

Servo Motor Control Modes

- Cyclic Synchronous Position-Velocity-Torque (CSP, CSV, CST)
- Profile Position-Velocity-Torque, Interpolated Position, Homing
- Indexer, Point-to-Point, PVT
- Camming, Gearing
- Position, Velocity, Torque

Stepper Motor Control Modes

- Cyclic Synchronous Position (CSP)
- Profile Position-Velocity-Torque, Interpolated Position, Homing
- Position/Velocity/Torque (Servo Mode)
- Position (Microstepping)
- Indexer, Point-to-Point, PVT
- Camming, Gearing

Command Interface

- CANopen application protocol over EtherCAT (CoE)
- ASCII and discrete I/O
- Stepper commands
- PWM velocity/torque command
- Master encoder (Gearing/Camming)

Communications

- EtherCAT
- RS-232

Feedback

- Digital quad A/B/X encoder
- Digital Halls

I/O Digital

- 24 HS inputs
- 8 MOSFET outputs

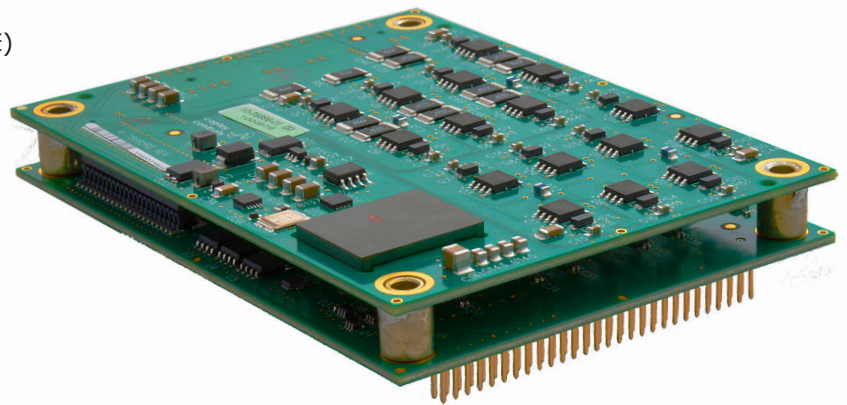
I/O SPI

- 1 HS input
- 4 CMOS HS outputs

Dimensions: mm [in]

- 101.6 x 85.1 x 21 [4.0 x 3.35 x 0.80]

4-AXIS DIGITAL DRIVE FOR SERVO AND STEPPER MOTORS



Model	Ic	Ip	Vdc
ME4-055-03	3	3	14~55

DESCRIPTION

The ME4 is a four-axis, high-performance, DC powered drive for control of stepper or servo motors via EtherCAT. Each axis is configurable to drive a stepper, brushless, or brush motor. Using advanced FPGA technology, the ME4 provides a significant reduction in the cost per node by combining stepper and servo motors into a compact package.

Each axis in the ME4 operates as an EtherCAT node under DSP-402 for motion control devices. Supported modes include: Cyclic position/velocity/torque, Profile Position-Velocity, Interpolated Position Mode (PVT), and Homing.

Servo mode of steppers allows position/velocity/torque control. Servo mode allows EtherCAT or digital PWM control of position/velocity/torque. In microstepping mode stepper command pulses and master encoder for camming or gearing is supported.

Twenty-four high-speed digital inputs with programmable functions are provided. There are eight MOSFET outputs that are 24V compatible. An SPI port is provided with one high-speed input and four high-speed digital outputs. If not used for SPI, the input and outputs are programmable for other functions.

An RS-232 serial port provides a connection to Copley's CME2 software for commissioning, firmware upgrading, and saving configurations to flash memory. The EtherCAT port is magnetically isolated.

Drive power is transformer-isolated DC from regulated or unregulated power supplies. An AuxHV input is provided for "keep-alive" operation permitting the drive power stage to be completely powered down without losing position information, or communications with the control system.

GENERAL SPECIFICATIONS

Test conditions: Load = Bipolar stepper: 2 mH + 2 Ω per phase. Ambient temperature = 25°C, +HV = HV_{max}

MODEL	ME4-055-03	
OUTPUT POWER (each axis)		
Peak Current	3 (2.12)	Adc (Arms-sine), ±5%
Peak time	1	Sec
Continuous current	3 (2.12)	Adc (Arms-sine) per phase (Note 1)
Maximum Output Voltage	Vout = HV*0.97 - Rout*Iout	
INPUT POWER (module)		
HVmin~HVmax	+14 to +55	Vdc Transformer-isolated
Ipeak	12	Adc (1 sec) peak
Icont	12	Adc continuous (Note 1)
Aux HV	+14 to +55 Vdc, 6 W max with all four encoders powered, 3 W max with no encoders	
PWM OUTPUTS		
Type	Dual H-bridge MOSFET, 12.5 kHz center-weighted PWM, space-vector modulation	
PWM ripple frequency	25 kHz	
CONTROL MODES SERVO MOTORS		
EtherCAT: CAN application protocol over EtherCAT (CoE): Cyclic Synchronous Position/Velocity/Torque, Profile Position/Velocity/Torque, Interpolated Position (PVT), Homing		
Digital PWM velocity/torque		
Digital position: CW/CCW, Pulse/Direction, Quadrature A/B		
Discrete I/O: camming, internal indexer and function generator		
CONTROL MODES STEPPER MOTORS		
EtherCAT: CAN application protocol over EtherCAT (CoE): Cyclic Synchronous Position/Velocity (Torque in servo mode) Profile Position/Velocity (Torque in servo mode), Interpolated Position (PVT), Homing		
Digital PWM velocity (Torque in servo mode)		
Digital stepper position commands, CW/CCW, Pulse/Direction, Quadrature A/B		
Discrete I/O: camming, internal indexer and function generator		
COMMAND INPUTS		
Type	EtherCAT, galvanically isolated from drive circuits	
Signals & format	TX+, TX-, RX+, RX-; 100BaseTX	
Data protocol	CANopen application protocol over EtherCAT (CoE)	
Node-ID Selection	Programmable, or via digital inputs. the A-Axis has a programmable unique, non-zero node-ID. The B, C, and D axes have ID that equal the A-Axis +1, +2, and +3	
Digital	PWM/Polarity (Pls/Dir), Step/Direction (CW/CCW), 2 MHz max Quad A/B encoder, 2 MLine/sec (8Mcount/sec after quadrature) Up to 32 sequences can be launched from digital inputs or ASCII commands	
Indexing	Quad A/B digital encoder, up to 10 Cam tables can be stored in flash memory	
Camming	RS-232 (see RS-232 Port, page 2)	
ASCII		
DIGITAL CONTROL		
Digital Control Loops	Current, velocity, position. 100% digital loop control	
Sampling rate (time)	Current loop: 12.5 kHz (80 μs), Velocity & position loops: 2.5 kHz (400 μs)	
Commutation	Sinusoidal, field-oriented control for stepper and servo motors	
Modulation	Center-weighted PWM with space-vector modulation	
Bandwidths	Current loop: 2.5 kHz typical, bandwidth will vary with tuning & load inductance	
HV Compensation	Changes in bus voltage do not affect bandwidth	
Minimum load inductance	200 μH line-line	
DIGITAL INPUTS		
[IN1~24]	High-speed digital, 100 ns RC filter, 10 kΩ pull-up to +3.3 Vdc, +5V compatible 74LVC14 Schmitt trigger, V _{T+} = 1.1~2.0 Vdc, V _{T-} = 0.8~1.5 Vdc, V _H = 0.3~1.2 Vdc	
[IN25]	SPI port MISO input, 47 ns RC filter, 1 kΩ pull-up to +3.3 Vdc 74LVCG14, V _{T+} = 1.3~2.2 Vdc, V _{T-} = 0.6~1.5 Vdc, V _H = 0.4~1.2 Vdc, +5V compatible	
DIGITAL OUTPUTS		
[OUT1~8]	Open-drain MOSFET with 1 kΩ pull-up with series diode to +5 Vdc 300 mAdc max, +30 Vdc max. Functions programmable	
[OUT9~12]	SPI port MOSI, SCLK, SS1, & SS2 signals, 74AHCT125 line drivers, +5V levels Iout: -0.8 mA source at VOH= 2.4V, 6 mA sink at VOL= 0.5V	
DC POWER OUTPUT		
[ENC5V]	+5 Vdc, 500 mA max, thermal and short-circuit protected	
FEEDBACK		
Digital Incremental Encoder	[IN25~36] are four groups of high-speed digital inputs programmed as A/B/X encoder inputs. Single-ended, +5V compatible, same specs as [IN1~24] 2 Mline/sec (8 Mcounts/sec) max when driven by active-output devices	

Notes:

1) Forced-air cooling may be required for operation at full output power on all axes.

MOTOR CONNECTIONS (PER AXIS)

Stepper	Phases A, /A, B, /B, PWM outputs to 2-phase, 4-wire bipolar stepper motors
Servo	Phases A, /A, /B for U, V, W brushless servo motors, or /A, /B for brush servo motors
Digital Incremental Encoder	Quadrature signals, (A, B, X), using inputs [IN25~36]
Encoder power	2 MHz maximum line frequency (8 M counts/sec) when driven by active devices (See DC POWER OUTPUTS section)

RS-232 PORT

Signals	RxD, TxD, Gnd for operation as a DTE device
Mode	Full-duplex, DTE serial port for drive setup and control, 9,600 to 115,200 Baud
Protocol	ASCII or Binary format

PROTECTIONS

HV Overvoltage	+HV > 55 Vdc	Drive outputs turn off until +HV < 55 Vdc
HV Undervoltage	+HV < +14 Vdc	Drive outputs turn off until +HV > +14 Vdc
Drive over temperature	Heat plate > 90°C.	Drive outputs turn off
Short circuits	Output to output, output to ground, internal PWM bridge faults	
I ² T Current limiting	Programmable: continuous current, peak current, peak time	

MECHANICAL & ENVIRONMENTAL

Size mm [in]	101.6 x 76.2 x 20.83 [4.00 x 3.00 x 0.83]
Weight	ME4: 0.09 kg [0.20 lb], ME4 + DevKit: 0.38 kg [0.84 lb]
Ambient temperature	0 to +45°C operating, -40 to +85°C storage
Humidity	0 to 95%, non-condensing
Vibration	2 g peak, 10~500 Hz (sine), IEC60068-2-6
Shock	10 g, 10 ms, half-sine pulse, IEC60068-2-27
Contaminants	Pollution degree 2
Environment	IEC68-2: 1990
Cooling	Forced air cooling may be required for continuous power output

AGENCY STANDARDS CONFORMANCE (PENDING)

In accordance with EC Directive 2004/108/EC (EMC Directive)

EN 55011: 2009/A1:2010	CISPR 11:2009/A1:2010 Industrial, Scientific, and Medical (ISM) Radio Frequency Equipment – Electromagnetic Disturbance Characteristics – Limits and Methods of Measurement Group 1, Class A
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EN 61000-6-1: 2007	Electromagnetic Compatibility (EMC) – Part 6-1: Generic Standards – Immunity for residential, Commercial and Light-industrial Environments
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In accordance with EC Directive 2006/95/EC (Low Voltage Directive)

IEC 61010-1:2001	Safety Requirements for Electrical Equipment for Measurement, Control and Laboratory Use
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Underwriters Laboratory Standards

UL 61010-1, 2nd Ed.: 2008	Electrical Equipment for Measurement, Control and Laboratory Use; Part 1: General Requirements
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UL File Number E249894

CONTROL MODES AND COMMAND INPUTS

This chart shows the possible combinations of Control Modes and the Command Inputs that are available in each mode. Servo mode is the use of encoder feedback to operate the stepper as a brushless motor.

Command Source	Control Mode			Motor Mode	
	Position	Velocity	Torque	Microstep	Servo
EtherCAT CSP or Profile Position	√			√	√
EtherCAT CSV or Profile Velocity		√		√	√
EtherCAT CST or Profile Torque			√		√
EtherCAT Homing	√			√	√
EtherCAT Interpolated Position	√			√	√
Quad A/B Encoder	√			√	√
Digital Pls/Dir	√			√	√
Digital CW/CCW	√			√	√
Digital PWM		√	√		√
CVM Indexer Position	√			√	√
CVM Indexer Velocity		√		√	√

Notes:

- 1) CSP = Cyclic Synchronous Position, CSV = Cyclic Synchronous Velocity, CST = Cyclic Synchronous Torque
- 2) Microstep = stepper motor with no feedback, Servo = stepper motor with feedback in servo mode, or brushless/brush servo motor with feedback.

CME 2 SOFTWARE

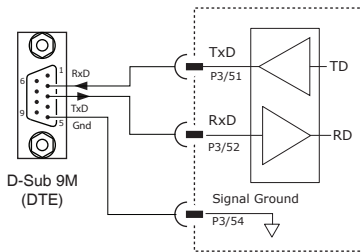
Drive setup is fast and easy using CME 2 software. All of the operations needed to configure the drive are accessible through this powerful and intuitive program. Auto-phasing of brushless motor Hall sensors and phase wires eliminates "wire and try". Connections are made once and CME 2 does the rest thereafter. Encoder wire swapping to establish the direction of positive motion is eliminated. Motor data can be saved as .CCM files. Drive data is saved as .CCX files that contain all drive settings plus motor data. This eases system management as files can be cross-referenced to drives. Once a drive configuration has been completed systems can be replicated easily with the same setup and performance.

RS-232 COMMUNICATIONS

ME4 is configured via a three-wire, full-duplex DTE RS-232 port that operates from 9600 to 115,200 Baud, 8 bits, no parity, and one stop bit. Signal format is full-duplex, 3-wire, DTE using Rx/D, Tx/D, and Gnd. Connections to the ME4 RS-232 port are through P2 The graphic below shows the connections between an ME4 and a computer COM port which is a DTE device.

