MODEL ACS300-XXXX

User's Manual

Digital Velocity/Torque/Position Mode Servo Drive

This manual covers the use and maintenance of the model ACS300 series Torque, Velocity and Position mode brushless motor control product family.

ElectroCraft
Incorporated

Title: **ACS300 User Manual**
Installation and Operation

Type of Documentation: User Hardware Manual

Document Type code: ACS300UM Rev 1.0 09-22-09.doc

Internal File Reference: Document Number: A11014

Purpose of Documentation: This documentation describes…

- Installation and operation of the ACS300 family drive.

Record of Revisions:

RELEASE NUMBER	DATE	DESCRIPTION	COMMENTS
1.0	09/22/09	ElectroCraft changes	Initial Release

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1 ACS300 Controller

1.1 Overview

This manual describes the installation and operation of the ACS300 series of digital high voltage servo-amplifiers manufactured by ElectroCraft MI, Inc.

This document applies to serial numbers ending with xxxx0105 and beyond.

The ACS300 amplifier is:

- Configurable operation modes: Torque, Velocity, and Position.
- Selectable BLAC (sine wave, flux vector) or BLDC (Six step, trapezoidal) commutation.
- 4 Quadrant performance.
- Phase output, PWM controlled output.
- Full digital control of all loops
- Variable servo rate from up to 16 kHz.
- Loop tuning via serial interface (No potentiometers!).
- Drive setup & status information available serially via RS232 link.
- 12 – 48 VDC input power supply range.
- Output current of 15 Amp continuous, 30 Amp peak.
- Compact package size.
- **ElectroCraft CompletePower™ Plus** graphical windows interface for Setup, Configuration and Tuning.

Software

For further documentation support of software and its usage, refer to the **ElectroCraft CompletePower™ Plus** software user's manual.

Parameters and Variables

For further documentation support of parameters, variables, commands and graphing refer to the ElectroCraft Parameter Guide.

2 ACS300 Introduction

2.1 Amplifier

The ACS300 is a fully digital servo amplifier that uses DSP technology to provide a powerful feature set that is fully configurable by means of a RS232 serial port. The ACS300 servo drive is configurable as a Torque, Velocity, or Position mode servo amplifier. The ACS300 is designed to operate a single 3 phase Brushed or Brushless DC or AC, permanent magnet motor. The motor may have either a WYE or Delta wound stator. The ACS300 provides commutation using Hall sensors or encoder feedback.

The ACS300 Torque, Velocity or Position modes accept serial +/- 10 volt DC analog or digital PWM.

2.2 Theory of Operation

The ACS300 operates as a "mode configurable" digital servo amplifier. This product is typically applied as a component within an end use industrial application. Within industry, application requirements for servo amplifiers vary widely. For example, one application may require an amplifier with an analog input reference for speed. Another application may require an amplifier that offers torque control and Hall sensor commutation only. For this reason the ACS300 offers a choice of many different servo-operating modes. This flexibility is made possible because all of the control functions within the ACS300 are implemented in software. The ACS300 physical I/O and closed loop functionality are selected using the **ElectroCraft CompletePower™ Plus** software setup utility. See Section 7, Introduction to the **ElectroCraft CompletePower™ Plus** software, and the **ElectroCraft CompletePower™ Plus** software User Manual for additional information on using this software.

The internal firmware architecture of the ACS300 is modular. ACS300 software is built as a series of components (or modules) that are linked together to form an ACS300 servo-operating mode. ACS300 software components are stored in flash memory. These components exist as Reference input modules, Feedback modules, PI (D) control modules, commutation modules and firmware extension modules.

An internal digital signal processor is used to read I/O signals, motor feedback signals and to process serial communication messages. Flash memory inside the ACS300 is used to store a library of modular software components. RAM memory is used for data logging and graphical tuning of the ACS300. The serial EEPROM provides nonvolatile memory for retention of user-configured parameters and operating mode.

3 Product Safety Precautions

READ THIS ENTIRE SECTION BEFORE ATTEMPTING TO USE THE ACS300 SERVO DRIVE! GIVE SPECIAL ATTENTION TO ALL BOLD PRINT ITEMS.

WARNING!

To operate your control successfully, these minimum safety precautions MUST be followed to insure proper performance without injury to the operator and damage to motor or control. **FAILURE TO OBSERVE THESE SAFETY PRECAUTIONS COULD RESULT IN SERIOUS BODILY INJURY, INCLUDING DEATH IN EXTREME CASES.**

3.1 Operation

1. Do not touch any of the output connector pins from connectors P1 (DC Input) or P2 (Motor Output) when power has been applied. The voltages at these connector pins are dangerous and can produce an electric shock. Bare wires from adjacent connector pins must never be allowed to touch one another.

2. P2 pin 6 must be connected to an external earth ground. Follow wiring procedures carefully. Know and understand which connectors are NOT electrically isolated from the DC voltages within the drive.

3. Read ElectroCraft's Life Support Policy in section 3.5 for application limitations.

4. Follow precautionary guidelines in this manual with regard to proper installation of an external shunt resistor. See Section 13 of this manual.

5. Do not operate the control in an explosive area or near explosive or flammable materials.

6. Do not use the control in environments where it is likely to be exposed to strong and/or frequent static discharge.

7. Conduct trial operations on the servo drive alone with the motor shaft disconnected from the machine to avoid any unexpected accidents. Motor shaft should be uncoupled and free to rotate without coming in contact with user or any stationary object during set up and preliminary operation.

8. Under no circumstances should a phase output from the control be connected to anything other than a passive inductive/resistive motor load. Short circuit protection for the drive is limited to momentary conditions only! Repetitive short circuits on any of the output pins for P1 and 2 will likely cause permanent damage to the ACS300.

9. Never touch any moving parts while the motor is running. Failure to observe this warning may result in injury.

10. Excessive speed and current can destroy some motors and possibly injure the user. Check the motor manufacturer's specifications to ensure that the maximum current and voltage for your control model, does not exceed their limitations.

11. External methods are advisable to limit both the top speed and travel motion of the motor and its load. Whenever the ACS300 drive is disabled for any reason, the motor is placed into a free/spinning coast mode.

12. When using the servomotor for a vertical axis, install safety devices to prevent work pieces from moving due to occurrences of over travel. Failure to do this may cause injury to work pieces or person.

13. Provide an appropriate stopping device on the machine side to ensure safety. A holding brake for a servomotor with brake is not a stopping device for ensuring safely. Failure to observe this warning may result in injury.

14. Do not parallel multiple motors off the same control.

15. Do not make any extreme adjustments or settings changes of parameters. Failure to observe this caution may result in injury due to instable operation.

16. Do not turn the control on or off frequently unless necessary. Failure to observe this caution may cause internal parts to deteriorate.

17. Avoid plugging connector P1 or P2 into the control while live power is applied to the connecting cables. Ignoring this precaution will cause electrical arcing at the connector pins, which can cause permanent connector damage. ElectroCraft recommends using a disconnect switch ahead of P1 and P2 if the ACS300 must be disconnected often.

18. Do not remove the connectors on ports P1, P2, J1 through J6 from the control while the motor is operating.

19. Do not service or modify this product. Only authorized personnel must perform disassembly or repair of the drive. Failure to observe warning may result in injury or damage to product.

20. Always operate the ACS300 within the prescribed voltage limits. Any attempt to operate outside these bounds may result in damage to the ACS300 control.

3.1.1 Use of ACS300 Jumpers

ACS300 Jumpers JU201 and JU202 – DC Operating Voltage

1. The ACS300 has two jumpers that must be set according to the desired input DC operating voltage range. Failure to set these jumpers correctly can result in permanent damage to the ACS300. Please see section 6.4 “Use of ACS300 Jumpers JU201 and JU202” and select the proper jumper setting for your application before applying power to the ACS300.

ACS300 Jumpers JU1, JU2, JU3, JU4 – Use of Encoder Feedback

1. The ACS300 has jumpers that must be set according to the type of feedback device used. With a differential encoder feedback only A, A!, B, and B is used. User may leave Z and Z! unconnected.
   If using a single ended encoder feedback A and B, (and not the A! and B!) is used, all four jumpers on the daughter card, right next to the encoder connector J4, must be shorted. These are JU1, JU2, JU3 and JU4. You can then leave Z and Z! unconnected.
2. If only Hall Effect is used and no encoder at all, leave the encoder connector unconnected.
3. See section 6.6.4, J4 Encoder Interface Circuitry, for additional information.

3.2 Storage and Transportation

1. Do not store or install the product in the following place
    a. Locations subject to temperature outside of the range specified.
    b. Locations subject to humidity outside the range specified.
    c. Locations subject to condensation as the result of extreme changes in temperature.
    d. Locations subject to corrosive or flammable gases and liquids.
    e. Locations subject to dust, salts, or iron contaminants.
    f. Locations subject to exposure to water, oil, or chemicals.
    g. Locations subject to shock or vibration.

    Failure to observe this caution may result in fire, electric shock, damage to the product.

2. Do not hold the product by the cables or motor shaft while transporting it. Failure to observe this caution may result in injury or malfunction.
3. Store the ACS300 drive when not in use, in temperatures between -20 to +85 degrees C.

3.3 Installation

1. Take appropriate and sufficient countermeasures when installing systems in the following locations.
    a. Locations subject to static electricity or other forms of noise.
    b. Locations subject to strong electromagnetic fields and magnetic fields.
    c. Locations subject to possible exposure to radioactivity.
    d. Locations close to power supplies including power lines.
    e. Failure to observe this caution may result in damage to the product.

2. Keep any external shunt resistor away from flammable materials. Read Section 13 carefully for more shunt installation details.

3. Never use this product in an environment subject to liquids, corrosive chemicals or gases, or combustibles, or where foreign materials are allowed to fall onto or collect inside the drive Failure to observe this caution may result in electric shock or fire.

4. Do not place heavy objects on the product. Failure to observe this warning may result in stopping operation of the product.

