

# **7I77/7I77D SIX AXIS ANALOG SERVO PLUS I/O DAUGHTERCARD**

V1.17

## **CAUTION!**

**The 7177s intended application is interfacing large servo motors. Servo motors are capable of inflicting serious injury both to people and mechanisms associated with the servo system. In addition, some motors use potentially lethal supply voltages.**

**When a servo system is first configured, unpredictable behavior should be EXPECTED. First time checks of basic servo operation (such as motor position versus analog output drive) should be done with the motor power leads disconnected.**

**NEVER depend on software commands to disable a motor when you or others would be exposed to a hazard should the motor start unexpectedly. Motor power should be always be removed when working on mechanical parts of the servo system.**

**Be especially careful with encoder wiring, as a simple bad connection of one encoder wire can lead to total loss of control and a runaway servo system.**

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# GENERAL

## DESCRIPTION

The 7177/7177D are daughtercard/breakout boards for use with MESA's 25 pin I/O FPGA cards like the 5125 and 7192. The 7177 is designed for interfacing up to 6 Axis of analog servo motor drives and also provides 48 isolated I/O points for general purpose field I/O use.

Six +-10V analog outputs and six encoder inputs (all with index) are provided for servo interfacing. Six floating drive enable outputs allow control of active high or active low drive enables. Encoder inputs can be individually set for differential or single ended mode.

48 points of isolated field I/O are provided for general control use including limit switch, control panel inputs, coolant enable and tool changer control outputs. Isolated I/O includes 32 sinking inputs and 16 sourcing (7177) or sinking (7177D) outputs. Inputs can sense 5V to 32V signals and the outputs can switch 5V through 28V signals. Maximum output load is 300 mA. Outputs are short circuit protected. Field I/O is powered by an isolated 10-32V field power source.

One RS-422 interface is provided for I/O expansion via a serial I/O daughtercard. All field wiring is terminated in pluggable 3.5 mm screw terminal blocks.

*Unless the 7177D is mentioned specifically, all information in this manual applies to both the 7177 and 7177D*

# HARDWARE CONFIGURATION

## GENERAL

Hardware setup jumper positions assume that the 7177 card is oriented in an upright position, that is, with the host interface DB25 connector pointing towards the left.

## VIN POWER SOURCE

The isolated field I/O on the 7177 runs from a switching power supply that can be powered by field power or a separate supply (VIN) with ground common with field power. Normally the 7177's VIN will be powered with field power. An on card jumper, W1 allows VIN to be connected to field power. If you wish to use a single power supply for the 7177's field outputs and field logic power, W1 should be placed in the left hand position. This connects field power to VIN. If you wish to use a separate supply for VIN, W1 should be placed in the right hand position. .

## CABLE 5V POWER

The 7177 can get its logic power from the host FPGA card or from TB1. W5 determines if the 7177 gets its 5V logic power from the host FPGA card or TB1.

If W5 is in the left hand position, host FPGA power is used and the host FPGA card must be jumpered to supply 5V to the daughtercard.

If W5 is in the right hand position, 5V power must be supplied to the 7177 via TB1 and the 7177 grounds the 4 DB25 signals used for host 5V power. In this case the FPGA card must be jumpered so that it does **not** supply power to the daughtercard.

***Never apply external 5V power to TB1 when W5 is in the left hand position or you may damage the 7177, FPGA card, PC, or connecting cable.***

## SETUP/OPERATE MODE

The 7177 field I/O and Analog output processors can run in setup mode or operate mode. In setup mode, the serial interface baud rate is fixed at 115.2 KBaud. In the operate mode, the baud rate is set to 2.5M baud (default). Setup mode is also less critical of host interface timing and enables a normal PC to communicate with the 7177 for setup and firmware update purposes. W4 controls the setup/operate mode selection for the Analog processor and W12 controls the setup/operate mode selection for the isolated field I/O processor. The jumpers **must** be in the "operate" mode for normal operation.

W4,W12	MODE	BAUD RATE
LEFT	Operate mode	2.5M baud (default, can be changed)
RIGHT	Setup Mode	115.2K baud (fixed)



# HARDWARE CONFIGURATION

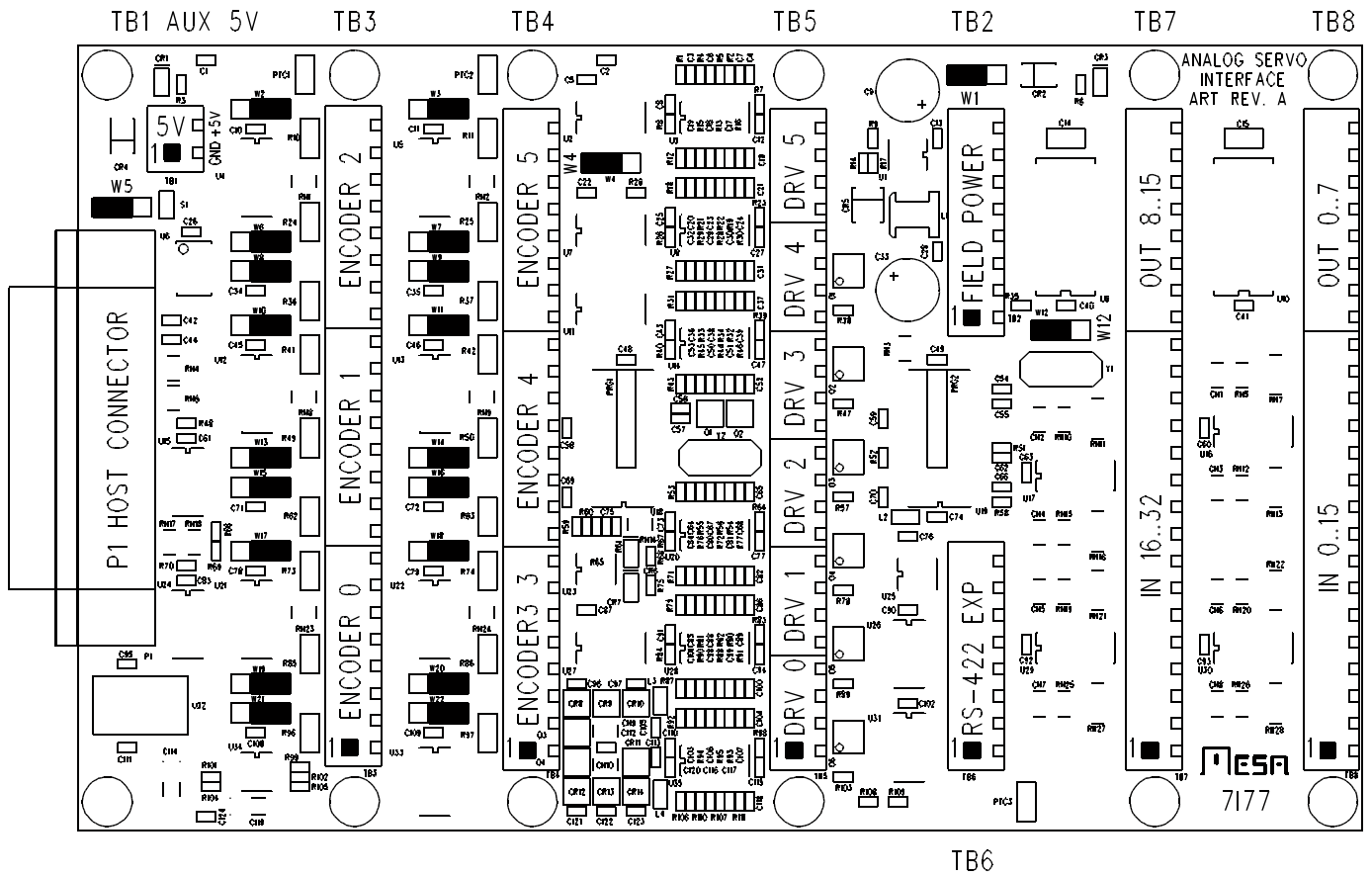
## ENCODER INPUT MODES

The 7177s six encoder inputs can be programmed for differential or single ended mode operation. Each encoder has 3 jumpers which set the input mode of the individual A/B/Z inputs. Normally these jumper will all be set to single ended or differential on a single encoder channel. The jumpers are set to the right hand position for differential inputs and the left hand position for single ended inputs. Note that the groups of three jumpers are close to the associated encoder connector. Default setting is differential (right hand position) for all encoders.

<b>ENCODER</b>	<b>A</b>	<b>B</b>	<b>Z</b>
0	W21	W19	W17
1	W15	W13	W10
2	W8	W6	W2
3	W22	W20	W18
4	W16	W14	W11
5	W9	W7	W3

# CONNECTORS

## 7177 CONNECTOR LOCATIONS AND DEFAULT JUMPER POSITIONS



Note: Terminal block pin 1s are marked with a square

# CONNECTORS

## P1 HOST INTERFACE CONNECTOR

P1 is the DB25F connector on the 7I77 that connects to the FPGA card. Actual pin functions depend on FPGA configuration but signal directions must be observed.