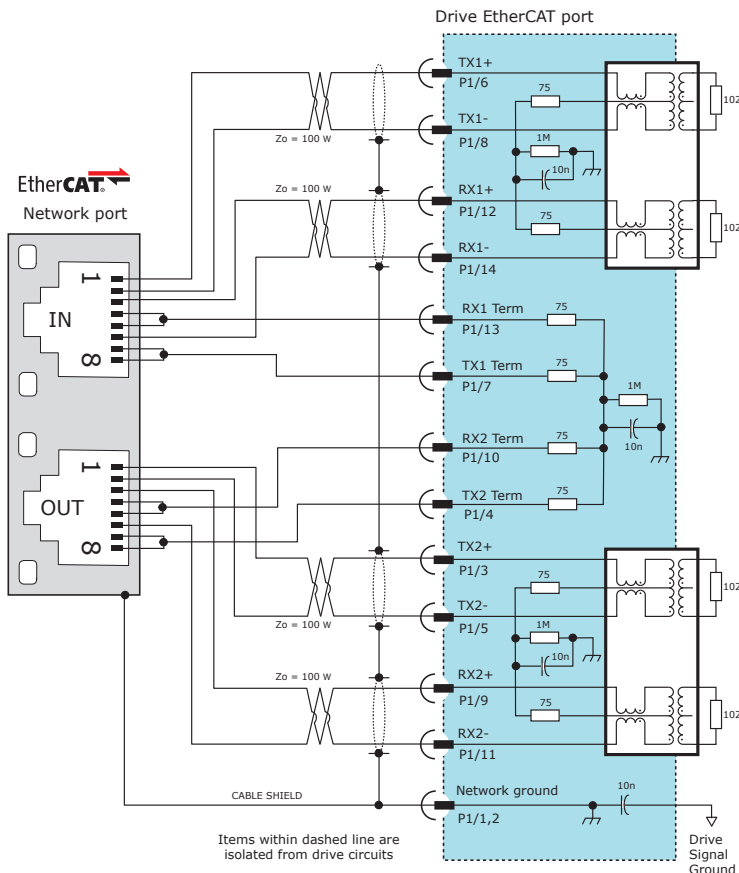
CME2 -> Tools -> Communications Wizard

RS232 PORT



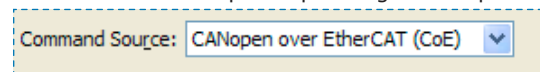
ETHERCAT COMMUNICATIONS

EtherCAT is the open, real-time Ethernet network developed by Beckhoff based on the widely used 100BASE-TX cabling system. EtherCAT enables high-speed control of multiple axes while maintaining tight synchronization of clocks in the nodes. Data protocol is CAN application layer over EtherCAT (CoE) based on DSP-402 for motion control devices. More information on EtherCAT can be found on this web-site: <http://ethercat.org/default.htm>



HOW IT LOOKS IN CME2

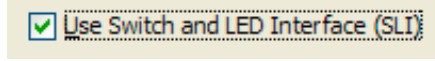
CME2 -> Basic Setup -> Operating Mode Options



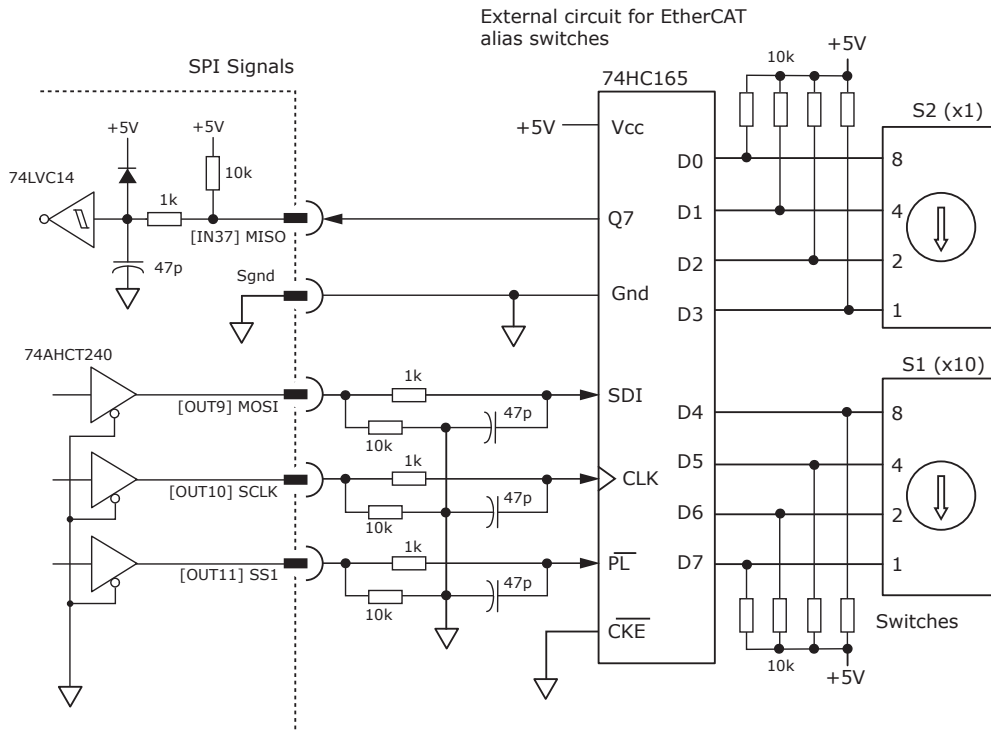
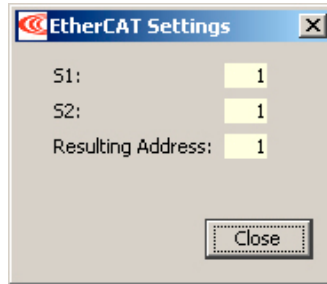
ETHERCAT DEVICE ID (STATION ALIAS) SWITCHES

The SPI port takes in the 8 signals from the two BCD encoded switches that set the EtherCAT Device ID and controls the LEDs on the EtherCAT port connectors. The graphic below shows the circuit for reading the EtherCAT Device ID switches. The 74HC165 works as a parallel-in/serial-out device. The 10k pull-down resistors pull the shift register inputs to ground when the ME4 is initializing. In the graphics below, the values of S1 are 16~255 and of S2 are 0~15. Together they provide Device ID range of 0~255.

CME2 -> Input/Output -> Digital Outputs



CME2 -> Amplifier -> Network Configuration



ETHERCAT 4-AXIS AND THE OBJECT DICTIONARY

Single-axis EtherCAT devices use objects in the range of 0x6000 to 0x67FF for standardized data that are read or written via the network as defined in CAN-CiA document CiA 301 CANopen Application Protocol and Communication Profile. The ME4 appears as a single slave node on an EtherCAT network that contains three logical devices: Axis A, B, and C. The standardized data objects for each is located in two sections of the object dictionary:

- Axis A = 0x6000 to 0x67FF (the same range as single-axis devices such as the BEL model)
- Axis B = 0x6800 to 0x6FFF
- Axis C = 0x7000 to 0x77FF
- Axis D = 0x7800 to 0x7FFF

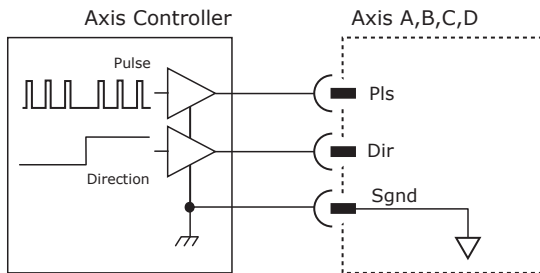
Axis B objects correspond exactly to the objects for Axis A and can be addressed easily by adding 0x800 to the index of an Axis A object. And Axis C object indexes are the same as Axis A objects + 0x1000. E.g. Mode of Operation for Axis A is 0x6060, Axis B is 0x6860, Axis C is 0x7060, Axis D is 0x7860.

DIGITAL COMMAND INPUTS

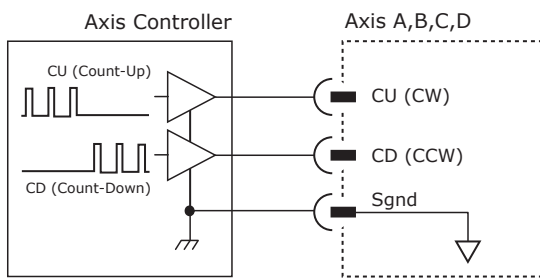
Digital commands are single-ended format and should be sourced from devices with active pull-up and pull-down to take advantage of the high-speed inputs. The active edge (rising or falling) is programmable for the Pulse/Dir and CU/CD formats.

DIGITAL POSITION

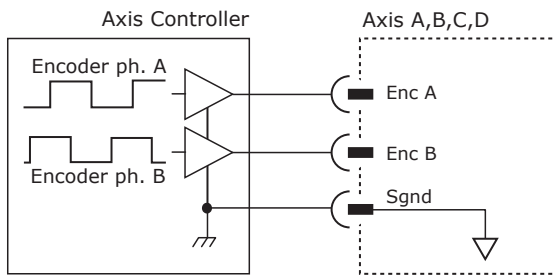
PULSE & DIRECTION



CU/CD (PULSE UP / PULSE DOWN)

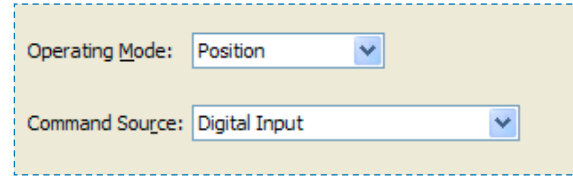


QUAD A/B ENCODER



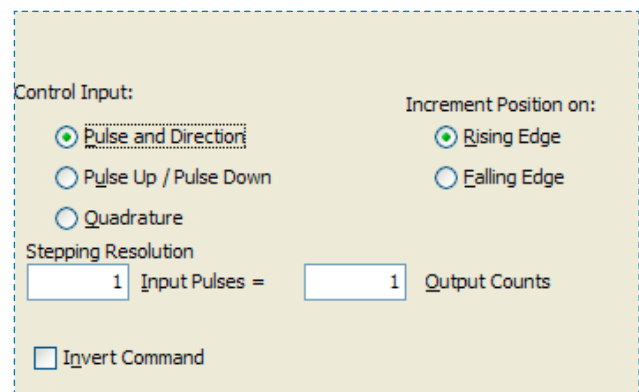
HOW IT LOOKS IN CME2

CME2 -> Basic Setup -> Operating Mode Options



HOW IT LOOKS IN CME2

CME2 -> Basic Setup -> Operating Mode Options



This screen shows the configuration screen for Pulse & Direction. CU/CD and Quad A/B encoder are selectable on this screen, too.

SIGNALS & PINS

The functions shown are the defaults. These can be programmed for other functions.

Functions			Axis A		Axis B		Axis C		Axis D	
			P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal
Enc A	Pulse	CW	19	[IN5]	25	[IN11]	31	[IN17]	37	[IN23]
Enc B	Dir	CCW	20	[IN6]	26	[IN12]	32	[IN18]	38	[IN24]

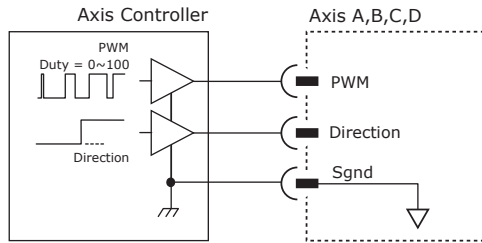
Note:

- The functions shown for [IN5~6], [IN11~12], [IN17~18] and [IN23~24] apply when they are used as digital command inputs for position control. These inputs are programmable if not used for these functions.

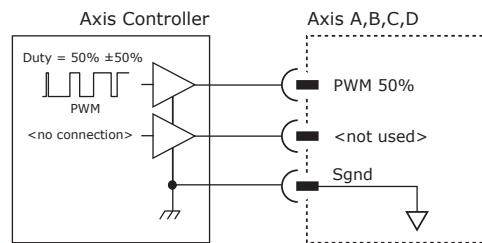
DIGITAL COMMAND INPUTS (CONT'D)

DIGITAL TORQUE, VELOCITY

PWM COMMAND (100% DUTY CYCLE)

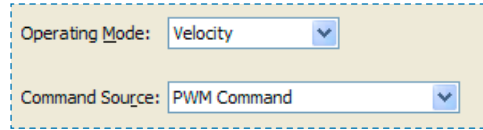


PWM COMMAND (50% DUTY CYCLE)

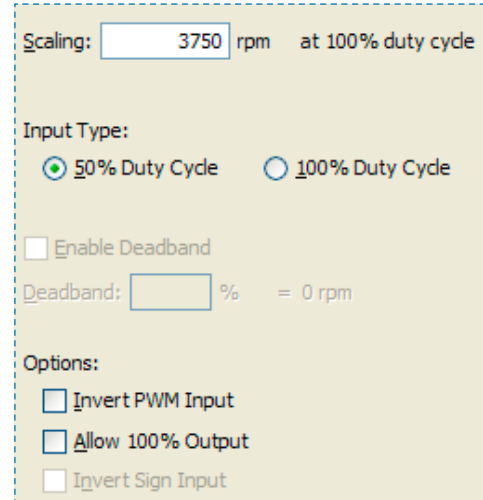


HOW IT LOOKS IN CME2

CME2 -> Basic Setup -> Operating Mode Options



CME2 -> Main Page-> PWM Command



This screen shows the 50% Duty Cycle selection. Other modes are selectable via radio buttons and pull-down menus for Operating Mode and Command Source.

SIGNALS & PINS

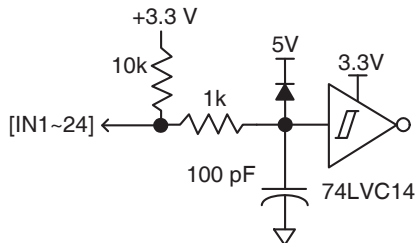
Function		Axis A		Axis B		Axis C		Axis D	
		P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal
PWM	PWM 50%	19	[IN5]	25	[IN11]	31	[IN17]	37	[IN23]
Polarity	n/a	20	[IN6]	26	[IN12]	32	[IN18]	38	[IN24]

Note:

- The functions shown for [IN5~6], [IN11~12], [IN17~18] and [IN23~24] apply when they are used as digital command inputs for position control. These inputs are programmable if not used for these functions.

DIGITAL COMMAND INPUTS

HIGH SPEED INPUTS [IN1~24]
5V tolerant



HI/LO DEFINITIONS: INPUTS

Input	State	Condition
IN1~24	HI	Vin >= 2.0 Vdc
	LO	Vin <= 0.8 Vdc

INPUT/OUTPUT

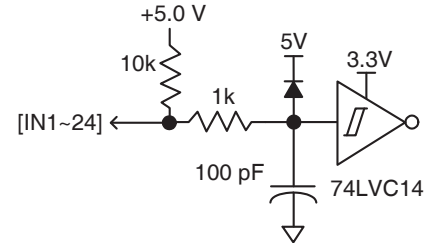
DIGITAL INPUTS

ME4 has 24 high-speed digital inputs, all of which have programmable functions. They are compatible with 5V logic and have 100 ns R/C filters when driven by devices with active pull-up/pull-down outputs.

Programmable functions of the digital inputs include:

- Drive Enable
- Positive Limit switch
- Negative Limit switch
- Digital Command Inputs
- Home switch
- Drive Reset
- Motion abort

HIGH-SPEED DIGITAL INPUTS
+5 VDC MAX



SIGNALS & PINS

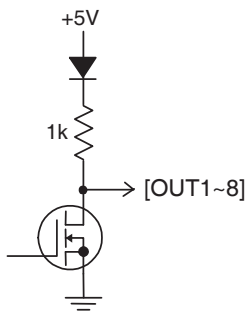
The pins in the chart are on connector P3. The functions shown are the defaults. These can be programmed for other functions.

