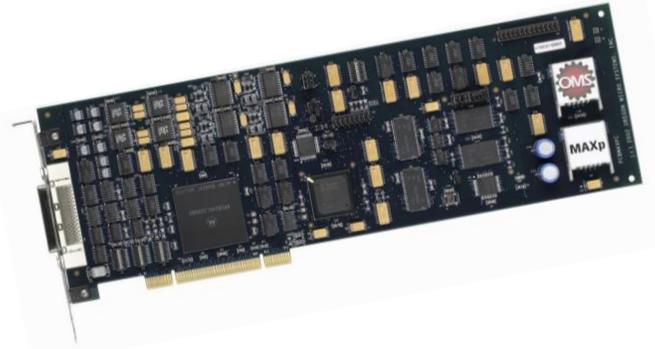




"The Company in Motion"™



MAXp

MAXp

Intelligent 8-Axis Motion Controller for PCI

- **PID update rate of 122 μ s on all 8 axes**

Delivers exceptional servo control on multi-axis applications. Identical outcomes when utilizing one or all axes of motion. Configurable PID filter with feedforward coefficients.

- **266 MHz, 32-bit RISC processor**

Updates all signals and data points providing superior application control. An order of magnitude faster than our competition.

- **64k Shared Memory**

Permits rapid data transfer to & from controller. Large size accommodates expandability to unique and custom applications.

- **PCI Universal Bus - 3.3 or 5.0 volts**

PCI Rev 2.2 compliant. Compatible with current and future PCI bus computers.

- **Memory**

32 Mb System Memory.

- **Controller I/O Capabilities**

4 Channels of general purpose Analog Input, with 16 bit, +/-10 VDC input

Up to 8 Analog outputs, +/- 10 VDC output

16 user-definable digital I/O

Home and Limit for each axis

- **Motion Feedback**

Support Quadrature Encoder Feed back up to 16 MHz.

- **Sophisticated Control Functionality**

16 bit DAC analog resolution. Step pulses from 0 to 4,176,000 steps per second (+/- 0 steps). Backlash compensation. Custom, Parabolic, "S"-curve & Linear trajectory profiles. Real time encoder position capture. S-Curve with 4-quadrant jerk parameters.

- **Control signals**

Opto-isolated Digital I/O. High density shielded 120 pin connector

Additional Features

- All communication via Device Driver and Driver Support DLL.
- Dual Port RAM is utilized for high-speed communications
- PCI 33 MHz Target Device
- Independent and coordinated motion of all axes.
- Slip & Stall detection with encoder feedback.
- Patented technology to minimize torque ripple and velocity modulation.
- Many control signals are opto-isolated.
- Independent home, positive and negative over-travel inputs.
- Non-volatile macro storage, parameter storage.
- Linear/Circular interpolation
- Constant or Variable Velocity contouring (all axes)
- 120 Pin I/O Breakout Module
- Field upgradable firmware
- Firmware upgrades and enhancements
- Customizable solutions available for your requirements
- Example programs and application code provided
- Web page support for downloading software and documentation
- Person to person toll-free tech support - call 800-707-8111

Tel: (503) 629-8081 or (800) 707-8111

Fax: (503) 629-0688

www.OMSmotion.com

OMS, Inc.

Beaverton, Oregon

DESCRIPTION

The MAXp is a full length PCI bus motion controller that conforms to the PCI Local Bus specification, rev 2.2. The MAXp is capable of up to 8-axis of control of which each axis can be configured as an open loop stepper, a closed loop stepper, or a servo axis.

The MAXp is powered by a PowerPC processor. This high performance processor provides a 64-bit Floating Point processor and is clocked at 266MHz. This provides the MAX with the pure processing power to update every signal of the controller, i.e. I/O bits, direction, limits, etc., at rates of 122µs.

The MAXp supports 16 general purpose digital I/O signals which are opto-isolated for optimum noise immunity. The home and overtravel inputs are also opto-isolated. In addition it has four general purpose analog inputs that can be used to sense Pressure Transducers, Dial Switches, etc. Analog inputs can also be used to control velocity override. These analog inputs have 16-bit resolution with +/- 10 VDC input.

Each axis has servo output signal capability; configured as a +/- 10V or 0-10V signal and is driven by a 16-bit DAC. The servo control loop is a PID filter with feedforward coefficients and an update rate of 122µs. The step pulse is a TTL level, 50% duty cycle square wave that supports velocities of 0 through 4,176,000 pulses per second. Encoder feedback functionality supports quadrature encoders up to 16 MHz and is used as the servo feedback, as feedback for the stepper axes or as independent position feedback. Encoder feedback is also used to provide slip and or stall detection. Every axis includes dedicated +/- over travel inputs, a home input, and an auxiliary output. The MAXp is available in several different models that support a different number of axes.

PROGRAMMING

MAXp motion controllers are easily programmed with ASCII character commands through an extensive command structure. These commands are combined into character strings to create sophisticated motion profiles with features of I/O and other functionality. A separate FIFO command queue for each axis is used to store the commands once they are parsed by the MAXp. The commands are executed sequentially, allowing the host to send a complex command sequence and attend to other tasks while the MAXp manages the motion process. These command queues store 2559 command values and include a command loop counter which allows multiple executions of any queued command.

All commands are sent to the controller as two or three character ASCII strings. Some of these commands expect one or more numerical operands to follow. These commands are identified with a '#' after the command. The '#' indicates a signed integer input parameter or a signed fixed point number of the format ##.# when user units are enabled. User Units define, distances, velocity and acceleration parameters and may be inputted in inches, millimeters, revolutions, etc.

