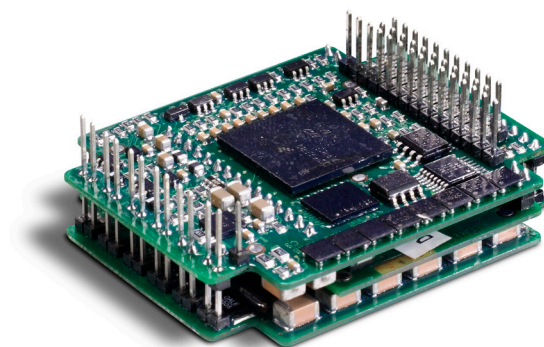

ExtrIQ_{Line}

Hornet and Bee Digital Servo Drive Installation Guide



February 2019 (Ver. 1.306)



www.elmomc.com

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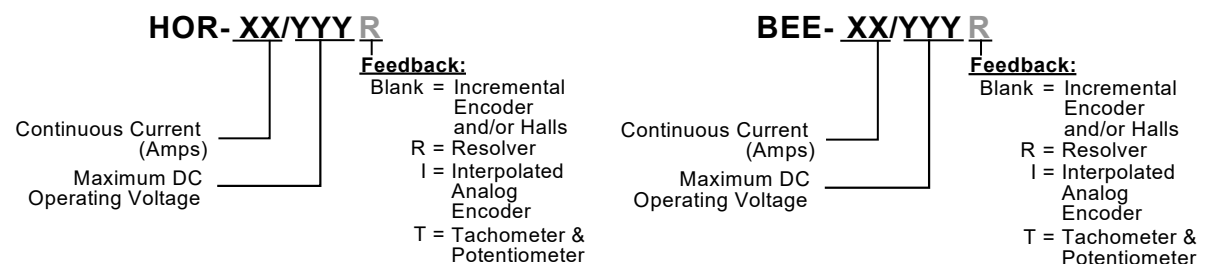
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Catalog Number



Related Products:

Evaluation Board

Catalog Number: EVA-WHI/GUI/BEL

Evaluation Board User Manual

MAN-EVLBRD-WHI-BEL-GUI.pdf (available on our web site)

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| 1.0 | Feb. 2007 | Initial release |
| 1.1 | April 2008 | Updated Power Rating Tables in Chapter 4 |
| 1.2 | July 2010 | MTCR 03-010-02: Updated Section 3.4;Figure 21; Section 3.16; Section 4.1.8 |
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Chapter 1: Safety Information

In order to achieve the optimum, safe operation of the Hornet and Bee servo drives, it is imperative that you implement the safety procedures included in this installation guide. This information is provided to protect you and to keep your work area safe when operating the Hornet and Bee as well as the accompanying equipment.

Please read this chapter carefully before you begin the installation process.

Before you start, ensure that all system components are connected to earth ground. Electrical safety is provided through a low-resistance earth connection.

Only qualified personnel may install, adjust, maintain and repair the servo drive. A qualified person has the knowledge and authorization to perform tasks such as transporting, assembling, installing, commissioning and operating motors.

The Hornet and Bee servo drives contain electrostatic-sensitive components that can be damaged if handled incorrectly. To prevent any electrostatic damage, avoid contact with highly insulating materials, such as plastic film and synthetic fabrics. Place the product on a conductive surface and ground yourself in order to discharge any possible static electricity build-up.

To avoid any potential hazards that may cause severe personal injury or damage to the product during operation, keep all covers and cabinet doors shut.

The following safety symbols are used in this manual:



Warning:

This information is needed to avoid a safety hazard, which might cause bodily injury.



Caution:

This information is necessary for preventing damage to the product or to other equipment.



1.1. Warnings

- To avoid electric arcing and hazards to personnel and electrical contacts, never connect/disconnect the servo drive while the power source is on.
- Power cables can carry a high voltage, even when the motor is not in motion. Disconnect the Hornet and Bee from all voltage sources before it is opened for servicing.
- The Hornet and Bee servo drives contain grounding conduits for electric current protection. Any disruption to these conduits may cause the instrument to become hot (live) and dangerous.
- After shutting off the power and removing the power source from your equipment, wait at least 1 minute before touching or disconnecting parts of the equipment that are normally loaded with electrical charges (such as capacitors or contacts). Measuring the electrical contact points with a meter, before touching the equipment, is recommended.



1.2. Cautions

- The Hornet and Bee servo drives contain hot surfaces and electrically-charged components during operation.
- The maximum DC power supply connected to the instrument must comply with the parameters outlined in this guide.
- When connecting the Hornet and Bee to an approved 11 to 95 VDC auxiliary power supply, connect it through a line that is separated from hazardous live voltages using reinforced or double insulation in accordance with approved safety standards.
- Before switching on the Hornet and Bee, verify that all safety precautions have been observed and that the installation procedures in this manual have been followed.
- Do not clean any of the Hornet and Bee drives' soldering with solvent cleaning fluids of pH greater than 7 (8 to 14). The solvent corrodes the plastic cover causing cracks and eventual damage to the drive's PCBs.

Elmo recommends using the cleaning fluid Vigon-EFM which is pH Neutral (7).

For further technical information on this recommended cleaning fluid, select the link:

http://www.zestron.com/fileadmin/zestron.com-usa/daten/electronics/Product_TI1s/TI1-VIGON_EFM-US.pdf

1.3. Directives and Standards

The Hornet and Bee conform to the following industry safety standards:

| Safety Standard | Item |
|--|--|
| Approved IEC/EN 61800-5-1, Safety | Adjustable speed electrical power drive systems |
| Recognized UL 508C | Power Conversion Equipment |
| In compliance with UL 840 | Insulation Coordination Including Clearances and Creepage Distances for Electrical Equipment |
| In compliance with UL 60950-1 (formerly UL 1950) | Safety of Information Technology Equipment Including Electrical Business Equipment |
| In compliance with EN 60204-1 | Low Voltage Directive 73/23/EEC |

The Hornet and Bee servo drives have been developed, produced, tested and documented in accordance with the relevant standards. Elmo Motion Control is not responsible for any deviation from the configuration and installation described in this documentation. Furthermore, Elmo is not responsible for the performance of new measurements or ensuring that regulatory requirements are met.

1.4. CE Marking Conformance

The Hornet and Bee servo drives are intended for incorporation in a machine or end product. The actual end product must comply with all safety aspects of the relevant requirements of the European Safety of Machinery Directive 98/37/EC as amended, and with those of the most recent versions of standards EN 60204-1 and EN 292-2 at the least.

According to Annex III of Article 13 of Council Directive 93/68/EEC, amending Council Directive 73/23/EEC concerning electrical equipment designed for use within certain voltage limits, the Hornet and Bee meet the provisions outlined in Council Directive 73/23/EEC. The party responsible for ensuring that the equipment meets the limits required by EMC regulations is the manufacturer of the end product.

1.5. Warranty Information

The products covered in this manual are warranted to be free of defects in material and workmanship and conform to the specifications stated either within this document or in the product catalog description. All Elmo drives are warranted for a period of 12 months from the date of shipment. No other warranties, expressed or implied — and including a warranty of merchantability and fitness for a particular purpose — extend beyond this warranty.

Chapter 2: Introduction

This installation guide describes the Hornet and Bee servo drives and the steps for their wiring, installation and power-up. Following these guidelines ensures maximum functionality of the drive and the system to which they are connected.

2.1. ExtrIQ Product Family

Elmo Motion Control's **ExtrIQ** product family is a set of durable motion control products for applications operating under extreme environmental conditions. The products are capable of withstanding the following extreme conditions:

| Feature | Operation Conditions | Range |
|----------------------------------|--------------------------|---|
| Ambient Temperature Range | Non-operating Conditions | -50 °C to +100 °C (-58 °F to 212 °F) |
| | Operating conditions | -40 °C to +70 °C (-40 °F to 160 °F) |
| Temperature Shock | Non-operating conditions | -40 °C to +70 °C (-40 °F to 160 °F) within 3 min |
| Altitude | Non-operating conditions | Unlimited |
| | Operating conditions | -400 m to 12,000 m (-1312 to 39370 feet) |
| Maximum Humidity | Non-operating conditions | Up to 95% relative humidity non-condensing at 35 °C (95 °F) |
| | Operating conditions | Up to 95% relative humidity non-condensing at 25 °C (77 °F), up to 90% relative humidity non-condensing at 42 °C (108 °F) |
| Vibration | Operating conditions | 20 Hz to 2000 Hz, 14.6g |
| Mechanical Shock | Non-operating conditions | ±40g; Half sine, 11 msec |
| | Operating conditions | ±20g; Half sine, 11 msec |

ExtrIQ products have a high power density in the range from 10 W to 9000 W and current carrying capacity of up to 200 A (400 A peak). **ExtrIQ** has been tested using methods and procedures specified in a variety of extended environmental conditions (EEC) standards.

Based on Elmo Motion Control's innovative **ExtrIQ** core technology, they support a wide range of motor feedback options, programming capabilities and communication protocols.

2.2. Drive Description

The Hornet and Bee series are highly resilient digital servo drives designed to deliver “the highest density of power and intelligence”. While both are light and highly compact solutions,



the Bee can be used whenever reduced size and weight are essential to the application. The Hornet delivers up to **1.6 KW of continuous power** or **3.2K W of peak power** in a 2.4 in³ (55 X 15 x 46.5 mm or 2.2" x 0.6" x 1.8") 38 cc package. The Bee delivers up to **200 W of continuous power** or **400 W of peak power**.

Designed for OEMs, the Hornet and Bee are part of the Elmo's **ExtriQ** product line designed to endure extended environmental operating conditions. The digital drives are based on Elmo's advanced **ExtriQ** motion control technology. They operate from a DC power source in current, velocity, position and advanced position modes, in conjunction with a permanent-magnet synchronous brushless motor, DC brush motor, linear motor or voice coil. They are designed for use with any type of sinusoidal and trapezoidal commutation, with vector control. The Hornet and Bee can operate as stand-alone devices or as part of a multi-axis system in a distributed configuration on a real-time network.

The drives are easily set up and tuned using Elmo's *Composer* software tools. This Windows-based application enables users to quickly and simply configure the servo drive for optimal use with their motor. The Hornet and Bee, as part of the **ExtriQ** product line, are fully programmable with Elmo's *Composer* motion control language.

Power to the drives is provided by a 11 to 95 VDC isolated DC power source (not included with the Hornet and Bee). A "smart" control-supply algorithm enables the Hornet and Bee to operate with only one power supply with no need for an auxiliary power supply for the logic.

If backup functionality is required for storing control parameters in case of power-loss, an external 11 to 95 VDC isolated supply should be connected (via the +VL terminal on the Hornet and Bee) providing maximum flexibility and backup functionality when needed.

Note: This backup functionality can operate from any voltage source within the 11 to 95 VDC range. This is much more flexible than to be restricted by only using a standard 24 VDC power supply.

If backup power is not needed, two terminals (VP and VL) are shorted so that the main power supply will also power the control/logic supply. In this way there is no need for a separate control/logic supply.

The Hornet and Bee are PCB mounted devices which enable efficient and cost saving implementation.

2.3. Product Features

2.3.1. Current Control

- Fully digital
- Sinusoidal commutation with vector control or trapezoidal commutation with encoder and/or digital Hall sensors
- 12-bit current loop resolution
- Automatic gain scheduling, to compensate for variations in the DC bus power supply



2.3.2. Velocity Control

- Fully digital
- Programmable PI and FFW (feed forward) control filters
- Sample rate two times current loop sample time
- “On-the-fly” gain scheduling
- Automatic, manual and advanced manual tuning and determination of optimal gain and phase margins

2.3.3. Position Control

- Programmable PIP control filter
- Programmable notch and low-pass filters
- Position follower mode for monitoring the motion of the slave axis relative to a master axis, via an auxiliary encoder input
- Pulse-and-direction inputs
- Sample time – four times that of the current loop
- Fast event capturing inputs
- PT and PVT motion modes
- Position-based and time-based ECAM mode that supports a non-linear follower mode, in which the motor tracks the master motion using an ECAM table stored in flash memory
- Dual (position/velocity) loop
- Fast output compare (OC)

2.3.4. Communication Options

Hornet and Bee users can use two communication options:

- RS-232 serial communication
- CAN for fast communication in a multi-axis distributed environment

2.3.5. Feedback Options

- Incremental Encoder – up to 20 Mega-Counts (5 Mega-Pulse) per second
- Digital Halls – up to 2 kHz
- Incremental Encoder with Digital Halls for commutation – up to 20 Mega-Counts per second for encoder
- Interpolated Analog (Sine/Cosine) Encoder – up to 250 kHz (analog signal)
 - Internal Interpolation - up to x4096
 - Automatic Correction of amplitude mismatch, phase mismatch, signals offset
 - Auxiliary emulated, unbuffered, single-ended, encoder output

- Resolver
 - Programmable 10 to 15 bit resolution
 - Up to 512 revolutions per second (RPS)
 - Auxiliary emulated, unbuffered, single-ended, encoder output
- Tachometer, Potentiometer
- Elmo drives provide supply voltage for all the feedback options

2.3.6. Fault Protection

The Hornet and Bee include built-in protection against possible fault conditions, including:

- Software error handling
- Status reporting for a large number of possible fault conditions
- Protection against conditions such as excessive temperature, under/over voltage, loss of commutation signal, short circuits between the motor power outputs and between each output and power input/return.
- Recovery from loss of commutation signals and from communication errors

2.4. System Architecture

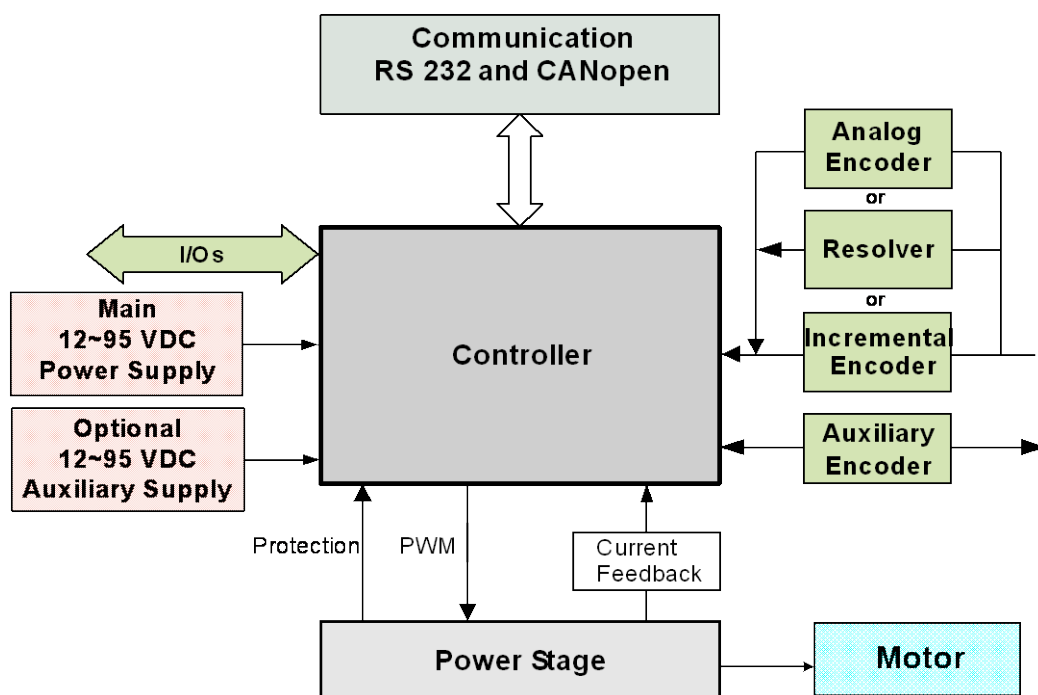


Figure 1: Hornet/Bee System Block Diagram

2.5. How to Use this Guide

In order to install and operate your Elmo Hornet or Bee servo drives, you will use this manual in conjunction with a set of Elmo documentation. Installation is your first step; after carefully



reading the safety instructions in the first chapter, the following chapters provide you with installation instructions as follows:

- **Chapter 3, *Installation***, provides step-by-step instructions for unpacking, mounting, connecting and powering up the Hornet and Bee.
- **Chapter 4, *Technical Specifications***, lists all the drive ratings and specifications.

Upon completing the instructions in this guide, your Hornet and Bee servo drives should be successfully mounted and installed. From this stage, you need to consult higher-level Elmo documentation in order to set up and fine-tune the system for optimal operation. The following figure describes the accompanying documentation that you will require.

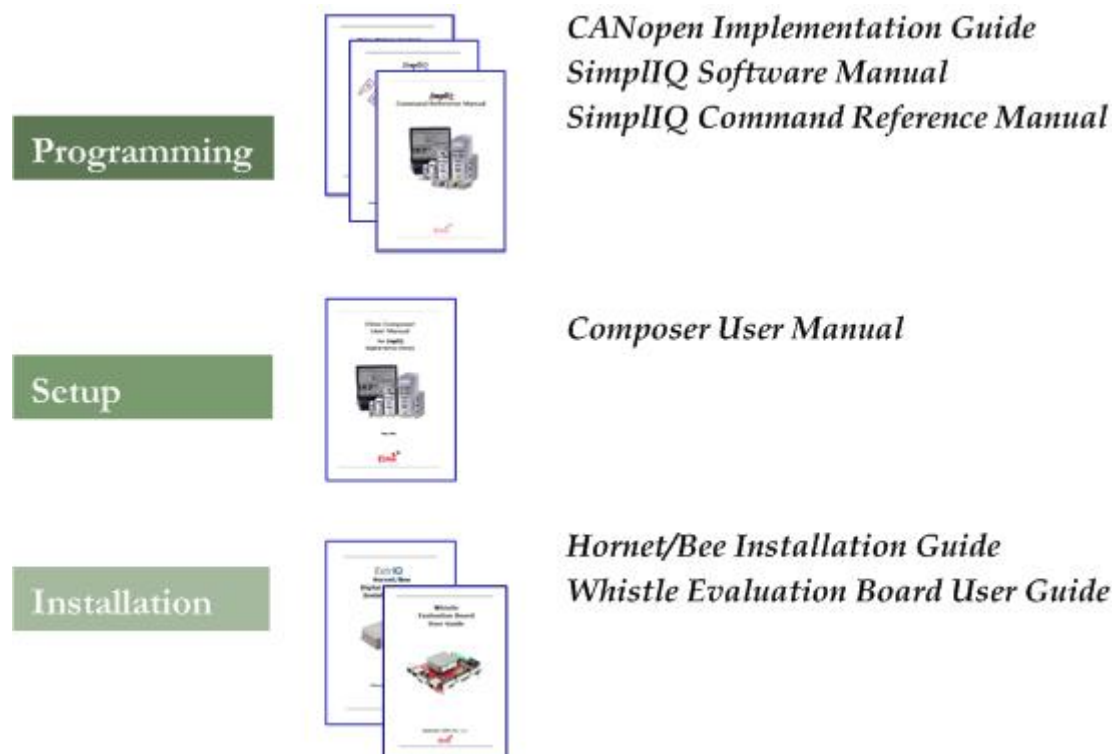


Figure 2: Elmo Digital Servo Drive Documentation Hierarchy

As depicted in the previous figure, this installation guide is an integral part of the Hornet and Bee documentation set, comprising:

- The *Composer Software Manual*, which includes explanations of all the software tools that are part of Elmo's Composer software environment.
- The *SimplIQ Command Reference Manual*, which describes, in detail, each software command used to manipulate the Hornet and Bee motion controller.
- The *SimplIQ Software Manual*, which describes the comprehensive software used with the Hornet and Bee.

Chapter 3: Installation

The Hornet and Bee must be installed in a suitable environment and properly connected to its voltage supplies and the motor.

3.1. Site Requirements

You can guarantee the safe operation of the Hornet and Bee by ensuring that they are installed in an appropriate environment.

| Feature | Value |
|---------------------------------|--|
| Ambient operating temperature | -40 °C to +70 °C (-40 °F to 160 °F) |
| Maximum operating altitude | 12,000 m (39370 feet) |
| Maximum non-condensing humidity | 95% |
| Operating area atmosphere | No flammable gases or vapors permitted in area |



Caution:

The Hornet and Bee dissipate heat by convection. The maximum ambient operating temperature of -40 °C to +70 °C (-40 °F to +160 °F) must not be exceeded.

3.2. Unpacking the Drives

Before you begin working with the Hornet and Bee, verify that you have all of their components, as follows:

- The Hornet or Bee servo drive
- The Composer software and software manual

The Hornet and Bee are shipped in cardboard boxes with Styrofoam protection.

