

## Installation instructions

**i** Refer to installation use and maintenance manual for more information.  
Available user manual at link <http://www.everelettronica.it/manhw.html>

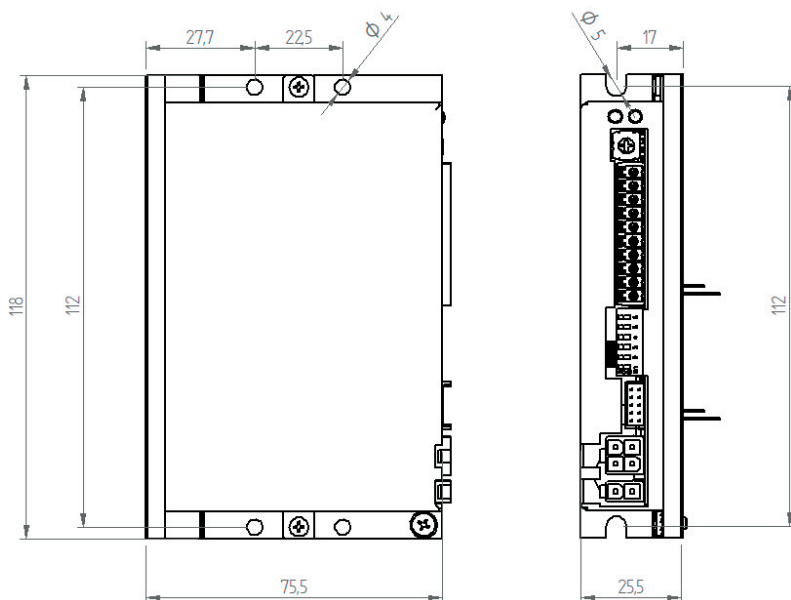


## 2 phase step motor bipolar chopper drive technical data

- DC power supply: 24 ~ 75 Vdc
- Phase current: up to 10 Apeak
- Chopper frequency: ultrasonic 40KHz
- Emulated Step angle: Full Step, 1/2, 1/4, 1/8, 1/16, 1/32, 1/64, 1/128, 1/5, 1/10, 1/20, 1/25, 1/30, 1/36, 1/50, 1/100 configurable by means of Dip-Switches and other step angle could be defined by software
- Protections against: over current, over/under voltage, overheating, short circuit between motor phase-to-phase and phase-to-ground
- Encoder input (not isolated): 5V Differential (RS422) incremental encoder
- Service SCL interface for programming and real time debugging
- Dimensions: 118 x 75.5 x 25.5 mm (without connectors)
- Protection degree: IP20
- Pollution degree: 2
- Working temperature 5°C ~ 40°C - Storage temperature -25°C ~ 55°C
- Humidity: 5% ~ 85% not condensing

**TITANIO**  
VECTOR · STEPPER · DRIVES

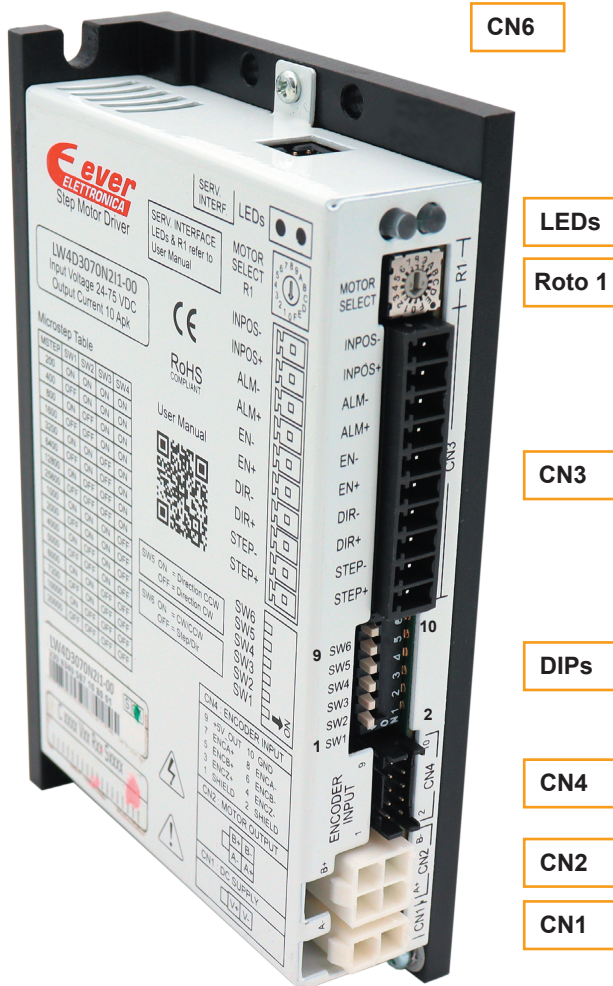
## Mechanical data



Dimensions in mm

# System connections

## Connectors:



# System connection

## CN1: Power supply

2 positions, pitch 4.2mm double row, PCB header connector

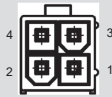
CN1.1	PGND	PWR_IN	Negative DC power supply input
CN1.2	VIN	PWR_IN	Positive DC power supply input



