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1. Product Overview

Thank you for choosing SDW series digital step servo drive.

Stepper servo is a stepper motor scheme formed based on the common open loop stepper motor in combination with position feedback and servo algorithm, which features high speed, high torque, high precision, low vibration, low heating and no loss of step.

Based on the new 32-bit DSP platform, and adopting the field oriented control (FOC) and field-weakening control algorithm design, SDW series stepper servo driver surpasses the performance of common steppers comprehensively.

- The built-in PID parameter adjustment function makes the motor better meet the application of different kinds of loads.
- The built-in field-weakening control algorithm makes the motor to reduce the magnetic field characteristics and keep the power at high speed.
- The built-in current vector control function makes the motor have the current characteristic of servo and low heating.
- The built-in micro-stepping command algorithm makes the motor can run while maintaining a stable and low vibration at various speeds.
- The encoder feedback with the built-in 4000 pulse resolution makes the positioning precision increase and never loses the step.

In conclusion, combined with the servo control scheme with stepper motor characteristics, SDW series stepper servo driver can enable the stepper motor to perform a better performance and replace servo applications of the same power so it's the most cost-effective option for automatic equipment.

SDW86 drive can set up micro-stepping and other parameters with DIP switch and testing software. It has protection functions of voltage, current and position, and adds alarm output interface. Its input and output signals are all optoelectronic isolation.

Power supply	20 - 80 VAC / 24 – 100VDC
Control precision	4000 Pulse/r
Pulse mode	Direction & pulse, CW/CCW double pulse
Current control	Servo vector control algorithm
Micro-stepping settings	DIP switch settings, or testing software settings
Speed range	Conventional 1200 ~ 1500rpm, up to 4000rpm
Resonance suppression	Automatically calculate the resonance point and inhibit the IF vibration
PID parameter adjustment	Test software to adjust motor PID characteristics
Pulse filtering	2MHz digital signal processing filter
Alarm output	Over current, over voltage and position error

We hope that our products with excellent performance can help you to complete the sports control program successfully.

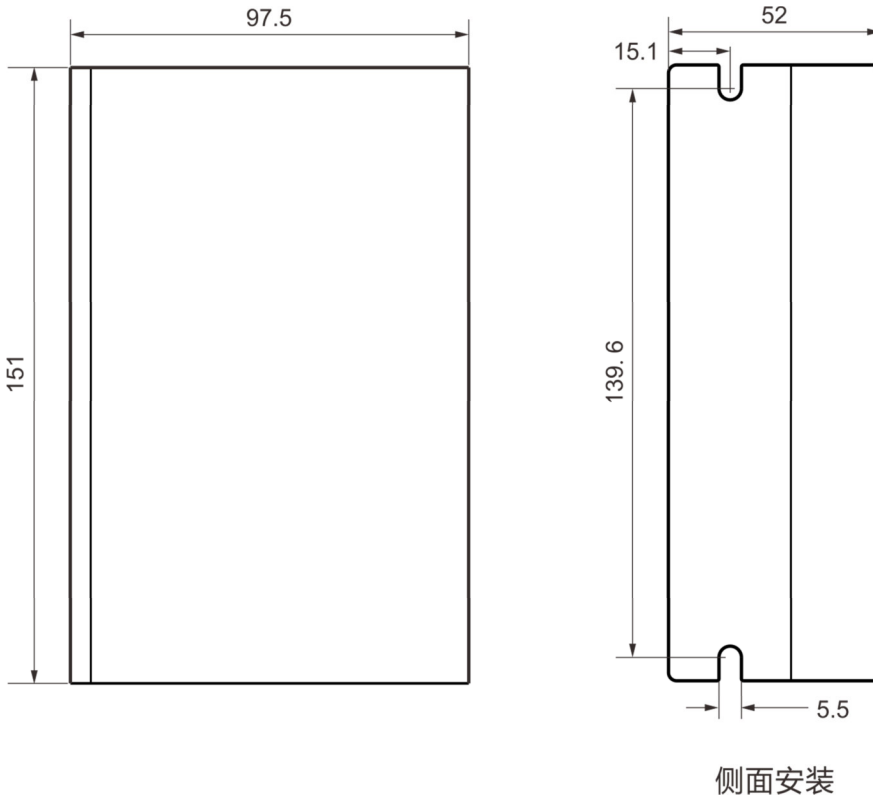
Please read this technical manual before using the products.

