

1-Axis Motor Control IC with High Functions

MCX501 User's Manual

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NOVA electronics

Prevent Electrostatic Discharge



ATTENTION: This IC is sensitive to electrostatic discharge, which can cause internal damage and affect normal operation. Follow these guidelines when you handle this IC:

- Touch a grounded object to discharge potential static.
- Wear an approved grounding wrist strap.
- Do not touch pins of this IC.
- Store this IC in appropriate static-safe packaging when not in use.

Safety Notice



WARNING: This IC is not designed or intended to be fail-safe, or for use in any application requiring fail-safe performance, such as in life-support or safety devices or systems that could lead to death, personal injury or severe property or environmental damage (individually and collectively, "critical applications"). Customer must be fully responsible for the use of this IC in critical applications.

Provide adequate design and operating safeguards in order to minimize risks associated with customer's applications when incorporating this IC in a system.

Compliance



ATTENTION: "Japanese Foreign Exchange and Foreign Trade Act" and other export-related laws and regulations must be observed and complied with. Do not use this IC for the purpose of the development of weapons such as mass destruction weapons and any military purposes. This IC shall not be used in equipment that manufacture, use and sale are prohibited by Japanese and foreign laws and regulations.

Before you begin



ATTENTION: Before using this IC, read this manual thoroughly to ensure correct usage within the scope of the specification such as the signal voltage, signal timing, and operation parameter values.

Installation of this IC



ATTENTION: This IC is provided in the form of a lead-free package. The installation conditions are different from those of the conventional lead-soldered IC. See Chapter 11 for the installation conditions of this IC.

About Reset



ATTENTION: Make sure to reset the IC when the power is on. This IC will be reset if RESETN signal is set to Low for more than 8 CLK cycles when a stable clock has been input. Please note that the IC will not be reset if the clock is not input.

Treatment of unused pins



ATTENTION: Make sure that unused input pins are connected to GND or VDD. If these pins are open, the signal level of pins will unstable and may cause malfunction. Make sure that unused bi-directional pins are connected to VDD or GND through high impedance (about 10k~ 100 k Ω). If these pins are directly connected to GND or VDD, the IC may be damaged by overcurrent in case of such as a programming mistake causes the output state.

Notes on S-curve acceleration/deceleration driving



ATTENTION: This IC is equipped with a function that performs decelerating stop. For a fixed pulse drive with S-curve deceleration of the symmetrical acceleration /deceleration. However, when the initial speed is set to an extremely low speed (10 or less), slight premature termination or creep may occur. Before using a S-curve deceleration drive, make sure that your system allows premature termination or

Technical Information



ATTENTION: Before using this IC, read "Appendix B Technical Information" on the last pages of this manual without fail because there are some important information.

The descriptions of this manual may change without notice because of the progress of the technologies, etc. Please download the up-date data from our website (<http://www.novaelec.co.jp/eng>) and/or ask us to supply you directly.

■ Terms and Symbols used in the Manual

Active	The function of a signal is the state of being enabled.
Drive	Action to output pulses for rotating a motor to the driver (drive unit) of a pulse type servo motor or seteping motor.
Fixed pulse drive	Drive that outputs specified pulses. Three types of drives: relative position drive, counter relative position drive and absolute position drive are available.
Continuous pulse drive	Drive that outputs pulses up to infinity unless a stop factor becomes active.
Jerk	Acceleration increasing/decreasing rate per unit time. This term includes a decreasing rate of acceleration (=Jerk).
Deceleration increasing rate	Deceleration increasing/decreasing rate per unit time. This term includes a decreasing rate of deceleration.
2's complement	2's complement is used to represent negative numbers in binary. [Example] In 16-bit length, -1 is FFFFh, -2 is FFFEh, -3 is FFFDh, ... -32768 is 8000h.
Creep	In deceleration of acceleration/ deceleration fixed pulse driving, output of specified driving pulses is not completed even if the speed reaches the initial speed and the rest of driving pulses is output at the initial speed (= Creep).
Premature termination	In deceleration of acceleration/ deceleration fixed pulse driving, output of specified driving pulses is completed and driving is terminated before the speed reaches the initial speed. This is a reverse behavior of creep.
↑	The rising edge of when a signal changes its level from Low to Hi.
↓	The falling edge of when a signal changes its level from Hi to Low.

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Update history

Nov/14/2012

Revised for the reason of a literal error.

1. OUTLINE

1.1 The Main Features of Functions

MCX501 is 1-axis motion control IC which connects to the master CPU with 8-bit or 16-bit bus and can control either a stepper motor driver or pulse type servo driver for position and speed.

This IC has no multiple of speed (Range Setting) to set the drive speed, that is to say it can freely output the drive speed from 1 pps up to 8 Mpps in increments of 1 pps. Acceleration/deceleration driving can perform trapezoidal acceleration/deceleration and smooth S-curve acceleration/deceleration.

■ Speed Range-Free

MCX501 is a new motion control IC that has no multiple of speed (Range Setting) to set the drive speed. This will enable us to freely set the speed from 1 pps up to 8 Mpps in increments of 1 pps.

When using the multiples of speed to set the speed by existing method, there are restrictions as described below.

- For the detailed speed setting of low-speed, less multiples of speed must be set.
→ As a result, driving cannot be shifted to high-speed.
- To perform the high-speed driving, larger multiples of speed must be set.
→ As a result, the detailed setting of drive speed cannot be configured.

MCX501 brings solutions to the inconvenience described above by Speed range-free, which makes it possible to directly change the speed from low-speed such as 1 or 2 pps to high-speed such as 1 Mpps during the driving.

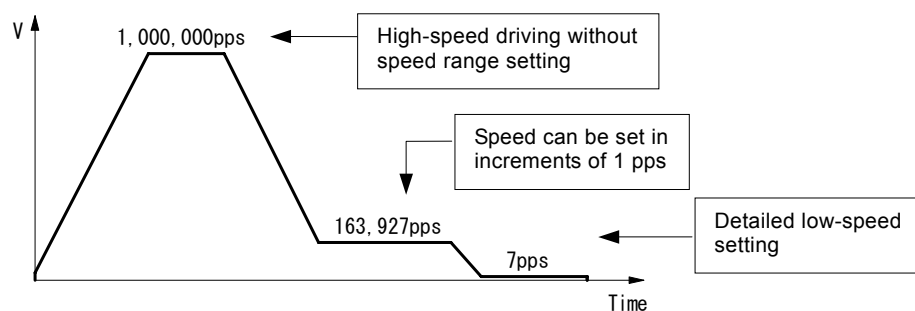


Fig. 1.1-1 Speed Range-Free

■ Easy and High-Accuracy Speed Setting

Since there is no need to set multiples of speed (Range Setting), the user can set a drive speed of output pulses as a speed parameter (at CLK = 16MHz).

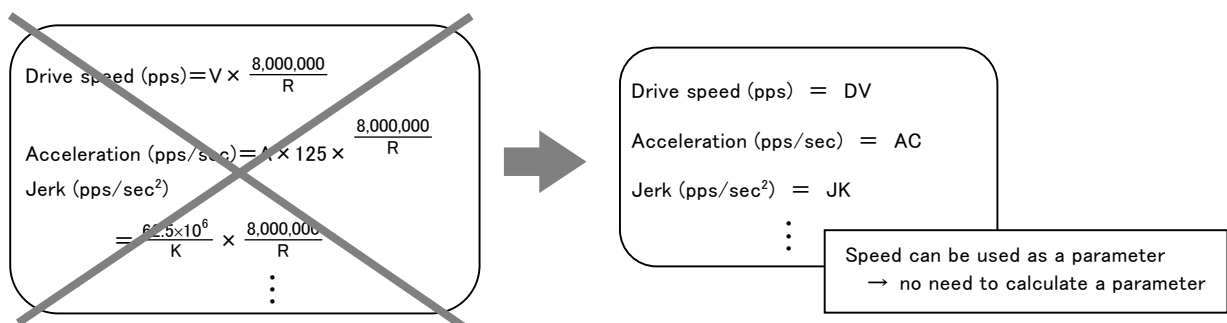


Fig. 1.1-2 Speed Parameter Setting

In the range of 1 pps to 8 Mpps, it can output the drive speed that is set with high accuracy. Speed accuracy of the pulse output is less than $\pm 0.1\%$, which is on the assumption that there is no frequency error of input clock (CLK). In fact, there is a frequency error of input clock (CLK), and speed accuracy depends on it.

■ Various Acceleration / Deceleration Drive Mode

◆ Types of acceleration/deceleration driving

Acceleration/deceleration driving can perform the following driving.

- Constant speed driving
- Linear acceleration/deceleration driving (symmetry/non-symmetry)
- S-curve acceleration/deceleration driving (symmetry/non-symmetry)

◆ Automatic deceleration start

In position driving of linear acceleration/deceleration (symmetry/non-symmetry) and S-curve acceleration/deceleration (symmetry), the IC calculates the deceleration start point when in deceleration, and automatically starts deceleration. (This is not applied to non-symmetry S-curve acceleration/deceleration driving.)

◆ S-curve acceleration/deceleration curve

S-curve acceleration/deceleration uses the method which increases/decreases acceleration or deceleration in a primary line, and the speed curve forms a secondary parabola acceleration/deceleration. In addition, it prevents triangle waveforms by a special method during S-curve acceleration/deceleration.

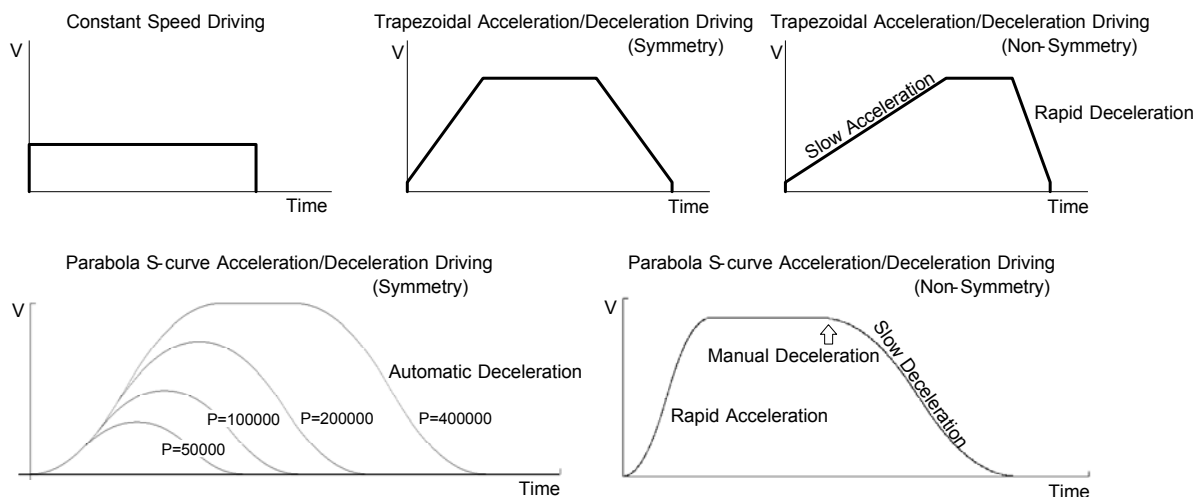


Fig. 1.1-3 Acceleration / Deceleration Drive Mode

■ Position Control

MCX501 has two 32-bit position counters: one is a logical position counter that counts the number of output pulses and the other is a real position counter that counts the feedback number of pulses from an external encoder.

The current position can be read by data reading commands anytime.

By using with synchronous action, the operation by the activation factor based on position data, such as a timer starts/stops at a specified position, can be performed.

■ Software Limit

MCX501 has a software limit function that controls driving to stop when the position counter is over a specified range. There are 2 stop types for when the software limit function is enabled: decelerating stop and instant stop.

■ Various Synchronous Actions

Synchronous action is the function that executes a specified action together with if a specified activation factor generates. These synchronous actions can be performed fast and precisely, independent of the CPU.

Synchronous action is possible to set up to 4 sets.

1 set of synchronous actions is configured with one specified activation factor and one specified action. 15 types of activation factors are provided, such as the passage of a specified position, start/termination of driving, the rising/falling edge of an external signal and expiring of an internal timer. In addition, 28 types of actions are provided, such as start/termination of driving, save the current position counter value to multi-purpose register and writing of a drive speed.

Multiple synchronous action sets can be used in combination, which allows users to develop a wide array of applications.

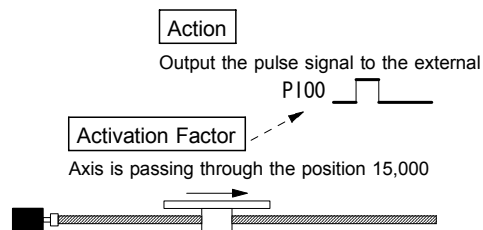


Fig. 1.1-4 Synchronous Action

Examples

- Outputs an external signal when passing through a specified position during the driving.
- Saves the current position to a specified register when an external signal is input during the driving.
- Outputs N split pulses from a specified position to the external during the driving.

■ Four Multi-Purpose Registers

MCX501 has four 32-bit length multi-purpose registers.

Multi-purpose register can be used to compare with the current position, speed and timer, and then can read out the status which represents comparison result and can output as a signal. In addition, it can activate a synchronous action according to comparison result or can generate an interrupt.

By using with synchronous action, it can save values of the position or current speed during the driving to multi-purpose registers and load values to parameters from multi-purpose registers.

■ Timer Function

MCX501 is equipped with the timer which can set with the range of $1 \sim 2,147,483,647 \mu\text{sec}$ in increments of $1 \mu\text{sec}$ (at $\text{CLK} = 16\text{MHz}$). By using with synchronous action, the following operations can be performed precisely.

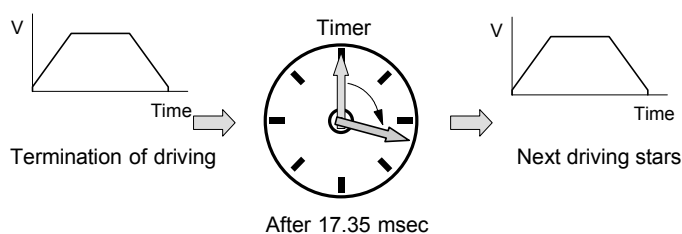


Fig. 1.1-5 Timer Function

Examples

- Starts driving after specified periods when the driving is finished.
- Starts driving after specified periods after an external signal is input.
- Stops continuous pulse driving after specified periods.
- Times from position A to position B.

■ Output of Split Pulse

This is a function that outputs split pulses during the driving, which synchronizes axis driving and performs various operations in the specified intervals.

The split length, pulse width of a split pulse and split pulse number can be set. By using with synchronous action, the output of split pulses can be started/terminated from a specified position and the split length or pulse width of a split pulse can be changed by an external signal.

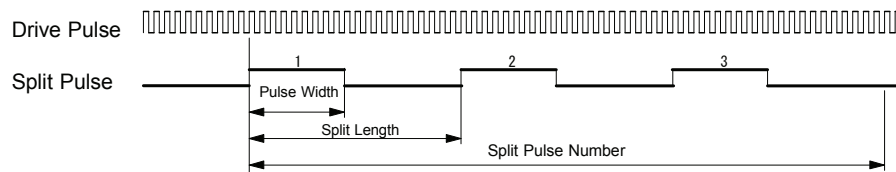


Fig. 1.1-6 Split Pulse Output

■ Automatic Home Search Function

This IC is equipped with the function that automatically executes a home search sequence without CPU intervention. The sequence comprises high-speed home search → low-speed home search → encoder Z-phase search → offset drive.

Deviation counter clear pulses can be output for a servo motor driver. In addition, the timer between steps which sets stop time among each step is available, and the operation for a home search of a rotation axis is provided.

■ Servo Motor Feedback Signals

MCX501 has input pins for servo feedback signals such as encoder 2-phase, in-positioning and alarm signals. An output signal for clearing a deviation counter is also available.

■ Interrupt Signals

Interrupt signals can be generated by various factors. For example, (1). at the start/finish of a constant speed drive during the acceleration/deceleration driving, (2). at the end of driving, and (3). when the comparison result of a multi-purpose register with a position counter changes.

■ Driving by External Signals

Driving can be controlled by external signals, which are the relative position driving, continuous pulse driving and MPG driving. This function is used for JOG feed or teaching mode, reducing the CPU load and making operations smooth.

■ Built-in Input Signal Filter

The IC is equipped with an integral type filter in the input step of each input signal. It is possible to set for each input signal whether the filter function is enabled or the signal is passed through. A filter time constant can be selected from 16 types (500nsec ~ 16msec).

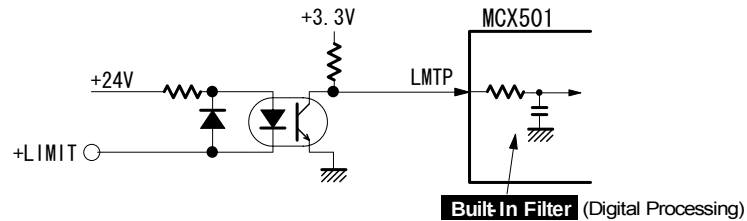


Fig. 1.1-7 Built-in Input Signal Filter

■ Real Time Monitoring

During the driving, the current status such as logical position, real position, drive speed, acceleration/deceleration, status of accelerating/constant speed driving/decelerating/acceleration increasing/acceleration constant/acceleration decreasing and a timer can be read in real time.

■ 8 or 16 Bits Data Bus Selectable

MCX501 can be connected to either 8-bit or 16-bit CPU.

If 8-bit data bus is used, eight pins which are not used for the data bus can be used as general purpose input signals.

1.2 Functional Block Diagram

MCX501 functional block diagram is shown as below.

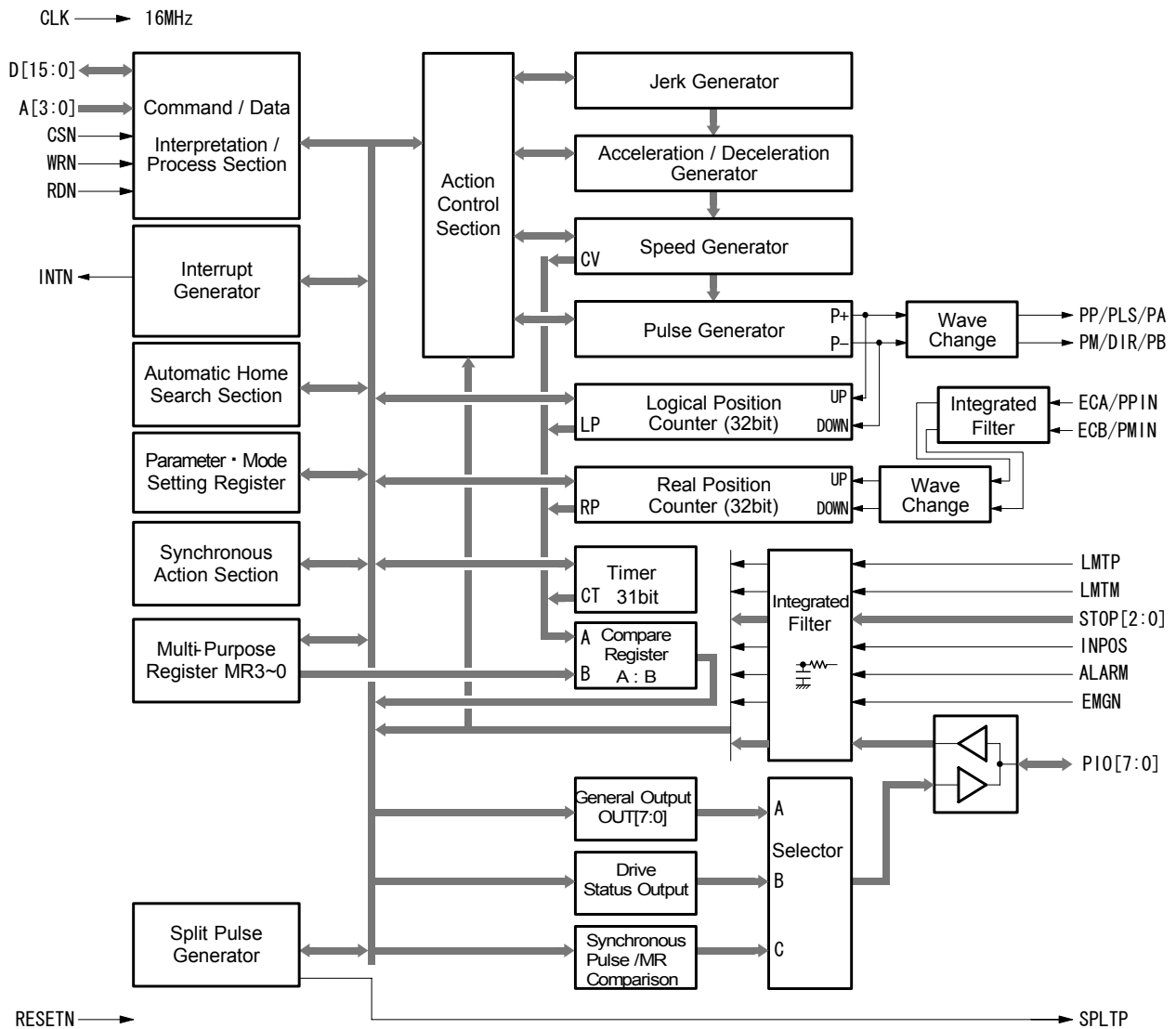


Fig. 1.2-1 MCX501 Functional Block Diagram

1.3 Specification Table

(CLK=16MHz)

Item	Subitem	Description	Note
Control Axis		1-axis	
Data Bus		16/8-bit selectable	
Drive Pulses Output	Drive Speed Range	1 pps ~ 8,000,000 pps (When CLK=20MHz: up to 10,000,000 pps)	
	Initial Speed Range	1 pps ~ 8,000,000 pps	
	Pulse Output Accuracy	± 0.1% or less (according to the setting speed)	
	Acceleration Range	1 pps/sec ~ 536,870,911pps/sec	
	Acceleration Increasing/ Decreasing Rate Range	1 pps/sec ² ~ 1,073,741,823 pps/sec ²	*1
	Acceleration/Deceleration Curve	Constant speed, Symmetrical/non-symmetrical linear acceleration/deceleration, Symmetrical/non-symmetrical parabola S-curve acceleration/ deceleration	
	Drive Pulse Range	•Relative position driving : -2,147,483,646 ~ 2,147,483,646 •Absolute position driving : -2,147,483,646 ~ 2,147,483,646	*2
	Position Driving Decelerating Stop Mode	Automatic decelerating stop Manual decelerating stop	*3
	Override	Output pulse number and drive speed are changeable during the driving	*4
	Driving Commands	Relative/Absolute position driving, +/-direction continuous driving	
	Triangle Form Prevention	can be used both in linear and S-curve acceleration/deceleration	
	Drive Pulse Output Type	Independent 2-pulse, 1-pulse 1-direction, Quadrature pulse and quad edge evaluation, Quadrature pulse and double edge evaluation are selectable	
Encoder Input	Drive Pulse Output Logic	Positive/Negative logical level selectable	
	Drive Pulse Output Pin	Possible to pin inversion	
Encoder Input	Input Pulse Input Type	Quadrature pulses input and quad edge evaluation, Quadrature pulses input and double edge evaluation, Quadrature pulses input and single edge evaluation, Up / down pulse input are selectable	
	Input Pulse Pin	Possible to pin inversion	
Position Counter	Logical Position Counter	Count Range: -2,147,483,648 ~ +2,147,483,647	*5
	Real Position Counter	Count Range: -2,147,483,648 ~ +2,147,483,647	*5
	Variable Ring	Possible to set the count maximum value of each position counter	
Software Limit	Setting Range	-2,147,483,648 ~ +2,147,483,647	
	Stop Mode	Decelerating/Instant stop selectable	
Multi-Purpose Register	Bit Length, Number of Registers	32-bit length 4 registers	
	Uses	Compare with position, speed and timer value, load data such as position and speed, and save data such as current position, speed and timer value	
Timer	Setting Range	1 ~ 2,147,483,647μsec	
Split Pulse	Split Length	2 ~ 65,535 pulses	*6
	Split Pulse Width	1 ~ 65,534 pulses	
	Split Pulse Number	1 ~ 65,535, or up to infinity	
Automatic Home Search	Sequence	STEP1 high-speed home search → STEP2 low-speed home search → STEP3 encoder Z-phase search → STEP4 offset drive •Enable/Disable each step and search signal/direction are selectable	
	Deviation Counter Clear Output	Clear pulse width within the range of 10μ ~ 20msec and logical level is selectable	
	Timer between Steps	Selectable from 1msec ~ 1,000msec	

Synchronous Action	Number of Sets	4 sets	*7
	Activation Factor	•When multi-purpose register comparison changed •Comparative object: logical/real position counter value, current drive speed, current timer value •Comparison condition: $\geq$, $>$, $=$, $<$ •When a timer is up •Start/Termination of driving, Start/Termination of acceleration/deceleration driving at constant speed •Start/Termination of split pulse, Output of split pulse •PION signal $\uparrow/\downarrow$, PION+4 signal Low and PION signal $\uparrow$, PION+4 signal Hi and PION signal $\uparrow$, PION+4 signal Low and PION signal $\downarrow$, PION+4 signal Hi and PION signal $\downarrow$ (n:0,1,2,3) •Activation command	
	Action	•Load value (MRn→setting value) - : Drive speed, Drive pulse number (Finish point), Split length, Split pulse width, Logical/Real position counter value, Initial speed, Acceleration •Save value (MRn←current value) : Logical/Real position counter value, Current timer value, Current drive speed, Current acceleration •Synchronous pulse output to the external •Start of relative/absolute position driving, Start of +/-direction continuous pulse driving, Start of relative/absolute position driving at the position set in MRn •Decelerating stop/Instant stop, Speed increase/decrease, Timer-start/stop, Start/Termination of split pulse	
	Repeat	Synchronous action can be operated once/repeatedly.	
Interrupt	Interrupt Factor	•When multi-purpose register comparison changed •Comparative object : logical/real position counter value, current drive speed, current timer value •Comparison condition : $\geq$, $>$, $=$, $<$ •Start/Termination of driving, Start/Termination of acceleration/deceleration driving at constant speed •When automatic home search is finished, When a timer is up •Output/Termination of split pulse, •When synchronous action 0/1/2/3 is activated	
	Enable / Disable	Enable/Disable each interrupt factor is selectable	
External Signal for Driving		•Relative position/Continuous pulse driving by EXPP, EXPM signals •MPG (encoder input : quadrature pulses input and single edge evaluation)	*8
External Stop Signal	Number of Signals	3 signals (STOP0~2)	
	Enable/Disable	Enable/Disable stop signal function is selectable	*9
	Logical Level	Low/Hi active is selectable	
	Stop Mode	When it is active, decelerating stop (When driving under initial speed, instant stop)	
Servo Motor Input/Output Signal	Signals	ALARM (alarm), INPOS (in-position), DCC (deviation counter clear)	
	Enable/Disable	Enable/Disable a signal is selectable.	
	Logical Level	Low/Hi active is selectable.	
General Input/Output Signal	Number of Signals	8 signals •Synchronous input, pins share the input pin for driving by external signals. •Synchronous action output, multi-purpose register comparison output, pins share drive status output signal pins.	
Driving Status Output Signal	Signals	•Driving, Error, Accelerating, Constant speed driving, Decelerating, Acceleration increasing, Acceleration constant, Acceleration decreasing •Drive status can also be read by status register.	*10

Over Limit Signal	Number of Signals	2 signals (for each + and - direction)	
	Enable/Disable	Enable/Disable limit function is selectable.	*9
	Logical Level	Low/Hi active is selectable.	
	Stop Mode	Decelerating stop or instant stop is selectable when it is active.	
	Input Pulse Pin	Possible to pin inversion	
Emergency Stop Signal		EMGN 1 point, stop drive pulses output at Low level. (Logical level can not be set)	
Integral Type Filter	Input Signal Filter	Equipped with integral filters in the input column of each input signal.	
	Time Constant	Time constant can be selected from 16 types. (500n, 1μ, 2μ, 4μ, 8μ, 16μ, 32μ, 64μ, 128μ, 256μ, 512μ, 1m, 2 m, 4 m, 8 m, 16 m [sec])	
	Enable/Disable	Enable/Disable filter function is selectable.	
Electrical Characteristics	Temperature Range for Driving	-40°C~+85°C	
	Power Voltage for Driving	+3.3V ±10%	
	Consumption Current	27mA (average), 44mA (max) at CLK=16MHz	
	Input Clock Pulse	16MHz (standard) 20MHz (max)	
	Input Signal Level	TTL level (5V tolerant)	
	Output Signal Level	3.3V CMOS Level (only TTL can be connected to 5V type)	
Package		•64-pin plastic TQFP, pin pitch: 0.5mm, RoHS compliant •Dimension: 10 × 10 × 1.0 mm	

<Further Note>

*1	Parameter that is used in S-curve acceleration/deceleration driving.
*2	Pulse range that can be set for the driving that outputs specified pulses. In continuous pulse driving, pulses are output up to infinity.
*3	Automatic deceleration stop performs decelerating stop automatically by calculating the deceleration start point based on specified drive pulses. Manual deceleration stop performs decelerating stop by setting the deceleration start point from the high order. This IC can perform automatic deceleration stop except for non-symmetrical S-curve acceleration/deceleration.
*4	After the start of driving, output pulse number can be changed for the same direction in only relative position driving.
*5	Logical position counter counts output pulses and real position counter counts encoder input pulses.
*6	While driving, split pulses are output at specified intervals in synchronization with driving pulses.
*7	1 set of synchronous actions is configured with one specified activation factor and one specified action.
*8	Input pins for external signals share the general purpose input/output pins.
*9	When the function is not used, it can be used as general purpose input.
*10	Drive status output signal pins share the general purpose input/output pins.

2. The Descriptions of Functions

2.1 Fixed Pulse Driving and Continuous Pulse Driving

There are two kinds of pulse output commands: fixed pulse driving that is performed based on the number of output pulses predetermined and continuous pulse driving that outputs pulses until a stop command is issued or stop signal is input. Fixed pulse driving has relative position driving, absolute position driving and counter relative position driving. Continuous pulse driving has +direction continuous pulse driving and -direction continuous pulse driving.

- Fixed pulse driving
 - Relative position driving
 - Absolute position driving
 - Counter relative position driving
- Continuous pulse driving
 - +Direction continuous pulse driving
 - -Direction continuous pulse driving

2.1.1 Relative Position Driving

Relative position driving performs the driving by setting the drive pulse number from the current position. To drive from the current position to the +direction, set the positive pulse number in the drive pulse number, and to the -direction, set the negative pulse number in the drive pulse number.

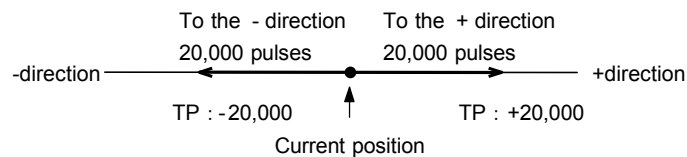


Fig. 2.1-1 Setting Example of Drive Pulse Number (TP) in Relative Position Driving

Relative position driving performs constant speed driving or acceleration/deceleration driving. Relative position driving in the acceleration/deceleration where acceleration and deceleration are equal, as shown in Fig. 2.1-2, automatic deceleration starts when the number of pulses becomes less than the number of pulses that were utilized at acceleration, and driving terminates when the output of specified drive pulses is completed.

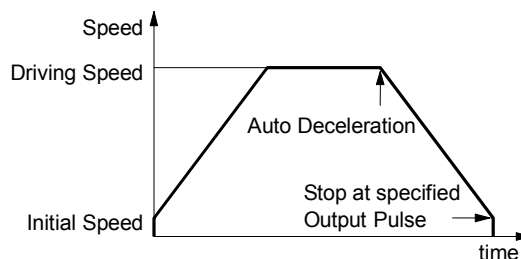


Fig. 2.1-2 Auto Deceleration and Stop in Relative Position Driving

Command code for relative position driving is 50h. To perform relative position driving in linear acceleration/deceleration, the following parameters must be set.

Table 2.1-1 Setting Parameters : Relative Position Driving

Parameter	Symbol	Comment
Acceleration/Deceleration	AC/DC	No need to set deceleration when acceleration and deceleration are equal.
Initial speed	SV	
Drive speed	DV	
Drive pulse number/ Finish point	TP	Set +pulse number for the +direction. Set -pulse number for the -direction.

2.1.2 Absolute Position Driving

Absolute position driving performs the driving by setting the destination point based on a home (logical position counter = 0). The destination point can be set by absolute coordinates regardless of the current position. The IC calculates drive direction and output pulse number according to the difference between the specified destination point and current position, and then performs the driving. In absolute position driving the destination point should be set by absolute coordinates within the range of driving space. So, the user first needs to perform automatic home search to determine the logical position counter before driving.

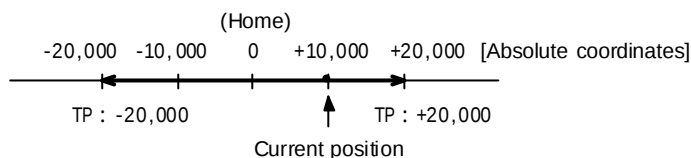


Fig. 2.1-3 Example of Specifying Finish Point (TP) in Absolute Position Driving

Absolute position driving performs constant speed driving or acceleration/deceleration driving as well as relative position driving.

Command code for absolute position driving is 54h. To perform absolute position driving in linear acceleration/deceleration, the following parameters must be set.

Table 2.1-2 Setting Parameters : Absolute Position Driving

Parameter	Symbol	Comment
Acceleration/Deceleration	AC/D C	No need to set deceleration when acceleration and deceleration are equal.
Initial speed	SV	
Drive speed	DV	
Drive pulse number/ Finish point	TP	Set the destination point by absolute coordinates.

2.1.3 Counter Relative Position Driving

Counter relative position driving performs the driving by setting the direction and drive pulse number to the destination point based on the current position. Unlike relative position driving, driving is performed in a direction opposite to the sign of the pulse number that is set in drive pulse number (TP). This is useful for when the user wants to determine a drive direction using a driving command, by setting the predetermined positive value to the drive pulse number in advance.

If the negative value is set to the drive pulse number, counter relative position driving performs the driving in the + direction.

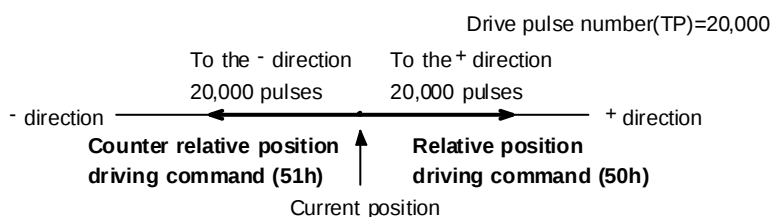


Fig. 2.1-4 Driving Direction is Determined by Relative/Counter Relative Position Driving Command

The operation of counter relative position driving is the same as relative position driving except the operation which drives in a direction opposite to the sign of the pulse number that is set in drive pulse number (TP). Command code for counter relative position driving is 51h.

A . Changing Drive Pulse Number in the middle of Driving (Override)

The drive pulse number (TP) can be changed in relative position driving and counter relative position driving. However, the drive direction must be the same before and after the change of drive pulse number. The drive pulse number cannot be changed to the value of different direction.

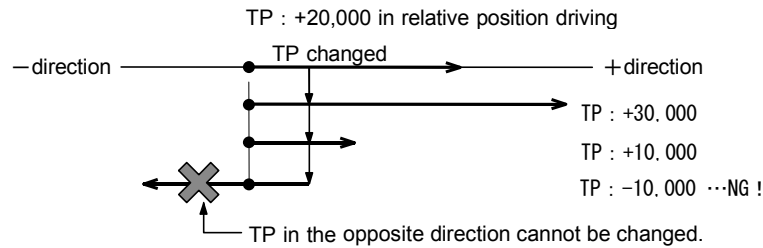


Fig. 2.1-5 Override Drive Pulse Number (TP) in Relative Position Driving

In acceleration/deceleration driving, if the rest of output pulses become less than the pulses at acceleration, and the drive pulse number (TP) is changed during deceleration, the driving accelerates again (Fig. 2.1-7). And if the output pulse number of changed drive pulse number (TP) is less than the number of pulses already output, the driving stops immediately (Fig. 2.1-8). In S-curve acceleration/deceleration driving, if the drive pulse number (TP) is changed during deceleration, the S-curve profile cannot be exactly tracked.

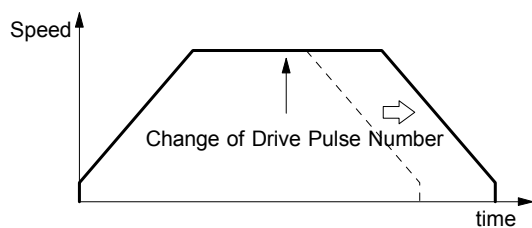


Fig. 2.1-6 Change of Drive Pulse Number during Driving

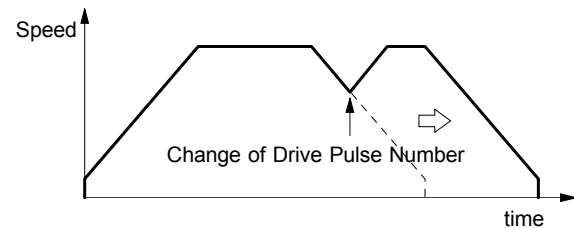
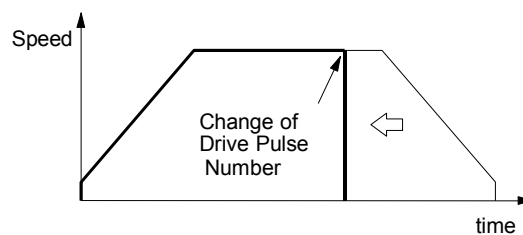
Fig. 2.1-7 Change of Drive Pulse Number
in Deceleration

Fig. 2.1-8 Changing Drive Pulse Number Less than Output Pulse Number

[Note]

- Absolute position driving cannot change the drive pulse number (TP) while driving.

B. Manual Deceleration for Fixed Pulse Acceleration/Deceleration Driving

As shown in Fig. 2.1-2, generally the deceleration of fixed pulse driving (relative position driving, absolute position driving and counter relative position driving) is controlled automatically by MCX501. However, in the following situations, it should be preset the deceleration point by the users.

- The change of speed is too often in the trapezoidal acceleration/deceleration fixed pulse driving.
- Speed is changed during the driving in the non-symmetry trapezoidal acceleration/deceleration and S-curve acceleration/deceleration fixed pulse driving.
- Acceleration, deceleration, jerk (acceleration increasing rate) and deceleration increasing rate are set individually for S-curve acceleration/deceleration fixed pulse driving (non-symmetry S-curve acceleration/deceleration).

To set manual deceleration mode, please set D0 bit of WR3 register to 1, and use manual decelerating point setting command (07h) to set a deceleration point. As to other operations, the setting is the same as those of fixed pulse driving.

