

PIN FUNCTIONS

| P1 - Signal Connector | | | |
|-----------------------|--------------------------------|--|-----|
| Pin | Name | Description / Notes | I/O |
| 1 | +REF IN | Differential Reference Input (± 10 V Operating Range, ± 15 V Maximum Input) | I |
| 2 | SIGNAL GND | Signal Ground | GND |
| 3 | -REF IN | Differential Reference Input (± 10 V Operating Range, ± 15 V Maximum Input) | I |
| 4 | CURRENT MONITOR | Current Monitor. Analog output signal proportional to the actual current output. Scaling is 2 A/V. Measure relative to signal ground. | O |
| 5 | $\overline{\text{INHIBIT IN}}$ | 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 |
| 6 | +V HALL OUT | Low Power Supply For Hall Sensors (+6 V @ 30 mA). Referenced to signal ground. Short circuit protected. | O |
| 7 | SIGNAL GND | Signal Ground | GND |
| 8 | HALL 1 | Single-ended Hall/Commutation Sensor Inputs (+5 V logic level) | I |
| 9 | HALL 2 | | I |
| 10 | HALL 3 | | I |
| 11 | CURRENT REFERENCE | Measures the command signal to the internal current-loop. This pin has a maximum output of ± 7.45 V when the drive outputs maximum peak current. Measure relative to signal ground. | O |
| 12 | 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 |
| 13 | ENCODER-B IN | Single-ended encoder channel B input. +5 V logic level. | I |
| 14 | ENCODER-A IN | Single-ended encoder channel A input. +5 V logic level. | I |
| 15 | VEL MONITOR OUT / TACH IN | Velocity Monitor. Analog output proportional to motor speed. In Encoder Velocity mode, output is proportional to the encoder line frequency. Encoder Velocity scaling is 22 kHz/V. For Tachometer Velocity mode, feedback voltage range is ± 60 VDC max. | O/I |
| 16 | OFFSET | Connection to external resistance for command offset adjustments. Apply a ± 10 V (10V Max) signal through an external potentiometer into this pin to offset the input gain. | I |

| P2 - Power Connector | | | |
|----------------------|--------------|---|-----|
| Pin | Name | Description / Notes | I/O |
| 1 | HIGH VOLTAGE | DC Power Input. 3A Continuous Current Rating Per Pin. | I |
| 2 | HIGH VOLTAGE | | I |
| 3 | NC (KEY) | Key: No Connection (pin removed) | - |
| 4 | PWR GND | Power Ground (Common With Signal Ground). 3A Continuous Current Rating Per Pin | GND |
| 5 | PWR GND | | GND |
| 6 | MOTOR C | Motor Phase Outputs. Current output distributed equally across 2 pins per motor phase, 3A continuous current carrying capacity per pin. | O |
| 7 | MOTOR C | | O |
| 8 | MOTOR B | | O |
| 9 | MOTOR B | | O |
| 10 | MOTOR A | | O |
| 11 | MOTOR A | | O |

HARDWARE SETTINGS

Switch Functions

| Switch | Description | Setting | |
|--------|--|-----------------|-------------|
| | | On | Off |
| 1 | Duty Cycle mode selector. Activates internal PWM feedback. | Duty Cycle mode | Other modes |
| 2 | Activate velocity feedback or monitor. For Encoder Velocity mode, activates feedback. For Current mode, activates velocity monitor. | Active | Inactive |
| 3 | Current mode selector. | Current mode | Other modes |
| 4 | 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 |

Mode Selection Table

| | SW1 | SW2 | SW3 |
|---------------------|-----|-----|-----|
| CURRENT | OFF | ON | ON |
| DUTY CYCLE | ON | OFF | OFF |
| ENCODER VELOCITY* | OFF | ON | OFF |
| TACHOMETER VELOCITY | OFF | OFF | OFF |

*NOTE: See details of switch 4 for further Encoder Velocity configuration information.

Jumper Settings

Jumpers are SMT, 0 ohm resistors located on the underside of the drive PCB. By default, the drive is configured with the jumpers installed. Typical drive operation will not require the jumpers to be removed. Please contact the factory before jumper removal.

| Jumper | Description | Configuration | |
|--------|---|---------------|-------------|
| | | Not Installed | Installed |
| JE1 | Inhibit logic. Sets the logic level of inhibit pins. Labeled JE1 on the PCB of the drive. | Low Enable | Low Inhibit |
| JE2 | Hall sensor phasing. Selects 120 or 60 degree commutation phasing. Labeled JE2 on the PCB of the drive. | 60 degree | 120 degree |

