

Description

The B40A20 PWM servo drive is designed to drive brushless DC motors at a high switching frequency. A single red/green LED indicates operating status. The drive is fully protected against over-voltage, under voltage, over-current, over-heating and short-circuits across motor, ground and power leads. Furthermore, the drive can interface with digital controllers or be used stand-alone, and requires only a single unregulated DC power supply. Loop gain, current limit, input gain and offset can be adjusted using 14-turn potentiometers. The offset adjusting potentiometer can also be used as an on-board input signal for testing purposes.

Power Range

| | |
|--------------------|--------------|
| Peak Current | 40 A |
| Continuous Current | 20 A |
| Supply Voltage | 40 - 190 VDC |


Features

- ▲ Four Quadrant Regenerative Operation
- ▲ DIP Switch Selectable Modes
- ▲ Adjustable Current Limits
- ▲ High Switching Frequency
- ▲ Differential Input Command
- ▲ On-Board Test Potentiometer
- ▲ Offset Adjustment Potentiometer
- ▲ Adjustable Input Gain
- ▲ Selectable 120/60 Hall Commutation Phasing
- ▲ Hall Velocity Mode
- ▲ Drive Status LED
- ▲ Velocity Monitor Outputs

MODES OF OPERATION

- Current
- Open Loop
- Hall Velocity
- Tachometer Velocity

COMMAND SOURCE

- ± 10 V Analog

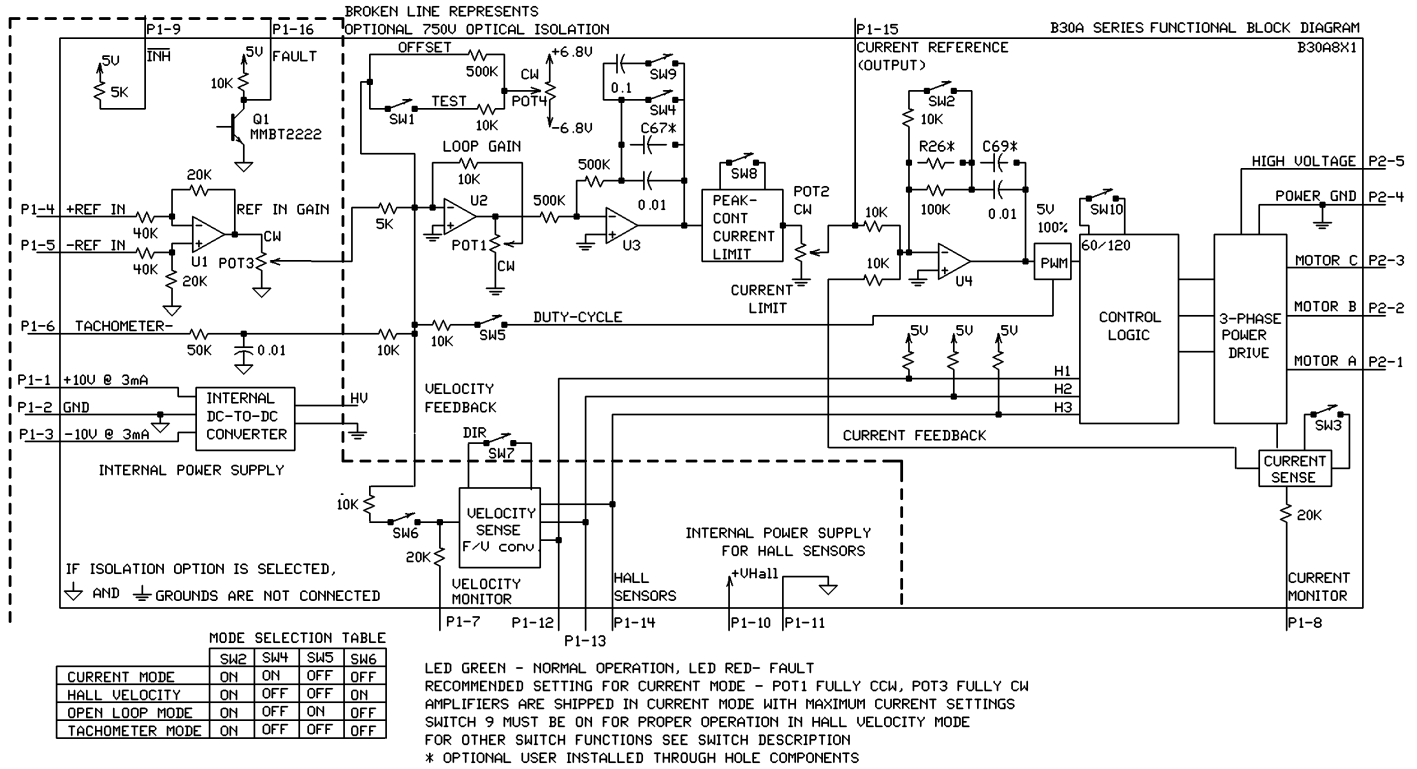
FEEDBACK SUPPORTED

- Halls
- Tachometer




COMPLIANCES & AGENCY APPROVALS

- UL
- cUL
- CE Class A (LVD)
- CE Class A (EMC)
- RoHS

BLOCK DIAGRAM



Information on Approvals and Compliances

| | |
|---|---|
|  | <p>US and Canadian safety compliance with UL 508c, the industrial standard for power conversion electronics. UL registered under file number E140173. Note that machine components compliant with UL are considered UL registered as opposed to UL listed as would be the case for commercial products.</p> |
|  | <p>Compliant with European CE for both the Class A EMC Directive 89/336/EEC on Electromagnetic Compatibility (specifically EN 61000-6-4:2001, EN 61000-6-2:2001, EN 61000-3-2:2000, and EN 61000-3-3:1995/A1:2001) and LVD requirements of directive 73/23/EEC (specifically EN 60204-1), a low voltage directive to protect users from electrical shock.</p> |