C. Offset Setting for Acceleration/Deceleration Driving

The offset function can be used for compensating the pulses when the decelerating speed does not reach the setting initial speed during acceleration/deceleration fixed pulse driving. MCX501 will calculate the acceleration/deceleration point automatically, and arrange the output pulses of deceleration phase that is equal to those of acceleration phase.

When setting the offset for deceleration, MCX501 will start deceleration early for the offset. The greater positive value is set for the offset, the closer the automatic declaration point becomes, for this reason creep pulses of the initial speed will increase at the termination of deceleration. If a negative value is set for the offset, output may stop prematurely before the speed reaches the initial speed (see Fig. 2.1-9).

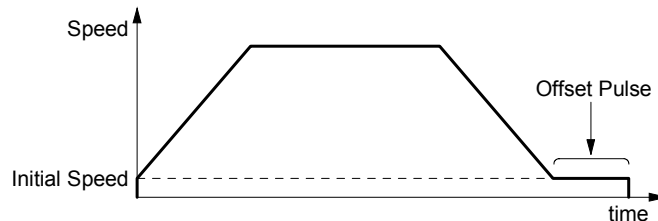


Fig. 2.1-9 Offset for Deceleration

The default value for the offset is 0 when MCX501 power-on reset. It is not necessary to change the shift pulse value in normal acceleration/deceleration fixed pulse driving. As for fixed driving in non-symmetrical trapezoidal acceleration/deceleration or S-curve acceleration/deceleration, if creep pulses or premature termination occurs at the termination of driving due to the low initial speed, correct by setting the acceleration counter offset appropriately.

2.1.4 Continuous Pulse Driving

When continuous pulse driving is performed, MCX501 will drive pulse output in a specific speed until a stop command or external stop signal becomes active. The user can use it for: home searching, teaching and speed control.

There are two stop commands, one is “decelerating stop” and the other is “instant stop”. And three input pins STOP0 ~ STOP2 can be connected for external decelerating stop (instant stop when driving under initial speed) signal. Enable/disable and active level can be set in mode setting.

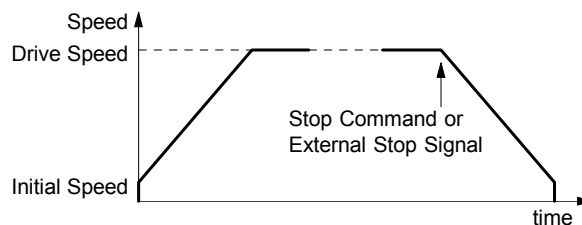


Fig. 2.1-10 Continuous Pulse Driving

+ Direction continuous pulse driving command (52h) and - Direction continuous pulse driving command (53h) are available. To perform acceleration/deceleration continuous pulse driving, parameters except drive pulse number (TP) must be set as well as fixed pulse driving.

Table 2.1-3 Setting Parameters : Continuous Pulse Driving

Parameter	Symbol	Comment
Acceleration/Deceleration	AC/DC	No need to set deceleration when acceleration and deceleration are equal.
Initial speed	SV	
Drive speed	DV	

■ Changing Drive Speed during the Driving (Override)

The drive speed can be changed freely during continuous pulse driving, which can be altered by changing a drive speed parameter (DV) or issuing a speed increase/decrease command.

In S-curve acceleration/deceleration driving, it will be invalid if the speed is changed in the middle of acceleration/deceleration.

In fixed pulse driving under the symmetry trapezoidal acceleration/deceleration and constant speed, a drive speed (DV) can be changed during the driving. However, if a speed of fixed pulse driving is changed at linear acceleration/deceleration, some premature termination may occur. So please note when using the IC with low initial speed.

In fixed pulse driving (automatic deceleration mode) under the non-symmetry trapezoidal acceleration/deceleration and S-curve acceleration/deceleration, the drive speed cannot be changed during the driving.

<Speed Change by Drive Speed Setting>

If a drive speed parameter (DV) is changed by drive speed setting command (05h), the setting will be immediately applied.

And if during acceleration/deceleration driving, the drive speed increases/decreases to a specified drive speed.

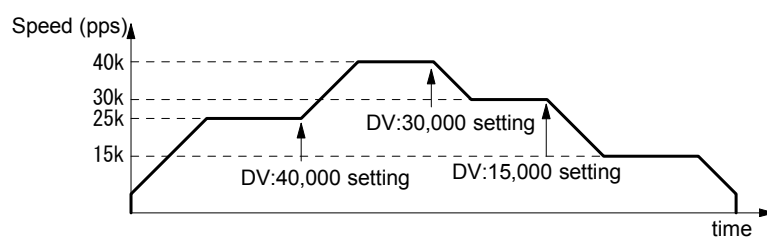


Fig. 2.1-11 Example of Drive Speed Change during the Driving

<Speed Change by Speed Increase/Decrease Command>

The speed increasing/decreasing value (IV) must be set in advance. If speed increase command (70h) or speed decrease command (71h) is issued during the driving, the setting will be immediately applied. And if during acceleration/deceleration driving, the drive speed increases/decreases from the current drive speed to the value of the speed increasing/decreasing value setting.

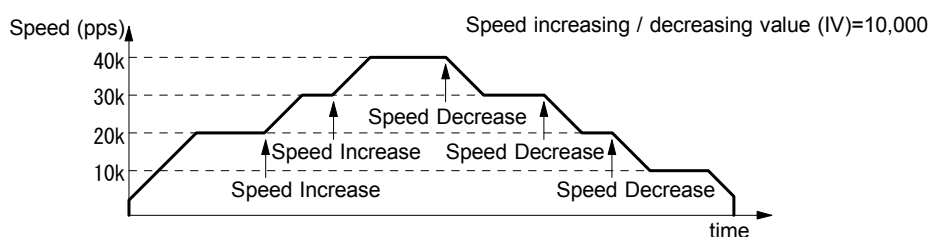


Fig. 2.1-12 Example of Speed Change by Speed Increase/Decrease Command

■ Stop Condition for External Input STOP2 to STOP0 in Continuous Pulse Driving

Assign a near home signal, a home signal and an encoder Z-phase signal in STOP0 to STOP2. (Assign an encoder Z phase signal in STOP2.) Enable/disable and logical levels can be set by WR2 register. If high-speed searching, continuous pulse driving is performed at acceleration/deceleration. And when the signal that is enabled becomes active, MCX501 will perform decelerating stop. If low-speed searching, continuous pulse driving is performed at constant speed. And when the signal that is enabled becomes active, MCX501 will perform instant stop.

This IC has automatic home search function. See Chapter 2.5 for details of automatic home search function.

2.2 Acceleration and Deceleration

There are the following speed curves that can trace from drive pulse output: Constant speed driving which does not perform acceleration/deceleration, Trapezoidal acceleration/deceleration driving which performs linear acceleration/deceleration to a setting speed, and S-curve acceleration/deceleration driving which performs acceleration/deceleration to a specified drive speed with a smooth curve.

And the following acceleration/deceleration driving is each available: Symmetry acceleration/deceleration where acceleration and deceleration are equal and Non-symmetry acceleration/deceleration where acceleration and deceleration are set individually.

- Constant speed driving
- Acceleration/Deceleration driving
 - Trapezoidal acceleration/deceleration driving
 - linear acceleration/deceleration (Symmetry)
 - Non-symmetry linear acceleration/deceleration
 - S-curve acceleration/deceleration driving
 - S-curve acceleration/deceleration (Symmetry)
 - Non-symmetry S-curve acceleration/deceleration

2.2.1 Constant Speed Driving

Constant speed driving outputs drive pulses at a constant speed without acceleration/deceleration. To perform constant speed driving, the drive speed must be set lower than the initial speed (that is the initial speed is higher than the drive speed.). Constant speed driving performs the driving at the drive speed lower than the initial speed without acceleration/deceleration. Stop mode is instant stop.

If the user wants to stop immediately when the home sensor or encoder Z-phase signal is active, perform the low-speed constant speed driving from the beginning not acceleration/deceleration driving.

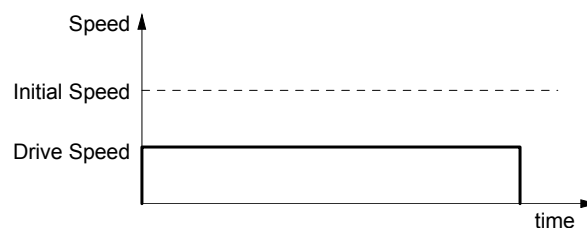


Fig. 2.2-1 Constant Speed Driving

To perform constant speed driving, the following parameters must be set.

Table 2.2-1 Setting Parameters : Constant Speed Driving

Parameter	Symbol	Comment
Initial speed	SV	Set higher than the drive speed (DV).
Drive speed	DV	
Drive pulse number / Finish point	TP	Not required for continuous pulse driving.

■ Example for Parameter Setting of Constant Speed

The constant speed is set 980 PPS as shown in Fig. 2.2-2 below. In this case, the relative position driving that the drive pulse number is 2450 is performed.

Initial speed	SV = 980	Set the value which initial speed $\geq$ Drive speed
Drive speed	DV = 980	
Drive pulse number	TP = 2450	

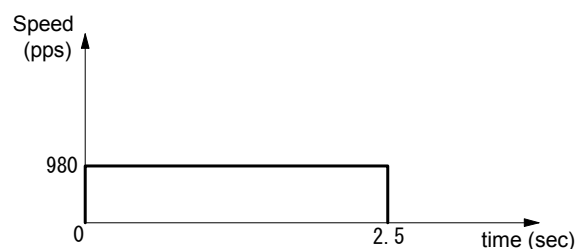


Fig. 2.2-2 Example of Constant Speed Driving

Please refer each parameter in Chapter 5.2.

■ Triangle Form Prevention of Trapezoidal Driving (Fixed Pulse Driving)

The triangle form prevention function prevents a triangle form in linear acceleration/deceleration fixed pulse driving even if the number of output pulses does not reach the number of pulses required for accelerating to a drive speed. The triangle form indicates the speed curve that shifts to deceleration during the acceleration phase in linear acceleration/deceleration driving. When the number of pulses that were utilized at acceleration and deceleration exceeds 1/2 of the total number of output pulses during acceleration, this IC stops acceleration and keeps that driving speed and then decelerates automatically. Therefore, even if the number of output pulses is less in fixed pulse driving, 1/2 of the number of output pulses becomes constant speed area and can make the triangle form into the trapezoidal form.

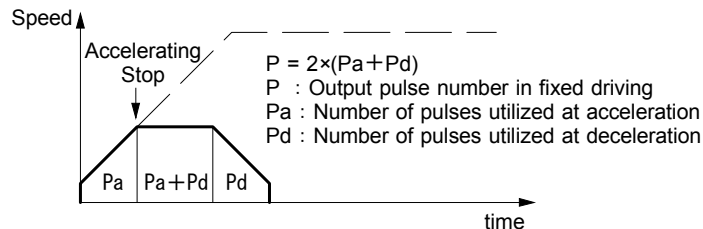


Fig. 2.2-5 Triangle Prevention of Linear Acceleration Driving

The triangle form prevention function in linear acceleration/deceleration fixed pulse driving is enabled from a reset. And it can be disabled by setting D13 bit of WR3 register to 1.

If the decelerating stop command is performed during acceleration, the triangle form prevention does not work. As shown in Fig. 2.2-3, deceleration starts from when the decelerating stop is performed.

2.2.3 Non-Symmetrical Trapezoidal Acceleration

If an object is to be moved using stacking equipment, there will be a need to change acceleration and deceleration of vertical transfer since gravity acceleration is applied to the object.

This IC can perform automatic deceleration in non-symmetrical linear acceleration/deceleration fixed pulse driving where acceleration and deceleration are different. It is not necessary to set a manual deceleration point by calculation in advance. Fig. 2.2-6 shows the case where the deceleration is greater than the acceleration and Fig. 2.2-7 shows the case where the acceleration is greater than the deceleration. In such non-symmetrical linear acceleration, the automatic deceleration start point is calculated by the IC based on the number of output pulses in fixed pulse driving and each rate parameter.

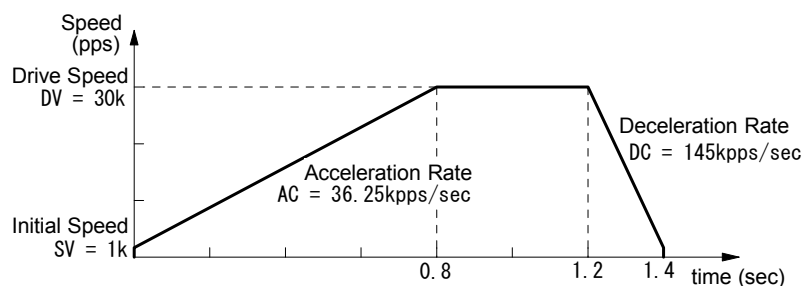


Fig. 2.2-6 Non-Symmetrical Linear Acceleration Driving (acceleration < deceleration)

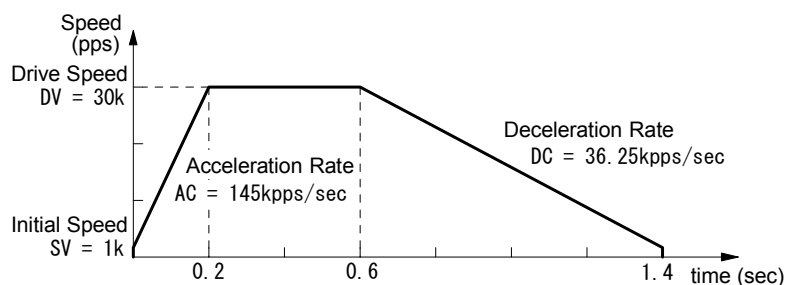


Fig. 2.2-7 Non-Symmetrical Linear Acceleration Driving (acceleration > deceleration)

To perform non-symmetry linear acceleration/deceleration driving using automatic deceleration, bits D2 to 0 of WR3 register and the following parameters must be set.

Table 2.2-4 Mode Setting : Non-symmetry Linear Acceleration/Deceleration

Mode Setting Bit	Symbol	Setting	Comment
WR3/D0	MANLD	0	Automatic deceleration
WR3/D1	DSNDE	1	When in deceleration, deceleration setting value is used.
WR3/D2	SACC	0	Linear acceleration/deceleration

Table 2.2-5 Setting Parameters : Non-symmetry Linear Acceleration/Deceleration

Parameter	Symbol	Comment
Acceleration	AC	
deceleration	DC	
Initial speed	SV	
Drive speed	DV	
Drive pulse number/Finish point	TP	Not required for continuous pulse driving.

[Note]

- In non-symmetry linear acceleration/deceleration driving, when acceleration > deceleration (Fig. 2.2-7), the following condition is applied to the ratio of acceleration and deceleration.

$$DC > AC \times \frac{DV}{8 \times 10^6}$$

DC : Deceleration (pps/sec)

AC : Acceleration (pps/sec) When CLK = 16MHz

DV : Drive speed (pps)

For instance, if the driving speed DV = 100kps, deceleration D must be greater than 1/80 of acceleration A. The value must not be less than 1/80 of acceleration.

- In non-symmetry linear acceleration/deceleration driving, if acceleration > deceleration (Fig. 2.2-7), the greater the ratio of acceleration AC to deceleration DC becomes, the greater the number of creep pulses becomes (about maximum of 10 pulses when AC/DC=10 times). When creep pulses cause a problem, solve the problem by increasing the initial speed or setting a minus value to the acceleration counter offset.

■ Example of Parameter Setting

As shown in Fig. 2.2-6, parameter setting of relative position driving in non-symmetrical linear acceleration/deceleration (acceleration < deceleration) is shown below.

Mode setting	WR3←0002h	Mode setting of WR3 register
Acceleration	AC = 36250	(30000-1000)/0.8 = 36250pps/sec
Deceleration	DC = 145000	(30000-1000)/0.2 = 145000pps/sec
Initial speed	SV = 1000	
Drive speed	DV = 30000	
Drive pulse number	TP = 27500	Relative position driving

2.2.4 S-curve Acceleration/Deceleration Driving [Symmetrical]

S-curve acceleration/deceleration driving performs acceleration and deceleration to a specified drive speed with a smooth curve that forms a secondary parabolic curve.

This IC creates an S-curve by increasing/decreasing acceleration/deceleration in a primary line at acceleration and deceleration of a drive speed.

Fig. 2.2-8 shows the operation of S-curve acceleration/deceleration driving where acceleration and deceleration are symmetrical.

- Section a. When driving starts, the acceleration increases on a straight line at a specified jerk. In this case, the speed data forms a quadratic curve.
- Section b. If the difference between a specified drive speed and the current speed becomes less than the speed that was utilized at acceleration increasing, the acceleration starts to decrease on a straight line at a specified jerk. The decrease ratio is the same as the increase ratio. In this case, the rate curve forms a parabola of reverse direction.
- Section c. When the speed reaches a specified drive speed or the acceleration reaches 0, the driving keeps that speed. In fixed pulse driving of S-curve acceleration/deceleration where acceleration and deceleration are symmetrical, when the rest of output pulses becomes less than the number of pulses that were utilized in accelerating, deceleration starts (automatic deceleration).
- Section d,e. Also in deceleration, the speed forms a S-curve by increasing/decreasing deceleration in a primary linear form.

The same operation is performed in acceleration/deceleration where the drive speed is changed during continuous pulse driving. However, In S-curve acceleration/deceleration driving, change of a drive speed during acceleration/deceleration is invalid.

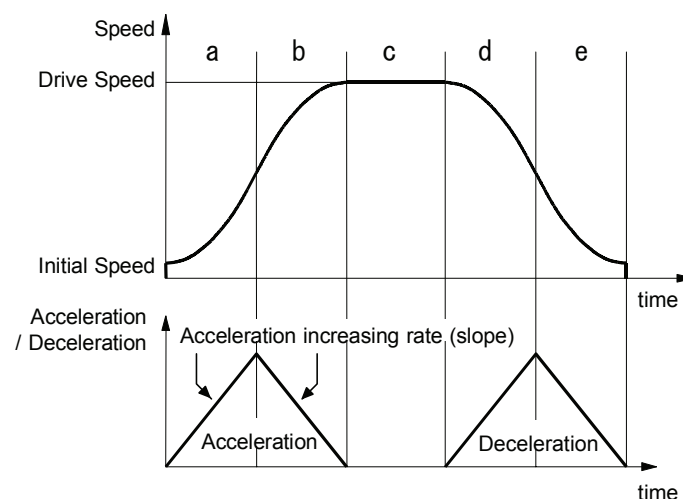


Fig. 2.2-8 S-curve Acceleration/Deceleration Driving (Symmetry)

To perform symmetry S-curve acceleration/deceleration driving by using automatic deceleration, bits D2 to 0 of WR3 register and the following parameters must be set.

Table 2.2-6 Mode Setting : S-curve Acceleration/Deceleration (Symmetry)

Mode Setting Bit	Symbol	Setting	Comment
WR3/D0	MANLD	0	Automatic deceleration
WR3/D1	DSNDE	0	When in deceleration, acceleration and jerk setting values are used.
WR3/D2	SACC	1	S-curve acceleration/deceleration

Table 2.2-7 Setting Parameters : S-curve Acceleration / Deceleration (Symmetry)

Parameter	Symbol	Comment
Jerk	JK	
Acceleration	AC	Set the maximum value : 536,870,911 (1FFF FFFFh).
Initial speed	SV	
Drive speed	DV	
Drive pulse number/Finish point	TP	Not required for continuous pulse driving.

■ Triangle Form Prevention of S-curve Acceleration/Deceleration Driving

S-curve acceleration/deceleration driving also has the triangle form prevention function for keeping a speed curve smooth.

In fixed pulse driving of S-curve acceleration/deceleration where acceleration and deceleration are symmetrical, when the number of output pulses does not reach the number of pulses required for accelerating to a drive speed or when decelerating stop is performed during S-curve acceleration, the triangle form prevention function works in both cases and keeps a speed curve smooth.

<The Prevention of Triangle Driving Profile in Fixed Pulse Driving>

In fixed pulse driving of S-curve acceleration/deceleration where acceleration and deceleration are symmetrical, when the number of output pulses does not reach the number of pulses required for accelerating to a drive speed, the following method is applied to keep a speed curve smooth.

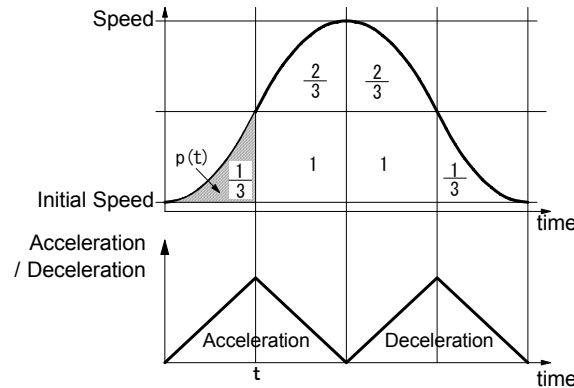


Fig. 2.2-9 The Rule of 1/12 of S-curve Acceleration/Deceleration

If the initial speed is "0" and the acceleration is increased up to the time "t" at a constant jerk "a", in the section of acceleration increasing, the speed "v(t)" in the time "t" can be expressed as follows.

$$v(t) = at^2$$

Therefore, the total number of pulses "p(t)" utilized during the time from "0" to "t" is the integral of the speed "v(t)" from the time "0" to "t".

$$p(t) = \frac{1}{3} \times at^3$$

This value indicates 1/3 of $at^2 \times t$ (the number of pulses of one square on the figure) regardless of the value of the jerk.

In fixed pulse driving, the acceleration is increased from the time "0" to "t" at a specified jerk, and is decreased from the time "t" at the same jerk. When the acceleration reaches 0, and if the deceleration is also increased/decreased at the same jerk, the number of pulses that were utilized in fixed pulse driving is expressed, as shown in Fig. 2.2-9, as follows.

$$\frac{1}{3} + \frac{2}{3} + 1 + 1 + \frac{2}{3} + \frac{1}{3} = 4 \text{ squares on the figure}$$

Therefore, the number of pulses (1/3 of a square) that were utilized during the time from "0" to "t" in acceleration increasing section is 1/12 of pulses that were utilized in all fixed pulse driving.

For this reason, in S-curve acceleration/deceleration fixed pulse driving, when the number of output pulses during acceleration is more than 1/12 of total output pulses, MCX501 will stop increasing acceleration and start to decrease the acceleration value with the speed curve as shown in Fig. 2.2-9. [Rule of 1/12]

This method makes an ideal curve when the initial speed is 0, however the initial speed cannot be 0, so the pulses from 0 on the figure to the initial speed will be excess and will be output at the peak of the speed.

<The Prevention of Triangle Driving Profile in Decelerating Stop>

In linear acceleration/deceleration driving, if the decelerating stop is commanded during acceleration, the speed curve forms a triangle form. In S-curve acceleration/deceleration driving, if the decelerating stop is commanded during acceleration as shown in Fig. 2.2-10, deceleration starts after the acceleration reaches 0.

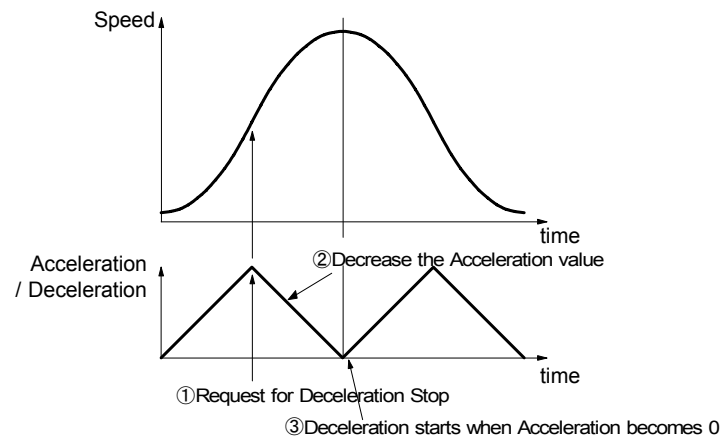


Fig. 2.2-10 Triangle Prevention of S-curve Acceleration/Deceleration by Decelerating Stop

■ Constraints for S-curve Acceleration/Deceleration Driving

- The drive speed cannot be changed during S-curve acceleration/deceleration fixed pulse driving.
- In S-curve acceleration/deceleration fixed pulse driving, if the drive pulse number is changed during deceleration, the S-curve profile cannot be exactly tracked.
- In S-curve acceleration/deceleration fixed pulse driving, if an extremely low value is set as the initial speed, premature termination (output of specified driving pulses is completed and terminated before the speed reaches the initial speed) or creep (output of specified driving pulses is not completed even if the speed reaches the initial speed and the rest of driving pulses is output at the initial speed) may occur in decelerating.
- The drive speed can be changed during S-curve acceleration/deceleration continuous pulse driving. However, the command to change the drive speed during acceleration/deceleration will be invalid. To change the speed in S-curve acceleration/deceleration continuous pulse driving, make sure to change it during constant speed driving (RR0 register CNST=1). Speed increase/decrease (70h, 71h) commands and speed change by synchronous action will also be invalid.

■ Example of Parameter Setting (Symmetry S-Curve Acceleration/Deceleration)

The figure shown below is the example of S-curve acceleration that reaches from the initial speed 100pps to the drive speed 40kpps in 0.4 seconds.

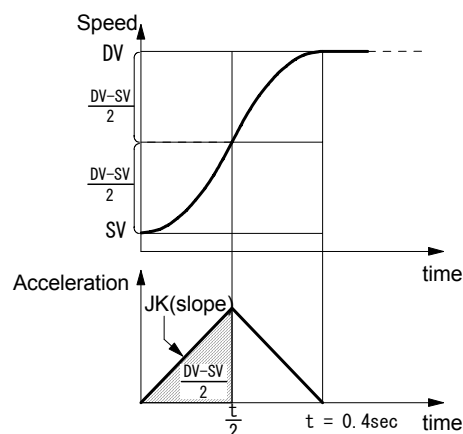


Fig. 2.2-11 Example of Symmetry S-Curve Acceleration/Deceleration Driving

At acceleration, acceleration is increased on a straight line based on a specified jerk (JK). The integral value (area indicated by diagonal lines) is the increased value of the speed from the initial speed “SV”.

Find the jerk (JK) to produce the result where the speed reaches a half $((DV-SV)/2)$ of the drive speed (DV) from the initial speed (SV) within a half $(t/2)$ of the acceleration time $(t=0.4\text{sec})$. Use the following expression to find a value of “JK” since the area indicated by diagonal lines which uses “JK” in the left-hand member, is equal to the right-hand member.

$$\frac{1}{2} \times JK \times \left(\frac{t}{2}\right)^2 = \frac{DV - SV}{2}$$

$$JK = \frac{4(DV - SV)}{t^2}$$

$$JK = \frac{4(40000 - 100)}{0.4^2} = 997,500 \text{ pps/sec}^2$$

Jerk	JK [pps/sec ²]
Drive speed	DV [pps]
Initial speed	SV [pps]
Acceleration time	t [sec]

Therefore, the parameters for S-curve acceleration/deceleration driving with the acceleration as shown in Fig. 2.2-11 are as follows.

Mode Setting	WR3 ← 0004h	Mode setting of WR3 register
Jerk	JK = 997500	
Acceleration	AC = 536870911	Set the maximum value : (1FFF FFFFh)
Initial speed	SV = 100	
Drive speed	DV = 40000	
Drive pulse number	TP = 27500	Set when fixed pulse driving is performed.

■ Partial S-curve Acceleration/Deceleration

In acceleration/deceleration driving with a linear section of acceleration and deceleration, it is possible to form a smooth S-curve only in the start/end part of acceleration or deceleration. To set the speed parameter for acceleration and deceleration, specify not the maximum value but the value of acceleration and deceleration in a linear section of acceleration/deceleration.

As shown in Fig. 2.2-12, section b,f indicate a linear section of acceleration/deceleration and section a,c,e,g indicate S-curve section of acceleration/deceleration.

At section a, the acceleration increases on a straight line from 0 to the acceleration setting value and the speed curve forms a secondary parabolic curve. When the acceleration reaches the acceleration setting value, the acceleration keeps that value and the speed curve forms a straight line in the acceleration of section b. If the difference between a specified drive speed and the current speed becomes less than the speed that was utilized at acceleration increasing, the acceleration starts to decrease at a specified jerk and the speed curve forms a parabola of reverse direction at section c. Also in deceleration, it forms a partial S-curve of deceleration.

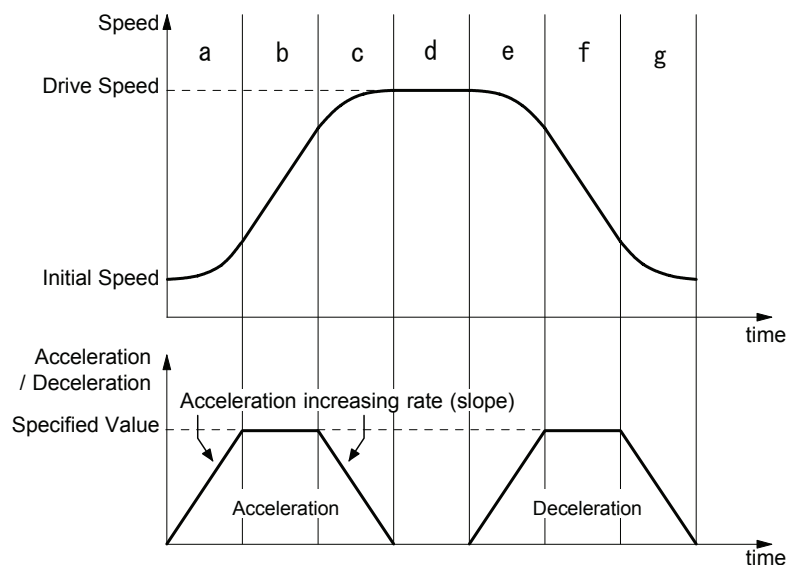


Fig. 2.2-12 Partial S-curve Acceleration/Deceleration Driving

■ Example of Parameter Setting (Partial S-curve Acceleration/Deceleration)

The figure shown below is the example of partial S-curve acceleration that reaches to 10kpps in 0.2 seconds by parabolic acceleration and then reaches from 10kpps to 30kpps in 0.2 seconds by acceleration on a straight line, finally reaches from 30kpps to 40kpps in 0.2 seconds by parabolic acceleration.

To simplify a calculation, suppose the initial speed is 0.

The acceleration increases to the first 10kpps in 0.2 seconds by straight line on a parabolic acceleration, and this integral value (area indicated by diagonal lines) corresponds to the rising speed 10kpps of the first parabolic acceleration. Therefore, the acceleration at 0.2 seconds is $10k \times 2 / 0.2 = 100kpps/sec$ and the jerk is $100k / 0.2 = 500kpps/sec^2$.

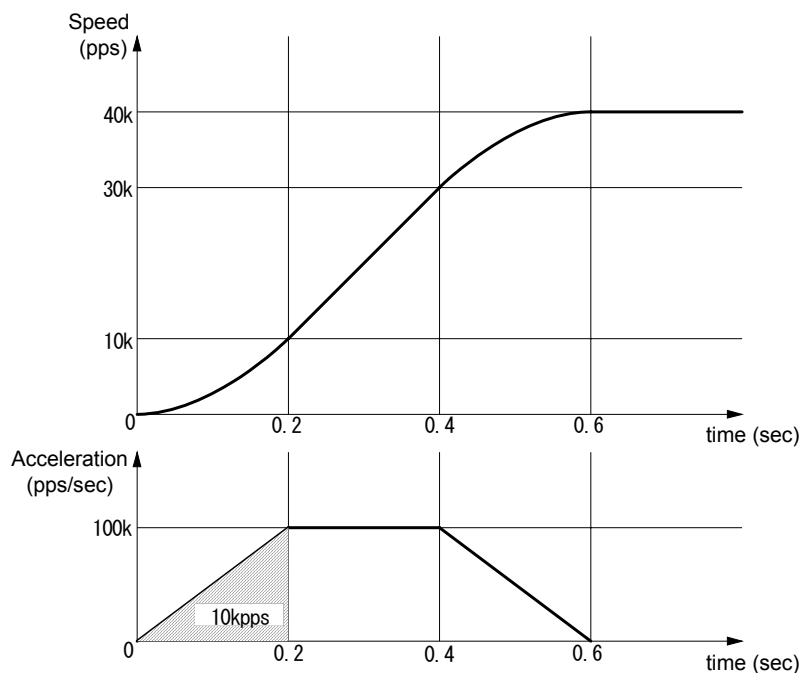


Fig. 2.2-13 Example of Partial S-curve Acceleration/Deceleration Driving

However the initial speed cannot be 0, the initial speed SV must be set the value larger than 0. In partial S-curve acceleration/deceleration, the initial speed SV should be the value more than a square root of acceleration AC.

Thus, with the acceleration as shown in Fig. 2.2-13, parameter setting of partial S-curve acceleration/deceleration driving is shown below.

Mode setting	WR3 ← 0004h	Mode setting of WR3 register
Jerk	JK = 500000	Set jerk for the section of parabolic acceleration (S-curve).
Acceleration	AC = 100000	Set Acceleration for the section of linear acceleration.
Initial speed	SV = 400	
Drive speed	DV = 40000	
Drive pulse number	TP = 40000	Set when fixed pulse driving is performed.

2.2.5 Non-symmetrical S-Curve Acceleration/Deceleration

In S-curve acceleration/deceleration driving, a non-symmetrical S-curve can be created by setting a jerk and a deceleration increasing rate individually. However, in non-symmetry S-curve acceleration/deceleration fixed pulse driving, a deceleration point must be specified manually because automatic deceleration is not available. Since a triangle form prevention function (1/12 rule) does not work either, a drive speed must be set according to the acceleration/deceleration increasing rate and the number of output pulses for fixed pulse driving.

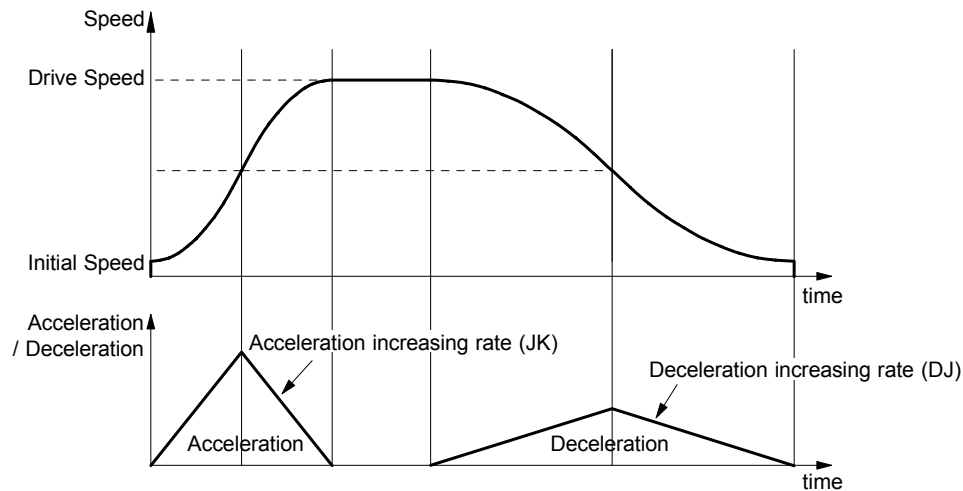


Fig. 2.2-14 Non-symmetry S-Curve Acceleration/Deceleration Driving

To perform non-symmetry S-curve acceleration/deceleration driving, bits D2 to 0 of WR3 register and the following parameters must be set.

Table 2.2-8 Mode Setting : Non-symmetry S-curve Acceleration/Deceleration

Mode Setting Bit	Symbol	Setting	Comment
WR3/D0	MANLD	1	Manual deceleration
WR3/D1	DSNDE	1	When in deceleration, deceleration setting value and deceleration increasing rate are used.
WR3/D2	SACC	1	S-curve acceleration/deceleration

Table 2.2-9 Setting Parameters : Non-symmetry S-curve Acceleration / Deceleration

Parameter	Symbol	Comment
Jerk	JK	
Deceleration increasing rate	DJ	
Acceleration	AC	Set the maximum value: 536,870,911 (1FFF FFFh)
Deceleration	DC	Set the maximum value: 536,870,911 (1FFF FFFh)
Initial speed	SV	
Drive speed	DV	
Drive pulse number/Finish point	TP	Not required for continuous pulse driving.
Manual deceleration point	DP	- Set the value calculated by subtracting the number of pulses that were utilized at deceleration from the number of output pulses in fixed pulse driving. - Not required for continuous pulse driving.

■ Example of Parameter Setting (Non-symmetry S-curve Acceleration/Deceleration)

The figure shown below is the example of non-symmetry S-curve acceleration/deceleration that reaches from the initial speed (SV) 100pps to the drive speed (DV) 40kpps in 0.2 seconds in accelerating, and decreases from the drive speed (DV) 40kpps to the initial speed (SV) 100pps in 0.4 seconds in decelerating. This is that drive pulse number (TP) is 20,000 and relative position driving.

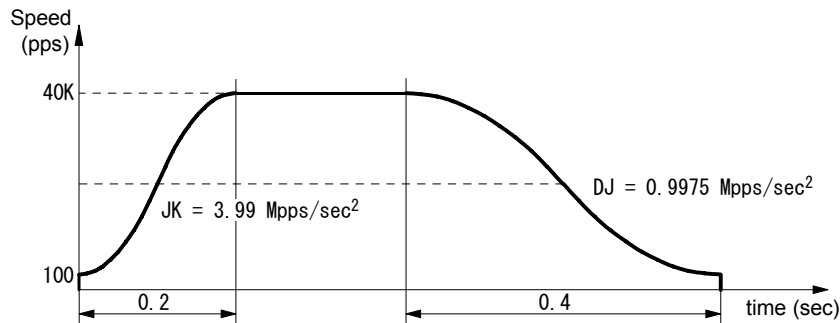


Fig. 2.2-15 Example of Non-symmetry S-Curve Acceleration/Deceleration Driving

Use the formula of the example of parameter setting (symmetry S-curve acceleration/deceleration) as described previously, and find a jerk and a deceleration increasing rate.

$$\text{Jerk} \quad JK = \frac{4(40000 - 100)}{0.2^2} = 3.99 \text{ Mpps/sec}^2$$

$$\text{Deceleration increasing rate} \quad DJ = \frac{4(40000 - 100)}{0.4^2} = 0.9975 \text{ Mpps/sec}^2$$

Next, set a deceleration point (DP) manually because automatic deceleration is not available in non-symmetry S-curve acceleration/deceleration. As a manual deceleration point, set the number of output pulses from the start of driving to the start of deceleration in fixed pulse driving. In relative position driving, it should be the value calculated by subtracting the number of pulses (Pd) that were utilized at deceleration from the number of drive pulses (TP), so first, find the number of pulses (Pd) that were utilized at deceleration.

$$\text{Pulses utilized at deceleration} \quad Pd = (DV + SV) \sqrt{\frac{DV - SV}{DJ}} = (40000 + 100) \sqrt{\frac{40000 - 100}{0.9975 \times 10^6}} = 8020$$

If the number of pulses (Pd) that were utilized at deceleration is 8,020 where the number of drive pulses (TP) is 20,000 in relative position driving, the manual deceleration point will be as follows.

$$\text{Manual deceleration point} \quad DP = TP - Pd = 20000 - 8020 = 11980$$

Therefore, parameter setting is shown below.