## CN2: Motor connection

4 positions, pitch 4.2mm double row, PCB header connector

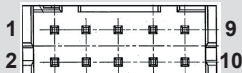
CN2.1	B/	PWR_OUT	Motor output phase B/
CN2.2	A	PWR_OUT	Motor output phase A
CN2.3	B	PWR_OUT	Motor output phase B
CN2.4	A/	PWR_OUT	Motor output phase A/



## CN4: Encoder input connection

10 positions, pitch 2mm double row, PCB header connector

CN4.1	SHIELD	/	Cable shield connection
CN4.2	SHIELD	/	Cable shield connection
CN4.3	ENCZ +	DIG_IN	Encoder Zero input positive
CN4.4	ENCZ -	DIG_IN	Encoder Zero input negative
CN4.5	ENCB +	DIG_IN	Encoder Phase B input positive
CN4.6	ENCB -	DIG_IN	Encoder Phase B input negative
CN4.7	ENCA +	DIG_IN	Encoder Phase A input positive
CN4.8	ENCA -	DIG_IN	Encoder Phase A input negative
CN4.9	+5 V	PWR_OUT	+5Vdc power supply output
CN4.10	GND	PWR_OUT	Negative side of power supply



Shield is internally connected to PE

## CN3: Digital I/O

10 positions, pitch 3.5mm single row, PCB header connector

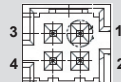
CN3.1	STEP +	DIG_IN	Clock frequency + input (Clock up+)
CN3.2	STEP -	DIG_IN	Clock frequency - input (Clock up -)
CN3.3	DIR +	DIG_IN	Motor direction + input (Clock down +)
CN3.4	DIR -	DIG_IN	Motor direction - input (Clock down -)
CN3.5	EN +	DIG_IN	Enable + input
CN3.6	EN -	DIG_IN	Enable - input
CN3.7	ALM +	DIG_OUT	ALARM output collector side
CN3.8	ALM -	DIG_OUT	ALARM output emitter side
CN3.9	INPOS +	DIG_OUT	INPOS output collector side
CN3.10	INPOS -	DIG_OUT	INPOS output emitter side



## CN6: Service SCI interface

4 positions, pitch 2mm double row, PCB header connector

CN6.1	TX/RX	Transmit / Receive Line
CN6.2	DE/RE	Drive Enable Negated / Receive Enable
CN6.3	+5V	+5V power out
CN6.4	GND	DNG power out

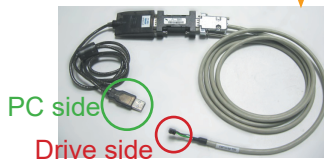
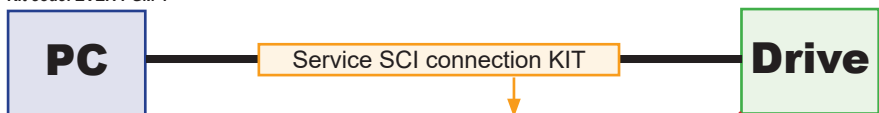


This connection is **only** possible with hardware and software provided by Ever.

# Service SCI connection



This connection is **only** possible with hardware and software provided by Ever.  
Kit code: EVER-PGM-1




**ATTENTION!!!**  
Correct insertion direction of the CN6: TAB UP.

## Dip-Switches Settings

Microstep value	DIPs			
	SW1	SW2	SW3	SW4
20000	OFF	OFF	OFF	OFF
10000	ON	OFF	OFF	OFF
7200	OFF	ON	OFF	OFF
6000	ON	ON	OFF	OFF
5000	OFF	OFF	ON	OFF
4000	ON	OFF	ON	OFF
2000	OFF	ON	ON	OFF
1000	ON	ON	ON	OFF
25600	OFF	OFF	OFF	ON
12800	ON	OFF	OFF	ON
6400	OFF	ON	OFF	ON
3200	ON	ON	OFF	ON
1600	OFF	OFF	ON	ON
800	ON	OFF	ON	ON
400	OFF	ON	ON	ON
200	ON	ON	ON	ON


SW5	Motor direction	SW6	Mode
OFF (default)	CW	OFF (default)	Step/Dir
ON	CCW	ON	CW/CCW

 **NOTE:** the device reads the Dip-Switches only during the power up. If it's necessary a setting change, shut down the system, change the settings and start up the system again to make the changes operating.