5. Do not cover or prevent air from escaping or entering through the vents with obstruction or foreign object. Failure to observe this caution may cause internal elements to deteriorate resulting in malfunction or fire.

6. Provide the specified clearance between the drive and the control panel or with other devices. Provide sufficient space around the drive for cooling by natural convection or provide cooling fans to prevent excessive heat, see section 6.3 for details. Failure to observe this caution may result in fire or malfunction.

3.4 Wiring

1. Verify **ALL** wiring **BEFORE** applying power to the control and motor. Motor may spin or oscillate uncontrollably if improperly wired. Drive may be damaged or improper wiring may prevent drive from operation.

2. **The ground P2, pin 6, MUST always be connected** to an appropriate external earth ground.

3. Connect the ground terminal to the electrical codes (ground resistance should be less than 100 ohms. Improper grounding may result in electric shock or fire.

4. Do not connect a three-phases or any supply power to the U, V, and W terminals. Failure to observe this caution may result in injury or fire.

5. Securely connect the power supply terminals and motor output terminals. Failure to observe this caution may result in fire.

6. Do not bundle or run power and signal lines together in the same duct. Keep power and signal lines separated by at least 30cm.

7. Use twisted-pair shielded wires or multi-core twisted pair shielded wires for signal and encoder feedback lines.

8. Always use the specified power supply voltage. An incorrect voltage may result in burning. Be particularly careful where the power supply is unstable. An incorrect power supply may result in damage to the product.

9. Install external breakers or other safety devices against short-circuiting in external wiring. Failure to observe this caution may result in fire or damage to the control.

3.5 Life Support Policy

READ THIS ENTIRE SECTION BEFORE ATTEMPTING TO USE THE ACE SERVO DRIVE! GIVE SPECIAL ATTENTION TO ALL BOLD PRINT ITEMS.

ElectroCraft's products are not authorized for use as critical components in life support devices or systems without the express written approval from ElectroCraft MI, Incorporated.

1. Life support devices or systems, are devices or systems which are intended for surgical implant into the body, or support or sustain life, and whose failure to perform, when properly used in accordance with instructions for use provided in the User's Manual and in the labeling, can be reasonable expected to result in a significant injury to the user.

2. A critical component is any component of a life support device or system whose failure to perform can be reasonably expected to cause the failure of the life support device or system, or to affect its safety or effectiveness.

4 Checking Product on Delivery

When your package arrives, inspect the shipping box and the unit carefully, and save ALL packing materials. Compare the packing slip against all items included in the shipping box. Any shortages or other inspection problems should be reported to ElectroCraft immediately.

The following procedure is used to check products upon delivery. Check the following items when your ACS300 is delivered.

- Verify that the model number marked on the nameplate of the drive(s) is the correct model ordered.
- Check the overall appearance. Check for damage or scratches that may have occurred during shipping.

If any damage, or if the unit is the wrong type, contact your ElectroCraft sales representative immediately.

Your ACS300 has arrived carefully packaged from ElectroCraft MI, in an antistatic bag. As you unseal this bag, inspect the contents carefully. There should not be any loose or damaged parts inside.

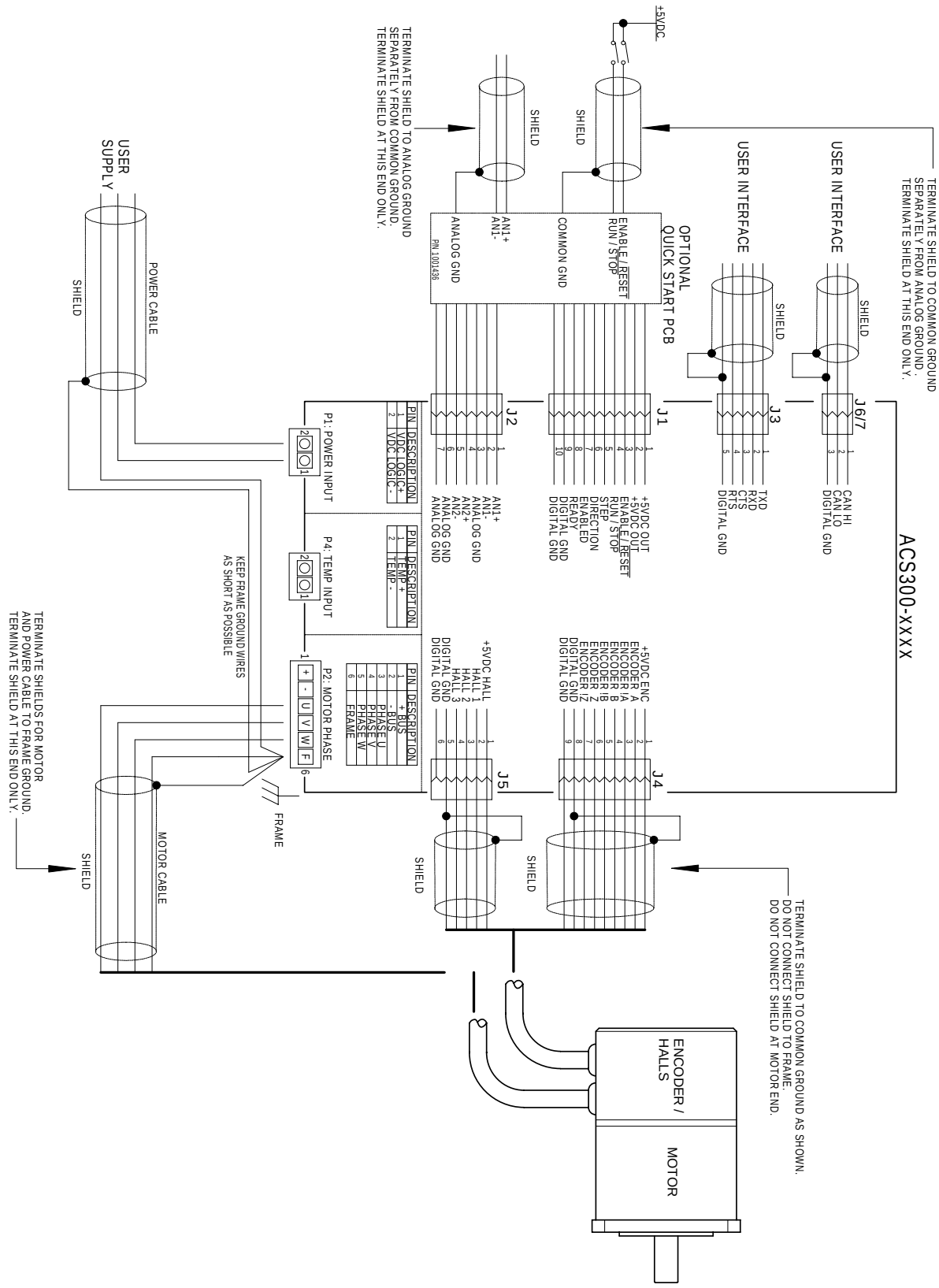
Never attempt to operate or power-up the drive if there is any visible external damage or if it sounds as though there are loose materials inside the chassis. While unpacking, if you discover any loose or damaged parts, notify ElectroCraft within two working days.

ElectroCraft recommends that all packing materials be saved in the event that the ACS300 needs to be shipped back. Always place the ACS300 in the same antistatic bag used in the original shipment. Abundant anti-static filler material should always be placed around the ACS300 so that it cannot shift inside the box. Extreme care should be exercised when placing packing material around all external connectors to prevent mechanical stress damage.

All material to be returned to ElectroCraft must have a Return Material Authorization (RMA) tracking number assigned before shipment. This may be obtained by contacting the ElectroCraft Service Dept. Any product returned without this number will be rejected by ElectroCraft.

Always insure your shipment for the proper replacement value of its contents. ElectroCraft will not assume responsibility for any returned goods that have been damaged outside of our factory because of improper packaging or handling. All goods shipped to ElectroCraft must be shipped FREIGHT PREPAID.

5 Recommended Cabling and Installation



6 ACS300 Installation and Setup

READ ENTIRE USER MANUAL FIRST BEFORE ATTEMPTING TO USE THIS PRODUCT.

If you require further assistance then provided within this manual, please email, call, or fax:

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www.electrocraft.com

This chapter presents installation procedures and instructions on how to setup your ACS300 drive.

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6.1 Mounting the ACS300

Use this preferred hardware type, see table below, for mounting your ACS300 drive. Mount your ACS300 in the following manner.

Base Mounted: Two M3/ No. 6 pan head screws. Include spring (locking) washer with plain washer.

Weight: Plate: 0.49lb (222g) or optional heatsink: 1.30lb (590g).
Size: 3.38" (85.73mm) x 5.25" (133.35mm) x 1.03" (26.29mm): Plate or 2.22" (56.44mm): Heatsink.

6.2 Environmental Conditions in the Control Panel

- Storage Temperature: -20-85 degree C
- Humidity: 5-95%RH, Non-condensing
- Operating Temperature range: 0-50 degree C
- Vibration: Install a vibration isolator beneath the drive to avoid subjecting it to vibration.

6.3 Installation in the Control Panel

Base Mount

When installing the ACS300, provide at least 10 mm (0.39 in) between units or control panel and at least 50 mm (1.97 in) above and below each drive. Install cooling fans above or below the drive to maintain a constant temperature inside the control panel and to prevent an excess temperature rise around the drive.

6.4 Use of the ACS300 Jumpers JU201 and JU202

❖ Jumpers JU201 and JU202 are located next to the power input connector P1; See Figure 2.

JU201:
Install JU201 when powering the ACS300 motor and logic inputs with the same supply.

Note: When JU201 is installed it is recommended that JU202 is **NOT** installed.

JU202:
Install JU202 when the voltage supplied to the logic power input (P1 pin 1) is between +12Vdc and +24Vdc. Remove JU202 when the voltage supplied to the logic power input is greater than +24Vdc.