To unpack the Hornet or Bee:

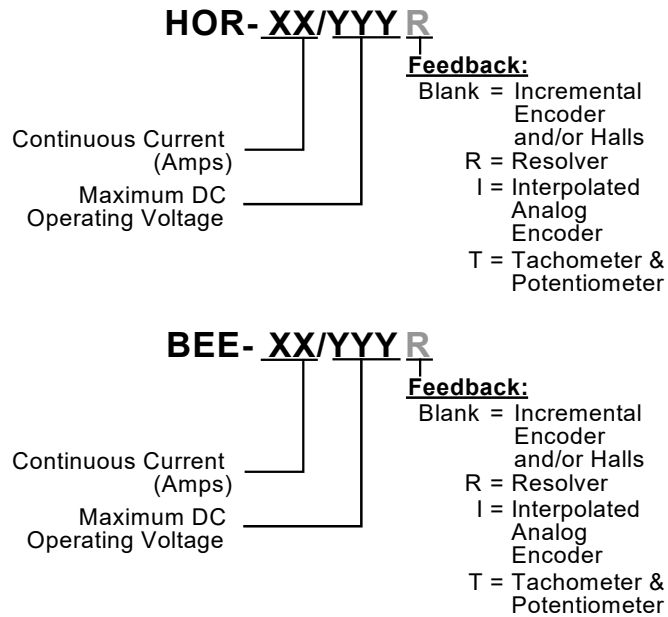
1. Carefully remove the servo drive from the box and the Styrofoam.
2. Check the drive to ensure that there is no visible damage to the instrument. If any damage has occurred, report it immediately to the carrier that delivered your drive.



3. To ensure that the Hornet or Bee you have unpacked is the appropriate type for your requirements, locate the part number sticker on the side of the Hornet or Bee. It looks like this:



The part number at the top gives the type designation as follows:



4. Verify that the Hornet or Bee type is the one that you ordered, and ensure that the voltage meets your specific requirements.

3.3. Connectors

The Hornet and Bee have nine connectors.

3.3.1. Connector Types

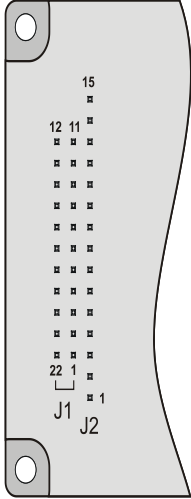
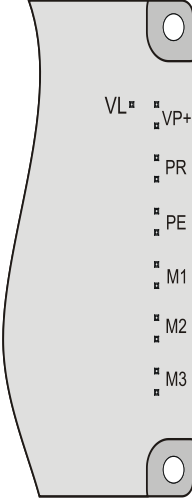
| Pins | Type | Port | Function | Connector Location |
|------|--------------------------|------|-------------------------------------|--|
| 2x11 | 2 mm pitch 0.51 mm sq | J1 | I/O, COMM, Auxiliary Feedback |   |
| 15 | | J2 | Main Feedback, Analog Input, LED | |
| 2 | | M1 | Motor power output 1 | |
| 2 | | M2 | Motor power output 2 | |
| 2 | | M3 | Motor power output 3 | |
| 2 | | PE | Protective earth | |
| 2 | | PR | Power input return | |
| 2 | | VP+ | Positive power input | |
| 1 | | VL | Auxiliary power input | |

Table 1: Connector Types



3.3.2. Pinouts

The pinouts in this section describe the function of each pin in the Hornet and Bee J1 and J2 connectors.

3.3.2.1. Connector J1

| Pin (J1) | Signal | Function |
|----------|----------------|--------------------------------------|
| 1 | RS232_RX | RS232 receive |
| 2 | RS232_TX | RS232 Transmit |
| 3 | RS232_COMRET | Communication return |
| 4 | SUPRET | Supply return |
| 5 | AUX PORT CHA | AUX PORT CHA (bidirectional) |
| 6 | SUPRET | Supply return |
| 7 | OUT1 | Programmable Digital output 1 |
| 8 | OUT2 | Programmable Digital output 2 |
| 9 | IN1 | Programmable Digital input 1 |
| 10 | IN2 | Programmable Digital input 2 |
| 11 | IN3 | Programmable Digital input 3 |
| 12 | IN4 | Programmable Digital input 4 |
| 13 | IN5 | Programmable Digital input 5 |
| 14 | IN6 | Programmable Digital input 6 |
| 15 | INRET | Programmable Digital input return |
| 16 | OUTRET2 | Programmable Digital output 2 return |
| 17 | OUTRET1 | Programmable Digital output 1 return |
| 18 | AUX PORT CHB | AUX PORT CHB (bidirectional) |
| 19 | AUX PORT INDEX | AUX PORT INDEX (bidirectional) |
| 20 | CAN_COMRET | Communication return |
| 21 | CAN_L | CAN_L busline (dominant low) |
| 22 | CAN_H | CAN_H busline (dominant high) |

**3.3.2.2. Connector J2**

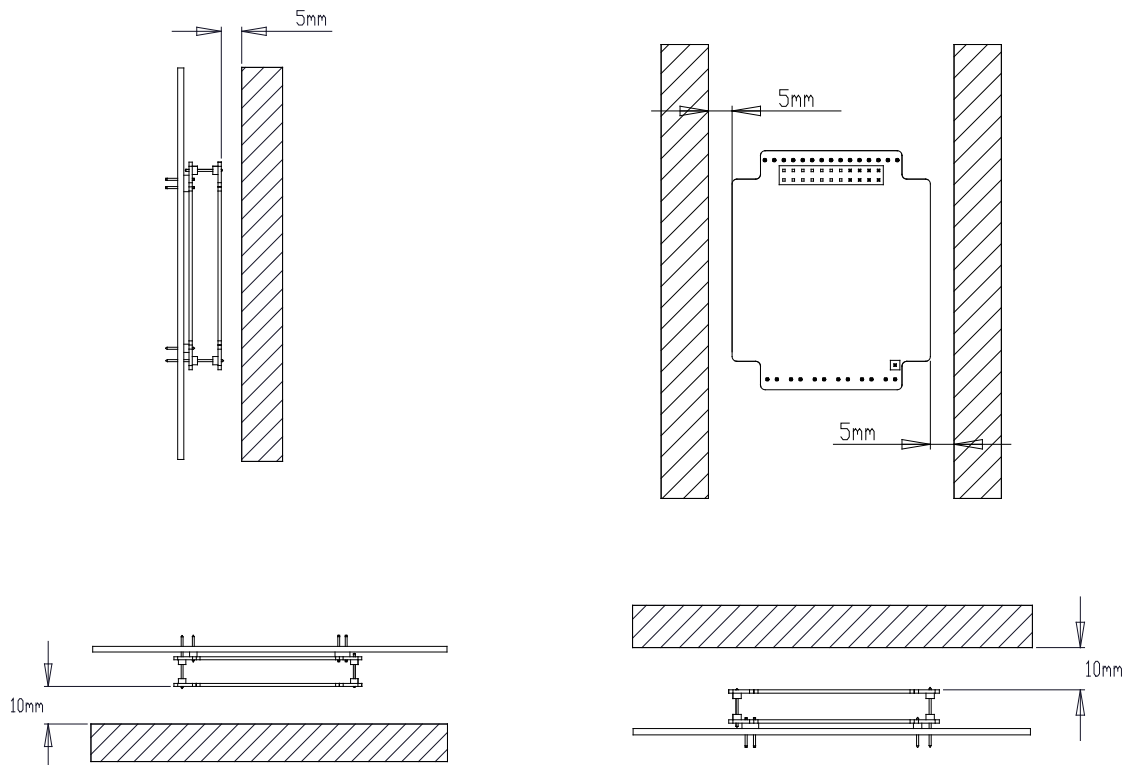
| Pin (J2) | Signal | Function |
|----------|-----------|---|
| 1 | +5V | Encoder/Hall +5V supply voltage. Maximum output current: 200 mA. |
| 2 | SUPRET | Supply return |
| 3 | ANALIN1+ | Analog input 1+ |
| 4 | ANALIN1- | Analog input 1- |
| 5 | CHA | Channel A input |
| 6 | CHA- | Channel A input complement |
| 7 | CHB | Channel B input |
| 8 | CHB- | Channel B input complement |
| 9 | INDEX+ | Index input |
| 10 | INDEX- | Index input complement |
| 11 | HA | Hall sensor A input |
| 12 | HB | Hall sensor B input |
| 13 | HC | Hall sensor C input |
| 14 | LED_2_OUT | Bi-color indication output 2 (Cathode) |
| 15 | LED_1_OUT | Bi-color indication output 1 (Anode) |



3.4.2. Bee

The Bee was designed for mounting on a printed circuit board (PCB) via 2 mm pitch 0.51 mm square pins. When integrating the Bee into a device, be sure to leave about 1 cm (0.4") outward from the lower board to enable free air convection around the drive. We recommend that the Bee be soldered directly to the board. Alternatively, the Bee can be attached to socket connectors mounted on the PCB.

Note: Elmo recommends you leave approximately 1 cm (0.4 in) of space on the side opposite the terminals to allow for free air convection.





3.5. Integrating the Hornet or Bee on a PCB

The Hornet and Bee are designed to be mounted on a PCB, either by soldering the pins directly to the PCB or by using suitable socket connectors. In both cases the following rules apply:

3.5.1. Traces

1. The **size of the traces** on the PCB (thickness and width) is determined by the current carrying capacity required by the application.
 - The rated continuous current limit (I_c) of the Hornet and Bee is the current used for sizing the motor traces (M1, M2, M3 and PE) and power traces (VP+, PR and PE).
 - For control, feedbacks and Input/output conductors the actual current is very small but “generous” thickness and width of the conductors will contribute to a better performance and lower interference.
2. The **traces should be as short as possible** to minimize EMI and to minimize the heat generated by the conductors.
3. The **spacing** between the high voltage conductors (VP+, PR, M1, M2, M3, VL) must be at least:
 - Surface layer: 1.5 mm
 - Internal layer: 0.10 mm

Complying with the rules above will help satisfy UL safety standards, and the IPC-D-275 standard for non-coated conductors, operating at voltages lower than 100 VDC.

3.5.2. Grounds and Returns

The “Returns” of the Hornet and Bee are structured internally in a star configuration. The returns in each functional block are listed below:

| Functional Block | Return Pin |
|---------------------------|--------------------------|
| Power | PR (Power Return) |
| Internal Switch Mode P.S. | PR (Power Return) |
| RS232 Communications | RS232_COMRET (J1/3) |
| CAN Communications | CAN_COMRET (J1/20) |
| Control section | Internal, not accessible |
| Main Feedback | SUPRET (J2/2) |
| Aux. Feedback | SUPRET (J1/4) |
| Analog input | ANLRET (J2/2) |

The returns above are all shorted within the Hornet or Bee in a topology that results in optimum performance.



1. When wiring the traces of the above functions, on the Integration Board, the **Returns** of each function must be **wired separately** to its designated terminal on the Hornet or Bee. **DO NOT USE A COMMON GROUND PLANE.** Shorting the commons on the Integration Board may cause performance degradation (ground loops, etc).
2. **Inputs:** The 6 inputs are optically isolated from the other parts of the Hornet/Bee. All 6 inputs share a single common "Return" (INRET - J1/15). To retain isolation, the Input Return pin, as well as other conductors on the input circuit, must be laid out separately.
3. **Outputs:** The 2 outputs are optically isolated from the other parts of the Hornet/Bee. Each output has a separate floating return (OUTRET1 - J1/17 for output 1 and OUTRET2 J1/16 for output 2). To retain isolation, the Output Return pins, as well as other conductors on the output circuit, must be laid out separately.
4. **Return Traces:** The return traces should be as large as possible, but without shorting each other, and with minimal crossovers.
5. **Main Power Supply and Motor Traces:** The power traces must be kept as far away as possible from the feedback, control and communication traces.
6. **PE Terminal:** The PE terminal is connected directly to the Hornet's heatsink or to the Bee's 2 PE strips on its lower board. In the Hornet, the heatsink serves as an EMI common plane. The PE terminal should be connected to the system's Protective Earth. Any other metallic parts (such as the chassis) of the assembly should be connected to the Protective Earth as well.
7. Under normal operating conditions, the PE trace carries no current. The only time these traces carry current is under abnormal conditions (such as when the device has become a potential shock or fire hazard while conducting external EMI interferences directly to ground). When connected properly the PE trace prevents these hazards from affecting the drive.

**Caution:**

Follow these instructions to ensure safe and proper implementation. Failure to meet any of the above-mentioned requirements can result in drive, controller or host failure.



3.6. The Hornet/Bee Connection Diagram

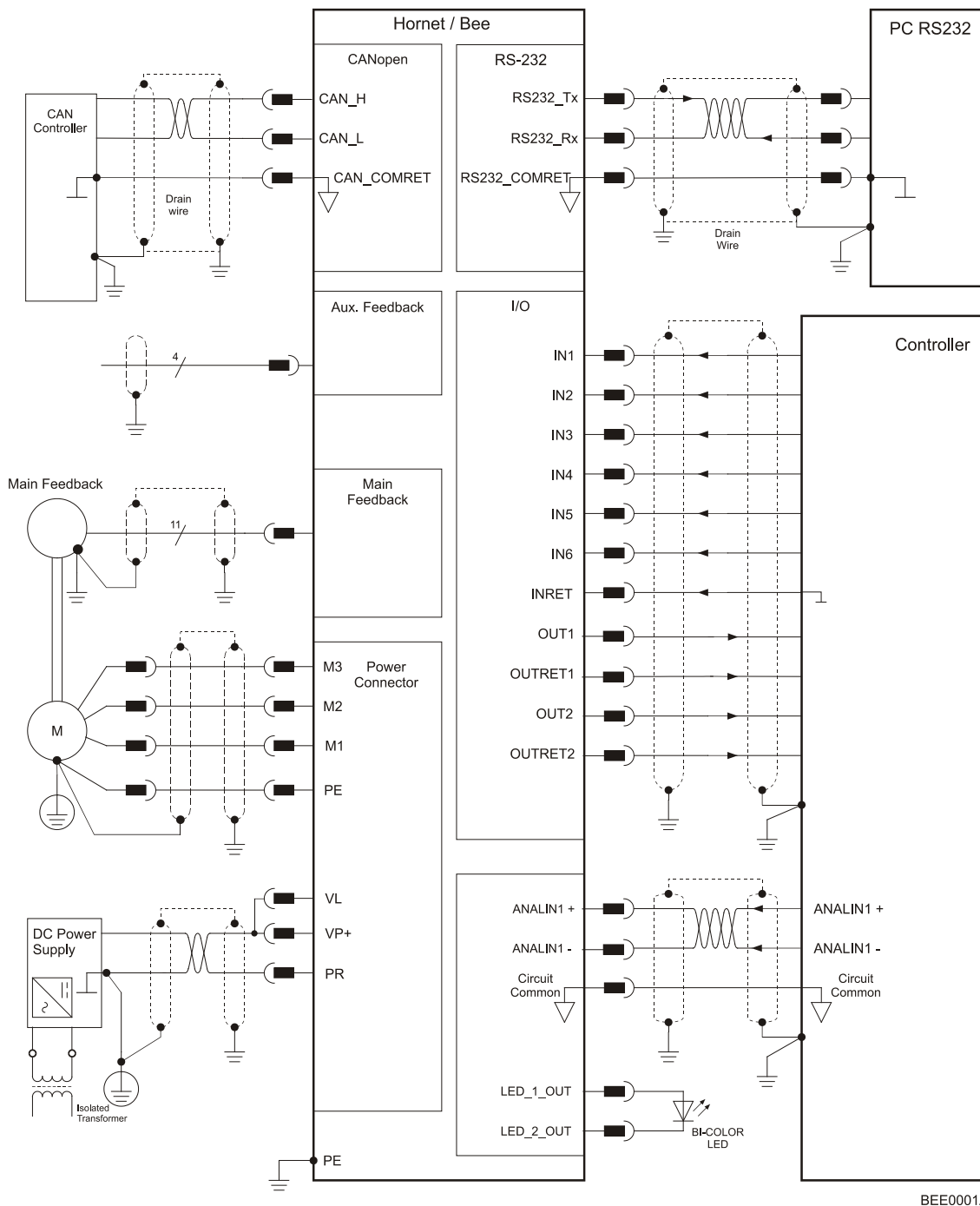
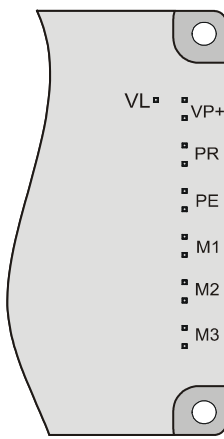


Figure 5: Hornet/Bee Connection Diagram

3.7. Main Power and Motor Power

The Hornet and Bee receive power from main and delivers power to the motor.

| Pin | Function | Cable | | Pin Positions |
|-----|------------------|----------|----------|---|
| VP+ | Pos. Power input | Power | |  |
| PR | Power return | Power | | |
| PE | Protective earth | Power | | |
| | | AC Motor | DC Motor | |
| PE | Protective earth | Motor | Motor | |
| M1 | Motor phase | Motor | N/C | |
| M2 | Motor phase | Motor | Motor | |
| M3 | Motor phase | Motor | Motor | |

Note: When connecting several drives to several motors, all should be wired in the same motor phases and feedback sequences. This will enable the same **ExtriQ** program to run on all drives.

Table 2: Connector for Main Power and Motor

3.7.1. Connecting Motor Power

Connect the M1, M2, M3 and PE pins on the Hornet/Bee in the manner described in Section 3.5 (Integrating the Hornet or Bee on a PCB). The phase connection is arbitrary as the Composer will establish the proper commutation automatically during setup. However, if you plan to copy the setup to other drives, then the phase order on all copy drives must be the same.

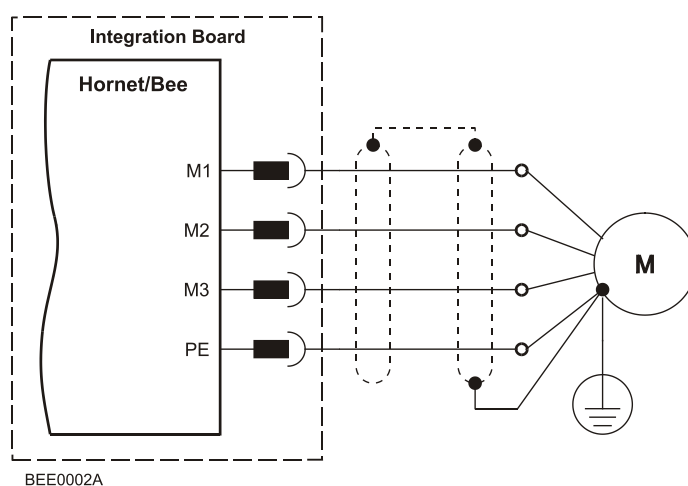


Figure 6: AC Motor Power Connection Diagram

3.7.2. Connecting Main Power

Connect the VP+, PR and PE pins on the Hornet/Bee in the manner described in Section 3.5 (Integrating the Hornet or Bee on a PCB).

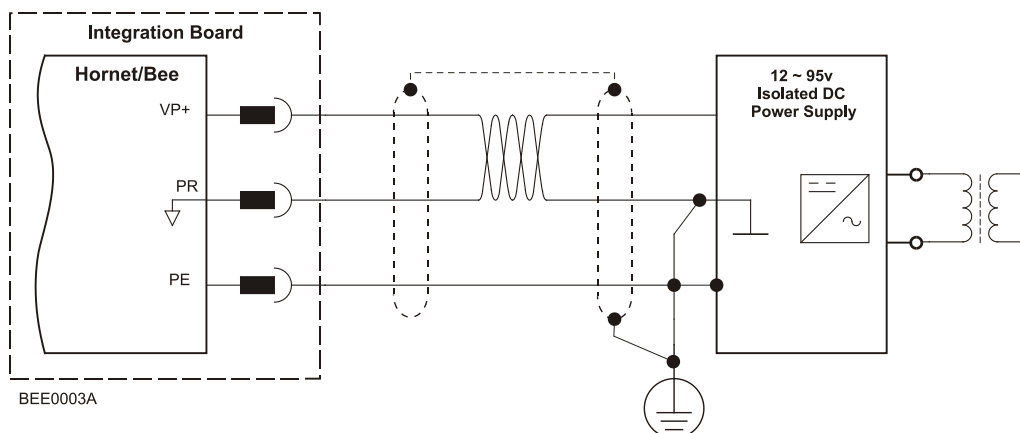


Figure 7: Main Power Supply Connection Diagram

3.8. Auxiliary Supply (for drive logic)

Notes for 11 to 95 VDC auxiliary supply connections:

Connect the VL and PR pins on the Hornet/Bee in the manner described in Section 3.5 (Integrating the Hornet or Bee on a PCB).

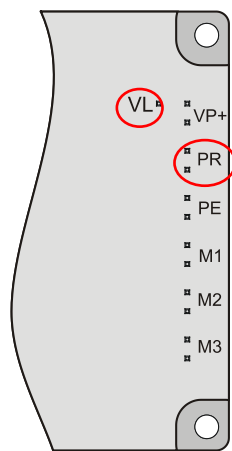

| Pin | | Function | Pin Positions |
|---|--|------------------------|--|
| VL | | Auxiliary Supply Input |  |
| PR | | Supply Input Return | |
| <div></div> <div>Caution: Power from the Hornet/Bee to the motor must come from the Main Supply and NOT from the Auxiliary Supply.</div> | | | |

Table 3: Auxiliary Supply Pins

3.8.1. Single Supply

A single isolated DC power supply can provide power for both the main power and the Auxiliary (Drive Logic) Supply. The drawing below shows how a single supply is connected.