Mode setting	WR3←0007h	Mode setting of WR3 register
Jerk	JK = 3990000	
Deceleration increasing rate	DJ = 997500	
Acceleration	AC = 536870911	Set the maximum value : (1FFF FFFFh)
Deceleration	DC = 536870911	Set the maximum value : (1FFF FFFFh)
Initial speed	SV = 100	
Drive speed	DV = 40000	
Drive pulse number	TP = 20000	
Manual deceleration point	DP = 11980	

[Note]

- The above expression used for calculating the number of pulses that were utilized at deceleration is an ideal expression. In the actual IC operation, creep or premature termination occurs depending on the parameter values that are set.

2.2.6 Pulse Width and Speed Accuracy

■ Duty Ratio of Drive Pulse

The period time of +/- direction pulse driving is decided by system clock SCLK. The tolerance is within $\pm 1\text{CLK}$ (At $\text{CLK}=16\text{MHz}$, the tolerance is $\pm 62.5\text{nsec}$). Basically, the duty ratio of each pulse is 50% as shown below. When the parameter setting is $\text{DV} = 1000\text{pps}$, the driving pulse is $500\mu\text{sec}$ on its Hi level and $500\mu\text{sec}$ on its Low level and the period is 1.00msec .

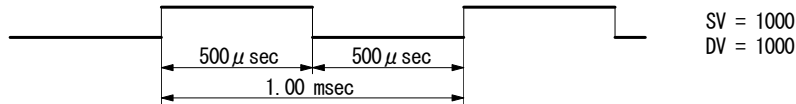


Fig. 2.2-16 Hi/Low Level Width of Driving Pulse Output (1000pps)

In acceleration/deceleration driving, the Low level pulse width is smaller than that of Hi level pulse during the acceleration; the Low level pulse is larger than that of Hi level pulse during the deceleration since the drive speed is increasing during outputting one drive pulse.

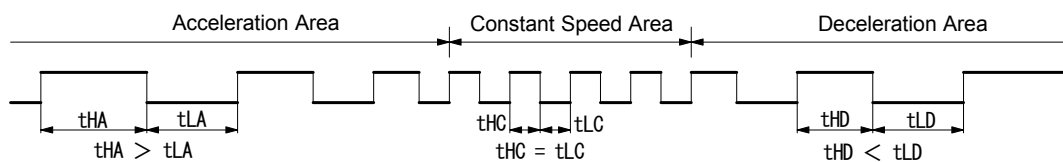


Fig. 2.2-17 Comparison of Drive Pulse Width in Acceleration / Deceleration

■ The Accuracy of Drive Speed

The circuits to generate drive pulses on MCX501 operate with input clock (CLK). If CLK input is standard 16MHz , the user had better drive the pulse speed in an exact multiple of CLK period (62.5nsec). However, in this case the frequency (speed) of driving pulse can only be generated by an exact multiple of CLK. For instance, double: 8.000MHz , triple: 5.333MHz , quadruple: 4.000MHz , five times: 3.200MHz , six times: 2.667MHz , seven times: 2.286MHz , eight times: 2.000MHz , nine times: 1.778MHz , ten times: 1.600MHz , Any fractional frequencies cannot be output. Therefore, MCX501 uses the following method to output any drive speed.

For instance, in the case of the drive speed $\text{DV} = 980\text{kpps}$, since this period is not an integral multiple of CLK period, pulses of 980kpps cannot be output under a uniform frequency. Therefore, as shown in the figure below, MCX501 combines 16 times and 17 times of CLK period in a rate of 674:326 to generate an average 980kpps .



Fig. 2.2-18 The Driving Pulse of 980kpps

According to this method, MCX501 can generate a constant speed driving pulse in a very high accuracy. And speed accuracy of pulse output is $\pm 0.1\%$ or less,

Using oscilloscope for observing the driving pulse, we can find the jitter about 1CLK (62.5nsec). This is no matter when putting the driving to a motor because the jitter will be absorbed by the inertia of motor system.

2.3 Position Control

MCX501 has two 32-bit up-and-down counters for controlling the current position (logical position counter and real position counter), which can compare with the current position by presetting a value to a multi-purpose register. In addition, the software limit function and variable ring function can be set to the logical and real position counters.

2.3.1 Logical Position Counter and Real position Counter

The logical position counter counts driving pulses in MCX501. When one +direction pulse is output, the counter will count up 1, and when one -direction pulse is output, the counter will count down 1.

The real position counter counts input pulse numbers from external encoder. The type of input pulse can be selected from either quadrature pulses type or Up/Down pulse type. (See Chapter 2.12.3)

Host CPU can read or write these two counters anytime. The counting range is between -2,147,483,648 ~ +2,147,483,647 and 2's complement is used for negative numbers. The values of the logical and real position counters are undefined at reset.

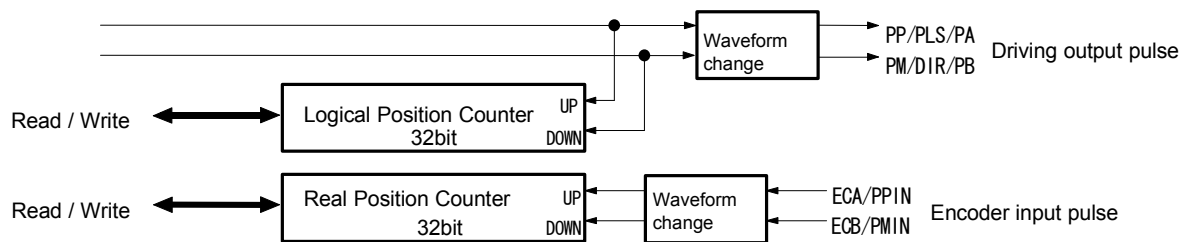


Fig. 2.3-1 Position Counter Functional Block Diagram

2.3.2 Position Comparison

MCX501 has four multi-purpose registers, which can be used to compare with the current position of the logical and real position counters. The comparison result of a multi-purpose register with the logical/real position counter can be read out even while driving. And when it meets the comparison condition, a signal can be output, or an interrupt or synchronous action activation can be executed.

For more details of the multi-purpose register comparison functions, see Chapter 2.4.

2.3.3 Software Limit

Software limit can be set to the logical position counter and real position counter. The object of software limit can be set by D14 bit of WR2 register. Two 32-bit registers (SLMT+, SLMT-) which set the software limit must be set the software limit position of +/- direction individually.

When the value of the logical/real position counter that the software limit is set is larger than the value of SLMT+ register, decelerating stop or instant stop is executed and D0 bit of RR2 register becomes 1. This error status will be cleared when the -direction driving command is executed and the value of the logical/real position counter is smaller than the value of SLMT+ register. It is the same with the SLMT- register of -direction.

In +direction software limit, if "position counter $\geq$ SLMT+ value", software limit error occurs. In -direction software limit, if "position counter $<$ SLMT- value", software limit error occurs.

Fig. 2.3-2 is the example of SLMT+ register = 10000, SLMT- register = -1000 and software limit function is enabled.

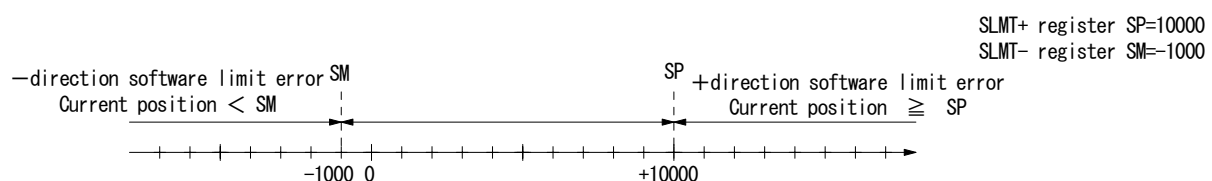


Fig. 2.3-2 Value Setting of Software Limit and Software Limit Error

Software limit function can be enabled/disabled by setting D13 bit of WR2 register. And there are two stop types of software limit, decelerating stop and instant stop, which sets D15 bit of WR2 register. SLMT+ and SLMT- registers can be written anytime.

Software limit function will be disabled and the values of SLMT+ and SLMT- registers will be undefined at reset.

2.3.4 Position Counter Variable Ring

A logical position counter and a real position counter are 32-bit up/down ring counters. Therefore, normally, when the counter value is incremented in the +direction from FFFF FFFFh which is the maximum value of the 32-bit length, the value is reset to 0. When the counter value is decremented in the -direction from 0, the value is reset to FFFF FFFFh. The variable ring function enables the setting of any value as the maximum value. This function is useful for managing the position of the axis in circular motions that return to the home position after one rotation, rather than linear motions.

The variable ring size, that is the maximum value of the logical/real position counter can be set to any value within the range of 1~2,147,483,647 (1~7FFF FFFFh). To use the variable ring function, set the logical position counter maximum value (LX) by logical position counter maximum value setting command (0Eh) and set the real position counter maximum value (RX) by real position counter maximum value setting command (0Fh).

The value of the logical position counter maximum value (LX) and real position counter maximum value (RX) will be FFFF FFFFh at reset. When not using the variable ring function, leave it at default.

■ Example of Variable Ring Setting

For instance, set as follows for a rotation axis that rotates one cycle with 10,000 pulses.

- ① Set 9,999 (270Fh) in the logical position counter maximum value (LX).
- ② Set 9,999 (270Fh) in the real position counter maximum value (RX) also if using a real position counter.

The count operation will be as follows.

- Increment in the +direction : ...→9998→9999→0→1→...
- Decrement in the -direction : ...→1→0→9999→9998→...

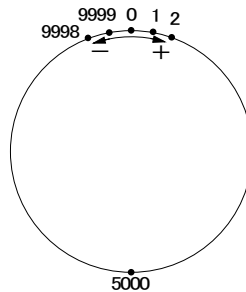


Fig. 2.3-3 Operation of Position Counter Ring Maximum Value 9999

[Note]

- It is possible to set the value within the range of 1~2,147,483,647 (1~7FFF FFFFh) as the maximum value of the variable ring function. The signed negative value (8000 0000h~FFFF FFEh) of a 32-bit register cannot be set.
- When setting values to the logical position counter (LP) and real position counter (RP), the values out of the range of the logical position counter maximum value (LX) and the real position counter maximum value (RX) cannot be set.

2.4 Multi-Purpose Register

MCX501 has four signed 32-bit multi-purpose registers (MR3~0).

Multi-purpose register can be used to compare with the current position, speed and timer, and then can read out the status which represents comparison result and can output as a signal. In addition, it can activate a synchronous action according to comparison result and can generate an interrupt. As an action of a synchronous action, it can load the values pre-set in multi-purpose registers as a new speed or drive pulse number, and can save the current position or speed in multi-purpose registers.

Multi-purpose registers can be written/read anytime, by using each multi-purpose register setting command (10h~13h) and multi-purpose register reading command (34h~37h).

The values of multi-purpose registers are undefined at reset.

2.4.1 Comparative Object and Comparison Condition

As the comparative objects of multi-purpose registers (MR3~0), the values of the logical position counter, real position counter, current drive speed and timer can be set. The comparison condition expression to the comparative object can be selected from $\geq$, $>$, $=$, $<$.

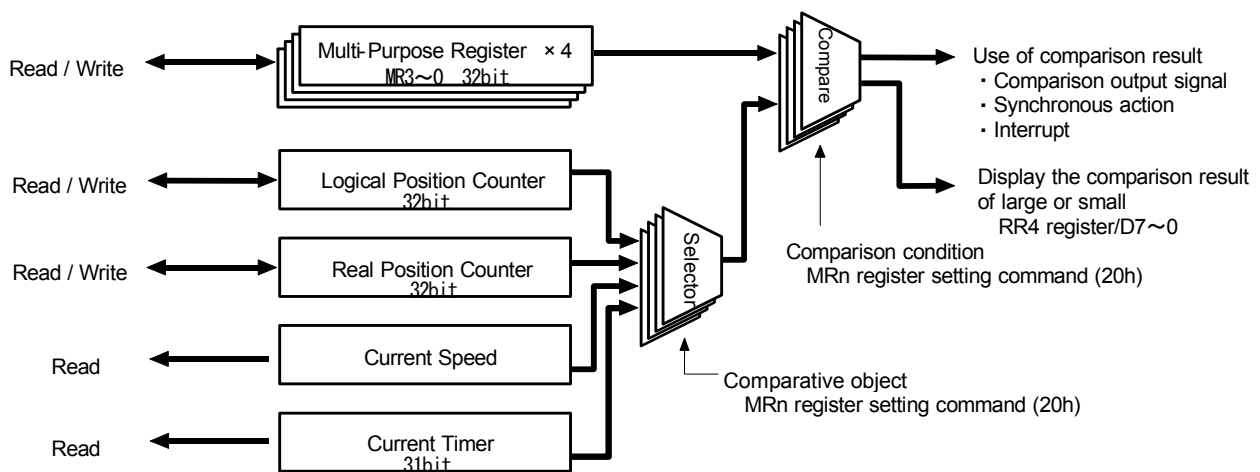


Fig. 2.4-1 Multi-Purpose Registers and Compare Function

The user can set the comparative object and comparison condition to four multi-purpose registers individually by using multi-purpose register mode setting command (20h). Set specified bits of WR6 data writing register and write multi-purpose register mode setting command (20h) to WR0 register, and then they will be set.

Multi-purpose register mode setting can be read out by multi-purpose register mode setting reading command (40h).

Multi-purpose register mode setting command (20h)

WR6	D15	D14	D13	D12 ^H	D11	D10	D9	D8	D7	D6	D5	D4 ^L	D3	D2	D1	D0
	M3C1	M3C0	M3T1	M3T0	M2C1	M2C0	M2T1	M2T0	M1C1	M1C0	M1T1	M1T0	M0C1	M0C0	M0T1	M0T0
	MR3 comparison condition		MR3 comparative object		MR2 comparison condition		MR2 comparative object		MR1 comparison condition		MR1 comparative object		MR0 comparison condition		MR0 comparative object	

Table 2.4-1 Setting of Comparative Object

(n:0~3)		
MnT1 bit	MnT0 bit	MRn Comparative Object
0	0	Logical position counter (LP)
0	1	Real position counter (RP)
1	0	Current drive speed value (CV)
1	1	Current timer value (CT)

Table 2.4-2 Setting of Comparison Condition

(n:0~3)		
MnC1 bit	MnC0 bit	MRn Comparison Condition
0	0	Comparative object $\geq$ MRn
0	1	Comparative object $>$ MRn
1	0	Comparative object $=$ MRn
1	1	Comparative object $<$ MRn

[Note]

When the comparative object is set to “current drive speed value (CV)” and comparison condition is set to “comparative object = MRn”, if the acceleration/deceleration exceeds 4,194,304 (400000h) pps/sec in linear and S-curve acceleration/deceleration driving, the comparison result may not become TRUE (active).

When the comparative object is “current drive speed value (CV)” and the acceleration/deceleration is more than this value, set the other conditions such as “comparative object $\geq$ MRn” and not “comparative object = MRn”.

■ Example: Comparison with Logical Position Counter

When the logical position counter value is larger than 500,000 and if the user wants the comparison result is TRUE, set as follows. In this case, MR0 is used as the register compared with the logical position counter.

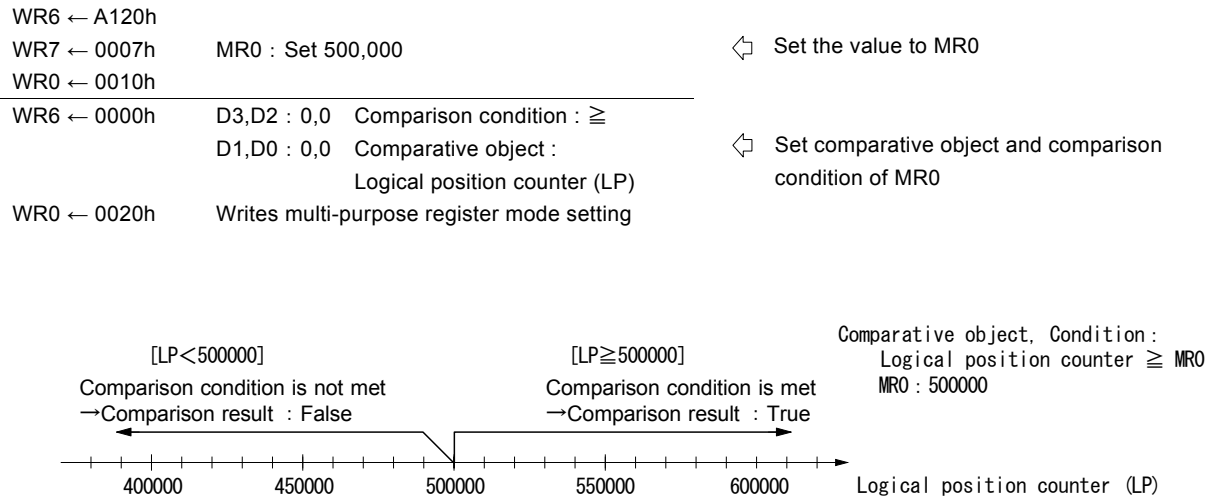


Fig. 2.4-2 Comparison Example of Multi-Purpose Register with Logical Position Counter

2.4.2 Usage of Comparison Result

The user can use the comparison result of comparative object with a multi-purpose register as a comparison output signal, synchronous action activation and interruption factor. The functions to use the comparison result and actions are as follows.

Table 2.4-3 Usage of Comparison Result and Actions

Function	Object	Action
Comparison output signal	PIO7~4 Output signals	When comparison result is TRUE, output signal is Hi.
Synchronous action activation	Synchronous action SYNC3~0	When comparison result changes to TRUE, synchronous action is activated.
Interruption factor	Interrupt function	When comparison result changes to TRUE, interrupt generates.

■ Comparison Output Signal

The user can output the comparison result of a multi-purpose register as a comparison output signal. When the comparison result of a multi-purpose register meets a specified comparison condition, the comparison output signal outputs Hi level, and when does not meet it, the comparison output signal outputs Low level.

The comparison results of multi-purpose registers (MR3~0) are output to each corresponding comparison output signal PIO7~4. PIO7~4 signals share the other signals such as the general purpose input/output signals. To use them as comparative output pins, the user needs to set the function of PIO7~4 signals to the comparison output signal by using PIO signal setting 1 command (21h) in advance.

Table 2.4-4 Comparison output signal and Bit corresponding to Multi-purpose Register

Multi-purpose register	Comparison output signal	PIO signal setting 1 command (21h) Setting bit of WR6 register
MR0	PIO4	WR6/D9,8 :1,1
MR1	PIO5	WR6/D11,10:1,1
MR2	PIO6	WR6/D13,12:1,1
MR3	PIO7	WR6/D15,14:1,1

For more details of the general purpose PIO signal, see Chapter 2.8.

■ Example: Comparison Output Signal

When the current drive speed exceeds 5,000pps during the driving, Hi is output to PIO5 output signal and when it is 5,000pps or less, Low is output to PIO5 output signal.

WR6 ← 1388h			
WR7 ← 0000h	MR1:Set 5,000		↩ Set the value to MR1
WR0 ← 0011h			
WR6 ← 0060h	D7,D6:0,1	Comparison condition: >	
	D5,D4:1,0	Comparative object: Current drive speed (CV)	↩ Set comparative object and comparison condition of MR1
WR0 ← 0020h	Writes multi-purpose register mode setting		
WR6 ← 0C00h	D11,D10:1,1	PIO5 Function: MR1 comparison output	↩ Set the function of PIO5 signal
WR0 ← 0021h	Writes PIO signal setting 1		

■ Synchronous Action Activation

Synchronous action can be activated according to the comparison result of a multi-purpose register. When the comparison result of a multi-purpose register changes to meet a specified comparison condition, the synchronous action is activated. If it already meets the comparison condition when the synchronous action is enabled, the synchronous action is not activated at that time. After it returns to False, if the comparison result of a multi-purpose register again changes to meet a specified comparison condition, the synchronous action will be activated.

The synchronous action activation according to the comparison result of multi-purpose register MR3~0 can be set as the activation factor of each corresponding synchronous action set SYNC3~0. To use the comparison result of a multi-purpose register as the activation factor of a synchronous action, firstly set the activation factor of a synchronous action set which the user wants to use as “MRn comparison changed to True” (activation factor code:01h) by the synchronous action SYNC0,1,2,3setting command (26h,27h,28h,29h) and then enable the synchronous action set by using in synchronous action enable setting command (81h~8Fh).

Table 2.4-5 Synchronous Action Set and Setting Command Corresponding to Multi-purpose Register

Multi-purpose Register	Synchronous Action Set	Synchronous Action Setting Command to set Activation Factor
MR0	SYNC0	Synchronous action SYNC0 setting command (26h)
MR1	SYNC1	Synchronous action SYNC1 setting command (27h)
MR2	SYNC2	Synchronous action SYNC2 setting command (28h)
MR3	SYNC3	Synchronous action SYNC3 setting command (29h)

In addition to the activation factor, synchronous action SYNC0,1,2,3 setting commands set other actions and repeat behavior for synchronous actions.

For more details of the synchronous action functions and settings, see Chapter 2.6.

■ Example: Synchronous Action Activation

While using 10 seconds timer, to activate relative position driving in SYNC2 after 5 seconds from timer-start, set as follows.
The timer activates the synchronous action after 5 seconds from timer-start and is up after 10 seconds.

WR6 ← 4B40h			
WR7 ← 004Ch	MR2 : Set 5,000,000		↩ Set the value to MR2
WR0 ← 0012h	(5 seconds = 5,000,000μsec)		
WR6 ← 9680h			
WR7 ← 0098h	Timer : Set 10,000,000		↩ Set 10 seconds to the timer value
WR0 ← 0016h	(10 seconds = 10,000,000)		
WR6 ← 0300h	D11,D10 : 0,0 Comparison condition: ≥ D9,D8 : 1,1 Comparative object: Current timer value (CT)		↩ Set comparative object and comparison condition of MR2
WR0 ← 0020h	Writes multi-purpose register mode setting		
WR6 ← 00A1h	Activation factor code 01h: MR2 comparison changed to True		
	Action code 0Ah : Start of relative position driving		↩ Set the function of synchronous action SYNS2
WR0 ← 0028h	Writes synchronous action SYNC2 setting		
WR0 ← 0084h	Synchronous action SYNC2 enable setting command		↩ Set to enable SYNC2

※ Parameters for relative position driving must be set in advance.

For more details of the relative position driving, see Chapter 2.1.1.

■ Generating an Interrupt

The user can generate an interrupt according to the comparison result of a multi-purpose register. When the comparison result of a multi-purpose register changes to meet a specified comparison condition, an interrupt generates. If it already meets the comparison condition when an interrupt is enabled, an interrupt does not generate at that time. After it returns the state not to meet a specified comparison condition, if the comparison result of a multi-purpose register again changes to meet the specified comparison condition, an interrupt will generate.

To generate an interrupt according to the comparison result of multi-purpose register MR3~0, the user needs to set each bit of the interrupt factor of WR1 mode register 1 to enable for the multi-purpose register that is used for comparison. The interrupt factor of when an interrupt generates can be checked by the interrupt factor check bit of RR1 Status register 1.

Table 2.4-6 Interrupt Enable and Check Bit corresponding to Comparison Result of Multi-purpose Register

Multi-purpose Register	Interrupt Enable Bit	Interrupt Factor Check Bit
MR0	WR1/D0: 1	RR1/D0: 1
MR1	WR1/D1: 1	RR1/D1: 1
MR2	WR1/D2: 1	RR1/D2: 1
MR3	WR1/D3: 1	RR1/D3: 1

For more details of the interrupt, see Chapter 2.10.

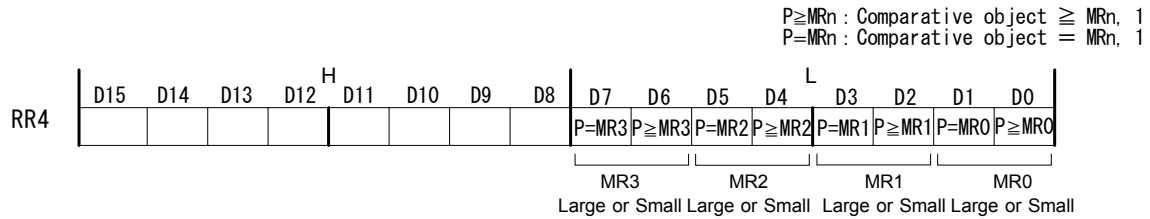
■ Example: Interrupt

When the real position counter value is passing through 30,000, an interrupt generates.

WR6 ← 7530h			
WR7 ← 0000h	MR3: Set 30,000		↩ Set the value to MR3
WR0 ← 0012h			
WR6 ← 0060h	D15,D14:1,0 Comparison condition: = D13, D12:0,1 Comparative object : Real position counter (RP)		↩ Set comparative object and comparison condition of MR3
WR0 ← 0020h	Writes multi-purpose register mode setting		
WR1 ← 0008h	Interrupt Factor: Enable MR3 comparison changed to True		↩ Set the interrupt factor

2.4.3 Comparison Result of Large or Small

The comparison result of large or small the multi-purpose register MR3~0 with each comparative object which is set by multi-purpose register mode setting command (20h) can be checked by RR4 register. Regardless of the comparison condition set by multi-purpose register mode setting command (20h), it displays the current state.



According to the bit of RR4 register, the comparison result of large or small the multi-purpose register as follows.

Table 2.4-7 Comparison Result Large or Small and Bit of RR4 register

(n:0~3)		
$P = MRn(D7,5,3,1)$	$P \geq MRn(D6,4,2,0)$	Comparison result with MRn
0	1	comparative object $> MRn$
x	1	comparative object $\geq MRn$
1	x	comparative object $= MRn$
x	0	comparative object $< MRn$

After the Example: Comparison with Logical Position Counter in 2.4.1 was performed, the bit of RR4 register changes according to the logical position counter value as shown below.

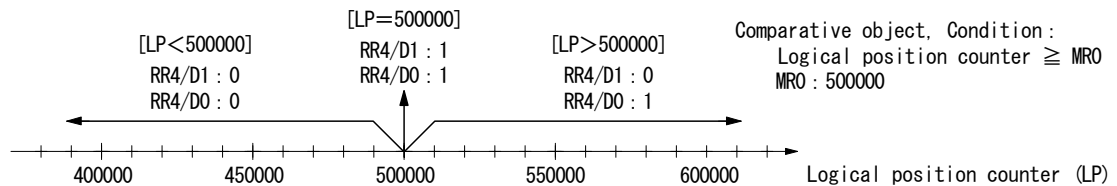


Fig. 2.4-3 Example of Comparison Result Large or Small and Bit of RR4 register

2.4.4 Load/Save of Parameters by Synchronous Action

By using the synchronous action, the user can load the value pre-set in a multi-purpose register as a new speed or drive pulse number, and save the current position and a speed to a multi-purpose register.

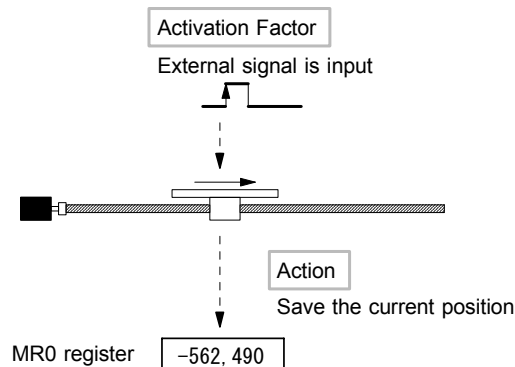


Fig. 2.4-4 Usage Example of Saving Parameters

There are 7 kinds of parameters that are loadable from the multi-purpose register by using the synchronous action and 5 kinds of parameters that can be saved to the multi-purpose register. Load/save of parameters will be executed to the multi-purpose register according to the synchronous action SYNC3~0 activation.

To load/save the parameters by using the synchronous action, the user needs to set the action code for the action of the synchronous action set which the user wants to use by executing synchronous action SYNC3~0 setting command (26h,27h,28h,29h). And the synchronous action set which the user wants to use must also be enabled by synchronous action enable setting command (81h~8Fh).

Table 2.4-8 Parameter Loaded/Saved by Synchronous Action

Action Code (Hex)	Loadable Parameter (Load)	Action Code (Hex)	Save the Current Value (Save)
01	Drive speed (DV)	05	Logical position counter (LP)
02	Drive pulse number/Finish point (TP)	06	Real position counter (RP)
03	Split pulse setting 1 (SP1)	07	Current timer value (CT)
04	Logical position counter (LP) (SYNC0)	08	Current drive speed (CV) (SYNC0)
	Real position counter (RP) (SYNC1)		Current acceleration/deceleration (CA) (SYNC1)
	Initial speed (SV) (SYNC2)		
	Acceleration (AC) (SYNC3)		
0F	Set drive pulse number (TP), and start relative position driving		
10	Set finish point (TP), and start absolute position driving		

Action Code (Hex): Code that sets synchronous action SYNC0,1,2,3 setting commands to the data writing register.

For more details of the load/save parameters to the multi-purpose register by using the synchronous action, see Chapter 2.6.

2.5 Automatic Home Search

This IC has a function that automatically executes a home search sequence such as high-speed home search → low-speed home search → encoder Z-phase search → offset drive without CPU intervention. The automatic home search function sequentially executes the steps from step 1 to step 4 that are listed below. The user can select execution or non-execution for each step. If non-execution is selected, it proceeds with next step without executing that step. And for each step, the user sets a search direction and a detection signal by mode setting. In steps 1 and 4, search operation or driving is performed at the high-speed that is set in the drive speed. In steps 2 and 3, search operation is performed at the low-speed that is set in the home search speed. In addition in steps 2 and 3, it is possible to output DCC (deviation counter clear signal) or clear the real/logical position counter when the signal is detected. The timer between steps can be used at the end of each step.

Table 2.5-1 Details of Automatic Home Search Sequence

Step number	Operation	Search speed	Detection signal
Step 1	High-speed home search	Drive speed (DV)	Specify any one of STOP0, STOP1 and Limit
Step 2	Low-speed home search	Home search speed (HV)	Specify either STOP1 or Limit
Step 3	Low-speed Z-phase search	Home search speed (HV)	STOP2
Step 4	High-speed offset drive	Drive speed (DV)	—

Generally, automatic home search has various operations according to the detection signal that is used. As shown in the following examples, there are some cases of a home search, such as using two sensors a near home signal and a home signal, and using only a home signal or only one limit signal.

(1) Example of the home search using a near home signal (STOP0) and a home signal (STOP1)

It searches a near home signal at high-speed in a specified direction, and then if a near home signal is detected, it performs decelerating stop. Next, it searches a home signal at low-speed, and then if a home signal is detected, it performs instant stop.

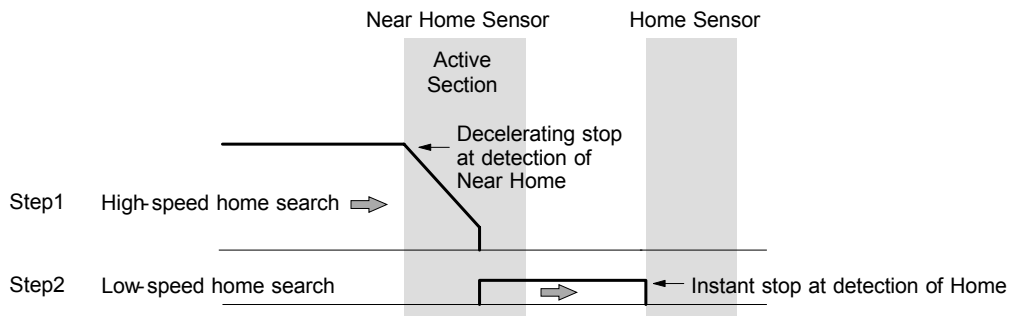


Fig. 2.5-1 Example 1 of Automatic Home Search

(2) Example of the home search using only a home signal (STOP1) or only one limit signal (LMTP/LMTM)

It searches a home signal or a limit signal at high-speed in a specified direction, and then if a signal is detected, it performs decelerating stop. Next, it escapes in the opposite direction from the signal active section, and then searches a home signal at low-speed, and if a home signal is detected, it performs instant stop. If a limit signal is used as a detection signal, it becomes the limit signal of a search direction.

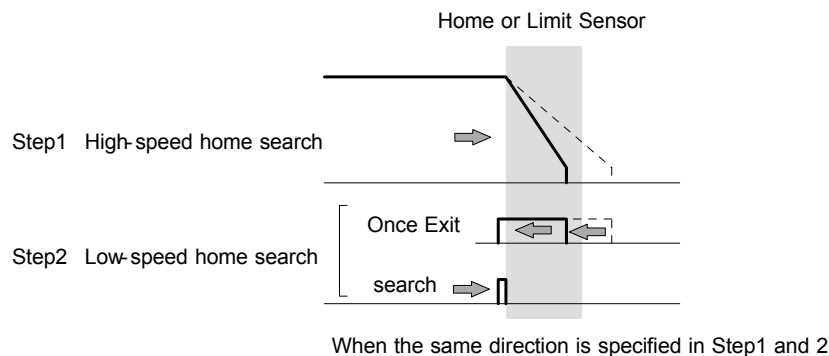


Fig. 2.5-2 Example 2 of Automatic Home Search

This IC provides several mode settings in response to these various home search operations.

2.5.1 Operation of Each Step

In each step, the user can specify execution/non-execution, the +/- search direction and a detection signal by mode setting. If non-execution is specified, it proceeds with next step without executing that step.

■ Step 1: High-speed home search

Drive pulses are output in a specified direction at the speed set in the drive speed (DV) until the specified detection signal becomes active. The user can specify any one of STOP0, STOP1 and limit signals as the detection signal. If a limit signal is selected, it becomes the limit signal of a search direction.

To perform high-speed search operation, set a higher value for the drive speed (DV) than the initial speed (SV). Acceleration/deceleration driving is performed and when the specified signal becomes active, the operation stops by deceleration.

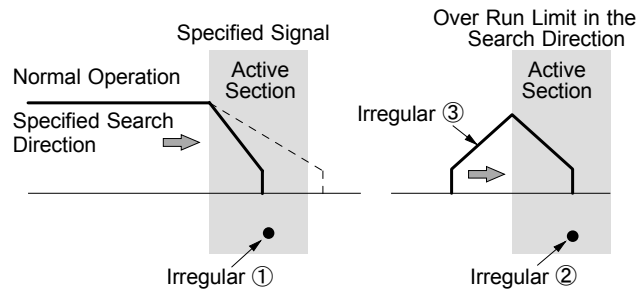


Fig. 2.5-3 Operation of Step 1

Irregular operation

- | | |
|---|---|
| ① A specified detection signal is already active before Step 1 starts. | → Proceeds with Step 2. |
| ② When STOP0 or STOP1 is specified as a detection signal and a limit signal in the search direction is already active before Step 1 starts. | → Proceeds with Step 2. |
| ③ When STOP0 or STOP1 is specified as a detection signal, and a limit signal in the search direction is activated during execution. | → Stops driving and proceeds with Step 2. |

Other operations in Step 1

At the end of step 1, the timer between steps can be used. For more details, see Chapter 2.5.3.

[Note]

- Since Step 1 performs a high-speed search, if the user specifies a limit signal as a detection signal, the limit stop mode must be set to decelerating stop mode (WR2/D12 : 1). For more details of the WR2 register, see Chapter 4.5.

■ Step 2: Low-speed home search

Drive pulses are output in a specified direction at the speed set in the home search speed (HV) until the specified detection signal becomes active. The user can specify either STOP1 or limit signal as a detection signal. If a limit signal is selected, it becomes the limit signal of a search direction. To perform low-speed search operation, set a lower value for the home search speed (HV) than the initial speed (SV). A constant speed driving mode is applied and when a specified signal becomes active, the operation stops instantly.

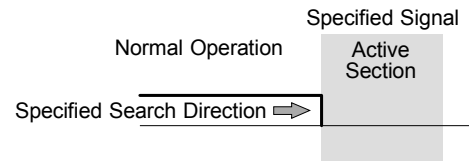


Fig. 2.5-4 Operation of Step 2

Irregular operation

- ① A specified signal is already active before Step 2 starts.

[Behavior]

The motor drives the axis in the direction opposite to a specified search direction at the home search speed (HV) until a specified signal becomes inactive. When a specified signal becomes inactive, the function executes Step 2 normal operation from the beginning.

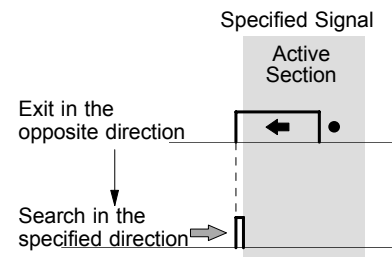


Fig. 2.5-5 Irregular Operation ① of Step 2

- ② When STOP1 is specified as a detection signal and a limit signal in the search direction is active before Step 2 starts.

[Behavior]

The motor drives the axis in the direction opposite to a specified search direction at the drive speed (DV) until STOP1 signal becomes active. When STOP1 signal becomes active, the motor drives in the direction opposite to a specified search direction at the home search speed (HV) until STOP1 signal becomes inactive. When STOP1 signal becomes inactive, the function executes Step 2 normal operation from the beginning.

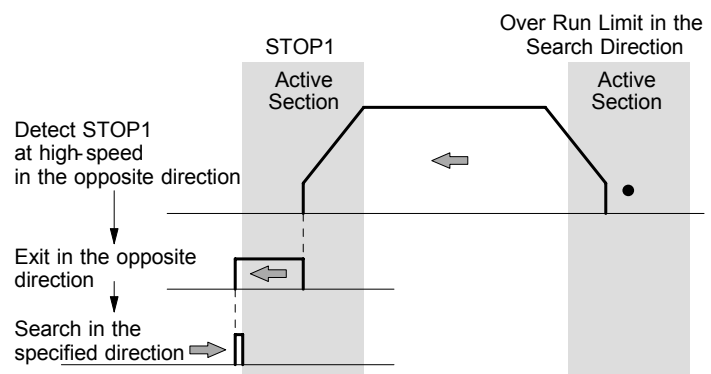


Fig. 2.5-6 Irregular Operation ② of Step 2

- ③ When STOP1 is specified as a detection signal and a limit signal in the search direction becomes active during execution.

[Behavior]

Driving stops and the operation described in Irregular operation ② is performed.