Functions					Axis A		Axis B		Axis C		Axis D	
					P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal
Enable					15	[IN1]	21	[IN7]	27	[IN13]	33	[IN19]
Pos Limit					16	[IN2]	22	[IN8]	28	[IN14]	34	[IN20]
Neg Limit					17	[IN3]	23	[IN9]	29	[IN15]	35	[IN21]
<not assigned>					18	[IN4]	24	[IN10]	30	[IN16]	36	[IN22]
Enc A	Pulse	CW	PWM	PWM 50%	19	[IN5]	25	[IN11]	31	[IN17]	37	[IN23]
Enc B	Dir	CCW	Polarity	n/a	20	[IN6]	26	[IN12]	32	[IN18]	38	[IN24]

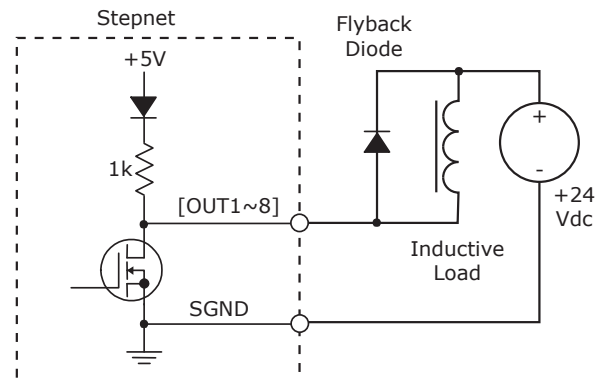
DIGITAL OUTPUTS

Digital outputs [OUT1~8] are open-drain MOSFETs with 1 kΩ pull-up resistors in series with a diode to +5 Vdc. They can sink up to 300 mAdc from external loads operating from power supplies to +30 Vdc. The outputs are typically configured as drive fault and motor brake. Additional functions are programmable. As a drive fault output, the active level is programmable to be HI or LO when a fault occurs. As a brake output, it is programmable to be either HI or LO to release a motor brake when the drive is enabled. When driving inductive loads such as a relay, an external fly-back diode is required. A diode in the output is for driving PLC inputs that are opto-isolated and connected to +24 Vdc. The diode prevents conduction from +24 Vdc through the 1 kΩ resistor to +5 Vdc in the drive. This could turn the PLC input on, giving a false indication of the drive output state.

DIGITAL OUTPUTS
30 VDC, 300 MA MAX



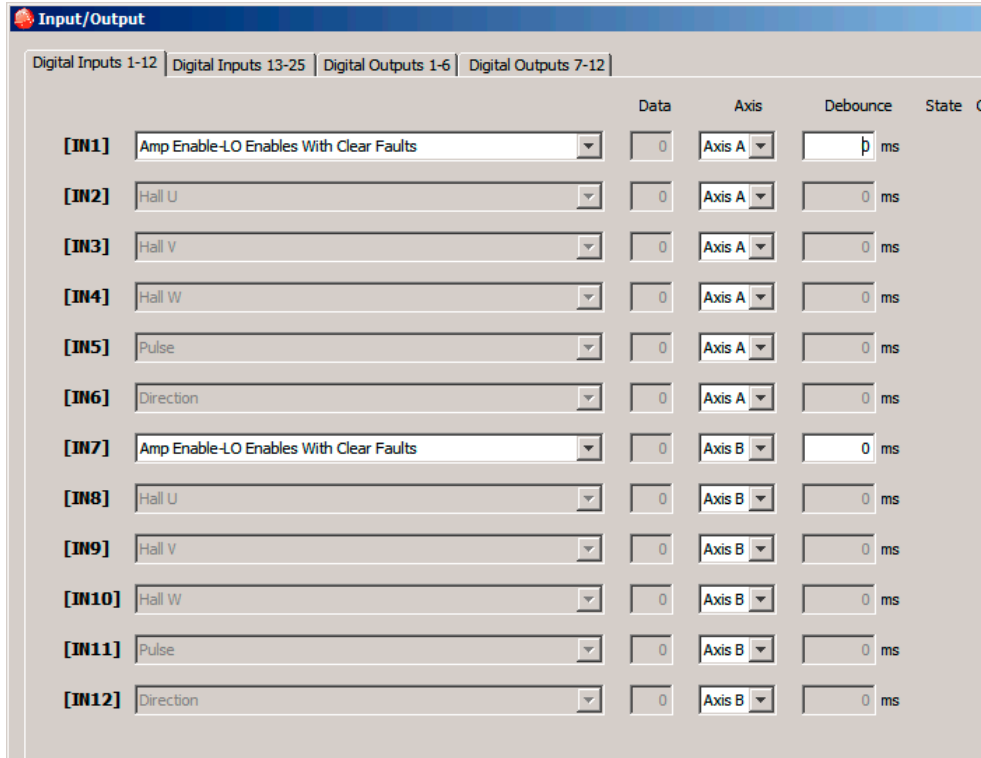
DRIVING INDUCTIVE LOADS



DIGITAL INPUT DETAILS

HOW IT LOOKS IN CME2

CME2 -> Main Page-> Input/Output -> Digital Inputs 1-12



Notes:

The functions for all of the inputs are programmable. The functions shown above are defaults for the combinations listed below:

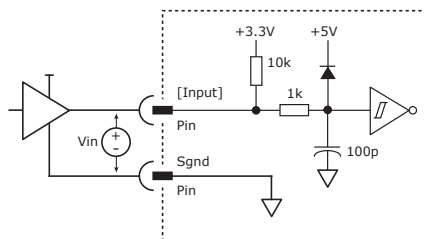
- [IN1] and [IN7] are the defaults for the Enable function.
- [IN2~4] and [IN8~10] are the Hall signal defaults when used on brushless servo motors.
If these are not used for Halls, the chart on page 8 shows the other default functions for these inputs
- [IN5~6] and [IN11~12] are the digital command input defaults for position, velocity, or torque control

DIGITAL INPUT PINS AND FUNCTIONS

Functions					Axis A		Axis B	
					P3 Pins	Signal	P3 Pins	Signal
Enable					15	[IN1]	21	[IN7]
Hall U					16	[IN2]	22	[IN8]
Hall V					17	[IN3]	23	[IN9]
Hall W					18	[IN4]	24	[IN10]
Enc A	Pulse	CW	PWM	PWM 50%	19	[IN5]	25	[IN11]
Enc B	Dir	CCW	Polarity	n/a	20	[IN6]	26	[IN12]

HIGH SPEED DIGITAL INPUTS [IN1~IN12]

5V tolerant



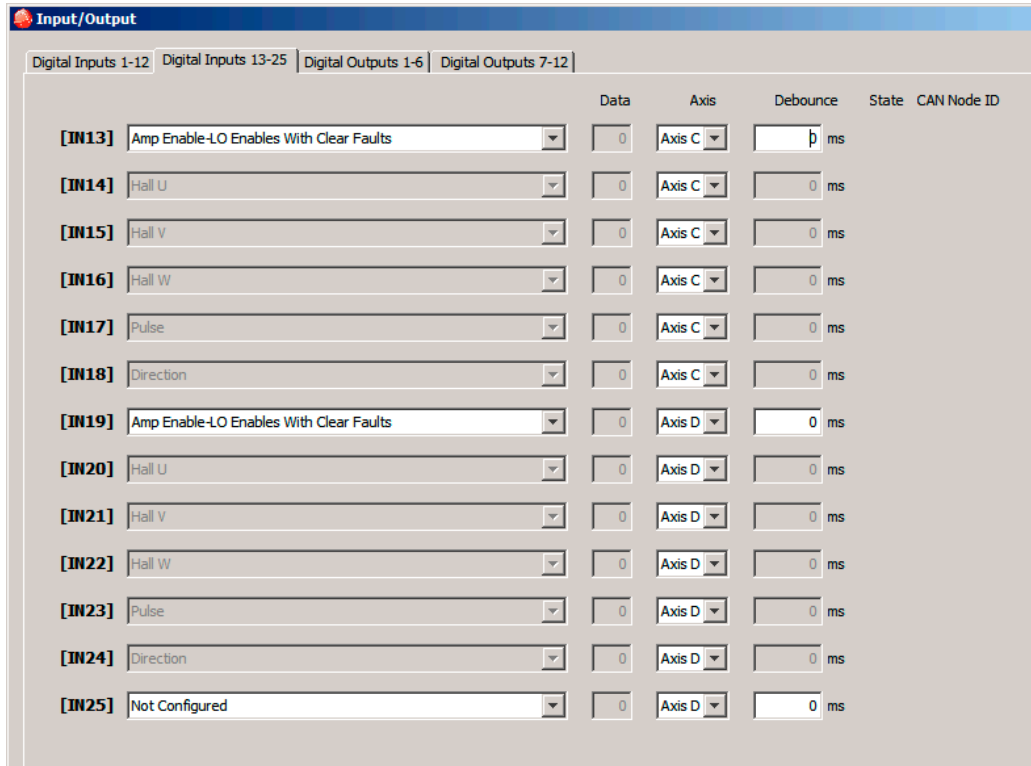
HIGH SPEED DIGITAL INPUTS [IN1~IN12] 5V tolerant

Input	State	Condition
IN1~12	HI	Vin >= 2.0 Vdc
	LO	Vin <= 0.8 Vdc

DIGITAL INPUT DETAILS

HOW IT LOOKS IN CME2

CME2 -> Main Page-> Input/Output -> Digital Inputs 13-25



Notes:

The functions for all of the inputs are programmable. The functions shown above are defaults for the combinations listed below:

- [IN13] and [IN19] are the defaults for the Enable function.
- [IN14~16] and [IN21~22] are the Hall signal defaults when used on brushless servo motors. If these are not used for Halls, the chart on page 8 shows the other default functions for these inputs
- [IN17~18] and [IN23~24] are the digital command input defaults for position, velocity, or torque control.

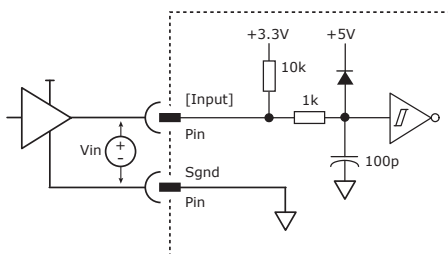
DIGITAL INPUT PINS AND FUNCTIONS

Functions					Axis C		Axis D	
					P3 Pins	Signal	P3 Pins	Signal
Enable					27	[IN13]	33	[IN19]
Hall U					28	[IN14]	34	[IN20]
Hall V					29	[IN15]	35	[IN21]
Hall W					30	[IN16]	36	[IN22]
Enc A	Pulse	CW	PWM	PWM 50%	31	[IN17]	37	[IN23]
Enc B	Dir	CCW	Polarity	n/a	32	[IN18]	38	[IN24]

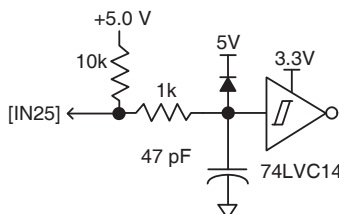
HI/LO DEFINITIONS: INPUTS

Input	State	Condition
IN13~24	HI	Vin >= 2.0 Vdc
	LO	Vin <= 0.8 Vdc

HIGH SPEED DIGITAL INPUTS [IN13~IN24]
5V tolerant



HIGH SPEED INPUT [IN25]
5V tolerant



IN25 SPI_MISO

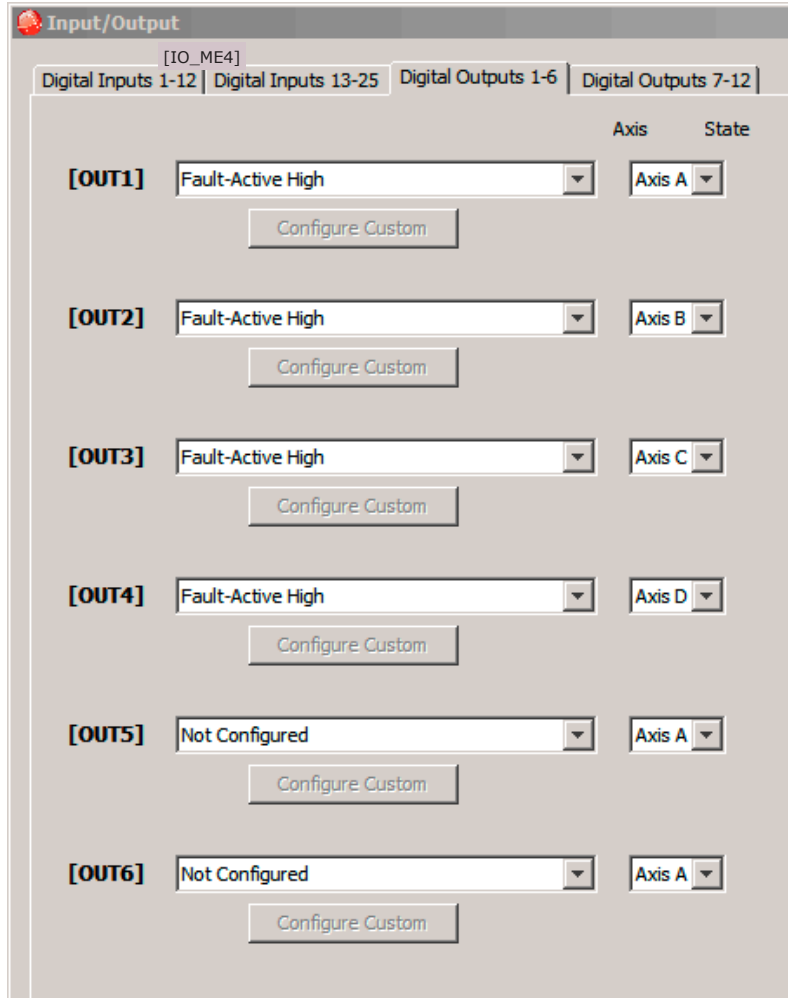
If the SPI port is not used, [IN25] is programmable for other functions.