The standard configuration is that JU202 is NOT installed (left open). When installed, JU202 bypasses some circuitry that protects the internal logic power supplies from voltages above +48V.

6.5 Simplified ACS300 Internal Block Diagram

This following diagram is provided to familiarize the user with the internal architecture of the ACS300. An internal digital signal processor (DSP) is used to read I/O signals, motor feedback signals and to process serial communication messages. ROM memory inside the ACS300 is used to store a library of modular software components. RAM memory is used for data logging and graphical tuning of the ACS300. The serial EEPROM provides nonvolatile memory for retention of user-configured parameters and operating mode. EEPROM memory is also used to extend the program functionality of the ACS300.

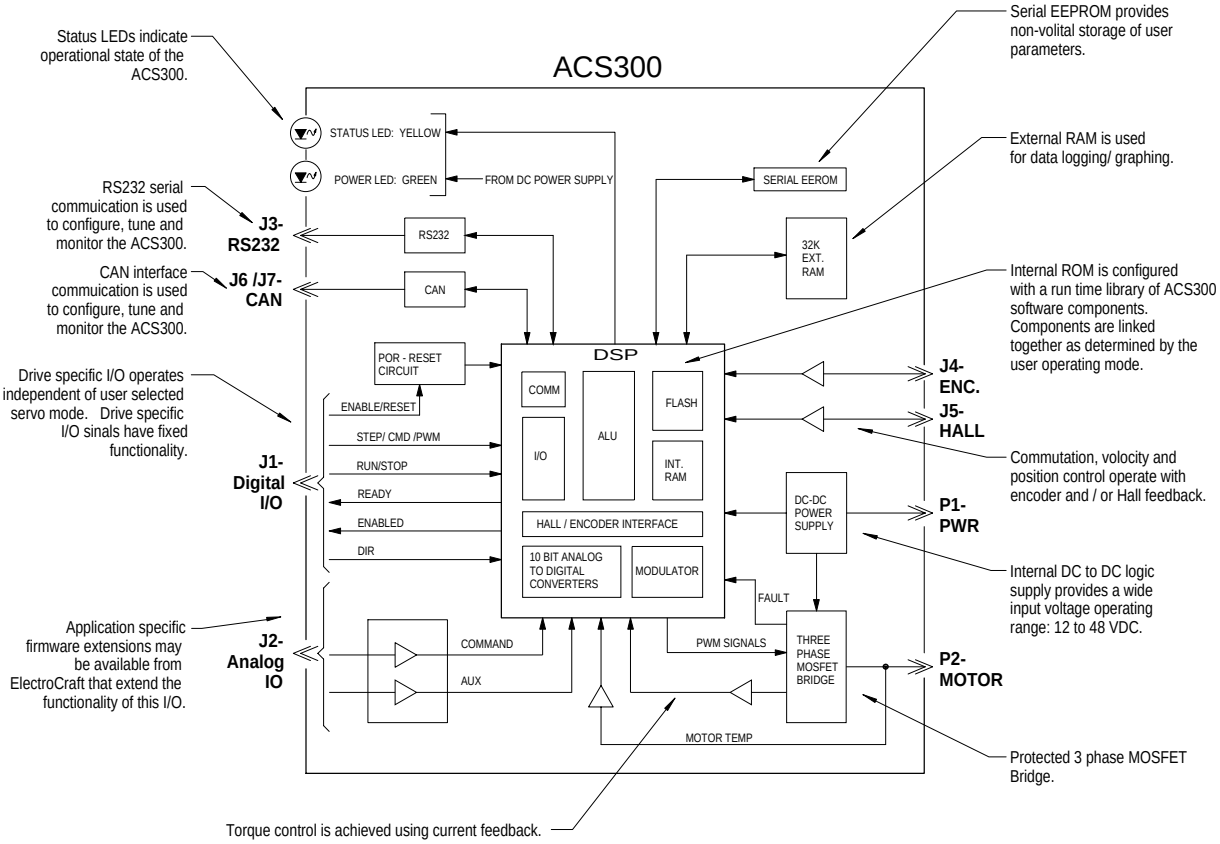

Figure 1: ACS300 Block Diagram

6.6 ACS300 Connector Description

Drive specific I/O operates independent of the user selected operating mode. Dive specific I/O signals have fixed functionality. These signals are used to interface the ACS300 to an outside control system. They provide signals for enabling, disabling, and monitoring the status of the ACS300.
For visual reference to the ACS300 connectors, see Figure 2 below.

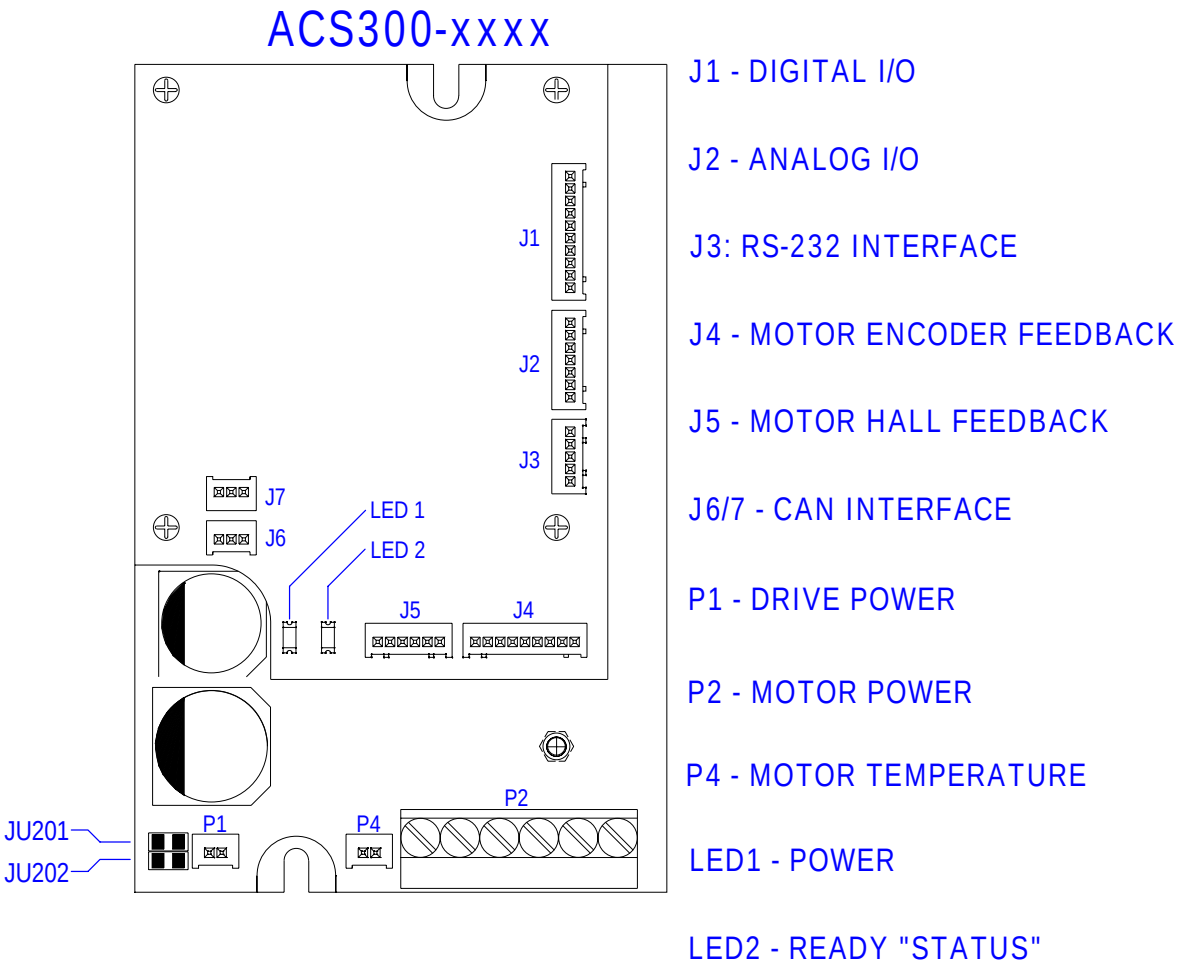

Figure 2: ACS300 Connector Layout

6.6.1 J1 Connector: User Digital I/O Control, Molex 35362-1010

Pin #	I/O	Description
1	Output	+5 Volts DC Power. Supplied regulated +5VDC power. 250mA Total available from drive from all pins.
2	Output	+5 Volts DC Power. Supplied regulated +5VDC power. 250mA Total available from drive from all pins.
3	Input	Enable/!Reset Control Signal Input; TTL compatible. +5.5 VDC maximum signal amplitude. 0 Volts minimum. 10K ohm internal pull down. Positive true logic. Forces a master hardware reset for entire drive on a falling edge. Drive recovers beginning after rising edge. Drive remains disabled while logic "0" is applied to this input.
4	Input	Run Command Signal Input; TTL compatible. 5.5 VDC maximum signal amplitude. 0 Volts minimum. 10K ohm internal pull down. Positive true logic. A logic "1" state will allow motor commutation once some level of current is commanded. A logic "0" state places motor into a coast state.
5	Input	Step Input; 0 to +5 VDC logic signal. TTL compatible. 10K ohm internal pull down. Used in step and direction mode. Used with direction input.
6	Input	Direction Input; Zero to +5 Volt logic signal. TTL compatible. +5.5 VDC maximum signal amplitude. 0 Volts minimum. 10K Ohm internal pull down. Selects relative direction of “Step” command. High is “positive” direction.
7	Output	Enabled Output; 0 to +5 VDC logic signal. Logic 0 when drive is in “Reset”. Logic 1 when drive is enabled and initialized.
8	Output	Ready Output; 0 to +5 VDC logic signal. Logic 0 when drive is in “Standby” or “Reset”. Logic 1 when drive is in “Run” mode and ready to deliver current.
9	Output	Common Return.
10	Output	Common Return.