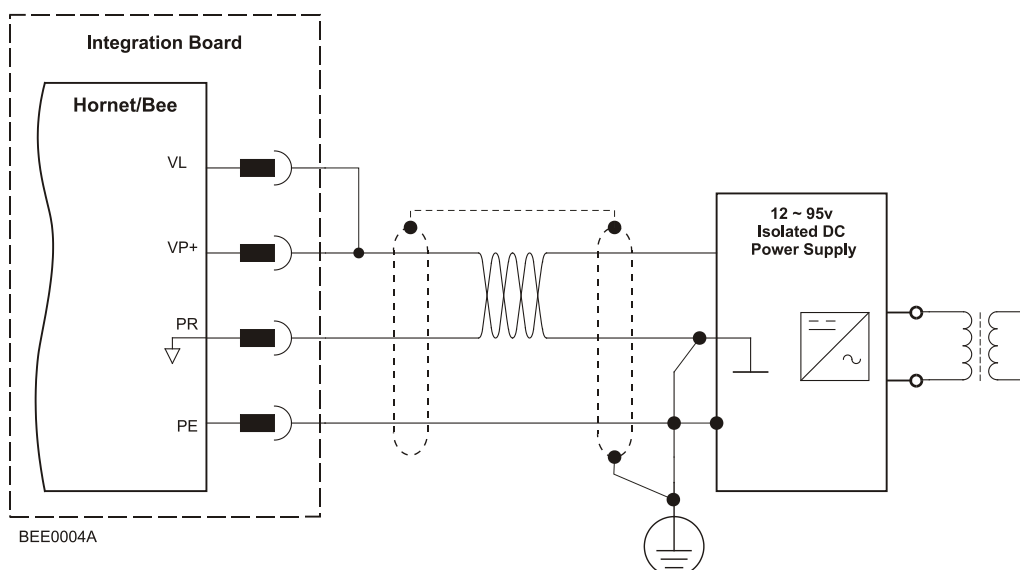


Figure 8: Single Supply for both the Main Power Supply and the Auxiliary Supply

3.8.2. Separate Auxiliary Supply

Power to the Auxiliary Supply can be provided by a separate Auxiliary Supply.

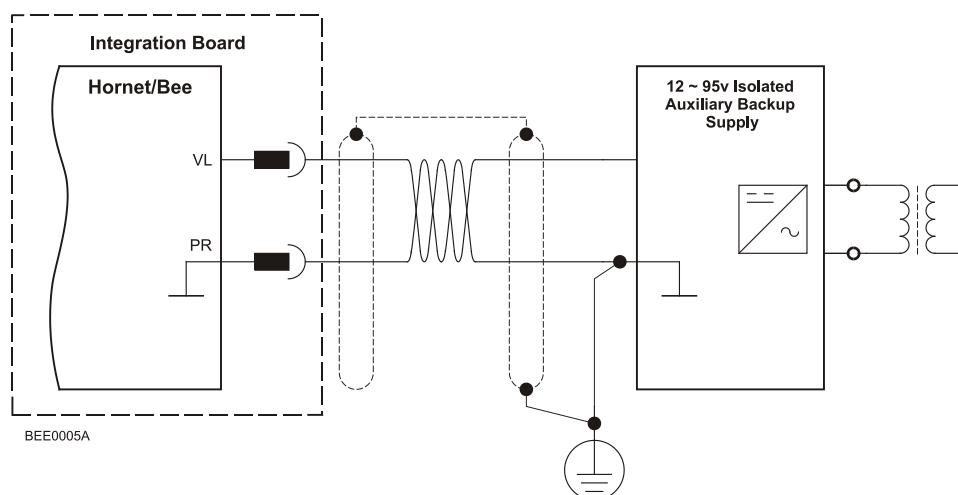


Figure 9: Separate Auxiliary Supply Connection Diagram

3.8.3. Shared Supply

A "Main" DC Power Supply can be designed to supply power to the drive's Logic as well as to the Main Power (see Figure 8). If backup functionality is required (for storing control parameters in case of power-outs) an additional backup supply can be connected by implementing 'diode coupling' (see the Auxiliary Backup Supply in Figure 10).

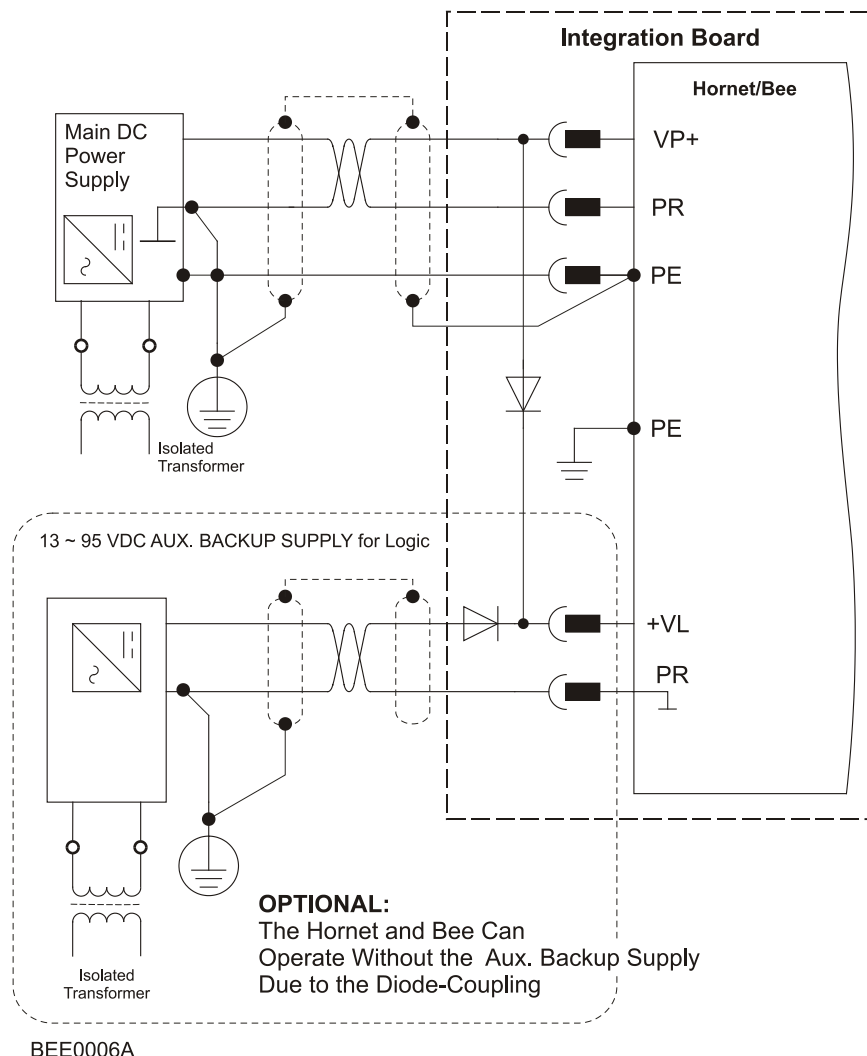


Figure 10: Shared Supply Connection Diagram



3.9. Main Feedback

The Main Feedback port is used to transfer feedback data from the motor to the drive. In order to copy the setup to other drives, the phase order on all copy drives must be the same.

The Hornet and Bee can accept any one the following devices as a main feedback mechanism:

- Incremental encoder only
- Incremental encoder with digital Hall sensors
- Digital Hall sensors only
- Interpolated Analog (Sine/Cosine) encoder (option)
- Resolver (option)
- Tachometer (option)

| | Incremental Encoder | | Interpolated Analog Encoder | | Resolver | | Tachometer and Potentiometer | |
|----------|---|-------------------------|-------------------------------|-------------------------|-------------------------------|--|-------------------------------|-------------------------------|
| | HOR-XX/YYYY_, BEE-XX/YYYY_ | | HOR-XX/YYYYI, BEE-XX/YYYYI | | HOR-XX/YYYYR, BEE-XX/YYYYR | | HOR-XX/YYYYT, BEE-XX/YYYYT | |
| Pin (J2) | Signal | Function | Signal | Function | Signal | Function | Signal | Function |
| 13 | HC | Hall sensor C input | HC | Hall sensor C input | NC | - | HC | Hall sensor C input |
| 11 | HA | Hall sensor A input | HA | Hall sensor A input | NC | - | HA | Hall sensor A input |
| 2 | SUPRET | Supply return | SUPRET | Supply return | SUPRET | Supply return | SUPRET | Supply return |
| 1 | +5V | Encoder/Hall +5V supply | +5V | Encoder/Hall +5V supply | +5V | Encoder/Hall +5V supply | +5V | Encoder/Hall +5V supply |
| 6 | CHA- | Channel A complement | A- | Sine A complement | S3 | Sine A complement | Tac 1- | Tacho Input 1 Neg. (20 V max) |
| 5 | CHA | Channel A | A+ | Sine A | S1 | Sine A | Tac 1+ | Tacho Input 1 Pos. (20 V max) |
| 10 | INDEX- | Index complement | R- | Reference complement | R2 | Vref complmnt f= 1/TS, 50 mA Maximum | NC | - |
| 9 | INDEX | Index | R+ | Reference | R1 | Vref f=1/TS, 50 mA Max. | POT | Potentiometer Input (5 V Max) |
| 12 | HB | Hall sensor B input | HB | Hall sensor B input | NC | - | HB | Hall sensor B input |
| 8 | CHB- | Channel B complement | B- | Cosine B complement | S4 | Cosine B complement | Tac 2- | Tacho Input 2 Neg. (50 V max) |
| 7 | CHB | Channel B | B+ | Cosine B | S2 | Cosine B | Tac 2+ | Tacho Input 2 Pos. (50 V max) |
| 3 | ANALIN+ is used for Analog Input | | | | | | | |
| 4 | ANALIN- is used for Analog Input | | | | | | | |
| 14 | LED_2_OUT (AOKLED cathode) is used for LED indication | | | | | | | |
| 15 | LED_1_OUT (AOKLED anode) is used for LED indication | | | | | | | |

Table 4: Main Feedback Pin Assignments

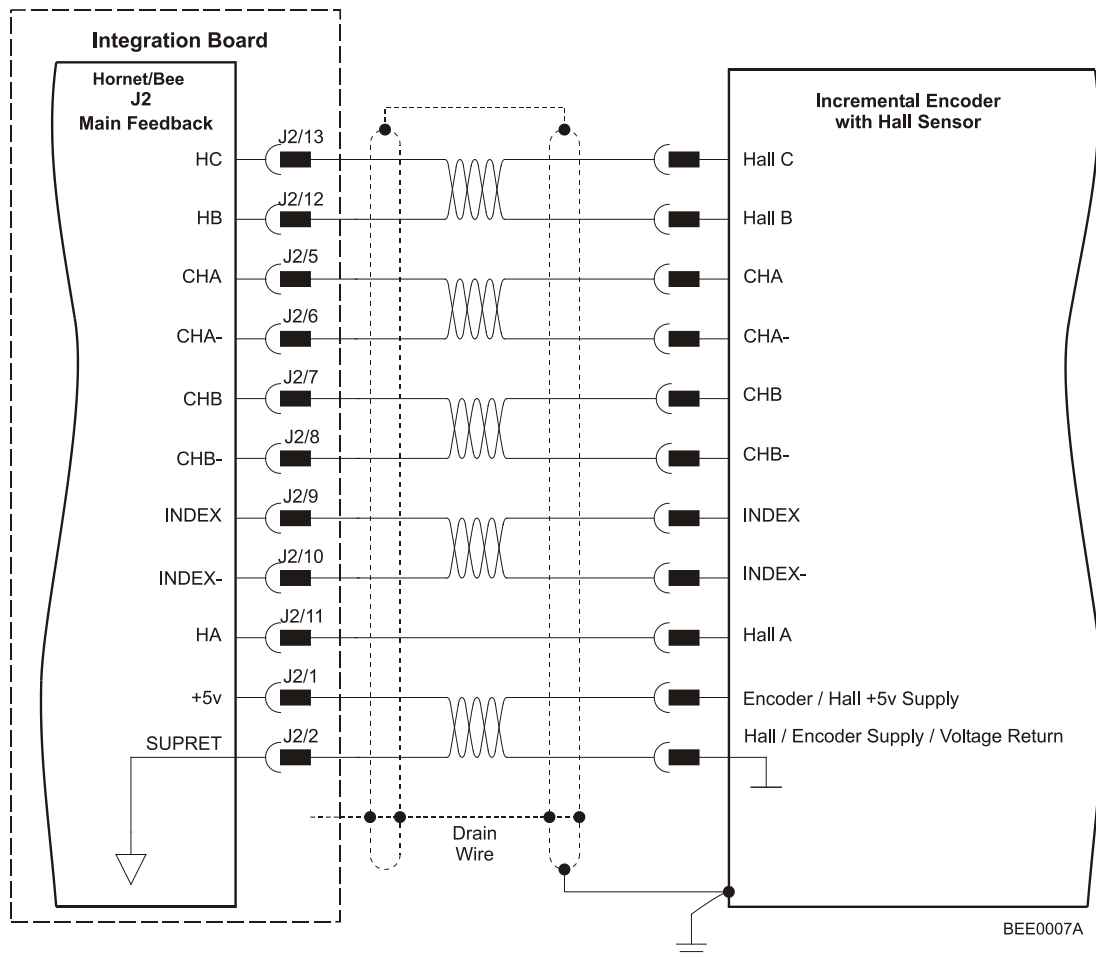


Figure 11: Main Feedback- Incremental Encoder Connection Diagram

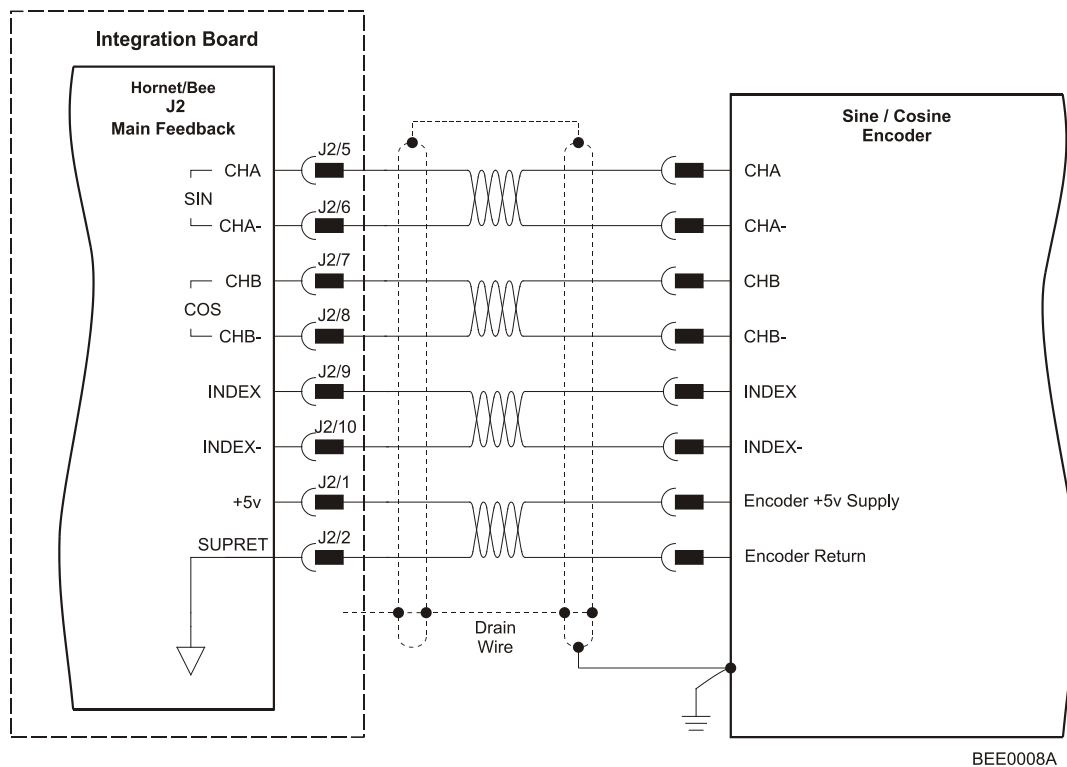


Figure 12: Main Feedback – Interpolated Analog (Sine/Cosine) Encoder Connection Diagram

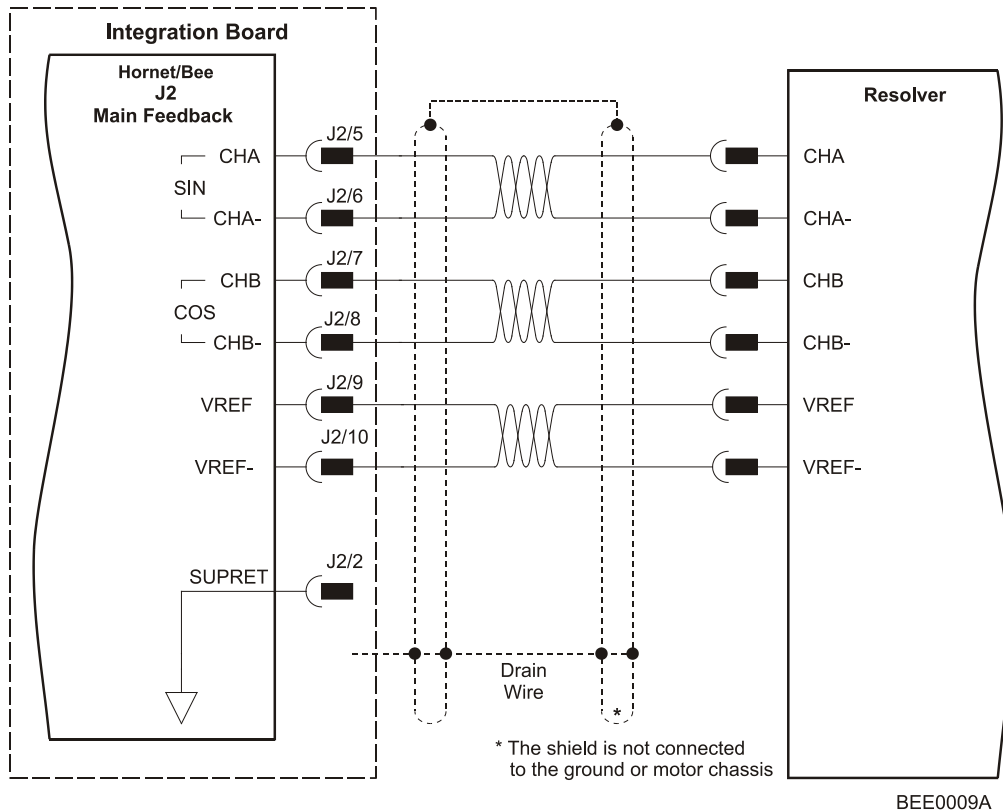
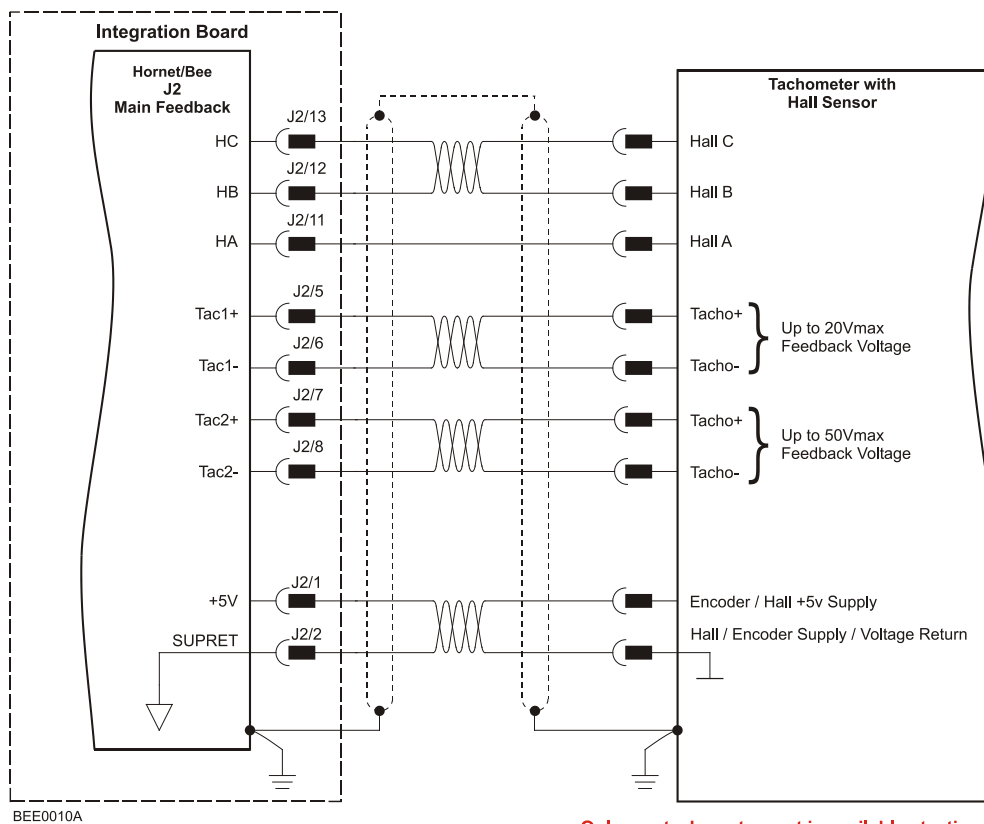