Input	State	Condition
IN25	HI	Vin >= 2.6 Vdc
	LO	Vin <= 0.7 Vdc
P3 Pin	9	[IN25]

DIGITAL OUTPUT DETAILS

HOW IT LOOKS IN CME2

CME2 -> Main Page-> Input/Output -> Digital Outputs 1-6



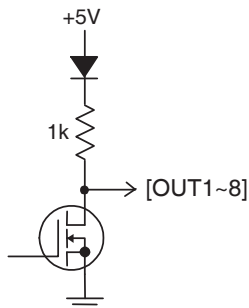
HI/LO DEFINITIONS: OUTPUTS 1~6

Output	State	Condition
OUT1~6	HI	MOSFET OFF
	LO	MOSFET ON

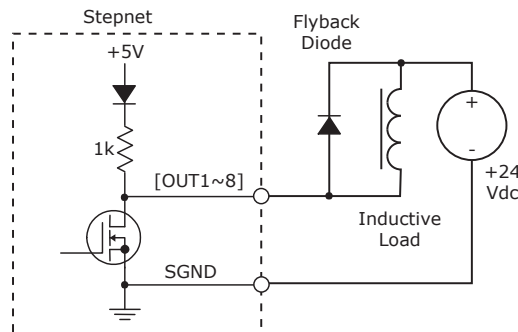
MOSFET OUTPUTS & PINS

Function	P3 Pin
[OUT1]	41
[OUT2]	42
[OUT3]	43
[OUT4]	44
[OUT5]	45
[OUT6]	46

MOSFET DIGITAL OUTPUTS



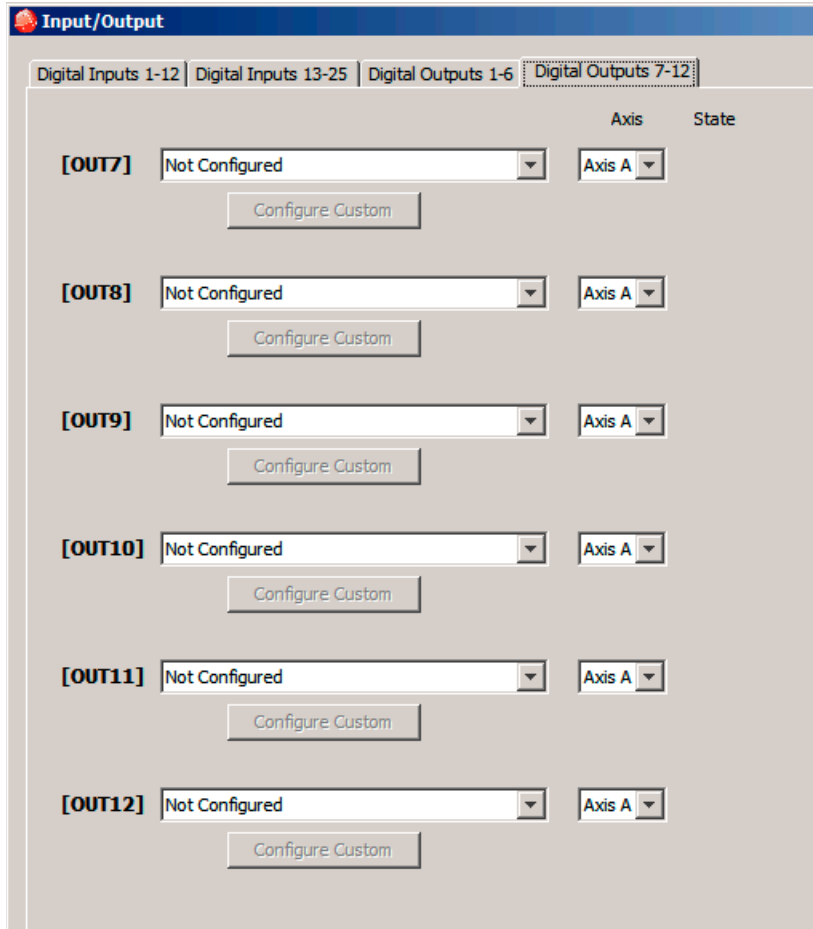
MOSFET DIGITAL OUTPUTS: INDUCTIVE LOADS



DIGITAL OUTPUT DETAILS

HOW IT LOOKS IN CME2

CME2 -> Main Page-> Input/Output -> Digital Outputs 7-12



HI/LO DEFINITIONS: OUTPUTS

Output	State	Condition
OUT7~8	HI	MOSFET OFF
	LO	MOSFET ON
OUT9~12	HI	Vout >= 2.2 Vdc
	LO	Vout <= 0.8 Vdc

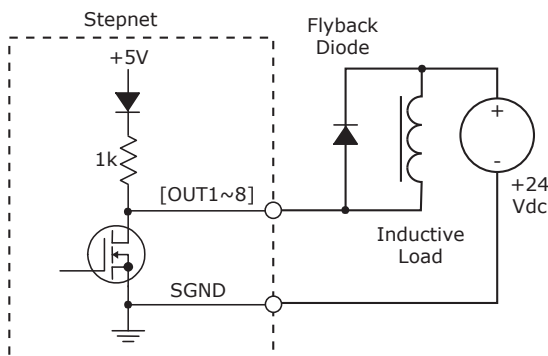
MOSFET OUTPUTS & PINS

Output	P5 Pin
[OUT7]	47
[OUT8]	48

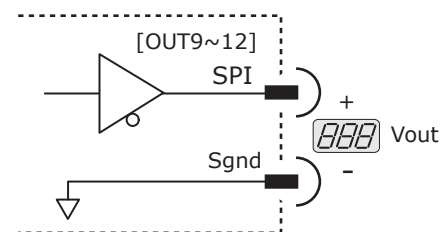
SPI OUTPUTS & PINS

Output	P5 Pin
[OUT9]	31
[OUT10]	32
[OUT11]	33
[OUT12]	34

MOSFET DIGITAL OUTPUTS [OUT7~8] WITH INDUCTIVE LOAD
300 mA max, 30Vdc max

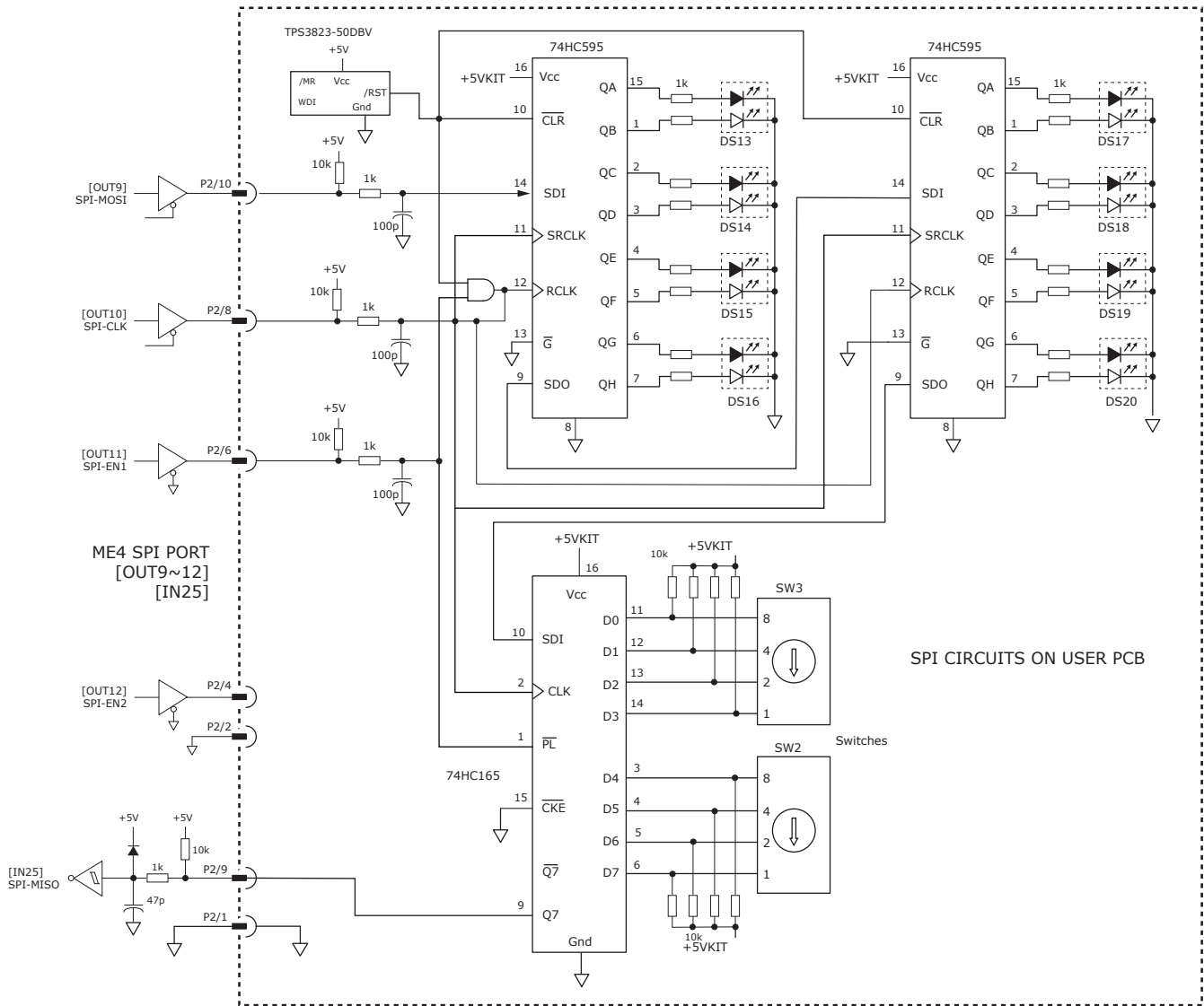


HIGH SPEED DIGITAL (SPI) OUTPUTS [OUT9~12]
74HCT125
5V max



SPI PORT

This graphic shows all of the SPI port outputs and input together. The connections shown are those used on the ME4 Development Kit as an example of the port's usage for inputs and outputs.



HI/LO DEFINITIONS: OUTPUTS

Input	State	Condition
[OUT9~12]	HI	Vout >= 2.2 Vdc
	LO	Vout <= 0.8 Vdc

SIGNALS & PINS

Output	P2 Pin
[OUT9]	10
[OUT10]	8
[OUT11]	6
[OUT12]	4
[IN25]	9
Sgnd	2

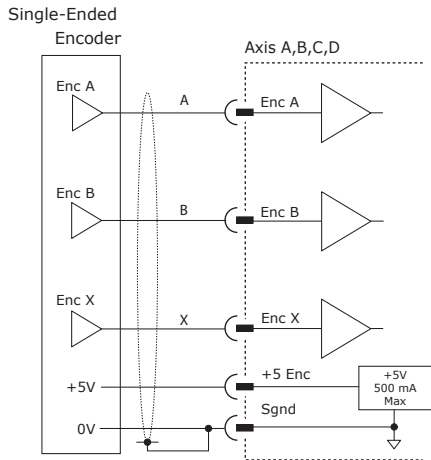
If these signals are not used for the SPI port, they are programmable for other functions.

MOTOR CONNECTIONS

Motor connections consist of: phases, encoder, and brake. The phase connections carry the drive output currents that drive the motor to produce motion. The encoder signals give position feedback and are used for velocity and position modes. A brake can provide a fail-safe way to prevent movement of the motor when the drive is shut-down or disabled.

SINGLE-ENDED ENCODER CONNECTIONS

Single-ended (SE) encoders must have active outputs (not open-collector). Cables should be shielded because SE encoders are more susceptible to electrical interference than differential-output encoders. And, they not be routed together with the phase connections which have PWM waveforms that could couple noise into encoder cabling.



CME2 -> Motor/Feedback -> Feedback



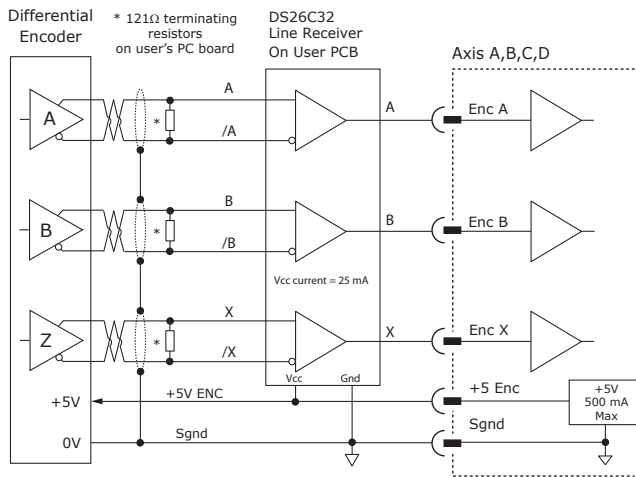
Important:

The ME4 +5V output is rated at 500 mA max which must be shared between encoders that are connected to it. If the combined current of four encoders is greater than 500 mA, then the mounting board of the ME4 must have +5V to power the devices.

If external +5V power is used for encoders, DO NOT CONNECT THIS TO THE +5V OUTPUT OF THE ME4. Encoders and/or other circuits may be powered either from external or ME4 +5V outputs as long as they both connect to Signal Ground.

DIFFERENTIAL ENCODER CONNECTIONS

To convert differential encoder outputs to single-ended signals, a line receiver must be mounted to the users PC board. Terminating resistors are also recommended to ensure signal quality. The maximum +5V output current from the ME4 is 500 mA which must support a maximum of four encoders. When using line receivers for differential encoders, the user must consider the total +5V power required for the four encoders and line receivers. If this exceeds 500 mA (2.5W) then the line receivers and/or encoders should be powered from a +5V source on the mounting PC board.



This graphic shows both encoder and line-receiver powered from the ME4 +5V output. If four encoders are connected like this, and assuming 25 mA for each line-receiver, then the available +5V power for each encoder would be 100 mA.

If the encoder power requirement is greater than 100 mA, then external +5V on the mounting board must be used in addition to the +5V from the ME4.

If external +5V power is used for encoders, DO NOT CONNECT THIS TO THE +5V OUTPUT OF THE ME4.

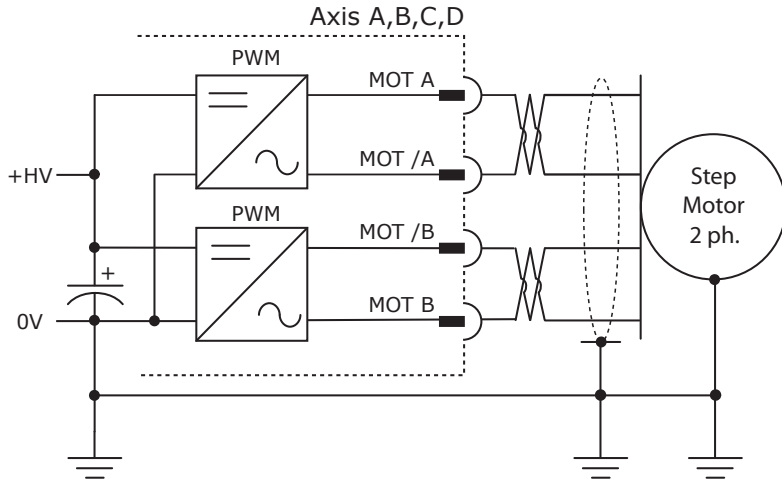
SIGNALS & PINS

Functions	Axis A	Axis B	Axis C	Axis D
	P3 Pins	P3 Pins	P3 Pins	P3 Pins
Enc A	1	2	7	8
Enc B	3	4	9	10
Enc X	5	6	11	12

MOTOR CONNECTIONS

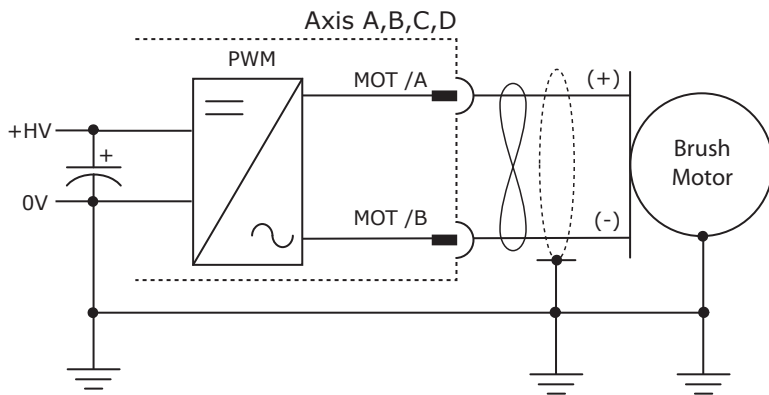
STEPPER MOTORS

The drive outputs are two H-bridge PWM inverters that convert the DC bus voltage (+HV) into sinusoidal voltage waveforms that drive the motor phase-coils. Cable should be sized for the continuous current rating of the drive. Motor cabling should use twisted, shielded conductors for CE compliance, and to minimize PWM noise coupling into other circuits. The motor cable shield should connect to motor frame and the drive HV ground terminal for best results.