DB25 PIN	GPIO	FUNCT	DIR	DB25 PIN	GPIO	FUNC	DIR
1	IO0	SS2TXEN	OUT	14	IO1	SS2TX	OUT
2	IO2	SS2RX	IN	15	IO3	SS1TX	OUT
3	IO4	SS1RX	IN	16	IO5	SS0TX	OUT
4	IO6	SS0RX	IN	17	IO7	ENCMUX	OUT
5	IO8	QCMUXA01	IN	18		GND	
6	IO9	QCMUXB01	IN	19		GND	
7	IO10	QCMUXI01	IN	20		GND	
8	IO11	QCMUXA23	IN	21		GND	
9	IO12	QCMUXB23	IN	22		GND or 5V	
10	IO13	QCMUXI23	IN	23		GND or 5V	
11	IO14	QCMUXA45	IN	24		GND or 5V	
12	IO15	QCMUXB45	IN	25		GND or 5V	
13	IO16	QCMUXI45	IN				

Notes:

1. If jumper W5 is in the left hand position, pins 22 through 25 are 5V, if W5 is in the right hand position, Pins 22 through 25 are GND.
2. GPIO pins are for first FPGA connector, next connector series begins at GPIO17.
3. Signal directions are relative to FPGA card, that is, an 'OUT' signal is an output from the FPGA card that drives the 7I77. Conversely an 'IN' signal is a FPGA input that is driven by the 7I77.

# CONNECTORS

## TB1 AUX 5V CONNECTOR

TB1 supplies 5V analog, encoder, and RS-422 interface power to the 7177. If the cable power option is used, TB1 may remain unconnected. If the cable power option is not used TB1 must be used to supply 5V power to the 7177.

When TB1 is used with an external 5V supply (not 5V from the host PC) , W5 must be in the right-hand position to avoid back-powering the host computer via the host interface card. TB1 is a two pin 3.5 MM pluggable terminal block supplied one two pin removable screw terminal plug. TB1 pinout is as follows:

TB1 PIN	SIGNAL
1	GND
2	5V

## TB2 FIELD POWER

TB2 is the 7177s field power connector. TB2 is a eight pin 3.5 MM pluggable terminal block supplied one eight pin removable screw terminal plugg. TB2 pinout is as follows:

TB2 PIN	SIGNAL	FUNCTION
1	VFIELD	FIELD POWER 8-32V (Bottom pin)
2	VFIELD	FIELD POWER 8-32V
3	VFIELD	FIELD POWER 8-32V
4	VFIELD	FIELD POWER 8-32V
5	VIN	FIELD I/O LOGIC POWER 8-32V
6	NC	
7	NC	
8	GROUND	VIN, VFIELD, COMMON (Top pin)

Note: When W1 is in the default left hand position, VIN is connected to VFIELD, so only VFIELD need be supplied to the 7177 to power its field IO.

# CONNECTORS

## TB3 ENCODER 0 THROUGH 2

TB3 is the 7I77s encoder 0 through 2 connector. Each encoder interface uses 8 pins TB3 is a 24 pin 3.5 MM pluggable terminal block with supplied with three eight pin removable screw terminal plugs.

TB3 PIN	FUNCTION	DIR
1	QA0	TO 7I77
2	/QA0	TO 7I77
3	GND	FROM 7I77
4	QB0	TO 7I77
5	/QB0	TO 7I77
6	+5V	FROM 7I77
7	IDX0	TO 7I77
8	/IDX0	TO 7I77
9	QA1	TO 7I77
10	/QA1	TO 7I77
11	GND	FROM 7I77
12	QB1	TO 7I77
13	/QB1	TO 7I77
14	+5V	FROM 7I77
15	IDX1	TO 7I77
16	/IDX1	TO 7I77
17	QA2	TO 7I77
18	/QA2	TO 7I77
19	GND	FROM 7I77
20	QB2	TO 7I77
21	/QB2	TO 7I77
22	+5V	FROM 7I77
23	IDX2	TO 7I77
24	/IDX2	TO 7I77

# CONNECTORS

## TB4 ENCODER 3 THROUGH 5

TB4 is the 7I77s encoder 3 through 5 connector. Each encoder interface uses 8 pins. TB4 is a 24 pin 3.5 MM pluggable terminal block supplied with three eight pin removable screw terminal plugs.

TB4 PIN	FUNCTION	DIR
1	QA3	TO 7I77
2	/QA3	TO 7I77
3	GND	FROM 7I77
4	QB3	TO 7I77
5	/QB3	TO 7I77
6	+5V	FROM 7I77
7	IDX3	TO 7I77
8	/IDX3	TO 7I77
9	QA4	TO 7I77
10	/QA4	TO 7I77
11	GND	FROM 7I77
12	QB4	TO 7I77
13	/QB4	TO 7I77
14	+5V	FROM 7I77
15	IDX4	TO 7I77
16	/IDX4	TO 7I77
17	QA5	TO 7I77
18	/QA5	TO 7I77
19	GND	FROM 7I77
20	QB5	TO 7I77
21	/QB5	TO 7I77
22	+5V	FROM 7I77
23	IDX5	TO 7I77
24	/IDX5	TO 7I77

# CONNECTORS

## TB5 ANALOG DRIVE INTERFACE

TB5 is the 7I77s analog drive interface connector. It has both the +-10V analog outputs and the drive enable connections. Each drive interface uses 4 pins. TB5 is a 24 pin 3.5 MM pluggable terminal block supplied with six four pin removable screw terminal plugs.

TB5 PIN	SIGNAL	DIRECTION
1	ENA0-	FROM 7I77
2	ENA0+	FROM 7I77
3	GND	FROM 7I77
4	AOUT0	FROM 7I77
5	ENA1-	FROM 7I77
6	ENA1+	FROM 7I77
7	GND	FROM 7I77
8	AOUT1	FROM 7I77
9	ENA2-	FROM 7I77
10	ENA2+	FROM 7I77
11	GND	FROM 7I77
12	AOUT2	FROM 7I77
13	ENA3-	FROM 7I77
14	ENA3+	FROM 7I77
15	GND	FROM 7I77
16	AOUT3	FROM 7I77
17	ENA4-	FROM 7I77
18	ENA4+	FROM 7I77
19	GND	FROM 7I77
20	AOUT4	FROM 7I77
21	ENA5-	FROM 7I77
22	ENA5+	FROM 7I77
23	GND	FROM 7I77
24	AOUT5	FROM 7I77

# CONNECTORS

## TB6 RS-422 INTERFACE

This interface is intended for I/O expansion with Mesa SSerial devices. The easiest way to make a cable for interfacing the 7177 to these devices is to take a standard CAT5 or CAT6 cable, cut it in half, and wire the individual wires to the 7177 screw terminals. The following chart gives the CAT5 to 7177 screw terminal connections (EIA/TIA 568B colors shown):

<b>TB6 PIN</b>	<b>SIGNAL</b>	<b>DIRECTION</b>	<b>CAT5 PIN</b>	<b>CAT5 568B COLOR</b>
1	GND	FROM 7177	4	BLUE
2	GND	FROM 7177	5	BLUE / WHITE
3	RX+	TO 7177	6	GREEN
4	RX-	TO 7177	3	GREEN / WHITE
5	TX+	FROM 7177	2	ORANGE
6	TX-	FROM 7177	1	ORANGE / WHITE
7	+5V	FROM 7177	7	BROWN / WHITE
8	+5V	FROM 7177	8	BROWN



# CONNECTORS

## FIELD INPUT/OUTPUT CONNECTORS

Terminal blocks TB8 and TB7 are the 7177s field input and output terminals. Inputs 0 through 15 and outputs 0 through 7 are terminated at TB8. Inputs 16 through 31 and outputs 8 through 15 are terminated at TB7. TB8 and TB7 are 3.5 MM pluggable terminal block with supplied removable screw terminal plugs. Pin one is at the bottom edge of the 7177 card.

### TB8 CONNECTOR PINOUT

TB8 PIN	I/O	TB8 PIN	I/O
1	INPUT0	13	INPUT12
2	INPUT1	14	INPUT13
3	INPUT2	15	INPUT14
4	INPUT3	16	INPUT15
5	INPUT4	17	OUTPUT0
6	INPUT5	18	OUTPUT1
7	INPUT6	19	OUTPUT2
8	INPUT7	20	OUTPUT3
9	INPUT8	21	OUTPUT4
10	INPUT9	22	OUTPUT5
11	INPUT10	23	OUTPUT6
12	INPUT11	24	OUTPUT7

# CONNECTORS

## FIELD INPUT/OUTPUT CONNECTORS

### TB7 CONNECTOR PINOUT

TB7 PIN	OUTPUT	TB7 PIN	OUTPUT
1	INPUT16	13	INPUT28
2	INPUT17	14	INPUT29
3	INPUT18	15	INPUT30
4	INPUT19	16	INPUT31
5	INPUT20	17	OUTPUT8
6	INPUT21	18	OUTPUT9
7	INPUT22	19	OUTPUT10
8	INPUT23	20	OUTPUT11
9	INPUT24	21	OUTPUT12
10	INPUT25	22	OUTPUT13
11	INPUT26	23	OUTPUT14
12	INPUT27	24	OUTPUT15

# OPERATION

## HOST INTERFACE

The 7177 is intended to operate with a FPGA card with parallel port pinout like the Mesa 5I25 or 6I25. The FPGA card supports the step/dir, encoder, and smart serial interface used by the field I/O and spindle interface and expansion RS-422 port. The FPGA card can also supply 5V power to the 7177.

