Stop (input)
6.	Reset (input) and Stop input	Error (output) and Stop (input)
7.	Direction signal ground (NOT for power)	DC power + (12VDC input)
8.	Direction signal input	DC power – (ground for 12VDC input)
9.	Step signal ground (NOT for power)	-
10.	Step signal input	-

RJ45E , IDC-10 to RJ45 translator module

The RJ45E module contains an IDC-10 female connector on one end and an RJ45 connector on the other end of the board. The module can be plugged directly into the drive's 'Encoder' labeled IDC-10 male signal connector and connects the signals to the RJ45 jack on the other end of the module.

Using the module makes the connection easy 'plug and play like" to an encoder or to our DRIVE differential line driver module.

Using this module is not absolutely necessary in all installations, the user should decide if it is needed for his application.

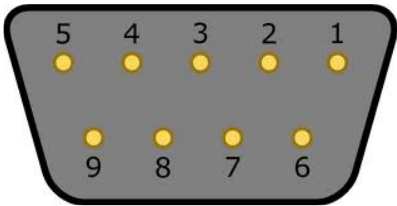
Pinouts of the RJ45E module:

Pin number	Signal in the IDC-10 connector	Signal in the RJ45 connector
1.	No internal connection (do not connect.)	Ground
2.	Cable shield connection.	5Volts
3.	Index- signal input	Index+ signal input
4.	Index+ signal input	Index- signal input
5.	B- signal input	A+ signal input
6.	B+ signal input	A- signal input
7.	A+ signal input	B+ signal input
8.	A- signal input	B- signal input
9.	5Volts (output to the encoder)	-
10.	Ground	-

DSUB9 IDC-10 to DSUB-9 cable assembly

The DSUB9 cable assembly contains an IDC-10 female connector crimped to a 10 wire ribbon cable's one end and a DSUB 9 female connector crimped to the other end of the ribbon cable. This cable assy can be used forexample to make a DSUB connection on a control box's front panel with assembling the crimped Dsub connector directly to the control box's wall facing out the box.

DSUB9 cable assembly connection sheet:

Pin number on the IDC-10 male connector on the drive (As marked on figure 1. and 2.)	Pin number of the DSUB-9 female connector on the ribbon cable end	<div>DSUB-9 female connector</div>  <div>viewed from the front of the cable end connector</div>
1.	NC (not terminated)	
2.	1.	
3.	6.	
4.	2.	
5.	7.	
6.	3.	
7.	8.	
8.	4.	
9.	9.	
10.	5.	

8. Troubleshooting

Q: When powering up the drive, the motor running with full speed to one direction and stops after a while with error-limit reached LED on.

A: Encoder is wired up in reverse, exchange motor Arm1 with Arm2 to reverse direction of the motor.



Q: The motor is oscillating over the nullpoint when powerup.

A: Tune the PID controller with the Servoconfigurator3 software.

Q: I like to control my motor with a PLC which has 24V I/Os, is it possible?

A: The step and direction pins are feed through optoisolators. Use a series resistor with the step and with the direction signal from the PLC. Resistor must be sized so that the optoisolator current is limited under 10mA.

Q: I like to control an AC servomotor with the drive, is it possible?

A: No. The drive can only control brush type DC servomotors.

Q: I have a disk-type servomotor with coil resistance of lower than 0.4 Ohms and an inductance of lower than 200uH, what to do?

A: Use a resistor wire and/or inductor in series with the motor coil to extend resistance to at least 0.4 Ohm and inductance to at least 200uH otherwise the motor and/or drive may damage.

Q: I have a motor that has a rated Voltage greater than 160VDC, can I used it with the drive.

A: Yes, but do not connect a PSU with an overvoltage, absolute maximum motor Voltage ratings of the drive is 160VDC. If your motor has higher rated Voltage, it should be operate from 160VDC maximum and will have a limited maximum speed and torque. The best way is to use a higher Voltage rated drive in this case, if any available.

For more information visit:

<http://www.cncdrive.com>
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