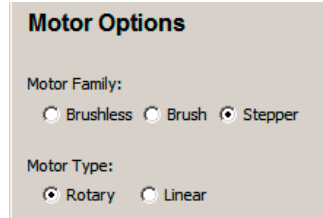
BRUSH MOTORS

The drive outputs are an H-bridge PWM inverter that convert the DC bus voltage (+HV) into DC voltage waveforms that drive the motor (+) & (-) terminals. Cable should be sized for the continuous current rating of the drive. Motor cabling should use twisted, shielded conductors for CE compliance, and to minimize PWM noise coupling into other circuits. The motor cable shield should connect to motor frame and the drive HV ground terminal for best results.



HOW IT LOOKS IN CME2

CME2 -> Basic Setup -> Motor Options

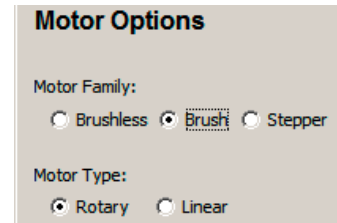


SIGNALS & PINS

Output	Motor	Axis A	Axis B	Axis C	Axis D
		J2 Pins	J2 Pins	J2 Pins	J2 Pins
Mot A	A	18	26	34	42
Mot /A	/A	17	25	33	41
Mot B	B	16	24	32	40
Mot /B	/B	15	23	31	39
+HV		1,2,3,4			
0V		5,6,7,8			
+AuxHV		9			

HOW IT LOOKS IN CME2

CME2 -> Basic Setup -> Motor Options



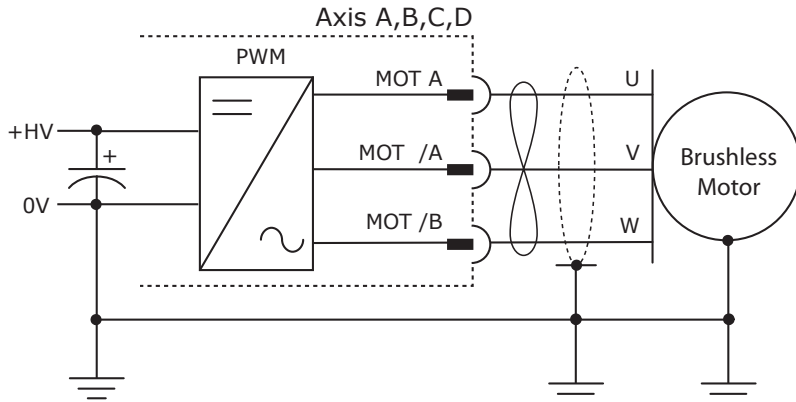
SIGNALS & PINS

Output	Motor	Axis A	Axis B	Axis C	Axis D
		J2 Pins	J2 Pins	J2 Pins	J2 Pins
Mot /A	(+)	17	25	33	41
Mot /B	(-)	15	23	31	39
+HV		1,2,3,4			
0V		5,6,7,8			
+AuxHV		9			

MOTOR CONNECTIONS

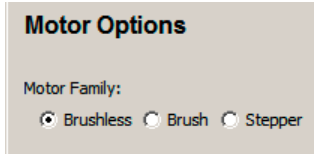
BRUSHLESS MOTORS

The drive outputs are a 3-phase PWM inverter that converts the DC bus voltage (+HV) into sinusoidal voltage waveforms that drive the motor U-V-W terminals. Cable should be sized for the continuous current rating of the drive. Motor cabling should use twisted, shielded conductors for CE compliance, and to minimize PWM noise coupling into other circuits. The motor cable shield should connect to motor frame and the drive HV ground terminal for best results.



HOW IT LOOKS IN CME2

CME2 -> Basic Setup -> Motor Options



SIGNALS & PINS

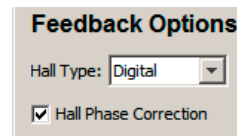
Output	Motor	Axis A	Axis B	Axis C	Axis D
		J2 Pins	J2 Pins	J2 Pins	J2 Pins
Mot A	U	18	26	34	42
Mot /A	V	17	25	33	41
Mot /B	/B	15	23	31	39
+HV		1,2,3,4			
0V		5,6,7,8			
+AuxHV		9			

DIGITAL HALL SIGNALS

Hall signals are single-ended signals that provide absolute feedback within one electrical cycle of the motor. There are three of them (U, V, & W) and they may be sourced by magnetic sensors in the motor, or by encoders that have Hall tracks as part of the encoder disc. They typically operate at much lower frequencies than the motor encoder signals, and are used for commutation-initialization after startup, and for checking the motor phasing after the servo drive has switched to sinusoidal commutation.

HOW IT LOOKS IN CME2

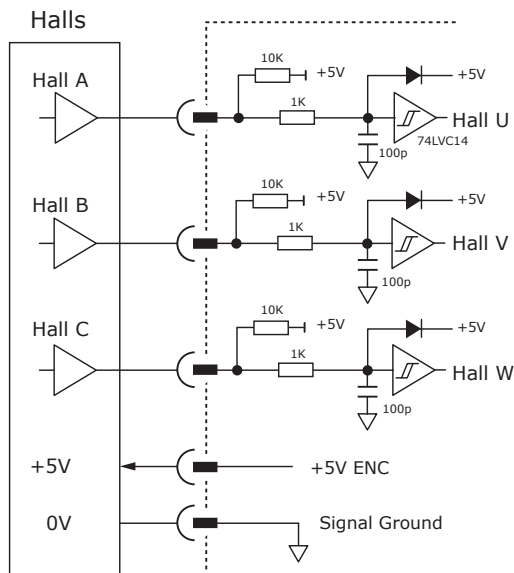
CME2 -> Basic Setup -> Feedback Options



Note: Hall phase correction is optional

HALL INPUTS

5V

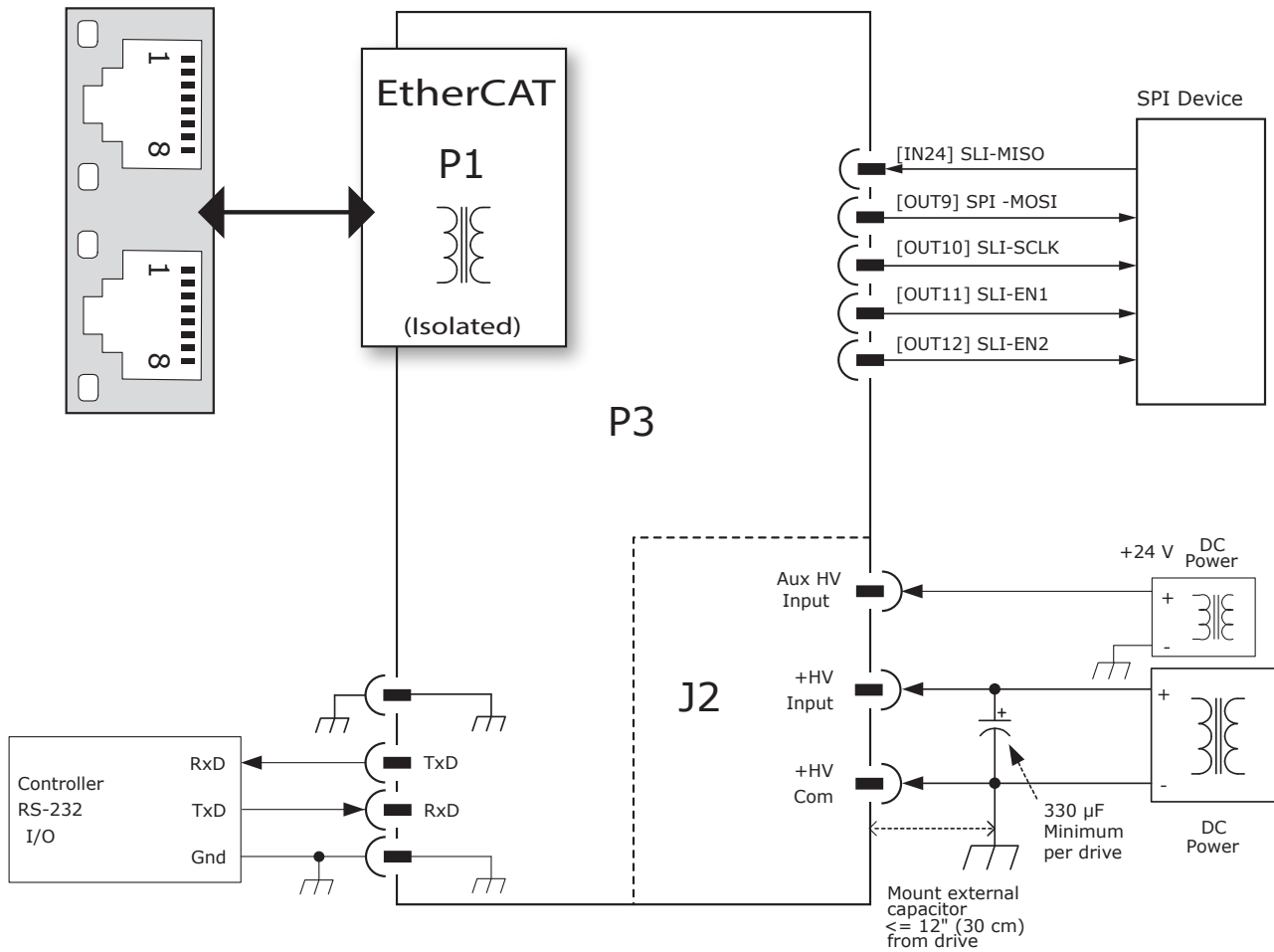


SIGNALS & PINS

Functions	Axis A		Axis B		Axis C		Axis D	
	P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal	P3 Pins	Signal
Hall U	16	[IN2]	22	[IN8]	28	[IN14]	34	[IN20]
Hall V	17	[IN3]	23	[IN9]	29	[IN15]	35	[IN21]
Hall W	18	[IN4]	24	[IN10]	30	[IN16]	36	[IN22]

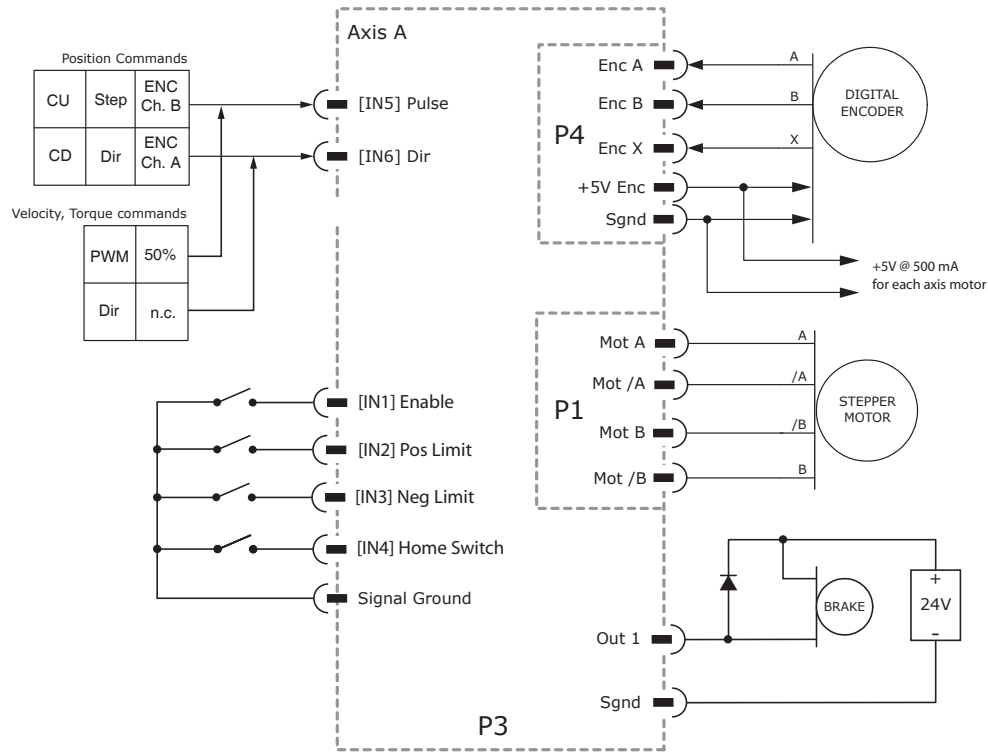
If these pins are not used for Hall signals, they can be programmed for other functions.

COMMON CONNECTIONS FOR ALL AXES



TYPICAL CONNECTIONS

Here is an example using a stepper motor with encoder feedback, driving a linear stage with positive and negative limit switches, and a home switch. Position commands are shown as digital inputs. For EtherCAT operation, these would not be used.



Axis A is shown as an example. The tables below show the pins for the same-named signals for axes B, C, and D.

INPUT SIGNALS & PINS

Functions					Axis A		Axis B		Axis C		Axis D	
					Pins	Signal	Pins	Signal	Pins	Signal	Pins	Signal
Enable					15	[IN1]	21	[IN7]	27	[IN13]	33	[IN19]
Positive Limit Switch					16	[IN2]	22	[IN8]	28	[IN14]	34	[IN20]
Negative Limit Switch					17	[IN3]	23	[IN9]	29	[IN15]	35	[IN21]
Home Switch					18	[IN4]	24	[IN10]	30	[IN16]	36	[IN22]
Enc A	Pulse	CW	PWM	PWM 50%	19	[IN5]	25	[IN11]	31	[IN17]	37	[IN23]
Enc B	Dir	CCW	Polarity	n/a	20	[IN6]	26	[IN12]	32	[IN18]	38	[IN24]

Notes:

- 1) Inputs functions shown for [IN1], [IN7], [IN13], and [IN19] are the default functions. These inputs are programmable if not used for these functions.
- 2) The functions shown for [IN5~6], [IN11~12], [IN17~18] and [IN23~24] apply when they are used as digital command inputs for position control. These inputs are programmable if not used for these functions.
- 3) The functions shown for [IN2~4] are typical inputs. These inputs are programmable if not used for these functions.