## Roto-Switch R1 Settings (Motor Select)

Functionality of the Roto-Switch R1 is defined by software. Connect to a PC on Service Interface connector.

R1 Position	Configuration
0 (default)	STP-MTRL-14026E
1	STP-MTRL-14034E
2	STP-MTR-17040E
3	STP-MTR-17048E
4	STP-MTR-17060E
5	STP-MTR-23055E
6	STP-MTR-23079E
7	STP-MTRH-23079E
8	STP-MTR-34066D
9	STP-MTRH-34066D
A	STP-MTRH-34097D
B	STP-MTRH-34127D
C	STP-MTRAC-42100D
D	STP-MTRAC-42151D
E	STP-MTRAC-42202D
F	All configurations set by software

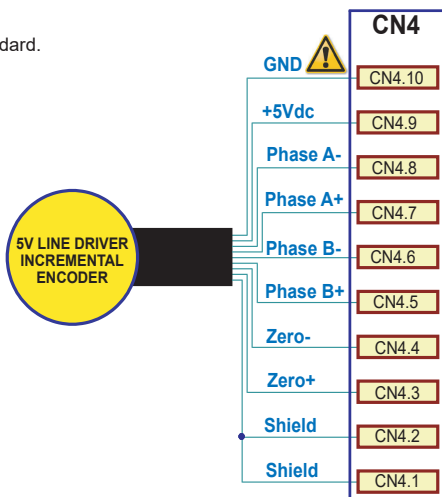
 **NOTE :** the device reads the Roto-Switch R1 only during the Power up. If it's necessary a setting change, shut down the system, change the settings and start up the system again to make the changes operating.

## Working Status (Led)

Visualization status			Description
1		<b>Green ON</b>	Correct functioning, drive enable
2		<b>Green Blinking</b>	Enable OFF, current zero
3		<b>Yellow ON Red OFF</b>	Missing setting of Inominal
4		<b>Yellow Blinking Red OFF</b>	Warning: connect with Service SCI kit and check with software
5		<b>Red ON Yellow OFF</b>	Protection: Motor is in open phase condition
6		<b>Yellow OFF Red Blinking</b>	Current protection
7		<b>Red ON (2 sec) Yellow 1 Blink</b>	Under/Over voltage protection
8		<b>Red ON (2 sec) Yellow 3 Blink</b>	Thermal protection
9		<b>Red ON (2 sec) Yellow 4 Blink</b>	Motor feedback error
10		<b>Red ON (2 sec) Yellow 6 Blink</b>	Motor current regulation is out of range
11		<b>Red ON (2 sec) Yellow 7 Blink</b>	eePLC user protection (generated by setting bit #0 of eePLC_user_settings)
12		<b>Red ON (2 sec) Yellow 8 Blink</b>	Error: connect with Service SCI and check with software

## Encoder input connection

Electrically NOT-isolated digital inputs.  
Differential 5Vdc that meet the RS422 standard.



Maximum supply current 100 mA.

**GND is internally in common with power ground, this is potentially dangerous. Take all necessary measures to avoid possible contacts in the final installation.**

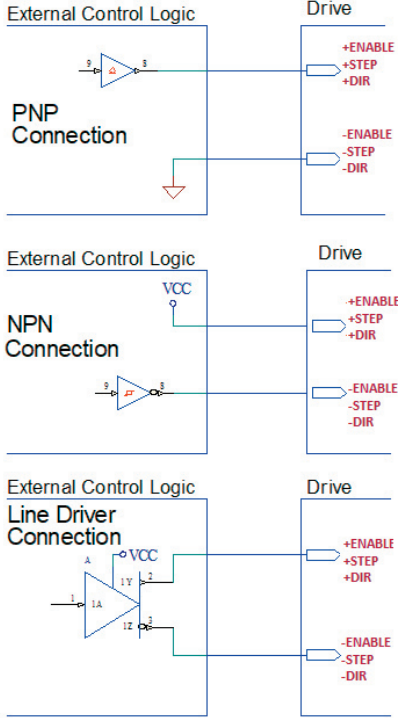
**Shield is internally connected to PE**