6.6.2 J2 Connector: User Analog I/O Control, Molex 35362-0710

Pin #	I/O	Description
1	Input	AN1+ Differential Input; ±10 Volt external command signal input. The polarity of this signal controls the relative applied direction of output motor torque. Input is protected to ±24 Volt maximum.
2	Input	AN1- Differential Input; ±10 Volt external command signal input. The polarity of this signal controls the relative applied direction of output motor torque. Input is protected to ±24 Volt maximum.
3	Input	Common Return.
4	Input	AN2+ Differential Input; ±10 Volt external signal input. Range and scaling is software configurable. Input is protected to ±24 Volt maximum.
5	Input	AN2- Differential Input; ±10 Volt external signal input. Range and scaling is software configurable. Input is protected to ±24 Volt maximum.
6	Input	Common return.
7	Input	Common return.

6.6.3 J3 Connector: RS-232 Communications, Molex 35362-0510

Pin #	I/O	Description
1	TX	RS232 TXD Output, RS232 signal level.
2	RX	RS 232 RXD Input, RS232 signal level.
3	CTS	RS 232 CTS Input, This input not implemented as a 'Clear to Send" and is only used for programming flash.
4	RTS	RS232 RTS Output, This output is not currently implemented.
5	GND	Common return.

6.6.4 J4 Connector: Encoder Feedback, Molex 35362-0910

Pin #	I/O	Description
1	Output	+5 Volts DC Power. Supplied regulated +5VDC power. 250mA Total available from drive from all pins.
2	Input	Encoder "A" Signal; zero to +5 Volt logic signal.
3	Input	Encoder "A!" Signal; zero to +5 Volt logic signal.
4	Input	Encoder "B" Signal; zero to +5 Volt logic signal.
5	Input	Encoder "B!" Signal; zero to +5 Volt logic signal.
6	Input	Encoder "Z" Marker Signal; zero to +5 Volt logic signal.
7	Input	Encoder "Z!" Marker Signal; zero to +5 Volt logic signal.
8	-	Common return.
9	-	Common return.

6.6.5 J5 Connector: Hall Feedback, Molex 35362-0610

Pin #	I/O	Description
1	Output	+5 Volts DC Power; Supplied regulated +5VDC power. 250mA Total available from drive from all pins.
2	Input	Hall Signal Input S1; zero to +5 Volt logic signal. 2.2K ohm internal pull up to +5v.
3	Input	Hall Signal Input S2; zero to +5 Volt logic signal. 2.2K ohm internal pull up to +5v.
4	Input	Hall Signal Input S3; zero to +5 Volt logic signal. 2.2K ohm internal pull up to +5v.
5	-	Common return.
6	-	Common return.

6.6.6 J6 and J7 Connectors: CAN Communications, Molex 35362-0310

Pin #	I/O	Description
1	In/Out	CAN HI; CAN Bus Communication.
2	In/Out	CAN LO; CAN Bus Communication.
3	In/Out	Common Return.

6.6.7 P1 Connector: DC Logic Power Input, Molex 35362-0210

Pin #	I/O	Description
1	Input	DC Input; +12 to +48 VDC Logic power.
2	Input	DC Common Return.

6.6.8 P2 Connector: DC Input / Motor Output, Screw Terminal

Pin #	I/O	Description
1	Input	DC Input; 0 to +48 VDC Motor and Logic (Optional) Power.
2	Input	DC Common Return.
3	Output	Motor Phase U; peak voltage out of this terminal is dependent upon the incoming voltage on connector P1 pin 2. Peak amperage is model dependent.
4	Output	Motor Phase V; peak voltage out of this terminal is dependent upon the incoming voltage on connector P1 pin 2. Peak amperage is model dependent.
5	Output	Motor Phase W; peak voltage out of this terminal is dependent upon the incoming voltage on connector P1 pin 2. Peak amperage is model dependent.
6	Input	Frame Ground.

6.6.9 P4 Connector: Motor Temperature Input, Molex 35362-0210

Pin #	I/O	Description
1	Input	Temp +; 4.99K ohm internal pull up to +5v.
2	Input	Temp –; motor temperature input. PTC, NTC, or switch.

Note: Reference section 13.7.1 Motor Temp Circuit Description and Fig. 12 for more information

7. ACS300 Status LED's

In normal operation, the ACS300 is either in a "Ready" state or in an "Error" state. When power is first applied, the green LED will come on steady, meaning that power has been applied. The Yellow LED should be flashing, meaning that the drive is enabled. When the drive is placed into "run mode" the flashing Yellow LED will come on steady.

7.1. User Ready "Status" LED (Yellow)

FLASH CODE	DESCRIPTION	POSSIBLE CAUSE	RESULT	RECOVERY METHOD
ON Steady	ACS300 is in "RUN" mode.	User commanded RUN mode via user interface	Clear all faults and STATUS flags Enable three-phase PWM	Not applicable
OFF	Processor is inoperable.	Drive is in reset Processor fault Improper user supplied +5Volts Drive is being reprogrammed	ACS300 will stay in a DISABLED mode	Disconnect power from the ACS300 for 1 min. to reset the microprocessor. Then re-apply power to allow microprocessors to operate
1	Drive is in "Standby" mode	The user commanded standby mode from the user interface A drive error placed the drive in standby mode.	The drive is placed in standby mode	Command run mode Toggle the run line, see Note 1
2	Reserved	-	-	-
3	Over Current Fault	Current is over the designated drive current for more than 0.5mS	The drive is placed in standby mode	Toggle the run line, see Note 1
4	Rail or Power Supply fault	Internal logic power supplies out of spec (+15V and +5V) Rail voltage > +60V	The drive is placed in standby mode	Toggle the run line, see Note 1
5	Reserved	-	-	-
6	EEPROM Fault or Check sum fault	The user EEPROM has a checksum error or DSP program memory error	The drive is placed in standby mode (hard fault)	Check the error using the "CF' command in the terminal page. If the error is "MEMORY EEPROM", issue the command "CR23130". If the error is "MEMORY DSP FLASH", reprogram the DSP. ➢ Warning! Either operation will reset all drive parameters to default state. Reload parameter file after these operations
7	Miscellaneous Faults	To determine cause use the RS232 connection and "CF" command in terminal window, see Note 2	The drive is placed in standby mode	Toggle the run line, see Note 1
	Locked rotor fault	Delivered current is greater than user specified current for more than user specified time with no hall transitions.		

Note 1: To toggle the run command, set the Run/! Stop signal to a logic '0' state for 100mS, then back to logic '1'

Note 2: If a drive fault does occur and a flash code appears on the Status LED, more details regarding the cause of the fault can be obtained using the "CF" Check Faults command through the drive's RS232 communications.

7.2. User Power LED (Green)

LED	Description	Possible Cause	Result	Recovery Method
ON	+5 VDC Power Indicator	• On if user power is on	• Required to Run	• N/A
OFF	+5 VDC Power Indicator	• No logic power	• Drive will not Run	• Apply +12 – 48VDC
DIM	+5 VDC Power Indicator	• Logic voltage input to low	• Drive may not run properly	• Apply +12VDC minimum

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8. Introduction to ElectroCraft CompletePower™ Plus Software

ElectroCraft CompletePower™ Plus is a Windows®-based program used for setup, configuration, system diagnostics and motion control management. **ElectroCraft CompletePower™ Plus** will lead the user through a step-by-step Wizard to create the correct configuration and information required for the user to run a particular motor with a particular drive. The result will be an "Application" containing all of the configuration information required to run the motor with the drive.

This section is described within the software user manual: **ElectroCraft CompletePower™ Plus** software users manual. Please refer to the software user's manual for full documentation support to properly configure and operate your drive.

Windows® is a registered trademark of the Microsoft Corporation.

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9 Recommended Minimum Hookup

Apply DC voltage to the Quick Start I/O interface:

a. J1 pin 1/2: +5VDC.
b. J1 pin 9/10: Common return

For additional information pertaining to the optional Quick Start I/O Test Interface, refer to document: Quick Start User Guide.doc(x) located at the ElectroCraft web site.

9.1 Diagram

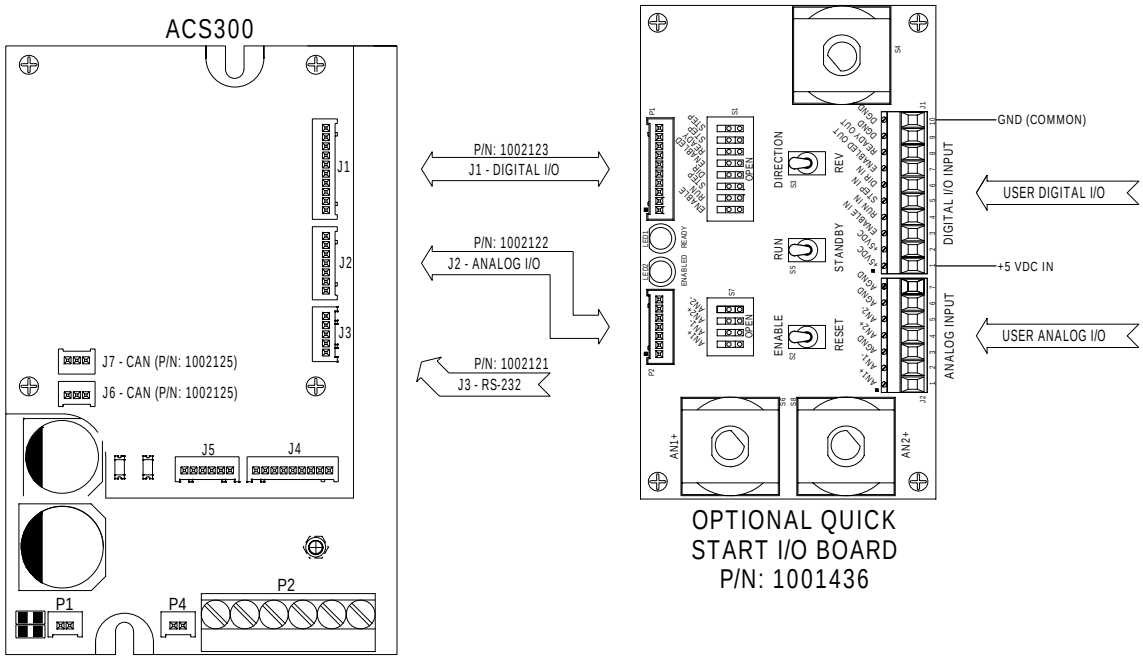

Figure 3: Optional Drive Setup

9.2 Wiring Diagrams for Optional User Interfaces

For mating connectors, see section 11. For additional accessories refer to appendix A

