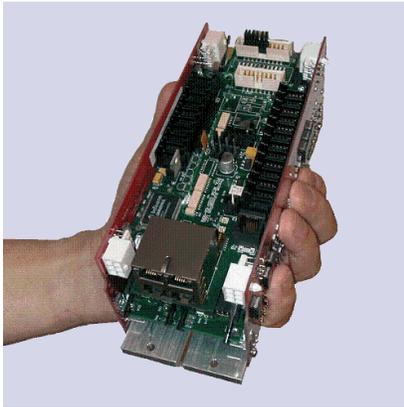




Guidance 3000/2000 Controllers



Hardware Introduction and Reference Manual

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Precise Automation Inc.
727 Filip Road
Los Altos, California 94024
U.S.A.
www.preciseautomation.com

Warning Labels

The following warning and caution labels are utilized throughout this manual to convey critical information required for the safe and proper operation of the hardware and software. It is extremely important that all such labels are carefully read and complied with in full to prevent personal injury and damage to the equipment.

There are four levels of special alert notation used in this manual. In descending order of importance, they are:



DANGER: This indicates an imminently hazardous situation, which, if not avoided, will result in death or serious injury.



WARNING: This indicates a potentially hazardous situation, which, if not avoided, could result in serious injury or major damage to the equipment.



CAUTION: This indicates a situation, which, if not avoided, could result in minor injury or damage to the equipment.

NOTE: This provides supplementary information, emphasizes a point or procedure, or gives a tip for easier operation

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Introduction to the Hardware

System Overview

System Description

The Guidance family of motion controllers incorporates a distributed control architecture that utilizes Ethernet for real-time communication. Each motion controller on the network includes a motion/vision processor and one or more optional motor drives. Up to 16 motion controllers can be placed on a single network. The controllers can be wired in a daisy-chain topology to minimize the number of wires in a machine although a star topology has certain advantages and is also supported.

The Guidance 3000 Controllers include integrated motor drives. They require an external 24 VDC supply for the logic and IO and a separate external motor power supply. The motor power supply voltage can range from 24 VDC to 320 VDC, allowing a wide range of motor sizes and powers to be controlled. These motion controllers are very compact and are intended to be placed near the point of use, which in many cases means they will be installed inside the machine rather than in an external control cabinet. The 3000 Series includes a dual axis (Guidance 3200) and a four axis (Guidance 3400) controller with integrated drives. For applications that only require motor voltages from 24 VDC to 90 VDC, the Guidance 2000 series of motion controllers provide the same functionality as the 3000 series at a reduced cost. In addition, the controller can be provided without the motor drives and only DAC channels to allow control of up to 4 (Guidance 0004) or 6 (Guidance 0006) external amplifiers. Since the Guidance 3400 Controller is the most general product and a superset of the functional contained in the other controllers, for simplicity, much of this document will focus on the 3400 model.

Motion axes can be grouped into “robots”, which are defined by a geometric (“kinematic”) model. A “robot” has a master controller that executes the kinematic model and sends out axes position commands to any slave controllers. The logical grouping of axes into robots is independent of the physical configuration of the motion controllers. For example, two single-axis controllers and one four-axis controller can be logically grouped into a six-axis robot, with one of the controllers designated as the master, and the other two as slaves. Motion can also be coordinated among robots on the same network. For example a four-axis robot can be coordinated with a two-axis robot.

Each Guidance Controller can have several types of peripherals attached to it. These include cameras, remote I/O, and a remote front panel. Only one front panel is required per networked group of controllers.

The controller is programmed by means of a PC connected through Ethernet. There are three programming modes: a Digital IO (PLC) mode, an Embedded Language mode, and a PC Control mode. When programmed in the PLC or Embedded Language mode, the PC can be removed after programming is completed and the controller will operate standalone. The PC is required for operation in the PC Control mode.

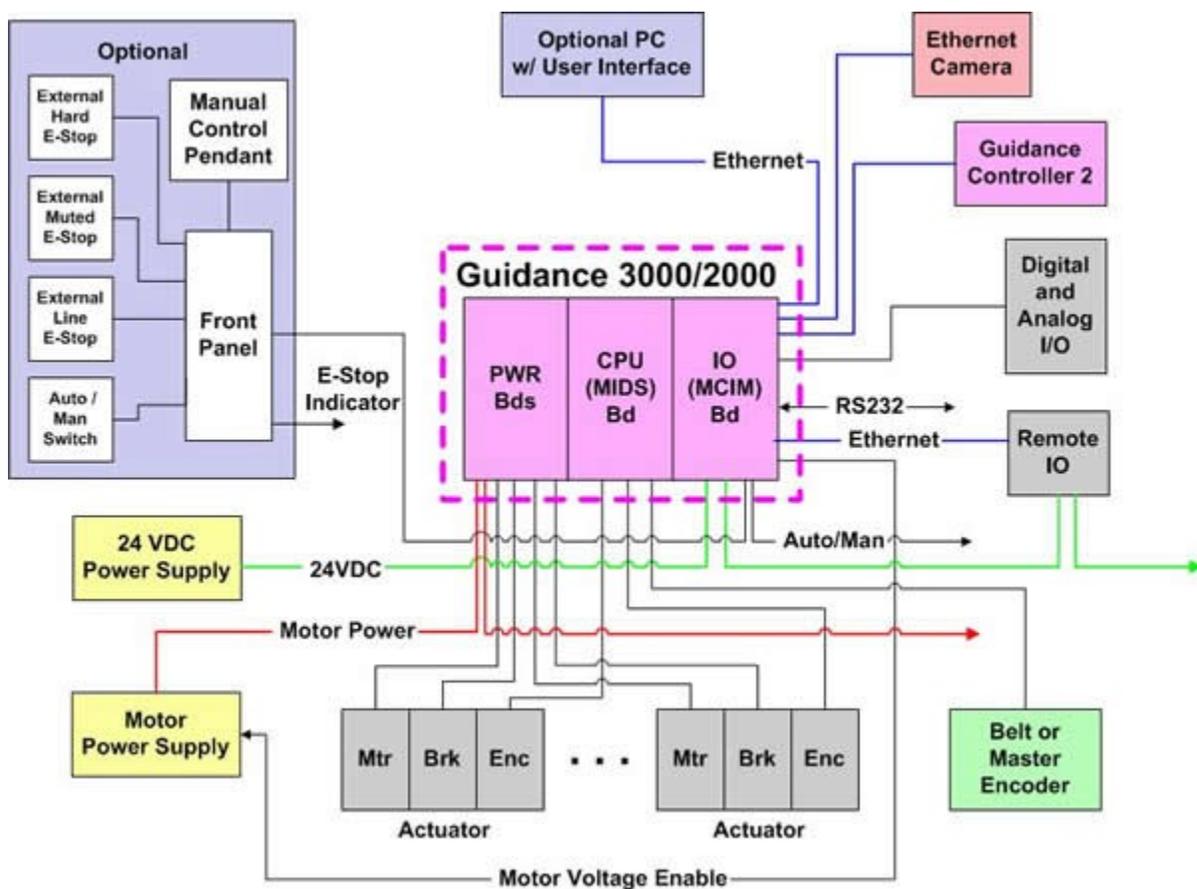
In all modes of operation, the controller includes a web based operator interface. This interface is used for configuring the system, starting and stopping execution, and monitoring its operation. The web interface can be accessed locally using a browser or remotely via the Internet. This remote interface is of great benefit in system maintenance and debugging.

Guidance 3000/2000 Controllers

The machine vision system, "PreciseVision", can execute either in a PC connected through Ethernet, or (in the future) for less demanding applications, in the motion controller processor. PreciseVision requires cameras to be connected via Ethernet, allowing any processor on the network to obtain and process information from any camera on the network, and provide the results to any motion controller on the network.

System Diagram

The Guidance 3000/2000 Series system diagram is shown below. The controller is configured to support Category 3 safety applications where required. An optional Front Panel will soon be available that contains Category 3 interlock circuitry as well as a keyed auto/manual switch, a high power button, and an E-Stop button. This front panel is not necessary for the system to operate. Users may wire their own E-Stop circuitry directly to the controller. An Ethernet Switch on the IO board allows Ethernet cameras to be plugged directly into the IO board where they can be accessed locally by the motion processor or remotely by a PC. A third party RS170 to Ethernet camera converter is available for users who wish to use RS170 cameras. External amplifiers can be interfaced via optional +/- 10VDC DAC outputs.



System Components

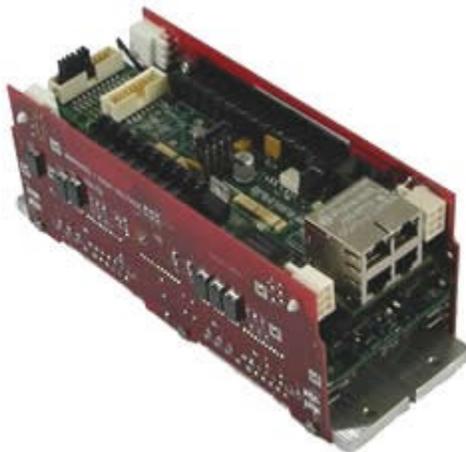
Guidance Controllers

All Guidance Controllers utilize either a standard or enhanced high performance processor (MIDS) board that is mated to one of several types of communications (MCIM) boards. The standard features provided by all controllers include: four dedicated encoder inputs, four configurable encoder inputs, 12 general purpose optically isolated digital inputs, 8 general purpose optically isolated digital outputs, 2 analog inputs, 2 RS-232 ports, 1 to 4 Ethernet ports, and an EC Category 3 compliant front panel interface with redundant E-stop circuits. The "enhanced" MIDS board adds support for analog and selected absolute encoders. Special versions of the MCIM board add 4 or 6 optional instrument grade +/- 10 VDC DAC channels that can interface to external motor amplifiers.

The Guidance 3000 series are the most general purpose controllers and include either two or four integrated motor drives. The drives can control motors that operate at bus voltages between 24 VDC and 320 VDC. The total motor power output of the controller is a function of the size of the heat sink on which it is mounted. The four amplifier version of this controller, the Guidance 3400 that can provide up to 20A peak current for each motor, is shown immediately below. The second picture is the Guidance 3430 that can provide up to 30A peak current for each motor.



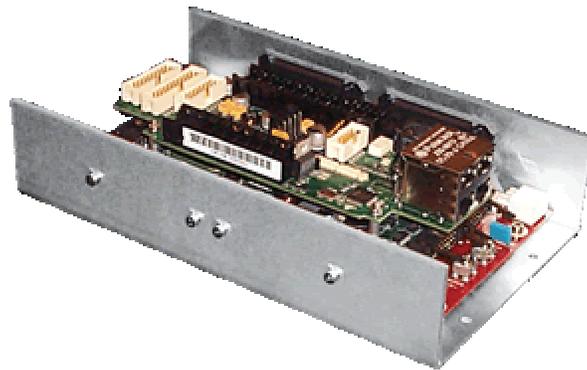
DANGER: The Guidance Controllers are open frame electrical devices that contain unshielded high voltage pins, components and surfaces. These products are intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.



Guidance 3000/2000 Controllers



For mechanisms with motors that operate between 24 VDC and 90 VDC, the Guidance 2000 Controllers offer the same capabilities as the Guidance 3000 series at a lower cost. The four drive Guidance 2400 is shown below.



For applications that require control of external 3rd party amplifiers and do not need integrated motor drives, the Guidance 0006 and 0004 are very compact, high performance controllers that include 6 or 4 DAC's at a very cost effective price. The Guidance 0006 is pictured below.



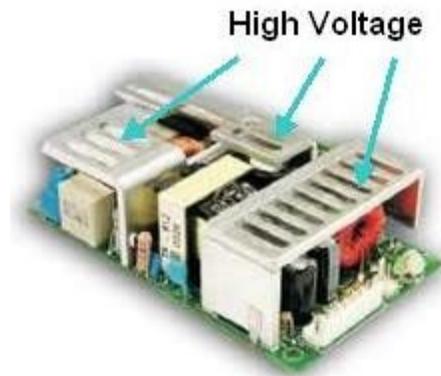
Low Voltage Power Supply

The Guidance Controllers require 0.7 amps of 24 VDC power for logic power and 2 amps for IO power for a total of 2.7 amps. An additional amp is required if this supply also drives the contactors on the motor power supply. For applications using remote IO or Ethernet cameras, Precise recommends a total of 5 amps. This voltage may be supplied by a user power supply or a 24 VDC power supply may be purchased from Precise.

A commercially available 125-watt, 24 VDC Power Supply, Mean Well P/N PPS-125-24, with AC input from 90V to 264V, is shown below.



DANGER: The 24VDC logic power supply is an open frame electrical device that has exposed unshielded high voltage pins, components and surfaces. In addition, **the heat sinks on the 24VDC Power Supply are not grounded and expose high voltage levels.** This product is intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.



Intelligent Motor Power Supplies

The Guidance 3000 Controllers can accept motor power from 24 VDC to 320 VDC. Precise offers two Intelligent Motor Power Supplies: the PrecisePower 500 and the PrecisePower 2000. These units include: integral relays for enabling/disabling motor power on command from the controller, large value output filter capacitors to store deceleration energy for use when power is needed, the ability to absorb line spikes, and built-in fuses.



DANGER: The PrecisePower Intelligent Motor Power Supplies are open frame electrical devices that have exposed unshielded high voltage pins, components and surfaces. In addition, these power supplies provide 340VDC volts and take several minutes to bleed down after power is disconnected. These products are intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Guidance 3000/2000 Controllers

The PrecisePower 500 (shown below) is a 500 watt auto-ranging power supply with dual input ranges of 90 to 132 VAC and 180 to 264 VAC 50/60 Hz and a 320 VDC output. This unit includes a single integral relay for enabling and disabling motor power from the controller.



As a rule-of-thumb, 500 watts from the power supply can normally drive motors with a total rating of approximately 2000 watts. This is due to the fact that motor power ratings are typically defined by the "rated torque" that can be supplied at the "rated speed" of a motor. However, in most robot applications, high torque is only required at low speed. For example, the PrecisePower 500 is being successfully used to drive a Cartesian robot at full speed where the sizes of its four motors are 750W, 400W, 200W and 100W (1450W total).

For applications requiring a larger intelligent motor power supply, the PrecisePower 2000 (shown below) delivers 2000 watts from a single-phase 208VAC service or 3400 watts from a three-phase 240VAC service. This unit includes dual integrated relays for enabling and disabling motor power on command from the controller. In addition, it has safety circuits to automatically shut-down the unit if it is switched to a short or is severely over-loaded.



Remote Front Panel, E-Stop Box and Manual Control Pendant

Precise plans to offer a remote front panel that contains a high power enable button, an auto/manual keyed selector switch, an E-Stop button, and a back panel connector for user E-Stops and interlocks. This unit will plug into the Remote Front Panel interface of the Guidance Controller. The controller can

operate without the remote front panel. When a front panel is not utilized, the following pins on the front panel connector must be jumpered. (All controllers are shipped with these jumpers installed.)

1-2, 3-4, 5-6, 7-8, 9-10, 11-12, 13-14

For systems that use more than one Precise Guidance Series Controller, the Auto/Manual signals can be daisy chained from controller to controller by connecting a ribbon cable from the 16-pin Auto/Manual daisy chain connector to either the front panel connector (pins 1-16) or the Auto/Manual daisy chain connector of the next controller.

The Guidance system supports several types of E-Stops, which will be connected at the rear connector of the Remote Front Panel. See the Controller Hardware Reference for a detailed description of the E-Stop and other Remote Front Panel Signals.

For users that wish to have an E-Stop button for their controller without a remote front panel, Precise sells an E-Stop Box with a connector pigtail that plugs into the remote front panel connector and includes the necessary jumpers.

For users who wish to have a Manual Control Pendant (MCP) that can be carried around the workcell, Precise offers a hardware MCP. The Precise MCP comes with a 25-pin DSub connector that directly attaches to PrecisePlace robots and the Guidance System. A 25-pin Dsub to 20-pin IDC connector adaptor cable is available for plugging the MCP into the Remote Front Panel connector of a Guidance 2000/3000 Controller. As with the E-Stop Box, the Precise MCP connector includes the necessary jumpers for the proper operation of the controller.



Remote IO Module

For applications that require additional IO capability beyond the standard functions provided with every Guidance Controller, a Precise Remote IO (RIO) module may be purchased. The RIO interfaces to any Guidance Controller via 10/100 Mb Ethernet and requires 24 VDC power. Up to 4 RIO's can be connected to a controller.

The basic RIO includes: 32 isolated digital input signals, 32 isolated digital output signals and one RS-232 serial line. An enhanced version of the RIO adds 4 analog input signals, a second RS-232 port and one RS-422/485 serial port. In addition, expansion boards will soon be offered that cost effectively add additional isolated digital inputs and outputs in groups of 32 each to the basic RIO.

The Enhanced RIO module is pictured below.



WARNING: The RIO contains unshielded 24 VDC signals and pins. This product is intended to be mounted in a cabinet or machine chassis that is not accessible when power is turned on.



Machine Vision Software and Cameras

All Guidance Controllers support the PreciseVision machine vision system. This is a vision software package that can run either on a PC for higher performance applications, or in the motion controller processor for simple applications (available in the future).

Cameras are connected to the processor via Ethernet. Vendors such as DALSA offer a variety of Ethernet machine vision cameras. In addition, vendors such as Pleora offer RS 170 to Ethernet converter boxes (iPORT PT-1000 ANL1/2/E) that allow a large variety of standard cameras to be connected to the Guidance network.

Machine Safety

Voltage and Power Considerations

The Guidance 3000 and 2000 Controllers require two DC power supplies: a 24 VDC power supply for the logic and user IO, and a separate motor power supply. The motor power supply must provide a voltage to the controller between 24 VDC and 320 VDC for the Guidance 3000 series and between 24 VDC and 90 VDC for the Guidance 2000 series.



DANGER: The Guidance 3000/2000, the PrecisePower Intelligent Motor Power Supplies, and the 24 VDC power supply are all open frame electrical devices that contain unshielded high voltage pins, components and surfaces. These products are intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Precise offers two Intelligent Motor Power Supplies: the 500-watt auto-ranging PrecisePower 500 with dual input ranges of 90 to 132 VAC and 180 to 264 VAC 50/60 Hz and the 2000-watt PrecisePower 2000 that operates between 90-240VAC single or three phase, 50/60Hz. These motor power supplies contain relays for enabling and disabling motor power from the controller.

The PrecisePower Intelligent Motor Power Supplies limit inrush current to approximately 6 Amps. They are protected against voltage surge to 2000 volts by means of MOVs at the line input. Transient over voltage (< 50 μ s) may not exceed 2000 V phase to ground, as per EN61800-31996. They are protected against over current by fast acting 250V fuses.

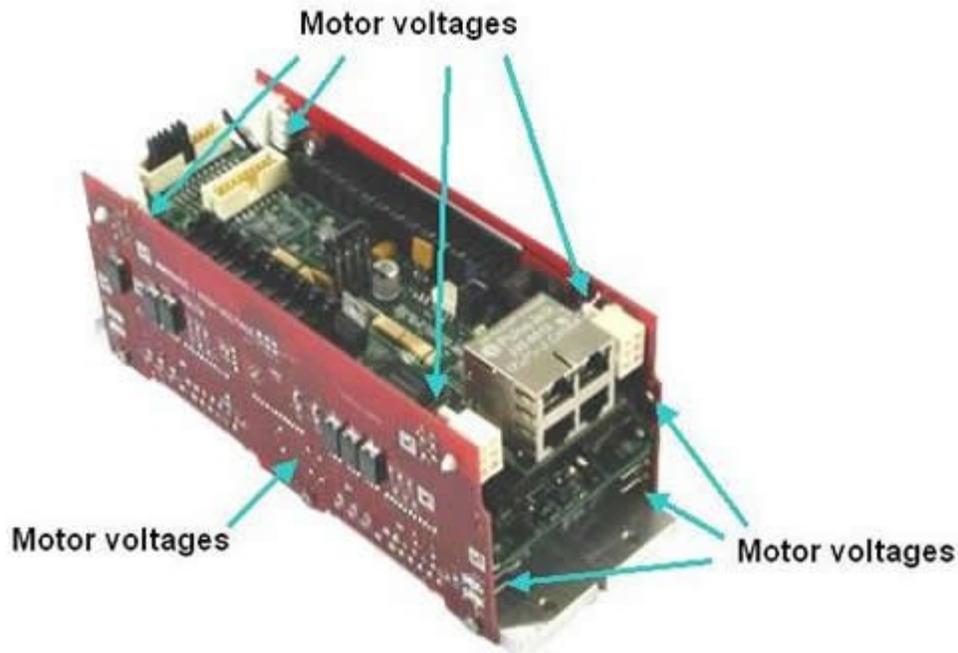
The Precise controller can monitor motor power through its datalogging function. Intermittent power dropouts can be detected by setting a trigger in the data logger which can record and time-stamp power fluctuations.