2. Application Environment and Installation

2.1 Environmental requirement

Item	SDW86
Installation environment	Avoid dust, oil and corrosive environment
Vibration	0.5G (4.9m/s ²) Max
Operating temperature/humidity	0°C ~ 45°C / 90% RH or less (no condensation)
Storage and transportation temperature:	-10°C ~ 70°C
Cooling	Natural cooling / away from the heat source
Waterproof grade	IP54

2.2 Drive installation dimensions



2.3 Drive installation requirements

Please install the drive vertically or horizontally, with its front facing forward, top facing upward to facilitate cooling.

During assembly, avoid drillings and other foreign matters falling inside the drive.

During assembly, please use M3 screw to fix.

When there is vibration source (such as a driller) close to the installation position, please use a vibrating absorber or a vibration resistant rubber gasket.

When multiple drives are installed in the control cabinet, please pay attention to reserve enough space for sufficient heat dissipation. If necessary, you can configure cooling fans to ensure good heat dissipation conditions in the control cabinet.

3. Drive Port and Connection

3.1 Port function description

Function	Grade	Definition	Remarks
Power supply input	AC	Input the AC power supply	AC 20~80V
	AC	Input the AC power supply	DC 24-100V
Motor connection	A+	Positive terminal of phase-A winding	Red
	A-	Negative terminal of phase-A winding	Blue
	B+	Positive terminal of phase-b winding	Green
	B-	Negative terminal of phase-b winding	Black
Encoder connection	EB+	Positive terminal of Encoder phase B	Green
	EB-	Negative positive terminal of Encoder phase B	Yellow
	EA+	Positive terminal of Encoder phase A	Brown
	EA-	Negative positive terminal of Encoder phase A	White
	VCC	Encoder working power 5V positive	Red
	GND	Encoder working power 5V ground terminal	Blue
Pulse connection	PUL+	Pulse input interface	3.3 ~ 24V level compatible
	PUL-		
	DIR+	Direction input interface	
	DIR-		
Enable terminal	ENA+	Enable control interface	
	ENA-		
Alarm output	ALM+	Alarm output interface	Less than 24V, 40mA
	ALM-		
In position output	Pend+	In position output interface	
	Pend-		

3.2 Power supply input

The power supply of the drive is both AC and DC power, the input voltage range: AC 20V~ 80V; DC 24V~ 110V.

Do not mistakenly connect the citizen power into the two ports of AC directly !!!

Power selection reference:**Voltage:**

The stepper motor has the characteristic of torque decreasing as the motor speed increases, and the voltage of the input power supply will affect the declining amplitude of the motor torque at high speed. Increasing the voltage of the input power supply appropriately can increase the output torque of the motor at high speed.

Stepper servos have higher revolution speed and torque output than ordinary steppers. Therefore, if the better high-speed performance is wanted, the power supply voltage of the drive is required to increase.

Current:

The work of the drive is to convert the input power supply with high voltage and low current to the low voltage and high current at both terminals of the motor winding. In actual application, the appropriate power supply is selected according to the motor mode and the torque of the load.

The effects of regeneration voltage:

When the stepper motor is working, it also keeps the characteristics of the generator. At deceleration, the kinetic energy accumulated by the load is converted into electric energy, which will be superimposed on the drive circuit and the input power. In application, attention should be paid to the setting of acceleration and deceleration time to prevent the protection of the drive or power supply.

When the drive is powered off, similarly, the drive LED indicator will be on if the load is increased to allow the motor to move

3.3 Encoder connection

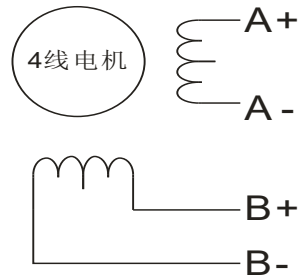
The SDW86 encoder is A/B differential output and is connected in the corresponding order when used.

EB+	EB-	EA+	EA-	VCC	GND
Green	Yellow	Brown	White	Red	Blue

Ruitech also provides a certain length of special cables for encoders. Please purchase the extension cables of different lengths according to the installation needs.

3.4 Motor connection

The matching motor of the SDW86 drive is the corresponding SDW series stepper servo motor, and its corresponding motor connection order is fixed and unique.