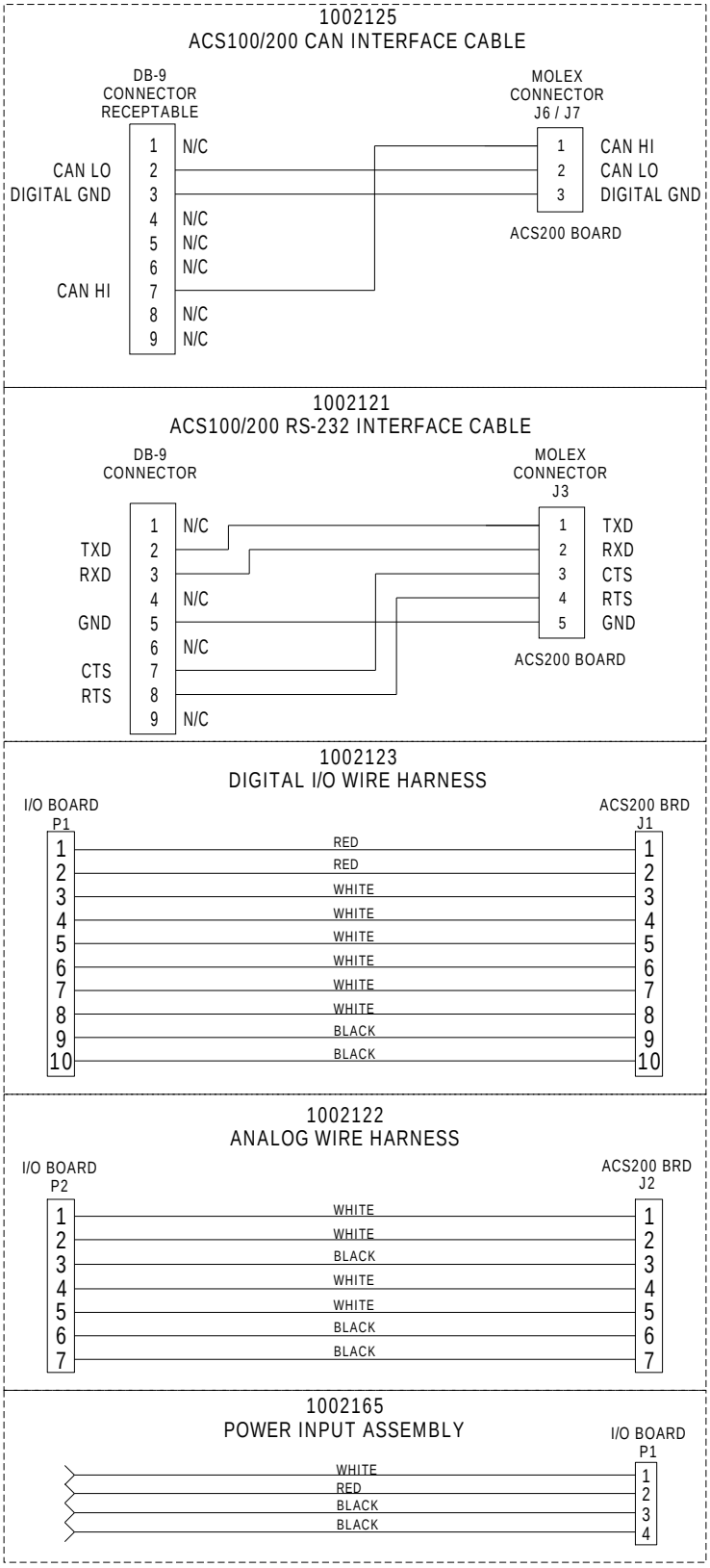

Figure 4: Optional Drive Setup Wiring Diagram

10 First Time Operation

10.1 Phasing the Motor

ElectroCraft has determined the correct motor phasing for all ElectroCraft motors. If your drive was ordered with an ElectroCraft motor specified, the correct parameter set for the mating ElectroCraft motor was loaded into your drive at the factory prior to shipment.

Alternate ElectroCraft motor parameters can be selected from the motor selection file on the software disk supplied with your drive, or you can contact ElectroCraft for these files.

In addition, ElectroCraft has established the correct motor phasing relationships for many other popular US and foreign motor manufacturers. A listing of these additional motor manufacturers may be obtained from ElectroCraft upon request.

10.2 Using ElectroCraft CompletePower™ Plus

To establish the correct motor phasing for a new or unknown motor ElectroCraft has provided a Windows based setup utility. Please refer to the **ElectroCraft CompletePower™ Plus** software user manual to setup your drive and analyze the performance of the drive as well as the motor.

Getting Started

To make use of this feature proceed as follows:

1. Install **ElectroCraft CompletePower™ Plus** software onto user PC.
2. Connect all motor phase and feedback wires to the drive.
3. Place drive into standby.
4. Connect power and establish communications.
5. Load a starting parameter set (Use default supplied in drive, user created or saved parameter set, or contact ElectroCraft for assistance).
6. The motor should now be properly phased for the ACS300. You can now proceed with drive loop tuning.

10.3 ACS300 Electrical Ratings

Ratings at Temperatures = 0…50°C, (unless otherwise noted)

Parameter	Conditions	Value	Units
Supply			
Supply voltage	Transient peak	-03 to 60	VDC
Supply voltage	Nominal operating	12 to 48	VDC
Supply current, surge	Inrush pulse duration <=100mS	30	A
Supply current, idle	No load condition.	40 to 340	mA
Supply current, operating		16 to 32	A
Over voltage protection	Internal peak supply limited.	58 to 62	VDC
Reversed polarity withstand	Continuous; supply current externally limited to:	-30	A
+5VDC Supply regulation	Encoder Inputs, Hall Inputs and Digital I/O	4.75 to 5.25	V
+5VDC Supply current available for external use	Encoder Inputs, Hall Inputs and Digital I/O	250	mA
P2-Motor Outputs			
Output current, continuous	No additional heatsink	15	Arms
Output current, peak		30	A
Short circuit withstand	Phase-to-phase, phase-to-ground, phase to-supply threshold.	+/- 16 to +/- 25	Amp
Short circuit protection delay		5 to 20	uS
On state voltage drop	Phase current = +/-5Amp	-500 to 350	mV
Off-state leakage current	Phase Voltage = +/-48V.	-500 to 500	uA
PWM frequency	Programmable, PWMPER	30	kHz
J1-Digital I/O Maximum Ratings			
Input voltage	All inputs; referenced to Common	-9 to 5	V
Input current	All inputs; referenced to Common	-20 to 20	mA
Output voltage	All outputs	-0.3 to 7	V
Output current	All outputs	48	mA
J1-Digital Inputs			
On state voltage threshold	Referenced to Common	3 to 5	V
Off state voltage threshold	Referenced to Common	0 to 0.5	V
On state current	Input = +5V	-8 to -12	mA
On state pulse width	Off voltage = 0V , On voltage = +3V	10	uS
Off state pulse width	On voltage = +5V , Off voltage = 0V	15	uS
J1-Digital Outputs			
On state current	Referenced to Common	10 to 15	mA
On state voltage drop	On state current = 15 mA	0.2 to 0.4	V
Off state voltage	Sustained	5 to 7	V
Off state leakage current	Off state = 5.5V	5 to 20	uA
J2-Analog Inputs			
Input voltage Common-mode	Referenced to AGND	-12 to 12	V
Input voltage differential	Nominal operating	-10 to 10	V
Input impedance	Differential	24	K Ohm
Input impedance	Common mode, referenced to AGND	12	K Ohm
Analog ground current	Maximum AGND to GND	-25 to 25	mA

ACS300 Electrical Ratings, continued

Ratings at Temperatures = 0…50°C, (unless otherwise noted)

Parameter	Conditions	Value	Units
J4-Encoder Inputs			
Input voltage, Max.	Common-mode, referenced to GND	-0.3 to 5.3	V
Input voltage, Max.	Differential peak A to A , B to B , Z to Z	-5 to 5	V
Input voltage, differential	RS422 receiver, A to A, B to B, Z to Z operating.	-5 to +5	V
J5-Halls			
Input voltage range	Transient peak	-0.3 to +5.3	V
Low level voltage	Operating	0 to 1.8	V
Low level input current	Internal 1 K pull up to +5V	4 to 5	mA
Input hysteresis		0.2 to 0.5	V
Other			
Thermal resistance	Base plate to ambient	1.24	°C/W
Frame isolation voltage withstand	GND to Frame.	250	V
Operating temperature	powered	0 to +50	°C
Storage temperature	Not powered	-20 to +85	°C
Humidity	Non-condensing	5 to 95	%RH
Weight	Cold Plate Model	0.49 /222	Lb./g