## EXTERNAL 5V POWER

The 7177s 5V power for the analog, RS-422, and encoder section has an approximately 650 mA current drain. Installed encoders, RS-422 devices, and load on the analog outputs can increase this to up to 2A. This is in excess of the host FPGA cards current supply capacity. So when longer cables or high power drain encoders are used, or PC 5V is toward the low side, external 5V power should be supplied to the 7177s TB1 connector. Both the FPGA card and the 7177 have power jumpers that must be correctly set to match the 5V power source (see hardware configuration section)

## STATUS LEDS

Six status LEDs are provided for power and field I/O operation monitoring. These LEDs are listed here:

LED	COLOR	LOCATION	FUNCTION
CR1	Yellow	Upper left	5V monitor
CR3	Yellow	Upper right	Field voltage monitor
CR6	Yellow	Lower middle	+16V monitor
CR7	Yellow	Lower middle	-12V monitor
CR15	Green	Lower right	Field I/O activity
CR16	Red	Lower right	Field I/O fault

In normal operation CR1 through CR7 must always be on. At power-up, CR15 should be off and CR16 on. The red LED CR16 indicates a watchdog fault, which is expected before host communications are established. Once running, CR15 should blink at about 1 Hz for a 1 KHz update rate, and CR16 should be off. Note: CR15 and CR16 are only present in revision B or greater 7177 cards.

# OPERATION

## ANALOG SERVO DRIVE INTERFACE

The 7I77 provides six channels of +-10V analog servo interface on connector TB5. Minimum load resistance is 2K Ohms. Normally analog servo drives use differential inputs to avoid ground loops. Suggested wiring is shielded twisted pair with 7I77 AOUTN to drive AIN+, 7I77 GNDN (adjacent to AOUTN) to drive AIN- as the twisted pair and 7I77 GNDN connected to the shield at the 7I77 end only. The drives common or GND signal should be connected to the 7I77 power GND with a separate wire.

## SERVO ENABLE OUTPUTS

Six uncommitted OPTO coupler outputs are available for drive enable. Five of these outputs are (ENA0 through ENA4) are switched in common while ENA5 can be independently switched for spindle applications. The ENA outputs are floating switches so can be used for active high and active low drive enables. Output rating of the switches is 50 mA max at 100VDC max . Note that the enable outputs are polarized and can be damaged with reverse polarity. For active high drive enables, ENAN+ should go to the appropriate positive power supply and ENAN- to the drive enable input. For active low enable drives, ENAN+ should go to the drive enable and ENAN- to control power ground.

## ANALOG SECTION WATCHDOG

The 7I77s analog outputs are automatically set to 0V and drive enable OPTO couplers turned off at power up and when more than 50 mS has elapsed between host communications to the 7I77s analog section. This is designed to help prevent runaways should 7I77 host communications fail. This is not a replacement for ESTOP circuit that removes servo power.

## ENCODER INTERFACE

The 7I77 provides six channels of quadrature encoder interface with index. Encoder inputs can be programmed for differential or single ended encoders. The encoder interface also provides short circuit protected 5V power to the encoders. When used with single ended encoders, the ENCA+, ENCB+ and IDX+ signals are wired to the encoder and the ENCA-, ENCB-, and IDX- terminal left unconnected.

## MAXIMUM ENCODER COUNT RATE

The 7I77 uses multiplexed encoder signals to save interface pins. The multiplexing rate will determine the maximum encoder count rate. Default multiplexing rate with HostMot2 firmware is ClockLow / 8, or approximately 4 MHz with 5I25 or 6I25 FPGA host interface cards, giving a resolvable count rate of 2 MHz. The Multiplexing rate can be increased if desired but high multiplex rates will require short cables between the FPGA controller card and the 7I77 due to signal integrity and time-of-flight considerations. Maximum practical multiplex rate is approximately 12 MHz (and 6 MHz count rates).

# OPERATION

## RS-422 INTERFACE

The 7177 has one RS-422 interface available on TB6. This interface is intended for I/O expansion with Mesa SSERIAL devices. The easiest way to make a cable for interfacing the 7177 to these devices is to take a standard CAT5 or CAT6 cable, cut it in half, and wire the individual wires to the 7177 screw terminals. The following chart gives the CAT5/6 to 7177 screw terminal connections (EIA/TIA 568B colors shown):

<b>TB6 PIN</b>	<b>7177 SIGNAL</b>	<b>DIRECTION</b>	<b>CAT5 PINS</b>	<b>CAT5 568B COLOR</b>
1	GND	FROM 7177	4	BLUE
2	GND	FROM 7177	5	BLUE / WHITE
3	RX+	TO 7177	6	GREEN
4	RX-	TO 7177	3	GREEN / WHITE
5	TX+	FROM 7177	2	ORANGE
6	TX-	FROM 7177	1	ORANGE / WHITE
7	+5V	FROM 7177	7	BROWN / WHITE
8	+5V	FROM 7177	8	BROWN

# OPERATION

## FIELD I/O

The 7177 has a 32 input, 16 output isolated field I/O system to support a wide range of input and output devices. The isolated I/O is intended for low voltage DC control systems (commonly 24VDC). Inputs are sinking type. That is they sense positive input voltages relative to field ground. Outputs are sourcing (7177) or sinking (7177D) type. Sourcing outputs supply field power to field ground referred loads. Sinking outputs ground field voltage referred loads when on.

## VIN AND FIELD POWER SUPPLY

The 7177 field I/O runs from field power supplies of 5 to 32 VDC. Field power supplies the power to the 7176 (No D) outputs and determines the 7177 input thresholds. VIN power runs the field I/O processor and normally is connected to field power. VIN must be greater than 8V for proper operation. This means VIN must come from a separate source if 5V field voltage is used. Power consumption is approximately 600 mW or 25 mA at 24V. *VIN power must be present for the 7177 field I/O to be detected and operate.* Field voltages that are too high or too low will cause faults.

## FIELD OUTPUT CHARACTERISTICS

The 7177 (no D) field outputs are high side or sourcing type drivers, that is they source positive voltage to a ground referred load. For example with a standard 24V field power, +24V connects to the 7176s field power input (on TB1) and the outputs on TB5 and TB6 now source +24V power to loads. All 7176 loads will have one side returned to ground or the negative lead of the 24V supply. The 7176s outputs can drive loads of up to 350 mA.

The 7177D field outputs are low side or sinking type drivers, that is they ground the load side of a field voltage referred load.

## SOURCING VS SINKING OUTPUTS

The advantage of sourcing type field wiring is that it is less likely to cause inadvertent device actuation from the most likely type of field wiring problem which is a short to ground. The advantage of sinking drivers is compatibility with existing hardware on retrofits and the capability of using mixed output voltages.

## SHORT CIRCUIT PROTECTION

The 7177s outputs have short circuit protection and will turn off if short circuit current exceeds approximately 800 mA. The 7177 firmware will detect this condition, disable the affected output and indicate a fault.

## OVER-TEMPERATURE PROTECTION

The output driver chips detect over-temperature conditions. If the 7177 detects a driver chip with a over-temperature warning flag asserted, it will disable the affected chip and indicate a fault.

# OPERATION

## FIELD OUTPUT CHARACTERISTICS

### MAXIMUM PER CHIP CURRENT

Because of thermal limitations there is a maximum per driver chip total current of 1.4 amps continuous. Each driver chip connects to 8 sequential outputs. If this limit is exceeded, the driver chip may go into thermal shutdown.

### VOLTAGE CLAMPS

The output driver chips used on the 7177 have built in Zener diode clamps to clamp inductive turn-off (fly-back) spikes. This means that flyback diodes are not normally required on small (less than 60 mA) inductive loads. ***If high current inductive loads are switched or inductive loads are switched at high frequencies, they must have flyback diodes to limit power dissipation in the 7177's driver chips.***

## FIELD INPUT CHARACTERISTICS

The 7177 field inputs have a nominal input resistance of 20K Ohms to field power ground. 7177 inputs sense positive input voltages above a preset threshold. For best general purpose use, default input threshold is 50% of the field power supply voltage with 10% hysteresis. That is with a 24V field voltage an input must be brought to 60% of 24V = 14.4V to be sensed as high and then brought to 40% of 24V = 9.6V to be sensed as low. These accurate thresholds and hysteresis allow high speed field signal detection while maintaining excellent noise immunity.

### WHY SINKING INPUTS

7177 field inputs are of the sinking type. That is, external power must be applied to the input to register as activated. This mode was chosen so that accidental grounding of an input will not register as an activated input.

It is suggested that inputs like limit switches use normally closed switches with one switch leg connected to field power and the other to the 7177 input pin, so the normal machine state (not at limits) is to have the inputs activated. This way, a open switch wire or wire shorted to ground will cause a detectable machine fault.

### ANALOG INPUTS

All field input pins are capable of reading the input voltage. These are not highly accurate or high resolution but can be useful for things like potentiometer inputs. Input resolution is 8 bits and input full scale value is 36.3V. Accuracy is +-5%. Software process data modes 1 and 2 allow reading the analog voltage on inputs 0 through 3, in addition to the 32 digital bit inputs.

### FIELD VOLTAGE MONITORING

The 7177 monitors the field voltage and can send this information to the host in some modes. If separate VIN is supplied to the 7177, the 7177 can report loss of field voltage to the host.

# OPERATION

## FIELD INPUT CHARACTERISTICS

### MPG INPUTS

Software mode 3 allows using inputs 16,17,18 and 19 as MPG quadrature encoder inputs. In this mode the input thresholds are automatically set to 2.5V for compatibility with 5V encoder signals. Default counter mode is 1X for compatibility with standard 100 PPR MPGs.

## FIELD I/O WATCHDOG AND FAULTS

The 7177 has a watchdog timer that will set all set a fault flag if host communication does not occur at a minimum rate. Default watchdog time is 50 mS which means if not accessed at a greater than 20 Hz rate, the watchdog will bite and disable the outputs.

When a fault flag is set, outputs can not longer be set and the host must first clear the fault before normal operation can continue. This is also the 7177s startup condition, meaning the host must first clear the fault before starting normal operation. This is normally handled by SSLBP.