## Digital inputs connection



Differential PNP, NPN and Line Driver type

### 5 - 24Vdc INPUTS



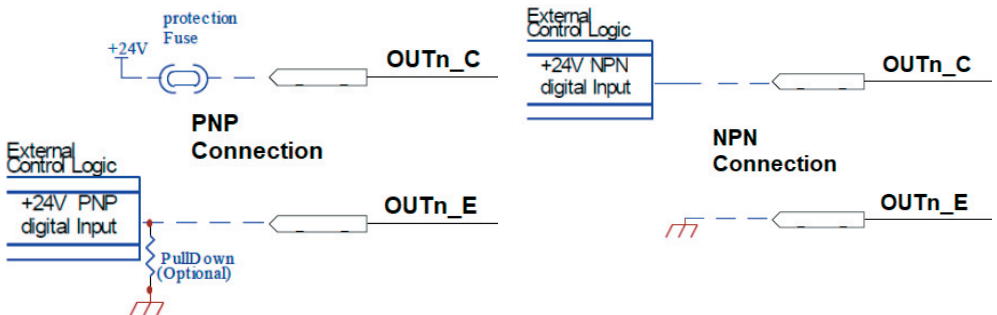
Standard (EN)			
Characteristics	MIN.	MAX.	Unit
Supply voltage	5	24	Vdc
Inputs frequency	--	2	kHz
Threshold switching voltage	--	2.5	Vdc
Current at 5 Vdc	--	6	mA
Current at 24 Vdc	--	15	mA

High speed (STEP & DIR)			
Characteristics	MIN.	MAX.	Unit
Supply voltage	24	24	Vdc
Inputs frequency	--	250	kHz
Threshold switching voltage	--	2.5	Vdc
Current at 5 Vdc	--	6	mA
Current at 24 Vdc	--	15	mA

## Digital outputs connection



Digital outputs are 5-24Vdc PNP/NPN, Iout=100mA, Fmax = 2 kHz



## Mating connectors

Connector	Description
CN1	Molex 39-01-2025
CN2	Molex 39-01-2045
CN3	Phoenix 1916371
CN4	Hirose DF11-10DS-2C

## Cables selection

Function	Cable	
	Minimum	Maximum
Power supply, Motor and PE	0.5 mm <sup>2</sup> (AWG20)	1.3 mm <sup>2</sup> (AWG16)
Encoder input	0.08 mm <sup>2</sup> (AWG28)	0.2 mm <sup>2</sup> (AWG24)
Digital Inputs and Outputs	0.08 mm <sup>2</sup> (AWG28)	0.5 mm <sup>2</sup> (AWG20)

## Verify the installation

- Check all connection: power supply, stepper motor and control logics.
- Make sure that all settings are correct for the application.
- Make sure that the characteristics of the DC power supply are appropriate for the drive.
- If possible, remove the load from the rotor of the motor to avoid wrong movements and eventual damages.
- Supply power and make sure that the green led is ON. If the led is OFF, shut down immediately and check if all connections are correct.
- Enable the current in the motor (without STEP Clock) and, if possible, verify the presence of the holding torque.
- Execute a movement of some steps and verify if the rotation direction is the desired one.



If the motion direction is not the desired one, it is possible to change it by leaving the DIR input unchanged and reversing the connection of a single phase of the motor to CN2, for example A with A/.

- Disconnect the power supply, fix the motor to the load and check the full functionality.

## Analysis of malfunctions



**When any of the following situations occur, the drive is placed in a fault condition.**

DEFECT	CAUSE	ACTION
Intervention of the thermal protection.	Can be caused by a heavy working cycle or a high current in the motor.	Improve the drive cooling by decent air flow or a fan. Consider to use a motor with a higher torque vs current rating.
Intervention of the current protection.	Short circuit on the motor powering stage(s) of the drive.	Check motor windings and cables to remove the short circuits replacing faulty cables or motor if necessary.
Intervention of the over/under voltage protection	Supply voltage out of range.	Check the value for the supply voltage.
Open phase motor protection.	Open circuit from motor windings and drive.	Check motor cables and connections to the drive.



**When any of the following situations occur, the drive doesn't work and isn't placed in an error condition.**

DEFECT	CAUSE	ACTION
Noisy motor movement with vibrations.	Can be caused due to a lack of power supply to a phase of the motor or a poor regulation of the winding currents.	Check the cables and connections of the motor and/or change the motor speed to exit a resonance region.
The external fuse on the power supply of the drive is burned.	Can be caused due to a wrong connection of the power supply.	Connect the power supply correctly and replace the fuse.
At high speed, the motor torque is not enough.	Can be due to a motor current self-limitation.	Increase the motor current (always within the limits), increase the supply voltage, change motor connection from series to parallel.

**EVER Motion Solutions**



Via del Commercio, 2/4 - 9/11

Loc. San Grato Z. I

26900 - L O D I - Italy

Phone +39 0371 412318 - Fax +39 0371 412367

email: [infoever@everelettronica.it](mailto:infoever@everelettronica.it)

web: [www.everelettronica.it](http://www.everelettronica.it)