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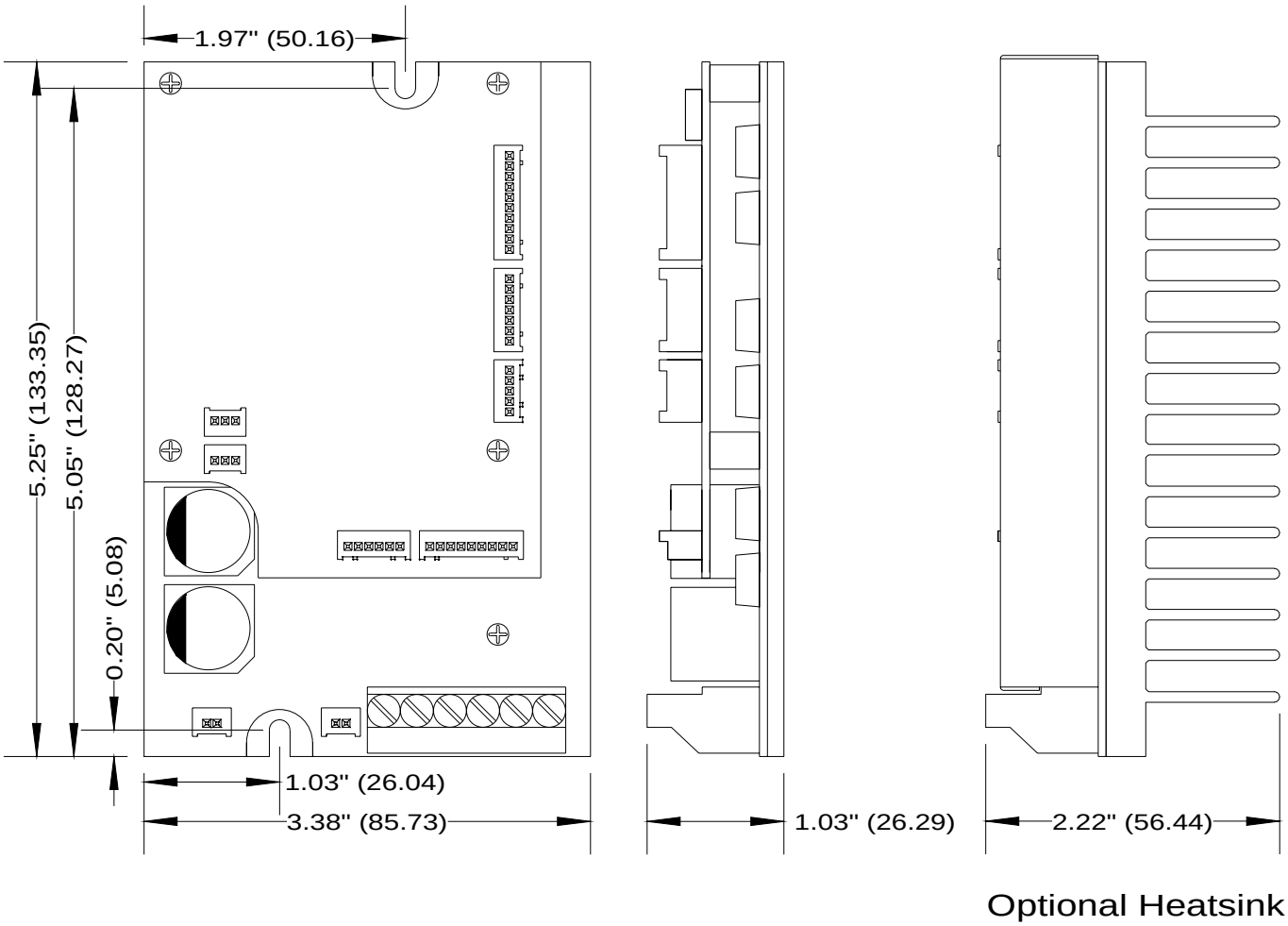
11. ACS300 Dimensional Drawing

Units: in (mm)



Note: For Optional heatsink and or cover please contact the Sales department.

Figure 5: ACS300 Package Outline

12. List of Mating Connectors

Ref.	Connector Name	Manufacturer	P/N	P/N Crimp Pin
J1	User Digital I/O Control	10 Pin Molex Sherlock	35507-1000	50212-8100
J2	User Analog I/O Control	7 Pin Molex Sherlock	35507-0700	50212-8100
J3	RS232 Communications	5 Pin Molex Sherlock	35507-0500	50212-8100
J4	Encoder Interface	9 Pin Molex Sherlock	35507-0900	50212-8100
J5	Hall Interface	6 Pin Molex Sherlock	35507-0600	50212-8100
J6 & J7	CAN Communications	3 Pin Molex Sherlock	35507-0300	50212-8100
P1	DC Logic Input	2 Pin MOLEX Sherlock	35507-0200	50212-8100
P2	DC Input / Motor Output	Phoenix or other Screw Terminal		
P4	Motor Temp Input	2 Pin MOLEX Sherlock	35507-0200	50212-8100

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13. ACS300 Interface Circuitry