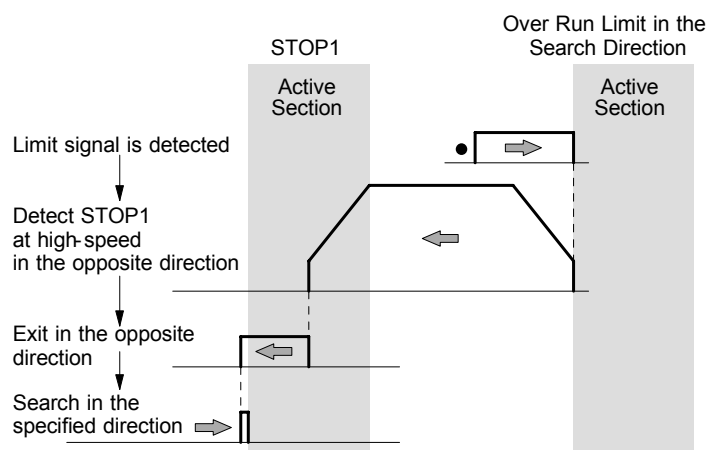


Fig. 2.5-7 Irregular Operation ③ of Step 2

④ When a detection signal is the same in Step 1 and Step 2 and a search direction is also the same in Step 1 and Step 2, and a specified signal is inactive before Step 2 starts.

[Behavior]

The operation described in Irregular operation ② is performed.

This operation is appropriate to the home search for a rotation axis.

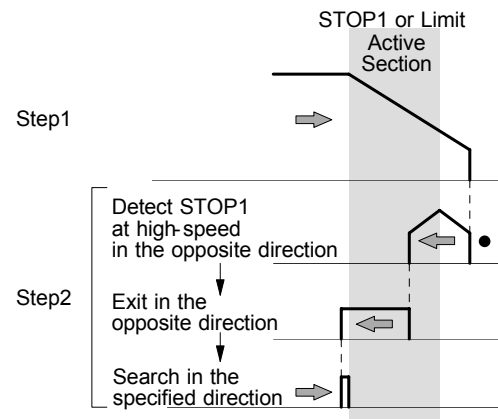


Fig. 2.5-8 Irregular Operation ④ of Step 2

Other operations in Step 2

While searching in a specified direction, when the detection signal of Step 2 changes from inactive to active, it is possible to output deviation counter clear signal (DCC) or clear the real/logical position counter. However during the irregular operation, if the detection signal changes to active while the motor drives the axis in the direction opposite to a specified search direction, these will not work. For more details of the deviation counter clearing (DCC) signal output, see Chapter 2.5.2.

After it escapes in the opposite direction of the irregular operation ①~④, the timer between steps can be used at the end of step 2.

■ Step 3: Low-speed Z-phase search

Drive pulses are output in a specified direction at the speed set in the home search speed (HV) until the encoder Z-phase signal (STOP2) becomes active. To perform low-speed search operation, set a lower value for the home search speed (HV) than the initial speed (SV). A constant speed driving mode is applied and when the encoder Z-phase signal (STOP2) becomes active, driving stops instantly.

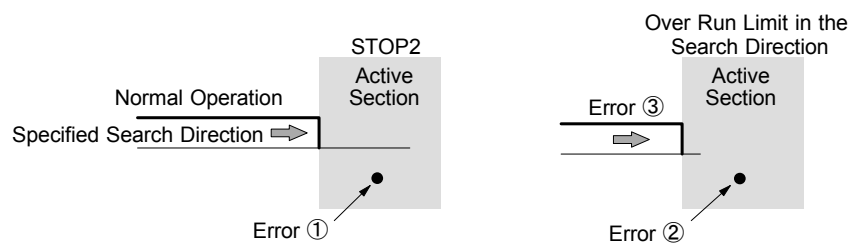


Fig. 2.5-9 Operation of Step 3

As a search condition, the AND condition of the encoder Z-phase signal (STOP2) and the home signal (STOP1) can be applied to stop driving.

Other operations in Step 3

When the encoder Z-phase signal (STOP2) changes to active, it is possible to clear the real/logical position counter. The real position counter can clear its counter without CPU intervention if STOP2 is active. This function is useful for solving the problem of Z-phase detection position slippage that occurs due to a delay of the servo system or the mechanical system when Z-phase search drive is set to low-speed.

When the encoder Z-phase signal (STOP2) changes to active, it is also possible to output deviation counter clear signal (DCC). And the timer between steps can be used at the end of step 3.

[Note]

- ① If the encoder Z-phase signal (STOP2) is already active at the start of Step 3, an error occurs and 1 is set in D6 bit of RR2 register. Automatic home search ends. Adjust the mechanical system so that Step 3 always starts from an inactive state that the encoder Z-phase signal (STOP2) is stable.
- ② If the limit signal in the search direction is already active before the start of Step 3, an error occurs and 1 is set in the search direction limit error bit (D2 or D3) of RR2 register. Automatic home search ends.
- ③ If the limit signal in the search direction becomes active during execution, search operation is interrupted and 1 is set in the search direction limit error bit (D2 or D3) of RR2 register. Automatic home search ends.

■ Step 4: High-speed offset drive

Drive pulses set in the drive pulse number (TP) are output at the speed set in the drive speed (DV) by relative position driving. This step 4 is normally used to move the axis from the mechanical home position to the operation home position. If a limit signal is selected as a detection signal, it is used to keep the operation home position away from the limit a little bit. If the limit signal of a drive direction becomes active before Step 4 starts or during execution, the operation stops due to an error and 1 is set in the search direction limit error bit (D2 or D3) of RR2 register. Automatic home search ends.

2.5.2 Deviation Counter Clearing Signal Output

In Step2 or Step3, when a specified detection signal (fixed to STOP2 in Step 3) rises to active, it is possible to output the deviation counter clear signal (DCC). And the logical level of deviation counter clear pulses and pulse width can be set. For more details, see Chapter 2.5.4.

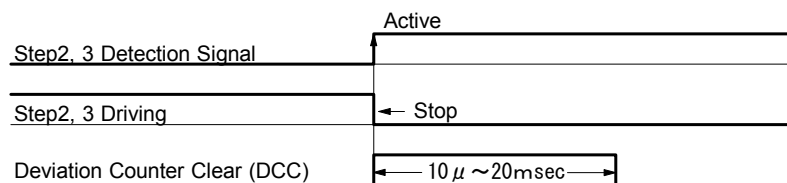


Fig. 2.5-10 Deviation Counter Clearing Signal Output

Deviation counter clearing output becomes active at the termination of search operation in Step 2 or Step 3, and Next step starts after the completion of deviation counter clear (DCC) pulses output.

2.5.3 Timer Between Steps

Each step for an automatic home search has the setting which reverses the motor. If the motor reverses suddenly, it may overload the mechanical system. The timer between steps helps to reduce the load on the mechanical system.

This IC can use the timer between steps at the end of each step. About Step 2, the timer between steps can be used after a specified irregular operation.

The user can set the use/nonuse of the timer between steps and timer value. For more details, see Chapter 2.5.4.

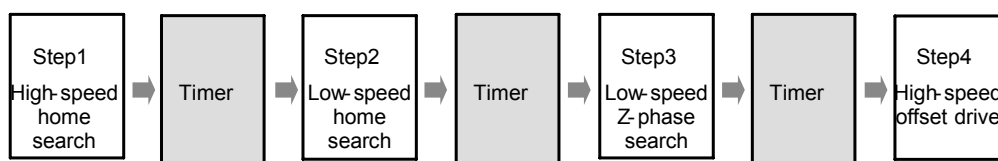


Fig. 2.5-11 Timer Between Steps

When the timer between steps is enabled, the timer starts at the end of each step and next step starts after the timer operation. About Step 2, if a specified irregular operation occurs, the timer between steps starts there too, and Step2 normal operation starts after the timer operation. For more details of the Step2 irregular operation, see Chapter 2.5.1.

[Note]

- The timer between steps cannot be set for each step individually. If enabled, all the timers which are between steps and after the specified irregular operation of Step 2 are all enabled, and the timer starts according to a specified timer value. If disabled, all the timers between steps are disabled.

2.5.4 Setting a Search Speed and a Mode

To perform an automatic home search, the following speed parameters and mode must be set.

■ Setting speed parameters

Table 2.5-2 Setting Speed Parameters

Speed parameter	Command code (hex)	Description
Drive speed (DV)	05	High-speed search and drive speed that is applied in Steps 1 and 4. However in irregular operation of Step 2, when the user searches in the direction opposite to a specified search direction, this drive speed is applied. Acceleration (AC) and initial speed (SV) must also be set to appropriate values to perform acceleration/deceleration driving. See Chapter 2.2.2.
Home search speed (HV)	14	Low-speed search speed that is applied in Steps 2 and 3. Set a value lower than the initial speed (SV) to stop instantly when a search signal becomes active. See Chapter 2.2.1.

■ Automatic home search mode setting 1

Automatic home search mode setting 1 can be set by setting each bit of WR6 register as shown below and then writing automatic home search mode setting 1 command (23h) into WR0 register. It specifies execution/non-execution of each step, detection signal, search direction, deviation counter clear output and logical/real position counter clear.

WR6	D15	D14	D13	D12 ^H	D11	D10	D9	D8	D7	D6	D5	D4 ^L	D3	D2	D1	D0
	S4EN	S3LC	S3RC	S3DC	S3DR	S3EN	S2LC	S2RC	S2DC	S2SG	S2DR	S2EN	S1G1	S1G0	S1DR	S1EN

① Execution/non-execution of each step

Specify whether operation of each step is executed.

0: Non-execution, 1: Execution

The specified bit for execution/non-execution in each step is shown in the table below.

Table 2.5-3 Execution/Non-execution Specified Bit in Each Step

	Step 1	Step 2	Step 3	Step 4	
Execution/Non-execution Specified Bit	D0 bit S1EN	D4 bit S2EN	D10 bit S3EN	D15 bit S4EN	0: Non-execution 1: Execution

② Search direction of each step

Specify the search direction of a detection signal in each step.

0: +direction, 1: -direction

The specified bit for a search direction in each step is shown in the table below.

Table 2.5-4 Search Direction Specified Bit in Each Step

	Step 1	Step 2	Step 3	Step 4	
Search Direction Specified Bit	D1 bit S1DR	D5 bit S2DR	D11 bit S3DR	—	0: +direction 1: -direction

③ Detection signal of each step

Step 1 can be selected from STOP0, STOP1 and limit signals. Step 2 can be selected from either STOP1 or limit signals. Step 3 is fixed to STOP2 signal. The same signal can be set in Step 1 and Step 2.

The detection signal specification in Step 1 and Step 2 is shown in the table below.

Table 2.5-5 Detection Signal Specification in Step 1 and Step 2

Step 1			Step 2	
D3 bit S1G1	D2 bit S1G0	Detection signal	D6 bit S2SG	Detection signal
0	0	STOP0	0	STOP1
0	1	STOP1	1	Limit signal
1	0	Limit signal		
1	1	—		

If a limit signal is specified as a detection signal, the limit signal in the search direction specified by D1 bit (S1DR) in Step 1 or D5 bit (S2DR) in Step 2 are selected. If the search direction is +direction, it becomes LMTP signal and If -direction, it becomes LMTM signal.

The logical level of an input signal that is detected must be set to Hi active or Low active by WR2 register. For more details of the WR2 register, see Chapter 4.5.

④ Deviation counter clear output and real/logical position counter clear setting

In Step2 and Step3, when a specified detection signal rises from inactive to active, the user can specify whether to output the deviation counter clear signal (DCC) or not. 0: Non- output, 1: Output

And at the end of Step 2, 3 and 4, the user can clear real/logical position counter. 0: Non- clear, 1: Clear

The specified bits for deviation counter clear signal (DCC) output and real/logical position counter clear in each step are shown in the table below.

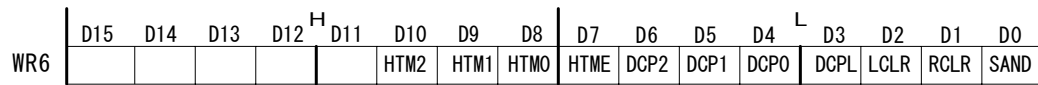
Table 2.5-6 DCC Output and Real/Logical Position Counter Clear Specified Bit in Each Step

	Step 1	Step 2	Step 3	Step 4	
Deviation counter clear signal (DCC) output	—	D7 bit S2DC	D12 bit S3DC	—	0: Non- output 1: Output
Real position counter clear	—	D8 bit S2RC	D13 bit S3RC	(※1)	0: Non- clear 1: Clear
Logical position counter clear	—	D9 bit S2LC	D14 bit S2LC	(※1)	

(※1) Real/logical position counter clear at the end of Step 4 (when Step 4 is executed), use the setting of automatic home search mode setting 2 (24h) for whether or not to clear at the end of an automatic home search. See “■Automatic home search mode setting 2” described in the next page.

■ Automatic home search mode setting 2

Automatic home search mode setting 2 can be set by setting each bit of WR6 register as shown below and then writing automatic home search mode setting 2 command (24h) into WR0 register. It specifies the logical level of deviation counter clear (DCC) output pulses and pulse width, enable/disable the timer between steps and timer time, real/logical position counter clear at the end of an automatic home search, AND stop condition for the encoder Z-phase signal (STOP2) and home signal (STOP1).



⑤ The logical level of deviation counter clear (DCC) output pulse and pulse width

For when deviation counter clear signal (DCC) is output in each step, the user can specify the logical level and pulse width. To specify the logical level, set D3 bit (DCPL) to 0: Hi pulse, 1: Low pulse

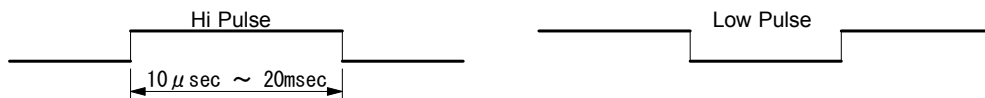


Fig. 2.5-12 The Logical Level of Deviation Counter Clear Output Pulse

Use 3bits, D6~4 (DCP2~DCP0) to set the pulse width. The settable pulse width is shown in the table below.

Table 2.5-7 The Pulse Width of Deviation Counter Clear Output

WR6/D6 DCP2	WR6/D5 DCP1	WR6/D4 DCP0	Pulse Width (CLK=16MHz)
0	0	0	10 μsec
0	0	1	20 μsec
0	1	0	100 μsec
0	1	1	200 μsec
1	0	0	1 msec
1	0	1	2 msec
1	1	0	10 msec
1	1	1	20 msec

⑥ Enable/disable the timer between steps

The user can set to enable/disable the timer between steps and timer time.

To enable/disable the timer between steps, set D7 bit (HTME) to 0: Disable, 1: Enable

The interval of the timer between steps is shown in the table below.

Table 2.5-8 The Interval of the Timer between Steps

WR6/D10 HTM2	WR6/D9 HTM1	WR6/D8 HTM0	Timer Time (CLK=16MHz)
0	0	0	1 msec
0	0	1	2 msec
0	1	0	10 msec
0	1	1	20 msec
1	0	0	100 msec
1	0	1	200 msec
1	1	0	500 msec
1	1	1	1000 msec

⑦ Real/logical position counter clear at the end of automatic home search

At the end of an automatic home search, the settings of real/logical position counter can be cleared.

To clear the real position counter, set D1 bit (RCLR) to 0: Non-clear, 1: Clear

To clear the logical position counter, set D2 bit (LCLR) to 0: Non-clear, 1: Clear

⑧ AND stop condition for encoder Z-phase signal (STOP2) and home signal (STOP1)

This is the function to stop driving when a home signal (STOP1) is active and an encoder Z-phase signal (STOP2) changes to active in Step 3. Set D0 bit (SAND) to 1, and driving will stop when a home signal (STOP1) is active and an encoder Z-phase signal (STOP2) changes to active.

[Note]

- Use this function only when STOP1 is selected as the detection signal in Step 2. When a limit signal is selected as the detection signal in Step 2, set to 0, or the operation does not work correctly.

2.5.5 Execution of Automatic Home Search and the Status

■ Execution of automatic home search

An automatic home search is executed by automatic home search execution command (5Ah). It will be started by writing the command code 5Ah to WR0 register after correctly setting the automatic home search mode and speed parameter.

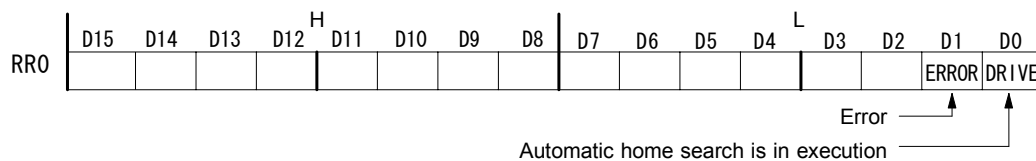
■ Suspension of automatic home search

In order to suspend automatic home search operation, write decelerating stop command (56h) or instant stop command (57h). The step currently being executed is suspended and the automatic home search is terminated.

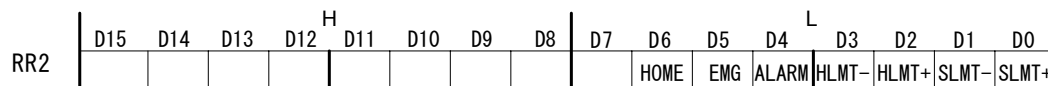
When the timer between steps is enabled and stop command is issued during the timer operation, the timer is also suspended and the automatic home search is terminated.

■ Status register

D0 bit of the main status register RR0 indicates driving is in execution. This bit also indicates the automatic home search is in execution. When an automatic home search starts, this bit is set to 1 and the state is maintained from the start of Step 1 operation to the end of Step 4 operation. At the termination of Step 4, the bit is reset to 0.



If an error occurs during the execution of automatic home search, D1 bit (ERROR) of RR0 register becomes 1. The error factor will be displayed in D6~D0 bits of RR2 register as shown below.



For more details of each error factor, see Chapter 4.11.

D14~D9 bits of RR3 register indicate the automatic home search execution state by numbers. The user can check the operation currently being executed.

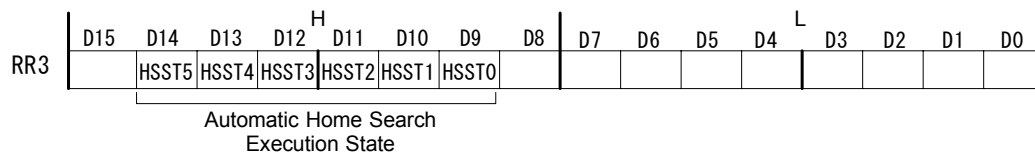


Table 2.5-9 Automatic Home Search Execution Status

Execution state	Execution step	Operation details
0		Waits for automatic home search execution command
3	Step 1	Waits for activation of a detection signal in the specified search direction
6		The timer is running between Step 1 and Step 2.
1 1	Step 2	Waits for activation of a detection signal in the direction opposite to the specified search direction (irregular operation)
1 5		Waits for deactivation of a detection signal in the direction opposite to the specified search direction (irregular operation)
1 8		The timer is running after irregular operation
2 0		Waits for activation of a detection signal in the specified search direction
2 3		The timer is running between Step 2 and Step 3, or deviation counter clear is outputting
2 8	Step 3	Waits for activation of STOP2 signal in the specified search direction
3 2		The timer is running between Step 3 and Step 4, or deviation counter clear is outputting.
3 6	Step 4	Offset driving in the specified search direction

2.5.6 Errors Occurring at Automatic Home Search

The following table lists the errors that may occur during the execution of an automatic home search.

Table 2.5-10 Errors Occurring at Automatic Home Search

Cause of the error	Operation of IC at the error	Display at termination
The ALARM signal was activated in any of the Steps 1 to 4	The search driving stops instantly without executing the following steps.	RR0/D1 : 1, RR2/D4 : 1
The EMGN signal was activated in any of the Steps 1 to 4	The search driving stops instantly without executing the following steps.	RR0/D1 : 1, RR2/D5 : 1
The limit signal in the positive direction (LMTP/M) is activated in Step 3 (Note)	The search driving stops instantly / by deceleration without executing the following steps.	RR0/D1 : 1, RR2/D3 or D2 : 1
The limit signal in the positive direction (LMTP/M) is activated in Step 4 (Note)	The offset action stops instantly / by deceleration and the operation stops.	RR0/D1 : 1, RR2/D3 or D2 : 1
The STOP2 signal is already active at the start of Step 3	Operation stops without executing the following steps.	RR0/D1 : 1, RR2/D6 : 1

Make sure to check the error bit (RR0/D1) of the main status register after the termination of an automatic home search. If the error bit is 1, the automatic home search is not performed correctly.

(Note) In Steps 1 and 2, when the limit signal in the positive direction becomes active, search driving stops instantly / by deceleration, however the error does not occur.

■ Symptom at sensor failure

It describes the symptoms when a failure occurs regularly in the sensor circuit such as a home search signal or a limit signal. However, analysis of intermittent failures caused by noise around the cable path, loose cable, or unstable operation of the device is difficult and such failures are not applicable to these cases described below. These symptoms may occur due to a logical setting error or signal wiring error at the development of a customer system.

Table 2.5-11 Symptom at Sensor Failure

Failure cause		Symptom
Failure in the device of the limit sensor and wiring path	Kept ON	The axis does not advance to the direction and the limit error bit (RR2/D3 or D2) is set to 1 at the termination.
	Kept OFF	The axis runs into the mechanical terminal point and the home search operation does not terminate.
Failure in the device of the Step1 detection signal (STOP0,1) sensor and wiring path	Kept ON	Although Step 1 is enabled and automatic home search is started from the signal OFF position, the axis advances to Step 2 without executing Step 1 (high-speed home search).
	Kept OFF	Operation stops in Step 1 (high-speed home search) by setting the limit and proceeds with irregular operation of Step 2. The home search result is correct, however, the operation is not normal.
Failure in the device of the Step2 detection signal (with STOP1) sensor and wiring path	Kept ON	The axis moves in the opposite direction in Step 2 (low-speed home search) and stops by setting the limit. At the termination, the error bit (RR2/D3 or D2) of the limit in the opposite direction is set to 1.
	Kept OFF	The axis moves in the opposite direction after setting the limit in the specified direction in Step 2 (low-speed home search) and terminates by setting the limit in the opposite direction. At the termination, the error limit (RR2/D3 or D2) of the limit in the reverse direction is set to 1.
Failure in the device of the Z-phase (STOP2) sensor and wiring path	Kept ON	Operation stops due to an error in Step 3 (low-speed Z-phase search). RR2/D6 is set to 1.
	Kept OFF	Operation stops in Step 3 (low-speed Z-phase search) by setting the limit in the specified direction. The error bit of the limit in the specified direction (RR2/D3 or D2) is set to 1 at the termination.

2.5.7 Notes on Automatic Home Search

■ Search speed

A home search speed (HV) must be set to a low speed to increase the home search position precision. Set a value lower than the initial speed to stop the operation immediately when an input signal becomes active.

For the encoder Z-phase search of Step 3, the relationship between the Z-phase signal delay and the home search speed (HV) becomes important. For instance, if a total of the photo coupler delay time of the Z-phase signal path and delay time of the integral filter incorporated in the IC is the maximum 500µsec, the home search speed must be set so that the encoder Z-phase output is ON for more than 1msec.

■ Step 3 (Z-phase search) starting position

In the Z-phase search of Step 3, the function stops search driving when the Z-phase signal (STOP2) changes from inactive to active. Therefore, the Step 3 starting position (that is, Step 2 stop position) must be stable and different from this change point. Normally, adjust mechanically so that the Step 3 starting position becomes the 180° opposite side to the encoder Z-phase position.

■ Software limit

Disable the software limit during the execution of automatic home search. If software limit is enabled, the automatic home search is not performed correctly. After the automatic home search is finished correctly, set a software limit after setting the real / logical position counter.

■ Logical setting of each input signal

Use the bits (WR2/D0,D2,D4) of WR2 register for the active logical setting of the input signal (STOP0,1,2) that is used by an automatic home search. In an automatic home search, the settings in the bits (WR2/D1,D3,D5) that enable/disable each signal are ignored.

2.5.8 Examples of Automatic Home Search

■ Example 1 Home search using a home signal

High-speed and low-speed home search is performed by one home signal, and encoder Z-phase search is not performed. Make sure to input a home signal to STOP1.

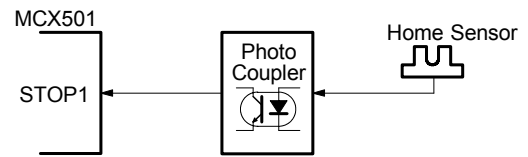


Fig. 2.5-13 Connection of Example 1 Automatic Home Search

The operation steps of an automatic home search are shown in the table below.

Table 2.5-12 Automatic Home Search Example 1 Operation

Step	Operation	Execution/ Non- execution	Detection signal	Signal level	Search direction	Search speed
1	High-speed search	Execution	STOP1	Low active	— direction	20,000pps
2	Low -speed search	Execution			— direction	500pps
3	Z-phase search	Non- execution	—	—	—	—
4	Offset drive	Execution	—	—	+ direction	20,000pps

In Step 1, a home search is performed at a high-speed of 20,000pps in the — direction until STOP1 signal detects Low level, and if it detects Low level (active), operation stops by deceleration.

In Step 2, if STOP1 signal is Low level (active), it drives at a low-speed of 500pps in the direction opposite to a specified direction (in this case + direction) by irregular operation ①, and then if STOP1 signal becomes Hi level (that is it escapes STOP1 active section), operation stops. After that it drives at a low-speed of 500pps in the direction specified by Step 2 and if STOP1 signal becomes Low level again, operation stops.

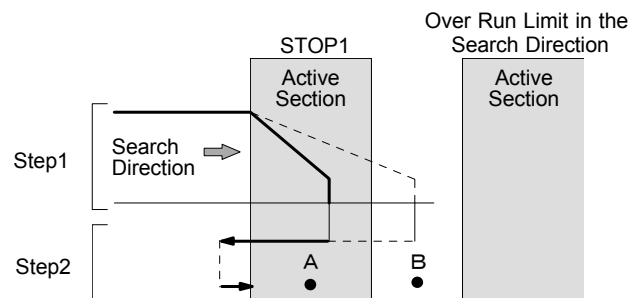


Fig. 2.5-14 Operation of Example 1 Automatic Home Search

In Step 1, in the case when it passes through STOP1 active section and then stops by deceleration, as the dash line shown in the figure above, it returns in the reverse direction once and escapes STOP1 active section, then search operation is performed in the specified direction by Step 2. This operation is applied to only when a detection signal and search direction is the same in Step 1 and Step 2.

When the automatic home search starting position is in point A as shown in the figure above, the function performs irregular operation ① of Step 2 without executing Step 1. When the starting position is in point B, the function performs irregular operation ② of Step 2 after setting the limit in the search direction in Step 1. For more details of the irregular operation ②, see Chapter 2.5.1.

In this example, suppose that a home search is performed without an encoder such as a stepping motor, and Z-phase search is not performed in Step 3. In Step 4, offset driving is performed to the operation home position up to 3500 pulses in the + direction.

【Program Example】

```

// WR2 Register setting
WR2 ← 0800h Write // Home signal logical setting: STOP1: Low active
                  // Enables hardware limit

// Input signal filter mode setting
WR6 ← 0A0Fh Write // D11~D8 1010 Filter delay: 512μsec
                  // D2      1 STOP1 signal: Enables the filter
WR0 ← 0025h Write // Writes a command

// Automatic home search mode setting 1
WR6 ← 8037h Write // D15      1 Step 4 execution/non-execution: Execution
                  // D14      0 Step 3 LP clear           Disable
                  // D13      0 Step 3 RP clear           Disable
                  // D12      0 Step 3 DCC output:        Disable
                  // D11      0 Step 3 search direction:  —
                  // D10      0 Step 3 execution/non-execution: Non-execution
                  // D9       0 Step 2 LP clear           Disable
                  // D8       0 Step 2 RP clear           Disable
                  // D7       0 Step 2 DCC output:        Disable
                  // D6       0 Step 2 detection signal:   STOP1
                  // D5       1 Step 2 search direction:  —direction
                  // D4       1 Step 2 execution/non-execution : Execution
                  // D3,2     0,1 Step 1 detection signal:  STOP1
                  // D1       1 Step 1 search direction:  —direction
                  // D0       1 Step 1 execution/non-execution : Execution
WR0 ← 0023h Write // Writes a command

// Automatic home search mode setting 2
WR6 ← 0000h Write // D15      0
                  // D14      0
                  // D13      0
                  // D12      0
                  // D11      0
                  // D10~8    0 Timer value
                  // D7       0 Timer between steps      Disable
                  // D6~4     0 DCC pulse width
                  // D3       0 DCC pulse logic
                  // D2       0 At the termination of home search, LP clear Disable
                  // D1       0 At the termination of home search, RP clear Disable
                  // D0       0 Step 2 & 3               Disable
WR0 ← 0024h Write // Writes a command

// High-speed home search and low-speed home search setting
WR6 ← 7318h Write // Acceleration/deceleration : 95,000 PPS/SEC
WR7 ← 0001h Write
WR0 ← 0002h Write

WR6 ← 03E8h Write // Initial speed : 1000 PPS
WR7 ← 0000h Write
WR0 ← 0004h Write

WR6 ← 4E20h Write // Speed of step 1 and 4 : 20000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 01F4h Write // Speed of step 2 : 500 PPS
WR7 ← 0000h Write
WR0 ← 0014h Write

// Offset pulse setting
WR6 ← 0DACH Write // Offset driving pulse count : 3500
WR7 ← 0000h Write
WR0 ← 0006h Write

// Starts execution of automatic home search
WR0 ← 005Ah Write

```

■ Example 2 Home search using a limit signal

The example that uses a limit signal of one side as an alternative home signal and performs a home search. In this case, a limit signal in the — direction is used as an alternative home signal. To perform a home search by using a limit signal, the following two conditions are applied.

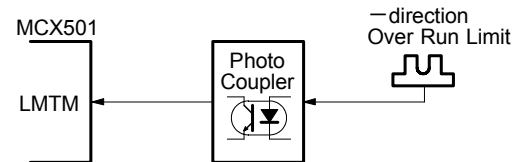


Fig. 2.5-15 Connection of Example 2 Automatic Home Search

- When high-speed search operation in Step 1 is performed, decelerating stop must be done sufficiently within the distance from the limit signal activation position to the mechanical limit position.
- The automatic home search position is not beyond the limit signal active section in the search direction (B in Fig. 2.5-16).

The operation steps of an automatic home search in this case are shown in the table below. The mode setting in Steps 1 and 2, when a search direction is specified in the — direction and a limit signal is specified as a detection signal, the limit signal of the — direction is determined (LMTM).

Table 2.5-13 Automatic Home Search Example 2 Operation

Step	Operation	Execution/ Non- execution	Detection signal	Signal level	Search direction	Search speed
1	High-speed search	Execution	LMTM	Low active	— direction	20,000pps
2	Low -speed search	Execution			— direction	500pps
3	Z-phase search	Non- execution	—	—	—	—
4	Offset drive	Execution	—	—	+ direction	20,000pps

The operation from Step 1 to Step 4 is the same as the operation using a home signal (STOP1) described above.

When the automatic home search starting position is in point A as shown in the right side figure, the function performs irregular operation ① of Step 2 without executing Step 1. And it escapes in the reverse direction from the limit signal active section once, and then search operation is performed in the specified direction.

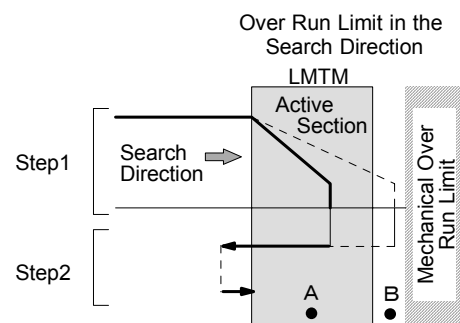


Fig. 2.5-16 Operation of Example 2 Automatic Home Search

【Program Example】

// WR2 Register setting

WR2 ← 1800h Write // Limit signal logical setting: LMTM: Low active
// Enables hardware limit Decelerating stop

Note1

// Input signal filter mode setting

WR6 ← 0A0Fh Write // D11~D8 1010 Filter delay :512μsec
// D1 1 LMTM signal: Enables the filter
WR0 ← 0025h Write // Writes a command

// Automatic home search mode setting 1

WR6 ← 807Bh Write // D15 1 Step 4 execution/non-execution : Execution
// D14 0 Step 3 LP clear : Disable
// D13 0 Step 3 RP clear : Disable
// D12 0 Step 3 DCC output : Disable
// D11 0 Step 3 search direction : —
// D10 0 Step 3 execution/non-execution : Non-execution
// D9 0 Step 2 LP clear : Disable
// D8 0 Step 2 RP clear : Disable
// D7 0 Step 2 DCC output : Disable
// D6 1 Step 2 detection signal : LMTM

```

// D5      1 Step 2 search direction:      -direction
// D4      1 Step 2 execution/non-execution: Execution
// D3,2    1,0 Step 1 detection signal:    LMTM
// D1      1 Step 1 search direction:      -direction
// D0      1 Step 1 execution/non-execution: Execution
WR0 ← 0023h Write // Writes a command

// Automatic home search mode setting 2
WR6 ← 0000h Write // D15      0
// D14      0
// D13      0
// D12      0
// D11      0
// D10~8    0 Timer value
// D7       0 Timer between steps          Disable
// D6~4     0 DCC pulse width
// D3       0 DCC pulse logic
// D2       0 At the termination of home search, LP clear Disable
// D1       0 At the termination of home search, RP clear Disable
// D0       0 Step 2 & 3                  Disable
WR0 ← 0024h Write // Writes a command

// High-speed home search and low-speed home search setting
WR6 ← 7318h Write // Acceleration/deceleration : 95,000 PPS/SEC
WR7 ← 0001h Write
WR0 ← 0002h Write

WR6 ← 03E8h Write // Initial speed : 1000 PPS
WR7 ← 0000h Write
WR0 ← 0004h Write

WR6 ← 4E20h Write // Speed of step 1 and 4 : 20000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 01F4h Write // Speed of step 2 : 500 PPS
WR7 ← 0000h Write
WR0 ← 0014h Write

// Offset pulse setting
WR6 ← 0DACH Write // Offset driving pulse count : 3500
WR7 ← 0000h Write
WR0 ← 0006h Write

// Starts execution of automatic home search
WR0 ← 005Ah Write

```

Note1: The bits in WR2 register, D10 bit is to set the logical setting of a limit signal, D11 bit is to enable a limit function and D12 bit is to set a limit operation. However in this case, when a limit signal is used as a detection signal, the limit signal will be enabled regardless of D11 setting in the operation of that step (D11 setting does not affect the operation of steps using a limit signal as a detection signal). D12 bit must be enabled decelerating stop and about D10 bit, set it according to the usage.

[Notes on using limit signals]

- The same search direction must be applied for Steps 1 and 2. For Step 3 (Z-phase search), apply a direction opposite to the direction of Steps 1 and 2. For Step 4 also (offset driving), apply a direction opposite to Steps 1 and 2 and make sure that automatic home search operation stops at the position beyond the limit active section.

■ Example 3 Home search for a servo motor

In the case of the pulse input type servo driver, normally an encoder Z-phase signal is output from the driver (a servo amplifier). To perform the home search with high position precision, a deviation counter in the driver must be cleared in the output timing of the encoder Z-phase and a deviation counter clear signal must be input. The example of the home search connecting these signals is shown below.

As shown in the figure below, the home signal (STOP1) is input through the interface circuit from the home sensor. The encoder Z-phase input (STOP2) and the deviation counter clear output (DCC) are connected to the servo driver through the interface circuit.

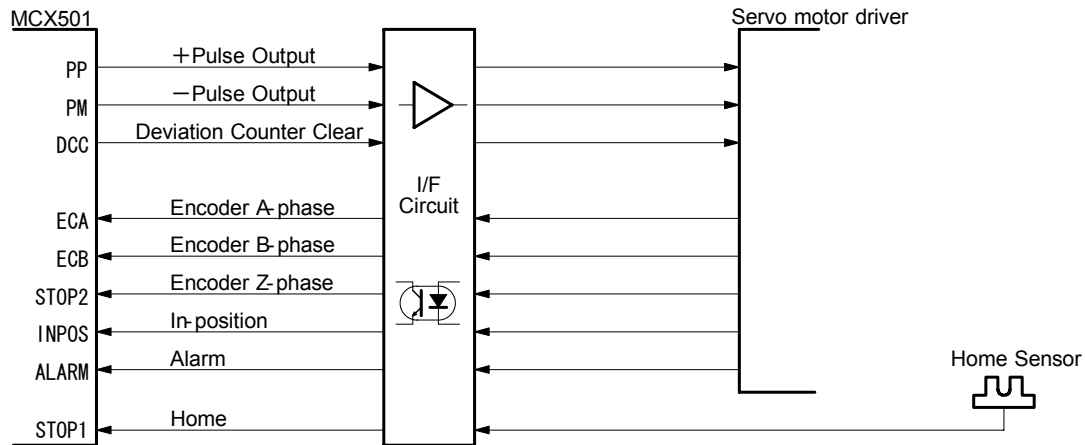


Fig. 2.5-17 Connection of Example 3 Automatic Home Search

Note: The encoder Z-phase input must be connected to STOP2 of the IC. The line receiver or the high speed photo coupler is appropriate to the interface circuit for a rapid response.

Table 2.5-14 Automatic Home Search Example 3 Operation

Step	Operation	Execution/ Non- execution	Detection signal	Signal level	Search direction	Search speed
1	High-speed search	Execution	STOP1	Low active	— direction	20,000pps
2	Low -speed search	Execution			— direction	500pps
3	Z-phase search	Execution	STOP2	Low	— direction	500pps
4	Offset drive	Execution	—	—	+ direction	20,000pps

The operation from Step 1 to Step 2 is the same as the operation using a home signal (STOP1) described above.

When STOP1 input becomes Low in Step 2, Step 2 ends and it proceeds with Step 3. In Step 3, a home search is performed at a speed of 500pps in the — direction until STOP2 (Z-phase) signal detects Low level, and if it detects Low level, operation stops instantly. DCC (deviation counter clear) is output by the ↓ of STOP2 input signal. In this case, DCC signal is set to output Hi pulses of 100 μ sec.

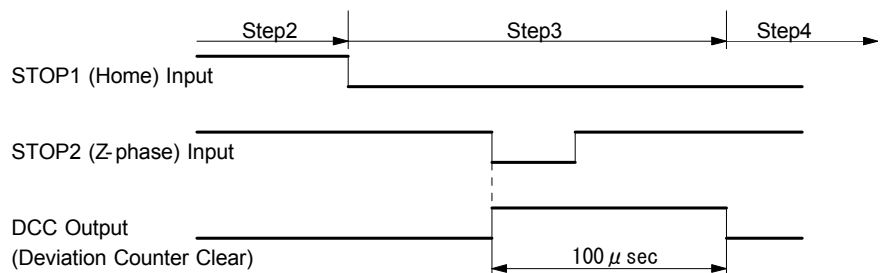


Fig. 2.5-18 Operation of Example 3 Automatic Home Search

In addition, when the STOP2 (Z-phase) signal becomes Low active in Step 3, the real position counter and logical position counter should be set to clear them.