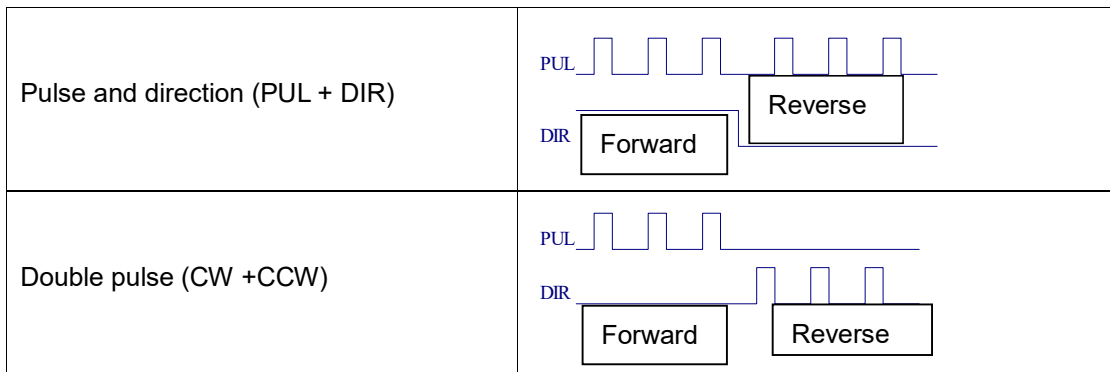
A+	Red
A-	Blue
B+	Green
B-	Black

3.5 Control signal connection

3.5.1 PUL, DIR Port: connection for pulse command

The signal interface of standard SDW series drive is pulse-shaped, and the SDW86 can receive two types of pulse command signals.

The upper controller can be the pulse signal generating device, such as PLC, MCU, control card and controller.



3.5.2 ENA port: enable/disable

When the default optocoupler is off, the drive outputs the current to the motor. When the internal optocoupler is on, the drive will cut off the current of each phase of the motor so that the motor is in a free state, and the stepper pulse can not be responded.

When the motor is in the wrong state, the port enables automatic disconnection. The level logic of the enable signal can be set to the opposite.

3.5.3 ALM and Pend port: alarm and In Position output

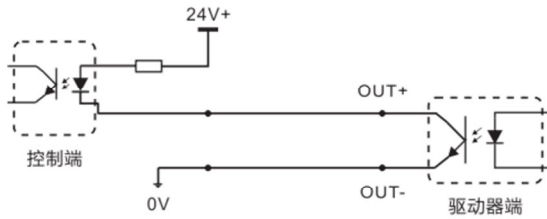
The ALM port is used to output the drive operating status to the external control circuit. ALM outputs opposite optocoupler levels respectively when the drive is in wrong state.

Pend port is used to output the in position signal of the driver. When the difference between the position of pulse command which output from the upper controller and the current position of stepper servo motor

is less than the setting data, the in position signal will be outputted. Then the upper controller receive this signal to confirm the completion of the in position.

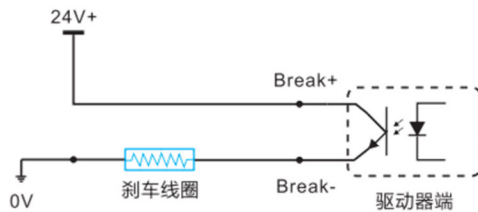
Besides, ALM and Pend port can control the switch of the stepper servo motor which contain the breaker by the break signal which formed by the software adjustment. The break coil is inductive load, and the coil will be high heating when the motor running, so that customer can choose the appropriate brake breaker in order to lower the heating and improve the lifetime and reliability.

Signal wiring example:



OUT为ALM或Pend，注意串接限流电阻

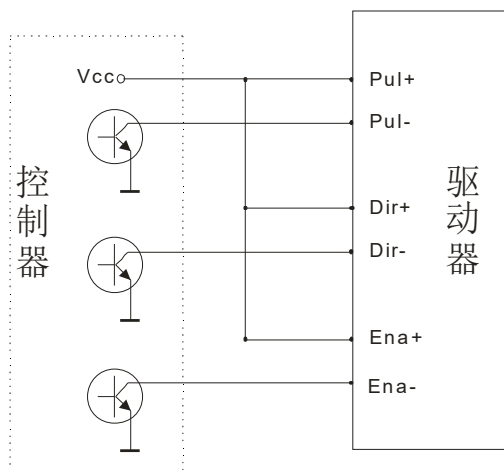
We will offer the solution of appropriate brake breaker.