13.1. J1: Digital I/O

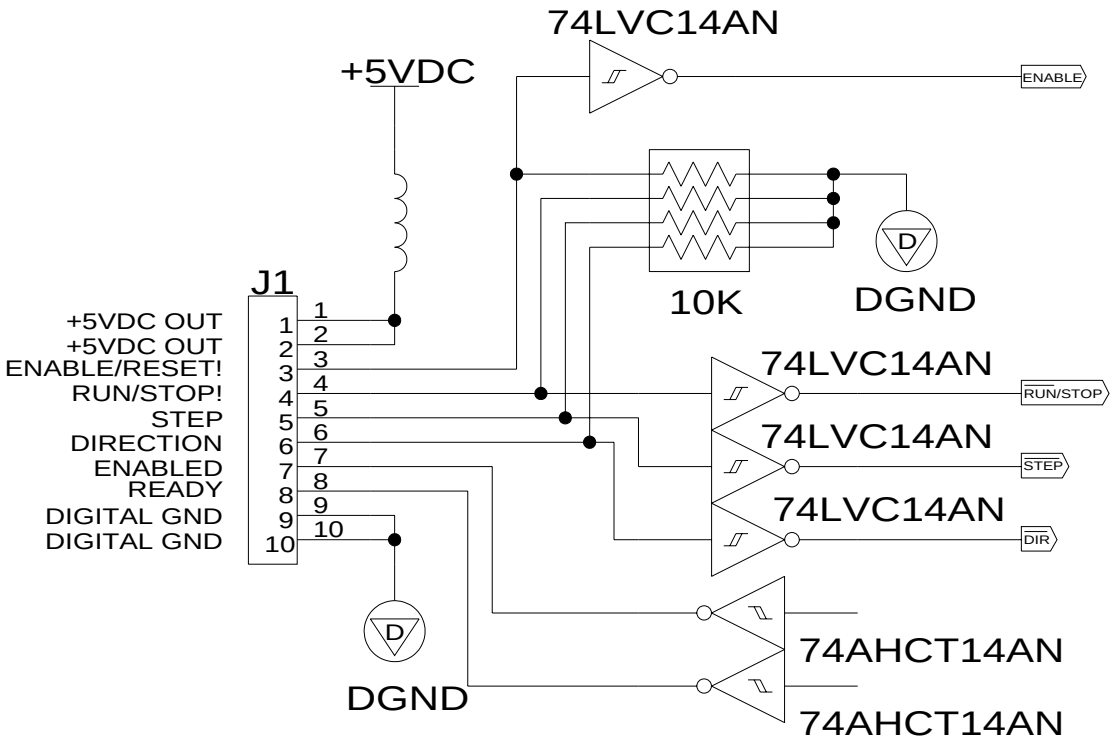

Figure 6: Digital I/O Interface Circuitry

13.2. J2: Analog I/O

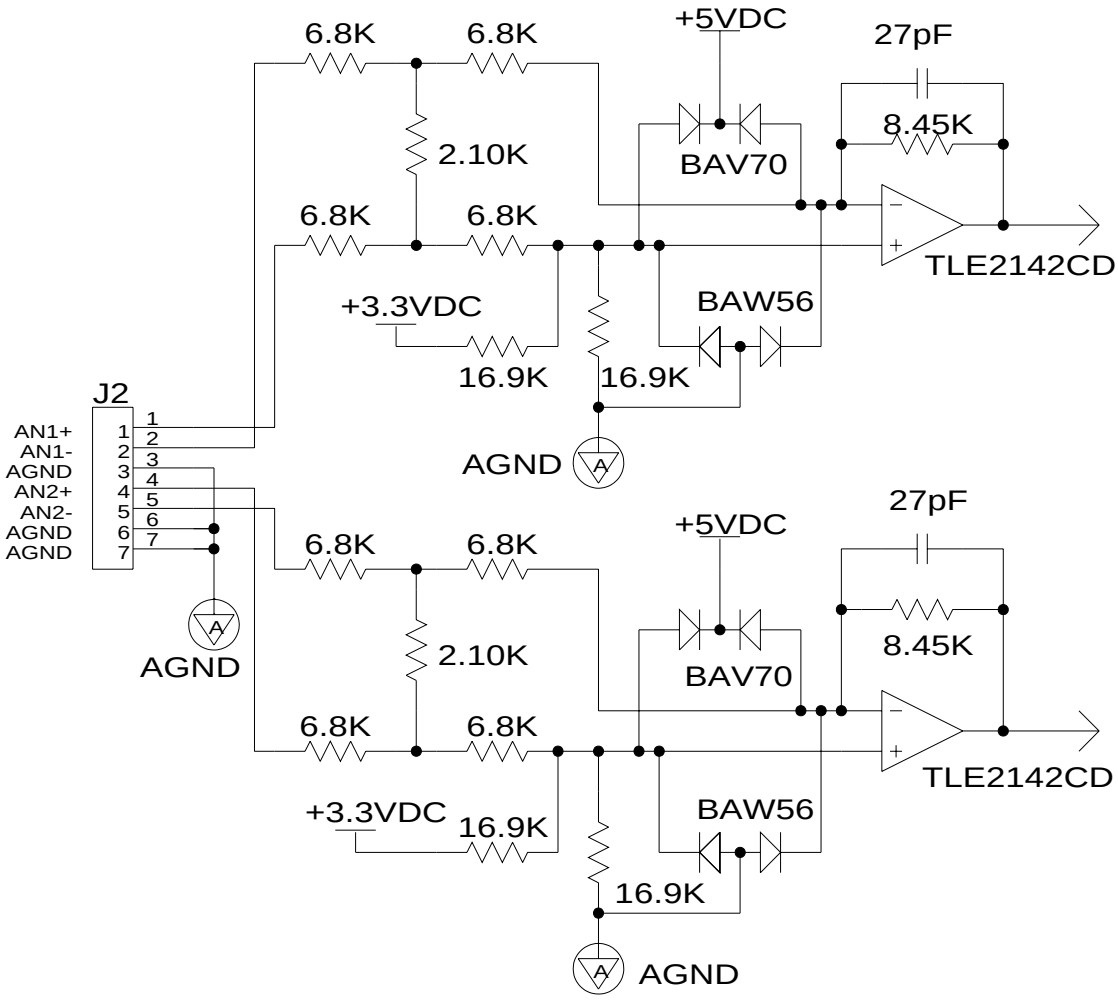

Figure 7: Analog I/O Interface Circuitry

13.3. J3: RS232 Communications Interface

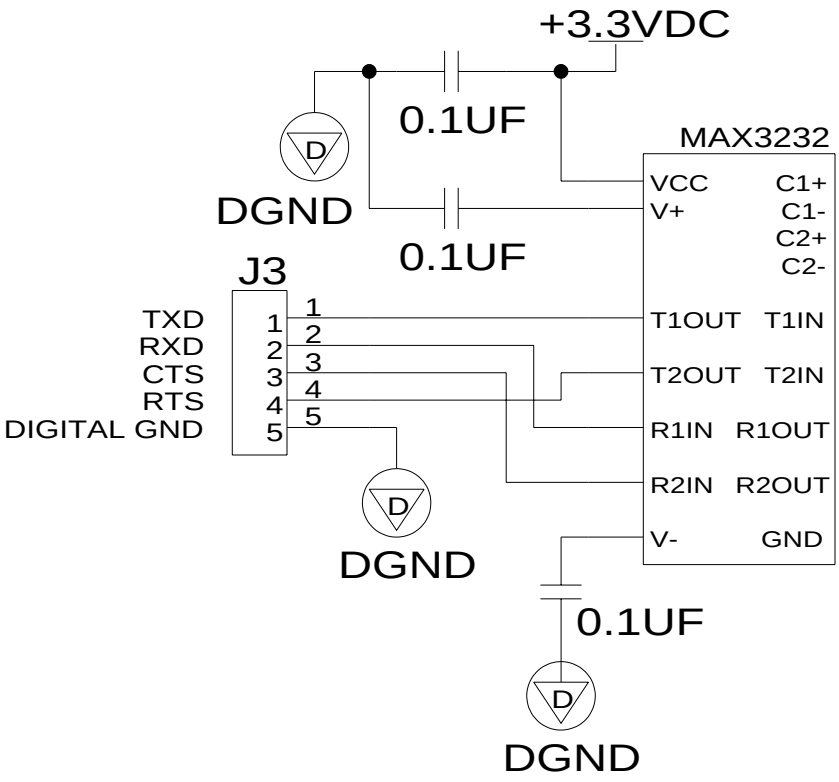

Figure 8: RS232 Communications Interface Circuitry

13.4. J4: Encoder Interface Overview

When using differential encoder feedback A, A!, B, and B!, user may leave Z and Z! unconnected.
If only a single ended encoder feedback A and B is used (and not the A! and B!), then the four jumpers JU1, JU2, JU3 and JU4, which is located on the ACS300 daughter board, must be shorted. You may then leave Z and Z! unconnected.

13.4.1. J4: Encoder Interface

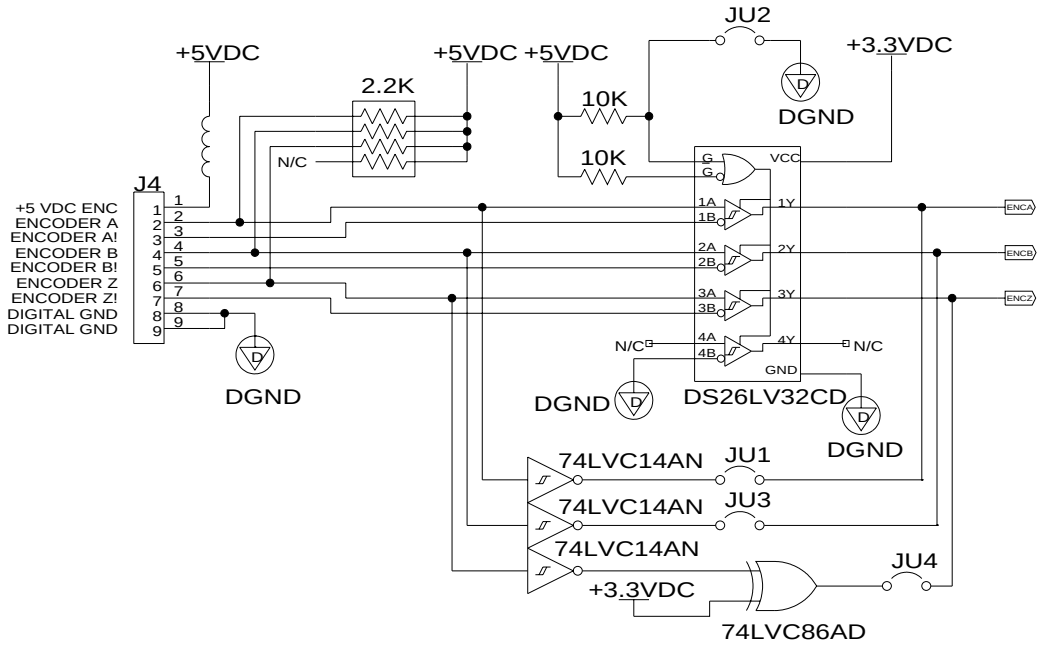

Figure 9: Encoder Interface Circuitry

13.5. J5: Hall Interface Overview

When only Hall based feedback is used and no encoder, leave the encoder connector open.

13.5.1. J5: Hall Interface

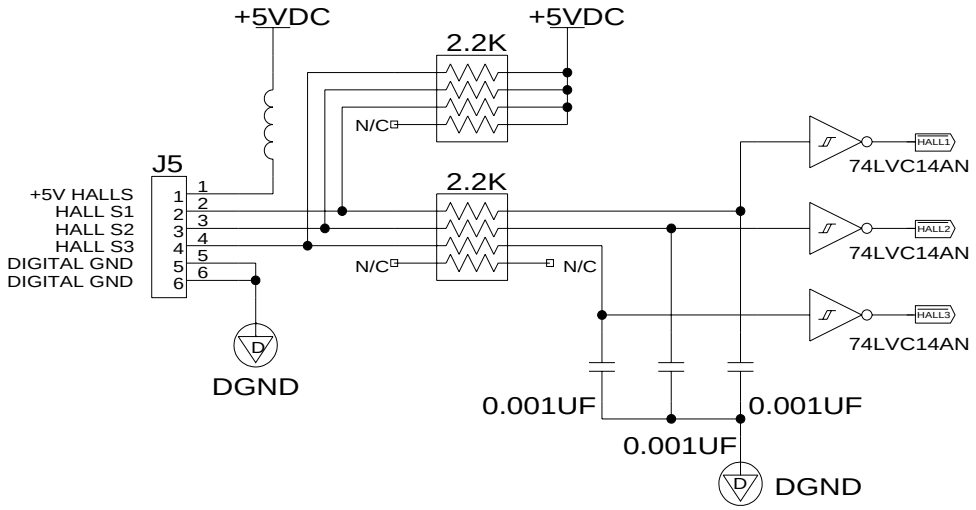

Figure 10: Hall Interface Circuitry

13.6. J6 and J7: CAN Interface

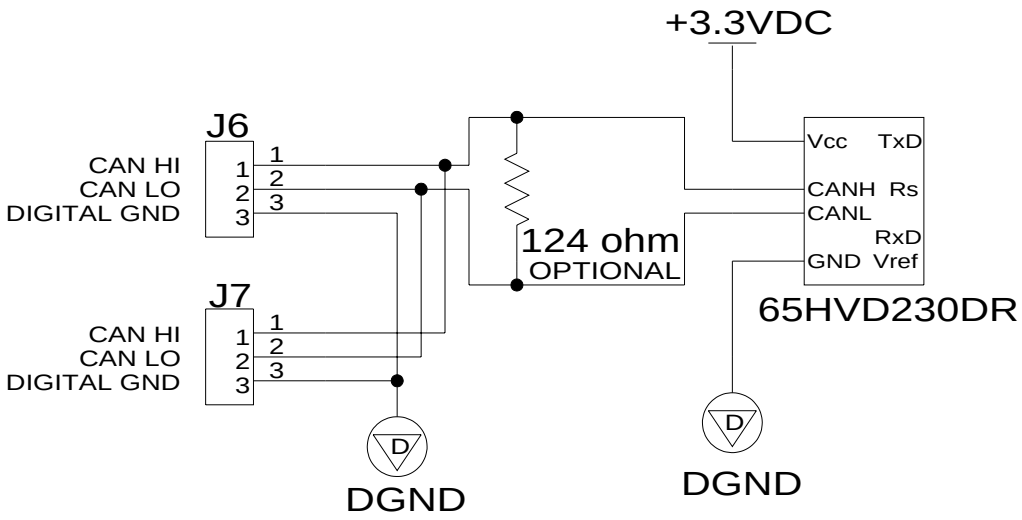

Figure 11: CAN Interface Circuitry

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13.7. Motor Temperature Overview

The **ElectroCraft CompletePower™ Plus** software allows the user to select a PTC or NTC temperature switch.