【Program Example】

```

// WR2 Register setting
WR2 ← 0800h Write // Home signal logical setting: STOP1,2:Lowactive
// Enables hardware limit

// Input signal filter mode setting
WR6 ← 0ACFh Write // D15~D12 0000 FilterFE6,7 delay:500nsec
// D11~D8 1010 FilterFE0-5 delay:512μsec
// D6 1 STOP2 signal: Enables the filter
// D2 1 STOP1 signal: Enables the filter
WR0 ← 0025h Write // Writes a command

// Automatic home search mode setting 1
WR6 ← FC37h Write // D15 1 Step 4 execution/non-execution : Execution
// D14 1 Step 3 LP clear Enable
// D13 1 Step 3 RP clear Enable
// D12 1 Step 3 DCC output : Enable
// D11 1 Step 3 search direction : -direction
// D10 1 Step 3 execution/non-execution : Execution
// D9 0 Step 2 LP clear Disable
// D8 0 Step 2 RP clear Disable
// D7 0 Step 2 DCC output : Disable
// D6 0 Step 2 detection signal : STOP1
// D5 1 Step 2 search direction : -direction
// D4 1 Step 2 execution/non-execution : Execution
// D3,2 0,1 Step 1 detection signal : STOP1
// D1 1 Step 1 search direction : -direction
// D0 1 Step 1 execution/non-execution : Execution
WR0 ← 0023h Write // Writes a command

// Automatic home search mode setting 2
WR6 ← 0020h Write // D15 0
// D14 0
// D13 0
// D12 0
// D11 0
// D10~8 0 Timer value
// D7 0 Timer between steps Disable
// D6~4 010 DCC pulse width 100μsec
// D3 0 DCC pulse logic Hi pulse
// D2 0 At the termination of home search, LP clear Disable
// D1 0 At the termination of home search, RR clear Disable
// D0 0 Step 2 & 3 Disable
WR0 ← 0024h Write // Writes a command

// High-speed home search and low-speed home search setting
WR6 ← 7318h Write // Acceleration/deceleration : 95,000 PPS/SEC
WR7 ← 0001h Write
WR0 ← 0002h Write

WR6 ← 03E8h Write // Initial speed: 1000 PPS
WR7 ← 0000h Write
WR0 ← 0004h Write

WR6 ← 4E20h Write // Speed of step 1 and 4: 20000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 01F4h Write // Speed of step 2, 3: 500 PPS
WR7 ← 0000h Write
WR0 ← 0014h Write

// Offset pulse setting
WR6 ← 0DACH Write // Offset driving pulse count : 3500
WR7 ← 0000h Write
WR0 ← 0006h Write

// Starts execution of automatic home search
WR0 ← 005Ah Write

```

2.6 Synchronous Action

Synchronous action of this IC performs various actions between the IC and an external device during the driving, such as output an external signal at a specified position or save the current position to a specified register by the external signal. For instance, the following actions can be performed.

Example 1 Outputs a signal to the external when passing through a specified position during the driving.

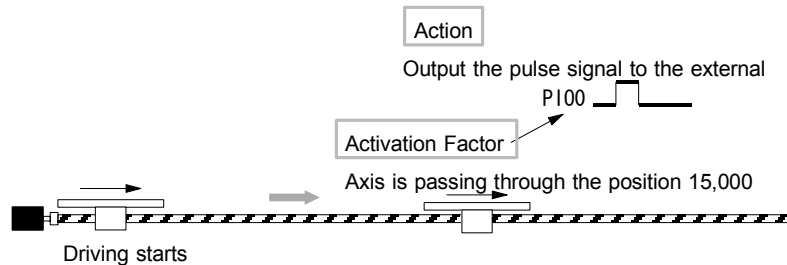


Fig. 2.6-1 Example 1 of Synchronous Action

Example 2 Saves the current position to a specified register when an external signal is input during the driving.

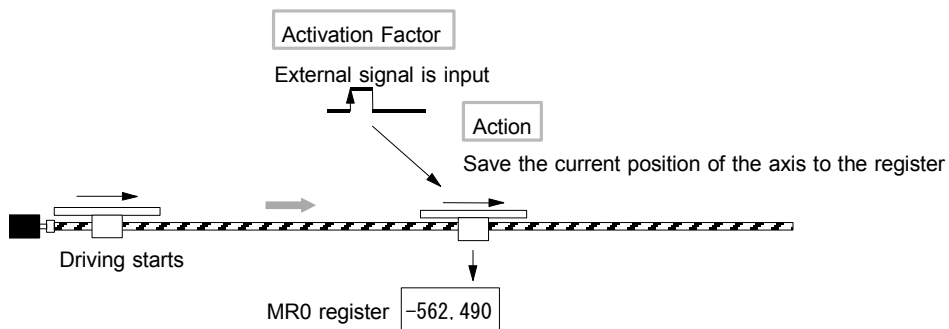


Fig. 2.6-2 Example 2 of Synchronous Action

Example 3 Outputs N split pulses from a specified position to the external during the driving.

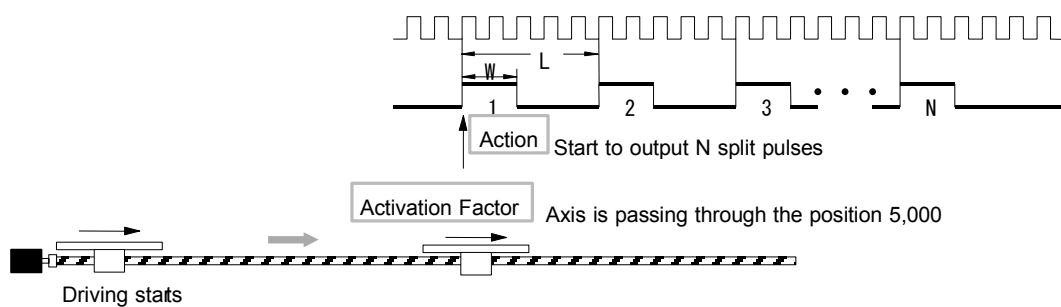


Fig. 2.6-3 Example 3 of Synchronous Action

Example 4 Measures the time to pass through from the position A to the position B during the driving.

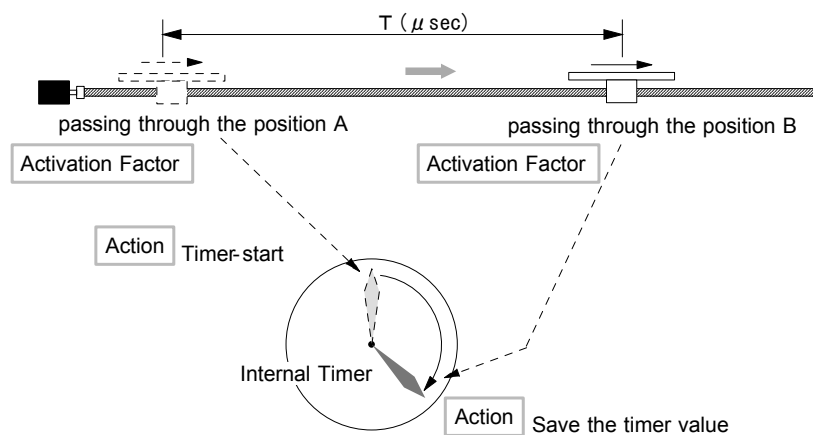


Fig. 2.6-4 Example 4 of Synchronous Action

Normally, such synchronous actions can be performed by coding a program on the CPU side. However, this function is useful when no delay caused by CPU interrupt handling or program execution time is allowed. The synchronous action of this IC is a function that executes a specified action immediately when a specified activation factor is generated. This linked action is performed without CPU intervention, achieving high-precision synchronous control.

One synchronous action set means that performs a specified action when a specified activation factor generates. MCX501 has independent 4 synchronous action sets.

MCX501 can perform 4 synchronous action sets independently, in addition can perform them together.

Each synchronous action set SYNC0~3 has 15 types of activation factors, the user selects one and configures it by the code. And about actions that are activated, 24 types of actions are provided.

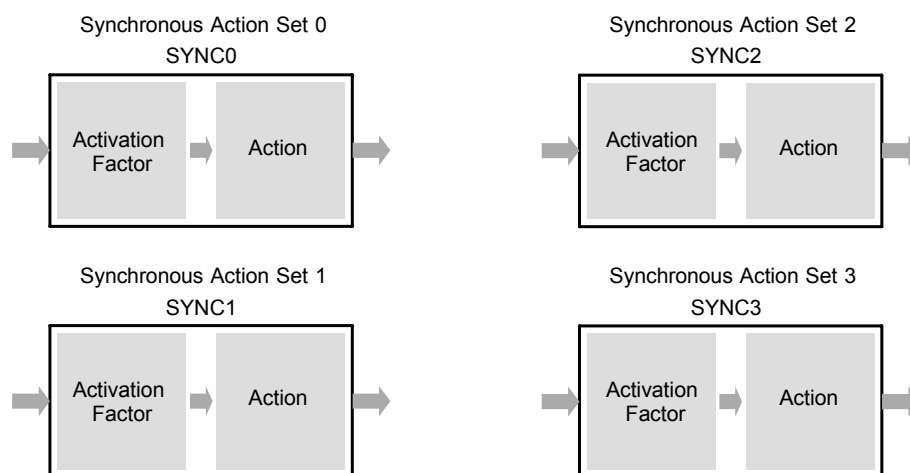


Fig. 2.6-5 Synchronous Action Set

2.6.1 Activation Factor

16 activation factors are provided for synchronous actions as shown in the table below.

Table 2.6-1 Activation Factors

Code (Hex)	Synchronous action set 0 SYNC0	Synchronous action set 1 SYNC1	Synchronous action set 2 SYNC2	Synchronous action set 3 SYNC3	Description
1	MR0 object changed to True	MR1 object changed to True	MR2 object changed to True	MR3 object changed to True	1
2	The internal timer is up				2
3	Start of driving				3
4	Start of driving at constant speed area in acceleration / deceleration driving				3
5	Termination of driving at constant speed area in acceleration / deceleration driving				3
6	Termination of driving				3
7	Start of split pulse				4
8	Termination of split pulse				4
9	Output of split pulse				4
A	PIO0 input signal ↑	PIO1 input signal ↑	PIO2 input signal ↑	PIO3 input signal ↑	5
B	PIO0 input signal ↓	PIO1 input signal ↓	PIO2 input signal ↓	PIO3 input signal ↓	6
C	PIO4 input Low and PIO0 input ↑	PIO5 input Low and PIO1 input ↑	PIO6 input Low and PIO2 input ↑	PIO7 input Low and PIO3 input ↑	7
D	PIO4 input Hi and PIO0 input ↑	PIO5 input Hi and PIO1 input ↑	PIO6 input Hi and PIO2 input ↑	PIO7 input Hi and PIO3 input ↑	8
E	PIO4 input Low and PIO0 input ↓	PIO5 input Low and PIO1 input ↓	PIO6 input Low and PIO2 input ↓	PIO7 input Low and PIO3 input ↓	9
F	PIO4 input Hi and PIO0 input ↓	PIO5 input Hi and PIO1 input ↓	PIO6 input Hi and PIO2 input ↓	PIO7 input Hi and PIO3 input ↓	10
0	NOP				11

Description 1: MRn object changed to True

It is activated when the comparative object of a multi-purpose register (MRn register) meets the comparison condition. As shown in the table, the MRn register corresponding to 4 synchronous action sets is fixed. The comparative object and comparison condition can be set by multi-purpose register mode setting command (20h). For instance, when the comparative object of MR0 register is set to the logical position counter (LP) and comparison condition is set to “comparative object $\geq$ MRn”, if the value of the logical position counter is equal to or larger than MR0 value, it will be activated. If comparison condition is already True when the synchronous action is enabled, the synchronous action is not activated at that time. After it returns to False, and then if it again changes to True, the synchronous action will be activated.

Description 2: The internal timer is up

It is activated when the internal timer is up. The timer value can be set by timer value setting command (16h). The timer can be started by timer-start command (73h) or the other synchronous action sets.

Description 3: Change of driving state

As shown below, it is activated when the change of a driving state generates during the driving.

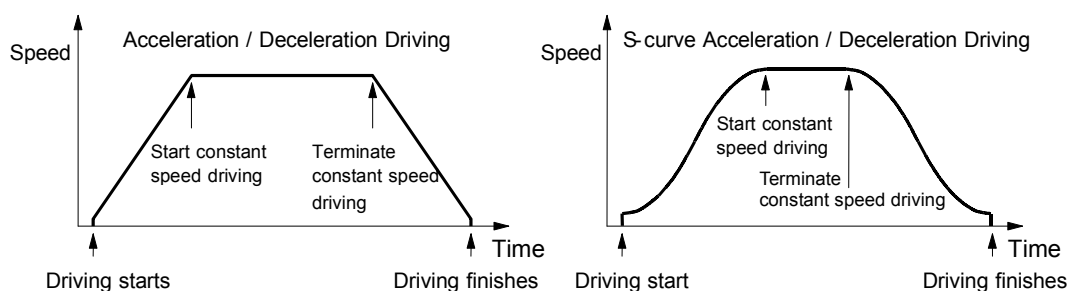


Fig. 2.6-6 Activation Factor regarding Driving State

[Note]

- The constant speed area (the area that driving is performed at a constant speed) may be slightly generated at the termination of driving in acceleration / deceleration driving.

Description 4: Split pulse

About “Start of split pulse”, a synchronous action is activated when split pulse is started by start of split pulse command (75h) or the other synchronous action sets.

About “Termination of split pulse”, a synchronous action is activated when output of the last split pulse is finished.

About “Output of split pulse”, a synchronous action is activated when split pulse is output (when rising or falling to the valid level). If a synchronous action is set to repeat, it is activated every split pulse.

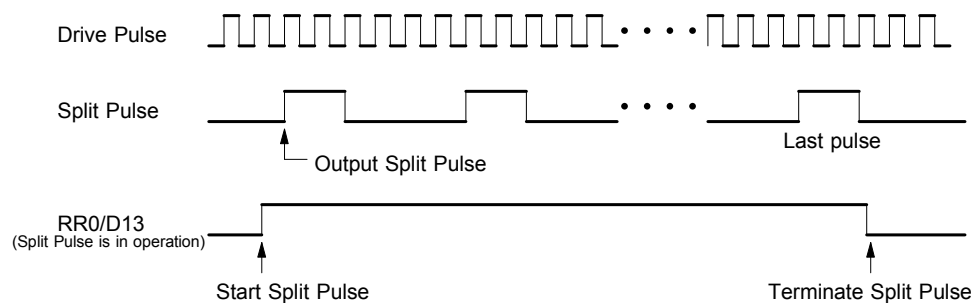


Fig. 2.6-7 Activation Factor of Split Pulse

Description 5: The change of when general purpose input signal is rising

About “PIOn input signal ↑”, it is activated when PIOn (n=0~3) input signal is rising from Low level to Hi level.

As shown in the table, the PIOn signal corresponding to 4 synchronous action sets is fixed.

If the input signal is already Hi level when the synchronous action is enabled, the synchronous action is not activated at that time. After it falls to Low level, and then if it again rises to Hi level, the synchronous action will be activated.

Description 6: The change of when general purpose input signal is falling

About “PIOn input signal ↓”, it is activated when PIOn (n=0~3) input signal is falling from Hi level to Low level.

As shown in the table, the PIOn signal corresponding to 4 synchronous action sets is fixed.

If the input signal is already Low level when the synchronous action is enabled, the synchronous action is not activated at that time. After it rises to Hi level, and then if it again falls to Low level, the synchronous action will be activated.

Description 7: General purpose input signal Low and the change of when rising

About “PIOm input Low and PIOn input ↑”, it is activated when PIOm (m=4~7) input signal is Low level and PIOn (n=0~3) input signal is rising from Low level to Hi level.

As shown in the table, the PIOn, PIOm signals corresponding to 4 synchronous action sets are fixed.

If PIOm input signal is already Low level and PIOn input signal is Hi level when the synchronous action is enabled, the behavior is the same as the description 5.

Description 8: General purpose input signal Hi and the change of when rising

About “PIOm input Hi and PIOn input ↑”, it is activated when PIOm (m=4~7) input signal is Hi level and PIOn (n=0~3) input signal is rising from Low level to Hi level.

As shown in the table, the PIOn, PIOm signals corresponding to 4 synchronous action sets are fixed.

If PIOm input signal is already Hi level and PIOn input signal is Hi level when the synchronous action is enabled, the behavior is the same as the description 5.

Description 9: General purpose input signal Low and the change of when falling

About “PIOm input Low and PIOn input ↓”, it is activated when PIOm (m=4~7) input signal is Low level and PIOn (n=0~3) input signal is falling from Hi level to Low level.

As shown in the table, the PIOn, PIOm signals corresponding to 4 synchronous action sets are fixed.

If PIOm input signal is already Low level and PIOn input signal is Low level when the synchronous action is enabled, the behavior is the same as the description 6.

Description 10: General purpose input signal Hi and the change of when falling

About “PIOm input Hi and PION input ↓”, it is activated when PION (m=4~7) input signal is Hi level and PION (n=0~3) input signal is falling from Hi level to Low level.

As shown in the table, the PION, PION signals corresponding to 4 synchronous action sets are fixed.

If PION input signal is already Hi level and PION input signal is Low level when the synchronous action is enabled, the behavior is the same as the description 6.

Description 11: NOP

It uses when the user does not set the condition of activation factor.

For instance, when the other SYNC activation is used in mode setting, the activation factor of a synchronous action set to be activated should be set to NOP.

2.6.2 Action

Activated actions are shown in the table below. Actions of code 01~09h, 0Fh, 10h are different depending on the synchronous action set 0 to 4.

Table 2.6-2 Actions

Code (Hex)	Synchronous action set 0 SYNC0	Synchronous action set 1 SYNC1	Synchronous action set 2 SYNC2	Synchronous action set 3 SYNC3	Description
01	MR0 → DV	MR1 → DV	MR2 → DV	MR3 → DV	1
02	MR0 → TP	MR1 → TP	MR2 → TP	MR3 → TP	1
03	MR0 → SP1	MR1 → SP1	MR2 → SP1	MR3 → SP1	1
04	MR0 → LP	MR1 → RP	MR2 → SV	MR3 → AC	1
05	LP → MR0	LP → MR1	LP → MR2	LP → MR3	2
06	RP → MR0	RP → MR1	RP → MR2	RP → MR3	2
07	CT → MR0	CT → MR1	CT → MR2	CT → MR3	2
08	CV → MR0	CA → MR1	—	—	2
09	PIO0 signal pulse output	PIO1 signal pulse output	PIO2 signal pulse output	PIO3 signal pulse output	3
0A	Start of relative position driving				
0B	Start of counter relative position driving				
0C	Start of absolute position driving				
0D	Start of +direction continuous pulse driving				
0E	Start of —direction continuous pulse driving				
0F	Start of relative position driving using MR0 value	Start of relative position driving using MR1 value	Start of relative position driving using MR2 value	Start of relative position driving using MR3 value	4
10	Start of absolute position driving using MR0 value	Start of absolute position driving using MR1 value	Start of absolute position driving using MR2 value	Start of absolute position driving using MR3 value	4
11	Decelerating stop				
12	Instant stop				
13	Drive speed increase				5
14	Drive speed decrease				5
15	Timer-start				
16	Timer-stop				
17	Start of split pulse				6
18	Termination of split pulse				6
00	NOP				7

Description 1: Load parameter value

It loads the value of a multi-purpose register MRn (n=0~3) into each parameter.

Table 2.6-3 Load parameter value

(n=0~3)	
Notation	Description
MRn → DV	Loads the value of MRn register into drive speed (DV).
MRn → TP	Loads the value of MRn register into drive pulse number (TP).
MRn → SP1	Loads the value of MRn register into split pulse data 1 (split length and pulse width).
MR0 → LP	Loads the value of MR0 register into logical position counter (LP).
MR1 → RP	Loads the value of MR1 register into real position counter (RP).
MR2 → SV	Loads the value of MR2 register into initial speed (SV).
MR3 → AC	Loads the value of MR3 register into acceleration (AC).

According to the number of synchronous action set, the MRn register that is used is fixed.

About action code 04h, the parameter that the value of MRn register is loaded changes according to the number of synchronous action set.

Description 2: Save parameter value

It saves each parameter value into a multi-purpose register MRn (n=0~3).

Table 2.6-4 Save parameter value

(n=0~3)	
Notation	Description
LP → MRn	Saves the value of logical position counter (LP) into MRn register.
RP → MRn	Saves the value of real position counter (RP) into MRn register.
CT → MRn	Saves the current timer value into MRn register.
CV → MR0	Saves the current drive speed into MR0 register.
CA → MR1	Saves the current acceleration / deceleration value into MR1 register.

According to the number of synchronous action set, the MRn register that is used is fixed.

About action code 08h, the synchronous action set 1 and 2 can only be enabled, and the parameter for saving the value into MRn register is different.

Description 3: Synchronous pulse signal output

The pulse signal is output from PION (n=0~3) signal.

The PION signal corresponding to 4 synchronous action sets is fixed.

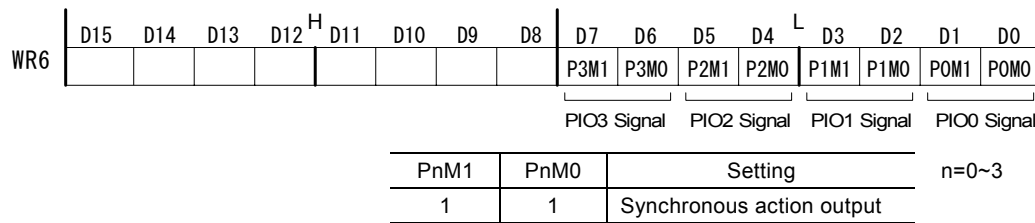
To perform this action, the following items must be set.

- ① PION signal synchronous pulse output setting
- ② Logical level of output pulse signal and pulse width settings

To output the pulse signal for a synchronous action to the external, general purpose input/output signals must be set for the synchronous pulse output by mode setting. And this signal must be set the logical level of whether Hi or Low pulses are output and pulse width. These settings can be set by PIO signal setting 1 command (21h) or PIO signal setting 2•Other settings (22h).

① PION (n=0~3) signal synchronous pulse output setting

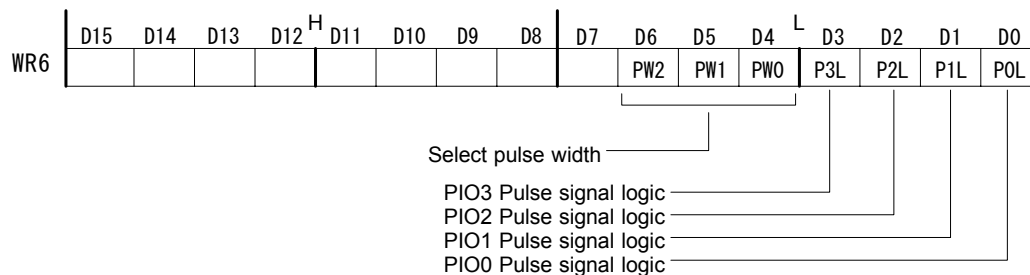
To set PION signal for the synchronous pulse output by mode setting, use PIO signal setting 1 command (21h) and set as shown below.



2 bits of WR6 register according to the PION signal that is used must be set to 1, 1 for the synchronous pulse output. For instance, when using PIO2 signal, set D5, D4 bits (P2M1, P2M0) of WR6 register to 1, 1 and then write PIO signal setting 1 command (21h) into WR0 register.

② Logical level of output pulse signal and pulse width settings

To set the logical level of output pulse signal and pulse width, use PIO signal setting 2•Other settings (22h) and set as shown below.



PnL (n=0~3)			Pulse signal logic
0			Outputs positive logic pulse
1			Outputs negative logic pulse

PW2	PW1	PW0	Pulse width (CLK=16MHz)
0	0	0	125nsec
0	0	1	312nsec
0	1	0	1μsec
0	1	1	4μsec
1	0	0	16μsec
1	0	1	64μsec
1	1	0	256μsec
1	1	1	1msec

Specify the logical level of PIO signal that is used to D0 to D3 bits (P0L~P3L) of WR6 register. 0 outputs the positive logic pulse and 1 outputs the negative logic pulse. The bit according to the unused signal should be set to either 0 or 1. And the pulse width shown above must be set to D4 to D6 bits (PW0~PW3) of WR6 register. The settings of WR6 register will be determined by writing PIO signal setting 2•Other settings (22h) into WR0 register.

[Note]

- The setting of pulse width is common in PIO0 ~ PIO3 all signals. It cannot be set to each signal individually.
- If the synchronous pulse output is activated continuously, when the user tries to activate the next during the synchronous pulse output, the synchronous pulse does not become inactive and it will output a specified pulse width again from when the next is activated.

Description 4: Start of relative / absolute position driving using MRn value

At the start of driving, the value of MRn register is set to drive pulse number (TP) and relative or absolute position driving is started.

Since the value of MRn register is written in drive pulse number (TP), the setting of drive pulse number (TP) will be changed by execution of this action. The changed value of drive pulse number (TP) can be checked by drive pulse number / finish point setting value reading command (46h).

Description 5: Drive speed increase / decrease

It increases/decreases the current drive speed during the driving. The increase / decrease value must be set by speed increasing / decreasing value setting command (15h) in advance.

This action is invalid during the acceleration / deceleration of S-curve driving.

Description 6: Start / termination of split pulse

“Start of split pulse” starts the split pulse with pre-set settings. The starting drive pulse of split pulse is determined by the timing of an activation factor generating. “Termination of split pulse” stops the split pulse in operation. The stop timing of split pulse is determined by the timing of an activation factor occurrence. For more details, see Chapter 2.7.

Description 7: NOP

It uses when no action is needed even though the activation factor becomes active.

This is useful for when the user wants to generate an interrupt only by an activation factor.

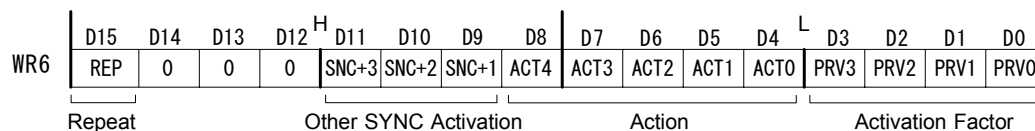
2.6.3 Synchronous Action Settings

There are SYNCn settings, Enable setting and Disable setting for synchronous action settings and by configuring these settings, a synchronous action is performed.

■ SYNCn Setting

It sets 4 synchronous action sets by synchronous action SYNCn setting command (26h, 27h, 28h, 29h), which sets the activation factor, actions, the activation of other synchronous action sets, the setting for whether the synchronous action is performed once or repeatedly.

Write the settings into WR6 register and then write synchronous action setting command.



① Activation factor setting

Specify the activation factor by 4 bits, D3~0 (PRV3~PRV0).

For instance, to set “Start of driving” as the activation factor, specify the code 3h, that is D3~0 is 0011.

For more details of the activation factor, see Chapter 2.6.1.

② Action setting

Specify the action by 5 bits, D8~4 (ACT4~ACT0).

For instance, to set “Start of split pulse” as the action, specify the code 17h, that is D8~4 is 10111.

For more details of the action, see Chapter 2.6.2.

③ Activation of other synchronous action sets

This bit is used to activate simultaneously with the action of the other synchronous action set when the activation factor is activated by the synchronous action set.

Specify by D11~9 bits (SNC+3~SNC+1).

To activate the action of the other synchronous action set, specify 1 and not to activate, specify 0.

The specified bit and the activation of other synchronous action sets are shown in the table below.

Table 2.6-5 Activation of Other Synchronous Action Sets

Self- synchronous action set	D11(SNC+3)	D10(SNC+2)	D9(SNC+1)
SYNC0	SYNC3 activation	SYNC2 activation	SYNC1 activation
SYNC1	SYNC0 activation	SYNC3 activation	SYNC2 activation
SYNC2	SYNC1 activation	SYNC0 activation	SYNC3 activation
SYNC3	SYNC2 activation	SYNC1 activation	SYNC0 activation

This function allows to perform more complex synchronous actions because it can activate multi-actions simultaneously to one activation factor.

For example, suppose the self-synchronous action set is SYNC0, and if the user wants to activate the actions of SYNC1, 2 when the activation factor of SYNC0 is activated, set D9 and D10 bits to 1 based on the table above. By these settings, when the activation factor of SYNC0 is activated, the actions of SYNC1, 2 will be activated with the action of SYNC0. At this time, the activation factor of SYNC1, 2 must be set to NOP and only set the action. In addition, they must be enabled by synchronous action enable setting command.

④ Synchronous action set repeat setting

The user can specify whether the synchronous action set is disabled or not after that is invoked once.

To enable the repeat setting, set D15 bit (REP) to 1 and to enable only once, set it to 0.

When the repeat setting is enabled, the synchronous action is invoked every activation of the activation factor. When it is enabled only once, the synchronous action is invoked at the first activation of the activation factor.

[Note]

- When the repeat setting is enabled, if the activation factor sets “Termination of driving” and the action sets “Start of relative position driving”, the operation from the termination to the start of driving loops infinitely. This can be stopped by synchronous action disable setting command (cannot be stopped by termination command)

■ Enable setting

Each synchronous action set can be enabled by synchronous action enable setting command (81h~8Fh).

When the synchronous action set is enabled, the action is invoked by when the activation factor is activated.

4 synchronous action sets have each corresponding command code. Synchronous action set SYNC0 is 81h, SYNC1 is 82h, SYNC2 is 84h and SYNC3 is 88h. These commands can be enabled in combination simultaneously. For instance, if 83h is executed, SYNC0, 1 become enable. For more details of a combination of command codes, see table 2.6-6.

When REP=0 is set in SYNCn setting, once the synchronous action is executed, the synchronous action becomes disable and even if the activation factor is activated again, the synchronous action will not be executed. When REP=1 is set, the synchronous action set keeps enable after the synchronous action is executed.

To enable the synchronous action set that is disabled by execution of the synchronous action, synchronous action enable setting command must be issued again.

When ERRDE=1 is set in PIO signal setting 2•Other settings command (22h), all the synchronous action sets change to disable if an error occurs (when D1 of RR0 (main status) register becomes 1). In this case, unless the error status is cleared, the synchronous action cannot be enabled by issuing synchronous action enable setting command. To clear the error status, issue error/finishing status clear command (79h).

Enable/disable of 4 synchronous action sets can be checked by D11~D8 bits (SYNC3~SYNC0) of RR0 (main status) register.

■ Disable setting

Each synchronous action set can be disabled by synchronous action disable setting command (91h~9Fh).

When the synchronous action set is disabled, the action is not invoked by when the activation factor is activated.

4 synchronous action sets are all disabled at reset.

4 synchronous action sets have each corresponding command code. Synchronous action set SYNC0 is 91h, SYNC1 is 92h, SYNC2 is 94h and SYNC3 is 98h. These commands can be disabled in combination simultaneously as well as synchronous action enable setting command. For more details of a combination of command codes, see table 2.6-6.

There are 3 occasions to change the state of a synchronous action to disable, “when synchronous action disable setting command is issued”, “when an error occurs by PIO signal setting 2•Other settings command (22h) when synchronous action disable setting (D7:ERRDE) is set to enable”, and “after the synchronous action is activated when it is set once (disable the repeat setting)”.

Enable/disable of 4 synchronous action sets can be checked by D11~D8 bits (SYNC3~SYNC0) of RR0 (main status) register.

Table 2.6-6 Enable/Disable and Command Code Corresponding to Synchronous Action Set

Command code (Hex)			Synchronous action set			
Enable setting	Disable setting	Activation	Synchronous action set 3 SYNC3	Synchronous action set 2 SYNC2	Synchronous action set 1 SYNC1	Synchronous action set 0 SYNC0
81	91	A1	—	—	—	○
82	92	A2	—	—	○	—
83	93	A3	—	—	○	○
84	94	A4	—	○	—	—
85	95	A5	—	○	—	○
86	96	A6	—	○	○	—
87	97	A7	—	○	○	○
88	98	A8	○	—	—	—
89	99	A9	○	—	—	○
8A	9A	AA	○	—	○	—
8B	9B	AB	○	—	○	○
8C	9C	AC	○	○	—	—
8D	9D	AD	○	○	—	○
8E	9E	AE	○	○	○	—
8F	9F	AF	○	○	○	○

○ : Enabled when enable setting command is executed and disabled when disable setting command is executed and activated when activation command is executed.

— : The state does not change when enable/disable setting command is executed. And not activated when activation command is executed.

2.6.4 Synchronous Action Execution

■ Execution steps of synchronous action

Synchronous action is performed as follows.

- ① Set the activation factor and action by synchronous action SYNCn setting command (26h~29h).
- ② Enable the synchronous action set by synchronous action enable setting command (81h~8Fh).
- ③ The synchronous action is activated when the activation factor that is set generates.

■ Activation by synchronous action activation command

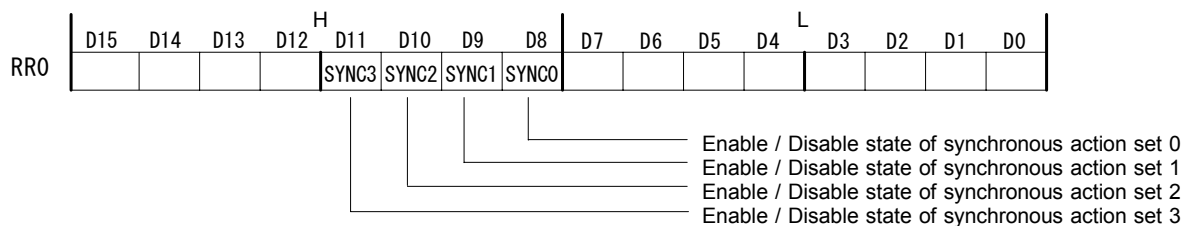
The synchronous action can also be activated by a command, which is the synchronous action activation command (A1h~Ah). Multiple synchronous action sets can be activated simultaneously by a command code. For the command code and corresponding synchronous action SYNC3~0, see table 2.6-6.

To activate a synchronous action by a synchronous action activation command, the user must enable a specified synchronous action set by a synchronous action enable setting command.

■ Main status register

The state of a synchronous action set can be checked by D11~D8 bits (SYNC3~SYNC0) of RR0 (main status) register.

1 indicates enable of the synchronous action set, 0 indicates disable of the synchronous action set.



2.6.5 Interrupt by Synchronous Action

The user can generate an interrupt when a synchronous action is activated.

It sets D15~D12 bits (SYNC3~SYNC0) of WR1 register.

When these bits are set to 1, an interrupt generates when the activation factor of the synchronous action set corresponding to the bit is activated.

For more details of the interrupt, see Chapter 2.10.

2.6.6 Examples of Synchronous Action

- Example 1 When passing through the position 15,000 during the driving, output synchronous pulses to PIO0.

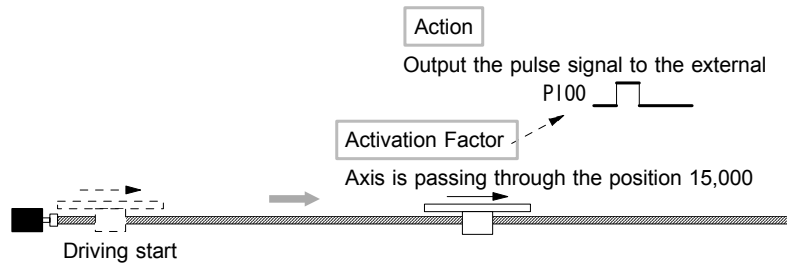


Fig. 2.6-8 Example 1: Synchronous Action

【Program Example】

```
// Drive setting (constant speed driving at 1000 PPS)
WR6 ← 1200h Write // Initial speed 8M PPS (maximum in specification)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 03E8h Write // Drive speed 1000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 0000h Write // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

// MRO setting
WR6 ← 3A98h Write // MRO 15000
WR7 ← 0000h Write
WR0 ← 0010h Write

// Multi-purpose register mode setting
WR6 ← 0000h Write // D1,D0 00 MOT1,0: MRO Comparative object Logical position counter
// D3,D2 00 MOC1,0: MRO Comparison condition ≥
WR0 ← 0020h Write

// PIO signal setting 1
WR6 ← 0003h Write // D1,D0 11 POM1,0: PIO0 signal Synchronous action output
WR0 ← 0021h Write

// PIO signal setting 2
WR6 ← 0070h Write // D0 0 POL: PIO0 Logical level of pulse signal Positive logic
// D6~D4 111 PW2~0: Pulse width 1msec (at CLK = 16MHz)
WR0 ← 0022h Write

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0091h Write // D3~D0 0001 PREV3~0: Activation factor MRO object changed to True
// D8~D4 01001 ACT4~0: Action synchronous pulse output
WR0 ← 0026h Write

// SYNC0 Enable
WR0 ← 0081h Write

// Start driving
WR0 ← 0052h Write // Starts +direction continuous pulse driving
```

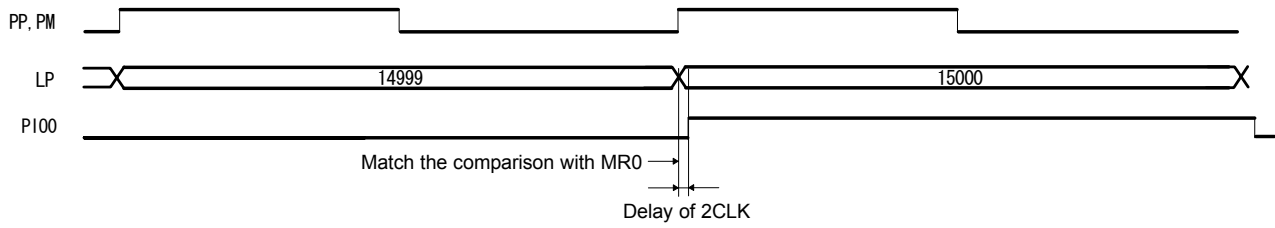


Fig. 2.6-9 Timing of Example 1: Synchronous Action

From Chapter 2.6.7, a delay from the generating of an activation factor is 1CLK and a delay up to the action is 1CLK, so the delay time of this synchronous action is 2CLK (125nsec).

■ Example 2 When an external signal is input during the driving, save the position data.