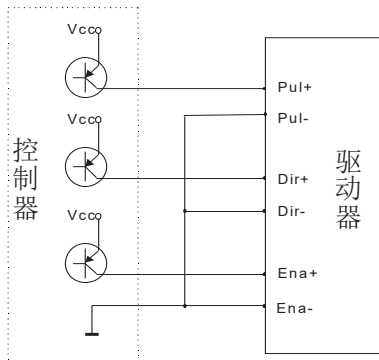
Break为刹车控制信号，由软件设置功能。
刹车线圈切勿接反(红+、黑-)

3.5.4 Control signal wiring example

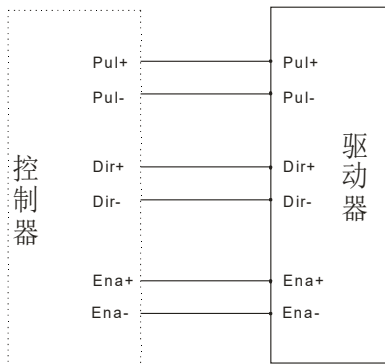
Common anode



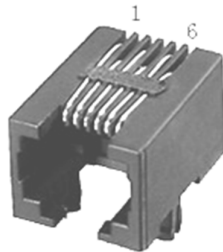
Common cathode



Difference



3.6 RS232 serial port

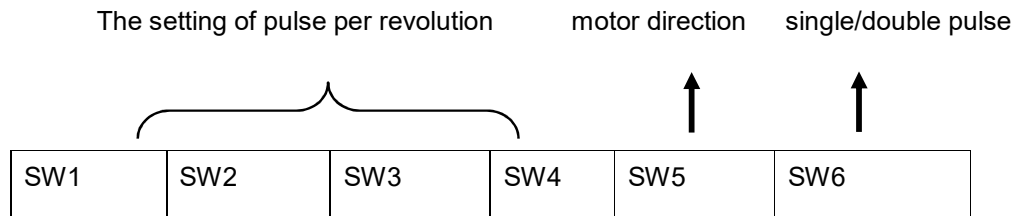


S/N	Symbol	Description
1	NC	
2	+5V	Positive terminal of power supply
3	TxD	RS232 transmitting terminal
4	GND	Ground terminal of power supply
5	RxD	RS232 receiving terminal
6	NC	

RS232 serial port is used to connect SDW86 testing software and change other related operating parameters of drive.

Do not pull/insert 232 serial port when the power supply is connected! ! !

4. The setting of DIP switches and operating parameters



4.1 The setting of pulse per revolution

Stepping count/revolution	SW1	SW2	SW3	SW4	Remarks
3600	on	on	on	on	The DIP switch is turned to the Default state and the testing software can freely change other micro-stepping level number
800	off	on	on	on	
1600	on	off	on	on	
3200	off	off	on	on	
6400	on	on	off	on	
12800	off	on	off	on	
25600	on	off	off	on	
51200	off	off	off	on	
1000	on	on	on	off	
2000	off	on	on	off	
4000	on	off	on	off	
5000	off	off	on	off	
8000	on	on	off	off	
10000	off	on	off	off	
20000	on	off	off	off	
40000	off	off	off	off	

DIP SW1, SW2, SW3, SW4 are used to set the number of pulse needed for per motor revolution

Motor speed = command pulse frequency ÷ pulse per revolution

Motor stroke = number of command pulses ÷ pulse per revolution

4.2 Motor direction selection

DIP SW5 is used to set the running direction of the motor under the initial pulse.

The “off” means that the motor direction is counterclockwise when inputting the initial pulse;

The “on” means that the motor direction is clockwise when inputting the initial pulse.

※ The initial pulse is the testing pulse used when developing the drive software; Please refer to the actual running direction of the motor.

4.3 Pulse filtering function selection

DIP SW6 is used to set the pulse filtering function of driver.

The “off” means the pulse filtering function is off;

The “on” means the pulse filtering function is on.

※ The pulse filtering function is the filtering action by the drive upon the input commands. When the filtering function is on, the drive will smoothen the input pulse command to make the acceleration and deceleration of motor softer, but this will also cause certain delay of the pulse command.