## FIELD I/O PARAMETERS

The 7177 has several user settable parameters, but normally only a very few need be changed in normal operation.

PARAMETER	TYPE	FUNCTION
NVBAUDRATE	UINT	Sets operate mode baudrate
NVUNITNUMBER	ULONG	Non-volatile unit number
UNITNUMBER	ULONG	Working unit number
NVWATCHDOGTIME	UINT	Non-volatile watchdog time in mS
WATCHDOGTIME	UINT	Working watchdog time in ms



# OPERATION

## NON-VOLATILE FIELD I/O PARAMETERS

All non volatile parameters start with the letters NV. Non-volatile parameters are stored permanently in the processors EEPROM and are copied to the volatile working parameters at power-up. Because of this, non-volatile parameters only take affect after a 7177 power cycle.

### OPERATE MODE BAUD RATE

The operate mode baud rate default is 2.5 MBaud. This should not be changed unless needed for non-standard applications. Baud rates are selected by writing an index value to the NVBAUDRATE parameter. The index numbers for available baud rates are as follows:

INDEX	BAUD	INDEX	BAUD	INDEX	BAUD
0	9600B	1	19200B	2	38400B
3	57600B	4	115200B	5	230400B
6	460800B	7	921600B	8	1.25MB
9	2.5MB*	10	5MB	11	10MB

### WATCHDOG TIMEOUT

The default watchdog period is 50 mS but can be set to different periods to suit the application. Watchdog timeout units are mS. A watchdog timeout value of 0 will disable the watchdog. The watch dog is a safety feature and should normally not be disabled nor set to long timeout periods unless the consequences of loss of control of outputs is not important. The non-volatile watchdog timeout is set via the NVWATCHDOGTIMEOUT parameter. The working watchdog timeout is set with the WATCHDOGTIME parameter.

# OPERATION

## RPD, WPD, AND UFLBP

The RPD, WPD, and UFLBP are command line utilities allow reading and writing volatile and non-volatile 7177 parameters, and updating the firmware on the 7177 To use these utilities on most operating systems, the 7177 must be in the setup mode or the operate mode baud rate must be 115200 KBaud or less

RPD, WPD, and UFLBP need environment variables preset before they will work. For Windows and 115200 baud, the following environment variables should be set:

```
SET BAUDRATE=115200
```

```
SET BAUDRATEMUL=1
```

```
SET PROTOCOL=LBP
```

```
SET INTERFACE=OSDEVICE
```

Example setting NVWATCHDOGTIMEOUT to 100 ms:

```
WPD NVWATCHDOGTIME 100
```

*Note this is permanent change in the 7177s watchdog timeout and like all non-volatile parameters, will only be applied after the 7177 has been power cycled*

Example reading 7177 faults in Hexadecimal:

```
RPD FAULT H
```

Example of temporarily disabling watchdog and the setting every other output on:

```
WPD WATCHDOGTIME 0
```

```
WPD OUTPUT AAAAAAAAAAAAAA H
```

Example of updating 7177 firmware with UFLBP

```
UFLBP 7177.BIN
```

Note the 7177 MUST be in setup mode for UFLBP to work properly.

# OPERATION

## SOFTWARE PROCESS DATA MODES

The 7177's digital I/O section (normally on serial channel 0) has 4 software selectable process data modes. These different modes select different sets of 7177 data to be transferred between the host and the 7177 during real time process data exchanges. For high speed applications, choosing the correct mode can reduce the data transfer sizes, resulting in higher maximum update rates.

- MODE 0 I/O only mode (32 bits of input data, 16 bit of output data)
- MODE 1 I/O plus analog input mode (32 bits of input data, 16 bits of output data, 4 analog input channels on inputs 0..3)
- MODE 2 I/O plus analog input and field voltage mode (32 bits of input data, 16 bits of output data, 4 analog input channels (on inputs 0..3) and field voltage analog in)
- MODE 3 I/O plus analog input and field voltage mode (32 bits of input data, 16 bits of output data, 4 analog input channels (on inputs 0..3), field voltage analog in and 2 MPG encoders on inputs 16..19). Default encoder count mode is 1X to match normal 100 PPR MPGs. Encoder input threshold is fixed at 2.5V for compatibility with 5V encoder outputs.

## REFERENCE INFORMATION

*Note that the following interface details presented here are not normally needed for users, as all register level interface details are handed by the driver code. This information is presented here for use by interface and driver developers.*

### SSLBP

#### GENERAL

SSLBP is a firmware option to HostMot2s SSERIAL serial interface that allows simple communication to LBP based peripherals like the 7177. SSERIAL is a part of the HostMot2 motion interface firmware for MESA's Anything-I/O FPGA cards.

#### REGISTER MAP

SSLBP has two global processor interface registers and four per channel remote device interface registers. For more details on mapping of these registers in HostMot2 memory space, see the REGMAP file that is included with the HostMot2 source distribution.

#### PROCESSOR INTERFACE REGISTERS

There are two processor interface registers, the COMMAND register and the DATA register. These registers allow low level communication to SSLBP's interface processor for issuing global commands, discovery, and debug operations.

# REFERENCE INFORMATION

## SSLBP

### COMMAND REGISTER

The commands register is a 16 bit register (right justified in the 32 bit interface) with the following format:

15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
W	M	R	D	S	T	T	T	N	N	N	N	N	N	N	N

W = BIT 15 Write bit, set high for control data write commands

M = BIT 14 ROM enable/ reset bit, set high to reset processor / download ROM

R = BIT 13 Request bit, set high for read or write command

D = BIT 12 Dolt bit, set high for Dolt commands

S = BIT 11 Start/Stop bit, actual operation depends on T:

ST = 1,0,0,0 Stop LBP interface = 0x08NN

ST = 1,0,0,1 Start LBP interface in normal mode = 0x09NN  
ST = 1,1,1,1 Start LBP interface in setup mode = 0x0FNN

N bits determine which channels start or do data transfer with remote device. A set bit indicates that the corresponding channel will start or do a data transfer.

A command is started when written to the command register. Command completion is signaled by the command register being cleared (to 0x0000) by the internal SSLBP firmware. If the command register is read before the command is complete, it will reflect the previously written command. *The command register should not be written when non-zero or unpredictable behavior may result.* There are two exceptions to this rule:

1. A STOP ALL command can always be written to reset the SSLBP interface.
2. Command writes with the ignore bit set can always be written (see below)

### COMMAND REGISTER WRITE IGNORE

*The command register has a feature that any command written with the MSB (bit 31) set will be ignored. This is for compatibility with DMA driven interfaces or any interfaces that use a fixed address list for low level hardware access so cannot skip writes.*

# REFERENCE INFORMATION

## SSLBP

### DATA REGISTER

SSLBP has a global 8 bit data register for debug and custom setup purposes. This register allows access to internal SSLBP parameters. The data register is right justified in the 32 bit Hostmot2 register.

### LOCAL READ OPERATIONS

The sequence used for reading a local SSLBP variable is as follows:

1. The parameter address ORed with the Request bit (bit 13) is written to the command register.
2. The host polls the command register until it reads as zero.
3. The host reads the parameter byte from the data register

### LOCAL WRITE OPERATIONS

The sequence used for writing a local SSLBP variable is as follows:

1. The host polls the command register until it reads as zero.
2. The host writes the data byte to the data register
3. The host writes the command register with the the parameter address Ored with both the Request bit (bit 13) and the Write bit (bit 15)

# REFERENCE INFORMATION

## SSLBP

### LOCAL PARAMETERS

There are a number of local SSLBP read only parameters that are useful for interface software and drivers to access using the local read operations:

LOCAL PARAMETER	ADDRESS	DESCRIPTION
INTERFACE_TYPE	0x0000	0x12 for SSLBP
INTERFACE_WIDTH	0x0001	Data port width (8)
MAJORREV	0x0002	Major SSLBP firmware revision
MINORREV	0x0003	Minor SSLBP firmware revision
GP_INPUTS	0x0004	Number of GP input bits (0 for SSLBP)
GP_OUTPUTS	0x0005	Number of GP output bits (0 for SSLBP)
PROCESSOR_TYPE	0x0006	0xD8 for Dumb8
CHANNELS	0x0007	1 to 8 depending on configuration

# REFERENCE INFORMATION

## SSLBP

### NORMAL START

When the FPGA is first configured or after a STOP command, all local communication, error and status parameters are initialized and all LBP communication channels are idle. A normal START command begins to establish communications with all remote LBP devices. A normal start command is issued by writing a Start bit with type bits of 0,0,1 with a bit mask of the desired channels to start in the low byte, This is 0x9NN hex where NN is the bitmask of channels to start. This command is written to the command register to start the selected channels.

Once a start command has been issued, all channels that are selected in the bit mask will be probed to determine if a LBP device exists. If a device exists on a channel, the SSLBP firmware will acquire the device name, and device unit number, and pointers to process data information from the remote device..

A normal start command also does a standard set of remote device setup operations when it detects a remote device. This setup includes clearing any faults, setting remote operational mode, and setting the outputs off. If no errors have occurred and all faults are clearable, the SSLBP firmware enters a "chatter" loop where it repeatedly sends output data of all 0's. This keeps the remote devices watchdog fed while waiting for the first DOIT command.

When the command completes (the command register is clear), the data register can be read to determine if all selected channels have started. A 1 bit in any position in the data register indicates that the corresponding channel has failed to start. If a channel has failed to start, more information about the failure can be determined by reading the CS register of the failed channel.