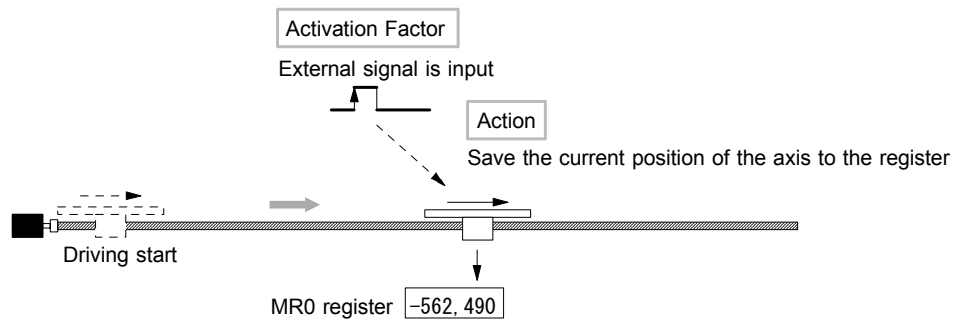


Fig. 2.6-10 Example 2: Synchronous Action

【Program Example】

```
// Drive setting (constant speed driving at 1000 PPS)
WR6 ← 1200h Write // Initial speed 8M PPS (maximum in specification)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 03E8h Write // Drive speed 1000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 0000h Write // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

// PIO signal setting 1
WR6 ← 0000h Write // D1,D0 00 POM1,0 : PIO0 signal General purpose・Synchronous input
WR0 ← 0021h Write

// Interrupt setting
WR1 ← 1000h Write // D12 1 SYNC0 : When synchronous action SYNC0 is activated

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 005Ah Write // D3~D0 1010 PREV3~0 : Activation factor PIOn input ↑
// D8~D4 00101 ACT4~0 : Action Save LP → MRn
WR0 ← 0026h Write

// SYNC0 Enable
WR0 ← 0081h Write

// Start driving
WR0 ← 0052h Write // Starts +direction continuous pulse driving

↓

SYNC0 is activated and interrupt occurs

↓

// Read logical position counter value saved in MR0
WR0 ← 0034h Write
RR6 → Read
RR7 → Read
```

From Chapter 2.6.7, a delay from the occurrence of an activation factor is from 0 (minimum) to 1CLK (maximum) and a delay up to the action is 1CLK, so the delay time of this synchronous action is from a minimum of 1CLK (62.5nsec) up to 2CLK (125nsec).

- Example 3 Calculates the time passing through from position A (10000) to position B (55000) during the driving.

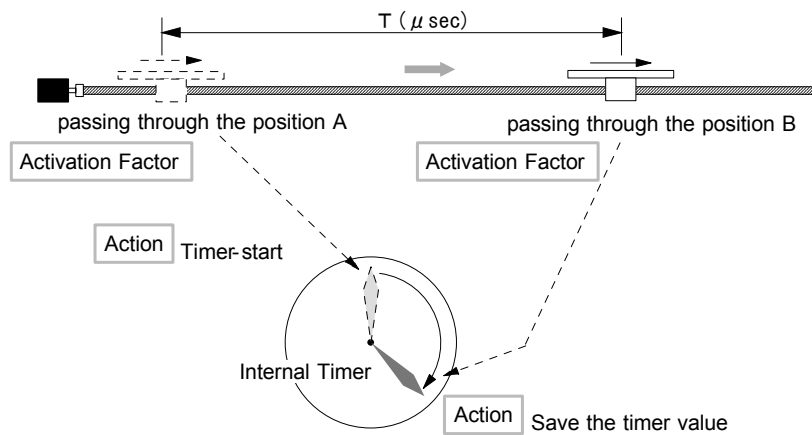


Fig. 2.6-11 Example 3: Synchronous Action

【Program Example】

```
// Drive setting (constant speed driving at 10K PPS)
WR6 ← 1200h Write // Initial speed 8M PPS (maximum in specification)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 2710h Write // Drive speed 10K PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 0000h Write // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

// Set a specified position to MRn register
// MR0 setting (specified position A: 10000)
WR6 ← 2710h Write // MR0 10000
WR7 ← 0000h Write
WR0 ← 0010h Write

// MR1 setting (specified position B: 55000)
WR6 ← D6D8h Write // MR1 55000
WR7 ← 0000h Write
WR0 ← 0010h Write

// Timer value setting
WR6 ← FFFFh Write // Timer value 2147483647 (maximum)
WR7 ← 7FFFh Write
WR0 ← 0016h Write

// Interrupt setting
WR1 ← 2000h Write // D13 1 SYNC1: When synchronous action SYNC1 is activated

// Multi-purpose register mode setting
WR6 ← 0000h Write // D1, D0 00 MOT1,0: MR0 Comparative object Logical position counter
// D3, D2 00 MOC1,0: MR0 Comparison condition ≥
// D5, D4 00 MIT1,0: MR1 Comparative object Logical position counter
// D7, D6 00 M1C1,0: MR1 Comparison condition ≥
WR0 ← 0020h Write

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0151h Write // D3~D0 0001 PREV3~0 : Activation factor MRn object changed to True
// D8~D4 10101 ACT4~0 : Action Timer-start
WR0 ← 0026h Write

// Synchronous action SYNC1 setting
WR6 ← 0071h Write // D3~D0 0001 PREV3~0 : Activation factor MRn object changed to True
// D8~D4 00111 ACT4~0 : Action Save CT → MRn
WR0 ← 0027h Write

// SYNC0,1 Enable
WR0 ← 0083h Write
```

```
// Start driving
WRO ← 0052h Write      // Starts +direction continuous pulse driving
```



SYNC1 is activated and interrupt occurs



```
// Read timer value saved in MR1
WRO ← 0035h Write
RR6 → Read
RR7 → Read

// Timer-stop
WRO ← 0074h Write
```

2.6.7 Synchronous Action Delay Time

A synchronous action delay is a total of the delay from the generating of an activation factor to an action as shown in the tables below.

■ Delay from the generating of an activation factor

1CLK=62.5nsec (CLK=16MHz)

Table 2.6-7 Delay from the Generating of an Activation Factor

Activation factor		Definition of the start of delay	Delay time (CLK)		
			Min.	Standard	Max.
MRn comparison changed to True	Logical position counter	From ↑ of the driving pulse when the LP value satisfies the comparison condition with MRn value		1	
	Real position counter	From ↑↓ of the ECA/B input signal when the RP value satisfies the comparison condition with MRn value	2		3
	Current drive speed	From when the current drive speed satisfies the comparison condition with MRn value		1	
	Current timer value	From when the current timer value satisfies the comparison condition with MRn value		1	
Timer is up		From when the current timer value reaches a specified value		0	
Start of driving		From ↑ of the WRN signal at writing of a driving command	2		3
Start of driving at constant speed area in acceleration / deceleration driving.		Form ↑ of the CNST signal		0	
Termination of driving at constant speed area in acceleration / deceleration driving.		From ↓ of the CNST signal		0	
Termination of driving		From Low level termination of the last driving pulse		1	
Start of split pulse		Form ↑ of the 1st SPLTP signal (when starting pulse is enabled)		0	
Termination of split pulse		From ↓ of the last SPLTP signal (positive logic)		2	
Output of split pulse		Form ↑ of the SPLTP signal (positive logic)		0	
PION input↑		Form ↑ of the PION signal (when the built-in filter is disabled)	0		1
PION input↓		From ↓ of the PION signal (when the built-in filter is disabled)	0		1
PION input Low and PIO(n+4)↑		Form ↑ of the PION (n+4) signal (when the built-in filter is disabled)	0		1
PION input Hi and PIO(n+4)↑		Form ↑ of the PION (n+4) signal (when the built-in filter is disabled)	0		1
PION input Low and PIO(n+4)↓		From ↓ of the PION (n+4) signal (when the built-in filter is disabled)	0		1
PION input Hi and PIO(n+4)↓		From ↓ of the PION (n+4) signal (when the built-in filter is disabled)	0		1
Activation command		Form ↑ of the WRN signal at writing of a synchronous action activation command	1		2

■ Delay up to an action

1CLK=62.5nsec (CLK=16MHz)

Table 2.6-8 Delay up to an Action

Action	Definition of the end of delay	Delay time (CLK)
Load MRn → DV	Until the MRn value is loaded into DV	1
Load MRn → TP	Until the MRn value is loaded into TP	1
Load MRn → SP1	Until the MRn value is loaded into SP1	1
Load MRn → LP (SYNC0), RP (SYNC1), SV (SYNC2), AC (SYNC3)	Until the MRn value is loaded into LP (SYNC0), RP (SYNC1), SV (SYNC2), AC (SYNC3)	1
Save LP → MRn	Until the LP value is saved to MRn	1
Save RP → MRn	Until the RP value is saved to MRn	1
Save CT → MRn	Until the CT value is saved to MRn	1
Save CV (SYNC0), CA (SYNC1) → MRn	Until the CV (SYNC0), CA (SYNC1) values are saved to MRn	1
Synchronous pulse PION output	Until ↑ of the synchronous pulse PION signal	1
Start of relative position driving	Until ↑ of the 1st driving pulse	3
Start of counter relative position driving	Until ↑ of the 1st driving pulse	3
Start of absolute position driving	Until ↑ of the 1st driving pulse	3
Start of + direction continuous pulse driving	Until ↑ of the 1st driving pulse	3
Start of - direction continuous pulse driving	Until ↑ of the 1st driving pulse	3
Relative position driving by drive pulse number of MRn value	Until ↑ of the 1st driving pulse	4
Absolute position driving to the finish point of MRn value	Until ↑ of the 1st driving pulse	4
Decelerating stop	Until the start of deceleration	(※1)
Instant stop	Until the termination of driving	(※1)
Drive speed increase	Until drive speed increase is started toward the changed speed.	1
Drive speed decrease	Until drive speed decrease is started toward the changed speed.	1
Timer-start	Until the timer-start	1
Timer-stop	Until the timer-stop	1
Start of split pulse	Until ↑ of the SPLTP signal (with starting pulse)	(※2)
Termination of split pulse	Until ↓ of the SPLTP signal	(※3)
Interrupt	Until ↓ of the INTN signal	1

(※1) The time until the one driving pulse being output is finished.

(※2) Since the split pulse is synchronized with the driving pulse, the delay will be 1 driving pulse cycle at the maximum.

(※3) The time until the split pulse being output is finished.

■ Calculation example of delay

For instance, the delay time from the activation factor “↑ of the PION input” to the action “Save LP → MRn” is a total of the “↑ of the PION input” delay time (0 to 1CLK) and “Save LP → MRn” delay time (1CLK), that is from a minimum of 1CLK up to 2CLK. The range is from a minimum of 62.5nsec up to 125nsec when CLK=16MHz.

■ Delay by the activation of the other SYNC

If the other SYNC is activated, the action will be activated with 1CLK delay compared to the action of self-synchronous action set.

2.7 Split Pulse

This is a function that outputs the split pulse which is synchronized with a drive pulse during the driving.

This function is useful for when the user wants to perform the other operation at regular pulse intervals, synchronizing with rotation of a motor and axis driving.

The pulse width of a split pulse, split length (cycle) and split pulse number can be set. And the logical level of pulses and with or without starting pulse can be specified. Split pulses are output from SPLTP (pin number: 64).

While driving, start of split pulse can be performed by a command or a synchronous action. When using a synchronous action, the user can start from a specified value of a position counter or $\uparrow$ of an external signal.

Split pulse example of Split length = 7, Pulse width = 3, Split pulse number = 5 and Positive logic

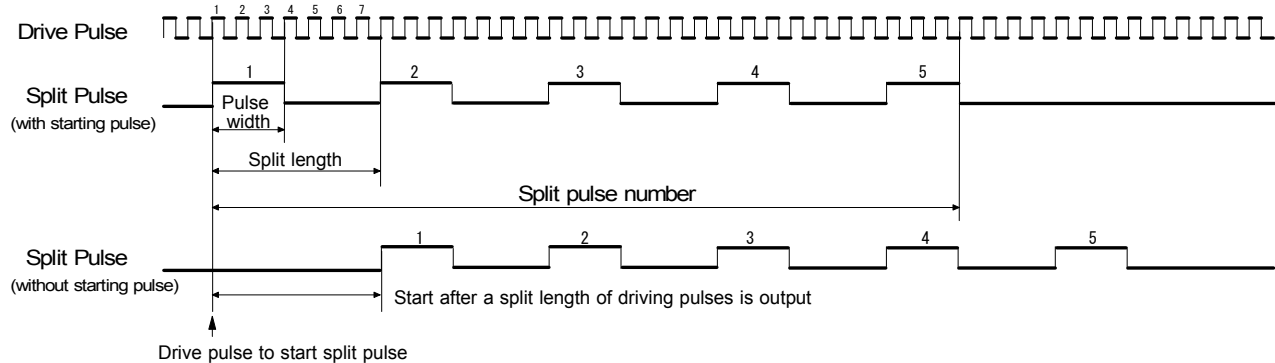


Fig. 2.7-1 Example of Split Pulse

2.7.1 Split Pulse Setting

To perform the split pulse, the following parameters and mode setting must be set.

■ Split length and pulse width setting

A split length and pulse width can be set by split pulse setting 1 command (17h). Set a split length to WR6 register and a pulse width to WR7 register. The unit of split length and pulse width is the number of drive pulses.

Because of the function of split pulse, set to split length > pulse width.

A split length can be set within the range of 2~65535 and a pulse width can be set within the range of 1~65534.

The user can check the settings by split pulse setting 1 reading command (47h).

A split length (cycle) and pulse width can be altered during the split pulse is in operation.

■ Split pulse number setting

The split pulse number can be set by split pulse setting 2 command (18h). Set the split pulse number to WR6 register.

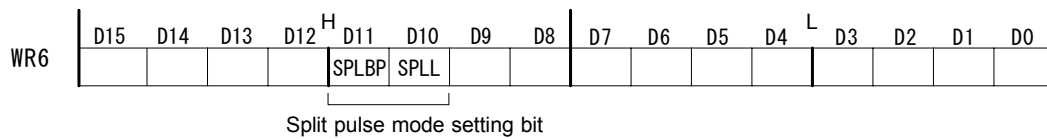
It can be set within the range of 0~65535. If 0 is set, it becomes infinite. After starting, it continues to output split pulses until termination of split pulse command is issued or driving is stopped.

The split pulse number can be altered during the split pulse is in operation.

■ Split pulse mode setting

The operating mode of split pulses can be set by PIO signal setting 2 • Other settings command (22h).

At the start of split pulse, set with or without starting pulse, and the logical level of split pulse output to D10, D11 bits of WR6 register.



Set the split pulse logic to D10 bit (SPLL).

As shown below, when 0 is set, it is positive logic pulse and when 1 is set, it is negative logic pulse.

Positive logic pulse :  Negative logic pulse : 

Fig. 2.7-2 Split Pulse Logic

Set with or without starting pulse to D11 bit (SPLBP).

When 1 is set to D11 bit (SPLBP), it starts with starting pulse and when 0 is set, it starts without starting pulse.

When with starting pulse is specified, after the start of split pulse, split pulses are output from next driving pulse. When without starting pulse is specified, after the start of split pulse, the first split pulse is output after a split length of driving pulses is output.

2.7.2 Start / Termination of Split Pulse

■ Start of split pulse

Split pulse is started by start of split pulse command (75h) or a synchronous action.

When a command is written or the action of a synchronous action is started, next driving pulse is the starting drive pulse of split pulse.

■ Termination of Split Pulse

Output of split pulse is terminated by any one of the following 3 behaviors.

- When output of specified split pulses is finished.
- When requested to stop by termination of split pulse command or the action of a synchronous action.
- When driving stops.

After output of specified split pulses is finished, it will stop when the last split pulse of specified split pulses becomes OFF.

When split pulse is stopped by termination of split pulse command (76h) or a synchronous action, if the split pulse is ON, it will stop after the split length of pulses is output. If it is OFF, it will stop at the timing of termination of split pulse command or execution of a synchronous action.

When output of split pulse is terminated by the stop of driving, regardless of split pulse output state, the split pulse becomes OFF and terminates at the timing of the stop of driving.

■ Main status register

Split pulse in operation can be checked by D13 bit (SPLIT) of RR0 (main status) register.

When D13 bit (SPLIT) is 1, split pulse is in operation and when it is 0, split pulse is stopped.

2.7.3 Split Pulse in Synchronous Action

Split pulse can be operated by a synchronous action.

As the activation factor of a synchronous action, the following 3 types can be specified: “at the start of split pulse”, “at the output of split pulse” and “at the termination of split pulse”.

As the action of a synchronous action, the following 3 types can be specified: “at the start of split pulse”, “at the termination of split pulse” and “load the data of a multi-purpose register to the split pulse data (split length and pulse width)”

For more details of these functions, see Chapter 2.6.

2.7.4 Interrupt by Split Pulse

An interrupt related to split pulse operation can be generated.

Set to D10, D11 bits of WR1 register.

When D10 bit (SPLTP) is 1, an interrupt generates at the $\uparrow$ of a pulse in each split pulse (when the split pulse logic is positive).

When D11bit (SPLTE) is 1, an interrupt generates when operation of split pulse is finished.

For more details of the interrupt function, see Chapter 2.10.

2.7.5 Notes on Split Pulse

- (1) When with starting pulse is enabled, only the first pulse is different in the timing of output. For more details, see Chapter 9.5.
- (2) While operating split pulse, if it stops by such as a command before output of specified split pulses is finished and then restarts split pulse again, it starts to count the split pulse number from 1.

2.7.6 Examples of Split Pulse

■ Example 1 Split pulse starts from the start of driving.

After issuing start of split pulse command, driving starts and split pulses are output with driving.

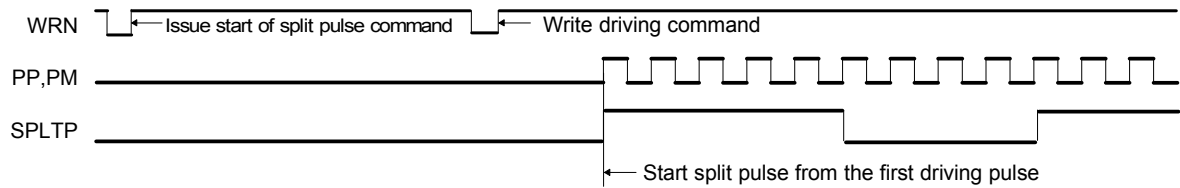


Fig. 2.7-3 Timing of Split Pulse Output by Start of Driving

【Program Example】

```
// Drive setting (constant speed driving at 1000 PPS)
WR6 ← 1200h Write      // Initial speed 8M PPS (maximum in specification)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 03E8h Write      // Drive speed 1000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 0000h Write      // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

// Split pulse setting
// Split length, pulse width setting
WR6 ← 0009h Write      // Split length 9
WR7 ← 0005h Write      // Pulse width 5
WR0 ← 0017h Write

// Split pulse number setting
WR6 ← 000Ah Write      // Split pulse number 10
WR0 ← 0018h Write

// Split pulse logic, starting pulse setting
WR6 ← 0800h Write      // D10 0 SPLL : Pulse logic Positive
                        // D11 1 SPLBP : With starting pulse
WR0 ← 0022h Write

// Start split (issue start of split pulse command before starting the drive)
WR0 ← 0075h Write

// Start driving
WR0 ← 0052h Write      // Starts +direction continuous pulse driving
```

After starting the drive, the first driving pulse becomes the starting drive pulse of split pulse.

After start of split pulse command is issued, split pulses are not output unless driving starts, but D13 bit (SPLIT) of RR0 (main status) register becomes 1 at the timing of when start of split pulse command is issued.

■ Example 2 Split pulse starts from position 5,000.

After starting the drive, split pulse starts from when the logical position reaches to 5,000. This is performed by the function of a synchronous action.

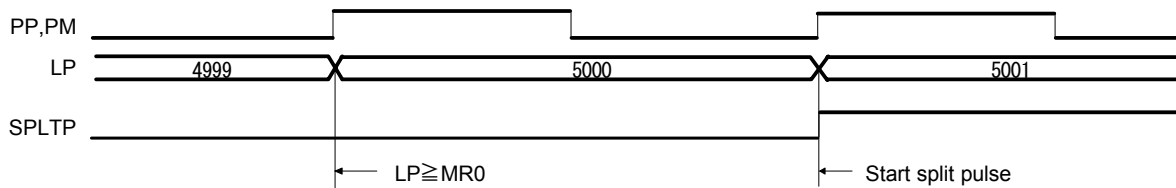


Fig. 2.7-4 Timing of Split Pulse Output by Comparison with MRn

【Program Example】

```
// Drive setting (constant speed driving at 1000 PPS)
WR6 ← 1200h Write      // Initial speed 8M PPS (maximum in specification)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 03E8h Write      // Drive speed 1000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 0000h Write      // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

// Split pulse setting
// Split length, pulse width setting
WR6 ← 0008h Write      // Split length 8
WR7 ← 0005h Write      // Pulse width 5
WR0 ← 0017h Write

// Split pulse number setting
WR6 ← 000Ah Write      // Split pulse number 10
WR0 ← 0018h Write

// Split pulse logic, starting pulse setting
WR6 ← 0800h Write      // D10 0 SPLL : Pulse logic Positive
WR0 ← 0022h Write      // D11 1 SPLBP : With starting pulse

// Multi-purpose register setting
// MRO setting
WR6 ← 1388h Write      // MRO 5000
WR7 ← 0000h Write
WR0 ← 0010h Write

// Multi-purpose register mode setting
WR6 ← 0000h Write      // D1, D0 00 MOT1,0 : MRO Comparative object Logical position counter
WR0 ← 0020h Write      // D3, D2 00 MOC1,0 : MRO Comparison condition ≥

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0171h Write      // D3~D0 0001 PREV3~0 : Activation factor MRn object changed to True
WR0 ← 0026h Write      // D8~D4 10111 ACT4~0 : Action start of split pulse

// SYNC0 Enable
WR0 ← 0081h Write

// Start driving
WR0 ← 0052h Write      // Starts +direction continuous pulse driving
```

If the comparative value is 5,000 and comparison condition is $\geq$, the value of the logical position counter that split pulse is started is 5001 as shown in the figure. That is, next driving pulse is the starting drive pulse when comparison condition changed to True.

■ Example 3 Split pulses are output at constant speed area during S-curve acceleration /deceleration driving.

At constant speed area during S-curve acceleration /deceleration driving, split pulses are output. This is performed by the function of a synchronous action.

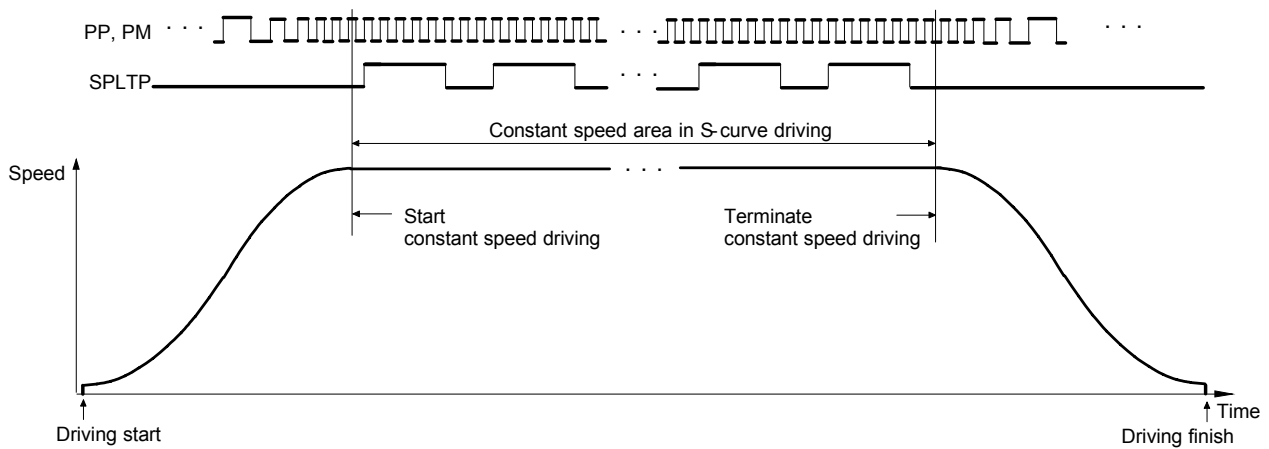


Fig. 2.7-5 Output of Split Pulses at Constant Speed Area in S-curve Driving

【Program Example】

```
// S-curve acceleration /deceleration drive setting
WR6 ← 000Ah Write      // Initial speed 10 PPS
WR7 ← 0000h Write
WR0 ← 0004h Write

WR6 ← 0FA0h Write      // Drive speed 4000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← FFFFh Write      // Acceleration 536870911(maximum)
WR7 ← 1FFFh Write
WR0 ← 0002h Write

WR6 ← A048h Write      // Jerk 893K PPS/SEC2
WR7 ← 000Dh Write
WR0 ← 0000h Write

WR6 ← 9C40h Write      // Drive pulse number 40000
WR7 ← 0000h Write
WR0 ← 0006h Write

WR6 ← 0000h Write      // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

WR3 ← 0004h Write      // D3      1 SACC : S-curve acceleration /deceleration

// Split pulse setting
// Split length, pulse width setting
WR6 ← 0008h Write      // Split length 8
WR7 ← 0005h Write      // Pulse width 5
WR0 ← 0017h Write

// Split pulse number setting
WR6 ← 0000h Write      // Split pulse number Infinite
WR0 ← 0018h Write

// Split pulse logic, starting pulse setting
WR6 ← 0800h Write      // D10      0 SPLL : Pulse logic Positive
                      // D11      1 SPLBP : With starting pulse
WR0 ← 0022h Write

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0174h Write      // D3~D0      0100 PREV3~0 : Activation factor Start constant speed driving
                      // D8~D4      10111 ACT4~0 : Action start of split pulse
                      // D15      0 REP : Repeat must be disabled
WR0 ← 0026h Write
```

```
// Synchronous action SYNC1 setting
WR6 ← 0185h Write      // D3~D0      0101 PREV3~0 : Activation factor   Finish constant speed driving
                        // D8~D4      11000 ACT4~0 : Action      termination of split pulse
                        // D15        0 REP       : Repeat      must be disabled

WR0 ← 0027h Write

// SYNC0.1 Enable
WR0 ← 0083h Write

// Start driving
WR0 ← 0050h Write      // Starts relative position driving
```

■ **Example 4** Starts to output split pulses from position 5,000 and changes split length and pulse width from position 10,000

Split pulse starts from the logical position 5,000 and changes a split length and pulse width from the logical position 10,000, and then outputs the rest of split pulses. This is performed by the function of a synchronous action.

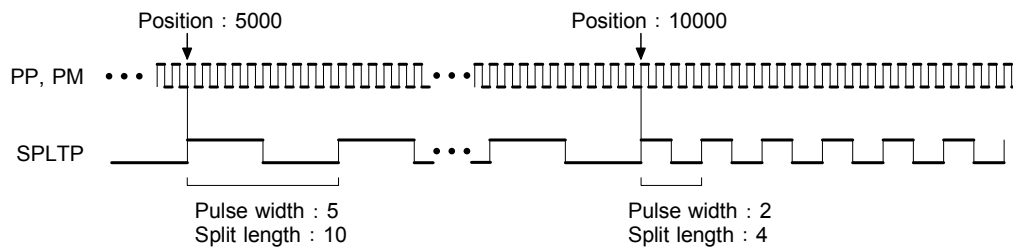


Fig. 2.7-6 Change Split Length and Pulse Width at Specified Position during the Driving

【Program Example】

```
// Drive setting (constant speed driving at 1000 PPS)
WR6 ← 1200h Write      // Initial speed 8M PPS (maximum)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 03E8h Write      // Drive speed 1000 PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 0000h Write      // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

WR6 ← 2EE0h Write      // Drive pulse number 12000
WR7 ← 0000h Write
WR0 ← 0006h Write

// Split pulse setting
// Split length, pulse width setting
WR6 ← 000Ah Write      // Split length 10
WR7 ← 0005h Write      // Pulse width 5
WR0 ← 0017h Write

// Split pulse number setting
WR6 ← 0320h Write      // Split pulse number 800
WR0 ← 0018h Write

// Split pulse logic, starting pulse setting
WR6 ← 0800h Write      // D10 0 SPLL : Pulse logic Positive
WR0 ← 0022h Write      // D11 1 SPLBP : With starting pulse

// Multi-purpose register setting
// MRO setting
WR6 ← 1387h Write      // MRO 4999
WR7 ← 0000h Write
WR0 ← 0010h Write

// MR1 setting
WR6 ← 2710h Write      // MR1 10000
WR7 ← 0000h Write
WR0 ← 0011h Write

// MR2 setting
WR6 ← 0004h Write      // Split length 4
WR7 ← 0002h Write      // Pulse width 2
WR0 ← 0012h Write

// Multi-purpose register mode setting
WR6 ← 0000h Write      // D1, D0 00 MOT1,0 : MRO Comparative object Logical position counter
                        // D3, D2 00 MOC1,0 : MRO Comparison condition ≥
                        // D5, D4 00 M1T1,0 : MR1 Comparative object Logical position counter
                        // D7, D6 00 M1C1,0 : MR1 Comparison condition ≥
WR0 ← 0020h Write
```

```

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0171h Write      // D3~D0      0001 PREV3~0 : Activation factor   MRn object changed to True
                        // D8~D4      10111 ACT4~0 : Action      start of split pulse
WR0 ← 0026h Write

// Synchronous action SYNC1 setting
WR6 ← 0201h Write      // D3~D0      0001 PREV3~0 : Activation factor   MRn object changed to True
                        // D8~D4      00000 ACT4~0 : Action      NOP
                        // D11~D9     001 SNC+3, 2, 1 : Other SYNC Activation   Activate SNC+1
WR0 ← 0027h Write

// Synchronous action SYNC2 setting
WR6 ← 0030h Write      // D3~D0      0001 PREV3~0 : Activation factor   NOP
                        // D8~D4      00011 ACT4~0 : Action      Load MRn → SP1
                        // D11~D9     001 SNC+3, 2, 1 : Other SYNC Activation   Activate SNC+1
WR0 ← 0027h Write

// SYNC2~0 Enable
WR0 ← 0087h Write

// Start driving
WR0 ← 0050h Write      // Starts relative position driving

```

In this case, if split pulse is set to output at the timing of position 4,999, it actually starts to output from position 5,000.

[Note]

- In this case, while operating split pulse, the user must use caution with changing a split length and pulse width by such as a synchronous action. Because split pulses around the change may cause unexpected behavior due to the timing of change.

2.8 General Purpose Input / Output Signal

MCX501 has 8 general purpose input / output pins, PIO7~0.

And under the following conditions, the input signal that has a specific function can be used as a general purpose input signal.

- ① When the function of an input signal is not used, set it to disable, and it can use as a general purpose input signal.
- ② When 8-bit data bus is used, high word D15~D8 which are not used for the data bus, can be used as general purpose input signals.

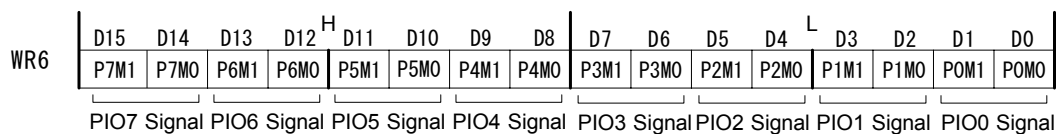
2.8.1 PION Signal

PION signal can be used as input/output signals for various purposes as shown below.

- 1) General purpose input signal
- 2) General purpose output signal
- 3) Input signal as the activation factor of a synchronous action
- 4) Synchronous pulse output signal as the action of a synchronous action
- 5) Output signal to output drive status
- 6) Output signal to output the comparison result of a multi-purpose register
- 7) Input signal for driving by external signals

■ PION signal function setting

The function of PION signals can be set by PIO signal setting 1 command (21h).



Set 2 bits corresponding to each PION signal of WR6 register according to purposes.

The functions corresponding to 2 bits of each PION signal are shown in the table below.

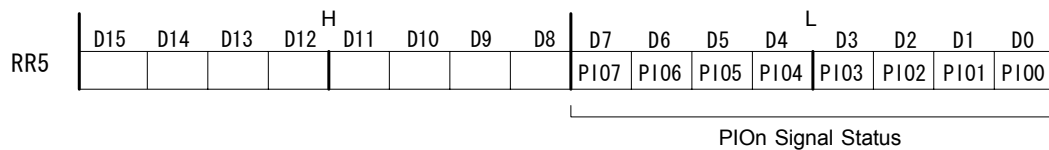
Table 2.8-1 PION Signal Function Setting

(n:0~7)		
PnM1 bit	PnM0 bit	Function
0	0	General purpose input PIO7~0 signals become an input state. In synchronous action, it can be activated by the signals ↑ or ↓. In driving by external signals, relative position driving or continuous pulse driving can be activated by PIO4, 5 signals.
0	1	General purpose output PIO7~0 signals become an output state.
1	0	Drive status output PIO7~0 signals become an output state and output the drive status.
1	1	Synchronous pulse · MRn comparison output PIO7~0 signals become an output state. PIO3~0 output shnchronous pulses and PIO7~4 output MRn comparison value.

■ PION signal reading

The signal levels of PION signals can be read out by D7~D0 bits (PIO7~PIO0) of RR5 register anytime regardless of input/output.

When the signal is Low level, 0 is displayed and when the signal is Hi level, 1 is displayed.



■ General purpose input

As the functions of an input signal, there are 3 kinds of input signals, general purpose input signal, synchronous input signal and input signal for driving by the external signal.

Set 2 bits corresponding to PION signal that is used to 0, 0 and set by PIO signal setting 1 command (21h).

Used as general purpose input signal

The signal levels of PIO7~0 signals are displayed in D7~D0 bits (PIO7~PIO0) of RR5 register. When the signal is Low level, 0 is displayed and when the signal is Hi level, 1 is displayed.

Used as synchronous input signal

Input change of PION signals can be used as the activation factor of a synchronous action.

For more details of the synchronous action, see Chapter 2.6.

Used as input signal for driving by external signals

Relative position driving or continuous pulse driving can be activated by PION signal and but a command.

Perform by using PIO4, PIO5 signals, and driving will be activated by the input state or input change of these signals.

For more details of driving by external signals, see Chapter 2.12.1.

■ General purpose output

Set 2 bits corresponding to PION signal that is used to 0, 1 and set by PIO signal setting 1 command (21h).

Writing into PION signal is performed by writing into WR4 register. The values written in D7~0 bits of WR4 register are output to PIO7~0 signals. When 0 is written in D7~0 bits, it is Low level output and when 1 is written, it is Hi level output.

■ Drive status output

Drive status can be output to PION signal.

Set 2 bits corresponding to PION signal that is used to 1, 0 and set by PIO signal setting 1 command (21h).

Drive status such as driving, accelerating and decelerating is output from PION signal.

For more details of the status output, see Chapter 2.12.7.

■ Synchronous pulse ·MRn comparison output

Set 2 bits corresponding to PION signal that is used to 1, 1 and set by PIO signal setting 1 command (21h).

Used as synchronous pulse output signal

As the action of a synchronous action, synchronous pulses can be output to PIO0~PIO3 signals.

For more details of the synchronous action, see Chapter 2.6.

Used as MRn comparison output signal

The comparison result of MRn register can be output to PION signal.

MR0~MR3 comparison output is output from PIO4~PIO7 signals.

For more details of the MRn register, see Chapter 2.4.

2.8.2 Other Input Signals

As shown in the table below, about input signals other than PION signals, when the functions of those signals are not used, they can be used as a general purpose input signal.

The signal levels of input signals are displayed in RR3 register. When the signal is Low level, 0 is displayed and when the signal is Hi level, 1 is displayed.

Input signals that can be used as a general purpose input signal are shown in the table below.

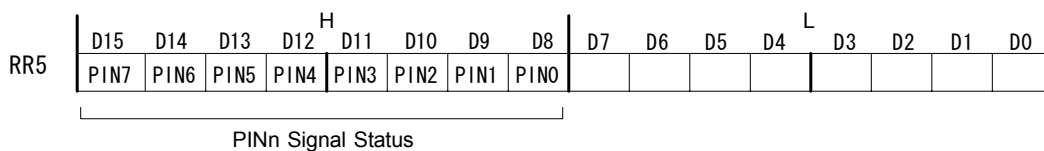
Table 2.8-2 Input signals can be used as general purpose input signal

Input signal (Pin number)	Function of the input signal	Bit of RR3 register	RR3 status display 0:Low level 1:Hi level
STOP0(42)	Driving stop signal	D0 bit (STOP0)	
STOP1(40)	Driving stop signal	D1 bit (STOP1)	
STOP2(39)	Driving stop signal	D2 bit (STOP2)	
ECA(37)	Encoder A-phase signal	D3 bit (ECA)	
ECB(38)	Encoder B-phase signal	D4 bit (ECB)	
INPOS(48)	In-position input signal from a servo driver	D5 bit (INPOS)	
ALARM(49)	Alarm signal from a servo driver	D6 bit (ALARM)	
LMTP(43)	+ direction hardware limit signal	D7 bit (LMTP)	
LMTM(44)	— direction hardware limit signal	D8 bit (LMTM)	

2.8.3 High word Data Signal in 8-bit Data Bus

When this IC is used in 8-bit data bus mode (H16L8=Low), high word D15~D8 which are not used for the data bus, can be used as general purpose input signals.

The signal levels are displayed in D15~D8 bits (PIN7~PIN0) of RR5 register. When the signal is Low level, 0 is displayed and when the signal is Hi level, 1 is displayed.



2.9 Timer

MCX501 is equipped with one timer, which can set with the range of 1 ~ 2,147,483,647 μ sec in increments of 1 μ sec (at CLK = 16MHz).

By using with synchronous action, various operations which combine a motor drive and timer functions can be performed precisely. The followings are some of examples.

- After the termination of driving, driving starts after the elapse of a specified time.

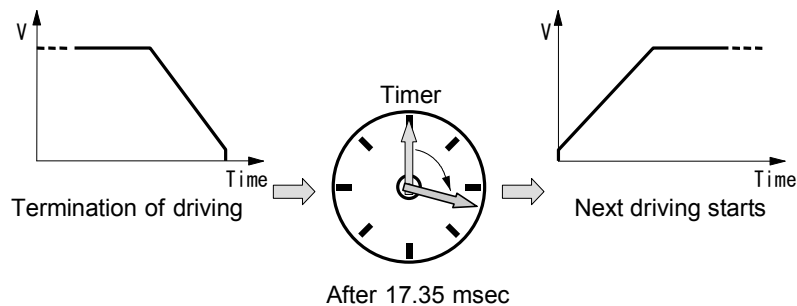


Fig. 2.9-1 Example 1 of Timer Operation

- Designated drive pulses are output with a specified time period correctly.

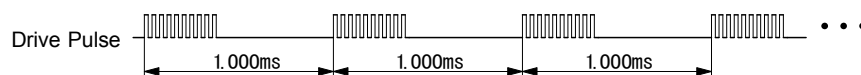


Fig. 2.9-2 Example 2 of Timer Operation

- Performs decelerating stop after driving at constant speed for a specified time in acceleration/deceleration driving.

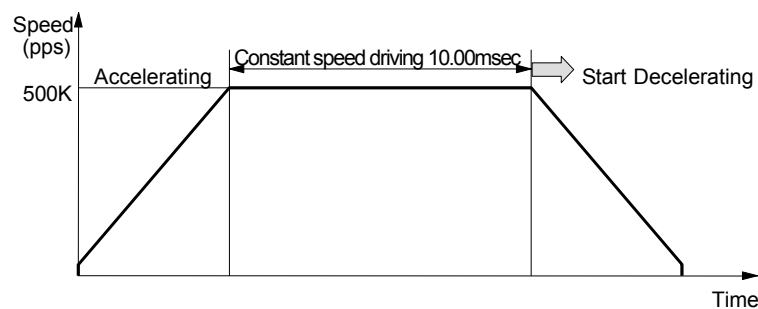


Fig. 2.9-3 Example 3 of Timer Operation

2.9.1 Timer Operation

MCX501 has a 31-bit length timer counter. When a timer is started, it counts up from 0 in increments of 1 μ sec, and when the count reaches the value specified by the timer value (the time is up), then the timer stops. When the operation mode of a timer is set to “once”, the timer operation is finished when the timer expires. When the operation mode of a timer is set to “repeat”, the count starts to count up from 0 again after the timer expires. And it repeats the operation unless the timer is stopped by timer-stop command or a synchronous action.