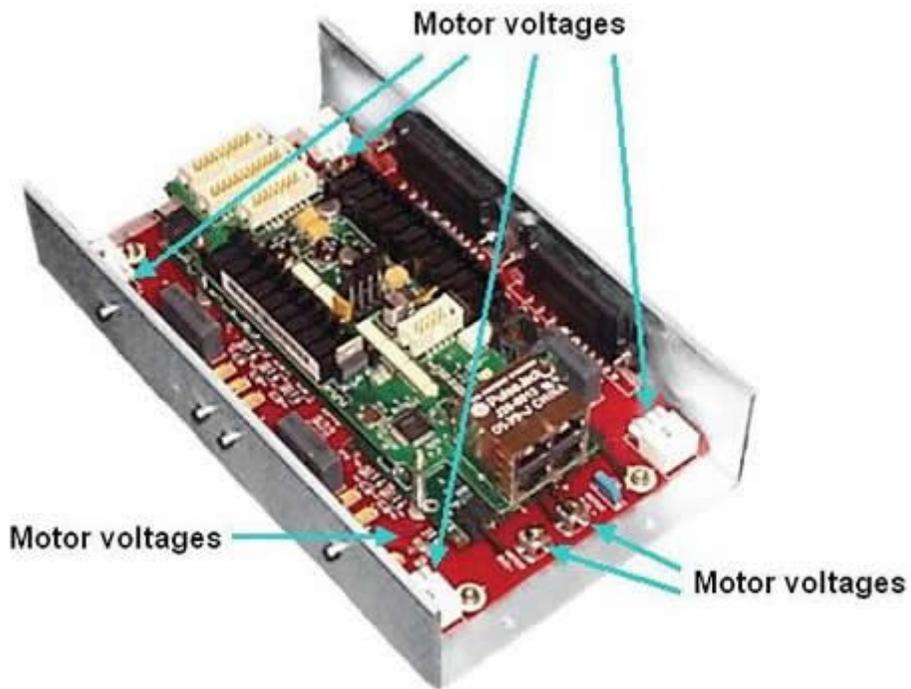
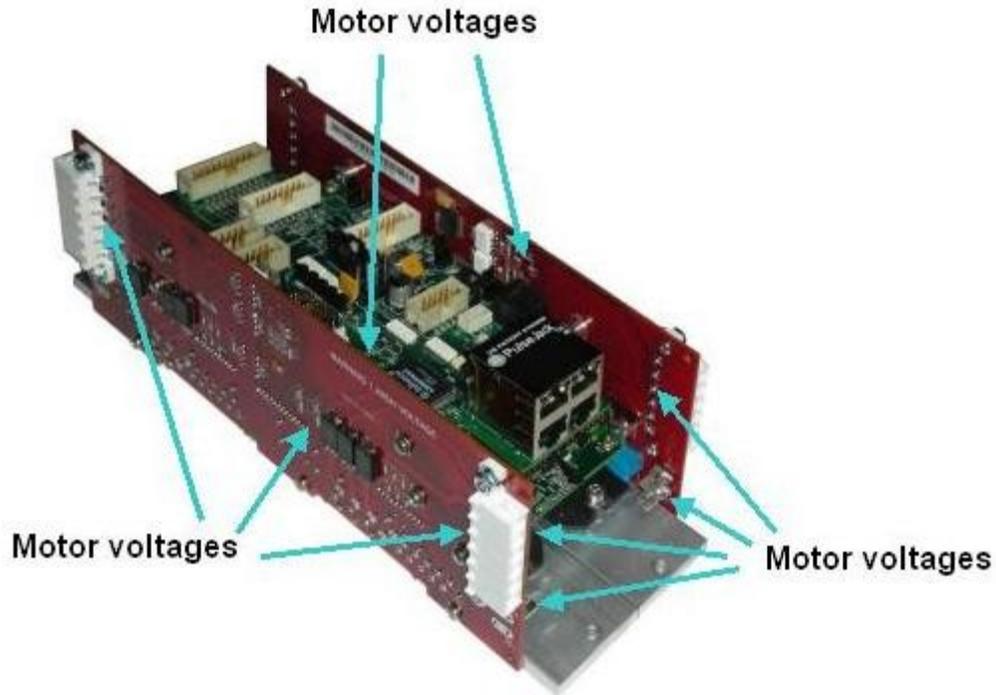
Enclosure Interlocks

If the Guidance 3000/2000 Controllers and their power supplies are mounted in a cabinet that can be opened without the use of a special maintenance tool, a high power disconnect switch should be connected to the enclosure door, such that when the door is opened, high power is disconnected from the supplies.



DANGER: The surfaces, connectors, and leads pictured in **Red** below or labeled indicate exposed elements of the Guidance 3000 and 2000 Controllers that carry motor power signals. Depending upon the motor power supply, these signals levels can range from 24 VDC to 340 VDC.





Safety and Agency Certifications

Precise controllers can operate computer-controlled mechanisms that are capable of moving at high speeds and exerting considerable force. Like all robot and motion systems and most industrial equipment, they must be treated with respect by the user and the operator.

This manual should be read by all personnel who operate or maintain Precise systems, or who work within or near the work cell.

We recommend that you read the *American National Standard for Industrial Robot Systems – Safety Requirements*, published by the Robotic Industries Association (RIA) in cooperation with the American National Standards Institute. The publication, ANSI/RIA R15.06, contains guidelines for robot system installation, safeguarding, maintenance, testing, startup, and operator training. We also recommend that you read the International Standard IEC 204 or the European Standard EN 60204, *Safety of Machinery – Electrical Equipment of Machines*, and ISO 10218 (EN 775), *Manipulating Industrial Robots – Safety*, particularly if the country of use requires a CE-certified installation.

Standards Compliance and Agency Certifications

The Precise Guidance Controllers are intended for use with other equipment and are considered a subassembly rather than a complete piece of equipment on their own. They meet the requirements of these standards:

- EN 61000-4-2 Electrostatic Discharge (8KV air, 6KV contact)
- EN 61000-4-3 Radiated Electromagnetic Field Immunity (3V/m, 27-500MHz)
- EN 61000-4-4 Electrical Fast Transient/Burst Immunity (2KV)
- EN 61000-4-5 Surge Immunity Test (1KV differential, 2KV common mode)
- EN 61000-4-6 Conducted Disturbances Immunity (RF: 150KHz – 80MHz)
- EN 50081-2 Electromagnetic Compatibility General Emissions Standard

To maintain compliance with the above standards the controller must be installed and used in accordance with the regulations of the standards, and in accordance with the instructions in this user's guide.

In addition to the above standards, the Guidance Controllers have been designed to comply with the following agency certification requirements (certification of compliance with these standards is currently in process):

- TUV
- UL
- CSA
- ANSI/RIA R15.06 Safety Standard

Moving Machine Safety

The Precise Guidance Controllers drive robots that can operate in Manual Control Mode (in which an operator directly controls the motion of the robot) or in Computer Control Mode (in which the robot operation is automatic). Manual Control Mode is often used to teach locations in the robot workspace. The robot's speed should be limited in Manual Control Mode to a maximum of 250mm per second for safety.

While some light-duty robots (like the PrecisePlace) can only apply moderate forces, it is always very important for operators to keep their hands, arms and especially their head out of the robot's operating volume.

In Computer Mode, robots can achieve speeds of 2000mm per second or even greater. During Computer Mode Operation, it is strongly recommended that operators be prevented from entering the robot work volume by safety barriers that are interlocked to the E-stop circuitry. Please refer to the ANSI/RIA R15.06

Guidance 3000/2000 Controllers

Safety Standard for Industrial Robots for information on recommended safe operating practices and enclosure design for robots of various sizes and payloads.

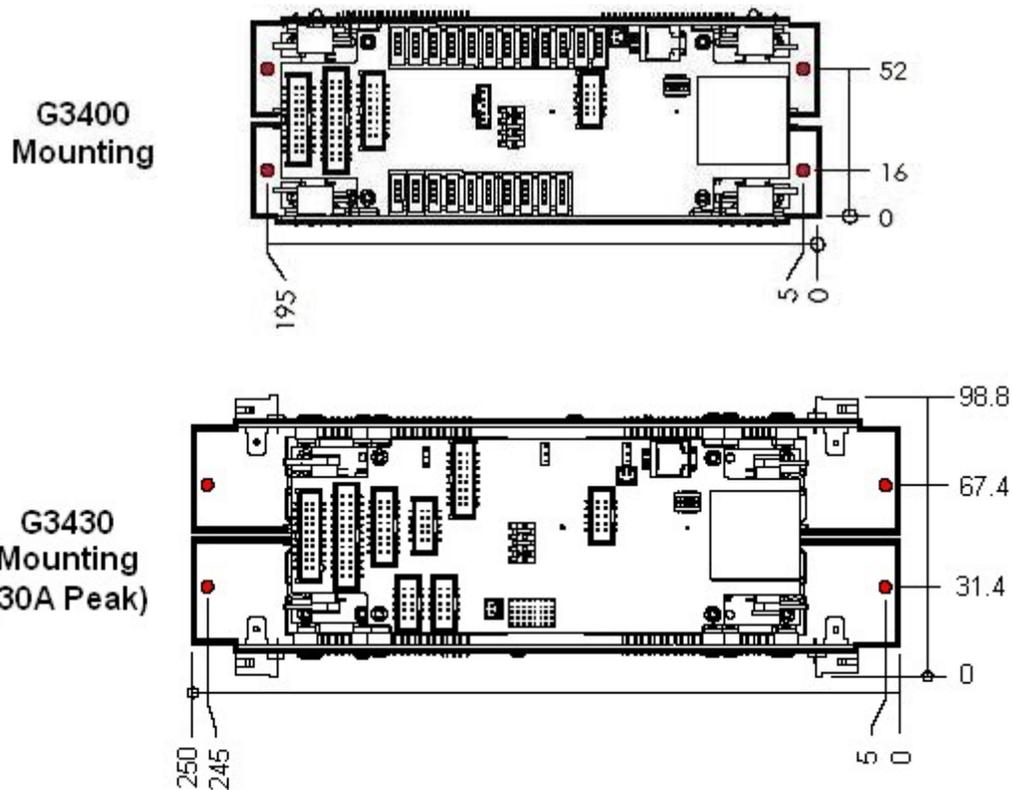
Installation Information

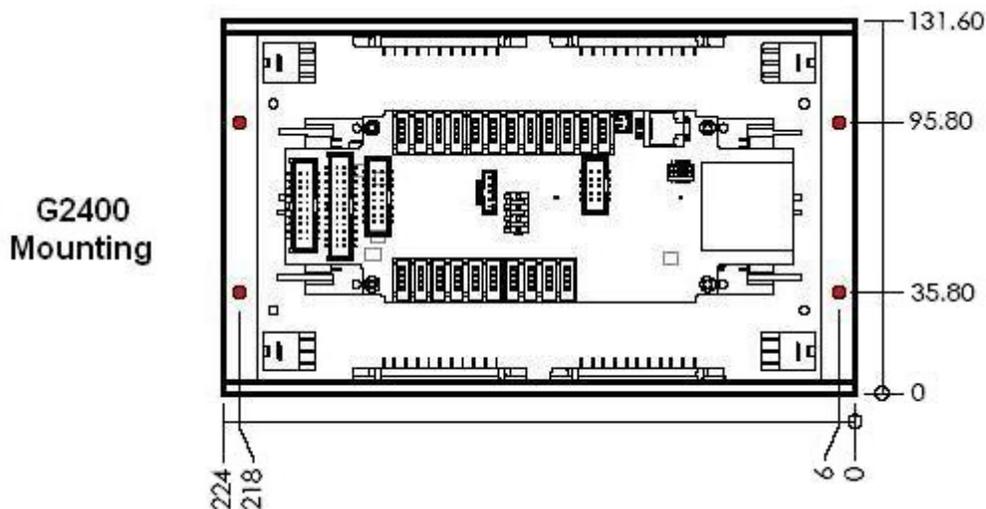
Heat Sinking and Mounting

The Guidance 3000 and 2000 Controllers must be attached to a heat sink for proper operation. The size of the heat sink depends on the total motor power controlled.

For 500 watts RMS total motor power, the heat sink should be a plate that is approximately 12 mm thick with a surface area of 0.160 m². For 1000 watts RMS motor power, the heat sink should have a surface area of approximately 0.320 m². For 2000 watts motor power, a fan should typically be added to the heat sink. The fan should be at least 80 mm square and provide a minimum of 25 CFM of air blowing axially through the controller.

The controller should be mounted to the heat sink with thermal grease and either M4 or 8-32 screws. For the Guidance 3000 and 2000 Controllers, the mounting holes are shown in **Red** in the following drawings, where all dimensions are in units of millimeters. The G3400 drawing applies to Guidance 3000 units with amplifiers that supply up to 20A peak current per motor.





A good indication of whether the controller is being properly cooled is to monitor the CPU and amplifier temperatures after the system has operated for an hour or two at its full speed and load. These temperatures can be read via the Web interface “Control Panels > System Information > System Console > Amp Temp”. **For long-term reliable operation, the CPU temperature should ideally be 70C or lower, but in no case higher than 80C. For the G3000 controllers, the amplifier temperatures should be 70C or lower. For the G2000 controllers, the amplifier temperature should be 90C or lower.** If the current ambient temperature is below the expected maximum operating temperature, add the difference between the current ambient and the maximum ambient to estimate the maximum CPU and amplifier temperatures. For example, if the current ambient is 25C and you expect to operate at the system’s maximum ambient of 40C, add 15C to the readings of the CPU and amplifier temperatures to determine if the cooling of the controller is sufficient.

For applications with high duty cycles and power, limited heat sinking and/or high ambient temperatures, a small fan blowing through the controller will greatly reduce the controller’s operating temperature.

Recommended Motor and Encoder Wiring

Wiring Overview

With the pressure to design high power motor drive electronics with low power losses, switching motor drive amplifiers now have edges that switch 400 volts as fast as once each 100 nS. While this helps to keep switching losses down, it has made receiving logic level signals from encoders and sensors very difficult. This is because every PWM edge must charge and discharge the motor wiring capacitance. The current spikes to do this can be as large as 4 amperes. This current flow causes the motor frame to have ground bounce on it due to the inductance of the ground return back to the amplifier. This ground bounce and the coupling between motor harness wire and encoder harness wires can introduce noise into the system. This section describes wiring techniques that will reduce the interference between motors and encoders.

It is very important that the wiring guidelines in this section be followed in order to avoid encoder quadrature errors, zero index errors, and other noise related problems.

NOTE: For systems that operate with a 48-volt motor bus, the ferrite beads and the 600-volt wire that are described in the following sections are not needed.

Motor Cables

UL recommends the following current ratings for 80° C wire.

Wire Size AWG	28	26	24	22	20	18	16	14	12	10
Amperes	0.6	1.0	1.6	2.5	4.0	6.0	10.0	15.0	20.0	30.0

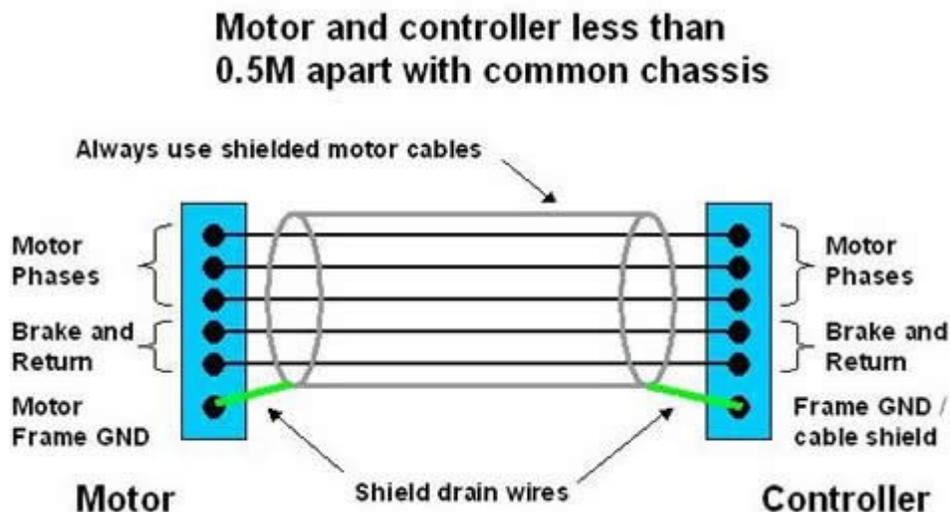
The **motor wire should always be shielded** and have a rating of 600 volts (except for 48VDC motor bus voltages and below). The typical wires that are shown in the table below have a 105° C rating. These wires do not have a drain wire, so a drain connection must be soldered to the shield.

	Alpha 16 AWG	Alpha 18 AWG	Beldon 16 AWG	Beldon 20 AWG
High Flex	85603CY	85803CY		
No Flex	3247	3242	9953	9963

Motor Wiring Path

If the motor frame and the amplifier heat sink are less than 0.5 meter apart and share the same metal chassis, **use shielded wire without a shield ferrite bead**. (“Ferrite beads” are sometimes referred to as “ferrite chokes” or “ferrite cores”.) In this case, the ground bounce of the motor will be small due to the short distance and the shared chassis. The shield must be connected to the amplifier at pin 5 and at the motor end, to the motor frame.

The following picture illustrates how this cable should be wired.

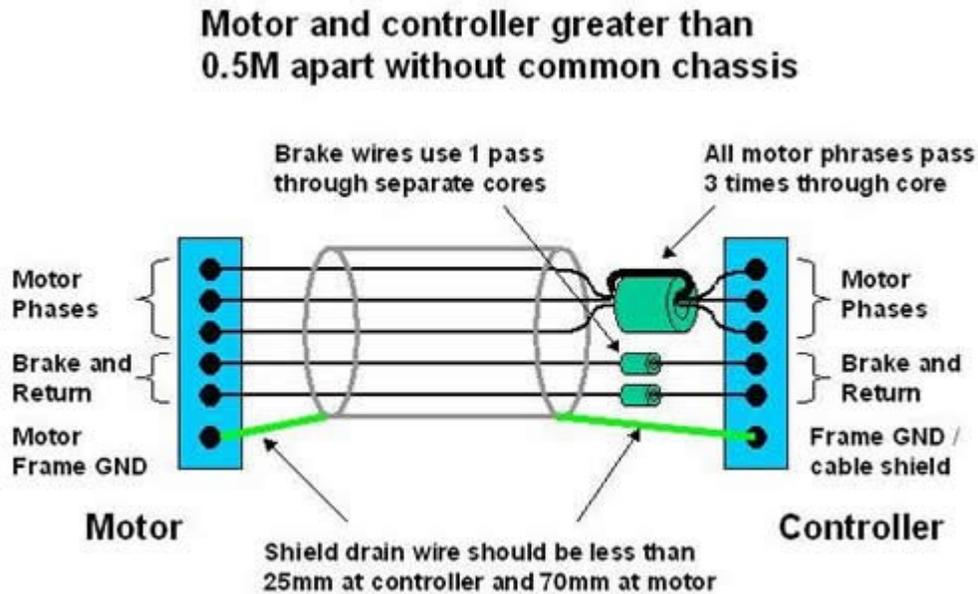


Guidance 3000/2000 Controllers

If the distance is more than 0.5 meter, **use a shield bead around the motor phase wires at the amplifier end of the harness to reduce the charging current spikes.** The phase wires as a group must pass thru the bead core three times. The ground or brake wires must **NOT** pass thru the bead core.

Another special consideration is if there is **no** chassis between motor and amplifier, the length of the shield drain wire must be kept as short as possible, probably no more than 25 mm at the amplifier connector end of the cable and no more than 70 mm at the motor end. This will cause the bead to be adjacent to the shield, in order to keep drain wire short.

The following picture illustrates how this cable should be wired.



Motor Ferrite Beads

Based upon the wire and insulation thickness, the following are typical ferrite cores that can be utilized.

Wire and Insulation Thickness	Ferrite Bead
Wires up to 1.5mm	FAIR-RITE #2631540002
Wires up to 2.9mm	FAIR-RITE #2631102002

Thermal rises of up to 40° C in the bead temperatures are acceptable. However, if the bead gets hotter, use the next size core of material 31 or one less turn through the bead. Never use more than 3 turns through the core to avoid diminishing the effectiveness of the ferrite. This is caused by adjacent wires capacitively coupling and passing the spikes through the core.

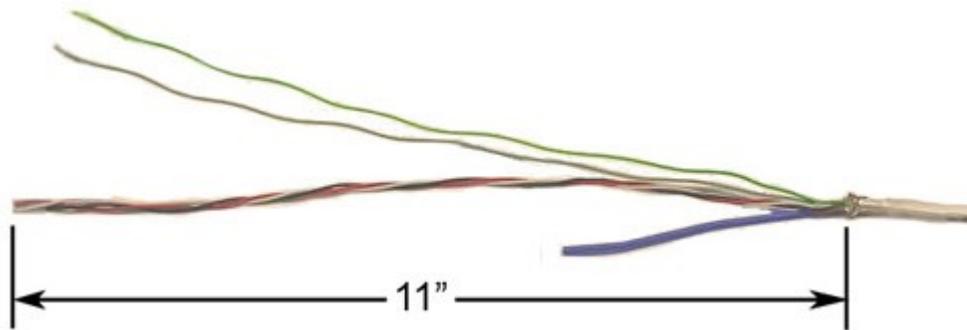
The effectiveness of the cores can be determined with a current probe with a window large enough to pass all the motor phases of the motor in question through the probe in the same direction. Put the probe on the amplifier side of the harness. This will measure the common mode ground current. Use just enough turns to reduce the amplitude of the current spike without causing any additional ringing. Usually you can achieve a 30-50% reduction in the spike amplitude.