Once a DOIT command has been executed, the firmware no longer "chatters" and it becomes the responsibility of the host interface to continue sending DOIT commands at a rate sufficient to feed the remote devices watchdog (faster than 20 Hz with the default 50 mS watchdog timeout period). If this is not done, the remote device's watchdog will bite, disabling its outputs and setting the fault flag. This will require a channel stop followed by a channel start to resume normal operations.



# REFERENCE INFORMATION

## SSLBP

### STOP ALL

A STOPALL command is issued to stop all channel communication. *STOPALL resets all channel variables and should always be issued by a driver when initializing the SSLBP interface.* A STOPALL followed by a START command can be used after a fault condition to re-establish communication with the remote LBP devices. Device discovery is only done once when START command is issued to a STOPed SSLBP. This means that if cabling, devices, or device hardware modes are are changed, a STOPALL command followed by a START command must be issued by the host to detect the changes. A STOPALL command is 0x0800.

### STOP INDIVIDUAL CHANNELS

In addition to stopping all channels, a individual stop command can be issued. A individual stop command include a bitmask of the channels to stop in the least significant 8 bits of the command (the N bits), that is a stop channel 1 command would be 0x802. The intended use of individual stop is per channel error recovery. It should not be used for normal interface startup as it does not reset channel variables, that is a 0x8FF command (stop all individual channels) is not equivalent to a 0X800 (STOPALL) command.

### DOIT

In normal operation SSLBP is designed to send host data from the interface registers to the remote device and request data from the remote device for presentation in the interface registers to the host. This SSLBP function is designed for high speed real time operation. Synchronization with the host is accomplished with the DOIT command.

When the host writes a DOIT command,, all outgoing process data from the host is sent to the remote devices and incoming process data is requested. Completion of the DOIT command is signaled by SSLBP clearing the COMMAND register. A DOIT command is completed when al requested channel transfers have completed or timed out. After the completion of a successful DOIT command, the incoming process data from the remote can be read.

A DOIT command contains the DOIT bit and an 8 bit mask in the 8 LSBs that selects the channels that will be requested to transfer data. *A DOIT should not be requested on an inactive channel, that is a channel that did not start.* After DOIT command completion the data register will contain a bit mask of channel status data. If any bit is set in the data register, it indicates a problem with the transfer (all zeros indicates no faults or errors).

The data register contents returned after a DOIT command can be used to minimize host access cycles by avoiding the need to read the per channel status registers. If detailed fault information is desired, the CS register can be read on any channel that shows a failed transfer.

# REFERENCE INFORMATION

## SSLBP

### PER CHANNEL INTERFACE DATA REGISTERS

SSLBP supports three 32 bit interface data registers per channel. These are called interface register 0, interface register 1, and interface register 2. These are read/write registers with independent incoming and outgoing data. These registers are used for both setup/discovery data when starting a data link and process data once the link is running. When a start command is issued and has successfully completed, per channel setup data will be available in the interface registers.

### PER CHANNEL CONTROL AND STATUS REGISTERS

SSLBP has a 32 bit control and status register for each channel. Like the interface data registers, these registers are used both for data link startup information and for status when the link is in operation.

### REMOTE MODES

Some remote devices have software selectable modes that determine the specific data transferred for each DOIT command. These modes are selected by writing the mode number to the most significant byte of the remote channels CSR before a START or SETUP START command is issued. A default value of 0x00000000 should be written to all CSRs if MODE is not used.

#### REMOTE MODE IS WRITTEN TO CSR MS BYTE BEFORE START

CS REG	MODE	0	0	0.
--------	------	---	---	----

### INTERFACE AND CS REGISTER DATA AT START

After a successful start command (either setup start or normal start), Interface register 0 reports the remote device's unit number. This is the number printed on the card label. Interface register 1 reports the remote device's 4 letter name (LSB first). Interface register 2 reports the remote devices global table of contents pointer (GTOCP) and process table of contents pointer (PTOCP) for the currently selected remote device mode. The GTOCP and PTOCP will be 0x0000 for devices that do not support process data discovery. *Note that the setup data will be overwritten with process data once the first DOIT command is issued.*

#### READ DATA FROM PER CHANNEL INTERFACE REGISTERS AFTER START

CS REG	X	COM_STATE	STATUS	LOCAL FLT.
INTERFACE 0	UNIT# BYTE 3	UNIT# BYTE 2	UNIT# BYTE 1	UNIT# BYTE 0
INTERFACE 1	NAME BYTE 3	NAME BYTE 2	NAME BYTE 1	NAME BYTE 0
INTERFACE 2	GTOCP BYTE1	GTOCP BYTE 0	PTOCP BYTE1	PTOCP BYTE 0

# REFERENCE INFORMATION

## SSLBP

### CS REGISTER AFTER START

The CS register is used for local SSLBP, and remote LBP device status and control information. Read access returns status information in both normal and setup mode. In normal mode, writes to the CS register are not used. After a normal start or setup start the CS register has the following format:

Byte3 = X undefined for SSLBP versions < 29, remote fault for versions >28 (See CS REGISTER AFTER DOIT section)

Byte2 = COM\_STATE Communication state code (debug only)

Byte1 = Communication status code (0x00 for OK)

Bit 7 = CommunicationNotReady

Bit 6 = NoRemotelD

Bit 5 = CommunicationError

Bit 0 = RemoteFault

Byte0 = Local Communication faults (sticky, cleared only by STOP)

Bit 7 = TooManyerrors

Bit 6 = RemoteFault

Bit 5 = SerialBreakError

Bit 4 = ExtraCharacterError

Bit 3 = TimeoutError

Bit 2 = OverrunError

Bit 1 = InvalidCookieError

Bit 0 = CRCError

# REFERENCE INFORMATION

## SSLBP

### CS REGISTER AFTER DOIT

After a successful DOIT command, or normal start with SSLBP versions >28 bytes 0 through 2 of CS register are the same as after a start command but in addition, the previously invalid byte 3 of the CS register contains remote fault information:

Byte3 = REMOTE\_FAULTS

Bit 7 = LBPCOMFault

Bit 6 = IllegalMode Fault

Bit 5 = LowVoltageFault

Bit 4 = HighVoltageFault

Bit 3 = OverCurrentFault

Bit 2 = OverTempFault

Bit 1 = NoEnableFault

Bit 0 = WatchdogFault

# REFERENCE INFORMATION

## SSLBP

### PROCESS DATA DISCOVERY

The SSLBP interface provides information to allow the host to determine the name, number, units, sizes, types, directions, and scaling of process data elements. This information is read from the remote device via a setup mode start followed by a series of remote read operations.

*Note to the bewildered: process data discovery and its complications are not needed to access the 7177 via SSLBP. In fact the 7177's data can be accessed via SSLBP with no more than a few register reads and writes. The sole purpose of process data discovery is to allow the driver to present nicely named and formatted data to the host without the driver having any built in knowledge of the remote device.*

### PROCESS TABLE OF CONTENTS

After a normal start or setup start command, the PTOCP word in the low word of interface register 2 is a pointer to the current process table of contents (PTOC) in the remote device.

*If remote devices that do not support process device discovery are present, their PTOCP will be 0, and process data organization must be inferred from the remote device name.*

Remote reads from this location will return the first entry in the PTOC. All PTOC entries are pointers with a size of 2 bytes. The end of the PTOC is marked with a 0 sentinel. Each PTOC entry points to a process data descriptor. Here is an example of a 5 entry PTOC (PDD is Process Data Descriptor)

ENTRY	ADDRESS	CONTENTS
0	PTOCP	POINTER TO PDD 0
1	PTOCP+2	POINTER TO PDD 1
2	PTOCP+4	POINTER TO PDD 2
3	PTOCP+6	POINTER TO PDD 3
4	PTOCP+8	POINTER TO PDD 4
5	PTOCP+10	0x0000 (END OF TABLE)

# REFERENCE INFORMATION

## SSLBP

### PROCESS DATA DESCRIPTOR

Each PTOC entry points to a process data descriptor or a mode descriptor. Each process data descriptor is a record with fields for data size, data type, data direction, minimum and maximum values, the address of the process data and the unit name and process data name. Each process data element has a corresponding process data descriptor record. In addition there are mode descriptor records that indicate the current hardware and software modes of the remote device. The process data descriptor record structure is as follows:

FIELD NAME	FIELD LENGTH	DESCRIPTION
RECORD_TYPE	8 BITS	RECORD TYPE = 0xA0
DATA_SIZE	8 BITS	DATA SIZE IN BITS
DATA_TYPE	8 BITS	DATA ELEMENT TYPE
DATA_DIRECTION	8 BITS	DATA DIRECTION
PARAM_MIN	32 BITS	IEEE-754 FP PARM MIN
PARAM_MAX	32 BITS	IEEE-754 FP PARM MAX
PARAM_ADD	16 BITS	ADDRESS OF PARM
UNIT_STRING	VARIABLE	NULL TERM. STRING
NAME_STRING	VARIABLE	NULL TERM. STRING

### PROCESS DATA DESCRIPTOR FIELDS

#### RECORD\_TYPE

The RECORD\_TYPE field is a single byte at the beginning of the process data descriptor for record typing and sanity checking. It is 0xA0 for process data records.

#### DATA\_LENGTH

The DATA\_LENGTH field is a single byte field that specifies the length of the process data element in bits. Minimum is 1 bit, maximum is 255 bits, however current SSLBP implementations are limited by the number of interface registers to a maximum of 96 bits.