Figure 13: Main Feedback – Resolver Connection Diagram



Only one tachometer port is available at a time

Figure 14: Main Feedback – Tachometer Feedback with Digital Hall Sensor Connection Diagram for Brushless Motors

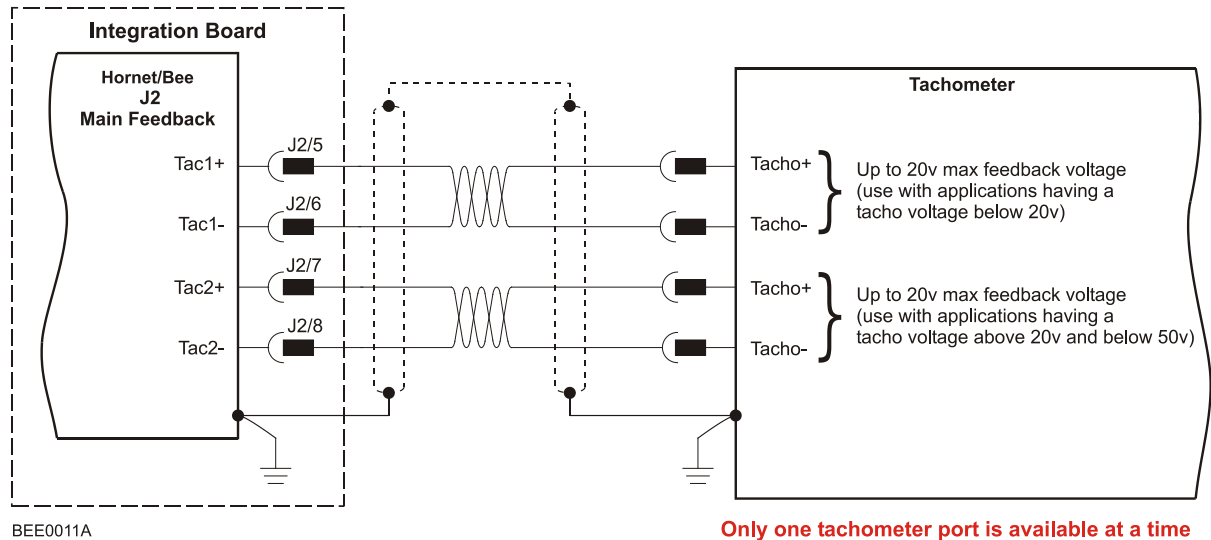


Figure 15: Main Feedback – Tachometer Feedback Connection Diagram for Brush Motors

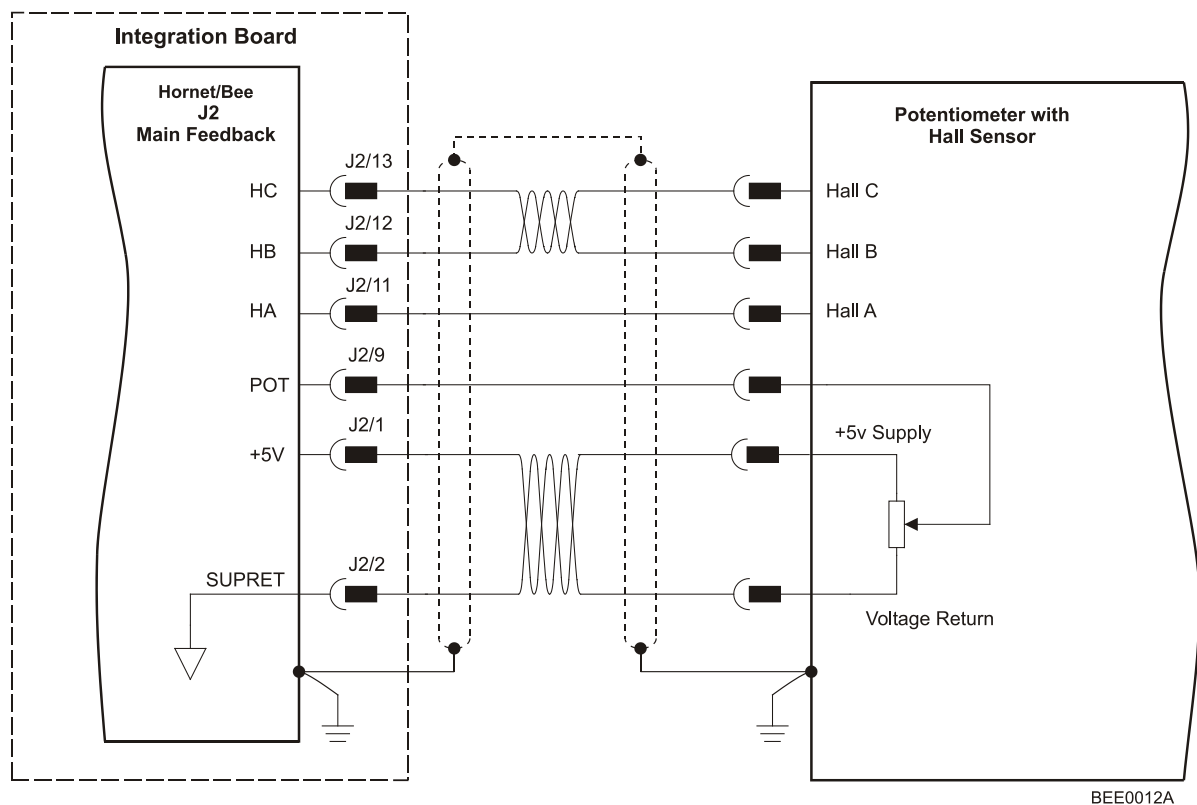
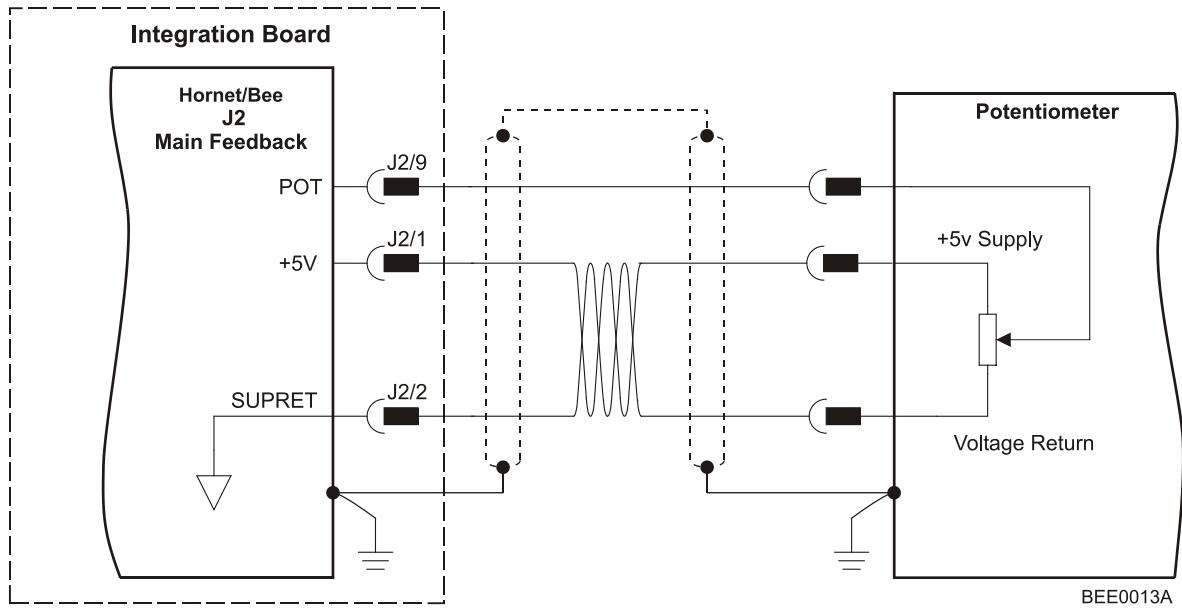


Figure 16: Main Feedback – Potentiometer Feedback with Digital Hall Sensor
Connection Diagram for Brushless Motors



BEE0013A

**Figure 17: Main Feedback –
Potentiometer Feedback Connection Diagram for Brush Motors and Voice Coils**

3.10. Auxiliary Feedback

For auxiliary feedback, select one of the following options:

- Single-ended emulated encoder outputs**, used to provide emulated encoder signals to another controller or drive. The Emulated Encoder Output Option is only available when using a Resolver or Analog Encoder as the main feedback device.

This option can be used when:

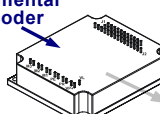
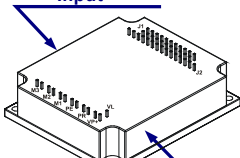
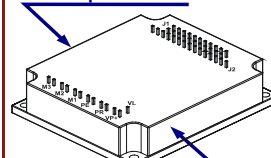
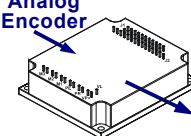
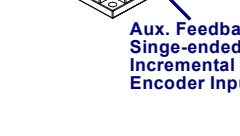

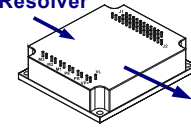
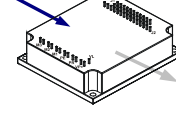
- The Hornet and Bee are used as current amplifiers to provide position data to the position controller.
 - The Hornet and Bee are used in velocity mode to provide position data to the position controller.
 - The Hornet and Bee are used as masters in follower or ECAM mode.
- Single-ended auxiliary encoder input**, for the input of position data of the master encoder in follower or ECAM mode.
 - Pulse-and-direction input**, for single-ended input of pulse-and-direction position commands.

When using one of the auxiliary feedback options, the relevant functionality is software selected for that option. Refer to the *SimplIQ Command Reference Manual* for detailed setup information.



3.10.1. Main and Auxiliary Feedback Combinations

The Main Feedback is always used in motion control devices whereas Auxiliary Feedback is often, but not always used. The Auxiliary Feedback connector on the Hornet/Bee has three bi-directional pins (CHA, CHB and INDEX). When used in combination with Main Feedback, the Auxiliary Feedback can be set, by software, as follows:

| Main Feedback | Auxiliary Feedback | | |
|---|---|--|--|
| | YA[4] = 4 (Aux. Feedback: output) | YA[4] = 2 (Aux. Feedback: input) | YA[4] = 0 (Aux. Feedback: input) |
| Incremental Encoder Input | ★ Main Feedback: Incremental Encoder  Aux. Feedback: There is no Auxiliary Feedback output option when an Incremental Encoder is the main feedback device | Main Feedback: Incremental Encoder or Analog Encoder or Resolver or Tachometer or Potentiometer Input  | Main Feedback: Incremental Encoder or Analog Encoder or Resolver or Tachometer or Potentiometer Input  |
| Interpolated Analog (Sine/Cosine) Encoder Input | ★ Main Feedback: Analog Encoder  Aux. Feedback: Analog Encoder position data emulated in single-ended, unbuffered Incremental Encoder format | Aux. Feedback: Single-ended Incremental Encoder Input  | Aux. Feedback: Single-ended Pulse & Direction Commands Input  |
| Resolver Input | ★ Main Feedback: Resolver  Aux. Feedback: Resolver position data emulated in single-ended, unbuffered Incremental Encoder format | | |
| Potentiometer Tachometer Input | Main Feedback: Potentiometer or Tachometer  Aux. Feedback: There is no Aux. Feedback output option when a Potentiometer or Tachometer is the main feedback device | | |
| Typical Applications | <ul style="list-style-type: none"> ★ Any application where the main encoder is used, not only for the drive, but also for other purposes such as position controllers and/or other drives. ★ Analog Encoder applications where position data is required in the Encoder's quadrature format. ★ Resolver applications where position data is required in the Encoder's quadrature format. | <p>Any application where two feedbacks are used by the drive.</p> <p>The Auxiliary Feedback port serves as an input for the auxiliary incremental encoder.</p> <p>For applications such as Follower, ECAM, or Dual Loop.</p> | <p>Any application where two feedbacks are used by the drive.</p> <p>The Auxiliary Feedback port serves as an input for Pulse & Direction Commands.</p> |

3.10.2. Auxiliary Feedback: Emulated Encoder Output Option (YA[4]=4)

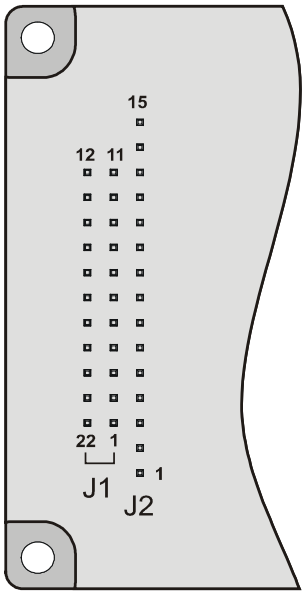
| Pin (J1) | Signal | Function | Pin Positions |
|--|--------|------------------|---|
| 4 | SUPRET | Supply return |  |
| 19 | INDEX+ | Index output | |
| 18 | CHBO | Channel B output | |
| 5 | CHAO | Channel A output | |
| Notes: <ul style="list-style-type: none"> The Emulated Encoder Output Option is only available when using a Resolver or Analog Encoder as the main feedback device. The Hornet/Bee's Auxiliary Feedback is single-ended. When mounted on an integration board, circuitry can be added to make it differential (Figure 20 (highly recommended)). | | | |

Table 5: Emulated Single-Ended Encoder Output Pin Assignments

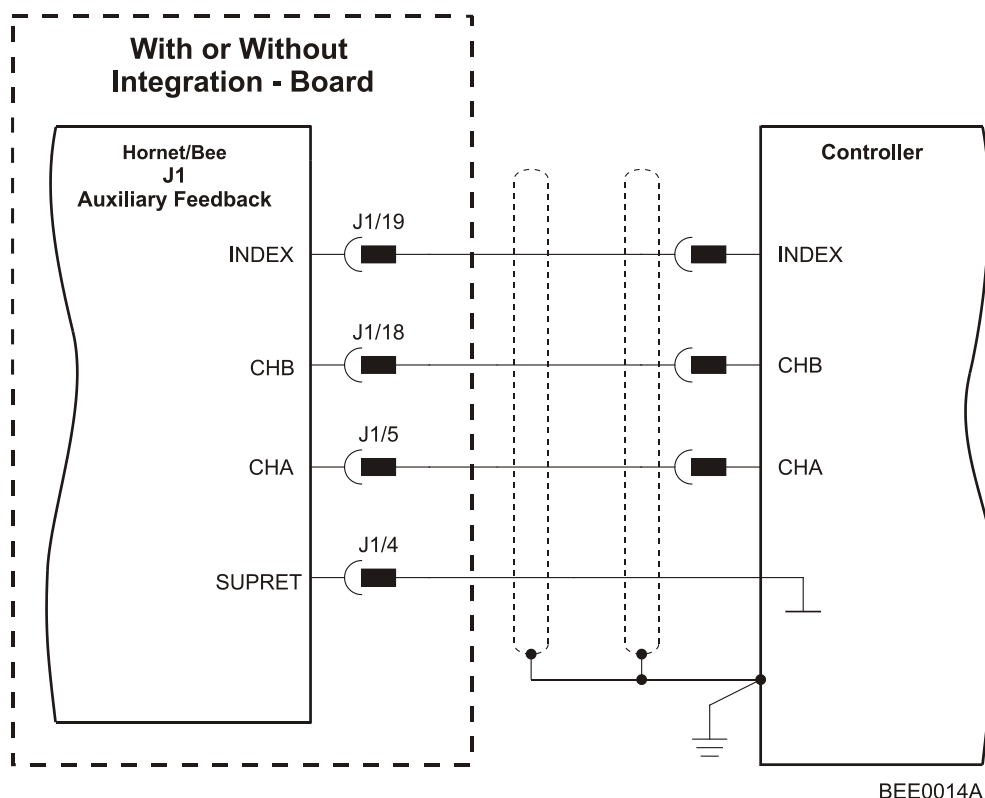


Figure 18: Emulated Encoder Direct Output – Acceptable Connection Diagram

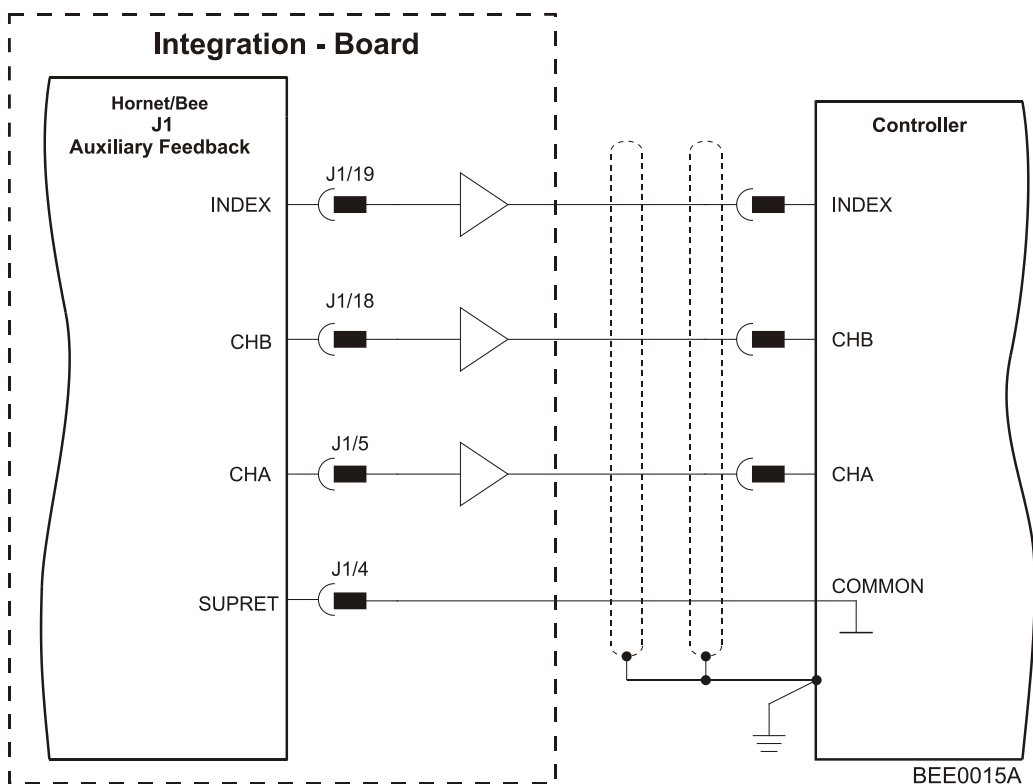


Figure 19: Emulated Encoder Buffered Output – Recommended Connection Diagram

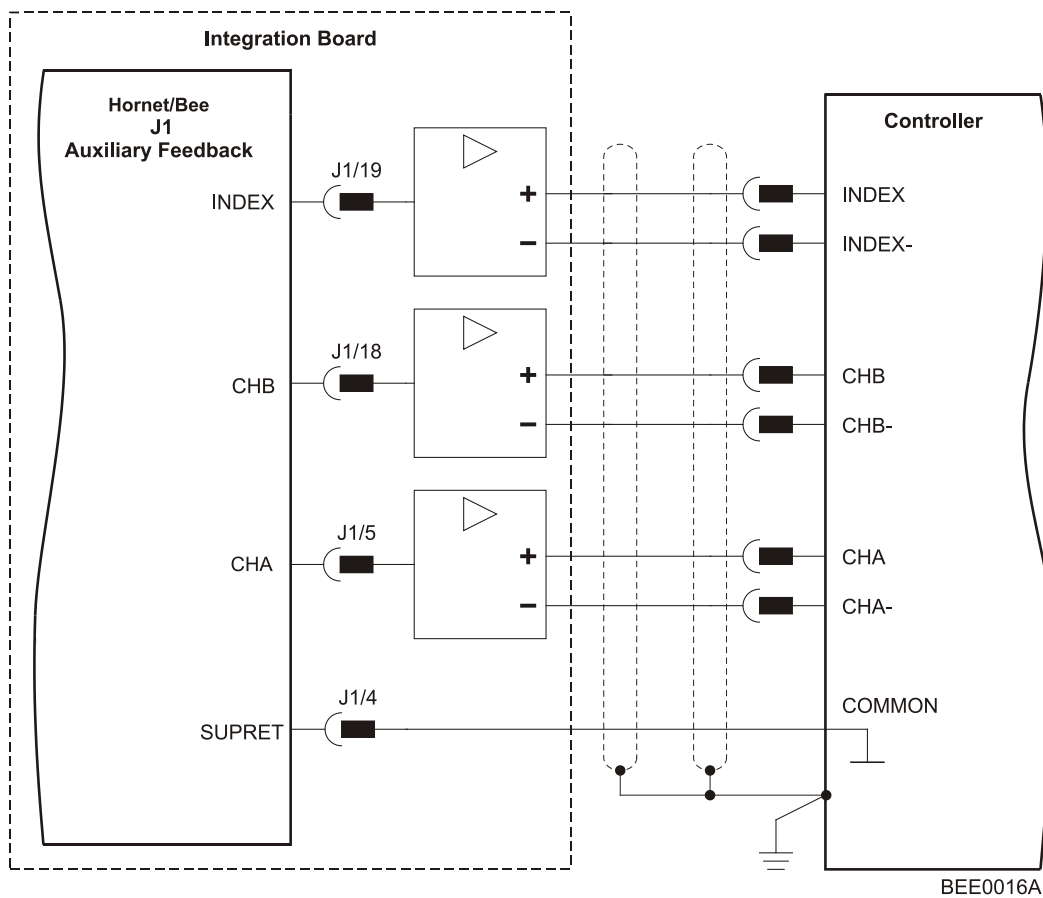


Figure 20: Emulated Encoder Differential Output – Highly Recommended Connection Diagram