ENCODER SIGNALS & PINS

Functions	Axis A	Axis B	Axis C	Axis D
	Pins	Pins	Pins	Pins
Enc A	1	2	7	8
Enc B	3	4	9	10
Enc X	5	6	11	12

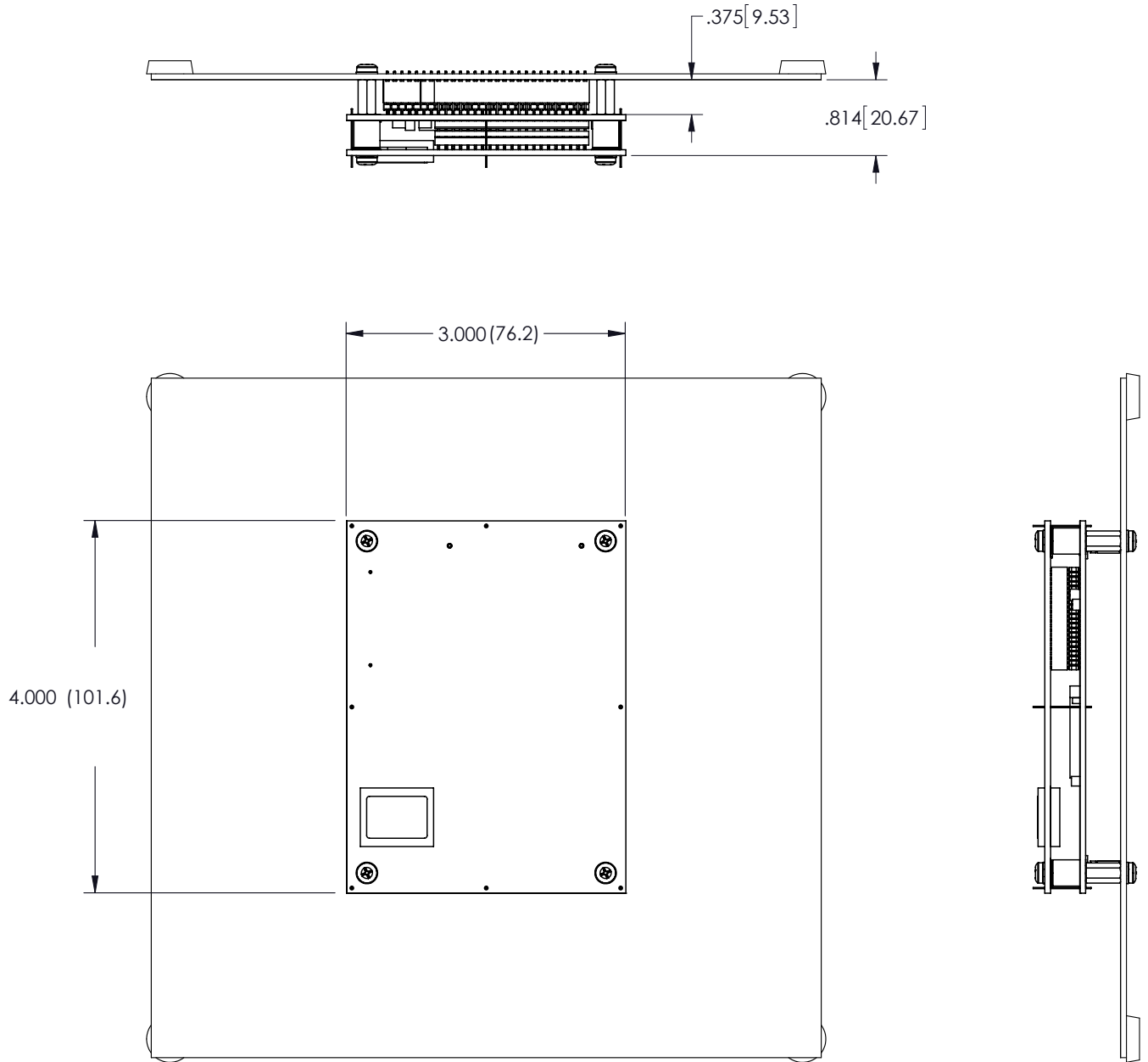
MOSFET OUTPUTS & PINS

Output	P3 Pin	Output	P3 Pin
[OUT1]	41	[OUT5]	45
[OUT2]	42	[OUT6]	46
[OUT3]	43	[OUT7]	47
[OUT4]	44	[OUT8]	48

The pins in these charts are on connector P3

MODULE DIMENSIONS

Units in inch (mm)

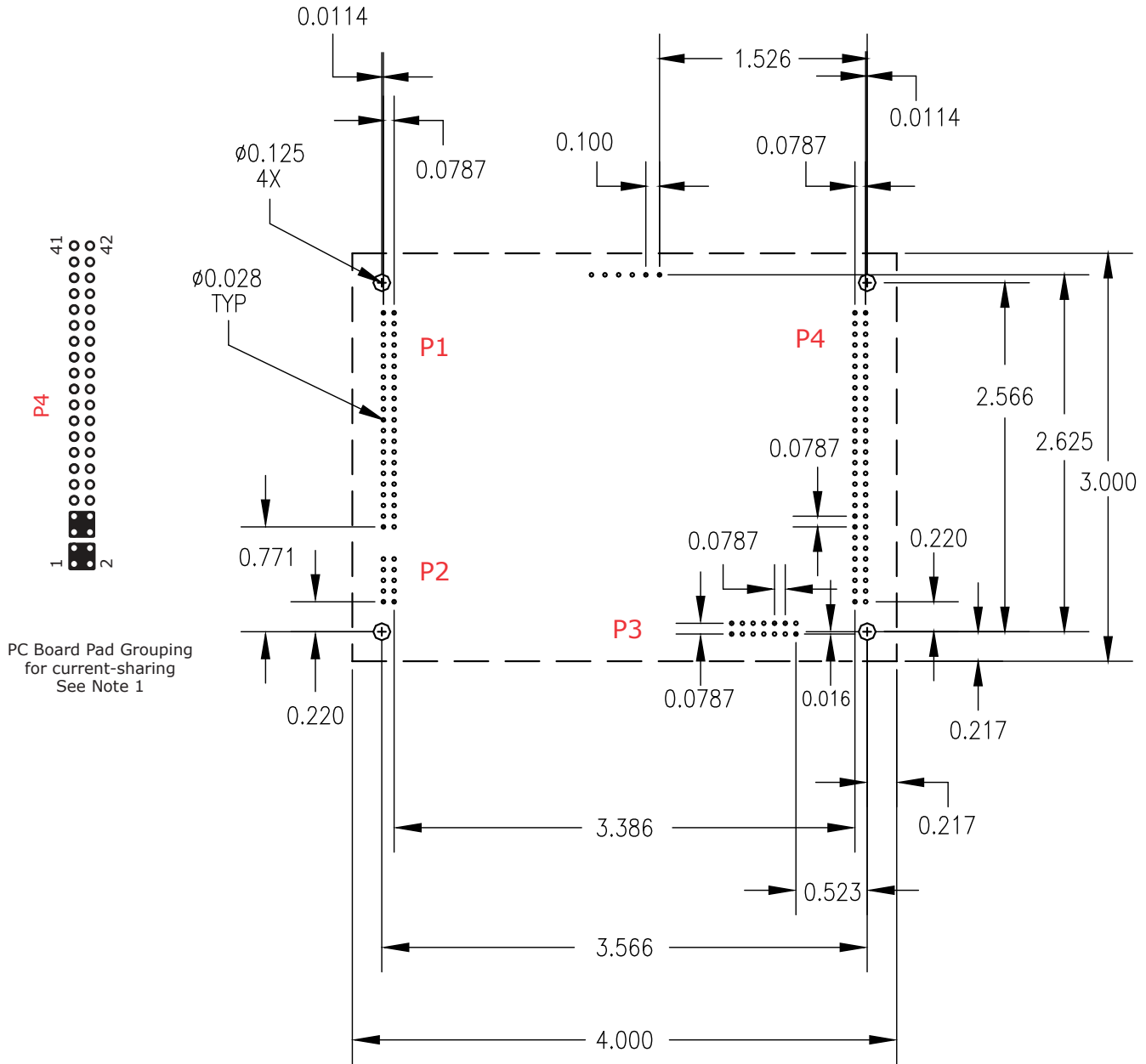


PRINTED CIRCUIT BOARD FOOTPRINT

Dimensions are inch (mm)

TOP VIEW

Viewed from above looking down on the connectors or PC board footprint to which the module is mounted



Mounting Hardware:

Qty	Description	Mfgr	Part Number	Remarks
1	Socket Strip	Samtec	SQW-121-01-L-D	P1: HV, Aux, & Motor
1	Socket Strip	Samtec	SQW-105-01-L-D	P2: SPI port
1	Socket Strip	Samtec	SQW-	P3: EtherCAT
1	Socket Strip	Samtec	SQW-128-01-L-D	P4: Input/Output
2	Standoff 6-32 X 1/4"	PEM	KFE-632-8ET	

Notes

1. P1 signals of the same name must be connected for current-sharing (see graphic above).
2. To determine copper width and thickness for P1 signals refer to specification IPC-2221. (Association Connecting Electronic Industries, <http://www.ipc.org>)

MOUNTING PC BOARD CONNECTORS & SIGNALS

P4 POWER

Mounting board connector:
Samtec SQW-121-01-L-D

Axis	Signal	Pin	Signal	Axis
D	Mot /A	41	42	Mot A
	Mot /B	39	40	Mot B
No connections		37	38	No connections
		35	36	
C	Mot /A	33	34	Mot A
	Mot /B	31	32	Mot B
No connections		29	30	No connections
		27	28	
B	Mot /A	25	26	Mot A
	Mot /B	23	24	Mot B
No connections		21	22	No connections
		19	20	
A	Mot /A	17	18	Mot A
	Mot /B	15	16	Mot B
No connections		13	14	No connections
		11	12	
HVaux		9	10	
HV Gnd		7	8	HV Gnd
		5	6	
+HV		3	4	+HV
		1	2	

P2 SPI PORT

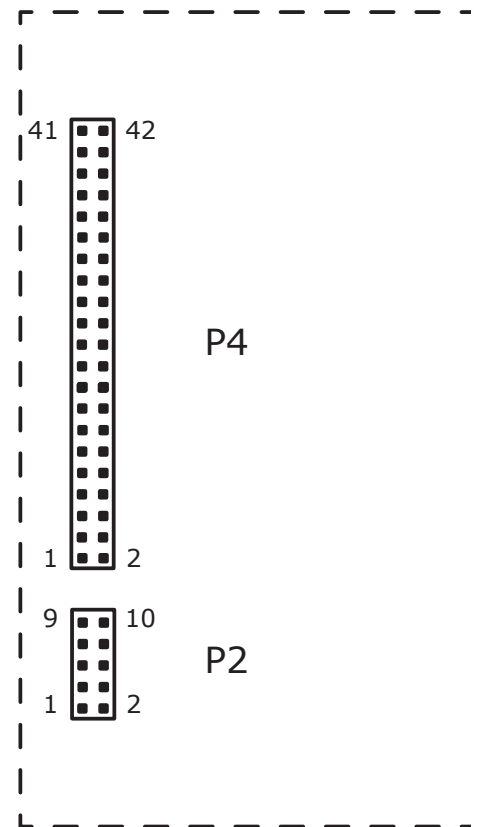
Mounting board connector:
Samtec SQW-105-01-L-D

Signal	Pin	Signal
SPI-MISO	9	10
Sgnd	7	8
Sgnd	5	6
+5V-ENC	3	4
Sgnd	1	2

Signal names in this chart are default settings that configure the port for the SPI function. If the SPI function is not used, the input and outputs on P2 are programmable for other functions.

TOP VIEW

Viewed from above looking down on the connectors or PC board footprint to which the module is mounted



CONNECTOR NAMING (P1, P2, ETC) APPLIES TO THE ME4 MODULE AND NOT TO PC BOARD MOUNTED SOCKETS

P3 INPUT/OUTPUT

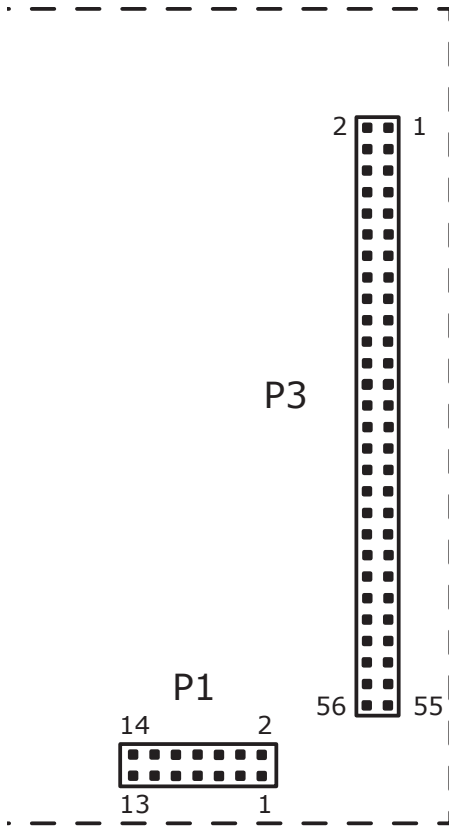
Mounting board connector:
Samtec SQW-128-01-L-D

Signal	Pin		Signal
ENC-A Axis-B	2	1	Axis-A ENC-A
ENC-B Axis-B	4	3	Axis-A ENC-B
ENC-X Axis-B	6	5	Axis-A ENC-X
ENC-A Axis-D	8	7	Axis-C ENC-A
ENC-B Axis-D	10	9	Axis-C ENC-B
ENC-X Axis-D	12	11	Axis-C ENC-X
ENC5V	14	13	Signal Gnd
Axis-A Hall-U [IN2]	16	15	[IN1] Axis-A Enable
Axis-A Hall-W [IN4]	18	17	[IN3] Axis-A Hall-V
Axis-A Dir [IN6]	20	19	[IN5] Axis-A Pulse
Axis-B Hall-U [IN8]	22	21	[IN7] Axis-B Enable
Axis-B Hall-W [IN10]	24	23	[IN9] Axis-B Hall-V
Axis-B Dir [IN12]	26	25	[IN11] Axis-B Pulse
Axis-C Hall-U [IN14]	28	27	[IN13] Axis-C Enable
Axis-C Hall-W [IN16]	30	29	[IN15] Axis-C Hall-V
Dir Axis-C [IN18]	32	31	[IN17] Axis-C Pulse
Axis-D Hall-U [IN20]	34	33	[IN19] Axis-D Enable
Axis-D Hall-W [IN22]	36	35	[IN21] Axis-D Hall-V
Axis-D Dir [IN24]	38	37	[IN23] Axis-D Pulse
Signal Gnd	40	39	Signal Gnd
MOSFET [OUT2]	42	41	[OUT1] MOSFET
MOSFET [OUT4]	44	43	[OUT3] MOSFET
MOSFET [OUT6]	46	45	[OUT5] MOSFET
MOSFET [OUT8]	48	47	[OUT7] MOSFET
Signal Gnd	50	49	Signal Gnd
RS-232 RxD	52	51	RS-232 TxD
Signal Gnd	54	53	N.C.
N.C.	56	55	N.C.

Signal names in this chart are default settings for brushless motors with Halls, position mode, and command source from digital inputs. Digital inputs [IN1~IN24] are programmable for other functions. Outputs [OUT1~OUT8] are programmable for other functions.