# REFERENCE INFORMATION

## SSLBP

### DATA\_TYPE

The DATA\_TYPE field is a single byte field that specifies the data type of the process data element. Data types are as follows:

NUMBER	DATA_TYPE	NOTE
0x00	PAD	To pad for byte alignment
0x01	BITS	Packed bits, LSB is BIT 0
0x02	UNSIGNED	Numeric unsigned
0x03	SIGNED	Numeric twos complement LSB first
0x04	NONVOL_UNSIGNED	Numeric unsigned
0x05	NONVOL_SIGNED	Numeric twos complement LSB first
0x06	STREAM	Continuous data stream
0x07	BOOLEAN	Any length non-zero = true

### DATA\_DIRECTION

The DATA\_DIRECTION field is a single byte field that specifies the data direction. Valid Data direction bytes are as follows:

0x00	INPUT	(Read from remote)
0x40	BI_DIRECTIONAL	(Read from and written to remote)
0x80	OUTPUT	(Written to remote)

### PARAMETER\_MIN

The PARAMETER\_MIN field is a 32 bit IEEE-754 floating point number that specifies the minimum value of the process data element. This is to allow the driver to present data in engineering units. Not valid for non-numeric data types

### PARAMETER\_MAX

The PARAMETER\_MAX field is a 32 bit IEEE-754 floating point number that specifies the maximum value of the process data element. This is to allow the driver to present data in engineering units. Not valid for non-numeric data types.

# REFERENCE INFORMATION

## SSLBP

### UNIT\_STRING

The UNIT\_STRING is a variable length null terminated string that specifies the units of the process data element

### NAME\_STRING

The NAME\_STRING is a variable length null terminated string that begins immediately after the UNIT\_STRING. It specifies the name of the process data element.

### NUMERIC PROCESS DATA SCALING

Currently all numeric process data is simple unsigned or signed (twos complement) binary data. The process data element PARAM\_MIN and PARAM\_MAX values in conjunction with the DATA\_SIZE can be used to scale this numeric data.

For unsigned data, PARAM\_MIN corresponds to a value of 0 and PARAM\_MAX corresponds to a value of  $(2^{DATA\_SIZE}) - 1$ . Meaning scaled unsigned data is  $RAW\_DATA * (PARAM\_MAX - PARAM\_MIN) / ((2^{DATA\_SIZE}) - 1) + PARAM\_MIN$ .

For signed data. PARAM\_MIN corresponds the value  $-(2^{DATA\_SIZE-1}) - 1$  and PARAM\_MAX corresponds the value  $(2^{DATA\_SIZE-1}) - 1$ , meaning scaled signed data is  $RAW\_DATA * (PARAM\_MAX - PARAM\_MIN) / ((2^{DATA\_SIZE-1}) - 1) + PARAM\_MIN$ .

### MODE DESCRIPTOR

In addition to the process data descriptors, the PTOC will have pointers to two mode descriptors. These are the currently selected hardware and software modes of the remote device.

FIELD NAME	FIELD LENGTH	DESCRIPTION
RECORD_TYPE	8 BITS	RECORD TYPE = 0xB0
MODE INDEX	8 BITS	WHICH MODE
MODE TYPE	8 BITS	MODE TYPE
UNUSED	8 BITS	UNUSED
MODE_NAME_STRING	VARIABLE	NULL TERM. STRING

### MODE TYPES

Currently there are only two mode types, HWMODE = 0x00 and SWMODE = 0x01 these correspond to hardware (EEPROM or Jumper setting )and software (dynamically changeable operational modes)



# REFERENCE INFORMATION

## SSLBP

### PROCESS DATA ELEMENT PACKING AND UNPACKING

Ultimately all process data is transferred to and from the host via the interface 0,1,2 registers.

*The packing of outgoing process data elements into these interface registers and unpacking of incoming process data elements from these interface registers is done in the order of process data descriptors listed in the PTOC. Process data elements in PTOC order and process descriptor DATA\_SIZE are packed into or unpacked from the interface registers from LSB to MSB and from interface register 0 through interface register 2.*

Read data and bidirectional data is unpacked from the interface registers read by the host. Write data and bidirectional data is packed into the interface registers written by the host.

Before a DOIT command is written to start a data transfer cycle with the remote device, the host must write its packed outgoing process data (OPD in table below) to the interface registers. (The CS register not currently used for outgoing data/control so is not written)

### HOST WRITES OUTGOING INTERFACE REGISTERS BEFORE DOIT

CS REG	MODE	X	X	X
INTERFACE 0	OPD BYTE 3	OPD BYTE 2	OPD BYTE 1	OPD BYTE 0
INTERFACE 1	OPD BYTE 7	OPD BYTE 6	OPD BYTE 5	OPD BYTE 4
INTERFACE 2	OPD BYTE 11	OPD BYTE 10	OPD BYTE 9	OPD BYTE 8

# REFERENCE INFORMATION

## SSLBP

### PROCESS DATA ELEMENT PACKING AND UNPACKING

After the DOIT command has completed, the incoming process data (IPD in table below) can be read along with the local and remote faults.

#### HOST READS INCOMING INTERFACE REGISTERS AFTER DOIT

CS REG	REMOTE. FLT	COM_STATE	STATUS	LOCAL FLT.
INTERFACE 0	IPD BYTE 3	IPD BYTE 2	IPD BYTE 1	IPD BYTE 0
INTERFACE 1	IPD BYTE 7	IPD BYTE 6	IPD BYTE 5	IPD BYTE 4
INTERFACE 2	IPD BYTE 11	IPD BYTE 10	IPD BYTE 9	IPD BYTE 8

### 7177 SPECIFIC PROCESS DATA EXAMPLE

Process data is remote device dependent and also dependent on remote device mode. The 7177 supports 3 software modes.

# REFERENCE INFORMATION

## SSLBP

### 7177 SPECIFIC FIELD I/O PROCESS DATA EXAMPLE

In the default input/output mode the process data appears in the interface registers in the order shown:

#### 7177 OUTGOING FIELD I/O PROCESS DATA FOR MODE (1)

<b>CS REG</b>	X	X	X	X
<b>INTERFACE 0</b>	X	X	TB7 OUTS 15..8	TB8 OUTS 7..0
<b>INTERFACE 1</b>	X	X		
<b>INTERFACE 2</b>	X	X	X	X

#### 7177 INCOMING FIELD I/O PROCESS DATA FOR MODE (1)

<b>CS REG</b>	REMOTE. FLT	COM_STATE	STATUS	LOCAL FLT.
<b>INTERFACE 0</b>	TB7 INS 31..24	TB7 INS 23..16	TB8 INS 15..8	TB8 INS 7..0
<b>INTERFACE 1</b>	ANALOG3	ANALOG2	ANALOG1	ANALOG0
<b>INTERFACE 2</b>	X	X	X	X

Note that this information is just for user convenience as the process data organization in the interface registers can be determined by process data discovery.

# REFERENCE INFORMATION

## SSLBP

### NORMAL MODE OPERATION

In normal mode the sequence of operations for a cyclic access with write before read is as follows:

Note steps 1 through 5 are setup operations and are only done once per session

1. Issue STOP ALL command (0x800), wait for COMMAND register clear to verify stop command completion.
2. Issue normal START command (0x9NN) with bitmask (NN) of channels to start.
3. Wait for COMMAND register clear to verify start command completion. (may be many mS)
4. Read data register to verify that all selected channels started (a 1 in any channel position bit means a fault in the channel that the bit represents)
5. Read device unit number (This can only be read before DOIT has been asserted)
6. Check command register, if not clear, cycle time is too short.  
  
(Note the command register should never be written to when not clear except to issue a stop command or when written with the command ignore bit set)
7. Check data register, any 1 bits indicate previous DOIT command failed for in the corresponding channels
8. Read per channel Interface register 0 and interface register 1 for input process data
9. Write per channel output process data ( for 7I77) to interface 0 register and interface 1 register
10. Write DOIT command = 0x10NN where NN is the bit mask of channels to initiate transfers.
11. Wait for next cycle, at next cycle time, loop back to state 6

This sequence can be modified if a read-modify-write sequence is required, this requires polling the command register for send/receive completion. This will take a maximum of 100 uSec from the DOIT command to command register clear and valid input data.

# REFERENCE INFORMATION

## SETUP START

When the FPGA is first configured or after a stop all command, all LBP communication channels are idle. A SETUP START command first initializes and all local communication, error and status parameters and begins to establish communications with all remote LBP devices. Unlike the NORMAL START command, SETUP START does no device specific setup but instead creates a pass-through access mode that allows the host to read or write any remote LBP device parameter. This allows simple utilities to setup 7177 volatile and non-volatile parameters, and allows the host to do process data discovery to determine the input and output process data information from the remote device.

### SETUP MODE OPERATION

In setup mode the SSLBP interface is used as a passthrough device to allow reading and writing parameters to the remote LBP device.