|  | <p>RoHS (Reduction of Hazardous Substances) is intended to prevent hazardous substances such as lead from being manufactured in electrical and electronic equipment.</p> |

SPECIFICATIONS

| Power Specifications | | |
|---|---------|--|
| Description | Units | Value |
| DC Supply Voltage Range | VDC | 40 - 190 |
| DC Bus Over Voltage Limit | VDC | 195 |
| Maximum Peak Output Current ¹ | A | 40 |
| Maximum Continuous Output Current | A | 20 |
| Maximum Power Dissipation at Continuous Current | W | 190 |
| Minimum Load Inductance (Line-To-Line) ² | μH | 250 |
| Switching Frequency | kHz | 22 |
| Control Specifications | | |
| Description | Units | Value |
| Command Sources | - | ±10 V Analog |
| Feedback Supported | - | Halls, Tachometer |
| Commutation Methods | - | Trapezoidal |
| Modes of Operation | - | Current, Hall Velocity, Open Loop, Tachometer Velocity |
| Motors Supported | - | Brushed, Brushless, Voice Coil |
| Hardware Protection | - | Invalid Commutation Feedback, Over Current, Over Temperature, Over Voltage, Short Circuit (Phase-Phase & Phase-Ground) |
| Mechanical Specifications | | |
| Description | Units | Value |
| Agency Approvals | - | CE Class A (EMC), CE Class A (LVD), cUL, RoHS, UL |
| Size (H x W x D) | mm (in) | 186.7 x 111.7 x 25.4 (7.4 x 4.4 x 1) |
| Weight | g (oz) | 680 (24) |
| Heatsink (Base) Temperature Range ³ | °C (°F) | 0 - 65 (32 - 149) |
| Storage Temperature Range | °C (°F) | -40 - 85 (-40 - 185) |
| Form Factor | - | Stand Alone |
| P1 Connector | - | 16-pin, 2.54 mm spaced, friction lock header |
| P2 Connector | - | 5-port, 5.08 mm spaced, screw terminal |

Notes

1. Maximum duration of peak current is ~2 seconds.
2. Lower inductance is acceptable for bus voltages well below maximum. Use external inductance to meet requirements.
3. Additional cooling and/or heatsink may be required to achieve rated performance.