3.10.3. Auxiliary Feedback: Single-Ended Encoder Input Option (YA[4]=2)

| Pin (J1) | Signal | Function | Pin Positions |
|--|--------|---------------------------|---------------|
| 4 | SUPRET | Supply return | |
| 19 | INDEX | Auxiliary index input | |
| 18 | CHB | Auxiliary channel B input | |
| 5 | CHA | Auxiliary channel A input | |
| Note: The Hornet/Bee's Auxiliary Feedback is single-ended. When mounted on an integration board, circuitry can be added to make it differential (Figure 23 (highly recommended)). | | | |

Table 6: Single-Ended Auxiliary Encoder Pin Assignment

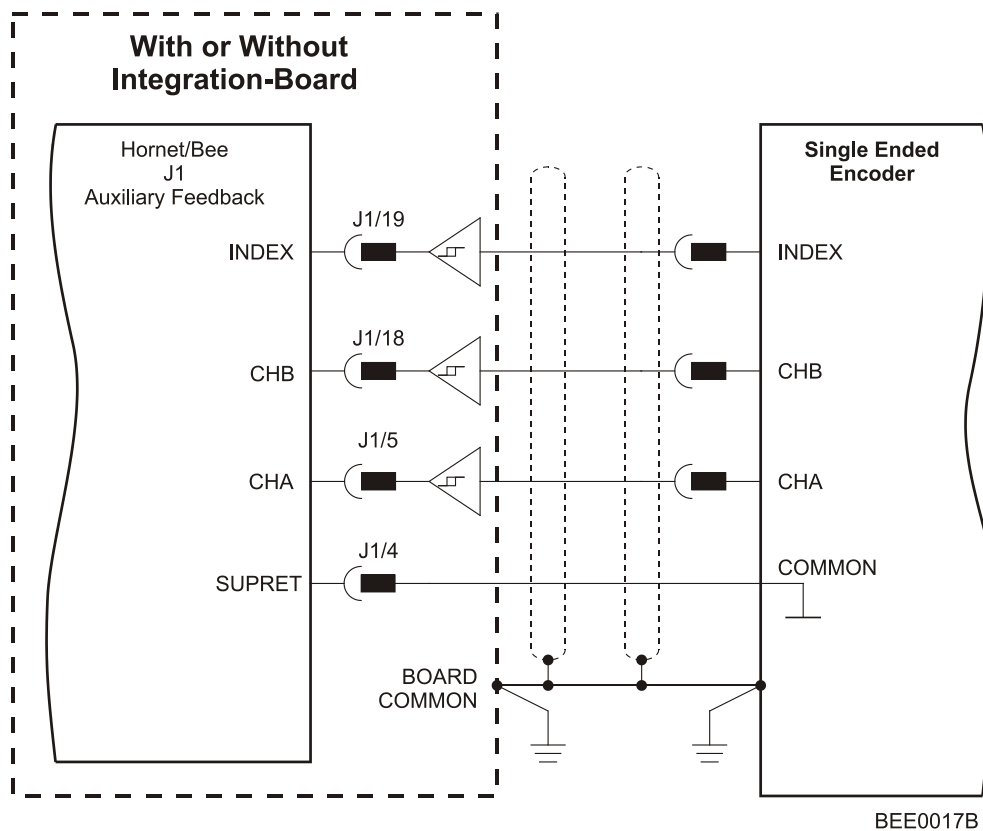


Figure 21: Single-Ended Auxiliary Encoder Input - Acceptable Connection Diagram

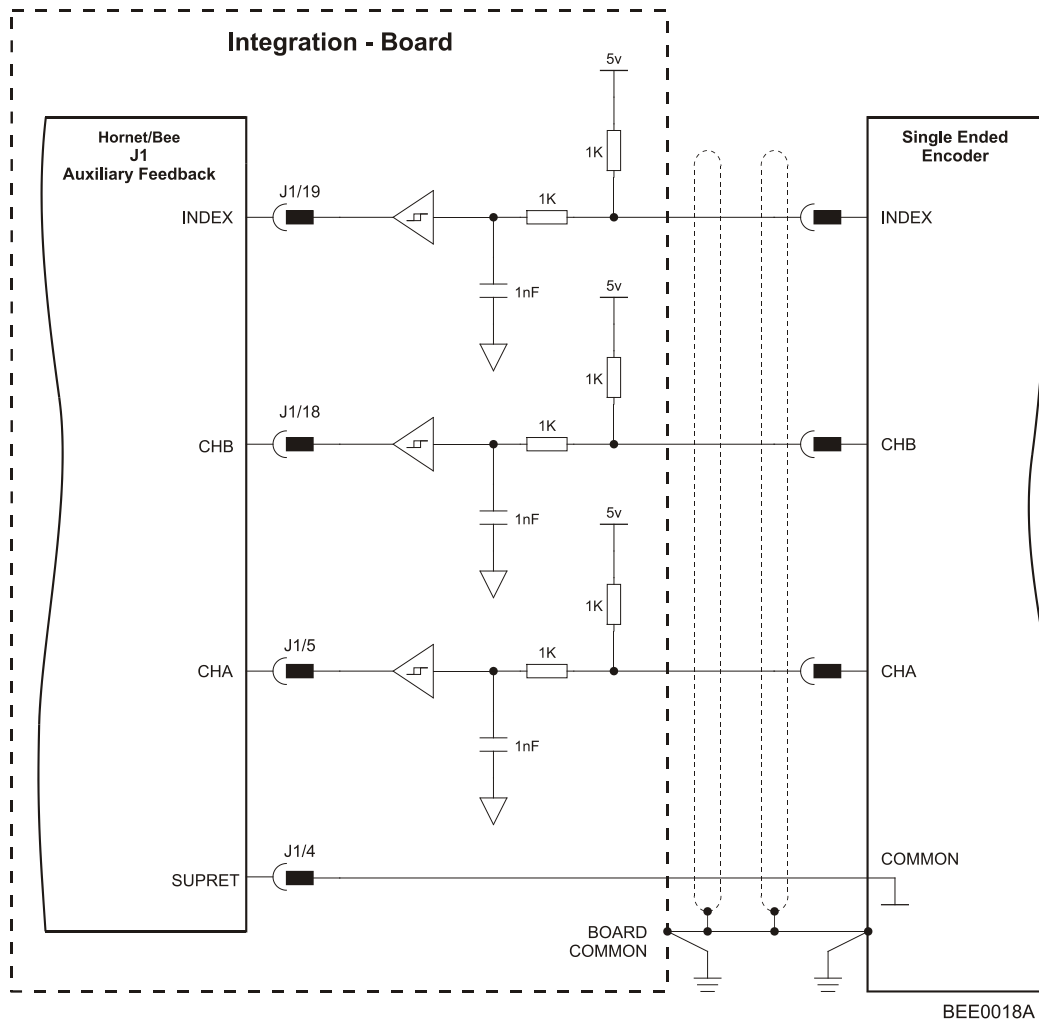


Figure 22: Single-ended Auxiliary Encoder Input - Recommended Connection Diagram

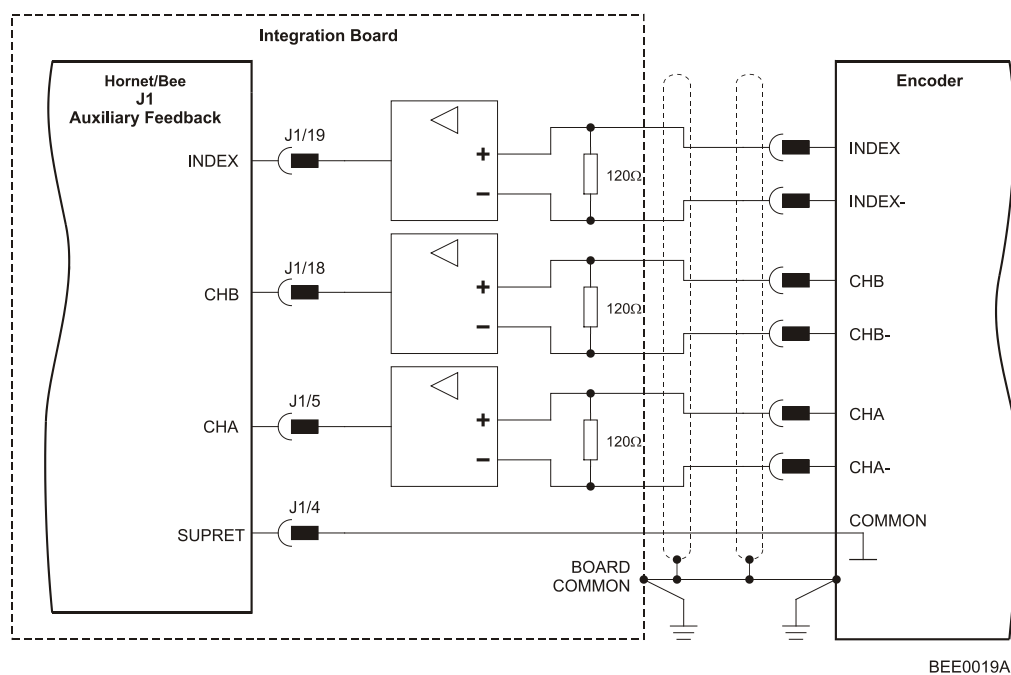


Figure 23: Differential Auxiliary Encoder Input – Highly Recommended Connection Diagram

3.10.4. Auxiliary Feedback: Pulse-and-Direction Input Option (YA[4]=0)

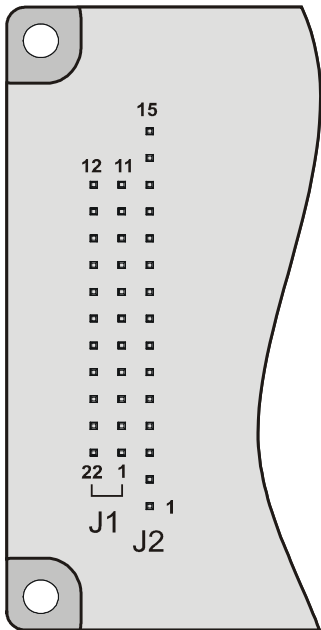
| Pin (J1) | Signal | Function | Pin Positions |
|---|----------|---|---|
| 4 | SUPRET | Supply return |  |
| 18 | DIR/CHB | Direction input (push/pull 5 V or open collector) | |
| 5 | PULS/CHA | Pulse input (push/pull 5 V or open collector) | |
| Note: The Hornet/Bee's Auxiliary Feedback is single-ended. When mounted on an integration board, circuitry can be added to make it differential (Figure 26). | | | |

Table 7: Pulse-and-Direction Pin Assignments

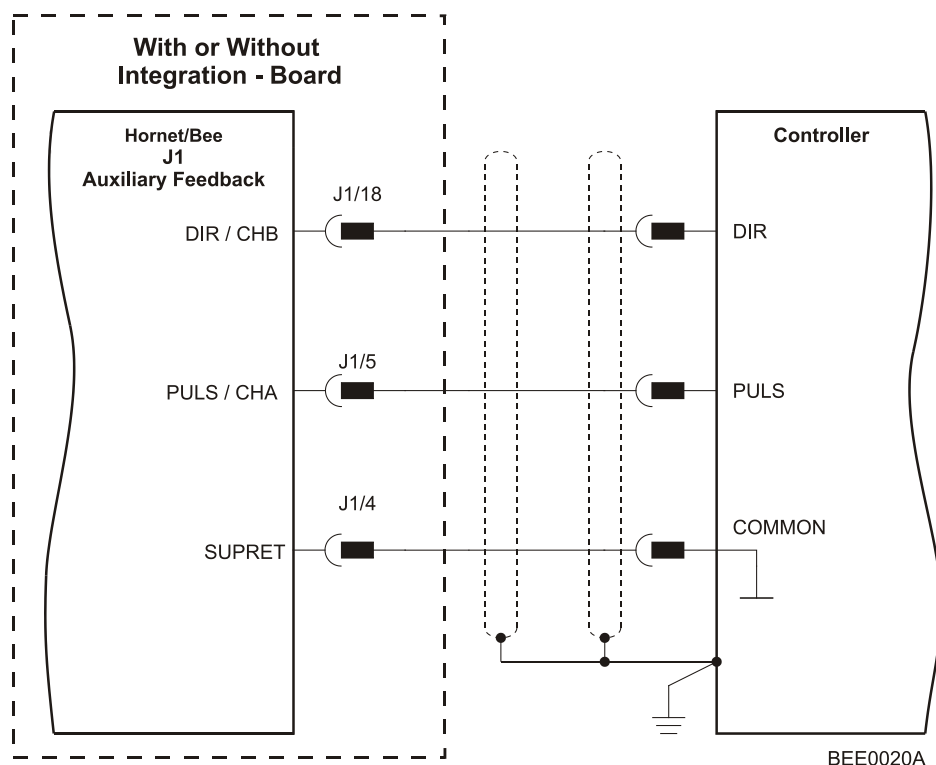


Figure 24: Pulse-and-Direction Auxiliary Encoder Input – Direct Connection Diagram

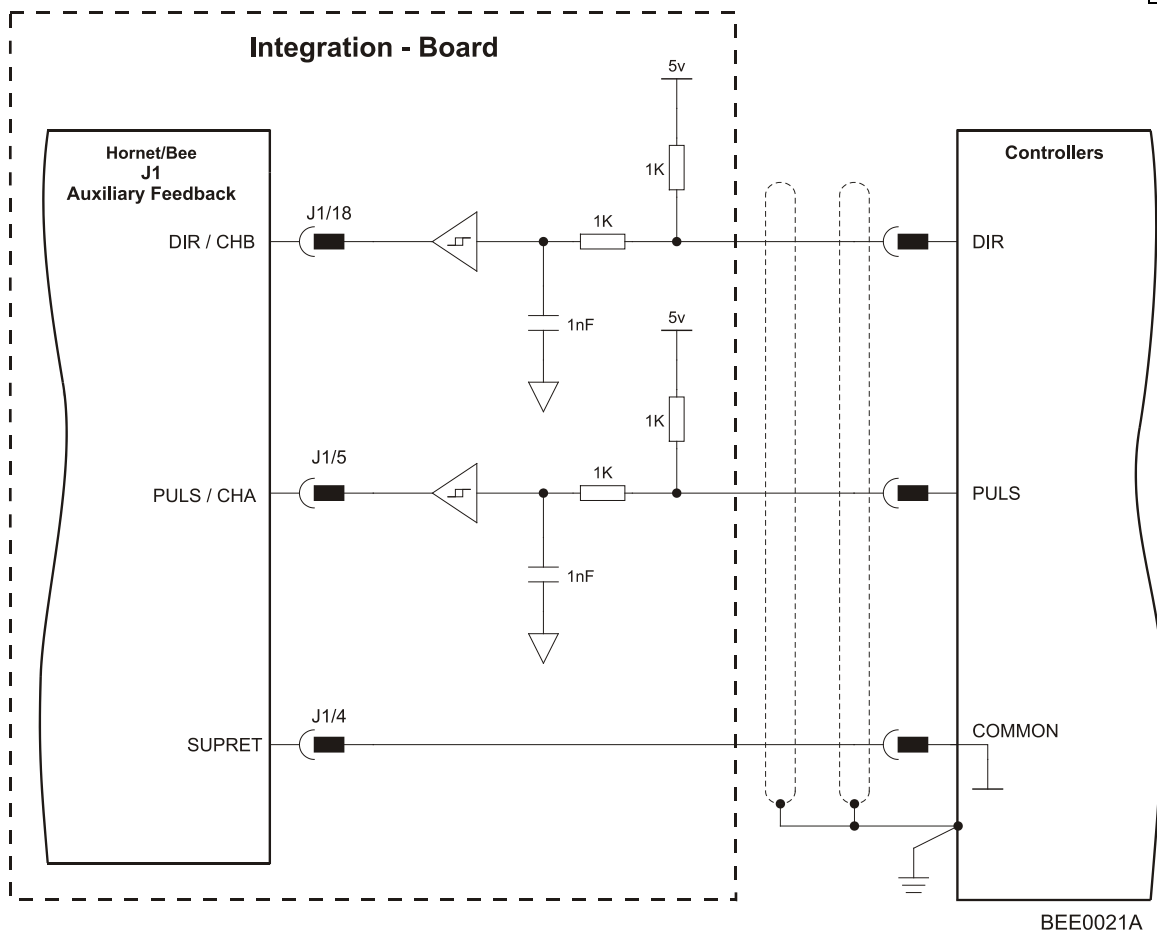


Figure 25: Pulse-and-Direction Auxiliary Encoder Input – Buffered Connection Diagram

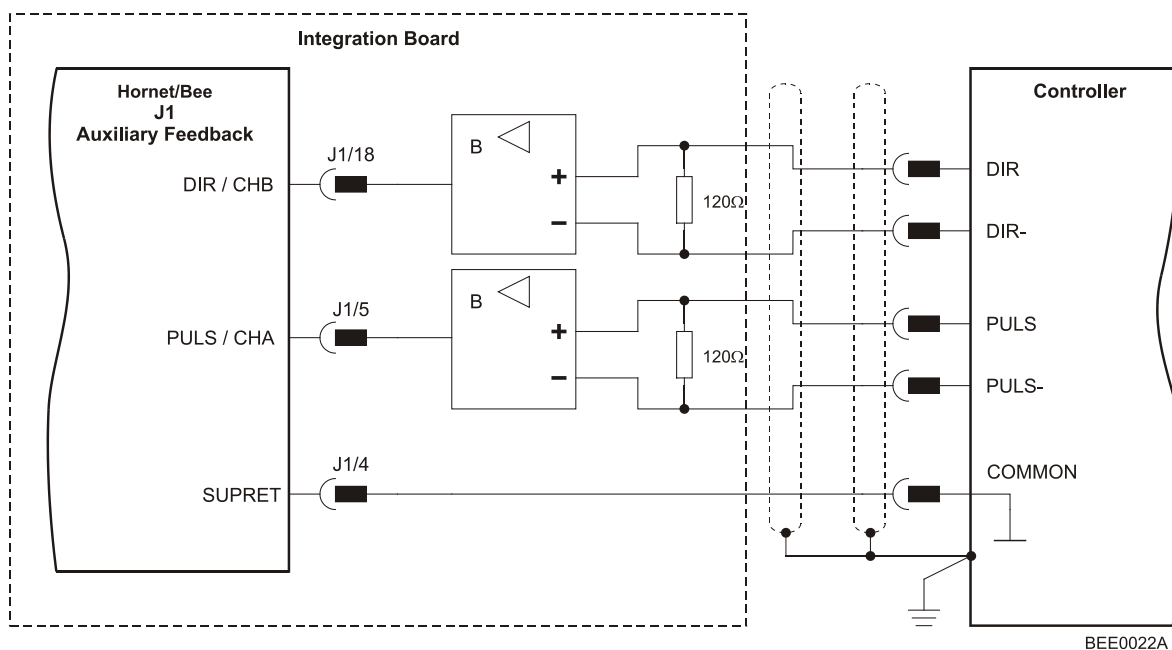


Figure 26: Pulse-and-Direction Auxiliary Encoder Input – Differential Connection Diagram

3.11. I/Os

The Hornet and Bee have:

- 6 Digital Inputs
- 2 Digital Outputs
- 1 Analog Input

| I/O | J1 | J2 | Total |
|----------------|----|----|-------|
| Digital Input | 6 | - | 6 |
| Digital Output | 2 | - | 2 |
| Analog Input | - | 1 | 1 |

3.11.1. Digital Input

Each of the pins below can function as an independent input.

