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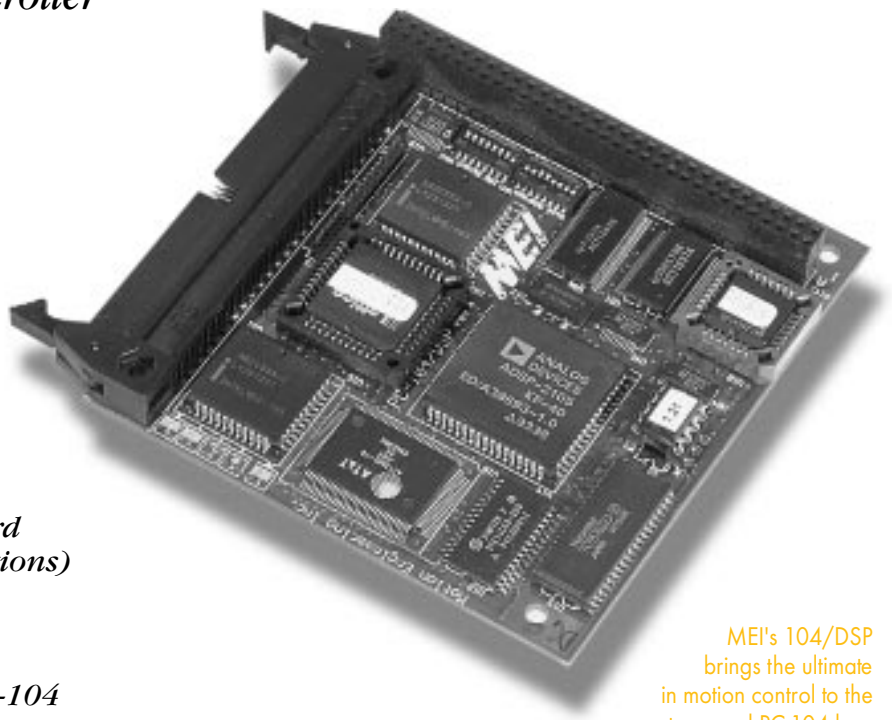
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Find the *Danaher / Kollmorgen / Motion Engineering 104/DSP* at our website: *Click HERE*

DSPlite
PC-104
Analog

*C-programmable Motion Controller*

# 104/DSP



MEI's 104/DSP brings the ultimate in motion control to the compact, rugged PC-104 bus.

- *C-programmable using MEI standard C function libraries (over 250 functions)*
- *PC-104 card supports up to 4 axes*
- *Fast host communication across PC-104 bus at 1.2 MB/sec*
- *Supports both servos and steppers*
- *20 user I/O lines*
- *16-bit servo output resolution*
- *375 kHz step/direction output*
- *Point-to-point and coordinated motion*
- *Supports DOS, Windows 3.X, Windows NT, Windows95, Lynx/OS, VxWorks, QNX, VRTX, and OS/9*
- *Flexible DSP architecture allows on-the-fly changes to many motion parameters*

The 104/DSP combines MEI's proven DSP-based motion control architecture with the compact, rugged design of the PC-104 bus interface. Hardware features include 16-bit servo outputs, encoder inputs to 5 MHz, and 20 lines of user I/O.

You program the 104/DSP using MEI's flexible C function libraries with over 250 motion control functions. Combining MEI C libraries with compilers from Microsoft, Borland, Watcom, Symantec, and others speeds development of complex motion applications.

The 104/DSP provides a rich set of software algorithms, including a sophisticated second-order PID control algorithm with velocity, acceleration, and friction feed-forward.

Advanced features include electronic gearing and camming, dual-loop control, circular and linear interpolation, and trapezoidal, S-curve, parabolic, and custom motion profiles.

The 104/DSP allows motion control programs to share execution between the on-board DSP (for numerically intensive real-time functions) and the host (for non-real-time functions). This results in an ideal division of labor with minimal host intervention.

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# *Software Features*

*Powerful C-programming Libraries* The 104/DSP draws both its power and flexibility from MEI's C function libraries. These libraries enable applications developed on the 104/DSP to run on any MEI motion controller.

```
set_move_speed(speed);
set_move_accel(accel);
start_point_list();
move_2(x1,y1);
move_2(x2,y2);
end_point_list();
```

*Sample coordinated motion routine*

The MEI C libraries contain over 250 functions you can use to create motion control programs from simple point-to-point motion to complex multi-axis coordinated motion. Along with source code, MEI provides hundreds of sample applications to help speed development.