PIN FUNCTIONS

| P1 - Signal Connector | | | |
|-----------------------|------------------|--|-----|
| Pin | Name | Description / Notes | I/O |
| 1 | +10V 3mA OUT | ±10 V @ 3 mA low power supply for customer use. Short circuit protected. Reference ground common with signal ground. | O |
| 2 | SIGNAL GND | | GND |
| 3 | -10V 3mA OUT | | O |
| 4 | +REF IN | Differential Reference Input (±10 V Operating Range, ±15 V Maximum Input) | I |
| 5 | -REF IN | | I |
| 6 | -TACH IN | Negative Tachometer Input (Maximum ±60 V). Use signal ground for positive input. | I |
| 7 | VEL MONITOR OUT | Velocity Monitor. Analog output proportional to motor speed. In Hall Velocity mode, output is proportional to the electrical cycle frequency. Hall Velocity scaling is 134 Hz/V. | O |
| 8 | CURR MONITOR OUT | Current Monitor. Analog output signal proportional to the actual current output. Scaling is 4.1 A/V by default but may be reduced to half this value by setting DIP switch SW-3 to OFF (see Hardware Settings section below). Measure relative to signal ground. | O |
| 9 | INHIBIT IN | TTL level (+5 V) inhibit/enable input. Leave open to enable drive. Pull to ground to inhibit drive. Inhibit turns off all power devices. | I |
| 10 | +V HALL 30mA OUT | Low Power Supply For Hall Sensors (+6 V @ 30 mA). Referenced to signal ground. Short circuit protected. | O |
| 11 | GND | Signal Ground | GND |
| 12 | HALL 1 | Single-ended Hall/Commutation Sensor Inputs (+5 V logic level) | I |
| 13 | HALL 2 | | I |
| 14 | HALL 3 | | I |
| 15 | CURRENT REF OUT | Measures the command signal to the internal current-loop. This pin has a maximum output of ±7.25 V when the drive outputs maximum peak current. Measure relative to signal ground. | O |
| 16 | FAULT OUT | TTL level (+5 V) output becomes high when power devices are disabled due to at least one of the following conditions: inhibit, invalid Hall state, output short circuit, over voltage, over temperature, power-up reset. | O |

| P2 - Power Connector | | | |
|----------------------|--------------|--|-----|
| Pin | Name | Description / Notes | I/O |
| 1 | MOTOR A | Motor Phase A | O |
| 2 | MOTOR B | Motor Phase B | O |
| 3 | MOTOR C | Motor Phase C | O |
| 4 | POWER GND | Power Ground (Common With Signal Ground) | GND |
| 5 | HIGH VOLTAGE | DC Power Input | I |

HARDWARE SETTINGS

Switch Functions

| Switch | Description | Setting | |
|--------|---|------------------------|------------------------|
| | | On | Off |
| 1 | Test/Offset. Switches the function of the Test/Offset pot between an on-board command input for testing or a command offset adjustment. OFF by default. | Test | Offset |
| 2 | Current loop proportional gain adjustment. ON by default. | Decrease | Increase |
| 3 | Current scaling. When OFF, increases sensitivity of current sense thus reducing both peak and continuous current limit by 50%. The scaling of the current monitor output signal becomes ½ its ordinary value when this switch is OFF. | Full-current | Half-current |
| 4 | Outer loop integration. Activates or deactivates integration. ON, by default, for current mode and OFF for other modes. | Inactive | Active |
| 5 | Mode selection. See mode selection table below. | - | - |
| 6 | Mode selection. See mode selection table below. | - | - |
| 7 | Velocity feedback polarity. Changes the polarity of the internal feedback signal and the velocity monitor output signal. Inversion of the feedback polarity may be required to prevent a motor run-away condition. | Standard | Inverted |
| 8 | Current ratio. Used to set continuous-to-peak current ratio. Default is ON. | Cont./Peak Ratio = 50% | Cont./Peak Ratio = 25% |
| 9 | Outer loop integral gain adjustment. It is recommended to leave this switch OFF for most applications, but ON for Hall Velocity Mode. | Decrease | Increase |
| 10 | Hall sensor phasing. Selects 120°/60° commutation phasing. ON by default. | 120° | 60° |

Mode Selection Table

| | SW2 | SW4 | SW5 | SW6 | Tachometer |
|---------------------|-----|-----|-----|-----|---------------|
| CURRENT | ON | ON | OFF | OFF | Not Connected |
| OPEN LOOP | ON | OFF | ON | OFF | Not Connected |
| HALL VELOCITY* | ON | OFF | OFF | ON | Not Connected |
| TACHOMETER VELOCITY | ON | OFF | OFF | OFF | Connected |

*NOTE: See details of switch 7 and 9 for further Hall Velocity configuration information.