### REMOTE READ EXAMPLE:

For a remote word read, the sequence of operations is as follows:

1. Issue a STOPALL command (0x800), wait for COMMAND register clear to verify stop command completion.
2. Issue a setup START command (0xFNN) with bitmask (NN) of channels to start
3. Wait for COMMAND register clear to verify start command completion. (may be many mS)
4. Read data register to verify that all selected channels started (a 1 bit means a fault in the channel that the bit represents)
5. Write LBP word read command (0x45) in the MSByte ORed with the parameter address to the selected channels CS register. (0x4500PPPP)
6. Issue a DOIT Command
7. Wait for the command register to be clear
8. Check that the data register is clear, any set bits indicate an error
9. Read the returned data in the LS word of the selected channels Interface0 register
10. Repeat from step 5 for any additional remote data reads

Remote read byte, word, long and double are basically equivalent, the only difference being the LBP command (0x44,0x45,0x46,0x47 respectively) and the size of the data read from the interface register(s)

# REFERENCE INFORMATION

## SSLBP

### REMOTE WRITE EXAMPLE:

For a remote word write, the sequence of operations is as follows:

1. Issue a STOPALL (0x800) command, wait for COMMAND register clear to verify stop command completion.
2. Issue a setup START command (0xFNN) with bitmask (NN) of channels to start
3. Wait for COMMAND register clear to verify start command completion. (may be many mS)
4. Read data register to verify that all selected channels started (a 1 bit means a fault in the channel that the bit represents)
5. Write the new parameter data to the selected channels Interface0 register (right justified)
6. Write LBP word write command (0x65) in the MSByte ORed with the parameter address to the selected channels CS register. (0x6500PPPP)
7. Issue a DOIT Command
8. Wait for the command register to be clear
9. Check that the data register is clear, any set bits indicate an error
- . Repeat from step 5 for any additional remote parameter writes

Remote write byte, word, long and double are basically equivalent, the only difference being the LBP command (0x64,0x65,0x66,0x67 respectively) and the size of the data written to the interface register(s)

# REFERENCE INFORMATION

## SSLBP

### DISCOVERY SEQUENCE:

for process data discovery (of one channel) the sequence of operations is as follows:

Note that the first section acquires the PTOC and the second section reads the records pointed to by the PTOC. For brevity, the remote read sequence (steps 5 through 9 of the remote read procedure) will be listed here as "remote read"

### FIRST PART, ACQUIRE PTOC:

1. Issue a STOPALL (0x800) command, wait for COMMAND register clear to verify stop command completion.
2. Issue a setup START command (0xFNN) with bitmask (NN) of channels to start
3. Wait for COMMAND register clear to verify start command completion. (may be many mS)
4. Read data register to verify that the selected channels started (a 1 bit means a fault in the channel that the bit represents)
5. Read PTOCP from interface register 2, of selected channel, if zero, remote device does not support discovery
6. Remote read word at PTOCP
7. If word data is 0, PTOC collection is complete goto step 11
8. Save value in local PTOC table, and increment local PTOC table index
9. Increment PTOCP value by 2 (as it is a word pointer)
10. Repeat from step 6

# REFERENCE INFORMATION

## SSLBP

### DISCOVERY SEQUENCE

SECOND PART, READ PROCESS DESCRIPTOR AND MODE DESCRIPTOR RECORDS:

11. For each PTOC entry acquired in the previous step:
12. Remote read byte at PTOC+0
12. If byte is 0xA0, proceed to step 16, reading process data descriptor
14. If byte is 0xB0, proceed to step 25 reading mode descriptor
15. If byte is neither, there is a error
16. Remote read byte at PTOC+1 This is DATA\_SIZE
17. Remote read byte at PTOC+2 This is DATA\_TYPE
18. Remote read byte at PTOC+3 This is DATA\_DIRECTION
19. Remote read long at PTOC+4 This is PARAM\_MIN.
20. Remote read long at PTOC+8 This is PARAM\_MAX
21. Remote read word at PTOC+10 This is PARAM\_ADD (not used normally)
22. Read UNIT\_STRING starting at PTOC+12
  - Initialize CharPointer to PTOC+12
  - repeat (remote read byte at CharPointer, increment CharPointer, if byte is 0: done)
23. Read NAME\_STRING starting at CharPointer
  - repeat (remote read byte at CharPointer, increment CharPointer, if byte is 0: done)
24. Repeat with next PTOC = step 11



# REFERENCE INFORMATION

## SSLBP

### DISCOVERY SEQUENCE

SECOND PART, READ PROCESS DESCRIPTOR AND MODE DESCRIPTOR RECORDS:

25. Remote read byte at PTOC+1 This is MODE\_INDEX

26. Remote read byte at PTOC+2 This is MODE TYPE

27. Read MODE\_NAME\_STRING starting at PTOC+4

    Initialize CharPointer to PTOC+4

    repeat (remote read byte at CharPointer, increment CharPointer, if byte is 0: done)

28. Repeat with next PTOC = step 1

29. Select next channel # and repeat from step 5

## REFERENCE INFORMATION

### LBP

LBP is a simple binary master slave protocol where the host sends read, write, or RPC commands to the 7177, and the 7177 responds. All controller communication to the 7177 is done via LBP. LBP commands always start with a command header byte. This header specifies whether the command is a read or write or RPC, the number of address bytes(0, or 2), and the number of data bytes(1 through 8).The 0 address size option indicates that the current address pointer should be used. This address pointer will be post incremented by the data size if the auto increment bit is set. RPC commands allow any of up to 64 stored commands to be executed in response to the single byte command.

Note that the low level serial interface details presented here are not normally needed for 7177 card access, as all the low level details are handed by the SSLBP code in the SSerial interface built into the FPGA, but is presented here for completeness.

#### LBP DATA READ/WRITE COMMAND

0	1	WR	RID	AI	AS	DS1	DS0
---	---	----	-----	----	----	-----	-----

- Bit 7.. 6      **CommandType:** Must be 01b to specify data read/write command
- Bit 5          **Write:** 1 to specify write, 0 to specify read
- Bit 4          **RPCIncludesData:** 0 specifies that data is from stream, 1, that data is from RPC (RPC only, ignored for non RPC commands)
- Bit 3          **AutoInc:** 0 leaves address unchanged, 1 specifies that address is post incremented by data size in bytes.
- BIT 2          **AddressSize:** 0 to specify current address, 1 to specify 2 byte address.
- Bit 1..0      **DataSize:** Specifies data size, 00b = 1 bytes, 01b = 2 bytes, 10 b= 4 bytes, 011b = 8 bytes.

When multiple bytes are specified in a read or write command, the bytes are always written to or read from successive addresses. That is, a 4 byte read at location 0x21 will read locations 0x21, 0x22, 0x23, 0x24. The address pointer is not modified after the command unless the AutoInc bit is set.

## REFERENCE INFORMATION

### LBP

#### EXAMPLE LBP COMMANDS

Write 4 bytes (0xAA, 0xBB,0xCC,0xDD) to addresses 0x010,0x011,0x012,0x013 with AutoInc so that the address pointer will be left at 0x014 when the command is completed:

COMMAND BITS	CT1	CT0	WR	RID	AI	AS	DS1	DS0
<b>LBPWrite: 2 add 4 data</b>	0	1	1	0	1	1	1	0
Write Address LSB	0	0	0	1	0	0	0	0
Write Address MSB	0	0	0	0	0	0	0	0
Write data 0	1	0	1	0	1	0	1	0
Write Data 1	1	0	1	1	1	0	1	1
Write Data 2	1	1	0	0	1	1	0	0
Write Data 3	1	1	0	1	1	1	0	1

Write 2 more bytes (0xEE,0xFF) at 0x014 and 0x015:

COMMAND BITS	CT1	CT0	WR	RID	AI	AS	DS1	DS0
<b>LBPWrite: 0 add 2 data</b>	0	1	1	0	0	0	0	1
Write data 0	1	1	1	0	1	1	1	0
Write data 1	1	1	1	1	1	1	1	1

Read 8 bytes at 0x010,0x011,0x012,0x013,0x014,0x015,0x016,0x017:

COMMAND BITS	CT1	CT0	WR	RID	AI	AS	DS1	DS0
<b>LBPRead: 2 add 8 data</b>	0	1	0	0	0	1	1	1
Read Address LSB	0	0	0	1	0	0	0	0
Read Address MSB	0	0	0	0	0	0	0	0

# REFERENCE INFORMATION

## LBP

### LOCAL LBP COMMANDS

In addition to the basic data access commands, there are a set of commands that access LBP status and control the operation of LBP itself. These are organized as READ and WRITE commands

### LOCAL LBP READ COMMANDS

(HEX), all of these commands return a single byte of data.

**0xC0** Get unit address

**0xC1** Get LBP status

LBP Status bit definitions:

BIT 7 Reserved

BIT 6 Command Timeout Error

BIT 5 Invalid write Error (attempted write to protected area)

BIT 4 Buffer overflow error

BIT 3 Watchdog timeout error

BIT 2 Reserved

BIT 1 Reserved

BIT 0 CRC error

**0xC2** Get CRC enable status (note CRCs are always enabled on the 7177)

**0xC3** Get CRC error count

**0xC4 .. 0xC9** Reserved

**0xCA** Get Enable\_RPCMEM access flag

**0xCB** Get Command timeout (character times/10 for serial)

**0xCC .. 0xCF** Reserved

**0xD0 .. 0xD3** 4 character card name

# REFERENCE INFORMATION

## LBP

### LOCAL LBP READ COMMANDS

**0xD5 .. 0xD7** 4 character configuration name (only on some configurations)

**0xD8** Get low address

**0xD9** Get high address

**0xDA** Get LBP version

**0xDB** Get LBP Unit ID (Serial only, not used with USB)

**0xDC** Get RPC Pitch

**0xDD** Get RPC SizeL (Low byte of RPCSize)

**0xDE** Get RPC SizeH (High byte of RPCSize)

**0xDF** Get LBP cookie (returns 0x5A)

# REFERENCE INFORMATION

## LBP

### LOCAL LBP WRITE COMMANDS

(HEX), all of these commands except 0xFF expect a single byte of data.