Expiring of a timer can be set as the activation factor of a synchronous action, and various operations such as the start of driving or output of an external signal can be performed. For more details of the synchronous action, see Chapter 2.6.

In addition, when a timer expires, the user can generate an interrupt signal and so it is possible to perform the operation in synchronization with the CPU.

2.9.2 Timer Setting

To operate a timer, the timer value and operation mode (once / repeat) must be set.

■ Timer value setting

A timer value can be set by timer value setting command (16h). Set values in WR6, 7 registers and write timer value setting command (16h) into WR0 register, and then it will be set. It sets with the range of 1 ~ 2,147,483,647 μ sec in increments of 1 μ sec (See Chapter 5.2.22).

The timer value can be changed while operating a timer.

■ Timer operation mode setting

Set the operation mode of a timer in D14 bit (TMMD) of WR3 register.

When 0 is set to D14 bit (TMMD), the timer operates once and when 1 is set, the timer operates repeatedly.

2.9.3 Timer-Start / Timer-Stop

■ Timer-start

A timer is started by timer-start command (73h) or activating the action in which timer-start code is set of synchronous action.

■ Timer-stop

In the operation mode is once, a timer stops when the count reaches the value specified by the timer value (the time is up). While operating a timer, it can be stopped by timer-stop command (74h) or a synchronous action.

When the operation mode is repeat, it can be stopped by timer-stop command (74h) or a synchronous action.

2.9.4 Timer and Synchronous Action

Timer operation can be used in a synchronous action.

As the activation factor of a synchronous action, "Timer is up" can be specified. As the action of a synchronous action, there are 3 kinds, "CT $\rightarrow$ MRn (saves the current timer value into MRn register)", "Timer-start" and "Timer-stop" can be specified. For more details of these functions, see Chapter 2.6.

2.9.5 Timer Operating State and Current Timer Value Reading

■ Current timer value reading

The current timer value in operation can be read out by current timer value reading command (38h).

A timer counter starts to count up from 0, and the value of a timer counter can be read out anytime during operation.

A timer counter clears to 0 when a timer stops. After a timer is finished or issuing timer-stop command, if the user reads the current timer value, 0 will be read out.

■ Main status register

Timer operating state can be checked by D12 bit (TIMER) of RR0 (main status) register. When a timer starts, D12 bit (TIMER) becomes 1 and that indicates the timer is in operation.

2.9.6 Interrupt by Timer

The user can generate an interrupt signal when a timer is up. Set D9 bit (TIMER) of WR1 register to 1.

For more details of the interrupt function, see Chapter 2.10.

2.9.7 Examples of Timer

■ Example 1 Driving starts after 17.35msec when the driving is finished.

When relative position driving is finished, it again starts the same relative position driving after 17.35msec. This is performed by the function of a synchronous action.

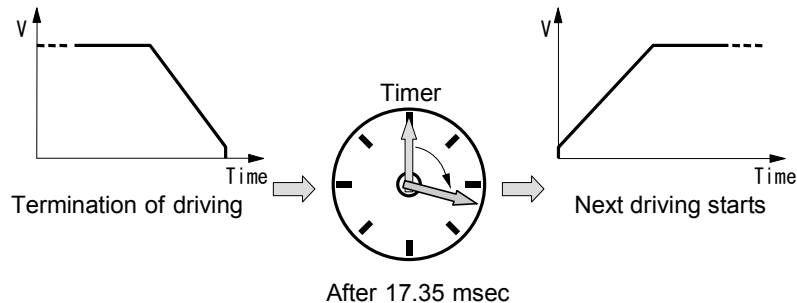


Fig. 2.9-4 Example 1: Timer Operation

【Program Example】

```
// Acceleration/deceleration driving setting
WR6 ← 0190h Write      // Initial speed 400 PPS
WR7 ← 0000h Write
WR0 ← 0004h Write

WR6 ← 9C40h Write      // Drive speed 40K PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← E848h Write      // Acceleration 125K PPS/SEC
WR7 ← 0001h Write
WR0 ← 0002h Write

WR6 ← 9C40h Write      // Drive pulse number 40000
WR7 ← 0000h Write
WR0 ← 0006h Write

// Timer setting
// Single timer
WR3 ← 0000h Write      // D14      0 TMMD: Timer operation Once

// Timer value setting
WR6 ← 43C6h Write      // Timer value 17350 μsec
WR7 ← 0000h Write
WR0 ← 0016h Write

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0156h Write      // D3~D0      0110 PREV3~0 : Activation factor Stops driving
                        // D8~D4      10101 ACT4~0 : Action Timer-start
WR0 ← 0026h Write

// Synchronous action SYNC1 setting
WR6 ← 00A2h Write      // D3~D0      0010 PREV3~0 : Activation factor Timer is up
                        // D8~D4      01010 ACT4~0 : Action Starts relative position driving
WR0 ← 0027h Write

// SYNC1~0 Enable
WR0 ← 0083h Write

// Start driving
WR0 ← 0050h Write      // Starts relative position driving
```

■ Example 2 Outputs designated drive pulses every 1msec.

Relative position driving ($20\text{kpps} \times 10$ pulses of the constant speed drive) starts every 1msec. This is performed by the function of a synchronous action.

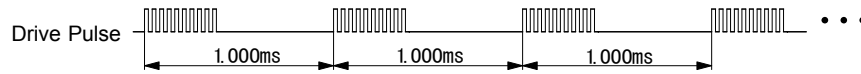


Fig. 2.9-5 Example 2: Timer Operation

【Program Example】

```
// Drive setting (constant speed driving at 1000 PPS)
WR6 ← 1200h Write      // Initial speed 8M PPS (maximum in specification)
WR7 ← 007Ah Write
WR0 ← 0004h Write

WR6 ← 4E20h Write      // Drive speed 20K PPS
WR7 ← 0000h Write
WR0 ← 0005h Write

WR6 ← 000Ah Write      // Drive pulse number 10
WR7 ← 0000h Write
WR0 ← 0006h Write

WR6 ← 0000h Write      // Logical position counter 0
WR7 ← 0000h Write
WR0 ← 0009h Write

// Timer setting
// Repeat timer
WR3 ← 4000h Write      // D14      1 TMMD : Timer operation Repeat

// Timer value setting
WR6 ← 03E8h Write      // Timer value 1000μsec
WR7 ← 0000h Write
WR0 ← 0016h Write

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0153h Write      // D3~D0      0011 PREV3~0 : Activation factor Starts driving
                        // D8~D4      10101 ACT4~0 : Action Timer-start
                        // D15      0 REP : Repeating action Disabled
WR0 ← 0026h Write

// Synchronous action SYNC1 setting
WR6 ← 80A2h Write      // D3~D0      0010 PREV3~0 : Activation factor Timer is up
                        // D8~D4      01010 ACT4~0 : Action Starts driving
                        // D15      1 REP : Repeating action Enabled
WR0 ← 0027h Write

// SYNC1~0 Enable
WR0 ← 0083h Write

// Start driving
WR0 ← 0050h Write      // Starts relative position driving

.
.
.

// Stop driving
WR0 ← 0074h Write      // Stops driving

// Disable synchronous action SYNC1
WR0 ← 0092h Write      // Disables synchronous action SYNC1
```

- Example 3 Performs decelerating stop in acceleration/deceleration driving after driving at constant speed for 10msec.

After acceleration/deceleration driving starts, a timer starts from the start of constant speed area for 10msec and when time is up, it performs decelerating stop. This is performed by the function of a synchronous action.

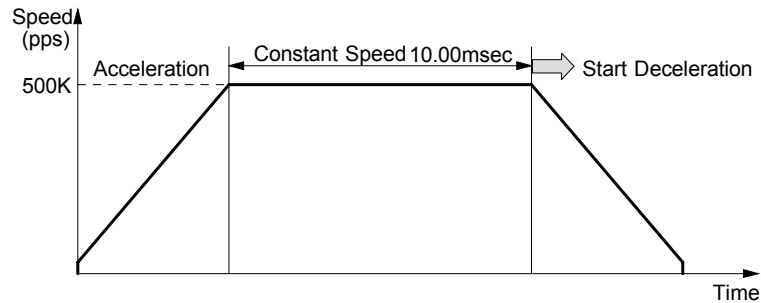


Fig. 2.9-6 Example 3: Timer Operation

【Program Example】

```
// Acceleration / deceleration driving setting
WR6 ← 0064h Write      // Initial speed 100 PPS
WR7 ← 0000h Write
WR0 ← 0004h Write

WR6 ← A120h Write      // Drive speed 500K PPS
WR7 ← 0007h Write
WR0 ← 0005h Write

WR6 ← E848h Write      // Acceleration 125K PPS/SEC
WR7 ← 0001h Write
WR0 ← 0002h Write

// Timer setting
// Single timer
WR3 ← 0000h Write      // D14      0 TMMD: Timer operation Once

// Timer value setting
WR6 ← 2710h Write      // Timer value 10000 μsec
WR7 ← 0000h Write
WR0 ← 0016h Write

// Synchronous action setting
// Synchronous action SYNC0 setting
WR6 ← 0154h Write      // D3~D0  0100 PREV3~0 : Activation factor Starts driving at constant speed area
                        // D8~D4  10101 ACT4~0 : Action Timer-start
WR0 ← 0026h Write

// Synchronous action SYNC1 setting
WR6 ← 0112h Write      // D3~D0  0010 PREV3~0 : Activation factor Timer is up
                        // D8~D4  10001 ACT4~0 : Action Decelerating stop
WR0 ← 0027h Write

// SYNC1~0 Enable
WR0 ← 0083h Write

// Start driving
WR0 ← 0052h Write      // Starts+direction continuous pulse driving
```

2.10 Interrupt

MCX501 has functions that generate an interrupt, which are the interrupt relevant to driving, the interrupt using a multi-purpose register and the interrupt by generating of a synchronous action. Thus, the user can generate an interrupt with various factors. The interrupt signal to the host CPU is only the one INTN signal.

All interrupt factors can be set to enable / disable. At reset, all interrupt signals are disabled.

■ Interrupt factor

Factors that generate an interrupt are as follows.

Table 2.10-1 Factors of Interrupt

Enable / Disable WR1 Register	Status RR1 Register	Factors of Interrupt
D0 (CMR0)	D0 (CMR0)	The comparison result of multi-purpose register MR0 with a comparative object changed to meet the comparison condition.
D1 (CMR1)	D1 (CMR1)	The comparison result of multi-purpose register MR1 with a comparative object changed to meet the comparison condition.
D2 (CMR2)	D2 (CMR2)	The comparison result of multi-purpose register MR2 with a comparative object changed to meet the comparison condition.
D3 (CMR3)	D3 (CMR3)	The comparison result of multi-purpose register MR3 with a comparative object changed to meet the comparison condition.
D4(D-STA)	D4(D-STA)	Driving starts.
D5(C-STA)	D5(C-STA)	Pulse output starts at constant speed area in acceleration / deceleration driving.
D6(C-END)	D6(C-END)	Pulse output is finished at constant speed area in acceleration / deceleration driving.
D7(D-END)	D7(D-END)	Driving is finished.
D8(H-END)	D8(H-END)	Automatic home search is finished.
D9(TIMER)	D9(TIMER)	Timer expires.
D10(SPLTP)	D10(SPLTP)	Outputs split pulse. (in positive logic, generates at ↑ of split pulse)
D11(SPLTE)	D11(SPLTE)	Split pulse is finished.
D12(SYNC0)	D12(SYNC0)	Synchronous action SYNC0 is activated.
D13(SYNC1)	D13(SYNC1)	Synchronous action SYNC1 is activated.
D14(SYNC2)	D14(SYNC2)	Synchronous action SYNC2 is activated.
D15(SYNC3)	D15(SYNC3)	Synchronous action SYNC3 is activated.

■ Interrupt setting and reading

Each factor of interrupt can be masked by setting levels in WR1 register bits: 1- enable and 0 - disable as shown in the table above. When the interrupt factor that is enabled becomes True, the corresponding bit of RR1 register will be set to 1 and the interrupt output signal (INTN) will be on the Low level. After the RR1 status has been read from the host CPU, RR1 register will be cleared from 1 to 0 and INTN will return to the Hi-Z level. That is, the interrupt signal is automatically cleared by reading RR1 register. And the information that an interrupt generated is sent to the CPU only once by the first reading of RR1 register after the interrupt, and after that, if the user reads RR1 register, the bit indicates 0 unless the next interrupt factor becomes True (Read-reset method).

■ Multiple interrupts

When multiple interrupt factors are enabled, if the first interrupt factor becomes True, the signal will be on the Low and the corresponding bit of RR1 register will be set to 1. After that, if the other factor becomes True before the CPU reads RR1 register, the bit corresponding to the other factor will be set to 1. In this case when reading RR1 register, two or more bits indicate 1 and the each interrupt factor notifies the generating of it.

■ Interrupt in 8-bit data bus

When 8-bit data bus is used, individually set each WR1H/WR1L register to 1– enable or 0 – disable. When an interrupt generates (interrupt signal is Low), individually read each RR1H/ RR1L register. If either register is only enabled, there is no need to read another register. The bits that indicate an interrupt are cleared to 0 by reading RR1H register once and RR1L register is the same as RR1H. When all the bits of both registers are cleared, the interrupt signal (INTN) returns to the Hi-Z level.

For more details of the WR1 register, see Chapter 4.4 and details of RR1 register, see Chapter 4.10.

Notes on the read timing from CPU

The timing of read/write cycles from the CPU is shown in Chapter 8.2.2. In read cycle, the address signal A[3:0] must be determined in the section of RDN signal is Low level. tAR minimum is 0 and tRA minimum is 3nsec. If this condition is violated and non-valid address data is into the section of RDN signal is **in** Low level, the data of RR1 register will be cleared by reading the other register and the interrupt signal may be cleared. Please note the read timing from the CPU when using the interrupt signal.

2.11 Input Signal Filter

This IC is equipped with an integral type filter in the input stage of each input signal. Figure 2.11-1 shows the filter configuration of each input signal. The time constant of a filter is determined by the T oscillation circuit in the diagram. This IC has two time constants A and B, and it is determined by the kinds of an input signal which of the time constants A or B is used. Enable/disable of a filter and a time constant can be set by input signal filter mode setting command (25h).

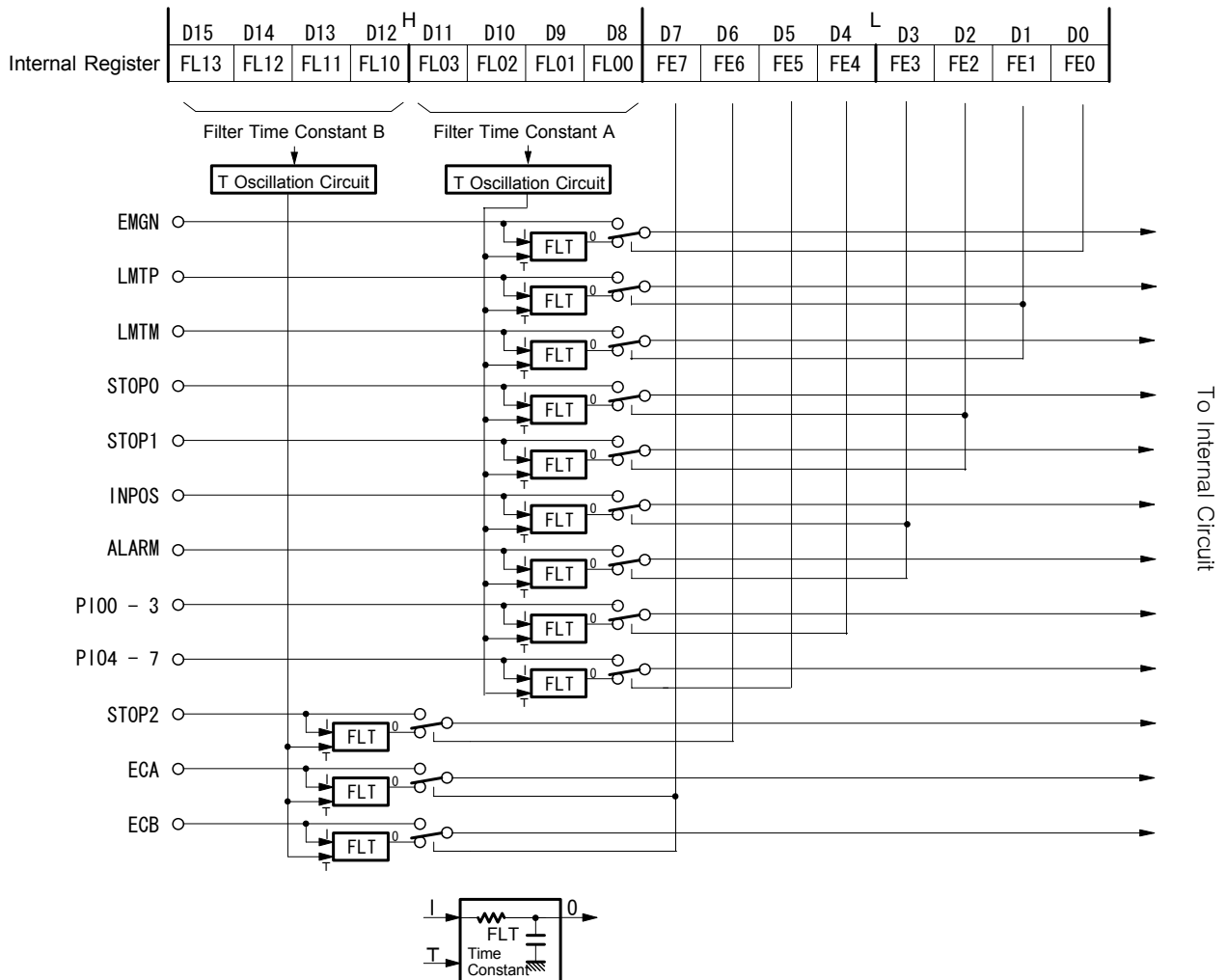


Fig. 2.11-1 Concept of Input Signal Filter Circuit

2.11.1 Setting of Input Signal Filter Function

The filter function of each input signal can be set by input signal filter mode setting command (25h).

WR6	D15	D14	D13	D12 ^H	D11	D10	D9	D8	D7	D6	D5	D4 ^L	D3	D2	D1	D0
	FL13	FL12	FL11	FL10	FL03	FL02	FL01	FL00	FE7	FE6	FE5	FE4	FE3	FE2	FE1	FE0
	Filter Time Constant B				Filter Time Constant A				Enable / Disable of Each Input Signal Filter							

The user can set whether the IC built-in filter function is enabled or the signal is passed through, to D7~0 bits (FE7~FE0) of each input signal. Set 1 to enable the filter function and 0 to disable (through).

Input signals corresponding to each bit is shown in the table 2.11-1. The time constant A or B applied to each input signal is determined.

Table 2.11-1 Input Signal and Corresponding Time Constant

Specified bit	Input signal	Applied time constant
D0(FE0)	EMGN	Filter Time Constant A
D1(FE1)	LMTP, LMTM	
D2(FE2)	STOP0, STOP1	
D3(FE3)	INPOS, ALARM	
D4(FE4)	PIO3~0	
D5(FE5)	PIO7~4	
D6(FE6)	STOP2	Filter Time Constant B
D7(FE7)	ECA, ECB	

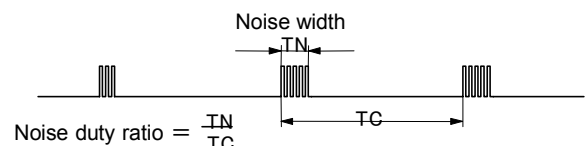
Use D11~ D 8 bits (FL03~FL00) for setting the filter time constant A and D15~D12 bits (FL13~FL10) for setting the filter time constant B.

Select a filter time constant from 16 stages shown in the table 2.11-2. When a time constant is increased, the removable maximum noise width increases, however, the signal delay time also increases. Therefore, set an appropriate value. Normally, set Ah or Bh for the time constant A. The time constant B (FL13~10) is provided for an encoder input signal.

Table 2.11-2 Time Constant and Removable Maximum Noise Width

(CLK=16MHz)		
Time constant (Hex)	Removable maximum noise width* 1	Input signal delay time
0	437.5 n sec	500 n sec
1	875 n sec	1μsec
2	1.75μsec	2μsec
3	3.5μsec	4μsec
4	7μsec	8μsec
5	14μsec	16μsec
6	28μsec	32μsec
7	56μsec	64μsec
8	112μsec	128μsec
9	224μsec	256μsec
A	448μsec	512μsec
B	896μsec	1.024msec
C	1.792msec	2.048msec
D	3.584msec	4.096msec
E	7.168msec	8.192msec
F	14.336msec	16.384msec

*1: Noise width



It requires that the noise duty ratio (time ratio under which noise is generated in the signal) must be 1/4 or less.

At reset, all input signal filter functions are disabled (through).

2.11.2 Example of Setting Input Signal Filters

For the input signals belong to the filter time constant A, set a 128 μ sec delay filter to EMGN, LMTP, LMTM, STOP0, STOP1 input signals and set “through” to other input signals.

ECA, ECB, STOP2 input signals belong to the filter time constant B are “through”.

【Program Example】

```
// Input/output signal filter mode setting
WR6 ← 0807h Write // D15~D12 0000 Filter time constant B Filter delay: 500nsec
                  // D11~D8 1000 Filter time constant A Filter delay: 128 $\mu$ sec
                  // D7 0 ECA, ECB signal(Filter time constant B) : Disables the filter (through)
                  // D6 0 STOP2 signal(Filter time constant B) : Disables the filter (through)
                  // D5 0 PI04-7 signal(Filter time constant A) : Disables the filter (through)
                  // D4 0 PI00-3 signal(Filter time constant A) : Disables the filter (through)
                  // D3 0 INPOS, ALARM signal(Filter time constant A) : Disables the filter (through)
                  // D2 1 STOP0,1 signal(Filter time constant A) : Enables the filter
                  // D1 1 LMTP, LMTM signal(Filter time constant A) : Enables the filter
                  // D0 1 EMGN signal(Filter time constant A) : Enables the filter
WR0 ← 0025h Write
```

2.12 Other Functions

2.12.1 Driving By External Signals

Relative position driving and continuous pulse driving can be controlled by either commands or external signals (EXPP, EXPM). This function can reduce the host CPU load for JOG feed or teaching mode. By inputting an encoder 2-phase signal of MPG, jog feed will be enabled.

PIO4, 5 signals of general purpose input/output signals are assigned to EXPP, EXPM signals.

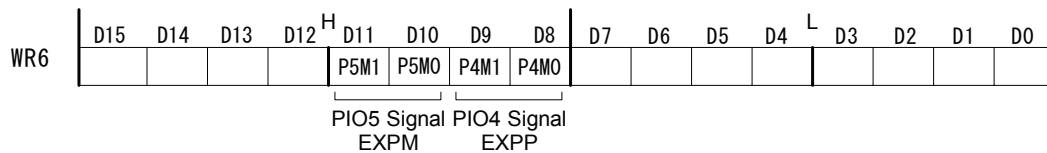
To perform driving by external signals, the following items must be set.

- ① Set PIO4, 5 signals to the input by PIO signal setting 1 command (21h).
- ② Set the driving mode by PIO signal setting 2•Other settings (22h).

■ Function Setting for Driving by External Signals of PIO4 Signal

To perform driving by external signals, set PIO4, 5 signals of general purpose input/output signals to EXPP, EXPM input signals for driving by external pulses.

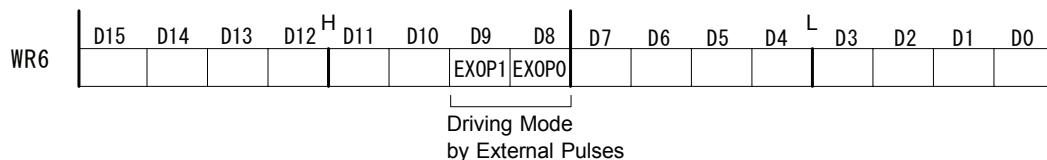
It is set in D11~8 bits of PIO signal setting 1 command (21h).



To use the function of PIO4 signal as the input signal for driving by external pulses (EXPP), set D9, 8 bits to 0, 0. Similarly, set D11, 10 bits of PIO5 signal to 0, 0.

■ Mode setting for driving

This is the mode setting for driving by external pulses. It is set in D9, 8 bits of PIO signal setting 2•Other settings (22h).



Use 2 bits, D9, 8 bits to set the mode of driving by external signals (EXPP, EXPM).

The driving mode corresponding to each bit is shown in the table below.

Table 2.12-1 Mode of Driving by External Signals

D9(EXOP1)	D8(EXOP0)	Mode of driving by external signals
0	0	Disables the driving by external signals
0	1	Continuous pulse driving mode
1	0	Relative position driving mode
1	1	MPG mode

■ Relative position driving mode

Set D9, 8 bits of PIO signal setting 2•Other settings (22h) to 1, 0 and set the appropriate speed parameters for relative position driving and drive pulse number (positive value). Once EXPP falls down to the Low level (↓), +direction relative position driving will start by ↓ of it. Similarly, once EXPM falls down to the Low level (↓), -direction relative position driving will start by ↓ of it. The Low level width of each signal must be larger than 4 CLK cycles. Before the driving is finished, if the signal falls down from the Hi to Low level again, it will be invalid.

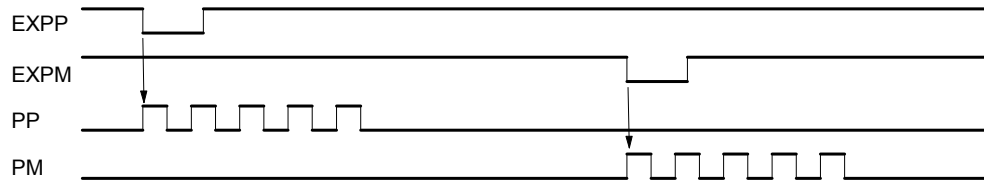


Fig. 2.12-1 Example of Relative Position Driving (Drive Pulse Number: 5) by External Signal

■ Continuous Pulse Driving Mode

Set D9, 8 bits of PIO signal setting 2•Other settings (22h) to 0, 1 and set the appropriate speed parameters for continuous pulse driving. Once EXPP falls down to the Low level (↓), the + direction driving pulses will be output continuously during the low level. If EXPP returns from Low level to Hi level, decelerating stop will be performed in trapezoidal driving and instant stop will be performed in constant speed driving. Similarly, EXPM will output the -direction driving pulses continuously during the low level. If the other input signal of EXPP/EXPM signals falls down from the Hi to Low level, the driving in the other direction will start immediately after the driving in the current direction is finished.

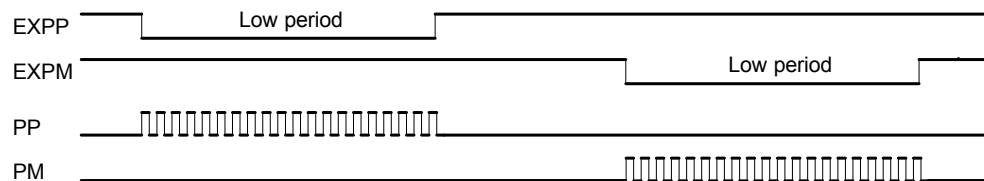


Fig. 2.12-2 Example of Continuous Pulse Driving by External Signal

■ MPG mode

Set D9, 8 bits of PIO signal setting 2•Other settings (22h) to 1, 1 and set the appropriate speed parameters for driving and drive pulse number. Connect the A-phase signal of an encoder to EXPP input and the B-phase signal to EXPM input. When EXPM signal is on the Low level, +direction relative position driving is activated at the rising edge ↑ of EXPP signal. When EXPM signal is on the Hi level, -direction relative position driving is activated at the rising edge ↑ of EXPP signal. When the drive pulse number is set to 1, one drive pulse is output at the each rising edge ↑ of EXPP signal. If drive pulse number is set to TP, the TP number of drive pulses is output.

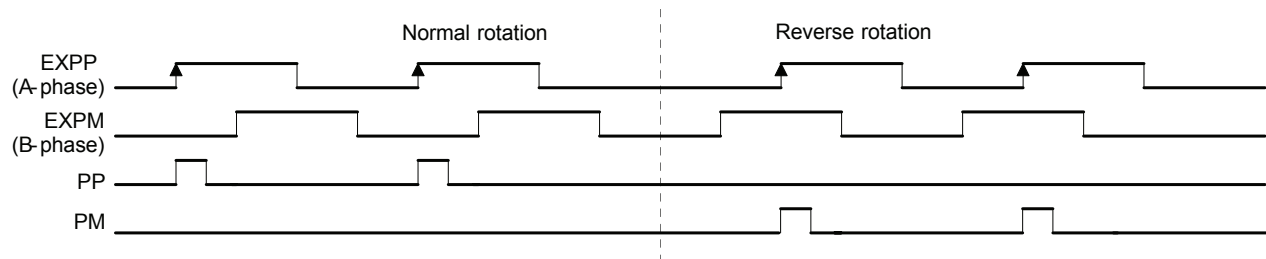


Fig. 2.12-3 Example of Driving (Drive Pulse Number: 1) by MPG

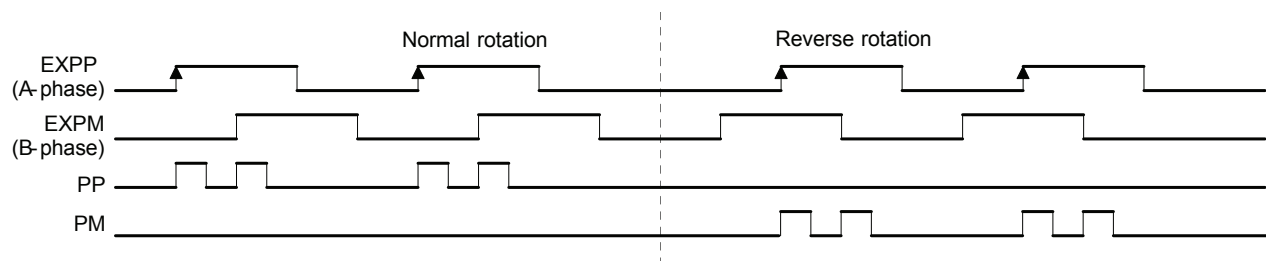


Fig. 2.12-4 Example of Driving (Drive Pulse Number: 2) by MPG

Set the speed parameter in the following conditions to complete output of the TP number of drive pulses with a period from the rising edge ↑ of EXPP signal to the next rising edge ↑ of EXPP signal.

$$DV \geq F \times TP \times 2$$

DV : Drive speed (pps)

TP : Drive pulse number

F : Frequency (Hz) at the maximum speed of MPG encoder

For instance, under the conditions where the maximum frequency of MPG is $F=500\text{Hz}$ and the drive pulse number is $TP=1$, the drive speed must be $DV=1000\text{pps}$ or greater. Since acceleration/deceleration driving is not applied, set the initial speed SV to the value larger than the drive speed DV. However, when a stepping motor is used for driving, the drive speed must not exceed the self-starting frequency of the motor.

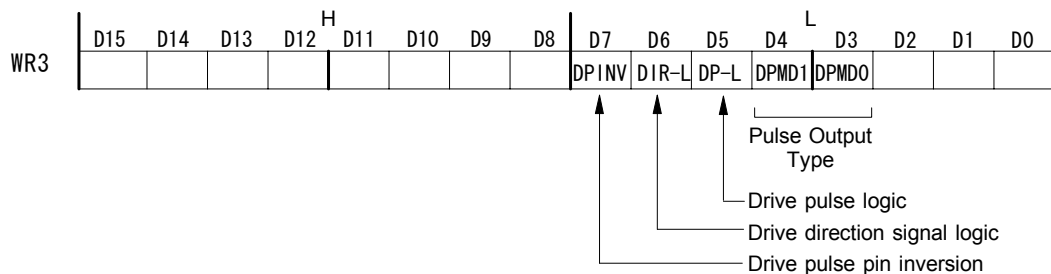
2.12.2 Pulse Output Type Selection

Drive pulse output signals are PP/PLS/PB (35) and PM/DIR/PB (36). Four pulse output types are available as shown in the table below. In independent 2-pulse type, when the driving is in the + direction, the pulse output is from PP, and when the driving is in the – direction, the pulse output is from PM. In 1-pulse 1- direction type, PLS is for output of drive pulses and DIR is for output of direction signals. In quadrature pulse type, the A-phase signal of quadrature pulse is output to PA and the B-phase signal of quadrature pulse is output to PB. In quadrature pulse and quad edge evaluation, when output of PA, PB pulses changes, the logical position counter is up (down). In quadrature pulse and double edge evaluation, when output of PA pulses changes, the logical position counter is up (down).

Table 2.12-2 Drive Pulse Output Type

Pulse Output Type	Signal	Driving in the + direction					Driving in the - direction					
		LP	0	1	2	3	4	4	3	2	1	0
Independent 2-pulse	PP											
	PM											
1-pulse 1-direction	PLS											
	DIR											
Quadrature pulses and quad edge evaluation	PA											
	PB											
Quadrature pulses and double edge evaluation	PA											
	PB											

Pulse output type can be set by D4, 3 bits (DPMD1, 0) of WR3 register.



The mode setting for driving corresponding to each bit is as follows.

Table 2.12-3 Drive Pulse Output Type

D4(DPMD1)	D3(DPMD0)	Pulse Output Type
0	0	Independent 2-pulse
0	1	1-pulse 1-direction
1	0	Quadrature pulse and quad edge evaluation
1	1	Quadrature pulse and double edge evaluation

Please refer to Chapter 9.2 for the the timing of output pulse signal (PLS) and direction signal (DIR) in 1-pulse 1-direction type. When the user wants to set DIR signal before driving, issue direction signal + setting command (58h) or direction signal – setting command (59h).

And it sets the logical level of driving pulses by D5 bit (DP-L), the logical level of the direction (DIR) output signal by D6 bit (DIR-L) and sets whether the output pins of a drive pulse signal are replaced or not by D7 bit (DPINV).

2.12.3 Encoder Pulse Input Type Selection

The encoder pulse input (ECA/PPIN, ECB/PMIN) which counts up/down the real position counter can be selected from 2 types, quadrature pulses input and Up / Down pulse input.

■ Quadrature pulses input

As quadrature pulses input types, the user can select from 3 types, quadrature pulses input and quad edge evaluation, quadrature pulses input and double edge evaluation, quadrature pulses input and single edge evaluation.

When quadrature pulses input type is engaged and ECA signal goes faster 90 degree phase than ECB signal does, it's "count up" and ECB signal goes faster 90 degree phase than ECA signal does, it's "count down". And when quad edge evaluation is set, it counts Up/Down at the rising edge (↑) and falling edge (↓) of both signals. When double edge evaluation is set, it counts Up/Down at the rising edge (↑) and falling edge (↓) of A-phase signals. When single edge evaluation is set, it counts Up/Down at the rising edge (↑) of A-phase signals.

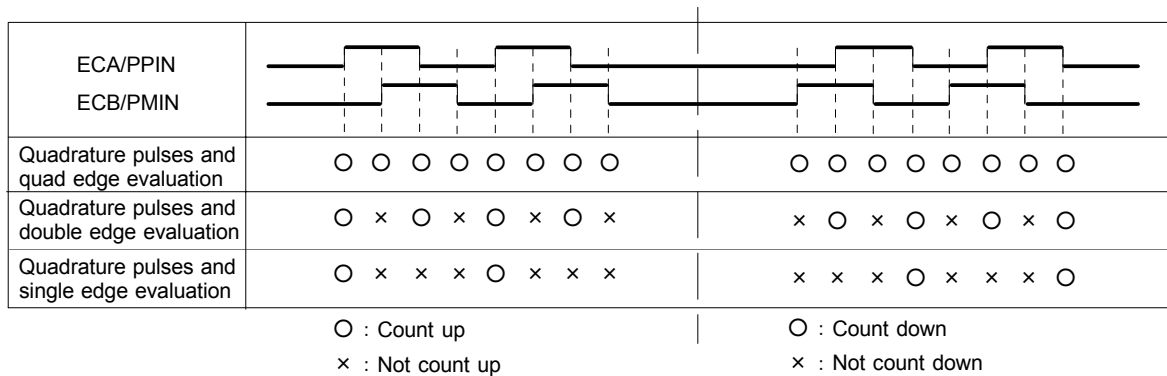


Fig. 2.12-5 Quadrature Pulse Input

■ Up/down pulse input

ECA/PPIN is for "count up" input, and ECB/PMIN is for "count down" input. The counter counts up when the positive pulses go up (↑). (when the positive logic is set.)

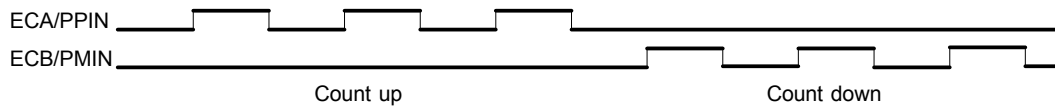
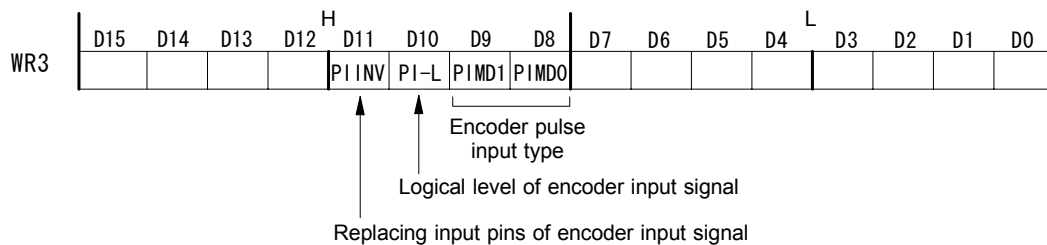


Fig. 2.12-6 Up / Down Pulse Input

■ Encoder Pulse Input Type Setting

Encoder pulse input type can be set by D8, 9 bits (PIMD0, 1) of WR3 register.



The encoder pulse input type corresponding to each bit is as follows.

Table 2.12-4 Encoder pulse input type

D9(PIMD1)	D3(PIMD0)	Encoder pulse input type
0	0	Quadrature pulses input and quad edge evaluation
0	1	Quadrature pulses input and double edge evaluation
1	0	Quadrature pulses input and single edge evaluation
1	1	Up / Down pulse input

And it sets the logical level of an encoder input signal by D10 bit (PI-L) and sets whether the input pins of an encoder pulse input are replaced or not by D11 bit (PIINV).

The increase/decrease of the real position counter due to replacing input pins of an encoder input signal as shown in the table below.