Potentiometer Functions

| Potentiometer | Description | Turning CW |
|---------------|--|--------------------------------------|
| 1 | Loop gain adjustment for open loop / velocity modes. Turn this pot fully CCW in current mode. | Increases gain |
| 2 | Current limit. It adjusts both continuous and peak current limit while maintaining their ratio. | Increases limit |
| 3 | Reference gain. Adjusts the ratio between input signal and output variables (voltage, current, or velocity). | Increases gain |
| 4 | Offset / Test. Used to adjust any imbalance in the input signal or in the amplifier. Can also be used as an on-board signal source for testing purposes. | Adjusts offset in negative direction |

Note: Potentiometers are approximately linear and have 12 active turns with 1 inactive turn on each end.

Through-hole Components[†]

| Location | Description |
|----------|--|
| C67* | Velocity Loop Integrator. Through-hole capacitor that can be added for more precise velocity loop tuning. See section below on Tuning with Through-hole components for more details. |
| C69* | Current Loop Integrator. Through-hole capacitor that can be added for more precise current loop tuning. See section below on Tuning with Through-hole components for more details. |
| R26* | Current Loop Proportional Gain. Through-hole resistor that can be added for more precise current loop tuning. See section below on Tuning with Through-hole components for more details. |

Tuning With Through-hole Components

In general, the drive will not need to be further tuned with through-hole components. However, for applications requiring more precise tuning than what is offered by the potentiometers and dipswitches, the drive can be manually modified with through-hole resistors and capacitors as denoted in the above table. By default, the through-hole locations are not populated when the drive is shipped. Before attempting to add through-hole components to the board, consult the section on loop tuning in the installation notes on the manufacturer's website. Some general rules of thumb to follow when adding through-hole components are:

- A larger resistor value will increase the proportional gain, and therefore create a faster response time.
- A larger capacitor value will increase the integration time, and therefore create a slower response time.

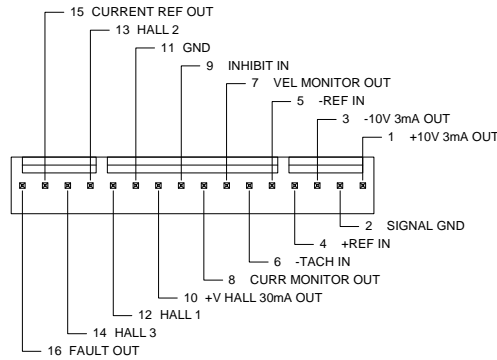
Proper tuning using the through-hole components will require careful observation of the loop response on a digital oscilloscope to find the optimal through-hole component values for the specific application.

[†]Note: Damage done to the drive while performing these modifications will void the warranty.

MECHANICAL INFORMATION

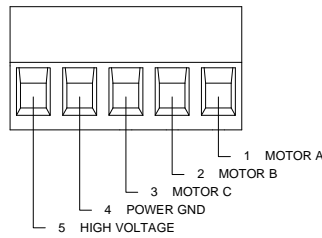
P1 - Signal Connector

| | | |
|-----------------------|--|---|
| Connector Information | 16-pin, 2.54 mm spaced, friction lock header | |
| Mating Connector | Details | Molex: P/N 22-01-3167 (connector) and P/N 08-50-0114 (insert terminals) |
| | Included with Drive | Yes |