TOP VIEW

Viewed from above looking down on the connectors or PC board footprint to which the module is mounted



CONNECTOR NAMING (P1, P2, ETC) APPLIES TO THE ME4 MODULE AND NOT TO PC BOARD MOUNTED SOCKETS

P1 ETHERCAT PORT

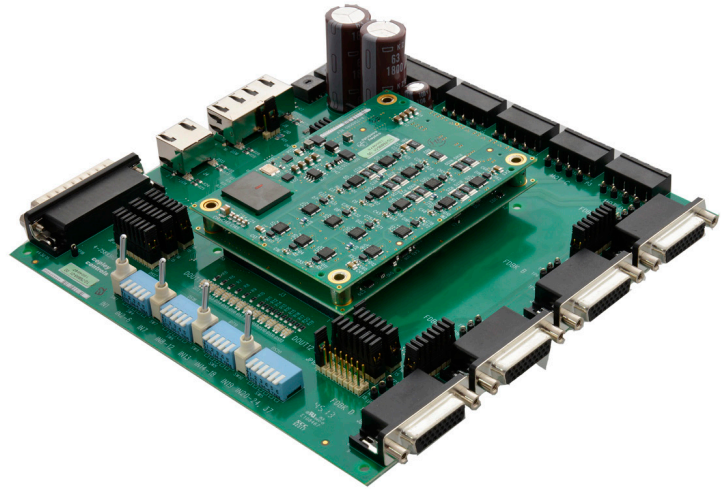
Signal	Pin		Signal
Shield	2	1	Shield
Tx2 Term	4	3	Tx2+
Tx1+	6	5	Tx2-
Tx1-	8	7	Tx1 Term
Rx2 Term	10	9	Rx2+
Rx1+	12	11	Rx2-
Rx1-	14	13	Rx1 Term

Mounting board connector:
Samtec SQW-107-01-L-D

DESCRIPTION

The Development Kit provides mounting and connectivity for one ME4 drive. Solderless jumpers ease configuration of inputs and outputs to support their programmable functions. Switches can be jumpered to connect to digital inputs 1~20 so that these can be toggled to simulate equipment operation. LED's provide status indication for the digital outputs, encoder A/B/X/S signals, and Hall signals. Test points are provided for these signals, too, making it easy to monitor these with an oscilloscope.

Dual EtherCAT connectors make daisy-chain connections possible so that other EtherCAT devices such as Copley's Accelnet Plus or Xenus Plus EtherCAT drives can easily be connected. Rotary switches are provided to set the EtherCAT slave Node-ID (address).



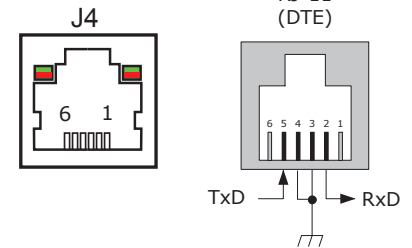
RS-232 CONNECTION

The RS-232 port is used to configure the drive for stand-alone applications, or for configuration before it is installed into an EtherCAT network. CME 2™ software communicates with the drive over this link and is then used for complete drive setup. The EtherCAT Node-ID that is set by the rotary switch can be monitored, and a Node-ID offset programmed as well.

The RS-232 connector, J8, is a modular RJ-11 type that uses a 6-position plug, four wires of which are used for RS-232. A connector kit is available (SER-CK) that includes the modular cable, and an adaptor to interface this cable with a 9-pin RS-232 port on a computer.

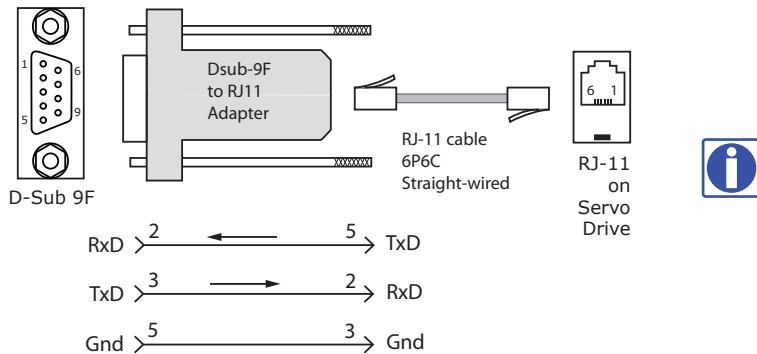
The LEDs on J4 are for the EtherCAT network status of Axis A & B, and are not associated with the RS-232 port function.

J8 SIGNALS



SER-CK SERIAL CABLE KIT

The SER-CK provides connectivity between a D-Sub 9 male connector and the RJ-11 connector J8 on the Development Kit. It includes an adapter that plugs into the COM1 (or other) port of a PC and uses common modular cable to connect to the XEL. The connections are shown in the diagram below.



Don't forget to order a Serial Cable Kit SER-CK when placing your order for an ME4 Development Kit!

INDICATORS (LEDS)

The AMP LEDs DS17~20 at switches SW1, 7, 9, and 10 show the operational state of each axis of the ME4. The STATUS LEDs on J9 & J4 show the state of the EtherCAT NMT (Network Management) state-machines of each axis in the drive. Details on the NMT state-machine can be found in the EtherCAT Programmers Manual, §3.1: <http://www.copleycontrols.com/Motion/pdf/EtherCATProgrammersManual.pdf>

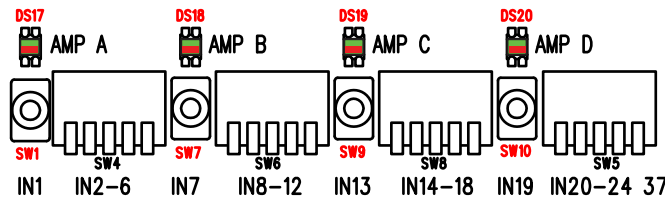
AMP LEDS

Four bi-color LEDs show the states of each axis of the ME4 by changing color, and either blinking or remaining solid. The possible color and blink combinations are:

- *Green/Solid:* Drive OK and enabled. Will run in response to reference inputs or EtherCAT commands.
- *Green/Slow-Blinking:* Drive OK but NOT-enabled. Will change to *Green/Solid* when enabled.
- *Green/Fast-Blinking:* Positive or Negative limit switch active. Drive will only move in direction not inhibited by limit switch.
- *Red/Solid:* Transient fault condition. Drive will resume operation when fault is removed.
- *Red/Blinking:* Latching fault. Operation will not resume until drive is Reset.

Drive Fault conditions. Faults are programmable to be either transient or latching:

- Over or under-voltage
- Motor over-temperature
- Encoder +5 Vdc fault
- Short-circuits from output to ground
- Drive over-temperature
- Internal short circuits
- Short-circuits from output to output



STATUS LEDS

Four bi-color LEDs on J9 & J4 give the state of the NMT state-machine of each axis by changing color, and either blinking or remaining solid. The possible color and blink combinations are:

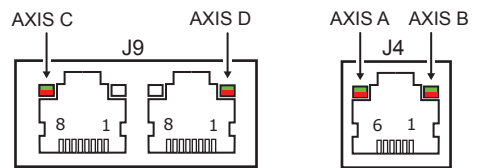
RUN (GREEN)

- Off *Init*
- Blinking *Pre-operational*
- Single-flash *Stopped*
- On *Operational*

ERROR (RED)

- Off *No error*
- Blinking *Invalid configuration, general configuration error*
- Single Flash *Warning limit reached*
- Double Flash *Error Control Event (guard or heartbeat event) has occurred*
- Triple Flash *Sync message not received within the configured period*
- On *Bus Off, the CAN master is bus off*

NETWORK STATUS LEDS



Note: Red & green led on-times do not overlap. LED color may be red, green, off, or flashing of either color.

EtherCAT Node ID (ADDRESS)

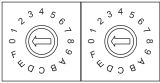
On a EtherCAT network, each device must have unique, non-zero Node-ID. In the ME4 DevKit, this is provided by two 16-position rotary switches with hexadecimal encoding. These can set the Node-ID of the drive's Axis A from 0x01~0xFF (1~255 decimal). The chart shows the decimal values of the hex settings of each switch.

Example 1: Find the switch settings for decimal Node-ID 107 (0x6B):

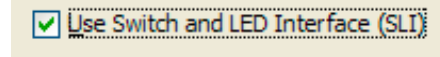
- 1) Find the highest number under SW21 that is less than 107 and set SW21 to the hex value in the same row: 96 < 107 and 112 > 107, so SW21 = 96 = Hex 6
- 2) Subtract 96 from the desired Node-ID to get the decimal value of switch SW22 and set SW22 to the Hex value in the same row: SW22 = (107 - 96) = 11 = Hex B
- 3) This example will produce the following CAN addresses for the ME4:
Axis A = 107 (0x6B), Axis B = 108 (0x6C), Axis C = 109 (0x6D), Axis D = 110 (0x6E)

CME2 -> Amplifier -> Network Configuration

SW2 SW3

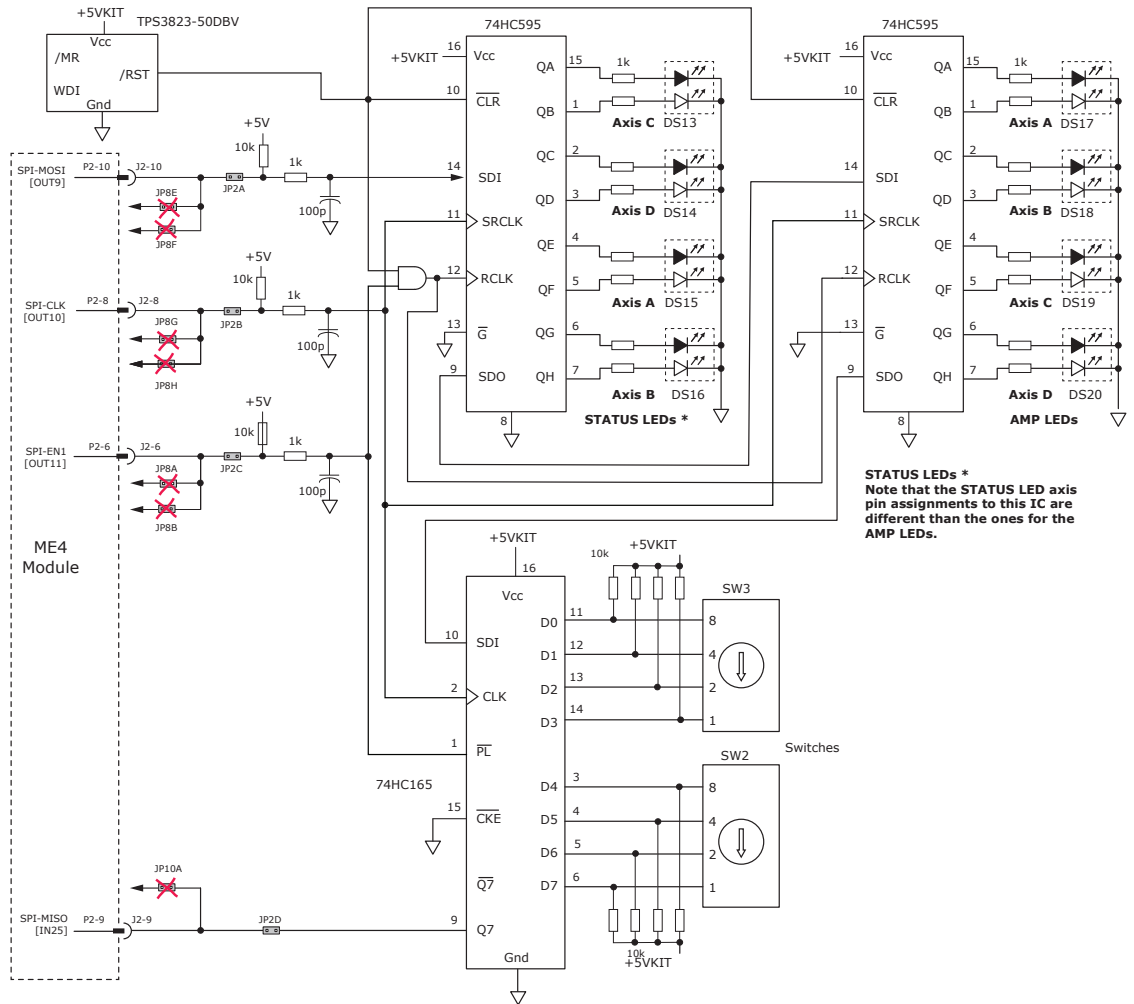


CME2 -> Input/Output -> Digital Outputs



EtherCAT Node-ID Switch Decimal values

HEX	SW2	SW3
0	0	0
1	16	1
2	32	2
3	48	3
4	64	4
5	80	5
6	96	6
7	112	7
8	128	8
9	144	9
A	160	10
B	176	11
C	192	12
D	208	13
E	224	14
F	240	15



STATUS LEDs *
Note that the STATUS LED axis pin assignments to this IC are different than the ones for the AMP LEDs.

EtherCAT NODE-ID (ADDRESS) SWITCH CONNECTIONS

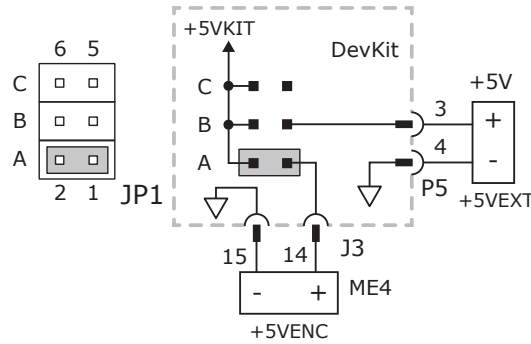
This graphic shows the connections to the EtherCAT Node-ID switches and to the status LEDs for the ME4 and EtherCAT. The switches are read once after the drive is reset, or powered-on. When changing the settings of the switches, be sure to either reset the drive, or to power it off-on. Outputs [OUT4,5,6] and input [IN18] operate as an SPI (Switch & LED Interface) port which reads the settings on the EtherCAT Node-ID switches, and controls the LEDs on the serial and EtherCAT port connectors.

The jumpers marked with red "X" should be removed so that SW18, or external connections to the signals do not interfere with the operation of the SPI port.

+5V POWER

The encoder +5VENC power on the feedback connectors J5~J8 is connected directly to the +5VENC power output from the ME4.