Brake Wiring

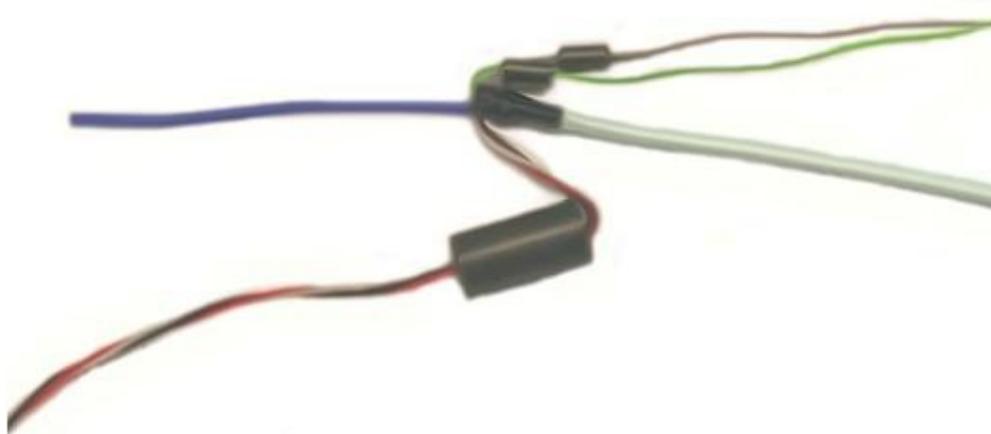
If the brake wires are in the shielded cable with the motor wires, then a separate bead must be used for each brake wire at the controller side of the harness. Use FAIR_RITE # 2673021801. One wiring pass straight through the bead is adequate.

Ferrite Bead Installation Illustration

The following series of pictures illustrate the process of installing a ferrite bead onto the harness at the **controller end** of the motor cable. In the first picture, the dark blue wire is the shield drain wire that has already been soldered to the shield. The shield was then covered with shrink tubing. This example also shows the optional beads on the brake wires.



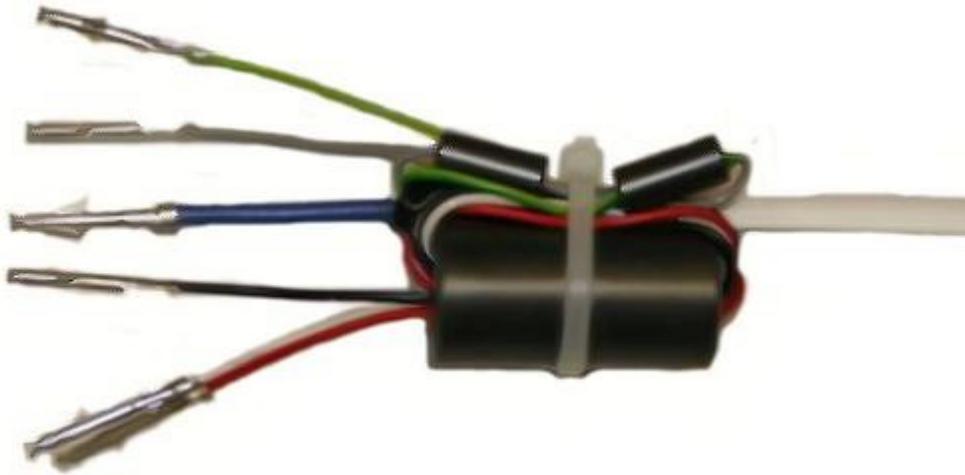
Step 1: Blue drain soldered to shield and wires cut to length



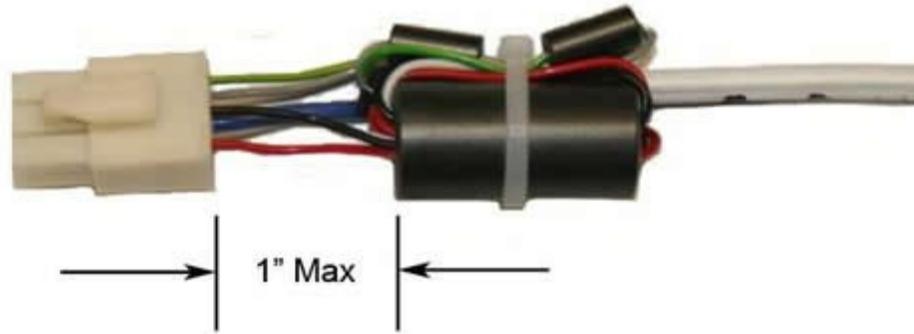
Step 2: Three motor wires through large core, brakes through small cores



Step 3: Three motor wires looped three times through large core



Step 4: All wires leads crimped to pins



Step 5: Final assembled cable with controller motor connector

Encoder Considerations

The preferred encoder should have a differential cable driver built in. The differential signal will cancel out much of the common mode noise that encoder wiring can pick up and, when used with twisted pair wire, will cancel out the magnetic pick up from the motor harness.

Some encoders have an open collector output or an output with only a 10K pull up resistor. These encoders should only be used with a cable driver IC such as a DS26C31 mounted nearby the encoder or the encoder should be mounted within 5 feet of controller and wired with shielded cable.

If an encoder's code wheel or linear mask is made with etched metal or other conductive material, **the encoder should not be used** if it is mounted to any housing or chassis that has ground bounce on it. For example, if such an encoder is directly mounted to a motor frame without electric insulation, its use could result in quadrature errors and other noise problems.

Encoder Cables

It is highly recommended that the encoder cable be shielded and contain 4 twisted pairs with a gage of AWG 24 or AWG 26. See the table below for recommended cables.

Unshielded encoder wiring should never be run next to unshielded motor wiring or other sources of noise.

	Alpha 24 AWG	Alpha 26 AWG	Beldon 24 AWG	Beldon 26 AWG
High Flex	86604CY	86504CY		
No Flex	5494C 5272C		88104	

One of the twisted pairs should be used for power and ground, one pair for A+ & A-, one pair for B+ & B- and one pair for Z+ & Z-. (See the next section for specific pin assignments.) **Connect the shield to pin 7 on the MIDS encoder connector.** On some encoders that are in a metal box with a metal shell connector, on the encoder end of the cable, connect the shield to the metal shell of the mating connector.

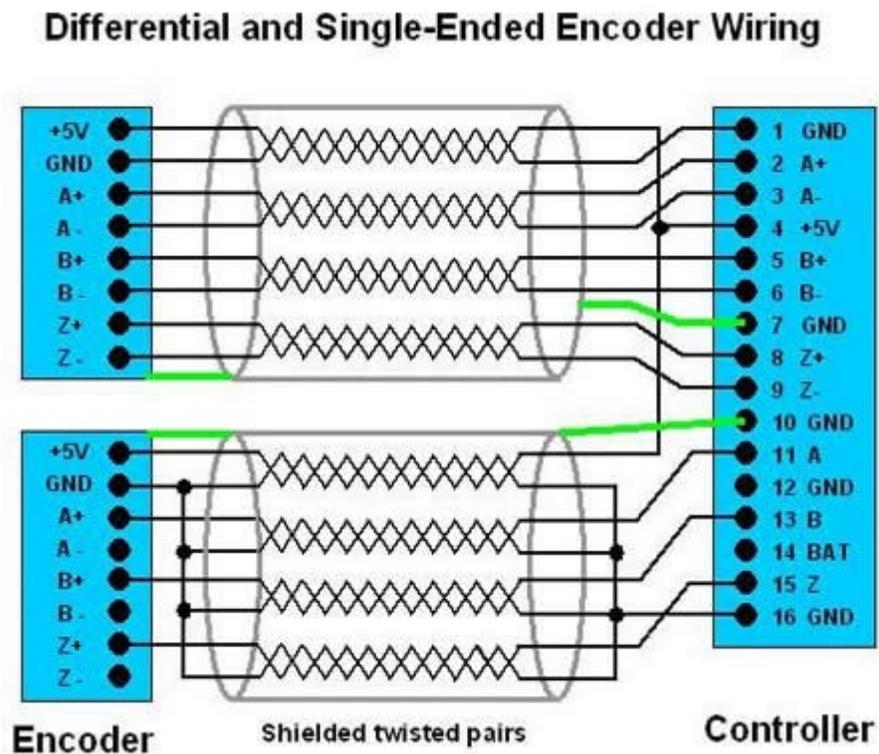
Encoder Wiring and Pin Assignments

The encoder connectors on the MIDS board can each be cabled to a differential encoder and an optional single-ended encoder. If a single-end encoder is not interfaced, these pins can be configured for use with hall effect sensors or end-of-travel switches and a home switch. Given a choice for wiring an encoder, the differential encoder input should always be used instead of the single-end encoder input to achieve greater noise immunity.

If a single-end encoder is wired, a shielded twist pair cable should still be used to ensure the best possible signals and avoid crosstalk between the signals. In this case, the low side of each twisted pair should be connected to ground and the low side of a differential encoder output should be left floating.

Due to pin limitations, if several wires must be connected to a single pin, a larger pin should be used.

The following drawing illustrates how to interface to both the differential and the single-ended encoder input signals.



Hardware Reference

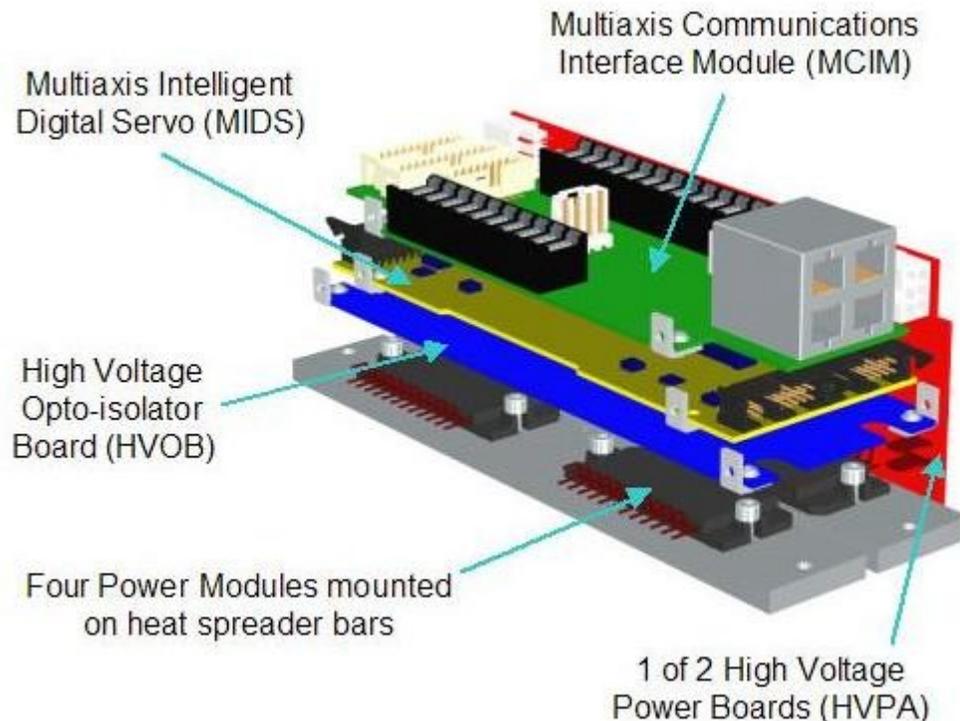
Guidance Controller Assemblies and Interfaces

Guidance Controller Major Assemblies

The Guidance Controllers are constructed from a number of major assemblies, several of which are common among the various types of controllers. Due to the extremely compact design of these controllers and the number of device interface options, connectors for services are mounted on a number of assemblies. Each of the major assemblies and their interfaces to other equipment are described in this section.

The picture below illustrates the primary assemblies of the Guidance 3000 Controller. For clarity, one of the two identical vertical High Voltage Power Boards (HVPA) has been removed.

All of the Guidance Controllers contain the Multiaxis Communications Interface Module (MCIM) and the Multiaxis Intelligent Digital Servo (MIDS) assemblies. The Guidance 3000 and 2000 families differ in their motor drive assemblies and the Guidance 0006 and 0004 do not have any drive assemblies.



Guidance 3000/2000 Controllers



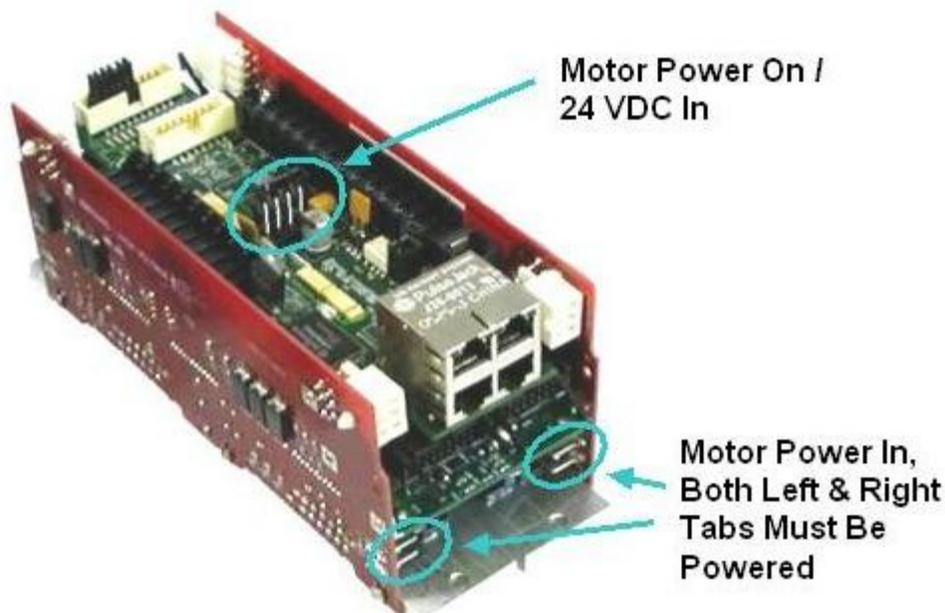
DANGER: The Guidance 3000 and 2000 contain unshielded high voltage pins, components and surfaces. These products are intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Power Connectors and Grounding

The Guidance 3000 Controller, Motor Power Supply, and 24 VDC Power Supply should be wired as shown below. All of the Guidance Controllers provide a single connector on their top board that both receives the 24 VDC to power their logic sections and outputs redundant signals that enable the output section of the motor power supply.

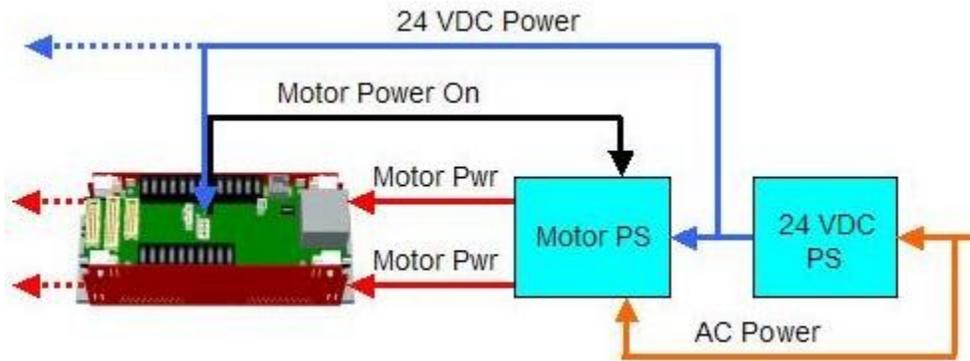
For the Guidance 3000, motor power must be provided to both vertical boards. Motor power tabs are available on both ends of each of the vertical boards. The redundant set of tabs are included to allow the motor power to be daisy chained to another controller. If a single controller is being powered, either set of tabs can be utilized. Amp 3-520133-2 Faston receptacles or equivalent hardware can be used to connect to the power tabs.

Frame ground is conducted continuously around the Guidance 3000 Controller by means of grounding pads and fastening lugs and screws. The frame ground continues through the heat sink.



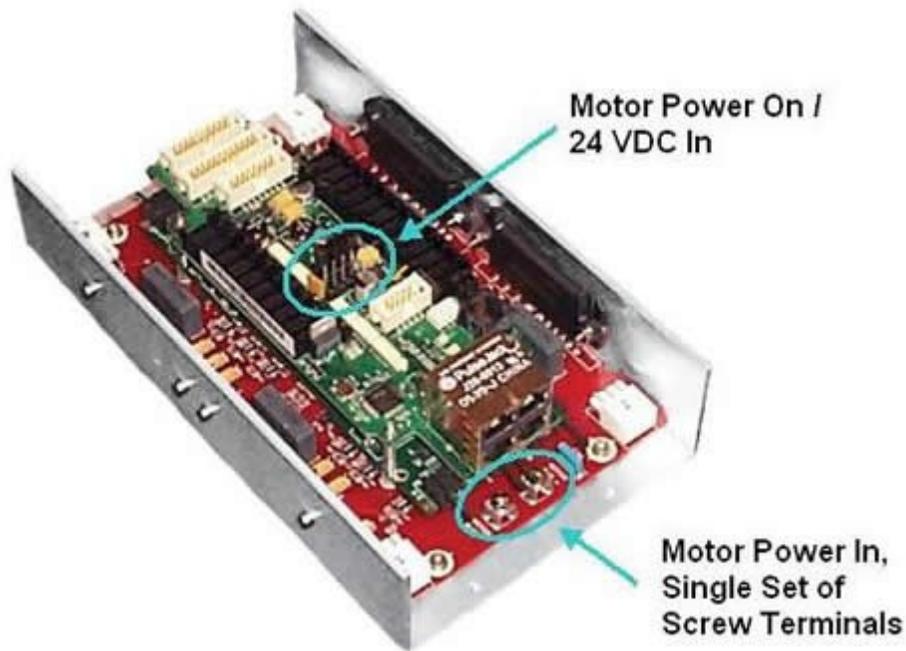
DANGER: The Guidance 3000, the PrecisePower Intelligent Motor Power Supplies, and the 24 VDC power supply are all open frame electrical devices that contain unshielded high voltage pins, components and surfaces. These products are intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

machine chassis that is not accessible when AC line power is turned on.



As a convenience, if you purchase a Guidance 3000, a Precise 24 VDC Low Voltage Power Supply and a PrecisePower Intelligent Motor Voltage Power Supply, you can also purchase a Guidance Controller Power Harness. This harness provides all of the connections between AC power, the two power supplies and the controller. These power and signal paths are illustrated in solid lines in the drawing above.

Unlike the Guidance 3000, the Guidance 2000 (shown below) provides a single pair of screw terminals for connecting DC motor power to the integrated motor drives. Other than providing just a single pair of motor power terminals, the power cabling for the Guidance 2000 is identical to the Guidance 3000.



Guidance 3000/2000 Controllers



DANGER: The Guidance 2000 is an open frame electrical device that contains unshielded voltage pins, components and surfaces. This product is intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Since the Guidance 0006 and 0004 controllers do not have integrated motor drives, they only require that power be provided on the "24 VDC power in" connector in order to operate.