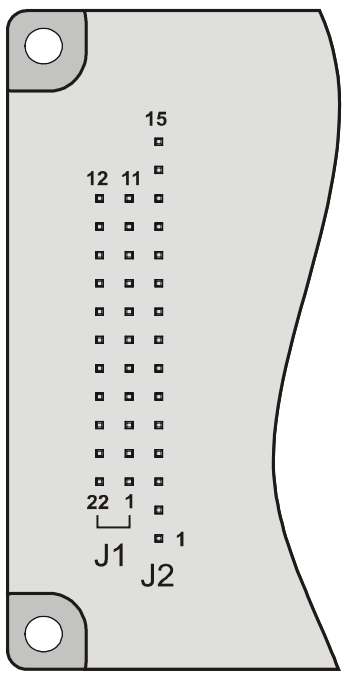
| Pin (J1) | Signal | Function | Pin Positions |
|----------|--------|---|---|
| 9 | IN1 | Programmable input 1 (general purpose, RLS, FLS, INH) |  |
| 10 | IN2 | Programmable input 2 (general purpose, RLS, FLS, INH) | |
| 11 | IN3 | Programmable input 3 (general purpose, RLS, FLS, INH) | |
| 12 | IN4 | Programmable input 4 (general purpose, RLS, FLS, INH) | |
| 13 | IN5 | Hi-Speed Programmable input 5 (event capture, Main Home, general purpose, RLS, FLS, INH) | |
| 14 | IN6 | Hi-Speed Programmable input 6 (event capture, Auxiliary Home, general purpose, RLS, FLS, INH) | |
| 15 | INRET | Programmable input return | |

Table 8: Digital Input Pin Assignments

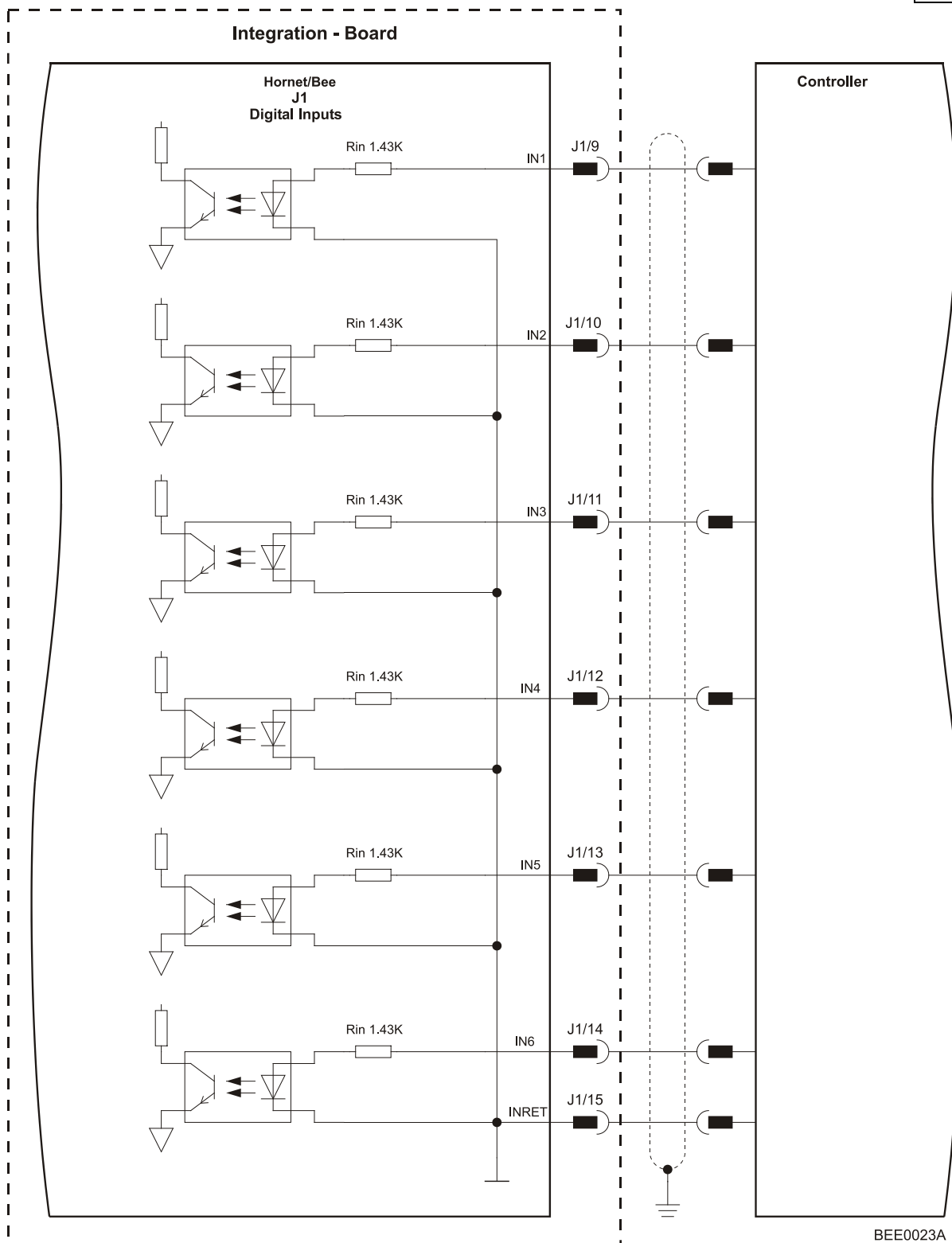


Figure 27: Digital Input Connection Diagram

3.11.2. Digital Output

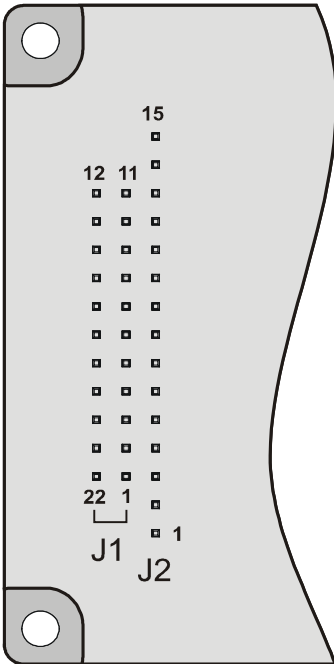
| Pin (J1) | Signal | Function | Pin Positions |
|----------|---------|--|---|
| 7 | OUT1 | High-Speed Programmable digital output 1 |  |
| 17 | OUTRET1 | Programmable digital output return 1 | |
| 8 | OUT2 | Programmable digital output 2 | |
| 16 | OUTRET2 | Programmable digital output return 2 | |

Table 9: Digital Output Pin Assignment

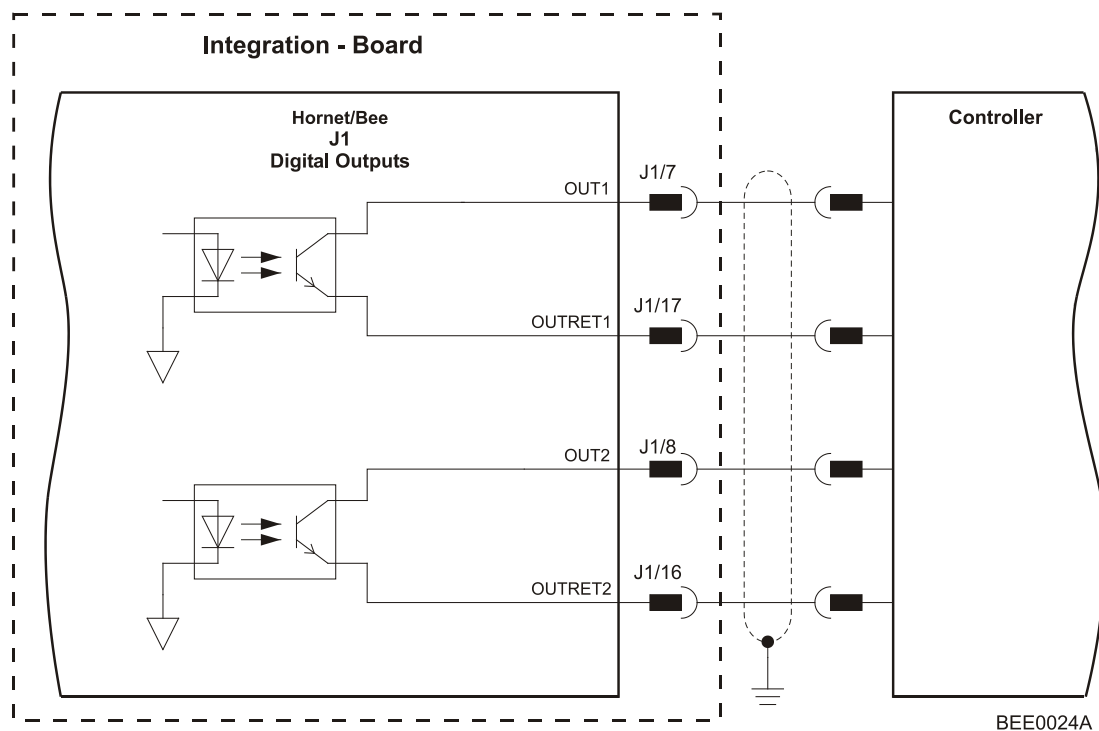


Figure 28: Digital Output Connection Diagram



3.11.3. Analog Input

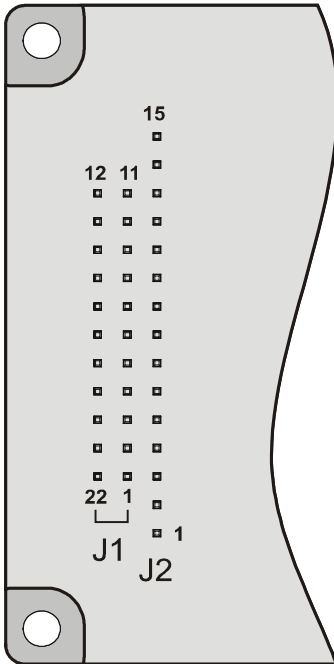
| Pin (J2) | Signal | Function | Pin Positions |
|----------|---------|-----------------|--|
| 3 | ANLIN1+ | Analog input 1+ |  |
| 4 | ANLIN1- | Analog input 1- | |
| 2 | ANLRET | Analog ground | |

Table 10: Analog Input Pin Assignments

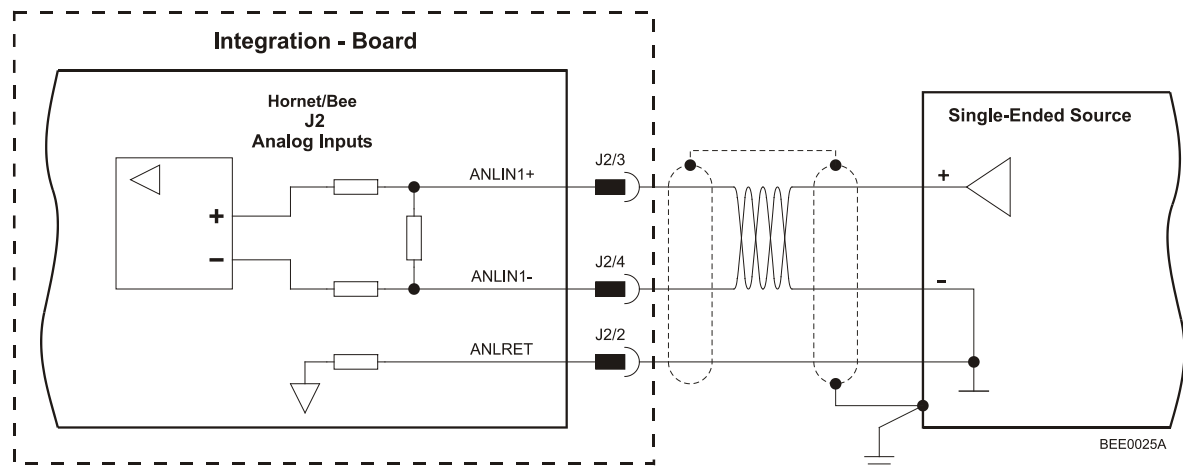


Figure 29: Analog Input with Single-Ended Source

3.12. Communications

The communication interface may differ according to the user's hardware. The Hornet and Bee can communicate using the following options:

- RS-232, full duplex
- CAN

RS-232 communication requires a standard, commercial 3-core null-modem cable connected from the Hornet or Bee to a serial interface on the PC. The interface is selected and set up in the Composer software.

In order to benefit from **CAN** communication, the user must have an understanding of the basic programming and timing issues of a CAN network.

For ease of setup and diagnostics of CAN communication, RS-232 and CAN can be used simultaneously.

3.12.1. RS-232 Communication

Notes for connecting the RS-232 communication cable:

- Connect the shield to the ground of the host (PC). Usually, this connection is soldered internally inside the connector at the PC end. You can use the drain wire to facilitate connection.
- The RS-232 communication port is **non-isolated**.
- Ensure that the shield of the cable is connected to the shield of the connector used for RS-232 communications. The drain wire can be used to facilitate the connection.

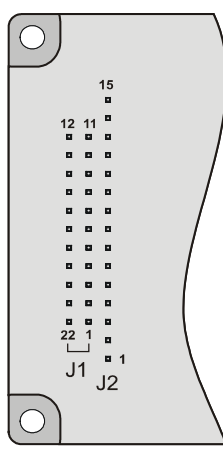
| Pin (J1) | Signal | Function | Pin Location |
|----------|--------------|----------------------|---|
| 1 | RS232_Rx | RS-232 receive |  |
| 2 | RS232_Tx | RS-232 transmit | |
| 3 | RS232_COMRET | Communication return | |

Table 11: RS-232 Pin Assignments

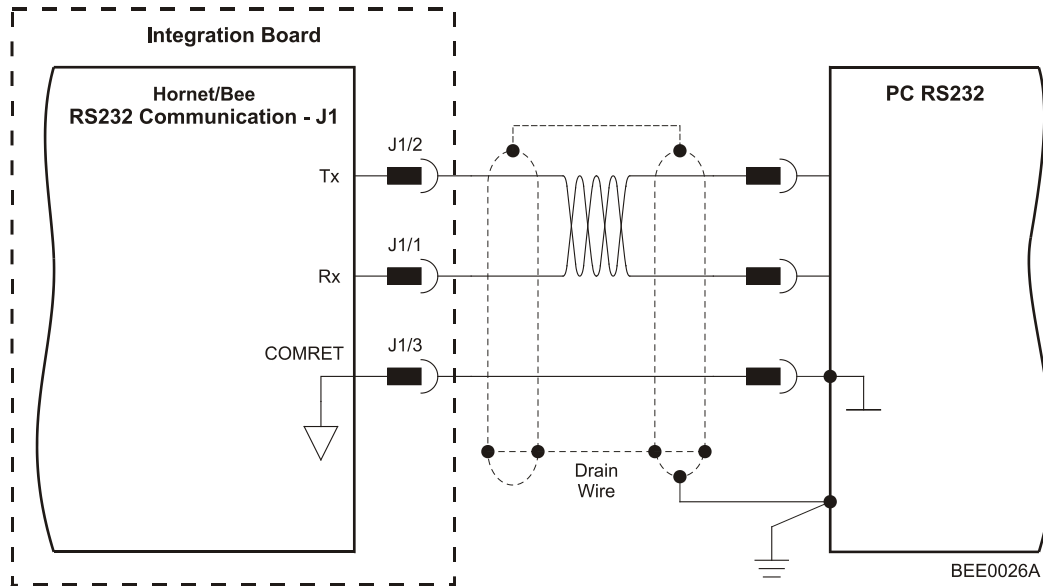


Figure 30: RS-232 Connection Diagram

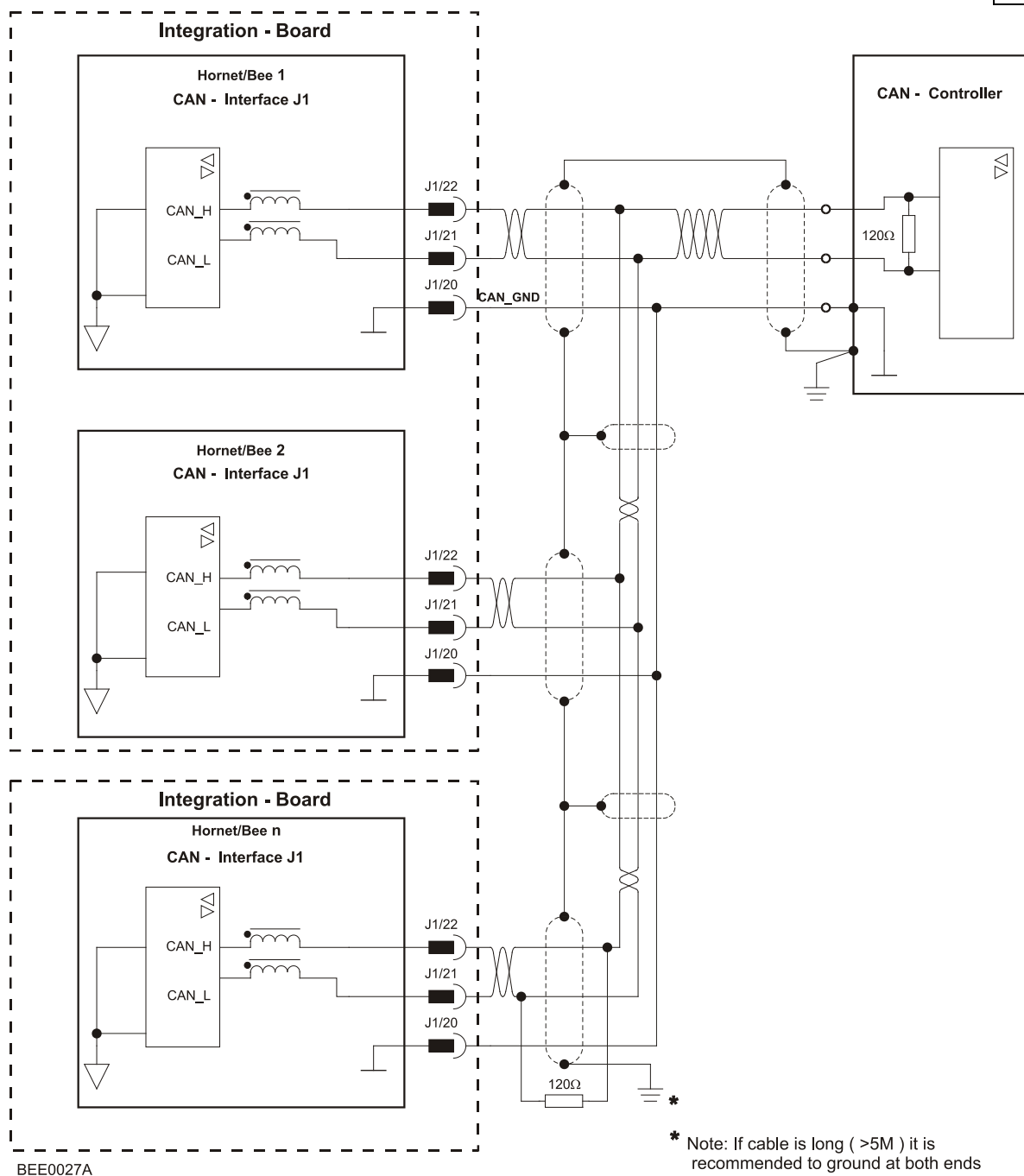
3.12.2. CAN Communication

Notes for connecting the CAN communication cable:

- Connect the shield to the ground of the host (PC). Usually, this connection is soldered internally inside the connector at the PC end. You can use the drain wire to facilitate connection.
- Ensure that the shield of the cable is connected to the shield of the connector used for communications. The drain wire can be used to facilitate the connection.
- Make sure to have a 120-Ω resistor termination at each of the two ends of the network cable.
- The Hornet and Bee's CAN ports are **non-isolated**.

| Pin (J1) | Signal | Function | Pin Positions |
|----------|---------|-------------------------------|---------------|
| 20 | CAN_GND | CAN ground | |
| 21 | CAN_L | CAN_L busline (dominant low) | |
| 22 | CAN_H | CAN_H busline (dominant high) | |

Table 12: CAN - Pin Assignments



BEE0027A

Figure 31: CAN Network Diagram

**Caution:**

When installing CAN communication, ensure that each servo drive is allocated a unique ID. Otherwise, the CAN network may hang.



3.13. Powering Up

After the Hornet or Bee is connected to its device, it is ready to be powered up.



Caution:

Before applying power, ensure that the DC supply is within the specified range and that the proper plus-minus connections are in order.

3.14. Initializing the System

After the Hornet or Bee has been connected and mounted, the system must be set up and initialized. This is accomplished using the *Composer*, Elmo's Windows-based software application. Install the application and then perform setup and initialization according to the directions in the *Composer Software Manual*.

3.15. Heat Dissipation

3.15.1. Hornet Thermal Data

The best way to dissipate heat from the Hornet is to mount it so that its heatsink faces up. For best results leave approximately 10 mm of space between the Hornet's heatsink and any other assembly.