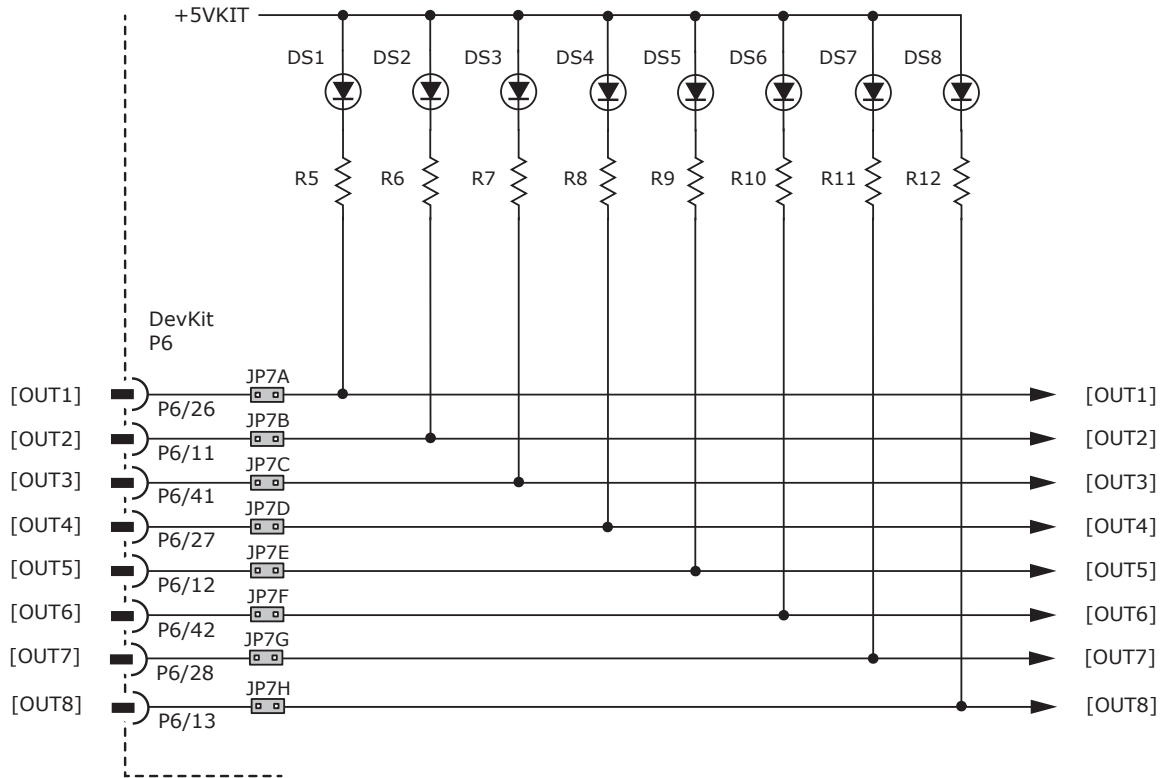
The SPI port components on the DevKit that drive the LEDs and read the Node-ID (address) switches connects to the signal +5VKIT. And the +5VKIT connects to a jumper on JP1 that selects source of the +5V power. This can be powered from either the +5VENC power from the ME4, or from an external +5V power supply that connects to P5-3. The default "A" position (on JP1 pins 1~2) selects the +5VENC from the ME4 as the power source for the +5VKIT. Moving the jumper to the "B" position (pins 3~4) selects the external +5V power source for +5VKIT. As noted below, only one jumper should be used to select the source of power for +5VKIT.



**IMPORTANT: ONLY ONE SHORTING PLUG CAN BE USED ON JP1-A or JP1-B POSITIONS
USE OF MORE THAN ONE PLUG WILL DAMAGE 5V POWER SUPPLIES IN THE ME4**

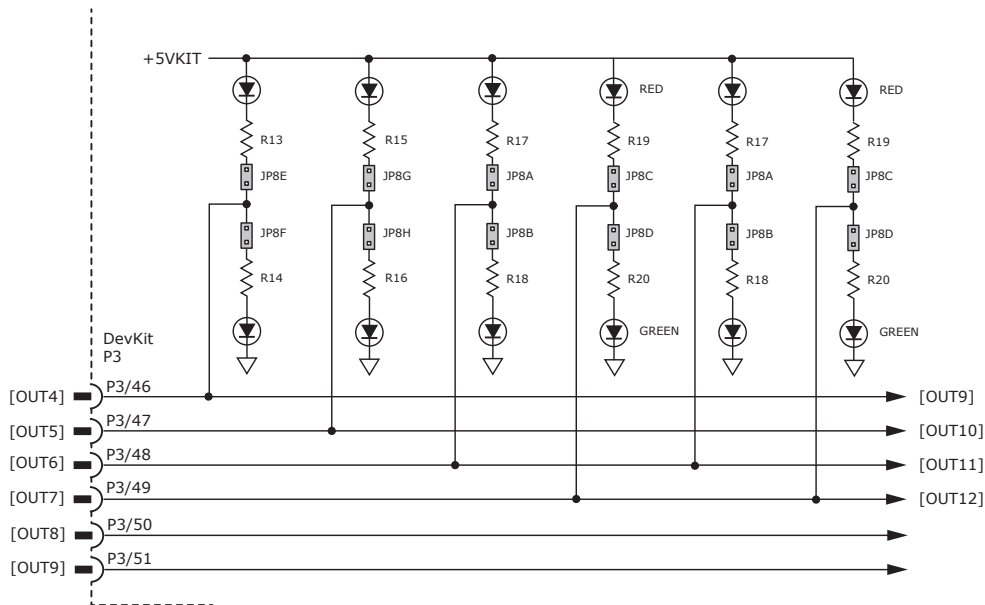
MOSFET OUTPUTS

There are eight MOSFET outputs that can drive controller logic inputs or relays. If relays are driven, then flyback diodes must be connected across their terminals to clamp overvoltages that occur when the inductance of the relay coil is suddenly turned off. LED indicators connected to the outputs will be ON when the output is MOSFET is ON and the output voltage will be near 0V. Outputs 1,2, & 3 are MOSFET types that sink current when ON, and appear as open-circuit when OFF. When these outputs are ON a red LED is turned on. When the outputs are OFF, the red LED is off. The green LED is not used on these outputs.



LOGIC OUTPUTS

Outputs 9~12 are CMOS types that pull up to 5V or down to ground. When these outputs go high it turns on the green LED. When they are low, the red LED is turned on.

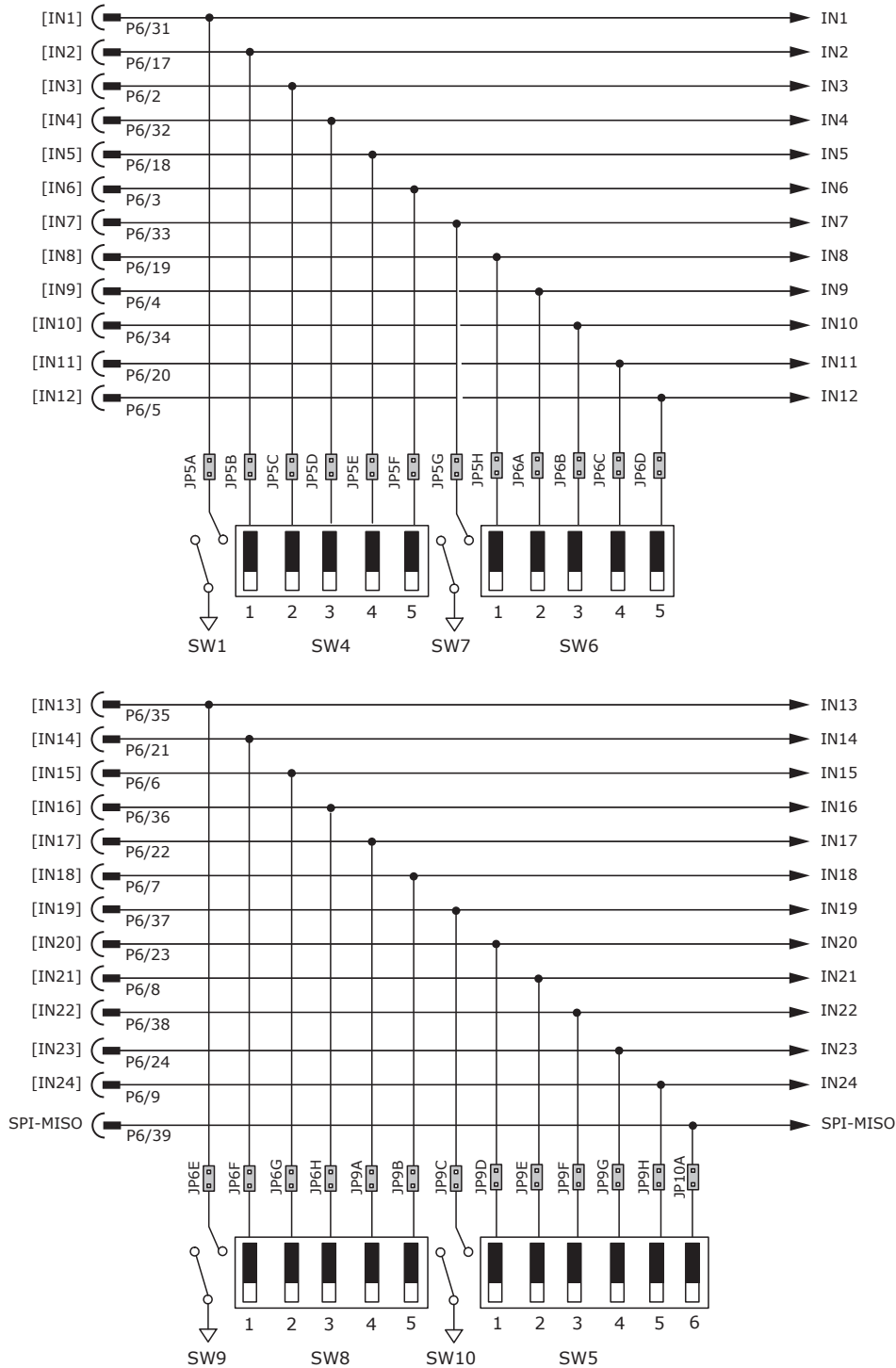


LOGIC INPUTS & SWITCHES

The Development Kit has jumpers that can connect the ME4 digital inputs to switches on the kit, or to the Signal connector J6.

As delivered, all of these jumpers are installed as shown. If connecting to external devices that actively control the level of an input, it is desirable to disconnect the switch which could short the input to ground.

For example, if [IN1] is connected to an external device for the Enable function, then jumper JP5A should be removed to take the switch SW1 out of the circuit. The figure below shows these connections.



DEVELOPMENT KIT CONNECTORS

The Development Kit mounts a single ME4 module and enables the user to test and operate the ME4 before it is mounted onto a PC board in the target system.

J5 J6 J7 J8
 AXIS A AXIS B AXIS C AXIS D FEEDBACK

PIN	SIGNAL	PIN	SIGNAL	PIN	SIGNAL
26	Signal Gnd	18	n.c.	9	Enc X
25	Signal Gnd	17	+5VENC	8	n.c.
24	n.c.	16	Signal Gnd	7	n.c.
23	n.c.	15	n.c.	6	+5VENC
22	n.c.	14	n.c.	5	Signal Gnd
21	n.c.	13	Enc A	4	Table 1 (below)
20	n.c.	12	n.c.	3	
19	n.c.	11	Enc B	2	
		10	n.c.	1	Frame Gnd

TABLE 1

This shows the signals connected to these pins on the axis feedback connectors J5~J8. The jumpers connect these pins to signals in the ME4.

Pin	Axis A	Axis B	Axis C	Axis D
2	IN2	JP4-A	IN8	JP4-E
3	IN3	JP4-B	IN9	JP4-F
4	IN4	JP4-C	IN10	JP4-G
7	IN5	JP4-D	IN11	JP4-H

P4: AXIS D MOTOR
 P3: AXIS C MOTOR
 P2: AXIS B MOTOR
 P1: AXIS A MOTOR

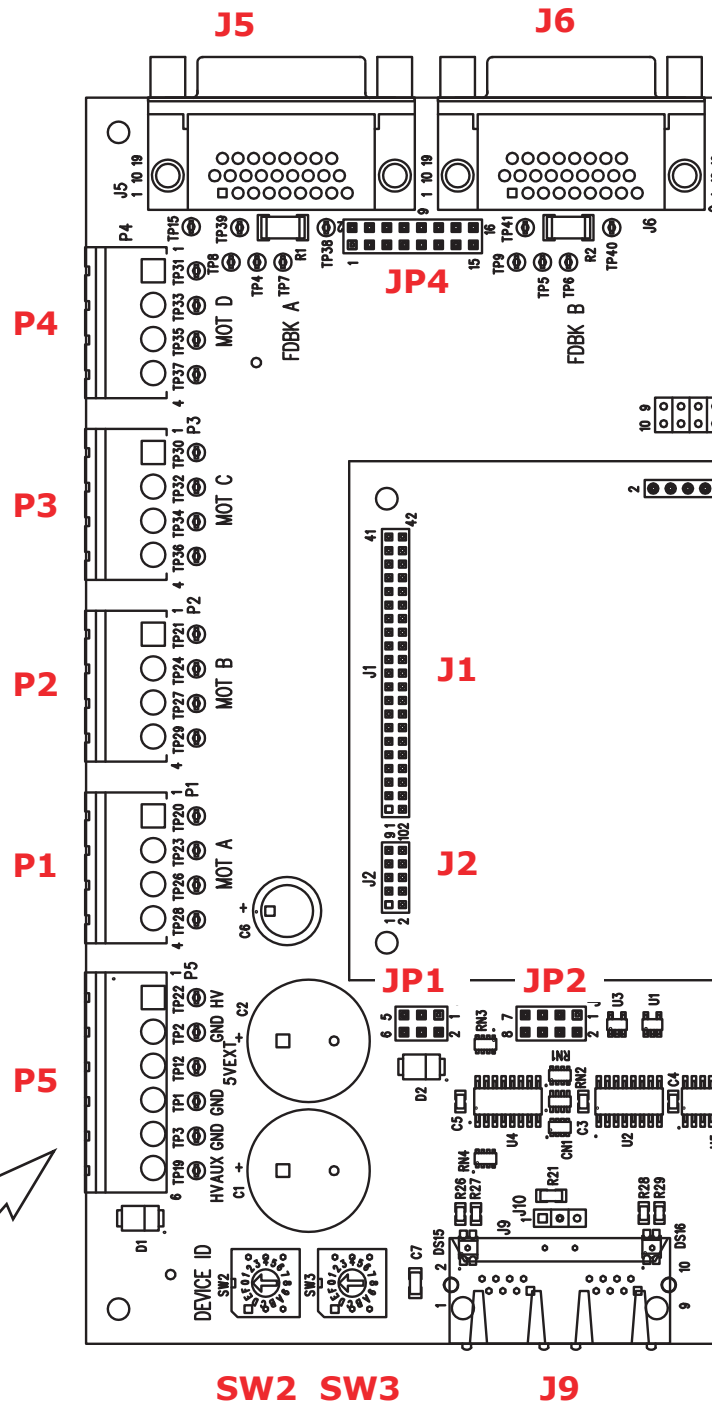
Connector, Euro, 4 Terminal, 5.08 mm

Signal	Pin
Motor A	1
Motor /A	2
Motor B	3
Motor /B	4

P5: HV, AUX, GND

Connector, Euro, 5 Terminal, 5.08 mm

Signal	Pin
+HV	1
HV Gnd	2
+5V Ext	3
Sgnd	4
HV Gnd	5
HV Aux	6



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MASTER ORDERING GUIDE

ME4-055-03	M4 Plus ME4 Stepper and Servo drive, 3/3A, 14~55 Vdc
MEK-055-04	Development Kit for M4 Plus ME4



ACCESSORIES

	QTY	Ref	Name	DESCRIPTION
Connector Kit for Development Kit MEK-CK-04	1	P5	+HV & Aux	Connector, Euro, 6 Terminal, 5.08 mm
	4	P1~P4	Motor	Connector, Euro, 4 Terminal, 5.08 mm
	1	P6	Control	44 Pin Connector, High Density, D-Sub, Female, Solder Cup
				44 Pin Connector Backshell
	4	J5~J8	Feedback	26 Pin Connector, High Density, D-Sub, Male, Solder Cup
4	26 Pin Connector Backshell			
SER-CK		J4	RS-232	Serial Cable Kit

16-01547 Document Revision History

Revision	Date	Remarks
00	July 28, 2016	Initial released version

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Note: Specifications subject to change without notice