Potentiometer Functions

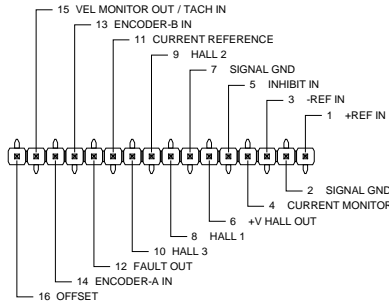
Potentiometers are located between the PCB and the drive baseplate, and are accessible from the side. Potentiometers are approximately linear and have 12 active turns with 1 inactive turn on each end.

| Potentiometer | Description | Turning CW |
|---------------|--|--------------------------------------|
| 1 | Loop gain adjustment for duty cycle / velocity modes. Turn this pot fully CCW in current mode. Located closest to the corner of the PCB. | Increases gain |
| 2 | Offset. Used to adjust any imbalance in the input signal or in the amplifier. Located furthest from the corner of the PCB. | Adjusts offset in negative direction |

MECHANICAL INFORMATION

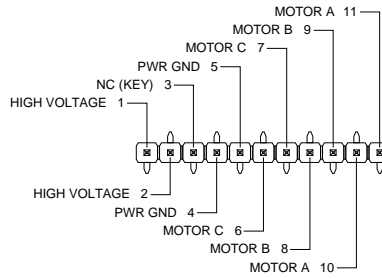
P1 - Signal Connector

| | | |
|-----------------------|---------------------|-------------------------------|
| Connector Information | | 16-pin, 2.54 mm spaced header |
| Mating Connector | Details | Samtec: BCS-116-L-S-PE |
| | Included with Drive | No |