3.15.1.1. Hornet Thermal Data

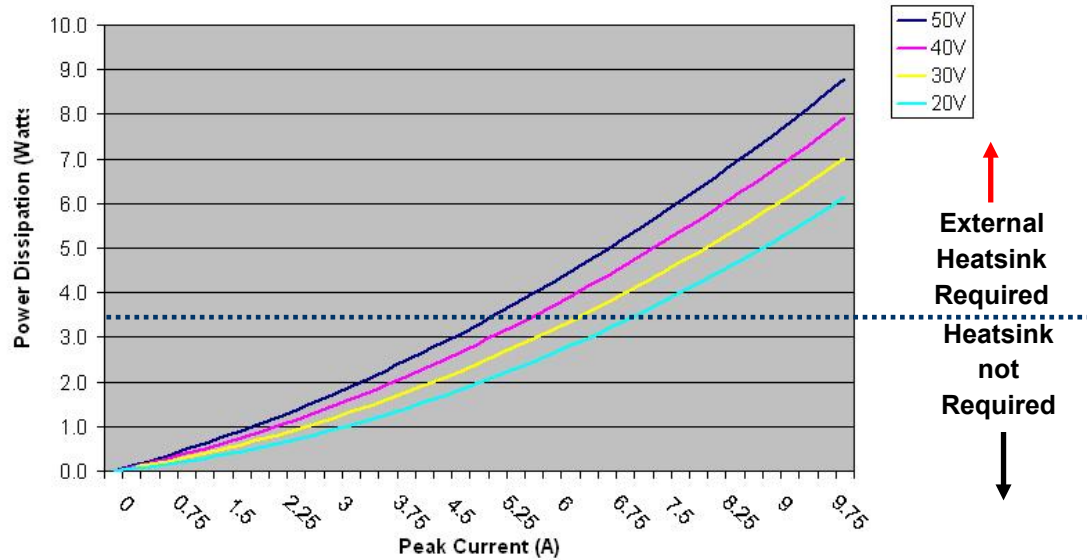
- Heat dissipation capability (θ): Approximately 10 °C/W.
- Thermal time constant: Approximately 240 seconds (thermal time constant means that the Hornet will reach 2/3 of its final temperature after 4 minutes).
- Shut-off temperature: 86 °C to 88 °C (measured on the heatsink)



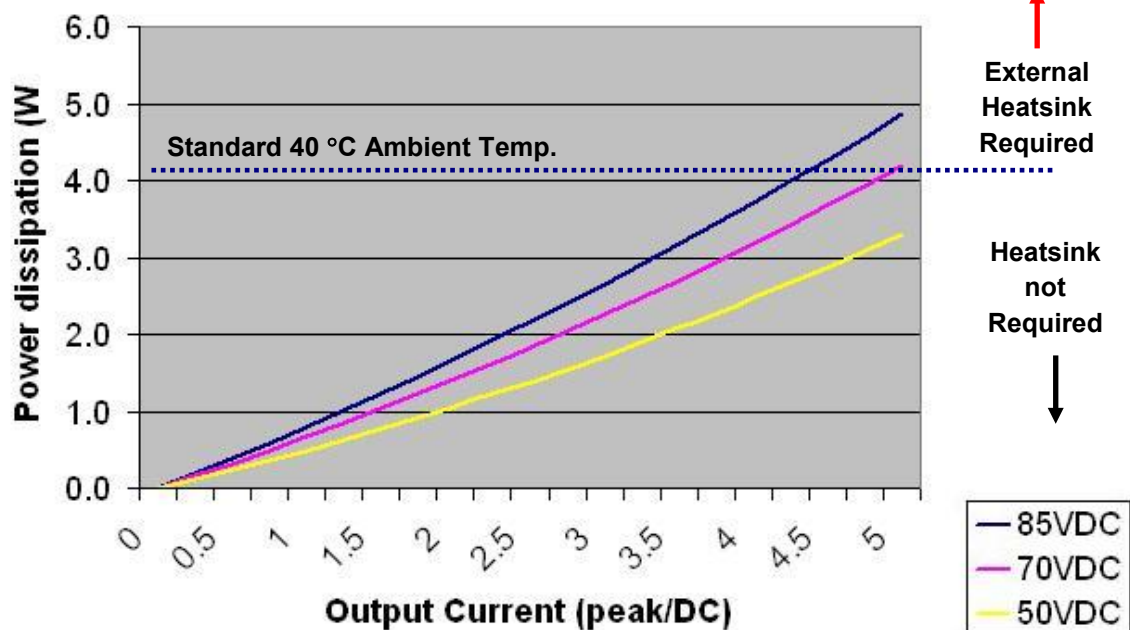
3.15.1.2. Heat Dissipation Data

Heat Dissipation is shown in graphically below:

Hornet - 60 Series Power Dissipation



Hornet-100 Power Dissipation





3.15.1.3. How to Use the Charts

The charts above are based upon theoretical worst-case conditions. Actual test results show 30% to 50% better power dissipation.

To determine if your application needs a heatsink:

1. Allow maximum heatsink temperature to be 80 °C or less.
2. Determine the ambient operating temperature of the Hornet.
3. Calculate the allowable temperature increase as follows:
 - for an ambient temperature of 40 °C , $\Delta T = 80\text{ °C} - 40\text{ °C} = 40\text{ °C}$
4. Use the chart to find the actual dissipation power of the drive. Follow the voltage curve to the desired output current and then find the dissipated power.
5. If the dissipated power is below 4 W the Hornet will need no additional cooling.

Notes:

- The chart above shows that no heatsink is needed when the heatsink temperature is 80 °C, ambient temperature is 40 °C and heat dissipated is 4 W.
- When an external heatsink is required, you can use the Elmo external heatsink (Catalog number: WHI-HEATSINK-2) – see Figure 4.

3.15.2. Bee Thermal Data

The best way to dissipate heat from the Bee is to mount it so that its lower board faces upward. For best results leave approximately 10 mm of space between the Bee's lower board and any other assembly.



3.16. Evaluation Board and Cable Kit

A circuit board is available for evaluating the Hornet. It comes with standard terminal blocks for power connections and D-sub plugs/sockets for signal connections. The Evaluation Board is provided with a cable kit.

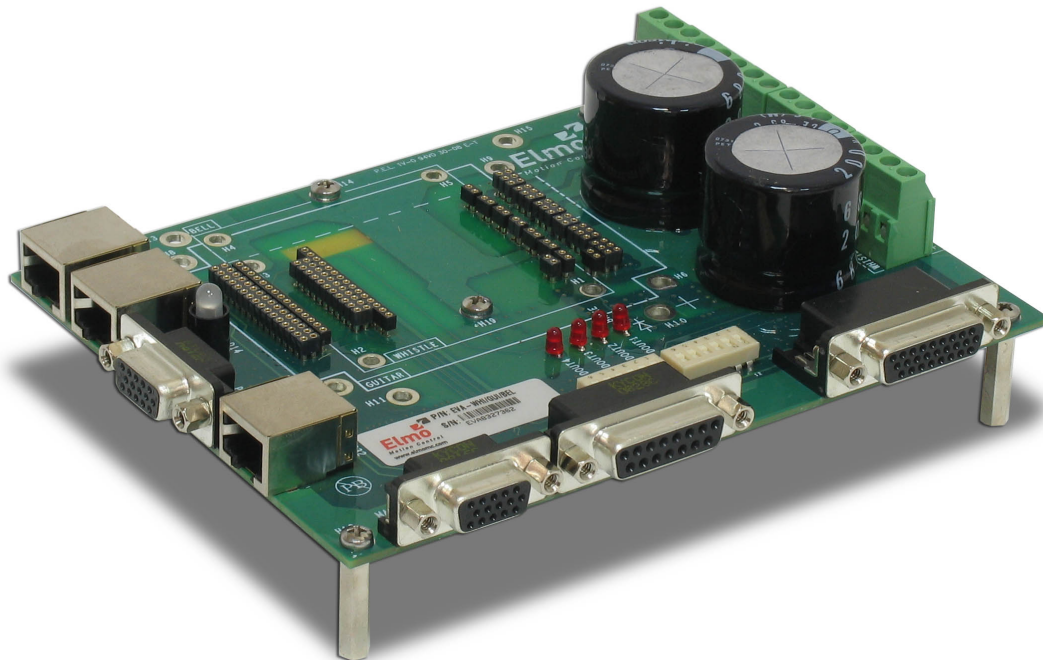


Figure 32: The Evaluation Board (available upon request)

Evaluation Board

Catalog Number: EVA-WHI/GUI/BEL

Evaluation Board User Manual

MAN-EVLBRD-WHI-BEL-GUI.pdf (available on our web site)



Chapter 4: Technical Specifications

This chapter provides detailed technical information regarding the Hornet and Bee. This includes its dimensions, power ratings, the environmental conditions under which it can be used, the standards to which it complies and other specifications.

4.1. Features

The features of the Hornet and Bee determine how they control motion, as well as how they process host commands, feedback and other input.

4.1.1. Motion Control Modes

- Current/Torque - up to 14 kHz sampling rate
- Velocity - up to 7 kHz sampling rate
- Position - up to 3.5 kHz sampling rate

4.1.2. Advanced Positioning Control Modes

- PTP, PT, PVT, ECAM, Follower, Dual Loop, Current Follower
- Fast event capturing inputs
- Fast output compare (OC)
- Motion Commands: Analog current and velocity, pulse-width modulation (PWM) current and velocity, digital (SW) and Pulse and Direction

4.1.3. Advanced Filters and Gain Scheduling

- “On-the-fly” gain scheduling of current and velocity
- Velocity and position with “1-2-4” PIP controllers
- Automatic commutation alignment
- Automatic motor phase sequencing

4.1.4. Fully Programmable

- Third generation programming structure with motion commands – “Composer”
- Event capturing interrupts
- Event triggered programming



4.1.5. Feedback Options

- Incremental Encoder – up to 20 Mega-Counts (5 Mega-Pulse) per second
- Digital Halls – up to 2 kHz
- Incremental Encoder with Digital Halls for commutation – up to 20 Mega-Counts per second for encoder
- Interpolated Analog (Sine/Cosine) Encoder – up to 250 kHz (analog signal)
 - Internal Interpolation - up to x4096
 - Automatic Correction of amplitude mismatch, phase mismatch, signal offset
 - Emulated encoder outputs, single-ended, unbuffered of the Analog encoder
- Analog Hall Sensor
- Resolver
 - Programmable 10 to 15 bit resolution
 - Up to 512 revolutions per second (RPS)
 - Emulated encoder outputs, single-ended, unbuffered of the Resolver.
- Auxiliary Encoder inputs (ECAM, follower, etc.) single-ended, unbuffered.
- Tachometer & Potentiometer
- Provide power (5 V, 200 mA max) for one Encoder, Resolver or Hall.

4.1.6. Input/Output

- One **Analog Input** – up to 14-bit resolution
- Six programmable **Digital Inputs**, optically isolated (two of which are fast event capture inputs).
 - Inhibit/Enable motion
 - Software and analog reference stop
 - Motion limit switches
 - Begin on input
 - Abort motion
 - Homing
 - General-purpose
- Two programmable **Digital Outputs**, optically isolated (open collector) one with fast output compare (OC)
 - Brake Control
 - Amplifier fault indication
 - General-purpose
 - Servo enable indication
- Pulse and Direction inputs (single-ended)
- PWM current command output for torque and velocity



4.1.7. Built-In Protection

- Software error handling
- Abort (hard stops and soft stops)
- Status reporting
- Protection against:
 - Shorts between motor power outputs
 - Shorts between motor power outputs and power input/return
 - Failure of internal power supplies
 - Over temperature
 - Continuous temperature measurement; temperature can be read on the fly; a warning can be initiated X degrees before temperature disable is activated.
 - Over/Under voltage
 - Loss of feedback
 - Following error
 - Current limits

4.1.8. Accessories

- External heatsink (Hornet), see Section 3.4.1 for more details.
Catalog number: WHI-HEATSINK-2.
- Evaluation Board, see Section 3.16 for a picture and more details.
Catalog number: EVA-WHI/GUI/BEL.
- Cable Kit, see Section 3.16 for more details.
Catalog number: CBL-EVAUNIKIT01.

4.1.9. Status Indication

- Output for a bi-color LED

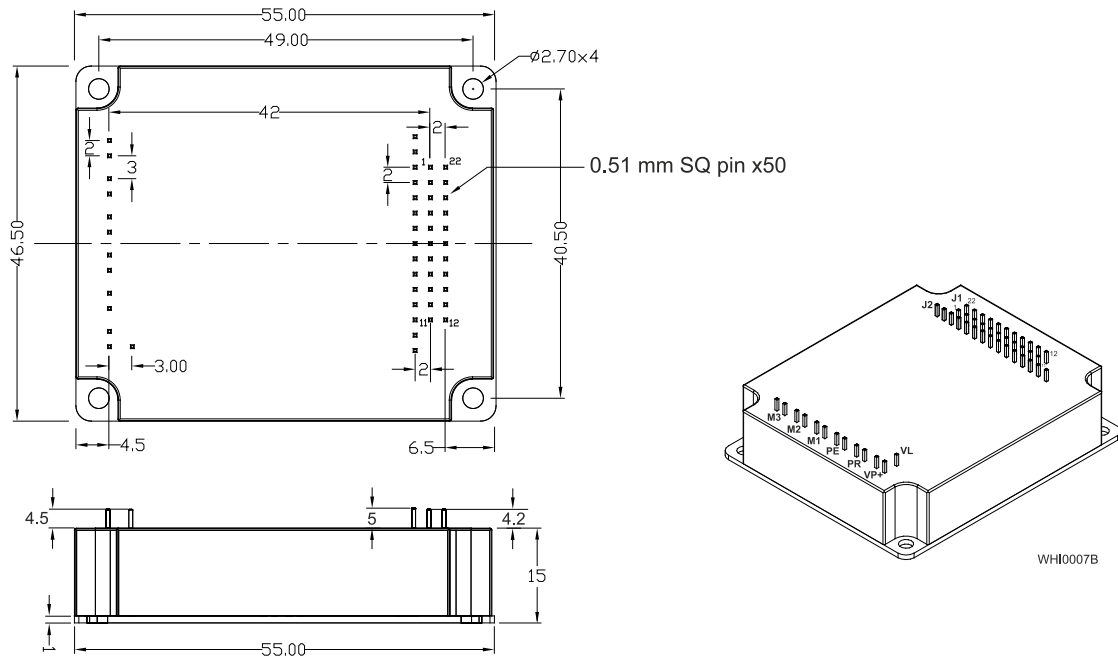
4.1.10. Automatic Procedures

- Commutation alignment
- Phase sequencing
- Current loop offset adjustment
- Current loop gain tuning
- Current gain scheduling
- Velocity loop offset adjustment
- Velocity gain tuning
- Velocity gain scheduling
- Position gain tuning

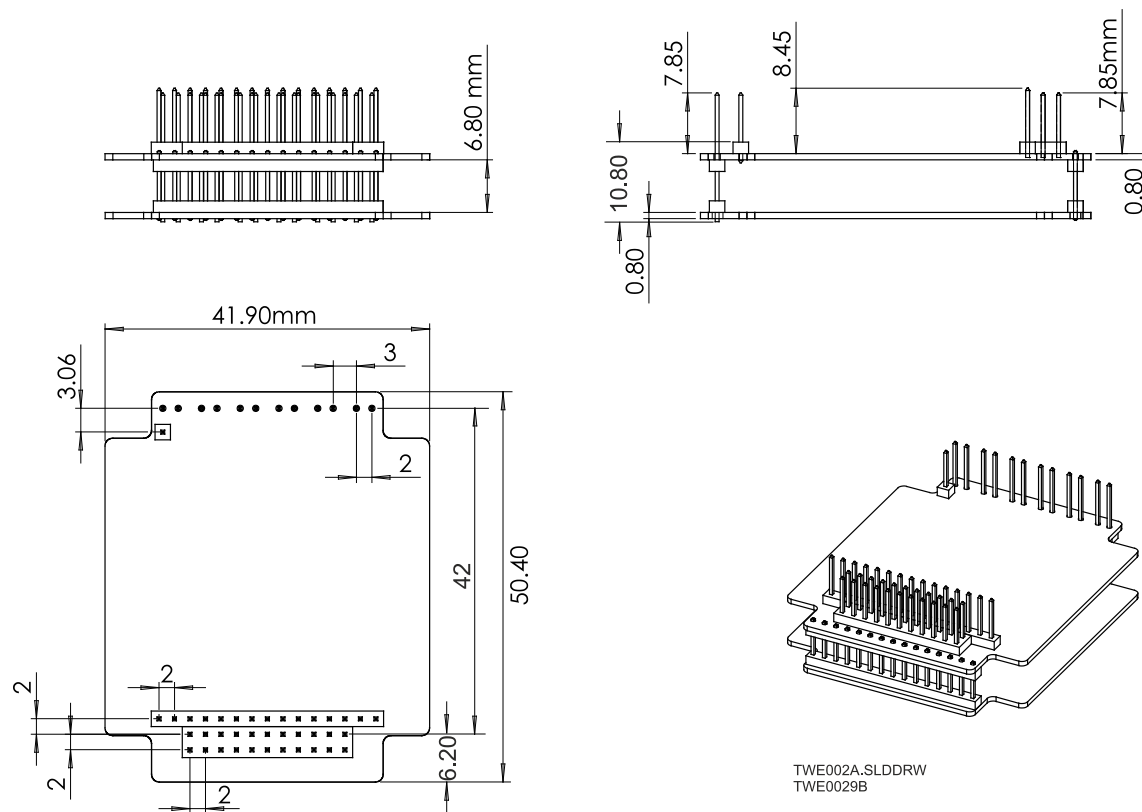


4.2. Dimensions

4.2.1. Hornet



4.2.2. Bee





4.3. Power Ratings

4.3.1. Hornet Up to 60V Rating

| Feature | Units | Units | | | Units | | | |
|--|---------|---|-------|------|-------|-------|-------|-------|
| | | 15/48 | 20/48 | 1/60 | 5/60 | 10/60 | 15/60 | 20/60 |
| Minimum supply voltage | VDC | 6 | | | 7.5 | | | |
| Nominal supply voltage | VDC | 42 | | | 50 | | | |
| Maximum supply voltage | VDC | 48 | | | 59 | | | |
| Maximum continuous power output | W | 600 | 800 | 50 | 240 | 480 | 720 | 960 |
| Efficiency at rated power (at nominal conditions) | % | > 99 | | | | | | |
| Maximum output voltage | | 95% of DC bus voltage at f=22 kHz | | | | | | |
| Auxiliary power supply | VDC | 11 to 95 VDC (up to 2.5 VA inc. 5 V/200 mA for encoder) | | | | | | |
| Amplitude sinusoidal/DC continuous current (I _c) | A | 15 | 20 | 1 | 5 | 10 | 15 | 20 |
| Sinusoidal continuous RMS current limit (I _c) | A | 10.6 | 14.1 | 0.7 | 3.5 | 7 | 10.6 | 14.1 |
| Peak current limit | A | 2 x I _c | | | | | | |
| Weight | g (oz) | 50 g (1.8 oz) | | | | | | |
| Dimensions | mm (in) | 55 x 15 x 46.5 (2.2" x 0.6" x 1.8") | | | | | | |
| Digital in/Digital out/ Analog in | | 6/2/1 | | | | | | |
| Mounting method | | PCB Mount | | | | | | |

**4.3.1. Hornet 100V Rating**

| Feature | Units | 2.5/100 | 5/100 | 10/100 | 15/100 | 20/100 |
|---|---------|---|-------|--------|--------|--------|
| Minimum supply voltage | VDC | 12 | | | | |
| Nominal supply voltage | VDC | 85 | | | | |
| Maximum supply voltage | VDC | 95 | | | | |
| Maximum continuous power output | W | 200 | 400 | 800 | 1200 | 1600 |
| Efficiency at rated power (at nominal conditions) | % | > 99 | | | | |
| Maximum output voltage | | 95% of DC bus voltage at f=22 kHz | | | | |
| Auxiliary power supply | VDC | 11 to 95 VDC (up to 2.5 VA inc. 5 V/200 mA for encoder) | | | | |
| Amplitude sinusoidal/DC continuous current (Ic) | A | 2.5 | 5 | 10 | 15 | 20 |
| Sinusoidal continuous RMS current limit (Ic) | A | 1.8 | 3.5 | 7 | 10.6 | 14.1 |
| Peak current limit | A | 2 x Ic | | | | |
| Weight | g (oz) | 50 g (1.8 oz) | | | | |
| Dimensions | mm (in) | 55 x 15 x 46.5 (2.2" x 0.6" x 1.8") | | | | |
| Digital in/Digital out/ Analog in | | 6/2/1 | | | | |
| Mounting method | | PCB Mount | | | | |



4.3.2. Bee

| Feature | Units | 3/60 | 2.5/100 |
|--|---------|--|---------|
| Minimum supply voltage | VDC | 7.5 | 12 |
| Nominal supply voltage | VDC | 50 | 85 |
| Maximum supply voltage | VDC | 59 | 95 |
| Maximum continuous power output | W | 160 | 200 |
| Efficiency at rated power (at nominal conditions) | % | > 99 | |
| Maximum output voltage | | 95% of DC bus voltage at f=22 kHz | |
| Auxiliary power supply | VDC | 11 to 95 VDC (up to 2.5 VA inc. 5 V/200 mA for encoder) | |
| Amplitude sinusoidal/DC continuous current (I _c) | A | 3.3 | 2.5 |
| Sinusoidal continuous RMS current limit (I _c) | A | 2.3 | 1.8 |
| Peak current limit | A | 2 x I _c | |
| Weight | g (oz) | 27 g (0.95 oz) | |
| Dimensions | mm (in) | 51 x 12.5 x 42 (2" x 0.49" x 1.65") | |
| Digital in/Digital out/Analog in | | 6/2/1 | |
| Mounting method | | PCB mount | |

4.3.3. Auxiliary Supply

| Feature | Details |
|--------------------------------|--|
| Auxiliary power supply | <i>Isolated DC source only</i> |
| Auxiliary supply input voltage | 11 VDC to 95 VDC |
| Auxiliary supply input power | <2.5 VA (this includes the 5 V/200 mA load for the main encoder only) |



4.4. Environmental Conditions

The ExtrIQ products are designed, manufactured and tested to meet extreme environmental conditions. The **ExtrIQ durability** is qualified, verified and tested according to the most severe environmental, EMC and safety standards exceeding the traditional and senior military Standards.