**0xE0** Reserved

**0xE1** Set LBP status (0 to clear errors)

**0xE2** Set CRC check enable (Flag non-zero to enable CRC checking)

**0xE3** Set CRC error count

**0xE4 .. 0xE9** Reserved

**0xEA** Set Enable\_RPCMEM access flag (non zero to enable access to RPC memory)

**0xEB** Set Command timeout (in mS for USB and character times for serial)

**0xEC .. 0xEF** Reserved

**0xF0 .. 0xF6** Reserved

**0xF7** Write LEDs

**0xF8** Set low address

**0xF9** Set high address

**0xFA** Add byte to current address

**0xFB .. 0xFC** Reserved

**0xFD** Set unit ID (serial only)

**0xFE** Reset LBP processor if followed by 0x5A

**0xFF** Reset LBP parser (no data follows this command)

# REFERENCE INFORMATION

## LBP

### RPC COMMANDS

RPC commands allow previously stored sequences of read/write commands to be executed with a single byte command. Up to 64 RPC's may be stored. RPC write commands may include data if desired, or the data may come from the serial data stream. RPCs allow significant command compression which improves communication bandwidth. When used with SSLBP, the 7177s process data transfer uses an RPC for efficiency

### LBP RPC COMMAND

1	0	RPC5	RPC4	RPC3	RPC2	RPC1	RPC0
---	---	------	------	------	------	------	------

Bit 7..6      **CommandType:** must be 10b to specify RPC

Bit 5..0      **RPCNumber:** Specifies RPC 0 through 63

In the 7177 LBP implementation, RPCPitch is 0x8 bytes so each RPC command has native size of 0x08 bytes and start 0x8 byte boundaries in the RPC table area. RPCs can cross RPCPitch boundaries if larger than RPCPitch RPCs are needed. The stored RPC commands consist of LBP headers and addresses, and possibly data if the command header has the RID bit set. RPC command lists are terminated by a 0 byte.

The RPC table is accessed at addresses 0 through RPCSize-1 This means with a RPCPitch of 0x8 bytes, RPC0 starts at 0x0000, RPC1 starts at 0x008, RPC2 starts at 0x0010 and so on.

Before RPC commands can be written to the RPC table, the RPCMEM access flag must be set. The RPCMEM access flag must be clear for normal operation.

# REFERENCE INFORMATION

## LBP

### EXAMPLE RPC COMMAND LIST

This is an example stored RPC command list. Note RPC command lists must start at a RPCPitch boundary in the RPC table but an individual RPC list can extend until the end of the table. This particular RPC example contains 2 LBP commands and uses 7 bytes starting at 0x0028 (RPC5 for 0x08 pitch RPC table)

Command1. Writes two data bytes to address 0x10, 0x11 with 2 data bytes supplied by host

Command2. Reads two data bytes from address 0x12,0x13

COMMAND BITS	CT1	CT0	WR	RID	I	AS	DS1	DS0
<b>LBPWrite: 2 add 2 data</b>	0	1	1	0	0	1	0	1
Write Address LSB	0	0	0	1	0	0	0	0
Write Address MSB	0	0	0	0	0	0	0	0
<b>LBPRead: 2 add 2 data</b>	0	1	0	0	0	1	0	1
Read Address LSB	0	0	0	1	0	0	1	0
Read Address MSB	0	0	0	0	0	0	0	0
<b>Terminator</b>	0	0	0	0	0	0	0	0

The data stream for this RPC would consist of these 3 bytes:

COMMAND BITS	CT1	CT0	R5	R4	R3	R2	R1	R0
<b>RPC 5</b>	1	0	0	0	0	1	0	1
Data 0 for Command 1	0	1	0	1	0	1	0	1
Data 1 for Command 1	1	1	0	0	1	1	0	0



## REFERENCE INFORMATION

### SPECIAL RPCS

All remotes that work with SSLBP must implement three special RPCs, the ProcessDataRPC, The UnitNumberRPC, and the DiscoveryRPC.

**DiscoveryRPC = 0xBB** – Returns one byte that specifies process input data size in bytes, and one byte that specifies the process output data size in bytes. Following the size bytes are two 16 bit pointers, the first is the PTOC and the second is the GTOC. Note that the remote software mode must be set before issuing the discovery RPC.

**UnitNumberRPC = 0xBC** – Returns 32 bit unit number.

**ProcessDataRPC = 0xBD** -- Normal process data transfer RPC followed by output data bytes. Returns one byte of remote fault information followed by input data. Number of input and output bytes are as specified in the DiscoveryRPC.

### CRC

LBP on the 7177 uses CRC checking of all commands and data to insure validity. The CRC used is a 8 bit CRC using the same polynomial as the Dallas/Maxim one wire devices ( $X^8+X^5+X^4+X^0$ ). The CRC must be appended to all LBP commands and all returned data will have a CRC byte appended. Commands with no returned data (writes or RPCs with no reads) will still cause a CRC byte to be returned, this CRC byte will always be 00H.

### FRAMING

Since LBP is a binary protocol with no special sync characters, the packet framing must be determined by other methods.

Framing is done by a combination of timing and pre-parsing the serial data. Timing based framing is used to reset the parser at gaps in the serial data stream. This provides fast resynchronization to allow robust operation in noisy environments. The actual timeout used needs to be optimized for the operating mode. In setup mode where a non real-time OS may be communicating with the remote device, the frame timing is set to its maximum value (25.5 character times). This is equivalent to 2.1 mS at 115200 baud. This means that host communications cannot have more than 2.1 mS delays between characters in a command sequence when in setup mode.

In operate mode, command timeout is set by SSLBP to be 4 character times (16 uSec at 2.5M baud). The SSLBP firmware always sends commands in bursts without inter-character gaps so will always meet this timing. The timing is set short so that the parser on the remote device will always be reset and ready for the next command at the highest repetition rates even if data has been corrupted by noise so that incomplete commands have been received.

# REFERENCE INFORMATION

## SSERIAL REMOTE RPCS

SSerial remote devices must implement three special RPCs to be compatible with the hosts FPGA SSLBP firmware. These RPCs may be normal in-memory RPCs or special hardwired RPCs for speed. Normal programmable RPCs are not required for compatibility with SSLBP so need not be implemented.

### UNIT NUMBER RPC

The unit number RPC returns the 4 byte remote unit number. Like all LBP data this is sent LSB first. This RPC is 0xBB hex.

### DISCOVERY RPC

The discovery RPC returns the total sizes of the receive and transmit process data in bytes and returns 16 bit pointers to the PTOC and GTOC (which are in turn tables of pointers to process data records and mode records). The discovery RPC is 0xBC hex.

Return data bytes are in the following order: RXSize, TXSize, PTOCLSB, PTOCMSB, GTOCLSB, GTOCMSB.

RXSize is host relative so this is the size of data that the remote transmits. Likewise TXSize is host relative so this is the size of process data the remote receives. Note that the remote should check its remote SW mode and remote HW mode flags and return size data and pointers appropriate for the currently selected mode. Note that the remote always sends remote fault data as the first byte of the process data sent to the host. This extra byte of data must be reflected in the RXSize byte.

### PROCESS DATA RPC

The Process data RPC is used to transfer process data to and from the host. The process data RPC should always receive and send the amount of RX and TX data that the Discovery RPC indicates. As mentioned above, the first byte of data sent from the remote to the host is always remote fault information as listed in CS REGISTER AFTER DOIT section of the manual. The process data RPC is 0xBD hex.

# REFERENCE INFORMATION

## SPECIFICATIONS

	MIN	MAX	NOTES
<b>GENERAL</b>			
HOST SUPPLY VOLTAGE 5V	4.5 VDC	5.5 VDC	
5V CURRENT	----	700 mA	No ext load.
<b>FIELD I/O</b>			
VIN (FIELD I/O LOGIC POWER)	10	32	VDC
VIN POWER CONSUMPTION	----	1 W	Typ. 600 mW
FIELD POWER	5	28	VDC
PER OUTPUT CURRENT	----	350	mA
(RESISTIVE LOADS AND INDUCTIVE LOADS WITH FLYBACK DIODE)			
FIELD OUTPUT CURRENT	----	60	mA
(INDUCTIVE LOADS WITH NO FLYBACK DIODE)			
PER CHIP CURRENT	----	1.4	Amp
INPUT IMPEDANCE	20K	24K	Ohms
<b>ANALOG OUTPUTS</b>			
OUTPUT ACCURACY	-0.8	+0.8	%FS
OUTPUT CURRENT	----	5	mA
OUTPUT RESOLUTION	----	13	Bits
RIPPLE AND NOISE	-0.1	+0.1	%FS

# REFERENCE INFORMATION

## SPECIFICATIONS

### ENABLE OUTPUTS

OUTPUT CURRENT	----	50	mA
OPEN CIRCUIT VOLTAGE	----	100	VDC
ON VOLTAGE AT 50 mA	----	1.2	VDC

### ENCODER INPUTS

INPUT COMMON MODE RANGE	-7	+12	Volts
INPUT TTL MODE THRESHOLD	1.4	1.8	Volts
DIFFERENTIAL MODE IMPEDANCE	131	135	Ohms
COUNT RATE	----	2	MHz

(With standard firmware/setup)

### RS-422 INTERFACE

MAXIMUM DATA RATE	----	10	MBIT/S
INPUT COMMON MODE RANGE	-7	+12	Volts
INPUT TERMINATION RESISTOR	131	135	Ohm
OUTPUT LOW (24 mA sink)	----	.8	Volts
OUTPUT HIGH (24 mA source)	VCC-.8	----	Volts

### ENVIRONMENTAL

TEMPERATURE -C VERSION	0°C	70°C
TEMPERATURE -I VERSION	-40°C	85°C

# REFERENCE INFORMATION

## DRAWINGS