MCIM (IO) Board

MCIM (IO) Board Connectors

The Multiaxis Communications Interface Module (MCIM) contains all of the connectors that provide interfaces to external equipment. These interfaces include:

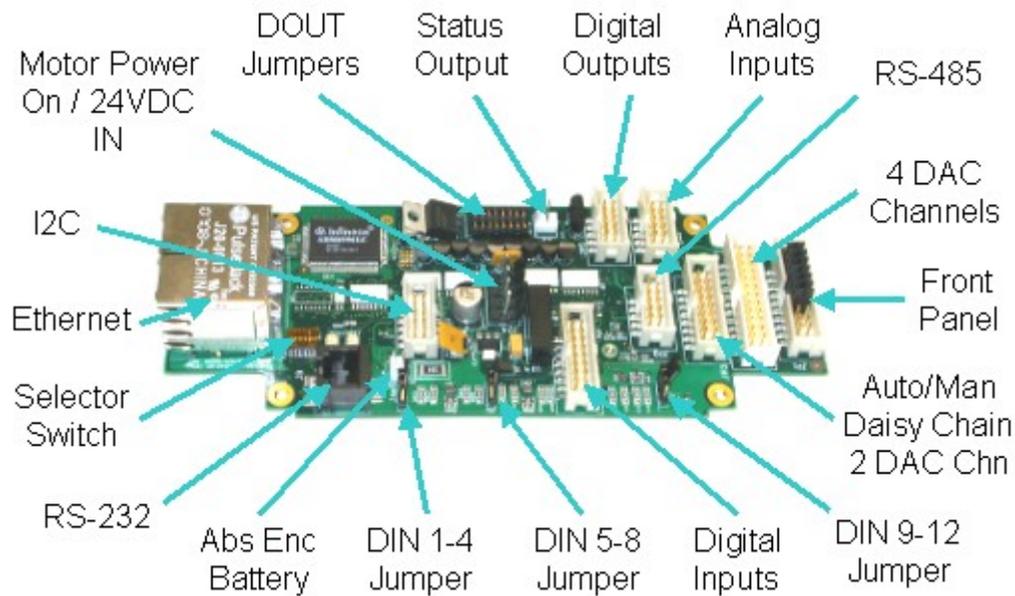
- [Absolute encoder battery](#)
- [Analog inputs AIN 1 and AIN 2 \(IDC type connector\)](#) or [Analog inputs \(individual connectors\)](#)
- [Analog output \(DAC\) channels](#)
- [Auto/Manual daisy chain & 2 DAC channels](#)
- [Digital inputs DIN 1 through Din 12 \(IDC type connector\)](#) or [Digital inputs \(individual connectors\)](#)
- [Digital outputs DOUT 1 through DOUT 8 \(IDC type connector\)](#) or [Digital outputs \(individual connectors\)](#)
- [Ethernet](#)
- [I2C](#)
- [Motor power-on enable / 24VDC controller power input](#)
- [Front panel connector with ESTOP and MCP/Secondary RS-232 serial port](#)
- [Primary RS-232 serial port](#)
- [RS-485 multi-drop serial port \(not available for general use\)](#)
- [Selector DIP switches](#)
- [Status Output](#)

There are three versions of the MCIM board that are currently being shipped. These boards offer very similar functionality. The principal differences between these boards is that the newer versions present the general digital input, output and analog input signals in IDC type connectors and support four Ethernet ports. The older type of board has a separate connector for each digital input, output and analog input signals and only supports a single Ethernet port. The other difference is that the newest type of board includes an RS-485 serial interface that is only used in special situations.

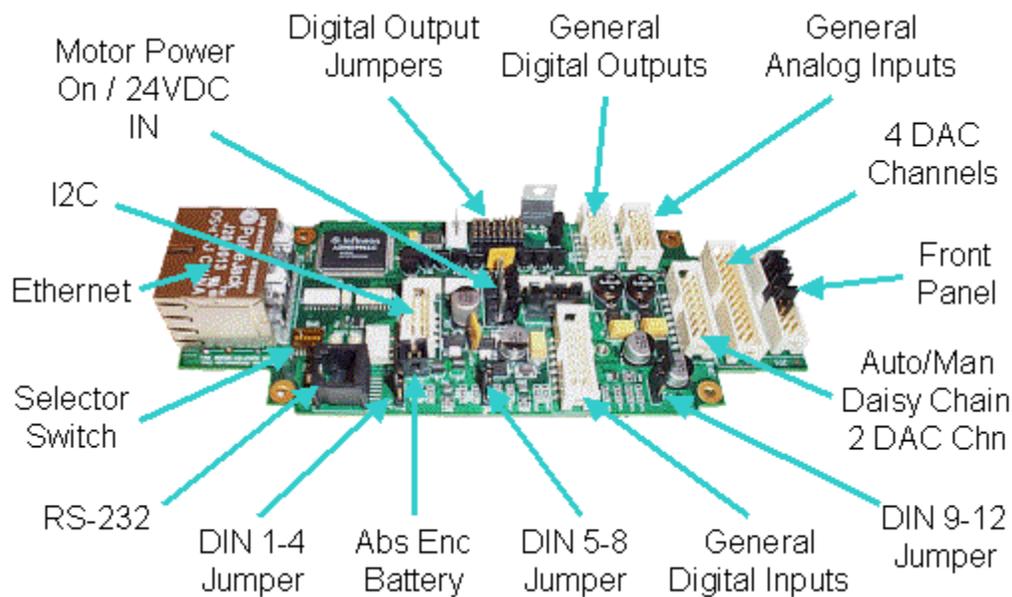


DANGER: The High Voltage Power Boards (HVPAs) and the Motor/Brake connectors and their leads contain unshielded high voltage pins that are positioned next to the MCIM connectors. It is intended that the Guidance Controller with these components be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

The MCIM with a RS-485 connector and IDC type DIO and AIO connectors is shown below. To jump to the detailed information for a specific connector, click on the connector interface name or the connector on the MCIM board in the following picture.

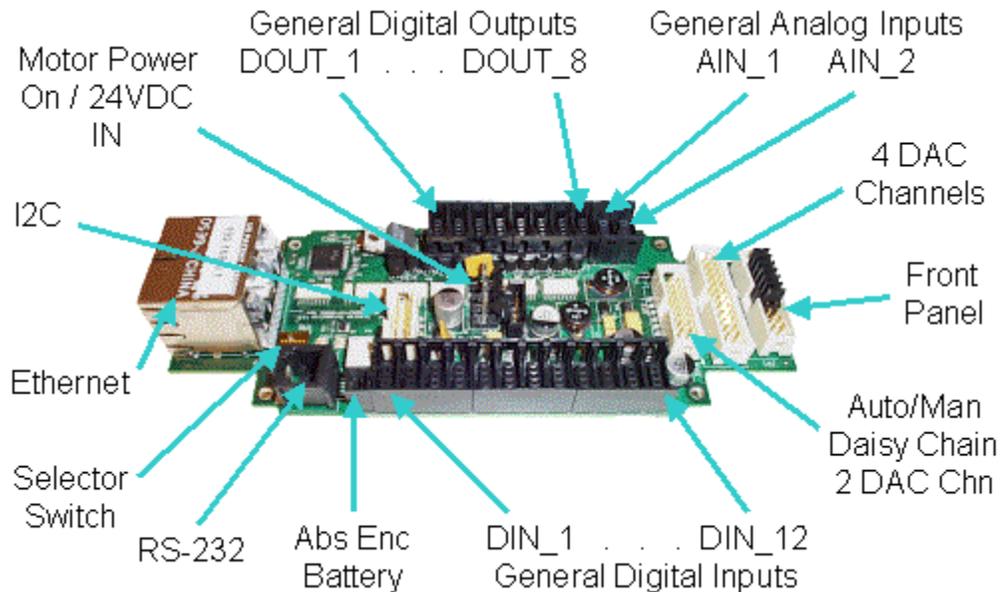


The MCIM without an RS-485 interface but with IDC type DIO and AIO connectors is shown below. To jump to the detailed information for a specific connector, click on the connector interface name or the connector on the MCIM board in the following picture.



The MCIM with individual DIO and AIO connectors is shown below. To jump to the detailed information for a specific connector, click on the connector interface name or the connector on the MCIM board in the following picture.

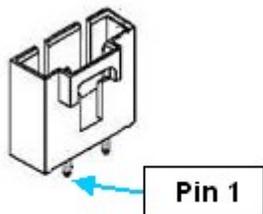
Guidance 3000/2000 Controllers



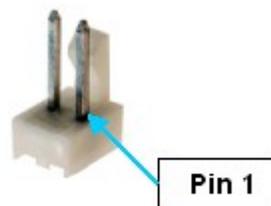
In the following sections, the pin-outs for each of the connectors plus the part numbers for the mating plugs are described.

Abs Encoder Battery Connector

Many commercially available absolute encoders require a modest amount of battery power in order to retain their counters when the Guidance controller is powered down. If your system is equipped with these types of encoders, a suitable battery source must be connected to the battery connector.



Molex 70543-0001



Molex 22-23-2021

Depending upon the version of MCIM board, the battery power must be connected to one of the Molex headers shown above. From the MCIM board, the power flows down to the MIDS board and then connects to pins on the encoder connectors. (Please see the reference pages for the [MIDS Encoder connectors](#) for additional information.)

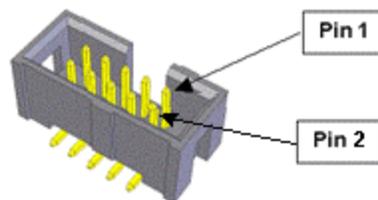
Pin	Description
1	+VBAT
2	GND
User Plug Part for Molex 22-23-2021	Molex 22-01-2021
User Plug Part for Molex 70543-0001	Molex 50-57-9202 plug with crimp terminals Molex PN 16-

02-0103 and hand crimp tool 11-01-0208
--

Analog Input (IDC Type Connector)

The MCIM board provides two general purpose analog input channels. For MCIM's with an IDC type AIO connector, these signals are conveyed through a single connector. In this connector, pin 6 is the input for the first +/- 10VDC analog channel and pin 8 is the input for the second channel.

The Analog to Digital Converter has a 12-bit resolution and a conversion delay of 3.2 microseconds. The two ADC channels are alternately scanned, so a new reading is available for each channel every 6.4 microseconds. The input impedance of the analog conversion circuit is 20,000 ohms. There is a 4 KHz noise filter on each input.



The following table details the pin out for the analog input connector.

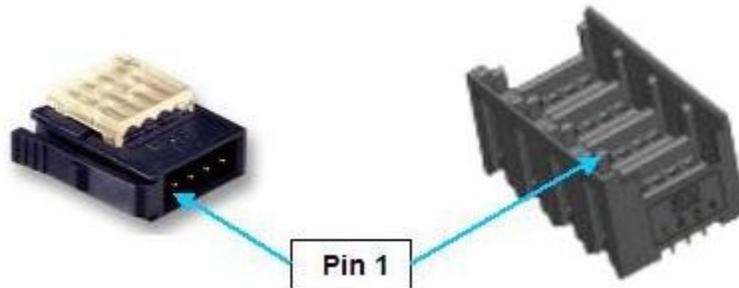
Pin	Description
1	24 VDC
2	24 VDC
3	24 VDC
4	24 VDC
5	GND
6	+/- 10 VDC input signal, channel 2
7	GND
8	+/- 10 VDC input signal, channel 1
9	GND
10	GND
User Plug Part No	AMP 76285-1 or Molex 22-55-2101 or 90142-0010. For the Molex plug, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

Analog Input (Individual Connectors)

There are two analog input connectors on the Guidance MCIM with individual AIO connectors. These use the same plugs as the digital input and output connectors. On these two connectors, pin 1 is connected to

Guidance 3000/2000 Controllers

ground, pin 2 is not connected, pin 3 is the analog input signal, +/-10 VDC, and pin 4 is 24VDC. The Analog to Digital Converter has a 12-bit resolution and a conversion delay of 3.2 microseconds. The two ADC channels are alternately scanned, so a new reading is available for each channel every 6.4 microseconds. The input impedance of the analog conversion circuit is 20,000 ohms. There is a 4 KHz noise filter on each input.

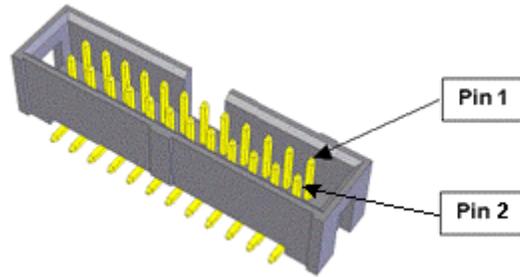


The mating plug for digital inputs and outputs and analog inputs is the 3M 37104 series Mini-Clamp Plugs. For example, if you use the 3M 3319 Series High Flex Life IDC Flat Cable with 24 AWG wire, the part number for the required plugs is 3M 37104-3122-000 FL. Please see the section on Digital Input Connectors for more information on these plugs.

Pin	Description
1	GND
2	Not connected
3	+/- 10 VDC input signal
4	24VDC
User Plug Part No	3M 37104 series Mini-Clamp Plugs or Amp 1473562-4

Analog Output, 4 Channels

The Guidance Controller can be optionally supplied with either 4 or 6 instrument grade Digital to Analog Converter (DAC) output channels. These DACs are primarily intended to interface the controller to 3rd party, external motor amplifiers. These external amplifiers can be used in place of or in combination with the controller's integrated motor drives. The signals for the first four DAC channels are provided on a single connector. If supplied, the signals for the next two DAC channels are provided on the [Auto/Man Daisy Chain connector](#).

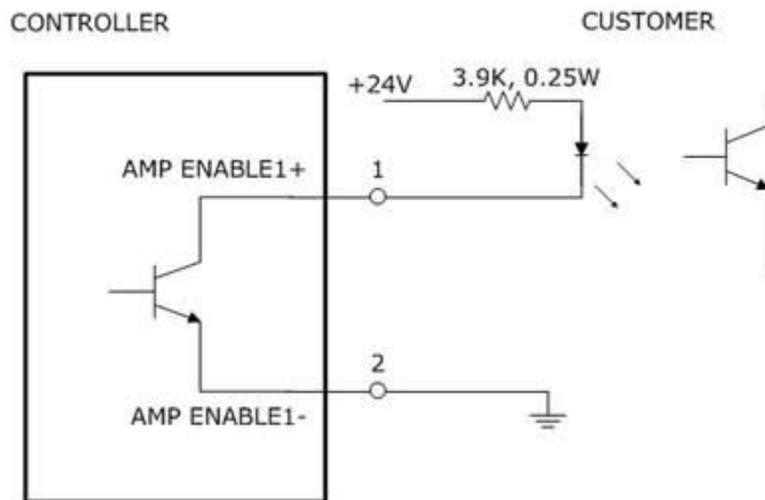


Each of the DAC's has an output range of +/- 10VDC. The DAC values have a resolution of 16 bits and are monotonic to 16 bits as well. They have a settling time of approximately 10 usec.

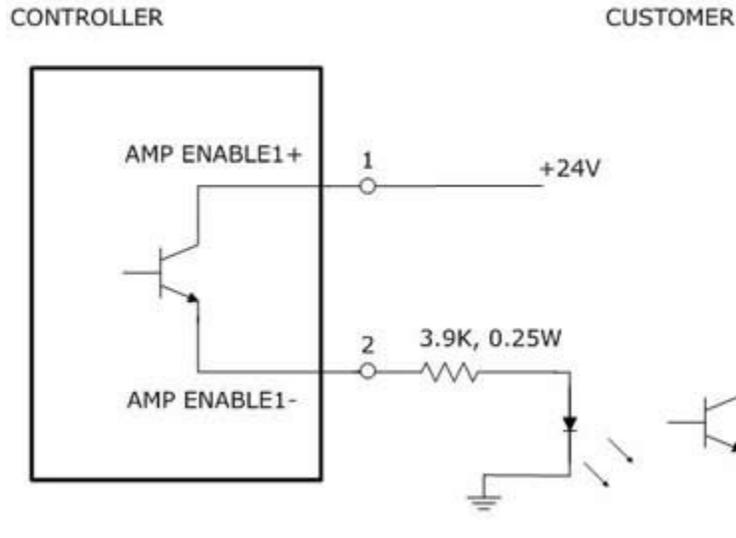
Associated with each DAC channel is an "AMP ENABLE " digital output signal and an "AMP FAULT " digital input signal. The amp enable allows the controller to individually turn on the power to motors. The amp fault signals aid in isolating hardware problems. For the amp enable and amp fault signals, high values are at 24 VDC.

The following drawings illustrate how to wire the AMP ENABLE digital output signals for the first channel in both sinking and sourcing configurations. The AMP ENABLE signals for channels 2 to 6 can be wired in an analogous manner.

AMPLIFIER ENABLE OUTPUT WIRED AS SINKING OUTPUT

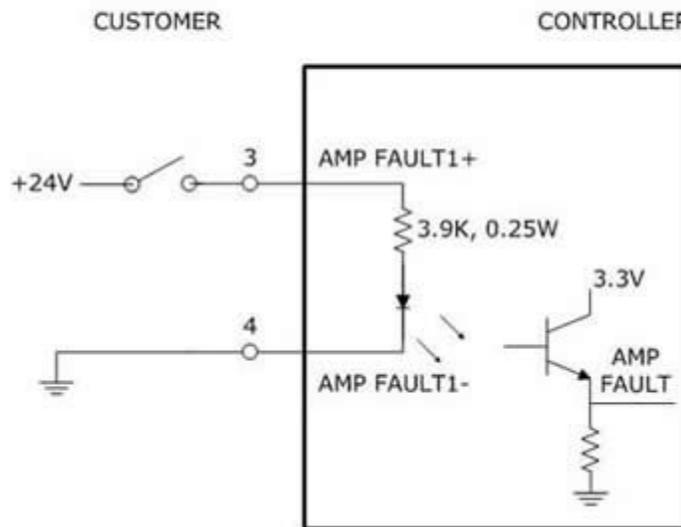


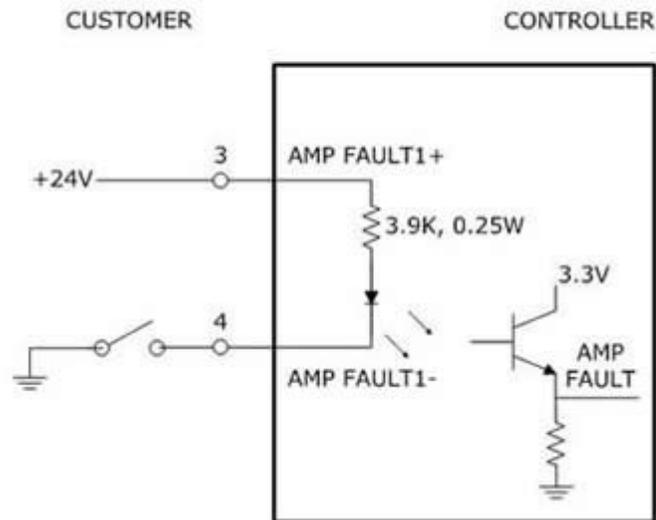
AMPLIFIER ENABLE OUTPUT WIRED AS SOURCING OUTPUT



The following drawings illustrate how to wire the AMP FAULT input signals for the first channel in both sinking and sourcing configurations. The AMP FAULT signals for channels 2 to 6 can be wired in an analogous manner.

AMPLIFIER FAULT INPUT WIRED AS SINKING INPUT



AMPLIFIER FAULT INPUT WIRED AS SOURCING INPUT

The following table details the pin out for the primary analog output connector.

Pin	Description
1	24 VDC AMP ENABLE1 +
2	24 VDC AMP ENABLE1 -
3	24 VDC AMP FAULT1 +
4	24 VDC AMP FAULT1 -
5	+/- 10 VDC DAC1+
6	+/- 10 VDC DAC1-
7	24 VDC AMP ENABLE2 +
8	24 VDC AMP ENABLE2 -
9	24 VDC AMP FAULT2 +
10	24 VDC AMP FAULT2 -
11	+/- 10 VDC DAC2+
12	+/- 10 VDC DAC2-
13	24 VDC AMP ENABLE3 +
14	24 VDC AMP ENABLE3 -
15	24 VDC AMP FAULT3 +
16	24 VDC AMP FAULT3 -
17	+/- 10 VDC DAC3+
18	+/- 10 VDC DAC3-
19	24 VDC AMP ENABLE4 +
20	24 VDC AMP ENABLE4 -
21	24 VDC AMP FAULT4 +
22	24 VDC AMP FAULT4 -
23	+/- 10 VDC DAC4+

Guidance 3000/2000 Controllers

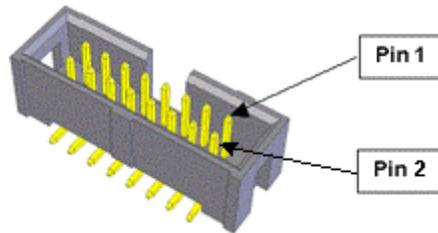
24	+/- 10 VDC DAC4-
User Plug Part No	Amp 746285-5 or Molex 22-55-2241 or Molex 90142-0024. For the Molex plugs, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

Auto/Manual Daisy Chain & 2 DAC Channels

This connector carries a combination of signals: redundant Auto/Manual safety signals and the signals associated with the optional 5th and 6th DAC channels.

The Auto/Manual signals replicate the state of the Auto/Manual signals that are received on the [Remote Front Panel Interface](#). This connector permits these signals to be easily propagated to other networked controllers. When the robot is manually operated, these signals should force all networked controllers to automatically go into a safe, low speed mode.

The DAC channels and their associated signals operate in the same manner as the first four channels that are provided on the [Analog Output, 4 Channel](#) connector. Please see the documentation on the first four DAC channels for details on the DAC specification, a description of the associated signals, and sample wiring diagrams.



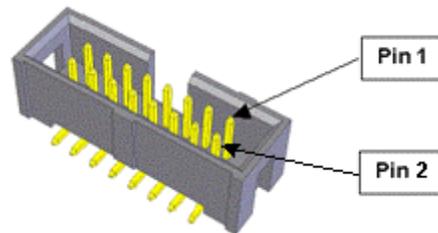
For the Auto/Manual and Amp Enable/Fault signals, high values are at 24 VDC.