The ExtrIQ series of drives support the following extended environmental conditions.

| Feature | Operation Conditions | Range |
|----------------------------------|--------------------------|---|
| Ambient Temperature Range | Non-operating conditions | -50 °C to +100 °C (-58 °F to 212 °F) |
| | Operating conditions | -40 °C to +70 °C (-40 °F to 160 °F) |
| Temperature Shock | Non-operating conditions | -40 °C to +70 °C (-40 °F to 160 °F) within 3 min. |
| Altitude | Non-operating conditions | Unlimited |
| | Operating conditions | -400 m to 12,000 m (-1312 to 39370 feet) |
| Maximum Humidity | Non-operating conditions | Up to 95% relative humidity non-condensing at 35 °C (95 °F) |
| | Operating conditions | Up to 95% relative humidity non-condensing at 25 °C (77 °F), up to 90% relative humidity non-condensing at 42 °C (108 °F) |
| Vibration | Operating conditions | 20 Hz to 2,000 Hz, 14.6g |
| Mechanical Shock | Non-operating conditions | ±40g; Half sine, 11 msec |
| | Operating conditions | ±20g; Half sine, 11 msec |



4.5. Control Specifications

4.5.1. Current Loop

| Feature | Details |
|---|---|
| Controller type | Vector, digital |
| Compensation for bus voltage variations | “On-the-fly” automatic gain scheduling |
| Motor types | <ul style="list-style-type: none">• AC brushless (sinusoidal)• DC brushless (trapezoidal)• DC brush• Linear motors• “Voice” coils |
| Current control | <ul style="list-style-type: none">• Fully digital• Sinusoidal with vector control• Programmable PI control filter based on a pair of PI controls of AC current signals and constant power at high speed |
| Current loop bandwidth | <2.5 kHz |
| Current sampling time | Programmable 70 to 100 µsec |
| Current sampling rate | Up to 16 kHz; default 11 kHz |



4.5.2. Velocity Loop

| Feature | Details |
|--|--|
| Controller type | PI |
| Velocity control | <ul style="list-style-type: none"> Fully digital Programmable PI and FFW control filters "On-the-fly" gain scheduling Automatic, manual and advanced manual tuning |
| Velocity and position feedback options | <ul style="list-style-type: none"> Incremental Encoder Digital Halls Interpolated Analog (Sin/Cosine) Encoder (optional) Resolver (optional) Tachometer and Potentiometer (optional) <p>Note: With all feedback options, 1/T with automatic mode switching is activated (gap, frequency and derivative).</p> |
| Velocity loop bandwidth | <350 Hz |
| Velocity sampling time | 140 to 200 µsec (2x current loop sample time) |
| Velocity sampling rate | Up to 8 kHz; default 5.5 kHz |
| Velocity command options | <ul style="list-style-type: none"> Analog Internally calculated by either jogging or step <p>Note: All software-calculated profiles support on-the-fly changes.</p> |

4.5.3. Position Loop

| Feature | Details |
|--------------------------|---|
| Controller type | "1-2-4" PIP |
| Position command options | <ul style="list-style-type: none"> Software Pulse and Direction Analog Potentiometer |
| Position loop bandwidth | <80 Hz |
| Position sampling time | 280 to 400 µsec (4x current loop sample time) |
| Position sampling rate | Up to 4 kHz; default 2.75 kHz |



4.6. Feedbacks

The Hornet and Bee can receive and process feedback input from diverse types of devices.

4.6.1. Feedback Supply Voltage

The Hornet and Bee have two feedback ports (Main and Auxiliary). The drives supply voltage only to the main feedback device. The user must provide a separate power supply for auxiliary feedback devices if needed.

| Feature | Details |
|-----------------------------|--------------------------------|
| Main encoder supply voltage | 5 V $\pm 5\%$ @ 200 mA maximum |

4.6.2. Main Feedback Options

4.6.2.1. Incremental Encoder Input

| Feature | Details |
|---|--|
| Encoder format | <ul style="list-style-type: none">• A, B and Index• Differential• Quadrature |
| Interface | RS-422 |
| Input resistance | Differential: 120 Ω |
| Maximum incremental encoder frequency | Maximum absolute: 5 MHz pulses |
| Minimum quadrature input period (P_{IN}) | 112 nsec |
| Minimum quadrature input high/low period (P_{HL}) | 56 nsec |
| Minimum quadrature phase period (P_{PH}) | 28 nsec |
| Maximum encoder input voltage range | Common mode: ± 7 V Differential mode: ± 7 V |

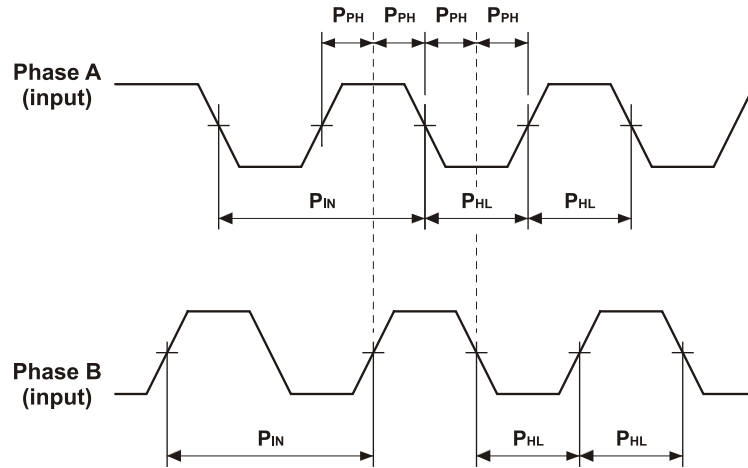


Figure 33: Main Feedback - Encoder Phase Diagram

4.6.2.2. Digital Halls

| Feature | Details |
|-------------------|---|
| Halls inputs | <ul style="list-style-type: none"> • H_A, H_B, H_C. • Single ended inputs • Built in hysteresis of 1V for noise immunity |
| Input voltage | Nominal operating range: $0\text{ V} < V_{In_Hall} < 5\text{ V}$ Maximum absolute: $-1\text{ V} < V_{In_Hall} < 15\text{ V}$ High level input voltage: $V_{InHigh} > 2.5\text{ V}$ Low level input voltage: $V_{InLow} < 1\text{ V}$ |
| Input current | Sink current (when input pulled to the common): 3 mA Source current: 1.5 mA (designed to also support open collector Halls) |
| Maximum frequency | $f_{MAX} : 2\text{ kHz}$ |



4.6.2.3. Interpolated Analog (Sine/Cosine) Encoder

| Feature | Details |
|---------------------------------|---|
| Analog encoder format | Sine and Cosine signals |
| Analog input signal level | <ul style="list-style-type: none">• Offset voltage: 2.2 V to 2.8 V• Differential, 1 V peak to peak |
| Input resistance | Differential 120 Ω |
| Maximum analog signal frequency | f_{MAX} : 250 kHz |
| Interpolation multipliers | Programmable: x4 to x4096 |
| Maximum “counts” frequency | 80 mega-counts/sec “internally” |
| Automatic errors correction | Signal amplitudes mismatch Signal phase shift Signal offsets |
| Encoder outputs | See Auxiliary Encoder Outputs specifications (4.6.3) |

4.6.2.4. Resolver

| Feature | Details |
|------------------------------------|--|
| Resolver format | <ul style="list-style-type: none">• Sine/Cosine• Differential |
| Input resistance | Differential 2.49 k Ω |
| Resolution | Programmable: 10 to 15 bits |
| Maximum electrical frequency (RPS) | 512 revolutions/sec |
| Resolver transfer ratio | 0.5 |
| Reference frequency | 1/Ts (Ts = sample time in seconds) |
| Reference voltage | Supplied by the Hornet and Bee |
| Reference current | Up to ± 50 mA |
| Encoder outputs | See Auxiliary Encoder Output specifications (4.6.3) |



4.6.2.5. Tachometer*

| Feature | Details |
|--|----------------|
| Tachometer format | Differential |
| Maximum operating differential voltage for TAC1+, TAC1- | ± 20 V |
| Maximum absolute differential input voltage for TAC1+, TAC1- | ± 25 V |
| Maximum operating differential voltage for TAC2+, TAC2- | ± 50 V |
| Maximum absolute differential input voltage for TAC2+, TAC2- | ± 60 V |
| Input resistance for TAC1+, TAC1- | 46 k Ω |
| Input resistance for TAC2+, TAC2- | 100 k Ω |
| Resolution | 14 bit |

* Only one Tachometer port can be used at a time (either TAC1+/TAC1- or TAC2+/TAC2-).

TAC1+/TAC1- is used in applications with having a Tachometer of less than 20V.

TAC2+/TAC2- is used in applications with having a Tachometer of between 20V and 50V.

4.6.2.6. Potentiometer

| Feature | Details |
|--------------------------|--|
| Potentiometer Format | Single-ended |
| Operating Voltage Range | 0 to 5 V supplied by the Hornet/Bee |
| Potentiometer Resistance | 100 Ω to 1 k Ω ... above this range, linearity is affected detrimentally |
| Input Resistance | 100 k Ω |
| Resolution | 14 bit |

4.6.3. Auxiliary Feedback Port (output mode YA[4]= 4)

| Feature | Details |
|-------------------------------|---|
| Emulated output | <ul style="list-style-type: none"> A, B, Index Single ended |
| Output current capability | Maximum output current: $I_{OH}(\text{max}) = 2 \text{ mA}$ High level output voltage: $V_{OH} > 3.0 \text{ V}$ Minimum output current: $I_{OL} = 2 \text{ mA}$ Low level output voltage: $V_{OL} < 0.4 \text{ V}$ |
| Available as options | <ul style="list-style-type: none"> Emulated encoder outputs of analog encoder Emulated encoder outputs of the resolver |
| Maximum frequency | $f_{\text{MAX}} : 5 \text{ MHz pulses/output}$ |
| Edge separation between A & B | Programmable number of clocks to allow adequate noise filtering at remote receiver of emulated encoder signals |
| Index (marker): | Length of pulse is one quadrature (one quarter of an encoder cycle) and synchronized to A&B |

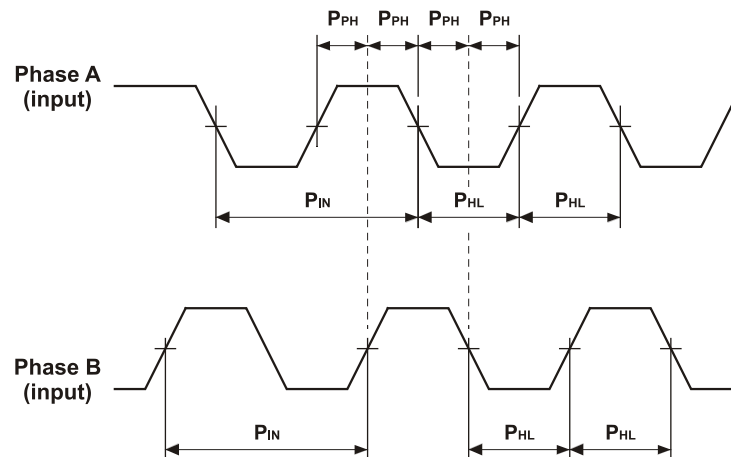
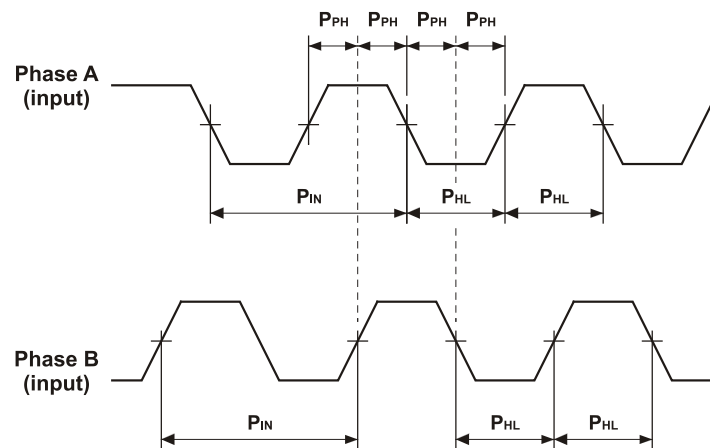


Figure 34: Auxiliary Feedback - Encoder Phase Diagram

**4.6.4. Auxiliary Feedback Port (Input mode YA[4]= 2, 0)**

| Feature | Details |
|--|---|
| Encoder input, pulse and direction input | <ul style="list-style-type: none"> • A, B, Index • Single ended |
| Output current capability | V_{in} Low: $0\text{ V} < V_{IL} < 0.8\text{ V}$ V_{in} High: $2\text{ V} < V_{IH} < 5\text{ V}$ Maximum absolute voltage: $0 < V_{in} < 5.5\text{ V}$ Input current: $\pm 1\text{ }\mu\text{A}$ |
| Available as options | <ul style="list-style-type: none"> • Single-ended Encoder inputs • Pulse and Direction inputs |
| Edge separation between A & B | Programmable number of clocks to allow adequate noise filtering at remote receiver of emulated encoder signals |
| Index (marker) | Length of pulse is one quadrature (one quarter of an encoder cycle) and synchronized to A&B |

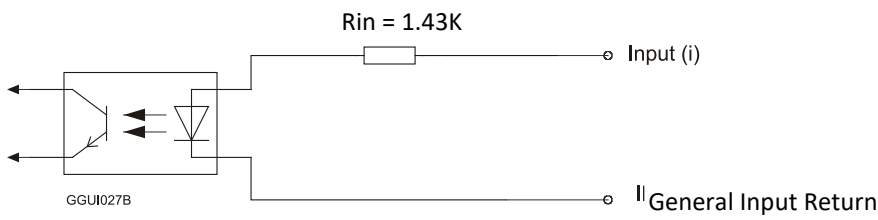
**Figure 35: Auxiliary Feedback - Encoder Phase Diagram**

4.7. I/Os

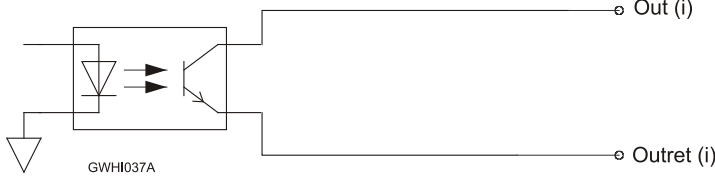
The Hornet and Bee have:

- 6 Digital Inputs
- 2 Digital Outputs
- 1 Analog Input

4.7.1. Digital Input Interfaces

| Feature | Details |
|---|---|
| Type of input | <ul style="list-style-type: none"> • Optically isolated • All six inputs share one signal return line |
| Input current for all inputs | $I_{in} = 2.4 \text{ mA @ } V_{in} = 5 \text{ V}$ |
| High-level input voltage | $2.5 \text{ V} < V_{in} < 10 \text{ V}$, 5 V typical |
| Low-level input voltage | $0 \text{ V} < V_{in} < 1 \text{ V}$ |
| Minimum pulse width | $> 4 \times TS$, where TS is sampling time |
| Execution time (all inputs): the time from application of voltage on input until execution is complete | <p>If input is set to one of the built-in functions — Home, Inhibit, Hard Stop, Soft Stop, Hard and Soft Stop, Forward Limit, Reverse Limit or Begin — execution is immediate upon detection: $0 < T < 4 \times TS$</p> <p>If input is set to General input, execution depends on program. Typical execution time: $\cong 0.5 \text{ msec}$.</p> |
| High-speed inputs – 5 & 6 minimum pulse width, in high-speed mode | <p>$T < 5 \mu\text{sec}$</p> <p>Notes:</p> <ul style="list-style-type: none"> • Home mode is high-speed mode and can be used for fast capture and precise homing. • High speed input has a digital filter set to same value as digital filter (EF) of main encoder. • Highest speed is achieved when turning on optocouplers. |
|  <p style="text-align: center;">Figure 36: Digital Input Schematic</p> | |

4.7.2. Digital Output Interface

| Feature | Details |
|--|--|
| Type of output | <ul style="list-style-type: none"> • Optically isolated • Open collector and open emitter |
| Maximum supply output (Vcc) | 30 V |
| Max. output current I _{out} (max) (V _{out} = Low) | I _{out} (max) ≤ 10 mA |
| VOL at maximum output voltage (low level) | V _{out} (on) ≤ 0.3 V |
| RL | <p>External resistor RL must be selected to limit output current to no more than 10 mA.</p> $R_L = \frac{V_{cc} - VOL}{I_o(max)}$ |
| Executable time | <p>If output is set to one of the built-in functions — Home flag, Brake or AOK — execution is immediate upon detection: 0 < T < 4 x TS</p> <p>If output is set to General output and is executed from a program, the typical time is approximately 0.5 msec.</p> |
|  <p style="text-align: center;">Figure 37: Digital Output Schematic</p> | |

4.7.3. Analog Input

| Feature | Details |
|---|---------|
| Maximum operating differential voltage | ± 10 V |
| Maximum absolute differential input voltage | ± 16 V |
| Differential input resistance | 3.74 kΩ |
| Analog input command resolution | 14-bit |



4.8. Communications

| Specification | Details |
|---------------|--|
| RS-232 | Signals: <ul style="list-style-type: none">• RxD , TxD , Gnd• Full duplex, serial communication for setup and control.• Baud Rate of 9,600 to 57,600 bit/sec. |
| CAN | CAN bus Signals: <ul style="list-style-type: none">• CAN_H, CAN_L, CAN_GND• Maximum Baud Rate of 1 Mbit/sec. Version: <ul style="list-style-type: none">• DS 301 V4.01 Layer Setting Service and Protocol Support: <ul style="list-style-type: none">• DS 305 Device Profile (drive and motion control): <ul style="list-style-type: none">• DS 402 |

4.9. Pulse-Width Modulation (PWM)

| Feature | Details |
|-------------------------------------|--|
| PWM resolution | 12-bit |
| PWM switching frequency on the load | 2/Ts (factory default 22 kHz on the motor) |



4.10. Compliance with Standards

| Specification | Details |
|--|---|
| Quality Assurance | |
| ISO 9001:2008 | Quality Management |
| Design | |
| Approved IEC/EN 61800-5-1, Safety | Printed wiring for electronic equipment (clearance, creepage, spacing, conductors sizing, etc.) |
| MIL-HDBK- 217F | Reliability prediction of electronic equipment (rating, de-rating, stress, etc.) |
| <ul style="list-style-type: none"> • UL 60950 • IPC-D-275 • IPC-SM-782 • IPC-CM-770 • UL 508C • UL 840 | Printed wiring for electronic equipment (clearance, creepage, spacing, conductors sizing, etc.) |
| In compliance with VDE0160-7 (IEC 68) | Type testing |
| Safety | |
| Recognized UL 508C | Power Conversion Equipment |
| In compliance with UL 840 | Insulation Coordination Including Clearances and Creepage Distances for Electrical Equipment |
| In compliance with UL 60950 | Safety of Information Technology Equipment Including Electrical Business Equipment |
| Approved IEC/EN 61800-5-1, Safety | Adjustable speed electrical power drive systems |
| In compliance with EN 60204-1 | Low Voltage Directive 73/23/EEC |



| EMC | |
|--|--|
| Approved IEC/EN 61800-3, EMC | Adjustable speed electrical power drive systems |
| In compliance with EN 55011 Class A with EN 61000-6-2 : Immunity for industrial environment, according to: IEC 61000-4-2 / criteria B IEC 61000-4-3 / criteria A IEC 61000-4-4 / criteria B IEC 61000-4-5 / criteria B IEC 61000-4-6 / criteria A IEC 61000-4-8 / criteria A IEC 61000-4-11 / criteria B/C | Electromagnetic compatibility (EMC) |
| Workmanship | |
| In compliance with IPC-A-610 , level 3 | Acceptability of electronic assemblies |
| PCB | |
| In compliance with IPC-A-600 , level 2 | Acceptability of printed circuit boards |
| Packing | |
| In compliance with EN 100015 | Protection of electrostatic sensitive devices |
| Environmental | |
| In compliance with 2002/96/EC | Waste Electrical and Electronic Equipment regulations (WEEE) Note: Out-of-service Elmo drives should be sent to the nearest Elmo sales office. |
| In compliance with 2002/95/EC (effective July 2006) | Restrictions on Application of Hazardous Substances in Electric and Electronic Equipment (RoHS) |