Filtering time setting: The default time of filtering function is 6.4ms, and the software can change the time below the 25.6ms.

4.4 Pulse mode selection

DIP SW7 is used to set the pulse command mode of drives.

The “off” means pulse + direction (single pulse) mode; the “on” means double pulse mode.

※ When you need to set the drive pulse mode to A/B orthogonal pulse mode, set the pulse mode check function to A/B orthogonal pulse mode in the testing software and turn on SW7.

4.5 Open/closed loop selection

DIP SW8 is used to set the drive control mode.







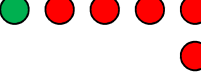
The “off” means the closed loop control mode;

The “on” means the open loop control mode.

※

※ **The above parameters are set for the DIP switches; For other parameters, please refer to Appendix A: Application Instructions for Testing Software**

5. Drive working status LED indication

LED status		Drive status
	Green indicator is on for long time	Drive not enabled
	Green indicator is flickering	Drive working normally
	One green indicator and one red indicator	Drive overcurrent
	One green indicator and two red indicators	Drive input power overvoltage
	One green indicator and three red indicators	The internal voltage of the drive is wrong
	One green and four red indicators	Tracking error exceeds limits
	One green and five red indicators	Encoder phase error

6. Common Faults and Troubleshooting

Phenomenon	Possible situations	Solutions
Motor does not work	Power indicator is off	Check the power supply circuit for normal power supply
	The motor rotor is locked but the motor does not work	Pulse signal is weak; increase the signal current to 7-16mA
	The speed is too slow	Select the right micro-stepping
	Drive is protected	Solve the alarm and re-power
	Enable signal problem	Pull up or disconnect the enable signal
	Command pulse is incorrect	Check whether the upper computer has pulse output
The steering of motor is wrong	The rotary direction of motor is reverse	Adjust the DIP SW5
	The motor cable is disconnected	Check the connection

	The motor has only one direction	Pulse mode error or DIR port damaged
Alarm indicator is on	The motor connection is wrong	Check the motor connection
	The motor connection and encoder connection are wrong	Check the sequence of encoder connection
	The voltage is too high or too low	Check the power supply
The position or speed is wrong	The signal is disturbed	Eliminate interference for reliable grounding
	The command input is incorrect	Check the upper computer instructions to ensure the output is correct
	The setting of Pulse per revolution is wrong	Check the DIP switch status and correctly connect the switches
	Encoder signal is abnormal	Replace the motor and contact the manufacturer
The drive terminal burned up	Short circuit between terminals	Check power polarity or external short circuit
	Internal resistance between terminals is too large	Check whether there is any solder ball due to excessive addition of solder on the wire connections
The motor is out of tolerance	Acceleration and deceleration time is too short	Reduce command acceleration or increase drive filtering parameters
	Motor torque is too low	Select the motor with high torque
	The load is too heavy	Check the load weight and quality and adjust the mechanical structure
	The current of power supply is too low	Replace the appropriate power supply

7.Optional Models of Function-Customization

In order to meet the application requirements of different occasions, SDW86 derives related models. Customers are required to confirm and distinguish before ordering:

Model	Function
SDW86 (standard)	Monopulse, 200K bandwidth, smooth filtering
SDW86-CCW	Double- pulse mode (DIP SW6 changes)
SDW86-QEP	Orthogonal pulse (can be used in encoder following applications,debugging software changes)
SDW86-FOC	Servo control mode two (control algorithm switching, debugging software changes)
SDW86-IO	IO switch mode (IO triggers fixed speed / positioning, derivation)
SDW86-PM	Drive programmable mode (customized control program, derivation)
SDW86-485	485 communication mode (485 communication application, derivation)

Appendix A. Application Instructions for Testing Software

For details, please see the SDW series adjustment software – HELP option

Appendix B. Guarantee Clause

B.1 Warranty period: 18 months

We provide quality assurance for one year from the date of delivery and free maintenance service for our products during the warranty period.

B.2 Exclude the following:

- Improper connection, such as the polarity of the power supply is reversed and insert/pull the motor connection when the power supply is connected.
- Beyond electrical and environmental requirements.
- Change the internal device without permission.

B.3 Maintenance process

For maintenance of products, please follow the procedures shown below:

- (1) Contact our customer service staff to get the rework permission.
- (2) The written document of the drive failure phenomenon is attached to the goods, as well as the contact information and mailing methods of the sender.