Pin	Description
1	AUTO_MAN2
2	24 VDC
3	AUTO_MAN1
4	24 VDC
5	24 VDC AMP ENABLE6 +
6	24 VDC AMP ENABLE6 -
7	24 VDC AMP FAULT6 +
8	24 VDC AMP FAULT6 -
9	+/- 10 VDC DAC6+
10	+/- 10 VDC DAC6-
11	24 VDC AMP ENABLE5 +
12	24 VDC AMP ENABLE5 -
13	24 VDC AMP FAULT5 +
14	24 VDC AMP FAULT5 -

15	+/- 10 VDC DAC5+
16	+/- 10 VDC DAC5-
User Plug Part No	Amp 746285-3 or Molex 22-55-2161 or Molex 90142-0016. For the Molex plugs, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

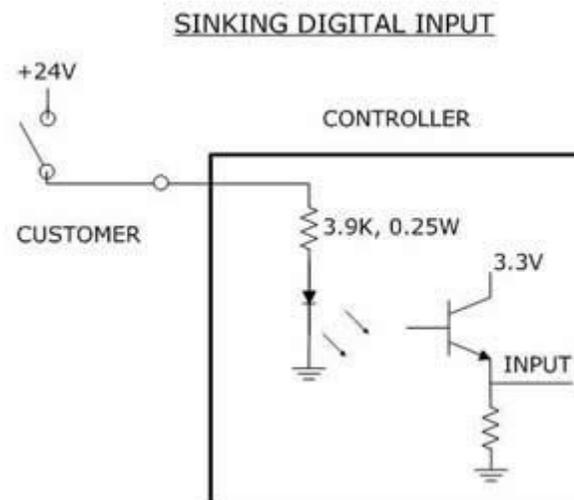
Digital Inputs (IDC Type Connector)

On MCIM boards with IDC type DIO connectors, 12 general purpose optically isolated digital input signal lines are provided and accessed in a single connector. This IDC type connector permits these signals to be easily interfaced to other devices.

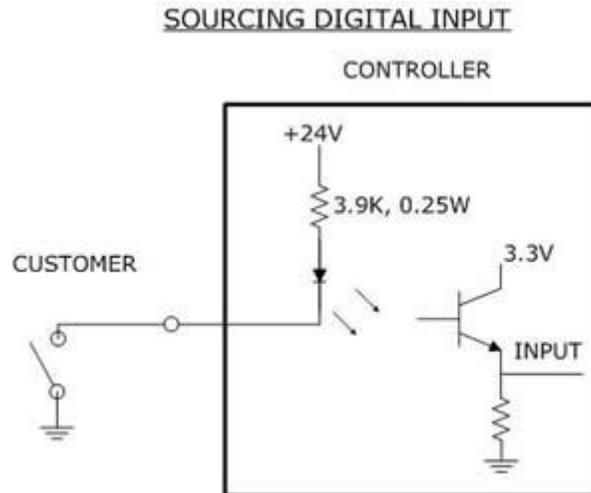


By setting three sets of [Sinking Versus Sourcing Jumpers](#), these inputs can be configured as either "sinking" or "sourcing" in groups of 4 signals.

If an input signal is configured as "sinking", the external equipment must pull the input high to 5VDC to 24VDC to indicate a logical high value or no voltage for a logical low.



If an input signal is configured as "sourcing", the external equipment must pull the signal input pin to ground to indicate a logical high and must let the line float high to 24VDC to signal a logical low value.



As shipped from the factory, all digital inputs are normally configured as "sourcing".

The pin out for the Digital Input Connector is described in the following table.

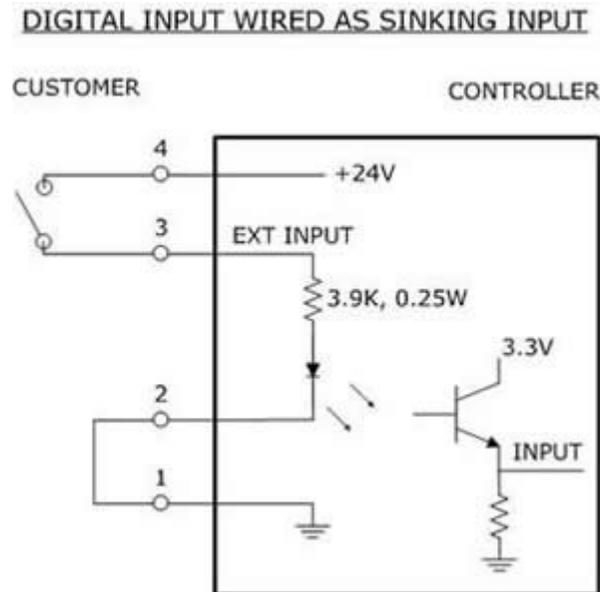
Pin	Description
1	24 VDC
2	GND
3	Digital Input 1
4	Digital Input 2
5	Digital Input 3
6	Digital Input 4
7	Digital Input 5
8	Digital Input 6
9	Digital Input 7
10	Digital Input 8
11	Digital Input 9
12	Digital Input 10
13	Digital Input 11
14	Digital Input 12
15	24 VDC
16	GND
User Plug Part No	Amp 746285-3 or Molex 22-55-2161 or Molex 90142-0016. For the Molex plugs, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

Digital Inputs (Individual Connectors)

On MCIM's with individual DIO connectors, there are 3 connector housings that each contain 4 digital input connectors, thus providing individual connectors for a total of 12 optically isolated digital input

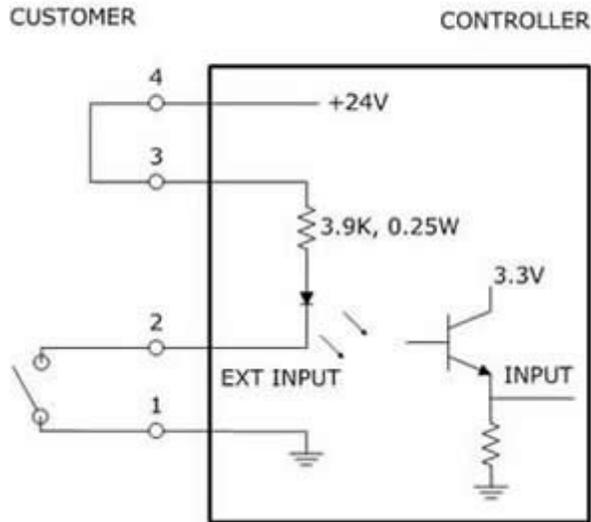
signals. Each digital input connector has 4-pins. Pin 1 is connected to ground and pin 4 is connected to 24 VDC. Pin 2 is connected to the cathode of the LED. Pin 3 is connected through a 3900 ohm resistor to the anode of the LED of an opto isolator.

To configure a digital input where the controller provides a ground (i.e. a "sinking" digital input) and the external equipment provides a voltage signal, pin 2 must be connected to pin 1 by means of a jumper wire in the IDC digital input connector, grounding the anode of the led, and pin 3 must be connected to the external signal. When pin 3 is pulled high (5-24 VDC), the opto driver is turned on and a positive digital input signal is sent to the controller. This wiring is illustrated in the following diagram.



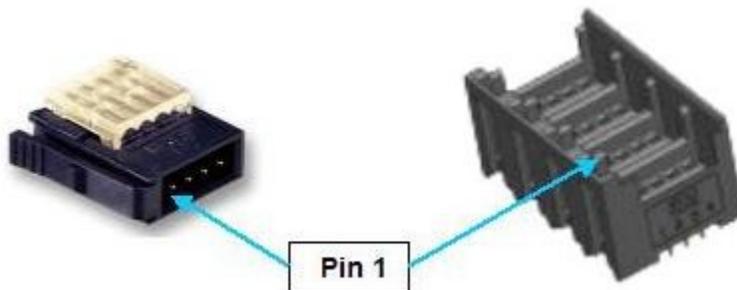
To configure a digital input where the controller provides the voltage (i.e. a "sourcing" digital input), pin 3 must be connected to pin 4 by means of a jumper wire in the IDC digital input connector, thus providing power to the cathode of the led, and pin 2 must be connected to the external signal. When pin 2 is connected to ground, the circuit is completed, the opto switch is turned on and a positive digital signal is sent to the controller. Pin 1 is located towards the center of the board. This wiring is illustrated in the following diagram.

DIGITAL INPUT WIRED AS SOURCING INPUT



The mating plug for digital inputs and outputs and analog inputs is the 3M 37104 series Mini-Clamp Plugs. For example, if you use the 3M 3319 Series High Flex Life IDC Flat Cable with 24 AWG wire, the part number for the required plugs is 3M 37104-3122-000 FL. Plugs for other wire diameters are shown below.

Pin	Sinking digital input	Sourcing digital input
1	GND	GND
2	Connected to pin 1	External input (GND or open)
3	External voltage input (5-24 VDC or open)	Connected to pin 4
4	24VDC	24VDC
User Plug Part No	3M 37104 series Mini-Clamp Plugs or Amp 1473562-4	



3M Plug Part Numbers:

Table 1				
Wire Insulation OD	1.6 ~ 2.0 [.063~.079]	1.2 ~ 1.6 [.047~.063]	1.0 ~ 1.2 [.039~.047]	0.8 ~ 1.0 [.031~.039]
Part # 20-22 AWG	2206	2165	2124	
Cover Color	Gray	Blue	Green	
Part # 24-26 AWG		3163	3122	3101
Cover Color		Orange	Yellow	Red

mm		[in.]	
Tolerance Unless Noted			
	0.0	0.00	
mm	±.1	±.10	

() Dimensions for Reference Only

Ordering Information

371XX-XXXX-000 FL

Positions
03 or 04

Wire AWG & OD:
2XXX = 20-22 AWG
3XXX = 24-28 AWG
Wire OD - see Table 1

Note: Terminate using common pliers or 3M™ Scotchlok™ E-9BM or E-9E crimping tools.

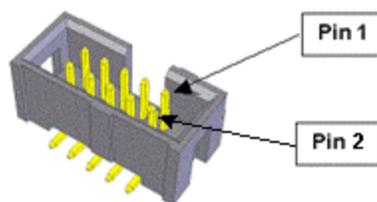
TS-2092-03
Sheet 2 of 2

AMP Plug Part Numbers:

Plug Housing					
Wire Range*	0.1-0.5 mm ² [27-20 AWG]				
Outside Diameter	0.6-0.9 [.024-.035]	0.9-1.0 [.035-.039]	1.0-1.15 [.039-.045]	1.15-1.35 [.045-.053]	1.35-1.60 [.053-.063]
Color	Orange	Red	Yellow	Blue	Green
Part Number	3-1473562-4	1-1473562-4	1437562-4	2-1473562-4	4-1473562-4

Digital Outputs (IDC Type Connector)

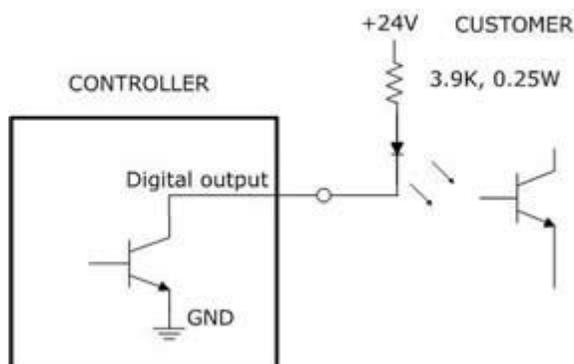
On MCIM boards with IDC type DIO connectors, 8 general purpose optically isolated digital output signal lines are provided and accessed in a single connector. This IDC type connector permits these signals to be easily interfaced to other devices.



By setting eight sets of [Sinking Versus Sourcing Jumpers](#), each output can be individually configured as either "sinking" or "sourcing".

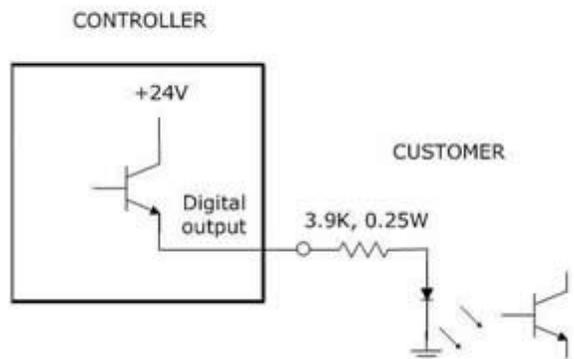
If an output signal is "sinking", the external equipment must provide a 5VDC to 24VDC pull up voltage on the output pin and the controller pulls this pin to ground when the signal is asserted as true.

SINKING DIGITAL OUTPUT



If an output signal is "sourcing", the external equipment must pull down the output pin to ground and the controller pulls this pin to 24VDC when the signal is asserted as true.

SOURCING DIGITAL OUTPUT



As shipped from the factory, all digital outputs are normally configured as "sinking".

The pin out for the Digital Output Connector is described in the following table.

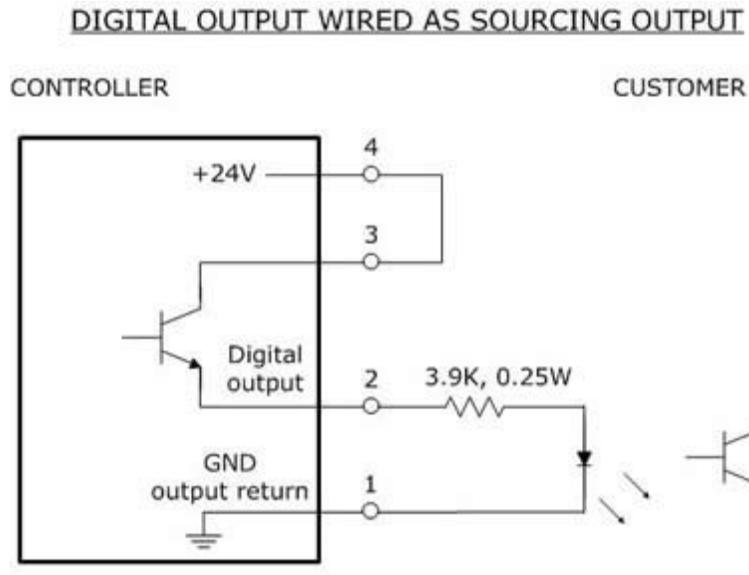
Pin	Description
1	Digital Output 1 - This output signal can drive 500mA of current whereas Outputs 2-8 can only drive 100mA. Due to this higher drive level, even when this output is off, a small amount of current leaks. This leakage can cause some devices that are connected to this signal to always indicate that this output is on. If this occurs, a small drainage resistor should be tied to this signal.
2	Digital Output 2
3	Digital Output 3
4	Digital Output 4
5	24 VDC
6	GND
7	Digital Output 5

8	Digital Output 6
9	Digital Output 7
10	Digital Output 8
User Plug Part No	AMP 746285-1 or Molex 22-55-2101 or 90142-0010. For the Molex plug, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

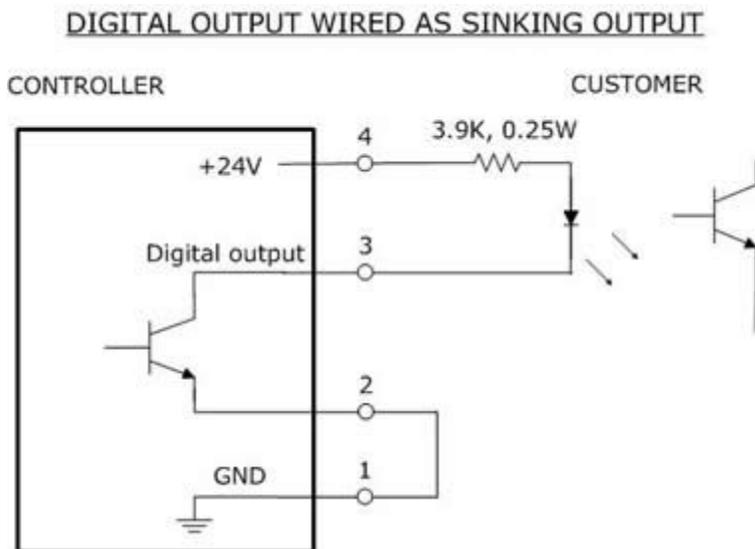
Digital Outputs (Individual Connectors)

On MCIM's with individual DIO connectors, there are 2 connector housings that each contain 4 digital output connectors, thus providing individual connectors for a total of 8 optically isolated digital output signals. Each digital output connector is a 4-pin connector in which pin 1 is connected to ground and pin 4 is connected to 24VDC. Pin 2 is connected to the emitter of the output transistor. Pin 3 is connected to the transistor collector.

To configure a digital output where the controller is providing a voltage signal (i.e. a “sourcing” digital output), pin 3 must be connected to pin 4 by means of a jumper wire in the IDC digital output connector thus connecting the collector of the transistor to 24 VDC. Pin 2 is then connected to the external equipment, which uses pin 1 as the ground return. When the controller turns the opto driver on, 24 VDC is provided to pin 2. This wiring is illustrated in the following diagram.



To configure a digital output where the controller is providing a ground signal (i.e. a “sinking” digital) output, pin 2 must be connected to pin 1 by means of a jumper wire in the IDC digital output connector thus grounding the emitter of the transistor. Pin 3 is connected to the external equipment that must provided 5-24VDC on this line. Pin 4 provides 24 VDC for use by the external equipment. When the controller turns the opto driver on, pin 3 will be pulled to ground. Pin 1 is located towards the center of the board. This wiring is illustrated in the following diagram.



Digital outputs 2-7 can drive 100ma, and output 1 can drive 200ma.

The mating plug for digital inputs and outputs and analog inputs is the 3M 37104 series Mini-Clamp Plugs. For example, if you use the 3M 3319 Series High Flex Life IDC Flat Cable with 24 AWG wire, the part number for the required plugs is 3M 37104-3122-000 FL. Please see the section on Digital Input Connectors for more information on these plugs.

Pin	Sourcing digital output	Sinking digital output
1	GND, output return	GND
2	Digital output signal (24 VDC)	Connected to pin 1
3	Connected to pin 4	Digital output signal (GND or open)
4	24VDC	24VDC
User Plug Part No	3M 37104 series Mini-Clamp Plugs or Amp 1473562-4	

Digital I/O: Sinking Versus Sourcing Jumpers

When referring to digital input and output signals, "sinking" and "sourcing" indicates whether the external equipment or the controller provides current to power the signaling operation. For the MCIM boards with IDC type DIO connectors, the selection of sinking or sourcing is controlled by a series of jumpers on the MCIM board.

For digital inputs, if the controller is "sinking", the external equipment must connect the input signal to a voltage to indicate a logical high value. If the controller is "sourcing", the external equipment must connect the input signal to ground to indicate a logical high value. The digital input signals can be configured as sinking or sourcing in groups of 4 signals. This configuration is performed using three sets of three jumper posts labeled J4, J5 and J6. **As shipped from the factory, all digital inputs are normally configured as "sourcing".**



For digital outputs, if the controller is "sinking", the external equipment must connect the output signal to a pull-up voltage. If the controller is "sourcing", the external equipment must connect the signal to a pull-down pin to ground. The digital output signals can be individually configured as sinking or sourcing. This configuration is performed using a block of 8 rows of jumper posts, 5 pins per roll, labeled J7. **As shipped from the factory, all outputs are configured as "sinking".**



The location of these posts are illustrated in the diagram of the Rev 6 MCIM and are identified by stenciled labels on the surface of the board.

The following tables indicate how the pins of each set of posts must be shorted ("jumpered") in order to achieve the specified configuration.

Digital Input Signals	For Sinking Inputs	For Sourcing Inputs
Inputs 1 to 4	J4-3 TO J4-2	J4-2 TO J4-1
Inputs 5 to 8	J5-3 TO J5-2	J5-2 TO J5-1
Inputs 9 to 12	J6-3 TO J6-2	J6-2 TO J6-1

Pins 1 are closest to the center of the board and pins 3 are closest to the edge of the MCIM board.

Digital Output Signals	For Sinking Outputs	For Sourcing Outputs
One row of 5 pins for each DOUT signal	Pins 2 TO 3 and 4 TO 5	Pins 1 TO 2 and 3 TO 4

The row closest to the Ethernet connector is for DOUT 1. Within each row, pins 1 are closest to the edge of the MCIM board and pins 5 are closest to the center of the board.

Ethernet Interface

In order to simplify networking controllers together via Ethernet, most recent Guidance Controllers contain four 10/100 BaseT Ethernet RJ45 connectors. In MCIM boards with IDC type DIO and AIO connectors, all

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four ports are active. For these boards, any of the four ports can be utilized with either a straight-thru or a cross-over Ethernet cable to connect to other equipment. However, in MCIM boards with individual DIO and AIO connectors, only one of the RJ45 connectors is operational. When interfacing to this type of MCIM, a standard, straight-thru cable must be used to connect the **bottom-left RJ45** connector directly to a PC.

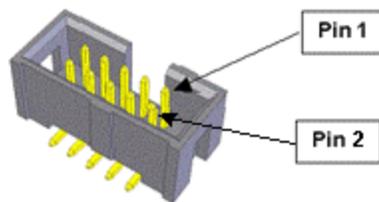


For MCIM's that support all four ports, the ports are interfaced to a built-in 10/100 Mbit Ethernet Switch that auto detects the sense of each cable. If two ports are connected to equipment that are communicating with each other but not the controller, the switch automatically routes the traffic between the two ports and does not send this information to the controller. For example, if an Ethernet camera is connected to one port and a PC is connected to another port, the camera image data will not burden the controller CPU.