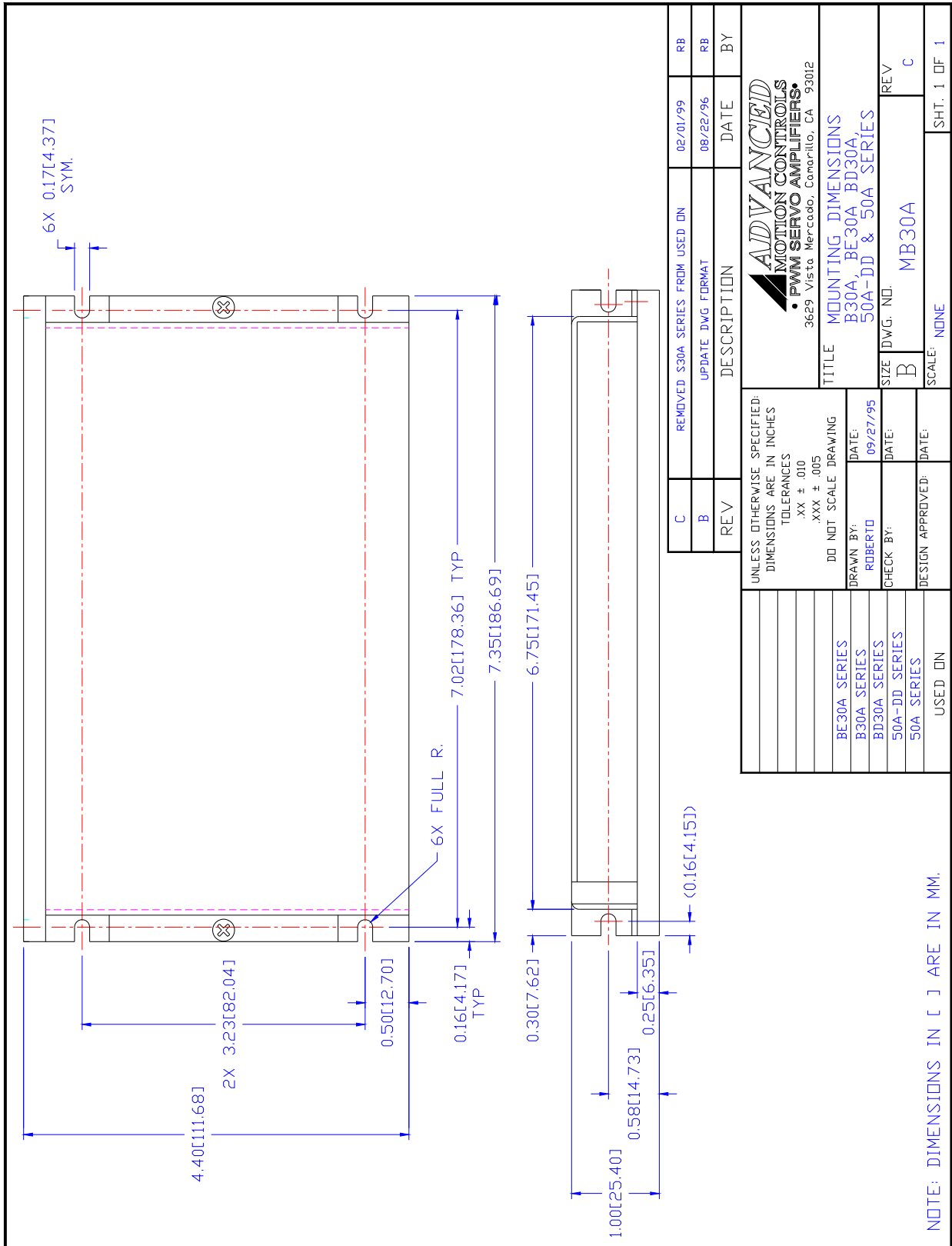


P2 - Power Connector

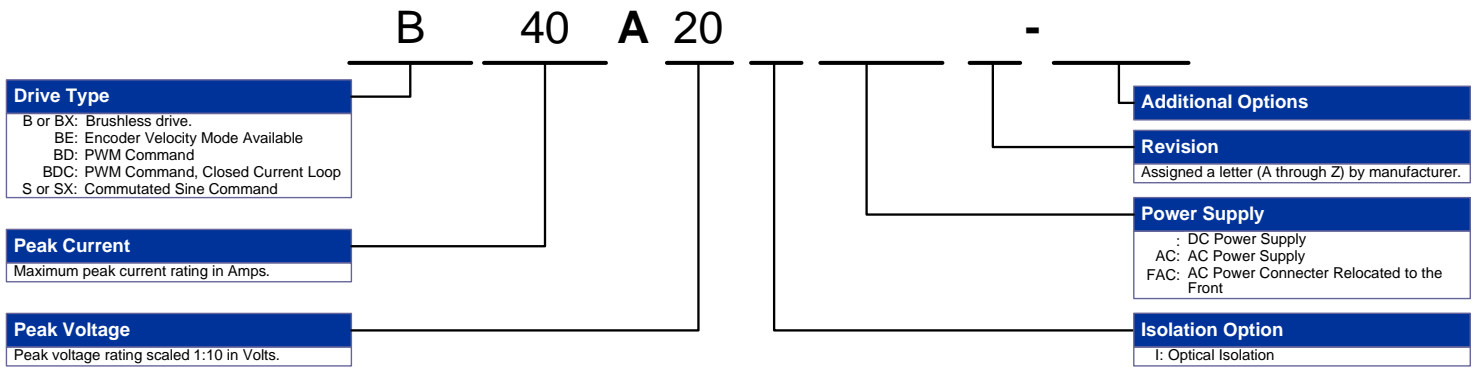
| | | |
|-----------------------|--|----------------|
| Connector Information | 5-port, 5.08 mm spaced, screw terminal | |
| Mating Connector | Details | Not applicable |
| | Included with Drive | Not applicable |