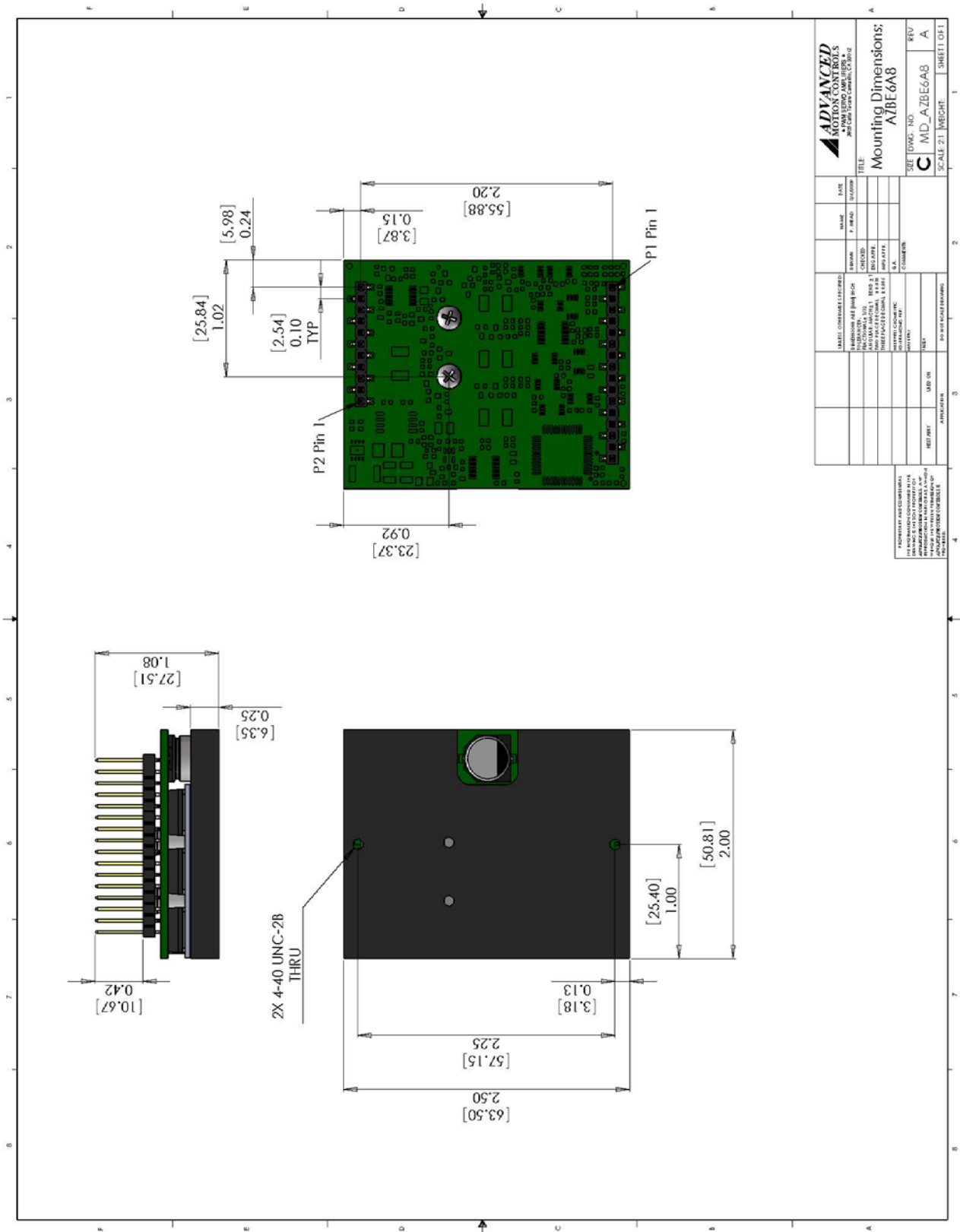


P2 - Power Connector

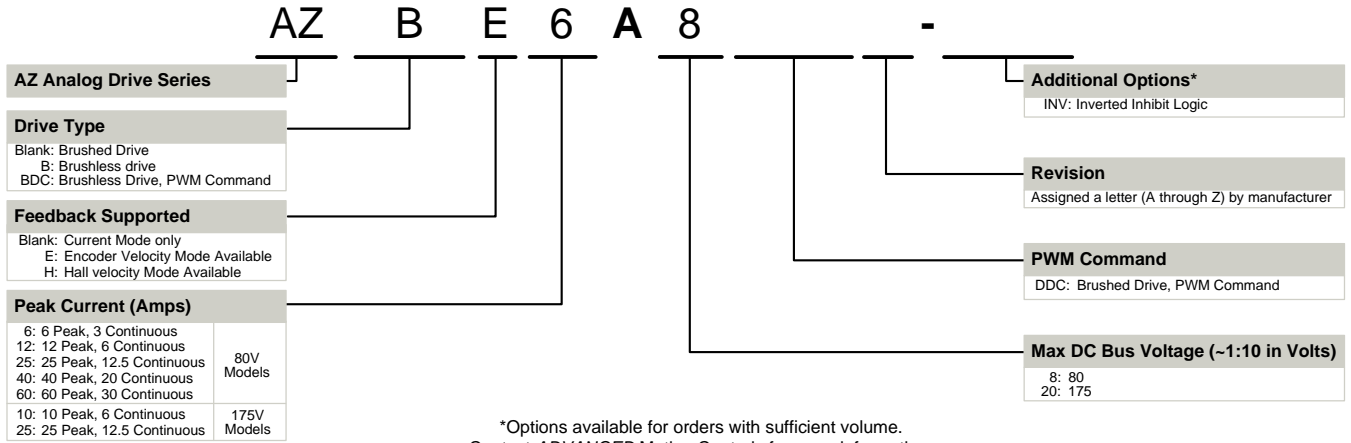
| | | |
|-----------------------|---------------------|-------------------------------|
| Connector Information | | 11-pin, 2.54 mm spaced header |
| Mating Connector | Details | Samtec: BCS-111-L-S-PE |
| | Included with Drive | No |



MOUNTING DIMENSIONS



PART NUMBERING INFORMATION



ADVANCED Motion Controls AZ series of servo drives are available in many configurations. Note that not all possible part number combinations are offered as standard drives. 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.

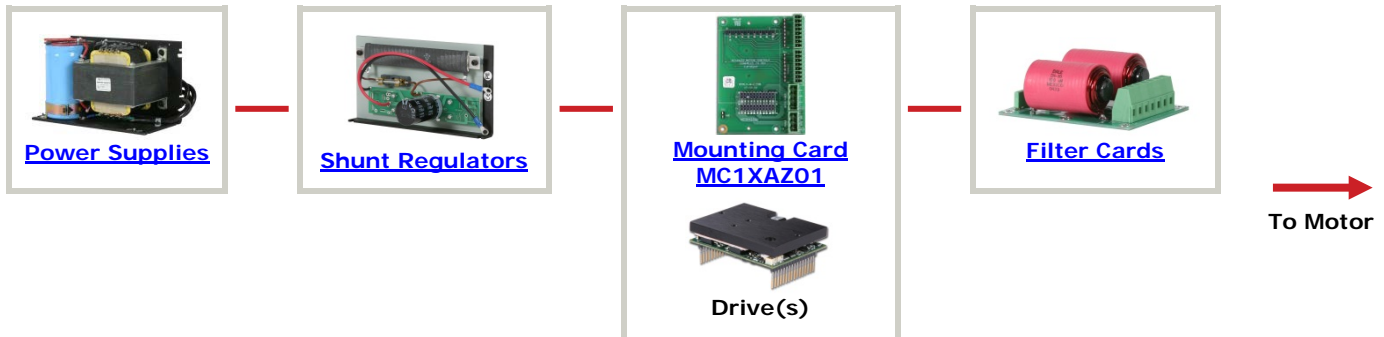
Examples of Modifications and Customized Products

- ▲ 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.