See the *Setup and Operation Quick Start Guide* for instructions on setting the IP address for the controller.

I2C Interface

The Guidance Controller provides an I2C interface. This is a high-speed serial protocol that can be daisy-chained to interconnect multiple I2C devices. Currently, I2C is utilized internally in the controller to interface to a clock/calendar chip, the MCIM dip switches, and a series of temperature sensors. In the PrecisePlace robots, I2C is used to interface the controller to the robot's Z-axis IO board. For the 2000W PrecisePower Intelligent Motor Power Supply, an I2C connection provides power supply status information to the Guidance controller.



Please note that the Rev A MCIM boards had a different pin out. Should you wish to connect a I2C Module to this type of MCIM, please contact Precise Automation.

Pin	Description
1	24 VDC
2	24 VDC
3	GND
4	GND
5	GND

6	GND
7	SDA
8	VCC
9	SCL
10	GND
User Plug Part No	Molex 22-55-2101. For this Molex plug, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

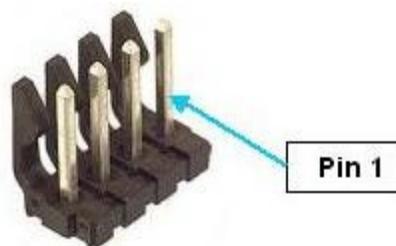
LED Indicators

There are two LED indicators mounted on the MCIM board. The conditions indicated by their colors are described in the following table.

	Red	Green
LED 1	<p>Off: System software has not started or is executing normally.</p> <p>On: System software was started but has stopped. An E-Stop is asserted by the hardware to ensure all motion has been terminated and power to the motors has been turned off.</p>	<p>Off: No power, or a severe hardware or firmware problem is preventing system initialization.</p> <p>On: Power is on and the system firmware and software are being loaded.</p> <p>Blinking: Normal operation. System software is loaded and active.</p>
LED 2	Not used	Not used

Motor Power On/24 VDC IN

This is a 4-pin header that is used to: (1) output signals that control turning on and off the external motor power supply and (2) input the 24 VDC that powers the digital section of the controller. If you purchase a PrecisePower Intelligent Motor Power Supply, Low Voltage Power Supply, and the Power Harness, there is a single cable that plugs into this header.



The motor "power on" signals are configured as a redundant pair of sinking signals. These should be wired to a pair of relays that are connected in series to enable and disable the motor power supply.

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Normally, 5 to 24 VDC is applied to this control circuit. The external motor power supply should be turned on when the controller's logic switches the "power on" signals to ground. These signals are automatically opened when an E-Stop or other condition occurs that requires that the amplifiers be shutdown.

The 24 VDC power input pins should be connected to a low voltage power supply that remains on independently of whether the motors are enabled. Turning off the 24 VDC will completely shutdown the controller.

The mating plug for this header is a Molex 09-50-3041 and the crimp style pins for this connector are 08-50-0105. The pin designations for this plug are as follows:

Pin	Description
1	GND
2	+24 VDC input
3	Motor power enable. Switched to ground when power is being enabled. Capable of sinking 2A at 24 VDC.
4	Motor power enable (Redundant signal). Provided to comply with safety standards.
User Plug Part No	Molex 09-50-3041. For this Molex plug, use Molex pins 08-50-0105 and Molex crimp tool 63811-2200.

Remote Front Panel Interface & Secondary RS-232 Port

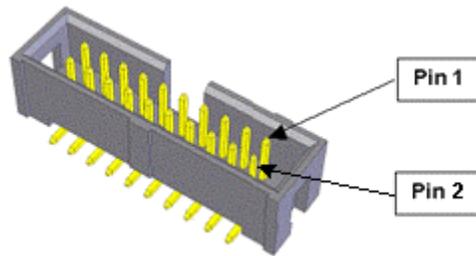
The remote front panel interface includes all of the signals necessary to implement a fully compliant EC Category 3 Safety front panel that includes a Manual Control Pendant. In particular, this connector provides signals (including redundancy as necessary) for implementing an E-Stop circuit, an auto/manual switch, a high power "on" button with a high power "on" indicator lamp, and a RS-232 interface to a Manual Control Pendant.

In the future, Precise will offer a Remote Front Panel option that plugs into this connector. Alternatively, customers can develop their own custom front panels (please see the section on "Safety Circuits For Remote Front Panel" for a suggested design). Or, if your application does not require a fully compliant Category 3 front panel, the controller can be operated without a front panel or with only a simple E-Stop button.

When a front panel is not utilized, the following pins on the front panel connector must be jumpered in order for the controller to operate properly. (The controller is shipped with these jumpers installed.)

1-2, 3-4, 5-6, 7-8, 9-10, 11-12, 13-14

If a Manual Control Pendant is not connected to the secondary RS-232 port provided in this connector, this serial interface can be accessed via a GPL procedure as device /dev/com2 for general communications purposes. Please note that unlike the primary serial interface, THIS SECONDARY SERIAL INTERFACE DOES NOT SUPPORT FLOW CONTROL.



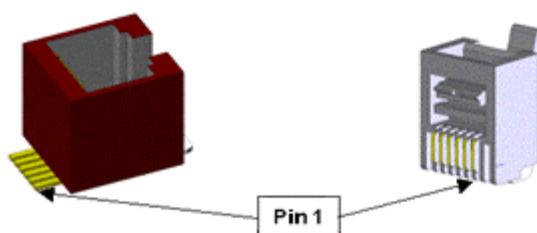
Pin	Description
1	Auto/Manual 2 (If no front panel or Auto/Manual switch, connect to pin 2). Input signal that is high to indicate that the system is being operated in a fully automatic mode or low or open for manual operation. This is normally controlled by a key switch on the Remote Front Panel of the master controller. During Manual Mode, each controller must restrict the speed of the mechanism using hardware means ("velocity restrict") in order to guarantee that the system can be safely operated even if the operator enters the work cell and commands the mechanism to move. The Auto/Manual signal is daisy chained to all controllers in a servo network.
2	24 VDC
3	Auto/Manual 1 (If no front panel or Auto/Manual switch, connect to pin 4). Redundant Auto/Manual input signal.
4	24 VDC
5	ESTOP_L 2 (If no front panel or E-Stop not asserted, connect to pin 6). An input signal that is low or open indicates that a hardware E-Stop condition has been asserted by some source. Set high if no E-Stop condition is asserted. The controller hardware will not permit motor power to be enabled when an E-Stop condition exists.
6	Force ESTOP_L. Output signal that, when low, indicates that the Remote Front Panel should force ESTOP_L 1 and ESTOP_L 2 to be asserted (low). The System Software toggles this signal low at startup to verify that the ESTOP_L 1, ESTOP_L 2, and External ESTOP circuits are properly working. The System Software also uses this as a means for asserting a hardware E-Stop condition during normal operation. This signal is normally held high.
7	ESTOP_L 1 (If no front panel or E-Stop not asserted, connect to pin 8). Redundant ESTOP input signal.
8	Force ESTOP_L. Redundant Force ESTOP_L output signal.
9	External ESTOP_L (If no front panel or not an External ESTOP, connect to pin 10). Diagnostic input signal that is low when an E-Stop is generated from an external source. This allows the System Software to display different error messages to alert the operator as to the source of the E-Stop condition.
10	Force ESTOP_L. Redundant Force ESTOP_L output signal.
11	High Power Lamp Fail (If no front panel, jumper to pin 12). Input signal that is set high or open if the Remote Front Panel lamp, which indicates when motor power is enabled, has failed. When this signal is high, motor power cannot be enabled.
12	Ground

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13	High Power Enable (If no front panel, jumper to pin 14). Input signal that must transition from low to high during the EC Category 3 power enable sequence to request that motor power be enabled. This is normally connected to a momentary contact "Enable power" push button on the Remote Front Panel.
14	Ground
15	Spare.
16	High Power Status. Output signal that is asserted (high) when high power to the motor is enabled. This is typically connected to a relay that turns on the High Power Lamp in the Remote Front Panel.
17	MCP RXD. RS-232 receiver serial line from the Manual Control Pendant or external device.
18	MCP TXD. RS-232 transmitter serial line to the Manual Control Pendant or external device.
19	5 VDC on MCIM's with IDC type DIO and AIO connectors, 24 VDC on MCIM's with individual DIO and AIO connectors.
20	5 VDC on MCIM's with IDC type DIO and AIO connectors, 24 VDC on MCIM's with individual DIO and AIO connectors.
User Plug Part No	Amp 746285-4 or Molex 22-55-2201 or Molex 90142-0020. For the Molex plugs, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

Primary RS-232 Serial Interface

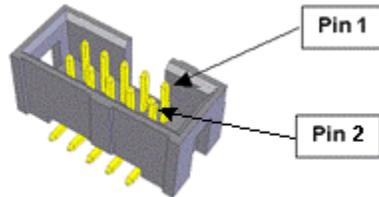
The primary RS-232 serial communication line connector is a RJ-11 modular jack, CablesNMor T23750. The plug is a standard RJ-11 phone plug, such as an Jameco 115617CH. This port is used as the serial console port and can also be accessed by GPL procedures as device /dev/com1.



Pin	Description
1	CTS - clear to send
2	RTS - ready to receive
3	Ground
4	RXD - controller receive data
5	TXD - controller transmit data
6	Not Connected
User Plug Part No	RJ-11 phone plug

RS-485 Serial Interface

RS-485 is a multi-drop serial communication interface. At the application level, it can transmit and receive data in a manner similar to an RS-232 interface with the added benefit that the communication lines can be daisy chained between multiple nodes instead of requiring point-to-point wiring. Currently, the RS-485 interface is only used between Precise hardware such as the controller for the PrecisePlace or PreciseFlex robots and their Z-Axis IO boards, and is **not available for interfacing to 3rd party devices.**



Pin	Description
1	24 VDC
2	24 VDC
3	GND
4	GND
5	GND
6	VCC
7	GND
8	RS485+
9	RS485-
10	GND
User Plug Part No	AMP 76285-1 or Molex 22-55-2101 or 90142-0010. For the Molex plug, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.

Selector Switch Settings

The 6-position selector switch provides a software system reset function and specifies controller configuration options. For normal operation, all switches should be set to ON.



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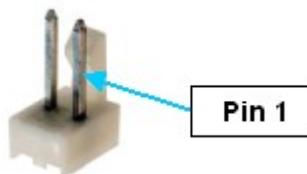
The pin definitions are:

Switch	Description
1	Software Reset. Set to ON for normal operation. Set to OFF to ignore the standard configuration files. If set to OFF when the system is restarted, the default configuration files (*.PAC) are applied instead of the standard files. This setting is utilized if a configuration file becomes corrupted or a setting inadvertently makes the system unusable.
2	Master or Slave node in a multiple controller servo network. This switch is normally set to ON to indicate the controller is operating standalone or is the Master in a servo network. Must be set to OFF to indicate that the controller is to startup as a Slave in a servo network.
3	TBD. Should be set to ON.
4	TBD. Should be set to ON.
5	TBD. Should be set to ON.
6	TBD. Should be set to ON.

Status Output Connector

The MCIM includes an LED that indicates the status of the controller by blinking. When the controller is first powered on, the LED blinks at a rate of once per second. When power to the motors is enabled, the blinking rate increases to 4 times per second. If the controller is embedded, an external LED can be connected to a General Digital Output Signal and the blinking function can be mapped to the signal.

As a convenience, the 8th General Digital Output Signal is duplicated in a 2 pin header. This permits an LED to be easily wired to the controller without having to breakout this one signal from the [General Digital Outputs Connector](#).

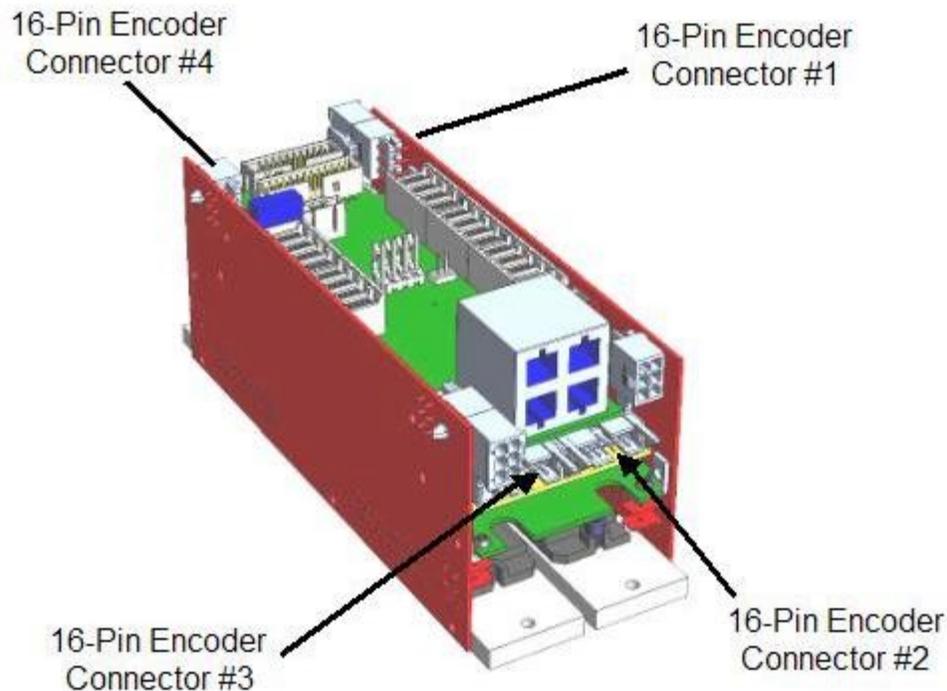


To configure the 8th Digital Output Signal to blink according to the controller status, the "Power State DOUT" (DataID 235) value in the controllers Parameter Database should be set to "8".

Pin	Description
1	Digital Output 8
2	GND
User Plug Part for Molex 22-23-2021	Molex 22-01-2021

MIDS Board Encoder Connectors

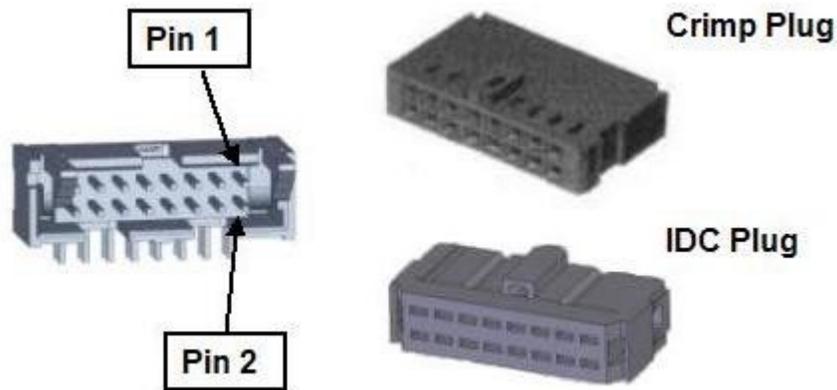
There are four identical 16-pin encoder connectors on the MIDS Board (CPU Board). There are two connectors mounted on each end of the board. They are numbered in the same order as the labeled motor connectors. The following illustrates the positions of the encoder connectors.



The MIDS connectors are configured so that a variety of incremental or absolute encoders can be connected to the controller. Pins 2, 3, 5, 6, 8 and 9 will accept either a standard digital or an optional analog sin wave encoder signal. For analog encoder signals, an optional 12-bit ADC is used to digitize the signals. This ADC can also interpolate the analog encoder signals to increase the effective resolution of the encoder. Absolute encoders are interfaced via these same signal pins. (See the "Third Party Equipment" section of this manual for information on connecting supported absolute encoders.) Either single ended or differential encoder signals can be connected to this main axis encoder interface. (Analog and absolute encoder interfaces are only available on the "Enhanced" versions of the Guidance Controllers due to special hardware requirements.)

In addition to the main axis encoder interface, there are 3 digital inputs available in each encoder connector. These can be configured for hall-effect sensors or two over-travel sensors plus a homing sensor. When configured for these functions, they should be treated as standard 5VDC sourcing digital inputs connections. Alternatively, these signals can interface to a second, single ended encoder. The single ended encoder can be used independently of the main axis encoder or the two encoders can be used together to implement dual encoder loop servo control of an axis of motion.

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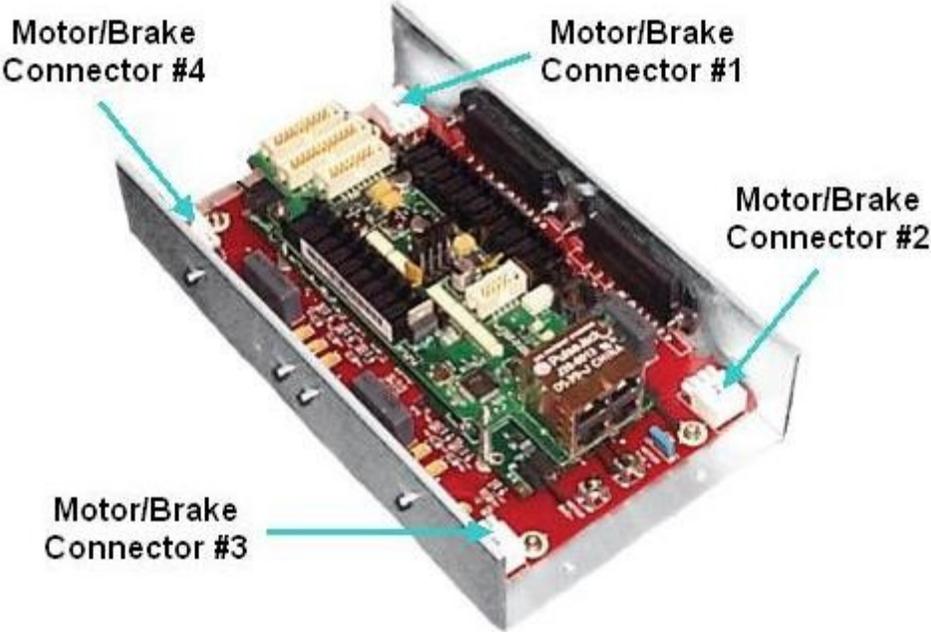
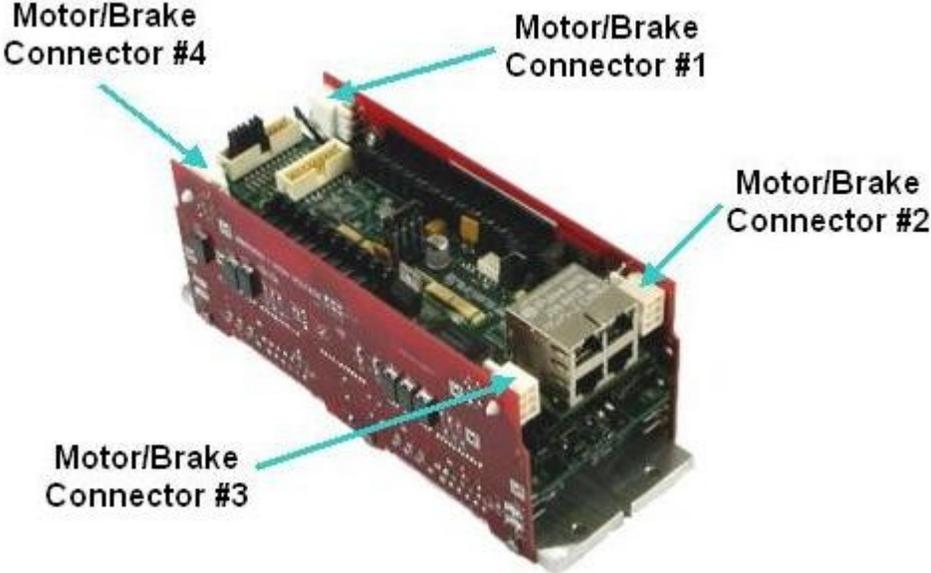


The following table defines the connector pin outs. The second column should be used when the 3 digital inputs are configured for hall-effect sensors or over-travel switches and a homing sensor. The third column describes the pin outs when a second, single ended encoder is utilized.

Pin	3 Digital Inputs (5 VDC)	2nd Encoder (5 VDC)
1	Gnd	
2	Encoder 1 A+ (Digital or Analog)	
3	Encoder 1 A- (Digital or Analog)	
4	5VDC provided to power encoders. The sum of the current drawn from all four encoder connectors is limited to 1 amp.	
5	Encoder 1 B+ (Digital or Analog)	
6	Encoder 1 B- (Digital or Analog)	
7	Gnd	
8	Encoder 1 Z+ (Digital)	
9	Encoder 1 Z- (Digital)	
10	Gnd	
11	Digital Input #1 Hall #1 or Homing Switch	Encoder 2 A+
12	Gnd (Reserved for Abs Encoder Bat Gnd)	
13	Digital Input #2 Hall #2 or Positive Over-Travel	Encoder 2 B+
14	Vcc (Reserved for Abs Encoder Bat Pwr)	
15	Digital Input #3 Hall #3 or Negative Over-Travel	Encoder 2 Z+
16	Gnd	
Board Header	Amp 104315-03-3-o-s	
IDC Plug	Amp 746285-3	
Alternate Crimp Plugs	Amp 102387-3 or Molex 90142-0016. For the Molex plug, use Molex pins 16-02-0102 and Molex crimp tool 63811-1000.	