13.7.1. Motor Temperature Input Circuit

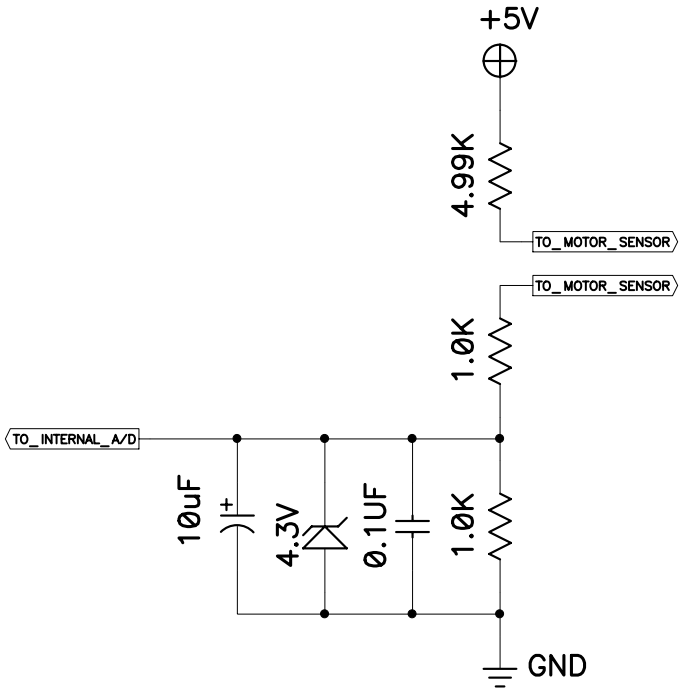


Figure 12: Motor Temperature Input Circuitry

14. External Shunt

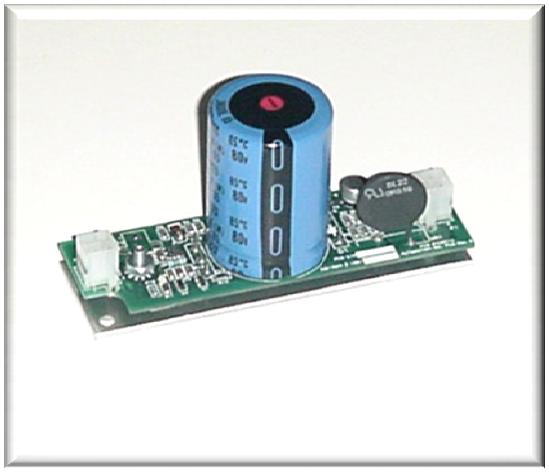


Figure 13: Optional Shunt Assembly

14.1. Use and Selection of the Optional Shunt Assembly

CAUTION!

WHEN THIS PRODUCT USES THE OPTIONAL SHUNT ASSEMBLY, PRECAUTIONS MUST BE FOLLOWED TO PREVENT A POSSIBLE FIRE HAZARD.

Never mount the external shunt where it can make contact with flammable materials, flammable liquid and/or flammable chemicals. Never use the ACS300, either with or without a shunt resistor of any type, in an explosive atmosphere. Never place the shunt resistor in the proximity of flammable materials that could melt or drop upon the shunt resistor body or the ACS300 drive.

THIS PRODUCT USES ELECTRIC POWER AND POSES A SHOCK HAZARD TO THE USER.

Shunt resistors function using high voltage electric power. Avoid physical contact with them whenever the ACS300 has power applied. Shunt resistor(s) can also become extremely hot. Follow the precaution statements, and in conjunction with the manufactures precautions, to help prevent a fire hazard. The electrical terminals of shunt resistors are also a shock hazard. High voltage electricity may be present on these terminals whenever the ACS300 has power applied.

In most applications when heavy dynamic braking and/or regenerative braking are involved, the ACS300 will require an external shunt resistor. To connect such a resistor requires the use of the optional ACS300 Shunt board. See Figure 13 above.

The minimum permissible combined resistance value for the shunt resistor(s) is 4 Ohms. Higher resistance values may be used. The resistor(s) should be rated for high momentary overloads. The External Shunt Board is supplied with a 40 watt / 50 ohm shunt resistor.

When the ACS300 shunt board is used it is wired between the P2 pin 1 DC Input and the DC power source. Please refer to section 6.6.7 for connector wiring.

The optional ACS200 shunt board operates in conjunction with a transistor switch that places the resistor(s) across the DC power rail. Should the transistor ever fail in the ON condition the resistor would remain powered continuously. This could result in the shunt resistor becoming very hot.

The selected wattage rating for the shunt resistor is application dependent. Usually a heavy-duty wire wound resistor will work best. However, not all wire wound resistors are suitable for shunt service. ElectroCraft has found the Ohmite type 250 series works reliably in many shunt applications.

If the user is supplying their own shunt resistor contact ElectroCraft for further application advice. Ask for Field Application Bulletin #101-0195.

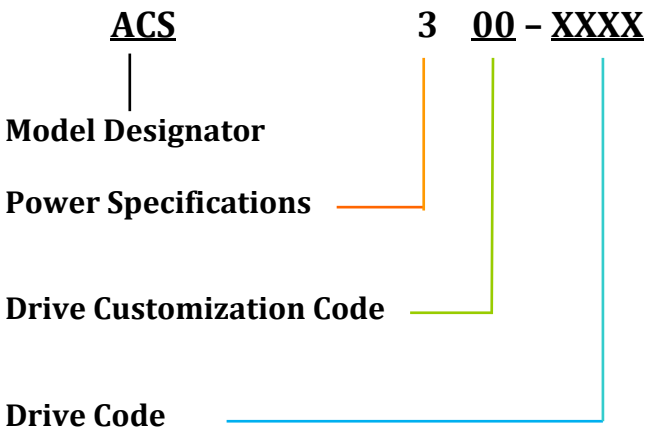
14.2. Connecting the Optional Shunt Board

Plug a cable (Part No. 1002131) from P2 of the optional shunt board to the ACS300.

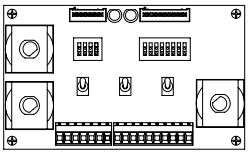
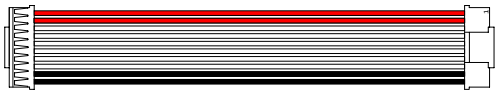
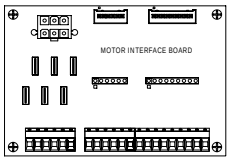
Shunt Board:
P1 – No Connect.
P2 - Power output to ACS300.
Pin1: N/C
Pin2: 0 to +48v drive motor supply.
(Blocking diode at P1 isolates all shunt board operations from power supply).
Pin3: N/C.
Pin4: Motor supply common (pass through connection from P1 to P2).

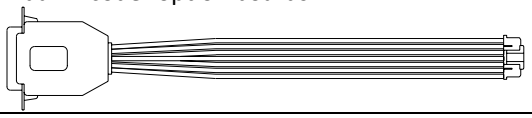
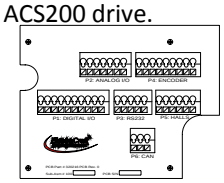
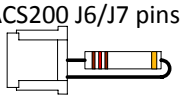
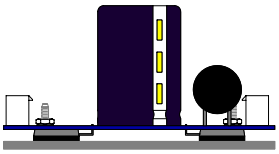
The shunt “turn-on” threshold is approximately 56V and the “turn-off” threshold is approximately 52V. A blocking diode in the shunt board prevents the excess voltage from feeding back to the power supply. As the drive “regenerates”, the shunt board will cycle on and off to dispose of the excess energy through the shunt resistor. Care should be taken to ensure the shunt resistor is not mounted next to any flammable material, as it could get hot.

15. Model Identification



16. Appendix A - Optional Accessories

Name	Length mm (inch)	Description	Part No.	
ACS300 Cable Kit	(305mm (12”)	ACS300 (6 cable assembly) to wire ends: Loose wires at user end. 	1002997	
Quick-Start I/O Test Board	108 x 65 x 36mm (4.25 x 2.5 x 1.4”) (W x H x D)	Test Board 	1001436	1003001 (set)
Quick Start to ACS100/200 Digital I/O Cable	305mm (12”)	Quick Start Test Board P1 to ACS200 J1. 	1002119	
Quick Start to ACS100/200 Analog I/O Cable	305mm (12”)	Quick Start Test Board P2 to ACS200 J2. 		
RS232 Interface Cable (Interface cable for PC)	356mm (14”)	D-sub 9 pin plug to ACS200 J3. 	1002121	
Motor Interface Test Board	96 x 65 x 21mm (3.8 x 2.5 x 0.83”) (W x H x D	Test Board used to easily wire motor to the ACS200 drive. 	1001732	
Hall Cable	305mm (12”)	Interface board J3 to ACS200 J5. 	1002112	
Encoder Cable	305mm (12”)	Interface board J2 to ACS200 J4. 	1002113	
ACS300 Motor Temperature Cable	305mm (12”)	ACS300 to wire ends: Loose wires at user end 	1001728	

Name	Length inch (mm)	Description	Part No.	
ACS to R/D or Dual Encoder Interface Cable	356mm (14”)	D-sub 15 pin to ACS200 J4. Used with R/D or Dual Encoder option boards. 	1002129	
ACS Connector Board	76.20 x 99.06mm 3.0 x 3.9”	Adapter Board with spring terminals to easily wire perifual devices to the ACS200 drive. 	1001203	
Can Interface – Wire ends	305mm (12”)	Loose wires at user end to ACS200 J6/J7. 	1002159	
CAN Interface – DB9F (Interface cable for PC)	356mm (14”)	D-sub 9 pin Plug to ACS200 J6/J7. 	1002125	
CAN Terminating Resistor	n/a	120 ohm resistor between ACS200 J6/J7 pins 1 and 2. 	1002127	
Shunt Board Assembly	114.3 x 64 x 35.56 mm (4.5 x 2.5 x 1.40”) (W x H x D)	External Shunt Board 	1001193	1002992 (set)
Shunt Board wire harness assemblies	14” (356mm)	Shunt board P2 to ACS300 P2. 	1002131	

Note: Custom lengths or applications may be ordered.