*Development Environment* MEI controllers support most popular compilers and operating systems, including those with true multitasking.

| Operating Systems | Compilers |
|---|---|
| DOS | Microsoft Visual C/C++ |
| Windows 3.x | Borland C/C++ |
| Windows NT | Watcom C/C++ |
| Windows95 | Symantec C/C++ |
| Lynx/OS | Visual BASIC for Windows |
| VxWorks | GNU |
| QNX | |
| OS/9 | |

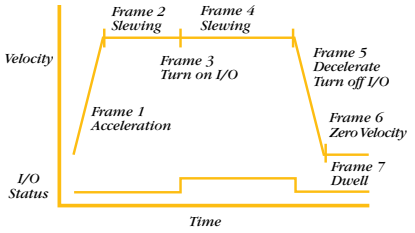
*PID and Notch Filters* The 104/DSP uses a software PID control algorithm optimized for high performance. This PID algorithm delivers quick update rates, stable operation, and easy tuning. An optional post-PID notch filter is available to eliminate mechanical resonances in a closed-loop system.

```
while (! done)
{ printf("Set SlavingRatio? ") ;
  gets(buffer) ;
  done=scanf(buffer,"%lf",&ratio)!=1;
  if (! done)
  {  endlink (SLAVE);
     set_position(3,0) ;
     set_position(1,0) ;
     link(3,1, ratio, ACTUAL) ;
  }
}
```

*Sample coordinated motion routine*

*Powerful Frame Architecture* To create a motion sequence, the DSP executes a series of "frames" that are generated by MEI C library functions and sent from the host. Each frame is an array of 20 words that contain position, velocity, acceleration, jerk, I/O status, and trigger information.

With up to 600 frames stored on-board, the 104/DSP can buffer complex motion sequences in memory for minimal host involvement. The host downloads frames and the 104/DSP executes them. For additional frames, either the host polls the board's buffer status or the 104/DSP sends an interrupt to the host.



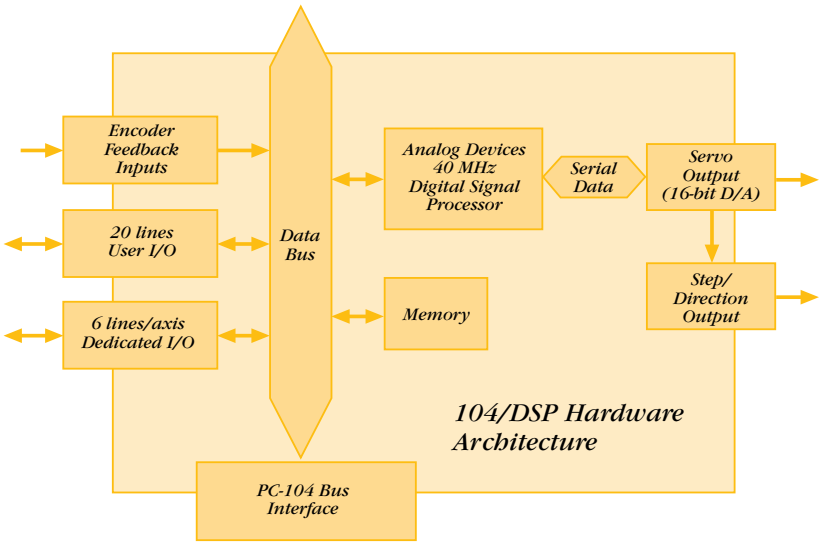

*Variety of Motion Profiles* With a single C function, you can program independent or simultaneous point-to-point motion for up to four axes (with your choice of trapezoidal, parabolic, S-curve, or user-defined profiles). You can trigger I/O bits on-the-fly for specified positions, velocities, or times.

Advanced Motion Features

- electronic gearing & camming
- coordinated motion with acceleration blending, cubic splining, or circular interpolation
- feed-speed override with pause-on-path
- tangential following and laser power control
- position latching (under 4 microseconds)
- encoder-based jogging
- sinusoidal commutation
- dual-loop control
- multiple coordinate systems
- helical and linear interpolation
- high-speed registration
- direct D/A outputs

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# Hardware Features




*High-Performance DSP Architecture* The 104/DSP uses a high-performance 40 MHz DSP to execute real-time motion control algorithms, offloading non-real-time functions to the host. The 104/DSP buffers commands from the host and stores motion and I/O sequences on-board.

This efficient division of labor frees the host from real-time requirements and enables fast host-to-DSP communication across the PC-104 bus. Even complex functions require virtually no CPU time once motion starts.

*Fast Communications* The host compiles C functions and transmits them as binary strings across the PC-104 bus at speeds up to 1.2 MB/sec. While the DSP can interrupt the host to request data or initiate other actions, no host involvement is required once compiled commands are downloaded.

The host CPU can access all on-board peripheral functions (such as digital I/O) without interrupting the real-time control loop calculations of the DSP.

```
set_feedback(linear,ENCODER);
set_feedback(rotary,ENCODER);
set_dual_loop(linear,rotary,TRUE);
```

*Sample dual-loop control routine*

Fast bus communications also allow the 104/DSP to take full advantage of ever-expanding host CPU performance by leveraging the multitasking capabilities of the Windows NT operating system.