HVPA/LVPA Motor/Brake Connectors

There are identical motor/brake connectors located on the High Voltage Power Amplifiers (HVPA) for the Guidance 3000 (excluding the 30A version, see below) and on the Low Voltage Power Amplifier (LVPA) for the Guidance 2000. Each HVPA has two motor drivers per board with two connectors mounted at the top edge. Each LVPA has four motor drives with a connector mounted at each corner. These connectors are numbered on their tops and are illustrated below for each type of controller.

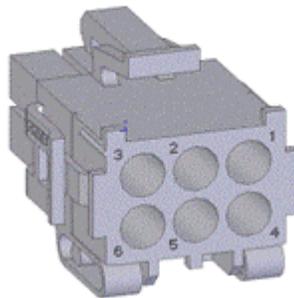


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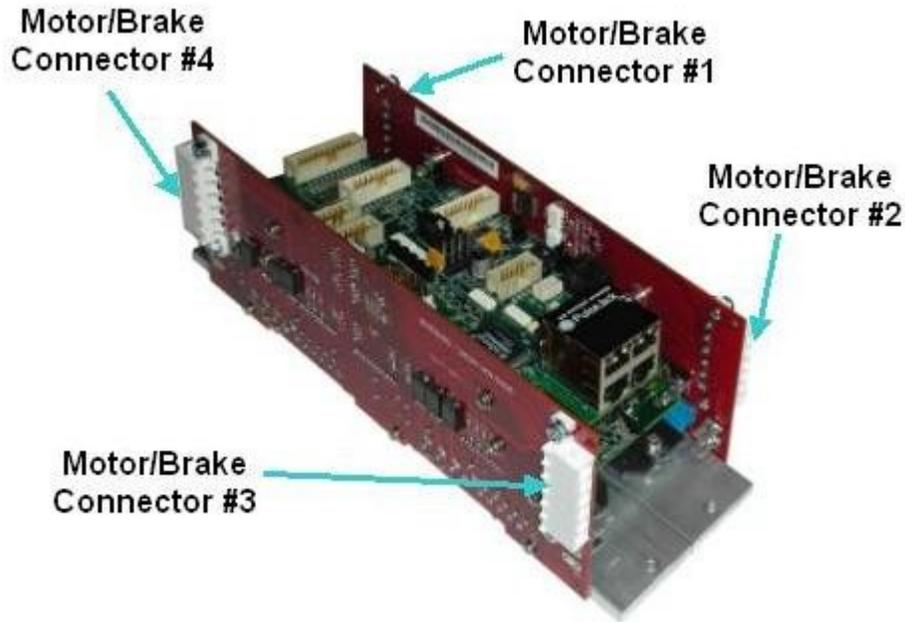
DANGER: The High and Low Voltage Power Amplifiers (HVPA's/LVPA's) and the Motor/Brake connectors and their leads contain unshielded high voltage pins, components and surfaces. It is intended that the Guidance Controllers with these components be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Mating plugs and pins for the motor/brake connectors are shown below. See the Amp Catalog 82181 page 91 for other wire gauges. Please note that although all of the motor/brake connectors have a brake signal, this is only provided as a wiring convenience. The Guidance Controllers currently turn all brakes on and off at one time, so independent brake control for each motor is not supported via the dedicated IO lines available in this connector.



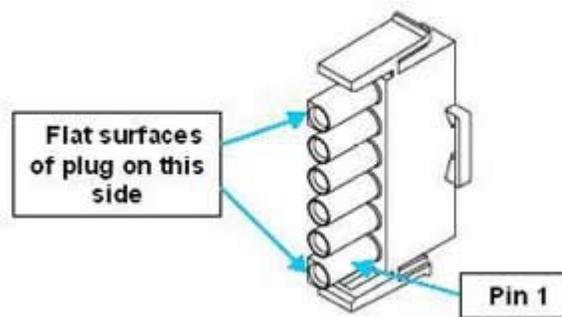
Pin	Description
1	Brake Power 24VDC, maximum current 2A total for all brakes
2	Motor Phase V
3	Motor Phase W
4	Brake Power Return
5	Motor Frame Ground/Cable Shield
6	Motor Phase U
Board Connector Part No	AMP Mini Universal Mate-N-Lok 2 6 pin 770969-1
User Plug Part No	Amp 794190-1 (pins AMP 794231-1)
User Socket Part No	Amp 794231-1 for 16-20 gauge wire
Crimp Tool	Amp 91594-1

The 30A version of the Guidance 3400 controller, the Guidance 3430, utilizes a different motor/brake connector that can support larger gage wires and higher motor currents. Each of the High Voltage Amplifier (HVPA2) boards has two motor drives and two connectors mounted on the side of the board. The numbering for the motor/brake connectors is illustrated below.



DANGER: The High Voltage Power Amplifiers and the Motor/Brake connectors and their leads contain unshielded high voltage pins, components and surfaces. It is intended that the Guidance Controllers with these components be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Mating plugs and pins for the motor/brake connectors are shown below. Please note that although all of the motor/brake connectors have a brake signal, this is only provided as a wiring convenience. The Guidance Controllers currently turn all brakes on and off at one time, so independent brake control for each motor is not supported via the dedicated IO lines available in this connector.



Pin	Description
1	Motor Phase U
2	Motor Phase V
3	Motor Phase W
4	Motor Frame Ground/Cable Shield

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5	Brake Power Return
6	Brake Power 24VDC, maximum current 2A total for all brakes
Board Connector Part No	Tyco Electronics 640587 Universal Mate-N-Lok
User Plug Part No	Tyco Electronics 640585 6 Circuit Universal Mate-N-Lok
User Socket Part No	AMP 350550-1 for 14-20 gauge wire
Crimp Tool	AMP 90546-1

Low Voltage Power Supply

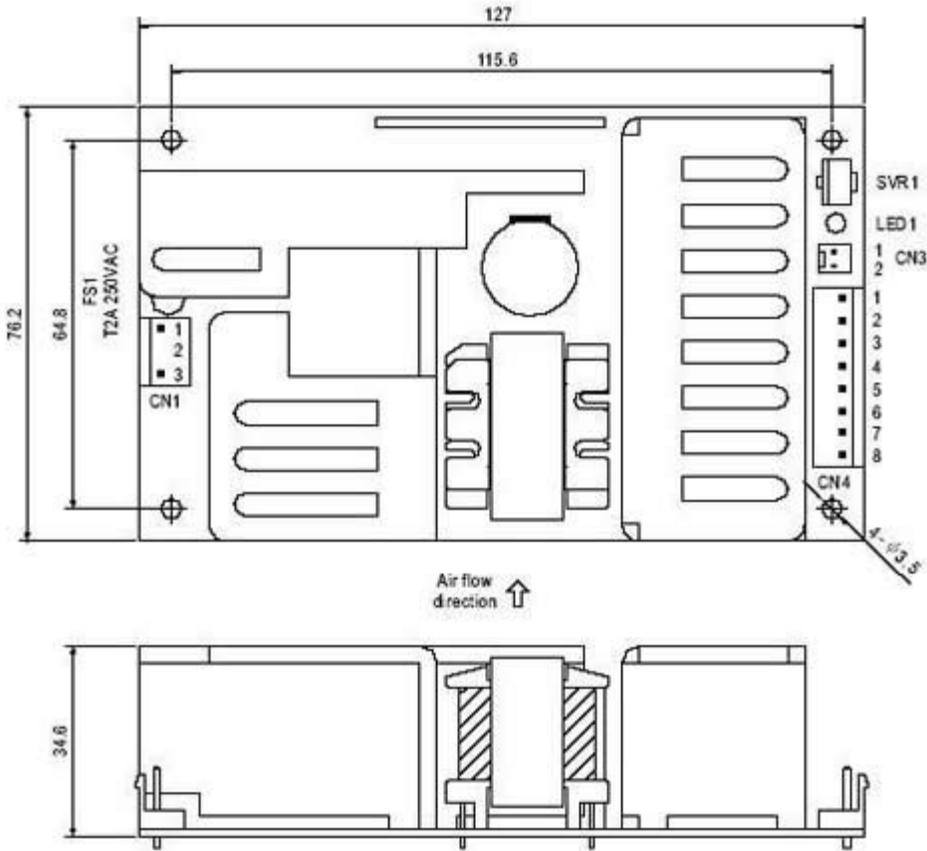
The Guidance Controller requires a minimum of 2.7 amps and preferably 4 amps of 24 VDC power for the logic and IO. An additional 1 amp is required to operate the dual safety contactors on the 2000W PrecisePower Intelligent Motor Power Supply.

A commercially available 24VDC power supply, the Mean Well P/N PPS-125-24 is shown below. This is a frameless supply that should be mounted on 4mm high standoffs. Mounting holes are 4mm diameter and will clear 3mm or 6-32 screws. They are located on 64.8mm and 115.6mm centers. The AC input connector is a JST VHR-3N and the DC output connector is a JST VHR-8N. Pins 1-4 on the DC connector are GROUND and pins 5-8 are 24VDC.

For the JST VHR connectors, use pins SVH-21T-1.1 and JST crimp tool WC-160.



DANGER: The Mean Well 24 VDC power supply is an open frame electrical device that contains unshielded high voltage pins, components and surfaces. This product is intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.



General Specification	Range
Input voltage	90 - 264 VAC
Input frequency	47 - 63 Hz
Output voltage	24 VDC
Output power	125 watts
Operating temperature	0 - 40 deg C
Storage temperature	-20 - 85 deg C
Dimensions	127 x 76.2 x 34.6 mm
Precise Part Number	PS10-EP-00125

Motor Voltage Power Supplies

Motor Voltage Power Supplies

The Guidance 3xxx Controllers can operate with motor bus voltages ranging from 24 VDC to 320 VDC. Users may employ their own DC motor power supply or may purchase an intelligent motor power supply from Precise. Precise offers two Intelligent Motor Power Supplies: the PrecisePower 500 (500 watts RMS) and the PrecisePower 2000 (2000 watts to 3400 watts RMS). These units include: integral relays for enabling/disabling motor power on command from the controller, large value output filter capacitors to store deceleration energy for use when power is needed, the ability to absorb line spikes, and built-in fuses.

To permit the Guidance Controller to enable and disable motor power, the power supply must be equipped with either one or two (redundant) relays. These relays should be wired to the "Motor power enable" signals provided on the "Motor Power On/24VDC" header of the controller.

If you purchase a PrecisePower unit and Precise's standard low voltage power supply, you can also obtain a Guidance Controller Power Harness that interconnects the two power supplies and the Guidance 3xxx Controller (see the section on "Power Connectors and Grounding").

Regarding the sizing of the motor power supply, as a rule-of-thumb for typical robotic application, a motor power supply can drive a group of motors whose total rating is approximately 4 times the rating of the motor power supply. For example, the 500 watt PrecisePower 500 can normally drive motors with a total rating of 2000 watts. This is due to the fact that motor power ratings are typically defined by the "rated torque" that can be supplied at the "rated speed" of the motor. However, in most robot applications, high torque is only require at low speed. As a case in point, the PrecisePower 500 is being successfully used to drive a Cartesian robot at full speed where the size of its four motors are 750W, 400W, 200W and 100W (1450W total).

PrecisePower 500 Intelligent Motor Power Supply

The PrecisePower 500 is a 500 watt auto-ranging Intelligent Motor Power Supply with dual input ranges of 90 to 132 VAC and 180 to 264 VAC 50/60 Hz and a 320 VDC output. This unit includes a single integral relay for enabling and disabling motor power from the controller, large value output filter capacitors to store deceleration energy for use when power is needed, the ability to absorb line spikes, the ability to limit the peak output voltage, and built-in fuses.

To enable the power supply's relay, a three conductor cable must connect the controller's "Motor Power On/24 VDC" connector to the three pin header pictured below in the top right of the power supply. This cable should connect the controller's "Motor power enable" signal, 24VDC and ground to the corresponding pins on the power supply. The 24VDC and ground signals must in turn be connected to the 24 VDC power supply, which provides low voltage power to both the controller and the motor voltage power supply. To connect to the three pin header to the motor power supply, a Molex 09-50-3031 or compatible plug can be utilized.

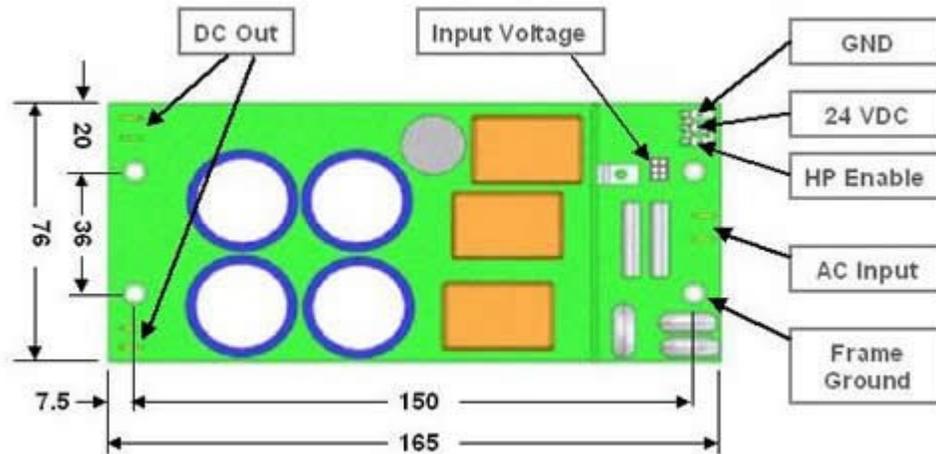
This motor power supply includes push on tabs for the input AC power and the output DC power. The DC output is provided on two pairs of output terminals that should be connected to the DC input terminals on the vertical (HVPA) power amplifier circuit boards of the Guidance Controller (see the section on "Power Connectors and Grounding"). Both the DC output terminals and the AC input terminals use tabs compatible with Amp 3-520133-2 Faston receptacles.

For mounting purposes, the power supply has four 4.1mm through holes as illustrated in the drawing below.

This power supply limits inrush current to 6 Amps. It is protected against voltage surge to 2000 volts common mode by means of MOVs at the line input. It is protected against over current by two 6.3 amp, 250V time lag fuses, Wickman PN 1811630000.

To configure this unit, at the right end of the power supply, there are three sets of jumper pins labeled "90-132V", "Auto", and "180-264V" and indicated as "Input Voltage" in the picture below. A jumper must be placed across one of these sets of pins to select the power supply operating mode. The power supply includes a voltage doubling circuit. This circuit is activated when the jumper is placed across the "90-132V" pins, disabled when the "180-264V" jumper is installed, and automatically activated when a jumper is placed across the "Auto" mode pins. The output voltage range for each jumper is illustrated in the following table. The power supply is normally shipped with the jumper on the "Auto" setting to allow it to generate a nominal voltage of 320 VDC worldwide with the factory setting.

AC input	90-132V (2X) Jumper	Auto Jumper	180-264V (1X) Jumper
90 to 132 VAC	253-372 VDC	253-372 VDC	127-186 VDC
180 to 264 VAC	Invalid setting	253-372 VDC	253-372 VDC



DANGER: The PrecisePower 500 Intelligent Motor Power Supply is an open frame electrical device that contains unshielded high voltage pins, components and surfaces. This product is intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

PrecisePower 2000 Intelligent Motor Power Supply

For applications requiring a larger intelligent motor power supply, the PrecisePower 2000 delivers 2000 watts of power from a single-phase 208VAC service or 3400 watts from a three-phase 240VAC service. This unit includes dual integrated relays for enabling and disabling motor power on command from the controller, large value output filter capacitors to store deceleration energy for use when power is needed, the ability to absorb line spikes, the ability to limit the peak output voltage, and built-in fuses. In addition, it has safety circuits to automatically shut-down the unit if it is switched to a short or is severely over-loaded.

In order to power the logic in this unit, 24VDC must be provided from a separate 24VDC power supply. As a wiring convenience, the AC line voltage input to the PrecisePower 2000 is presented on two pins that can be utilized to power the 24VDC supply. For these pins as well as two other headers, mating cables can be connected to the PrecisePower via a **????** or compatible plug.

To enable the PrecisePower's motor power output, its redundant dual relays must be connected to the "Motor Power On/24VDC" header of the controller and be enabled by the controller. A four conductor cable should be used to connect the two "Motor power enable" signals, 24VDC and ground. The 24VDC pin on the controller header is the DC input that provides power for the controller's logic. The PrecisePower routes its 24VDC input to the controller via this cable to simplify system wiring.

To satisfy IEC Category 3 requirements and to report power supply errors to the controller, a 10-pin 26AWG ribbon cable should be routed from the PrecisePower unit to the I2C plug on the Guidance Controller.

This intelligent motor power supply includes push on tabs for the input AC power and the output DC power. The DC output is provided on two pairs of output terminals that should be connected to the DC input terminals on the vertical (HVPA) power amplifier circuit boards of the Guidance Controller (see the section on "Power Connectors and Grounding"). Both the DC output terminals and the AC input terminals use tabs compatible with Amp 3-520133-2 Faston receptacles.

For mounting purposes, the power supply has four 6.4mm through holes as illustrated in the drawing below.

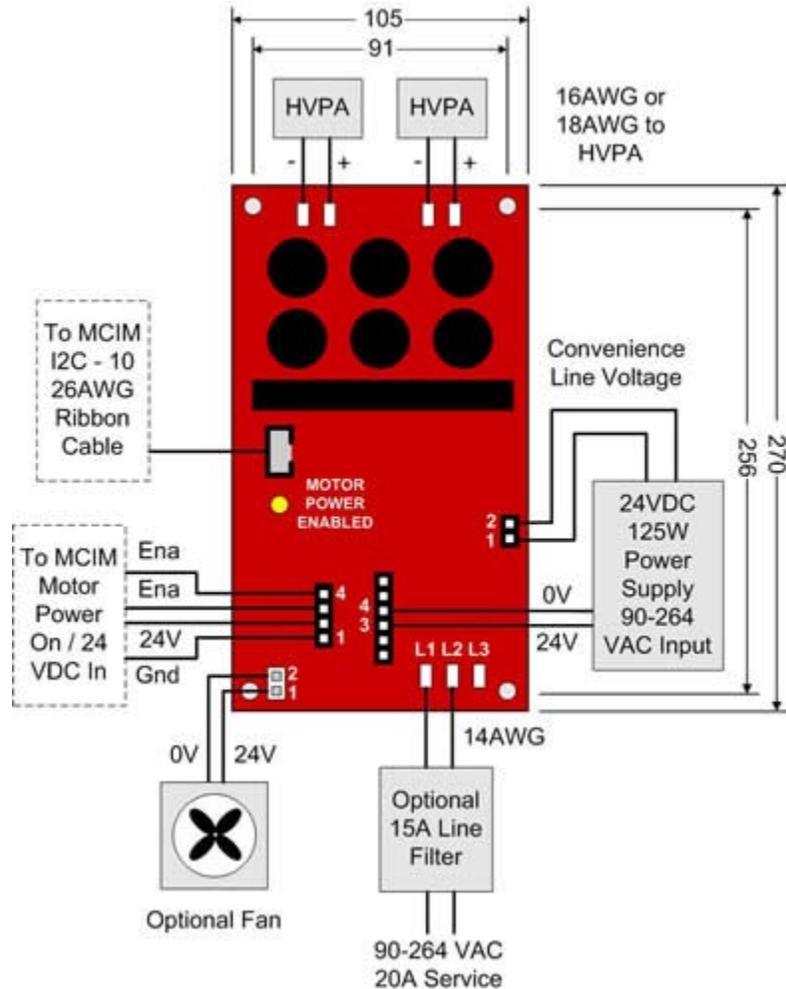
This power supply can accept line voltages from 90VAC to 240VAC. The motor power output voltage is a multiple of the input line voltage (output = 1.41*RMS_input). The maximum RMS power output of the unit is 2000 watts at 240VAC single phase or 3400 watts at 240VAC 3-phase. The single phase AC voltage is available worldwide.

To connect this power supply to a 3-phase AC source, simply connect the 3rd phase to the L3 Faston tab. No other changes are required. The 3-phase voltage compatible with this unit is only available in certain countries, notably the U.S., Japan and other parts of Asia.



WARNING: For this unit, the voltage from PHASE-TO-PHASE must not exceed 240VAC. Some countries specify their power in terms of the voltage of each phase relative to ground. A 3-PHASE POWER SOURCE SPECIFIED AT 220VAC WILL DAMAGE THE POWER SUPPLY IF THE PHASE-TO-PHASE VOLTAGE EXCEEDS 240VAC.