Synchronized moves may be made by entering the AA or AM command mode. This form of the command performs a context switch that allows entering commands of the format

MRx#,y#,z#,t#; u#, v#, r#, s#;

Numbers are entered for each axis commanded to move. An axis may be skipped by entering the comma with no parameter. The command may be prematurely terminated with a ",", i.e. a move requiring only the X and Y axes would use the command MRx#,y#; followed by the GO command. Each axis programmed to move will start together upon executing the GO command. The MAXp can be switched back to the independent-axis mode by entering the desired single axis command such as AX.

PROGRAMMING EXAMPLES

In a typical move requirement where it is desired to home the stage then move to a specified position, the following will demonstrate the programming for a single axis:

- Initialize the velocity and acceleration parameters to a suitable value. Set a PID filter gain values. Perform the home operation initializing the position counter to zero. Perform a motion to an absolute position of 10,000 and set the done flag for that axis when the move is finished.

The following would be input from the host computer:

```
AX;
VL5000;
AC50000;
KP20;
K11;
KD45;
HN;
HM0;
MA10000;
GO;
```

In a ID; move requiring a three axis coordinated move to a select position the following commands could be used:

```
AM;
VL5000,5000,5000;
AC50000,50000,50000;
MT1000,2000,3000;
GO;
ID;
```

The controller would calculate the relative velocities required to perform a straight line move from the current position to the desired absolute position so that all axes arrive at their destinations at the same time.

The following demonstrates cutting a hole with a 10,000 count radius using constant velocity contouring and circular interpolation:

- The contouring velocity is set to 1000 counts per second. A contour is defined beginning at coordinates 0,0 on the Z and T axes.
- Auxiliary output on the X axis is turned on, which could turn on the cutting torch or laser starting the cut at the center of the circle.
- A half circle is cut from the center to the outside of the hole positioning the cutting tool at the start of the hole.
- The hole is then cut, the torch turned off, the stage stopped and the contour definition completed.
- The stage is then positioned and the contour definition executed.

The following would be input from the host computer:

```
AA;
CV1000;
CD,,0,0;
AN;
CR0,5000,-3.1415926;
CR0,0,-6.2831853;
AF;
MT-10,10000;
CE;
MT,,-1000,0;
GO;
CX;
```

SPECIFICATIONS

Velocity

0 to 4,176,000 pulses per second simultaneous on each axis

Acceleration

0 to 8,000,000 pulses per second per second

Position range

± 2,147,487,647

Accuracy

Position accuracy and repeatability ±0 counts for point to point moves

Velocity accuracy ±0.01% of peak velocity in jog mode.

Environmental

Operating temperature range: 0 to 50 degrees centigrade

Storage temperature range: -20 to 85 degrees centigrade

Humidity: 0 to 90% non-condensing

Power

+5VDC +/-5% at 1 amp typical
 +3.3VDC +/-0.3% at amps typical
 +12VDC at 0.1 amp typical = +/-5%
 -12VDC at 0.1 amp typical = +/-10%

Dimensions

12.283" x 4.200" x 0.475"
 312 mm x 106mm x 12.06 mm

Communication Interface

Meets all signal specifications for PCI bus Specifications, Rev. 2.2.

Limit switch inputs

Opto-isolated TTL input levels (Opto, max 50mA). Input sense (low or high true) selectable by command input for each axis.

Connector

Single HI Density Shielded 120-Pin connector for all motor control functions. Mating connector and Strain Relief Hood. Separate 25-Pin D-Sub connector for all Digital I/O functions.

Home switch inputs

Opto-isolated TTL input levels (Opto, max 50mA). Input sense (low or high true) selectable by command input for each axis.

User definable I/O

Up to 16 bits of user definable Digital I/O. All bits are opto-isolated. 16 bits are user configurable that are configured as 8 inputs and 8 outputs from the factory. These signals are passed through an optocoupler with a maximum input forward current of 50mA and a maximum output emitter-collector voltage of 35V and 50mA collector current.

Analog inputs

Four independent analog inputs, 16 Bit resolution

Analog outputs

+/-10V and 0 to +10V,max. 1mA each. One per axis.

Step pulse output

Pulse width 50% duty cycle. Open collector TTL level signal (7406, max 48mA).

Direction output

Open collector TTL level signal (7406, max 48mA).

Encoder Feedback

Maximum 16 MHz after 4x quadrature detection. Differential TTL level signal (26LV32, max 15mA).

Reference

PCI specification, Rev. 2.2.
 PCB mechanical specification, IEEE 1101.1, 1101.10 and P1101.11

Software

High level expertise not required.

Over 200 ASCII character commands, expanded from current OMS command set.

Software drivers and DLLs for Windows® provided at no additional cost.

User Manual included.

Servo Tuning Assistant software tools included at no additional cost. Support software available for download at our website.

Part Number: 3701-0900000

Revision E

ORDERING INFORMATION									
Model	Computer Interface	Axes	Servo / Stepper	I/O					
				Limit	Auxiliary	Home	Digital General Purpose	Analog	
								In	Out
MAXp-1000	Universal PCI	1	User Definable	2	1	1	16	4	1
MAXp-2000		2	User Definable	4	2	2	16	4	2
MAXp-3000		3	User Definable	6	3	3	16	4	3
MAXp-4000		4	User Definable	8	4	4	16	4	4
MAXp-5000		5	User Definable	10	5	5	16	4	5
MAXp-6000		6	User Definable	12	6	6	16	4	6
MAXp-7000		7	User Definable	14	7	7	16	4	7
MAXp-8000		8	User Definable	16	8	8	16	4	8
IOMAX	120-Pin Connector Breakout Module								



"The Company in Motion"™

15201 NW Greenbrier Pkwy
B-1 Ridgeview
Beaverton, Oregon 97006
USA

(503) 629-8081, (800) 707-8111
Fax: (503) 629-0688
www.OMSmotion.com