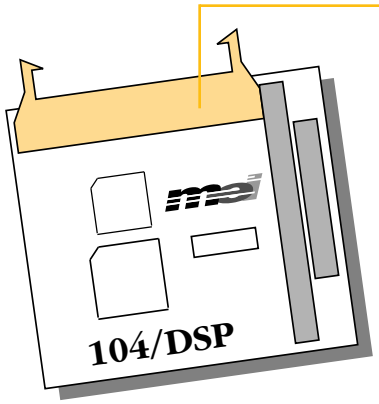
*Position Feedback* Up to four encoder inputs accept position feedback at up to 5 MHz. With MEI's unique Encoder Integrity Checking (EIC) feature, on-board encoder inputs can detect broken or shorted encoder wires, detect an illegal state, and digitally filter serious noise. EIC ensures that problems with either the encoder or its wiring won't result in a runaway condition.

## Hardware features

- 16-bit servo output resolution
- 32-bit or 48-bit accuracy in all kinematic functions (position, velocity, and acceleration)
- no arcane proprietary command languages
- support for servo and steppers on one board
- step output rates up to 375 kHz
- optional support for Temposonics sensors

## *Motor/Encoder Pin-outs*

| *Pin* | *Signal* | *Pin* | *Signal* |
|---|---|---|---|
| 1 | +5V | 27 | Positive Limit(0) |
| 3 | Encoder A(0) + | 29 | Negative Limit(0) |
| 5 | Encoder A(0) - | 31 | Home Input(0) |
| 7 | Encoder B(0) + | 33 | Amp Fault(0) |
| 9 | Encoder B(0) - | 35 | Amp Enable(0) |
| 11 | Encoder Index(0) + | 37 | In Position (0) |
| 13 | Encoder Index(0) - | 39 | User I/O PA0 |
| 15 | ±10V Analog Out(0) | 41 | User I/O PA1 |
| 17 | GND | 43 | User I/O PA2 |
| 19 | Step Pulse (0) +* | 45 | User I/O PC0 |
| 21 | Step Pulse (0) -* | 47 | User I/O PC1 |
| 23 | Direction(0) +* | 49 | GND |
| 25 | Direction(0) - * | | |




NOTE: *One axis connection shown; 100-pin high-density connector supports up to 4 axes*

* *Clock up/down optional*

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# *104/DSP Specifications*

## Processor
- Analog Devices, 40 MHz DSP

## Computer Interface
- PC-104 Compatible
- Switch-selectable address, I/O mapped
- Binary communication up to 1.2 MB/sec
- Host CPU interrupts

## Software Development Tools
- MEI standard C function libraries (over 250 functions)
- Compilers: Microsoft, Borland, Watcom, Symantec, GNU
- Operating system support: DOS, Windows 3.X, Windows NT, Windows95, Lynx/OS, VxWorks, QNX, VRTX, OS/9

## Servo Loop Update Rate
- User-programmable rate
- Maximum: 10 kHz (1 axis), 3.0 kHz (4 axes)
- Default: 1.25 kHz

## Servo Output
- ±10V DC at 16-bit resolution
- ±18 mA current
- 100 ppm long-term velocity accuracy

## Step Output
- Pulse rate ranges (16-bit resolution):
  0 to 375 kHz
  0 to 93.75 kHz
  0 to 23 kHz
- RS-422 line driver outputs
- ±20 mA current
- Step/direction or clock up/clock down*
- Pulse width: 50% duty cycle

## Position Feedback
- Incremental encoder: 5 MHz, single-ended or differential
- RS-422 line receivers/digital filtering
- Encoder checking: broken wire and illegal state detection
- Temposonics support: direct connection*

## Dedicated I/O (per axis)
- TTL compatible, 4.0 mA drive
- Inputs: positive and negative limits, home, amp-fault (SCR clamp protected)
- Outputs: in-position, amp-enable

## User I/O (per board)
- 20 lines, user programmed mode: input or output
- TTL compatible, 4.0 mA drive
- Direct access from host CPU

## Kinematic Ranges
- Position: 32-bit (±2.15 billion counts)
- Velocity: 48-bit (±65 million counts/sec at 2 kHz sampling)
- Acceleration: 48-bit (±131 billion counts/sec$^2$ at 2 kHz sampling)
- Jerk: 48-bit (±262 trillion counts/sec$^3$ at 2 kHz sampling)

## Motion Control Features
- Point-to-point motion
- Coordinated motion
- Cubic spline motion
- Electronic gearing and camming
- Feed speed override
- Dual-loop control
- High inertia compensation
- High-speed registration
- Tangential following*
- Laser power*
- Sinusoidal commutation*

## Motion Profiles
- Trapezoidal profile
- S-curve profile
- Parabolic profile
- Custom (user-defined)

## Power Requirements
- +5 V Icc = 0.8 A max
- +12V Icc = 10 mA max
- -12V Icc = 20 mA max

## Environmental Conditions
- Operating temperature: 0-50 degrees C
- Humidity: 20-95% RH, non-condensing

## Construction
- Full SMT; 4-layer PCB
- 100% bed of nails and fully functionally tested with 24-hour burn-in
- UL and CE compliant


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