MOUNTING DIMENSIONS



PART NUMBERING INFORMATION



ADVANCED Motion Controls servo drives are available in many configurations. All models listed in the selection tables of the website are readily available, standard product offerings.

ADVANCED Motion Controls also has the capability to promptly develop and deliver specified products for OEMs with volume requests. Our Applications and Engineering Departments will work closely with your design team through all stages of development in order to provide the best servo drive solution for your system. Equipped with on-site manufacturing for quick-turn customs capabilities, ADVANCED Motion Controls utilizes our years of engineering and manufacturing expertise to decrease your costs and time-to-market while increasing system quality and reliability.

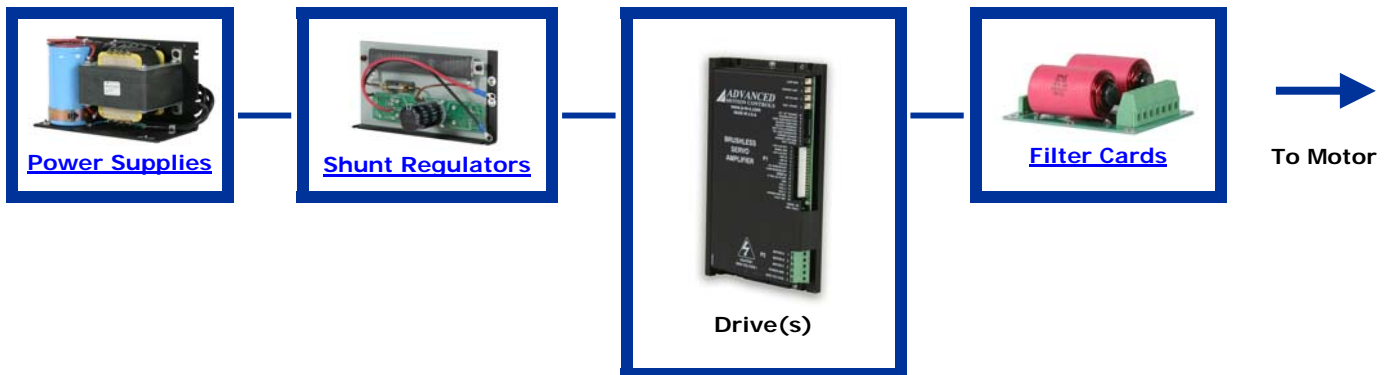
Examples of Customized Products

- ▲ Integration of Drive into Motor Housing
- ▲ Mount OEM PCB onto Drive Without Cables
- ▲ Multi-axis Configuration for Compact System
- ▲ Custom PCB and Baseplate for Optimized Footprint
- ▲ RTV/Epoxy Components for High Vibration
- ▲ OEM Specified Connectors for Instant Compatibility
- ▲ OEM Specified Silkscreen for Custom Appearance
- ▲ Increased Thermal Limits for High Temp. Operation
- ▲ Integrate OEM Circuitry onto Drive PCB
- ▲ Custom Control Loop Tuned to Motor Characteristics
- ▲ Custom I/O Interface for System Compatibility
- ▲ Preset Switches and Pots to Reduce User Setup
- ▲ Optimized Switching Frequency
- ▲ Ramped Velocity Command for Smooth Acceleration
- ▲ Remove Unused Features to Reduce OEM Cost
- ▲ Application Specific Current and Voltage Limits

Feel free to contact Applications Engineering for further information and details.

Available Accessories

ADVANCED Motion Controls offers a variety of accessories designed to facilitate drive integration into a servo system. Visit www.a-m-c.com to see which accessories will assist with your application design and implementation.



All specifications in this document are subject to change without written notice. Actual product may differ from pictures provided in this document.