



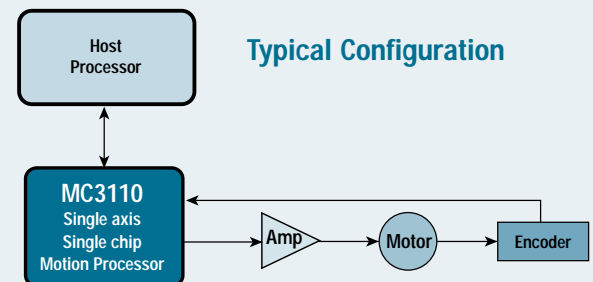
Pilot™ Motion Processor For Brushed Servo Motion Control MC3110

Features

- Available in 1-axis configuration.
- Motion profiles include S-curve, trapezoidal, velocity contouring and user-defined.
- Asymmetric acceleration and deceleration to custom program a trapezoidal motion profile.
- Advanced PID filter with velocity and acceleration feedforward, bias offset and 32-bit position error.
- Velocity and acceleration changes on-the-fly for trapezoidal and velocity contouring profiles.
- Incremental encoder quadrature input and parallel input for absolute encoder or resolver.
- Parallel and Serial (point-to-point or multi-drop) communications interface.
- Trace capabilities for system performance checks, servo-tuning, maintenance and diagnostics.
- 10-bit, 20kHz PWM or 16-bit DAC motor control output to amplifier.
- Advanced breakpoint capability allows precise sequencing of events.
- PLC-style programmable inputs and outputs, including one programmable input and one output.
- 256 16-bit word I/O locations for user defined peripherals.
- 8 general-purpose analog inputs.
- Two-directional limit switches, index input and home indicator.
- Axis settled indicator and tracking window in addition to automatic motion error detection.
- Comprised of a single 132-pin device (surface mount CMOS technology).
- Available in commercial and industrial temperature versions.



Typical Configuration



General Description

The Pilot single-axis, single chip motion processor for brushed servo motor control is ideal for embedded systems for industrial control, automation and robotic applications. The chip is a 132-pin device, surface mount CMOS technology and powered by 5 volts. The motion processor is driven by a host microprocessor through an asynchronous bi-directional serial port or through a 16-bit microprocessor-style parallel interface, giving users the ability to offload resource intensive motion control functions from the application's host.

With over 150 commands, PMD's instruction set offers flexibility and versatility to board designers and software applications programmers. Instructions are used to initialize and control the motion processor. User selectable profiling modes supported by the motion processor include S-curve, trapezoidal, velocity contouring and user-defined. The MC3110 accepts input parameters such as position, velocity and acceleration from the host and generates a corresponding trajectory.

The MC3110 has a pre-programmed PID filter with feedforward velocity and acceleration that can be scaled and a bias offset. The chip also supports a 32-bit

position error. The PID filter operates at 100µsec loop cycle time. Trace capabilities provide on-the-fly data storage to an external RAM for analyzing system performance, tuning servo filters and performing maintenance and diagnostics.

The motion processor accepts feedback from an incremental encoder or from an absolute encoder or resolver at rates up to 160 megacounts per second. 16-bit DAC or 10-bit, 20kHz PWM compatible output signals are supported.

Multiple breakpoints offer precise sequencing and control of events by the application program. PLC-style instructions are provided which operate on inputs and set outputs. The instructions use Event, Activity and Signal registers. Input signals include two limit switches (one for each direction of travel), home indicator and a general-purpose programmable input. One general-purpose programmable output signal is also provided. Eight general-purpose analog (0-5 V), and 256 (16-bit wide) general-purpose discrete inputs/outputs are available.

Technical Specifications

Available configurations	1 axis
Operating modes	Closed loop (motor command is driven from output of servo filter) Open loop (motor command is driven from user-programmed register)
Position range	-2,147,483,648 to +2,147,483,647 counts
Velocity range	Velocity-contouring profile mode: -32,768 to +32,767 counts/sample with a resolution of 1/65,536 counts/sample All others: 0 to 32,767 counts/sample with a resolution of 1/65,536 counts/sample
Acceleration and deceleration ranges	-32,768 to +32,767 counts/sample ² with a resolution of 1/65,536 counts/sample ²
Jerk range	0 to 1 counts/sample ³ , with a resolution of 1/ 4,294,967,296 counts/sample ³
Profile modes	S-curve point-to-point (Velocity, acceleration, jerk and position parameters) Trapezoidal point-to-point (Velocity, acceleration, deceleration and position parameters) Velocity-contouring (Velocity, acceleration and deceleration parameters) User-defined (Velocity, acceleration, jerk, time and position parameters)
Filter Modes	Scalable PID + velocity feedforward + acceleration feedforward + bias Also includes integration limit, settable derivative sampling time and output motor command limiting
Filter parameter resolution	16 bits
Motor output modes	PWM: 10-bit resolution at 20 kHz DAC: 16 bits
Maximum encoder rate	Incremental: Up to 5 Mcounts/sec Parallel-word: Up to 160.0 Mcounts/sec
Parallel encoder word size	16 bits
Parallel encoder read rate	20 kHz
Servo loop timing range	100 µsec to 3355 msec
Minimum servo loop time	100 µsec (nominal; exact time is 102.4 µsec)
Limit switches	2; one for each direction of travel
Position-capture triggers	2; index and home signals
Analog input	8 10-bit analog inputs
User-defined discrete I/O	256 16-bit wide user-defined I/O
Number of host instructions	151



Performance Motion Devices, Inc.
55 Old Bedford Road
Lincoln, MA 01773

tel: 781.674.9860
fax: 781.674.9861

e-mail: info@pmdcorp.com
www.pmdcorp.com

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MC3110DS2.0-1202

Environmental and Electrical Ratings

Storage Temperature (T_S)	-55° C to 150° C
Operating Temperature (T_A)	0° C to 70° C*
Power Dissipation (P_d)	650 mW
Nominal Clock Frequency (F_{CLK})	40.0 MHz
Supply Voltage Limits (V_{CC})	-0.3 V to +7.0 V
Supply Voltage Operating Range (V_{CC})	4.75 V to 5.25 V
Analog inputs	0 to 5.0 V dc

* An industrial version with an operating range of -40° C to 85° C is also available. Please contact PMD for more information.