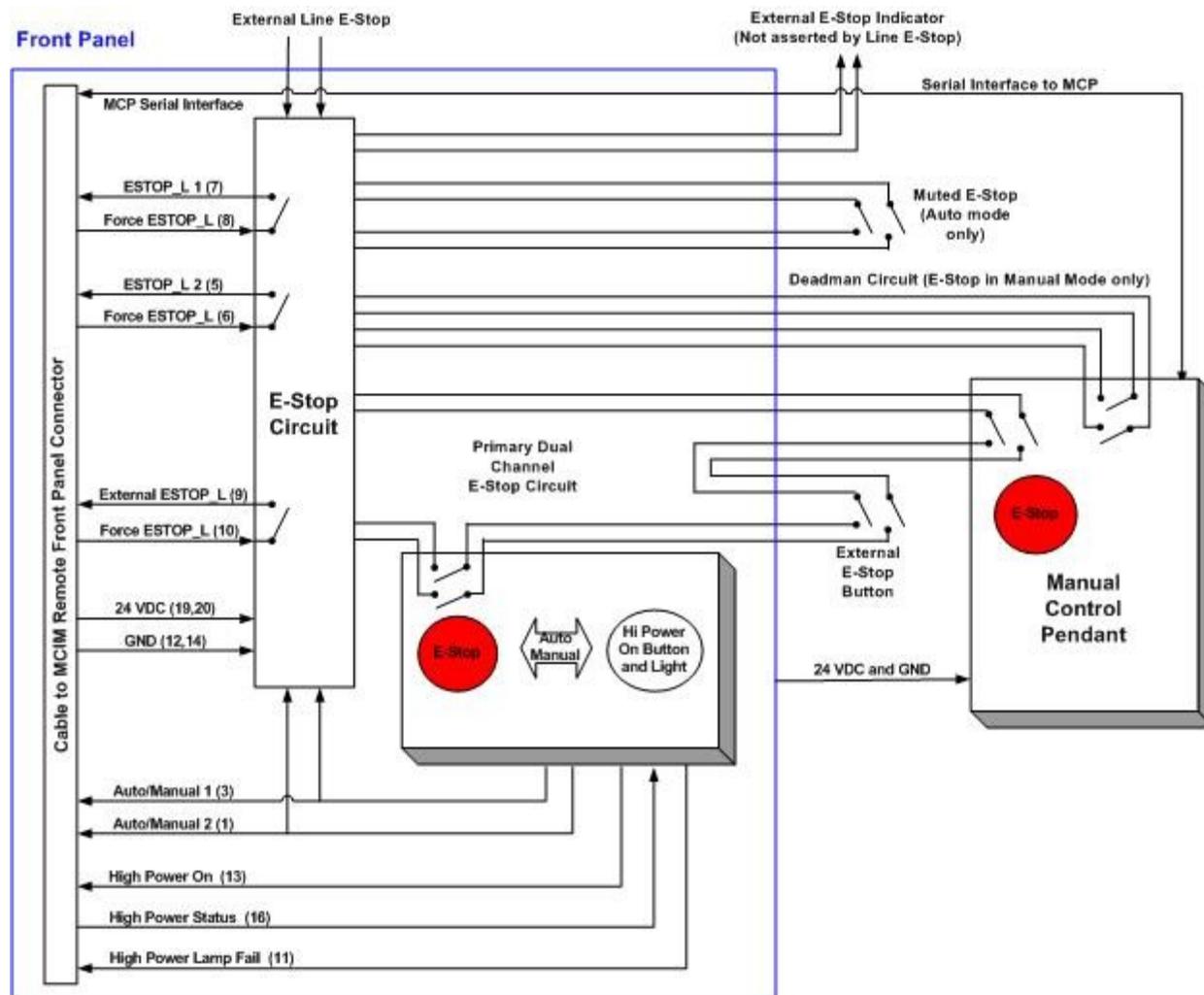
For 2000 watts and above, forced air is required to cool the PrecisePower. A 24VDC output connector is provided to powering an optional fan.



DANGER: The PrecisePower 2000 Intelligent Motor Power Supply is an open frame electrical device that contains unshielded high voltage pins, components and surfaces. This product is intended to be mounted in a cabinet or machine chassis that is not accessible when AC line power is turned on.

Safety Circuits For Remote Front Panel

The diagram below illustrates how a Category 3 compliant user front panel and manual control pendant can be interfaced to the Remote Front Panel Connector provided on the [MCIM](#) board. Should your application not require this level of operator interaction or compliance with full Category 3 safety regulations, the Remote Front Panel Connector documentation provides directions on how to jumper this connector for proper operation of the controller without the front panel.



Some of the features of the Remote Front Panel Safety Circuit are briefly described in the following paragraphs. For the signals that route to the Remote Front Panel Connector, the signal names correspond to the pin designators for this connector and the pin numbers are denoted in parentheses.

The Remote Front Panel circuit supports several different sources of E-Stop signals. Some of these E-Stops are always active while others are only active in certain modes of operation. Whenever an active E-Stop is asserted, the result is that the **ESTOP_L 1** and **ESTOP_L 2** signals are asserted by disconnecting them from the **Force ESTOP_L** signals. The E-Stop sources include the following:

External E-Stop Button . Normally connected to an E-Stop button or series of E-Stop buttons that are placed around the work cell.

External Line E-Stop. Typically utilized by external equipment in the cell or the manufacturing line to E-Stop the controller as well as other devices. In order to avoid a dead-lock condition, the **External E-Stop Indicator Signal** is asserted when any E-Stop source other than the **External Line E-Stop** is asserted. The **External E-Stop Indicator** is not asserted by the **External Line E-Stop** signal to avoid a dead lock condition that

could occur if an external device (such as a line control PLC) were to loop back the **External E-Stop Indicator** to the **External Line E-Stop** signal.

Muted E-Stop. This signal only generates an E-Stop Condition in Auto Mode. This allows the **Muted E-Stop** to be connected to a safety gate that surrounds the equipment. Opening the safety gate during normal automatic operation will turn off high power. However, during Manual Mode, an operator can open the gate and enter the cell without disabling high power.

MCP Deadman's Circuit. This circuit must be closed in order to operate the system during Manual Mode. A Deadman's circuit is typically connected to a 3 position hold-to-run switch integrated into the MCP. The Deadman's circuit is ignored during Auto Mode.

The **Auto/Manual** signals are connected to a switch that sets whether the system is being operated in automatic mode or manual mode. The setting of this switch also effects the **Muted E-Stop** and the **MCP Deadman's Circuit**.

The **High Power Status** signal from the MCIM connector is routed to a relay that turns on a lamp that indicates is motor power is enabled. If this lamp fails, the **High Power Lamp Fail** signal is asserted and motor power cannot be enabled until this problem is corrected.

The **High Power On Button** is a momentary contact switch that transitions the **High Power On** signal from low to high during the Category 3 power enable sequence.

Third Party Equipment

Third Party Equipment

This section contains instructions on interfacing to 3rd party equipment that is commonly utilized in combination with the Guidance Controllers. For detailed information on each of these products, please refer to the manuals provided by the manufactures of these components.

Panasonic A4 Serial Incremental/Absolute Encoder

This section provides wiring instructions for a Panasonic motor equipped with a Panasonic A4 17-bit serial incremental/absolute encoder or a 10000 count serial incremental encoder. These encoders transmit their position data as a serial bit stream via RS-485 lines rather than A-B incremental pulses. These encoders can be utilized as high resolution incremental encoders that provide either 17-bits or 10000 counts per revolution. In addition, if the 17-bit encoder is provided with continuous power with a battery backup, it functions as a high resolution absolute encoder that provides 33-bits of encoder position information. The continuous power is used to maintain a 16-bit "turns count" register that augments the 17-bits per turn data.

Due to the additional capabilities needed to process the absolute encoder signal, these encoders are only supported on the "Enhanced" versions of the Guidance Controllers.

For information on configuring this type of encoder, please see the *Software Setup* section of the *Controller Software* section of the *Documentation Library*.

The following are the wiring instructions for the **Encoder Connectors**.

Encoder Connector Pin	Wire Color	Signal Name	Controller Connector Pin
1	RED	BATTERY+	14
2	PINK	BATTERY -	12
3	GREEN	FG	
4	BLUE	PS+	2
5	VIOLET	PS-	3
6	NC	NC	
7	WHITE	VCC	4
8	BLACK	GND	1
9	NC	NC	

The following are the wiring instructions for the **Motor Power Connectors**:

Motor Connector Pin	Wire Color	Signal Name	Controller Connector Pin
1	RED	U	6
2	WHITE	V	2
3	BLACK	W	3
4	GREEN	GND	5
1	YELLOW	BRAKE+	1
2	YELLOW	BRAKE-	4

If the encoder is to be used in absolute mode, a battery must be connected to the [Absolute Encoder Battery Connector](#) on the MCIM board. Please see the information on that connector for detailed pin outs and plug types. The following table contains information on the required battery power.

External Battery Specification	
Maximum voltage	4.75V
Typical voltage	3.6V
Alarm trigger voltage	3.1V
Current for each encoder	3.6 uA

Tamagawa Serial Incremental/Absolute Encoder

This section provides wiring instructions for a motor equipped with a Tamagawa SA35-17/33Bit-LPS (T5667N120/N127) absolute encoder. This encoder transmits its position data as a serial bit stream via RS-485 lines rather than A-B incremental pulses. This encoder can be utilized as high resolution incremental encoder that provides 17-bits of resolution per revolution. In addition, if this encoder is provided with continuous power with a battery backup, it functions as a high resolution absolute encoder that provides 33-bits of encoder position information. The continuous power maintains a 16-bit "turns count" register that augments the 17-bits per turn data.

Due to the additional capabilities needed to process the absolute encoder signal, these encoders are only supported on the "Enhanced" versions of the Guidance Controllers.

For information on configuring this type of encoder, please see the *Software Setup* section of the *Controller Software* section of the *Documentation Library*.

The following are the wiring instructions for the **Encoder Connectors**.

Wire Color	Signal Name	Controller Connector Pin
BROWN	BATTERY+	14
BROWN/BLACK	BATTERY -	12
GRAY	FG	7
BLUE	PS+	2

Guidance 3000/2000 Controllers

BLUE/BLACK	PS-	3
RED	VCC	4
BLACK	GND	1

If the encoder is to be used in absolute mode, a battery must be connected to the [Absolute Encoder Battery Connector](#) on the MCIM board. Please see the information on that connector for detailed pin outs and plug types.

Yaskawa Sigma II Serial Absolute Encoder

This section provides wiring instructions for a Yaskawa motor equipped with a Yaskawa Sigma II Serial Absolute Encoder. The encoder can have 16-bits, 17-bits or 20-bits of resolution per revolution plus a battery backed-up multiple turns counter. This encoder transmits its position as a serial bit stream via RS-485 lines instead of A-B incremental pulses.

Due to the additional capabilities needed to process the absolute encoder signal, these encoders are only supported on the "Enhanced" versions of the Guidance Controllers.

For information on configuring this type of encoder, please see the *Software Setup* section of the *Controller Software* section of the *Documentation Library*.

The following are the wiring instructions for the **Encoder Connectors**.

Encoder Connector Pin	Wire Color	Signal Name	Controller Connector Pin
1	RED	5V	4
2	BLACK	GND	7
3	ORANGE	BATTERY +	14
4	WHITE/ORANGE	BATTERY -	12
5	LIGHT BLUE	DATA+	5
6	WHITE/LIGHT BLUE	DATA -	6

The following are the wiring instructions for the **Motor Power Connectors**:

Motor Connector Pin	Wire Color	Signal Name	Controller Connector Pin
1	RED	U	6
2	WHITE	V	2
3	BLUE	W	3
4	GREEN/YELLOW	FG	5
1	RED	BRAKE+	1
2	BLACK	BRAKE-	4

For the multi-turn counter to operate properly, a battery must be connected to the [Absolute Encoder Battery Connector](#) on the MCIM board. Please see the information on that connector for detailed pin outs and plug types. The following table contains information on the required battery power.

NOTE: Unlike other absolute encoders, the Sigma II does not have an internal battery or capacitor that can retain the multi-turn data. Therefore, if the external battery is disconnected while the controller's power is off or the cable from the controller to the encoder is disconnected at anytime, the multi-turn data will be lost and the absolute position of the motor and encoder will have to be re-established.

External Battery Specification	
Typical voltage	3.6V
Alarm trigger voltage	2.7V
Current for each encoder	20 uA

Appendix A: Product Specifications

Guidance 3000 and 2000 Controller Specifications

General Specification	Range & Features
Software	
Programming Interface	Three programming methods available: DIO MotionBlocks (PLC) Embedded Guidance Programming Language (GPL) PC/Unix controlled over Ethernet
Operator Interface	Web based operator interface supports local or remote control via browser connected to embedded web server
Motion Control	Extensive robotic and low-level motion control available Continuous path following, s-curve profiling Straight-line and circular motions Torque and velocity control Control of up to 32 axes via networked distributed control Distributed control network can consist of up to 16 controllers Optional conveyor belt tracking Optional kinematic models for various robot geometries
Optional: Machine Vision	Provides controller with a complete set of image-processing, measurement, inspection and finder tools. A powerful patented Object Locator finds parts in any orientation and at different scales within milliseconds.
Motion Control	
Motor Drives	Up to four integrated motor drives (current per channel) 10A standard: 10A peak/5.5A RMS/3.5A stall 20A option: 20A peak/9.5A RMS/6.5A stall 30A option (available as G3430 only): 30A peak/15A RMS/10A stall Bus voltage & total power for all drives: Guidance 3000: 24VDC to 320VDC, 3KW total Guidance 2000: 24VDC to 90VDC, 2KW total
3rd Party Amplifiers	Four or six +/- 10VDC 16-bit DAC channels optionally available for controlling external amplifiers
Position Sensors Interface	Four differential digital encoder interfaces Four configurable single-ended digital encoder interfaces Support for selected absolute encoders (requires "Enhanced" controller) Support for analog incremental encoders with interpolation for increased resolution (requires "Enhanced" controller)
Control Signals	Configurable limit stop, home, hall-effect, and brake signals

Appendix A: Product Specifications

Communications Interfaces	
General Communications	One or four 10/100 Mbps Ethernet ports RS-232 port with hardware flow control Remote front panel interface with second RS-232 port (no hardware flow control), compliant with IEC Category 3 safety standards
Digital Input Channels	12 general purpose optically isolated inputs, configurable in groups of four as sinking or sourcing 5VDC to 24VDC for logic high if sinking 24VDC supplied for logic high if sourcing Additional remote I/O available via Precise RIO modules or 3rd party MODBUS/TCP devices.
Digital Output Channels	8 optically isolated outputs, individually configurable as sinking or sourcing, 24VDC maximum pull up if sinking 24VDC supplied if sourcing 100mA maximum per channel Additional remote I/O available via Precise RIO modules or 3rd party MODBUS/TCP devices.
Analog I/O Channels	2 analog +/- 10VDC 12-bit inputs standard 4 or 6 analog outputs optionally available
Size	Guidance 3000: 80mm (W) x 200mm (L) x 84mm (H) Guidance 3430: 98.8mm (W) x 250mm (L) x 84mm (H) Guidance 2000: 138mm (W) x 225mm (L) x 61mm (H) Guidance 0006/0004: 80mm (W) x 200mm (L) x 60mm(H)
Required Low Voltage Logic Power	24VDC \pm 5%, power required for logic and I/O 2.7A minimum 4A recommended for typical use of digital I/O 1A additional required for 2KW PrecisePower Intelligent Motor Power Supply contactors

Guidance Controller Environmental Specifications

The Guidance Controllers must be installed in a clean, non-condensing environment with the following specifications:

General Specification	Range & Features
Ambient temperature	5°C to 40°C
Storage and shipment temperature	-25°C to +55°C
Humidity range	5 to 90%, non-condensing
Altitude	Up to 3000m
Free space around controller	6mm sides and top
Chassis protection class	IP20 (NEMA Type 1)
For EU or EEA countries	IP54, must meet EN 60204 (IEC 204)

PrecisePower 500 Intelligent Motor Power Supply Specifications

General Specification	Range & Features
Input Specifications	
Input voltage	Dual range: 90 to 132 VAC and 180 to 264 VAC, auto selecting
Input frequency	50 - 60 Hz
Input inrush current	3.4 A at 120 VAC in and 6.8 A at 240 VAC in
Output Specifications	
Output voltage	320 VDC nominal for dual input range with typical setting. 160 VDC nominal when input is 90 to 132 VAC and "180-264V" jumper selected.
Output power	500 watts RMS
Dimensions	165 mm x 76 mm x 58 mm
Precise Part Number	PS10-EA-00500

PrecisePower 2000 Intelligent Motor Power Supply Specifications

General Specification	Range & Features
Input Specifications	
Input voltage	90-240VAC Single phase or three phase
Input frequency	50 - 60 Hz
Input inrush current	6.7A at 240VAC input
Input current	12.4A RMS, 30A peak at 240VAC single phase & 2000 DC watts output
Output Specifications	
Output voltage, no load	DC = 1.41 X VAC RMS input
Output power	1000 Watts free air @ 240VAC single phase input 2000 Watts forced air @ 240VAC single phase input 2100 Watts forced air @ 208VAC 3 phase input 3400 Watts forced air @ 240VAC 3 phase input
% Regulation	5 to 7%
Maximum energy dump average power	100 Watts
Peak energy dump voltage	438 VDC
Dump release voltage	401 VDC
Cat-3	Yes, when used with Precise Automation software and I2C communication
Fault detection	Output short circuit, output overload, missing third AC phase
Dimensions	270 mm x 105 mm x 76 mm

Appendix A: Product Specifications

Precise Part Number	PS10-EA-02000
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Appendix B: FAQ

Frequently Asked Questions

This section contains a compilation of frequently asked questions related to the family of Guidance Controllers.

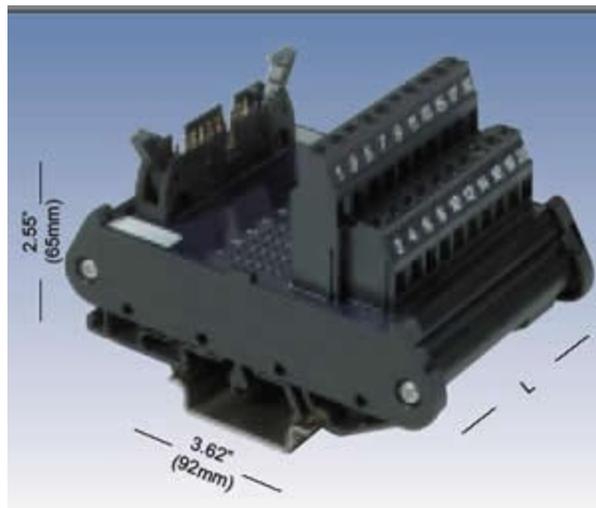
1. [Is there an alternative to purchasing crimping tools for connectors?](#)
2. [How do you connect a robot power enable button?](#)
3. [How do you release the motor brakes in a 1 or 2 axis system?](#)
4. [Why should grippers be wired to release when digital signals are ON?](#)

Is there an alternative to purchasing crimping tools for connectors?

If you do not wish to purchase and use the crimping tools required for the various Guidance Controller pin connectors, but you would still like a convenient means for breaking out the signals, you can purchase a module that converts a ribbon cable to a terminal block.

The unit displayed below is from Automation Systems Interconnect, Inc. (www.asi-ez.com) and is a "Standard Ribbon Cable DIN Rail Interface Module", Type IMRC. This accepts a terminated ribbon cable that connects to the Guidance Controller via an IDC connector.

For more information on this module, please see https://www.asi-ez.com/products_and_solutions/interface_modules/



Similar terminal blocks are also available from Phoenix Contact and are designed for ribbon cables that contain from 10 to 64 pins (<http://www.phoenixcon.com/products/interface/varioface/indexmain.asp>).

How do you connect a robot power enable button?

If you wish to connect a momentary contact button to enable robot power, you can wire the button to either a general digital input signal or use the dedicated input signal provided in the Remote Front Panel Connector.

If you connect the button to a general DIN, the number of the DIN signal should be set as the "Power enable DIN" (DataID 242) parameter database value. If you connect the button to the Remote Front Panel Connector "High Power On" input, the value of the dedicated input signal (DIN 18007) should be set as the value of DataID 242.

In either case, power will be enabled when the signal toggles from the OFF to the ON state.

How do you release the motor brakes in a 1 or 2 axis system?

For the integrated motor amplifiers of the Guidance Controllers, the brake signals that are presented in the four motor connectors are all tied together internally and are operated by the software that controls the 3rd axis/motor. This works correctly for 3 or 4 axis systems where the 3rd axis is the one that is affected by gravity.

If your system only has one or two axes, to configure the first or second axis to control the brake signals, set the "Auxiliary brake release DOUT channel" (DataID 10625) Parameter Database value for the appropriate axis to "8331". "8331" is the DOUT channel number for the dedicated DIO that controls the brake signal.

Why should grippers be wired to release when digital signals are ON?

Grippers or other tooling should always be wired to digital output signals such that an active (ON) state will release a part. This is an important practice since if the controller loses power and is restarted, all output signals are turned OFF by default. If a gripper is wired to release a part with an OFF signal, any parts left in a gripper from a previous operation would be dropped when the controller is restarted.