Table 2.12-5 Increase/Decrease of Real Position Counter due to Replacing Input Pins of Encoder Input Signal

WR3/D11(PIINV)	Pulse input mode	Increase/decrease of real position counter
0	quadrature pulses mode	Count UP when the A phase is advancing. Count DOWN when the B phase is advancing.
	Up / Down pulse mode	Count UP at PPIN pulse input. Count DOWN at PMIN pulse input.
1	quadrature pulses mode	Count UP when the B phase is advancing. Count DOWN when the A phase is advancing.
	Up / Down pulse mode	Count UP at PMIN pulse input. Count DOWN at PPIN pulse input.

2.12.4 Hardware Limit Signals

Hardware limit signals, LMTP and LMTM, are used for stopping the pulse output if the limit sensors of + and – directions are triggered.

The user can set to enable/disable a limit signal and set the logical level of a limit signal, and set whether to perform decelerating stop or instant stop when a limit signal becomes active, and select whether to replace input pins of hardware limit input signals.

Enable/disable of a limit signal, the logical level of a limit signal and the stop type can be set by D12~10 bits of WR2 register. For more details of the WR2 register, see Chapter 4.5.

Whether to replace input pins of hardware limit input signals or not can be set by D12 bit (LMINV) of WR3 register. For more details of the WR3 register, see Chapter 4.6.

The status of a limit signal can be read out from RR3 register anytime.

2.12.5 Interface to Servo Motor Driver

■ INPOS signal and ALARM signal

As the input signals for connecting a servo motor driver, there are the INPOS signal (in-position input signal) and the ALARM signal (alarm input signal).

The user can set each signal to enable/disable and the logical level by D9~6 bits of WR2 register. For more details of the WR2 register, see Chapter 4.5.

INPOS input signal is corresponding to the in-position signal of a servo motor driver. When set to enable, and if INPOS becomes active after driving is finished, D0 bit of RR0 (main status) register will return to 0.

ALARM input signal receives the alarm signal from a servo motor driver. When set to enable, it monitors ALARM signal during the driving, and when ALARM becomes active, driving will stop instantly. At this time, D4 (ALARM) and D14 (ALARM) bits of RR2 register become 1.

The status of these input signals from a servo motor driver can be read out from RR3 register anytime.

■ Deviation counter clear output signal

As a servo motor driver output signal, a deviation counter clear signal (DCC) is available.

The logical level of a deviation counter clear signal (DCC) and pulse width can be set by D3~6 bits of automatic home search mode setting 2 command (24h). For more details of the automatic home search mode setting 2 command (24h), see Chapter 5.3.5.

When deviation counter clear output command (72h) is issued, deviation counter clear pulses are output based on the logical level of pulses and pulse width set by automatic home search mode setting 2 command (24h).

In the case of using the deviation counter clear signal (DCC) in automatic home search, see Chapter 2.5.2 and 2.5.4.

2.12.6 Emergency Stop

MCX501 has the input signal EMGN that can perform the emergency stop function during the driving. Normally, this signal is kept on the Hi level. When it falls down to the Low level, driving will stop immediately and D5 (EMG) and D15 (EMG) bits of RR2 register become 1. Please be noted that there is no way to select the logical level of EMGN signal.

The status of EMGN signal can be read out from RR3 register anytime.

There are the following methods to perform the emergency stop function from the host CPU.

- a. Issue an instant stop command
Write instant stop command (57h) into WR0 register.
- b. Issue a command reset
Write 00FFh into WR0 register, and it will be reset.

2.12.7 Status Output

The status of driving/stop is output to D0 (DRIVE) bit of RR0 register and PIO0 signal.

The driving status of acceleration/constant speed/deceleration is output to D2 (ASND), D3 (CNST), D4 (DSND) bits of RR0 register and also the signals PIO2/ASND, PIO3/CNST, PIO4/DSND show the levels.

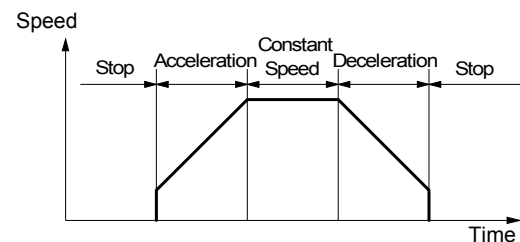


Fig. 2.12-7 Driving Status

Table 2.12-6 RR0 register and PION signal corresponding to Driving Status

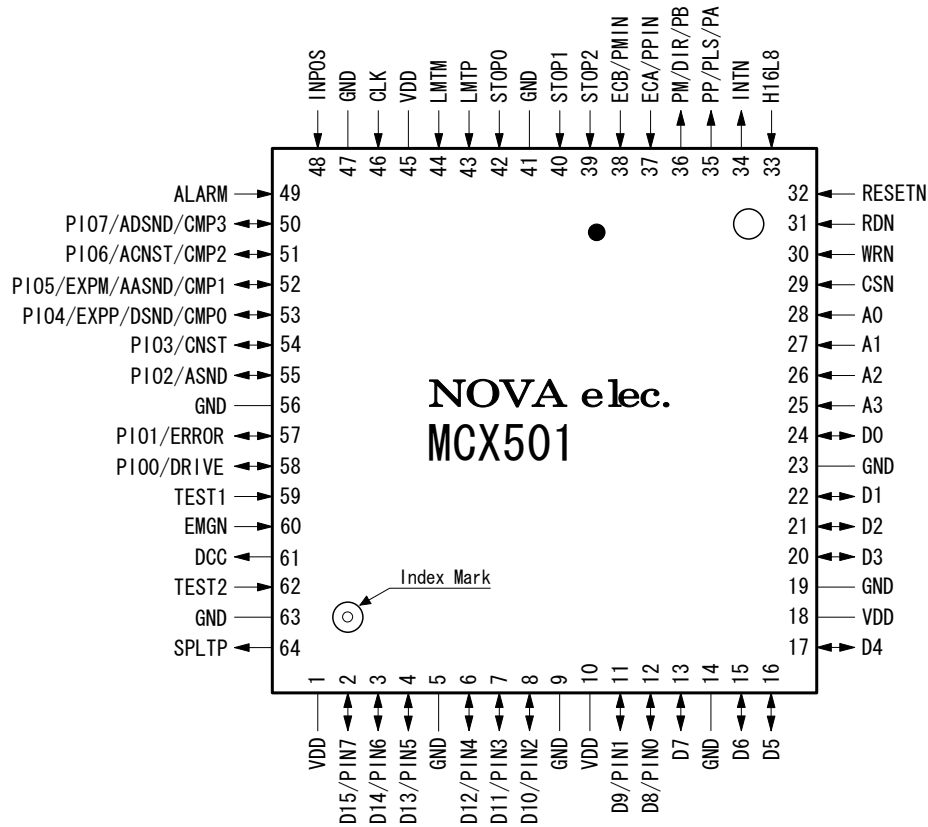
Drive Status	Main status register (RR0)				PION signal			
	D0/DRIVE	D2/ASND	D3/CNST	D4/DSND	PIO0/DRIVE	PIO2/ASND	PIO3/CNST	PIO4/DSND
Stop	0	0	0	0	Low	Low	Low	Low
Acceleration	1	1	0	0	Hi	Hi	Low	Low
Constant Speed	1	0	1	0	Hi	Low	Hi	Low
Deceleration	1	0	0	1	Hi	Low	Low	Hi

In S-curve acceleration/deceleration driving, the status of acceleration increasing / acceleration constant / acceleration decreasing is output to D5 (AASND), D6 (ACNST), D7 (ADSND) bits of RR0 register and PIO5/AASND, PIO6/ACNST, PIO7/ADSND signals.

To output the driving status to PION signal, use PIO signal setting 1 command (21h). See Chapter 5.3.2.

3. Pin Assignments and Signal Description

3.1 Pin Assignments



See Chapter 10 for the 64-pin plastic TQFP package: 10×10mm, external package: 12×12mm, pin pitch: 0.5mm

3.2 Signal Description

See Chapter 3.3 for description of input/output logic. An integral filter circuit is available in the internal input column of this IC for the input signals with – F – symbol.

Signal Name	Pin No.	Input/Output	Signal Description
CLK	46	Input A	Clock: clock signal for internal synchronous loop of MCX501 The standard frequency is 16 MHz. This signal is for drive speed, acceleration / deceleration and jerk. If the frequency setting is not 16 MHz, the setting values of speed and acceleration / deceleration are different.
D15/PIN7 ~ D8/PIN0	2~4, 6~8, 11~12,	Bi-directional A	DATA BUS (D15~D0): 3-state bi-direction 16-bit data bus When CSN=Low and RDN=Low, these signals are for outputting. Otherwise, they are high impedance inputs. If 8-bit data bus is used and D15~D8 are not used, they should be connected to VDD or GND through high impedance (about 10K~100 kΩ). Universal Input7~0 (PIN7~0): If 8-bit data bus is used, D15~D8 can be used as general purpose input. The signal status can be read from RR5 register anytime.
D7~D0	13,15~17, 20~22,24		

Signal Name	Pin No.	Input/Output	Signal Description
A3~A0	25~28	Input A	Address: address signal for host CPU to access the write / read registers If 16-bit data bus is used, A3 cannot be used and should be connected to GND.
CSN	29	Input A	Chip Select: input signal for selecting I/O device for MCX501 Set CSN to the Low level for data reading and writing.
WRN	30	Input A	Write Strobe: its level is Low while data is being written to MCX501. When WRN is Low, CSN and A3-A0 must be assured. When WRN is up (↑), the data will be latched in the write register, and while WRN is up (↑), the levels of D15~D0 should be assured.
RDN	31	Input A	Read Strobe: its level is Low while data is being read from MCX501. Only when CSN is on the low level, the selected read register data from A3~A0 address signals can be output from the data bus.
RESETN	32	Input A	Reset: reset (return to the initial setting) signal for MCX501. Setting RESETN to Low for more than 8 CLK cycles will reset MCX501. This IC must be reset by RESETN signal when the power is on. [Note] If there is no clock input to MCX501, setting RESETN to Low cannot reset this IC.
H16L8	33	Input A	Hi=16-bit, Low=8-bit: data bus width selection for 16-bit / 8-bit When the setting is Hi, 16-bit data bus is selected for processing the 16-bit data reading / writing in IC; when the setting is Low, 8-bit data bus (D7~D0) is active for data reading / writing.
TEST1 TEST2	59,62	—	Test: input terminal for internal-circuit test Make sure that both pins are open or connected to GND.
INTN	34	Output B	Interrupt: output an interrupt signal to the host CPU. If any interrupt factor generates an interrupt, INTN becomes Low level. When an interrupt is released, it will return to the Hi-Z level.
PP/PLS/PA	35	Output A	Pulse +/Pulse/Pulse Phase A: + direction drive pulse outputting It is on the Low level at reset, and while the driving is started, DUTY 50% (at constant speed) of the plus drive pulses is output. When the 1-pulse 1-direction mode is selected, this terminal is for drive output. When the quadrature pulse mode is selected, this terminal is for A-phase signal output.
PM/DIR/PB	36	Output A	Pulse -/Direction/Pulse Phase B: - direction drive pulse outputting It is on the Low level at reset, and while the driving is started, DUTY 50% (at constant speed) of the plus drive pulses is output. When the 1-pulse 1-direction mode is selected, this terminal is the direction signal. When the quadrature pulse mode is selected, this terminal is for B-phase signal output.
ECA/PPIN	37	Input A — F —	Encoder-A/Pulse +in: signal for encoder phase-A input This input signal, together with phase-B signal, will make the Up / Down pulse transformation to be the input count of real position counter. When the Up / Down pulse input mode is selected, this terminal is for UP pulses input. Once the input pulse is up (↑), the real position counter is counting up.
ECB/PMIN	38	Input A — F —	Encoder-B/Pulse -in: signal for encoder phase-B input This input signal, together with phase-A signal, will make the Up / Down pulse transformation to be the input count of real position counter. When the Up / Down pulse input mode is selected, this terminal is for DOWN pulses input. Once the input pulse is up (↑), the real position counter is counting down.
STOP2~0	39,40,42	Input A — F —	STOP 2~0: input signal to perform decelerating / instant stop These signals can be used for HOME searching. When the filter function is disabled, the active pulse width must be 2CLK or more. Enable / disable and logical levels can be set for STOP2~STOP0. In automatic home search, STOP0 can be assigned to a near home search signal, STOP1 to a home signal and STOP2 to an encoder Z-phase signal. The signal status can be read from register RR3.

Signal Name	Pin No.	Input/Output	Signal Description
LMTP	43	Input A — F —	OVER Limit +: signal of + direction over limit During the + direction drive pulse outputting, decelerating stop or instant stop will be performed once this signal is active. When the filter function is disabled, the active pulse width must be 2CLK or more. Enable / disable, decelerating stop / instant stop and logical levels can be set as commands. When the limit signal is enabled and this signal is in its active level during + direction driving, HLMT+ bit of RR2 register becomes 1. The signal status can be read from register RR3, and this signal can be used to search a home position.
LMTM	44	Input A — F —	OVER Limit -: signal of - direction over limit During the - direction drive pulse outputting, decelerating stop or instant stop will be performed once this signal is active. When the filter function is disabled, the active pulse width must be 2CLK or more. Enable / disable, decelerating stop / instant stop and logical levels can be set as commands. When the limit signal is enabled and this signal is in its active level during - direction driving, HLMT- bit of RR2 register becomes 1. The signal status can be read from register RR3, and this signal can be used to search the home position.
INPOS	48	Input A — F —	In-position: input signal for servo driver in-position Enable / disable and logical level can be set as commands. When enabled, DRIVE bit of main status register does not return to 0 until this signal becomes active after the driving is finished. The signal status can be read from register RR3.
ALARM	49	Input A — F —	Servo Alarm: input signal for servo driver alarm Enable/disable and logical level can be set as commands. When enabled and when changes to active level during the driving, ALARM bit of RR2 register becomes 1 and driving stops instantly. The signal status can be read from register RR3.
PIO7 /ADSND /CMP3	50	Bi-directional A — F —	Universal Input Output 7 / Acceleration Descend / Compare MR3: general purpose input / output signals (PIO7), acceleration decreasing status output signal (ADSND), MR3 comparison output (CMP3) share the same pin. The signal to use can be set as commands. General purpose input signal (PIO7) status can be read from register RR5. General purpose output signal (PIO7) can output the 1/0 data in WR4 register to Hi / Low. For synchronous action, it can be used as the input signal of an activation factor. Acceleration decreasing status output (ADSND) becomes Hi while the driving command is executed and when acceleration decrease. MR3 comparison output (CMP3) becomes Hi when it satisfies the comparison condition of multi-purpose register MR3.
PIO6 /ACNST /CMP2	51	Bi-directional A — F —	Universal Input Output6 / Acceleration Constant / Compare MR2: general purpose input / output signals (PIO6), acceleration constant status output signal (ACNST), MR2 comparison output (CMP2) share the same pin. The signal to use can be set as commands. About general purpose input / output signals (PIO6), it is the same as PIO7. For synchronous action, it can be used as the input signal of an activation factor. Acceleration constant status output (ACNST) becomes Hi while the driving command is executed and when acceleration keeps constant. MR2 comparison output (CMP2) becomes Hi when it satisfies the comparison condition of multi-purpose register MR2.

Signal Name	Pin No.	Input/Output	Signal Description
PIO5 /EXPM /AASND /CMP1	52	Bi-directional A — F —	Universal Input Output5/External Operation-/Acceleration Ascend/Compare MR1: general purpose input/output signals (PIO5), External Operation- (EXPM), acceleration increasing status output signal (AASND), MR1 comparison output (CMP1) share the same pin. The signal to use can be set as commands. About general purpose input/output signals (PIO5), it is the same as PIO7. For synchronous action, it can be used as the input signal of an activation factor. External Operation- (EXPM) is -direction drive starting signal from external source. When the position driving is commanded from an external source, -direction relative position driving will start if this signal is down (↓). When the continuous pulse driving is commanded from an external source, -direction continuous pulse driving will start if this signal is on the Low level. In MPG mode, the encoder B-phase signal is input to this pin. Acceleration increasing status output (AASND) becomes Hi while the driving command is executed and when acceleration increase. MR1 comparison output (CMP1) becomes Hi when it satisfies the comparison condition of multi-purpose register MR1.
PIO4 /EXPP /DSND /CMP0	53	Bi-directional A — F —	Universal Input Output4/External Operation+/Descend/Compare MR0: general purpose input/output signals (PIO4), External Operation+ (EXPP), deceleration status output signal (DSND), MR0 comparison output (CMP0) share the same pin. The signal to use can be set as commands. About general purpose input/output signals (PIO4), it is the same as PIO7. For synchronous action, it can be used as the input signal of an activation factor. External Operation+ (EXPP) is +direction drive starting signal from external source. When the position driving is commanded from an external source, +direction relative position driving will start if this signal is down (↓). When the continuous pulse driving is commanded from an external source, + direction continuous pulse driving will start if this signal is on the Low level. In MPG mode, the encoder A-phase signal is input to this pin. Deceleration status output (DSND) becomes Hi while the driving command is executed and when in deceleration. MR0 comparison output (CMP0) becomes Hi when it satisfies the comparison condition of multi-purpose register MR0.
PIO3 /CNST	54	Bi-directional A — F —	Universal Input Output3/Constant: general purpose input/output signals (PIO3), constant speed driving status output signal (CNST) share the same pin. The signal to use can be set as commands. About general purpose input/output signals (PIO3), it is the same as PIO7. For synchronous action, it can be used as the input signal of an activation factor or the output signal of synchronous pulses of the action. The logical level of synchronous pulses and pulse width can be set as commands. Constant speed driving status output (CNST) becomes Hi while the driving command is executed and when in constant speed driving.
PIO2 /ASND	55	Bi-directional A — F —	Universal Input Output2/Ascend: general purpose input/output signals (PIO2), acceleration status output signal (ASND) share the same pin. The signal to use can be set as commands. About general purpose input/output signals (PIO2), it is the same as PIO7. About synchronous action, it is the same as PIO3. Acceleration status output (ASND) becomes Hi while the driving command is executed and when in acceleration.
PIO1 /ERROR	57	Bi-directional A — F —	Universal Input Output1/Error: general purpose input/output signals (PIO1), error status output signal (ERROR) share the same pin. The signal to use can be set as commands. About general purpose input / output signals (PIO1), it is the same as PIO7. About synchronous action, it is the same as PIO3. Error status output (ERROR) becomes Hi while an error occurs.

Signal Name	Pin No.	Input/Output	Signal Description
PIO0 /DRIVE	58	Bi-directional A — F —	Universal Input Output0 / Drive: general purpose input / output signals (PIO0), drive status output signal (DRIVE) share the same pin. The signal to use can be set as commands. About general purpose input / output signals (PIO1), it is the same as PIO7. About synchronous action, it is the same as PIO3. Drive status display output (DRIVE) is set to High level while drive pulses are output. At execution of automatic home search, this signal is set to High level. The DRIVE signal is set to High level until INPOS becomes active when INPOS signal for the serve motor is enabled by mode selection.
EMGN	60	Input A — F —	Emergency Stop: input signal to perform the emergency stop When this signal is set to Low level during the driving, driving stops immediately and EMG bit of RR2 register becomes 1. When the filter function is disabled, the low level pulse width must be more than 2CLK. [Note] For this signal, its logical level cannot be selected.
DCC	61	Output A	Deviation Counter Clear: deviation counter clear output signal A deviation counter clear output (DCC) signal is output for a servo motor driver. The signal can be output by mode setting in automatic home search. It can also be output by a command.
SPLTP	64	Output A	Split Pulse: Outputs split pulses Split pulse output can be started and stopped by a synchronous action or a command. Split length, pulse width and pulse number can be set by a command. And output logic, with or without starting pulse can be set as commands.
GND	5,9,14, 19,23,41, 47,56,63		Ground (0V) Terminal All of the pins must be connected to 0V.
VDD	1,10, 18,45		+3.3V Power Terminal All of the pins must be connected to each power without fail.

3.3 Input/Output Logic

Input A	LVTTL Schmitt trigger input, which is high impedance because there is no pull high resistor for those signals in this IC. Input is 5V tolerant. 3.3V and 5V type output (CMOS level and TTL level) can be connected. The user should connect to GND or VDD if the input is not used. The signal with – F – symbol has an integral filter circuit in the internal input column of this IC.
Output A	It is 3.3V type CMOS level output, 6mA driving buffer (Hi level output current IOH=-6mA, VOH=2.4Vmin, Low level output current IOL=6mA, VOL=0.4Vmax). 5V type input can be connected when the other input is TTL level. If the other input is 5V type CMOS level, it cannot be connected. ※Note1
Output B	It is open collector type output, 9mA driving buffer, (Low level output current IOL=9mA, VOL=0.4Vmax). Pull up to +3.3V with high impedance if this output is used. It can also be connected to TTL level 5V type IC.
Bi-directional A	Input side is 5V tolerant LVTTL Schmitt trigger. Because there is no pull high resistor for those signals in this IC, the user should pull up the data bus with high impedance. The user should pull up to +3.3V with high impedance (about 10k~100 kΩ) when bits D15~D8 are not used. Output side is 3.3V type CMOS level output, 9mA driving buffer (Hi level output current IOH=-9mA, VOH=2.4Vmin, Low level output current IOL=9mA, VOL=0.4Vmax). 5V type bi-directional IC can be connected when the other input is TTL level. If the other input is 5V type CMOS level, it cannot be connected. □Note1

Note1: Even if the output signal of output A and Bi-directional A is pull up with 5V through resistor, Hi level output voltage cannot raise to Hi level input voltage of 5V type CMOS. Please don't design the logic like this.

3.4 Remarks of Logic Design

a. About TEST1, 2 Pins

Make sure that TEST1, 2 (59, 62) pins are open or connected to GND. If these pins are connected to VDD, it will not work correctly at all due to running the internal test circuit.

b. About Unused Input Pins

Make sure that unused input pins (Input A) are connected to GND or VDD. If these pins are open, the signal level of pins will be unstable and may cause malfunction.

c. About Unused Bi-directional Pins

Make sure that unused bi-directional pins (Bi-directional A) are connected to VDD or GND through high impedance (about 10k~100 k Ω). If these pins are directly connected to GND or VDD, the IC may be damaged by overcurrent in case of such as a programming mistake causes the output state.

d. De-coupling Capacitor

Please connect VDD and GND with two or three De-coupling capacitors (about 0.1 μ F).

e. Noise Generated by Terminal Induction

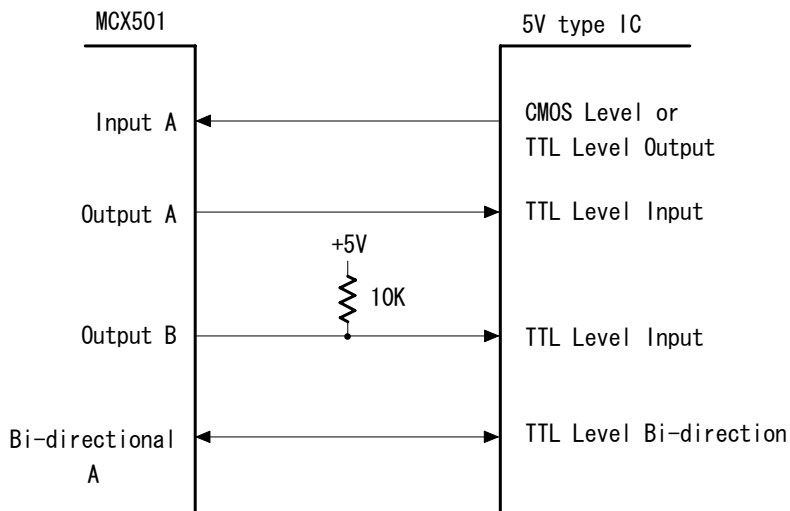
The noise will exist because the inductance is in these pins. The user can add a capacitor (10-100pF) to pins to reduce the noise.

f. Reflection on Transfer Path

The load capacity for outputting types A, B, and bi-directional A is 20-50pF. So, the reflection will happen if the PCB wiring is more than 60cm. Please shorten the PCB wiring length as shorter as you can.

g. Example of Connection between MCX501 and 5V type IC

The input/output logic of MCX501 is 5V tolerant. But its output logic can connect with TTL level input only. It cannot connect with CMOS level input.



4. Register

This chapter indicates the user how to access all the registers in MCX501, and what are the mapping addresses of these registers.

4.1 Register Address by 16-bit Data Bus

As shown in the table below, when 16-bit data bus is used, the access address of read / write register is 8-bit.

■ Write Register in 16-bit Data Bus

All registers are 16-bit length.

Address A2 A1 A0	Symbol	Register Name	Contents
0 0 0	WR0	Command Register	• for setting command
0 0 1	WR1	Mode register 1	• for setting the valid / invalid of interrupt
0 1 0	WR2	Mode register 2	• for setting the logical levels and enable/disable of external decelerating stop • for setting the logical levels and enable/disable of servo motor signal • for setting the the limit signal mode and software limit mode
0 1 1	WR3	Mode register 3	• for setting the auto and manual deceleration • for setting the acceleration/deceleration mode (symmetry/non-symmetry, linear acceleration/deceleration, S-curve acceleration/deceleration) • for setting the drive pulse output mode and pins • for setting the encoder input signal mode and pins
1 0 0	WR4	Output register	• for setting the output values of general purpose input/output signals PIO7~0
1 0 1	Not used		
1 1 0	WR6	Data writing register 1	• for setting the low word 16-bit (D15-D0) for data writing
1 1 1	WR7	Data writing register 2	• for setting the high word 16-bit (D31-D16) for data writing

- The bits of WR1, WR2, WR3 and WR4 are cleared to 0 at reset.

■ Read Register in 16-bit Data Bus

All registers are 16-bit length.

Address A2 A1 A0	Symbol	Register Name	Contents
0 0 0	RR0	Main status register	• driving status, acceleration/deceleration status, increase/decrease status of acceleration/deceleration and error status • enable/disable of synchronous action set • status of timer and split pulse operation
0 0 1	RR1	Status register 1	• interrupt message
0 1 0	RR2	Status register 2	• error message • finishing status
0 1 1	RR3	Status register 3	• input signal status • automatic home search execution state
1 0 0	RR4	Status register 4	• multi-purpose register comparison result
1 0 1	RR5	PIO read register	• general purpose input/output signal status
1 1 0	RR6	Data reading register 1	• low word of data register (D15 ~ D0) for data reading
1 1 1	RR7	Data reading register 2	• high word of data register (D31 ~ D16) for data reading

4.2 Register Address by 8-bit Data Bus

In case of the 8-bit data bus access, the 16-bit data bus can be divided into high and low word byte. As shown in the table below, xxxxL is the low word byte (D7~D0) of 16-bit register xxxx, xxxxH is the high word byte (D15~8) of 16-bit register xxxx. For the command register (WR0L, WR0H), make sure to write to only the low word byte (WR0L). (except for command reset)

■ Write Register in 8-bit Data Bus

Address A3 A2 A1 A0	Write Register
0 0 0 0	WR0L
0 0 0 1	WR0H
0 0 1 0	WR1L
0 0 1 1	WR1H
0 1 0 0	WR2L
0 1 0 1	WR2H
0 1 1 0	WR3L
0 1 1 1	WR3H
1 0 0 0	WR4L
1 0 0 1	WR4H
1 0 1 0	Not used
1 0 1 1	Not used
1 1 0 0	WR6L
1 1 0 1	WR6H
1 1 1 0	WR7L
1 1 1 1	WR7H

■ Read Register in 8-bit Data Bus

Address A3 A2 A1 A0	Read Register
0 0 0 0	RR0L
0 0 0 1	RR0H
0 0 1 0	RR1L
0 0 1 1	RR1H
0 1 0 0	RR2L
0 1 0 1	RR2H
0 1 1 0	RR3L
0 1 1 1	RR3H
1 0 0 0	RR4L
1 0 0 1	RR4H
1 0 1 0	RR5L
1 0 1 1	RR5H
1 1 0 0	RR6L
1 1 0 1	RR6H
1 1 1 0	RR7L
1 1 1 1	RR7H

4.3 Command Register: WR0

Command register is used for command registration. Set 0 to the high word byte (H) and command code to the low word byte (L).

After command code has been written to this register, the command will be executed immediately. The data writing command such as a drive speed setting must be written to registers WR6 and WR7 first. Otherwise, when the reading command is engaged, the data will be written and set, through IC internal circuit, to registers RR6 and RR7.

When using the 8-bit data bus, the user should write data into only the low word byte (L) (except for a command reset). A command will be executed immediately after writing the the low word byte.

It requires 125 nSEC (maximum) to access the command code when CLK=16MHz. Please don't write the next command during the period of time.

WR0	D15	D14	D13	D12	H				D7	D6	D5	D4	L			
	0	0	0	0	0	0	0	0								
Command Code																

D7 ~ 0 Command code setting
Please refer to chapter 5 for further description of command codes.

4.4 Mode Register1: WR1

Mode register WR1 is used for setting each interrupt factor to enable/disable. Each bit is set: 1: enable, 0: disable.

WR1	D15	D14	D13	D12	H				D7	D6	D5	D4	L			
	SYNC3	SYNC2	SYNC1	SYNC0	SPLTE	SPLTP	TIMER	H-END	D-END	C-END	C-STA	D-STA	CMR3	CMR2	CMR1	CMR0
Interrupt Enable/Disable																

D3~0 CMR3~0 Interrupt generates when the comparison result of multi-purpose register MR3~0 with a comparative object changes to meet the comparison condition. Use multi-purpose register mode setting command (20h) to set the object which the user wants to compare with MR3~0 and comparison condition.

D4 D-STA Interrupt generates at the start of driving.

D5 C-STA Interrupt generates when pulse output starts at constant speed area in acceleration / deceleration driving.

D6 C-END Interrupt generates when pulse output is finished at constant speed area in acceleration / deceleration driving.

D7 D-END Interrupt generates when the driving is finished.

D8 H-END Interrupt generates when the automatic home search is finished.

D9 TIMER Interrupt generates when the timer expires.

D10 SPLTP Interrupt generates at the ↑ of a pulse in each split pulse. (When the split pulse logic is set to Hi pulse)

D11 SPLTE Interrupt generates when the split pulse is finished.

D15~12 SYNC3~0 Interrupt generates when synchronous action SYNC3~0 is activated.

D15~D0 will be set to 0 at reset.

4.5 Mode Register2: WR2

Mode register WR2 is used for setting: (1). input signal STOP2~STOP0 (decelerating stop / instant stop during the driving), (2). input signal for a servo motor, (3). external limit inputs, (4). software limit.

WR2	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	SLM-M	SLM-O	SLM-E	HLM-M	HLM-E	HLM-L	ALM-E	ALM-L	INP-E	INP-L	SP2-E	SP2-L	SP1-E	SP1-L	SP0-E	SP0-L

- D4, 2, 0 SPn-L** The bit for setting enable logical levels for driving stop input signal STOPn (n:2~0).
0: active on the Low level, 1: active on the Hi level
In automatic home search, the logical level of the STOPn signal that is used is set in these bits.
- D5, 3, 1 SPn-E** The bit for setting enable / disable of driving stop input signal STOPn (n:2~0).
0: disable, 1: enable
Once STOP2~STOP0 are active and then driving starts, when STOP signal becomes active level, the decelerating stop will be performed during acceleration / deceleration driving and the instant stop will be performed during constant speed driving.
In automatic home search, the enable / disable bits of STOPn that are used should be set to disable.
- D6 INP-L** Setting logical level of in-position input signal INPOS from a servo driver.
0: active on the Low level, 1: active on the Hi level
- D7 INP-E** Setting enable / disable of INPOS input signal.
0: disable, 1: enable
When it is enabled, the DRIVE bit of RR0 (main status) register does not return to 0 until INPOS signal is on its active level after the driving is finished.
- D8 ALM-L** Setting active level of servo alarm input signal ALARM.
0: active on the Low level, 1: active on the Hi level
- D9 ALM-E** Setting enable / disable of input signal ALARM.
0: disable, 1: enable
When it is enabled, MCX501 will check the input signal during the driving. And if it is active, D4 (ALARM) bit of RR2 register will become 1 and the driving will stop.
- D10 HLM-L** Setting logical level of hardware limit input signals LMTP, LMTM.
0: active on the Low level, 1: active on the Hi level
- D11 HLM-E** Setting enable / disable of LMTP, LMTM limit input signals.
0: disable, 1: enable
Once it is enabled, if LMTP limit input signal is active during the + direction driving, D2 (HLMTP+) bit of RR2 register will become 1 and if LMTM limit input signal is active during the - direction driving, D3 (HLMTP-) bit of RR2 register will become 1. When it becomes active level, driving stops.
- D12 HLM-M** The bit for controlling stop type when LMTP, LMTM limit input signals are active.
0: instant stop, 1: decelerating stop
When limit signal is used as the stop signal of an automatic home search, set to 1: decelerating stop.
- D13 SLM-E** Setting enable / disable of software limit function.
0: disable, 1: enable
Once it is enabled, if + direction software limit error occurs during the + direction driving, D0 (SLMT+) bit of RR2 register will become 1 and if - direction software limit error occurs during the - direction driving, D1 (SLMT-) bit of RR2 register will become 1.
 - If + direction software limit: comparative position counter $\geq$ SLMT+ value, then error and driving stops.
 - If - direction software limit: comparative position counter $<$ SLMT- value, then error and driving stops.
Driving commands for the direction in which software limit error occurs will not be executed.

- D14 SLM-0 Setting the object of software limit to real position counter or logical position counter.
0: logical position counter, 1: real position counter
- D15 SLM-M The bit for controlling stop type when software limit function is enabled.
0: decelerating stop, 1: instant stop
(Note that the bit 0/1 is opposite of the bit for controlling stop type of hardware limit signals.)

D15~D0 will be set to 0 at reset.

4.6 Mode Register3: WR3

Mode register WR3 is used for setting: (1). manual deceleration, (2). acceleration/deceleration mode (symmetry / non-symmetry, linear acceleration/deceleration, S-curve acceleration/deceleration), (3). drive pulse output mode, (4). encoder input mode, (5). limit signal pin inversion, (6). trapezoid triangle form prevention function, (7). repeat timer.

WR3	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	0	TMD	AVTR	LMINV	PIINV	PI-L	PMD1	PMD0	DPINV	DIR-L	DP-L	DPMD1	DPMD0	SACC	DSNDE	MANLD

- D0 MANLD Setting manual / automatic deceleration for fixed pulse acceleration / deceleration driving.
0: automatic deceleration, 1: manual deceleration
The decelerating point (DP) should be set if the manual deceleration mode is engaged.
- D1 DSNDE Setting decelerating rate which is in accordance with the rate of the acceleration (symmetry) or an individual decelerating rate (non-symmetry).
Set whether jerk (symmetry) or an individual deceleration increasing rate (non-symmetry) is used as a deceleration increasing rate at S-curve deceleration.
0: symmetry acceleration/deceleration, 1: non-symmetry acceleration/deceleration
Automatic deceleration cannot be performed for non-symmetrical S-curve acceleration / deceleration fixed pulse driving. In this case, the D0 (MANLD) bit must be set to 1 and a manual deceleration point (DP) must be set.
- D2 SACC Setting the speed curve to either linear driving or S-curve driving during acceleration/deceleration driving.
0: linear driving, 1: S-curve driving
Before S-curve driving is engaged, jerk (JK) (deceleration increasing rate (DJ)) must be set.
- D4, 3 DPMD1, 0 Setting pulse output type.

D4(DPMD1)	D3(DPMD0)	Pulse Output Type
0	0	Independent 2-pulse
0	1	1-pulse 1-direction
1	0	Quadrature pulse and quad edge evaluation
1	1	Quadrature pulse and double edge evaluation

When independent 2-pulse type is engaged, + direction pulses are output through the output signal PP, and – direction pulses through PM.

When 1-pulse 1-direction type is engaged, + and – directions pulses are output through the output signal PLS, and DIR is for direction signals.

[Note] Please refer to Chapter 9.2 for the output timing of pulse signal (PLS) and direction signal (DIR) when 1-pulse 1-direction type is engaged.

When quadrature pulse type is engaged, the A-phase signal of quadrature pulse is output through the output signal PA, and the B-phase signal of quadrature pulse through PB.

- D5 DP-L Setting logical level of driving pulses.
0: positive logical level, 1: negative logical level



D6 DIR-L Setting logical level of the direction (DIR) output signal for 1-pulse 1-direction mode DIR-L.

D6(DIR-L)	+ direction	– direction
0	Low	Hi
1	Hi	Low

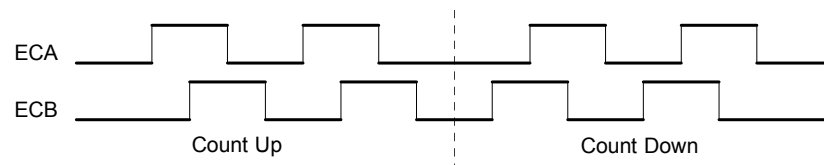
D7 DPINV Replaces output pins of drive pulse output between PP/PLS/PA signal and PM/DIR/PB signal.
0: initial setting, 1: pin inversion

When this bit is set to 1 and pulse output type is independent 2-pulse, drive pulses are output to the PM signal during the + direction driving and to the PP signal during the – direction driving. In the same way, output pins are replaced when in other pulse output types.

D9, 8 PIMD1, 0 Setting encoder pulse input type.
Real position counter counts Up/Down according to an encoder input signal.

D9(PIMD1)	D3(PIMD0)	Encoder pulse input type
0	0	Quadrature pulses input and quad edge evaluation
0	1	Quadrature pulses input and double edge evaluation
1	0	Quadrature pulses input and single edge evaluation
1	1	Up / Down pulse input

When quadrature pulses input type is engaged and ECA signal goes faster 90 degree phase than ECB signal does, it's "count up" and ECB signal goes faster 90 degree phase than ECA signal does, it's "count down". And when quad edge evaluation is set, it counts Up/Down at the rising edge (↑) and falling edge (↓) of both signals. When double edge evaluation is set, it counts Up/Down at the rising edge (↑) and falling edge (↓) of A-phase signals. When single edge evaluation is set, it counts Up at the rising edge (↑) of A-phase signals in the Low of B-phase signal, and it counts Down at the falling edge (↓) of A-phase signals in the Low of B-phase signal.



When Up / Down pulse input type is engaged, PPIN signal is for "count up" input, and PMIN signal is for "count down" input. So, it will count up when the positive pulses go up (↑).

D10 PI-L Setting logical level of an encoder input signal.
0: positive logical level, 1: negative logical level
When Up / Down pulse input type is engaged, it will count at the falling edge (↓) of the negative pulses.

D11 PI INV Replaces input pins of encoder pulse input between ECA/PPIN signal and ECB/PMIN signal.
0: initial setting, 1: pin inversion
This reverses the increase/decrease of the real position counter.

D11(PIINV)	Encoder pulse input type	Increase/decrease of real position counter (RP)
0	quadrature pulses input	Count UP when the A phase is advancing. Count DOWN when the B phase is advancing.
	Up / Down pulse input	Count UP at PPIN pulse input. Count DOWN at PMIN pulse input.
1	quadrature pulses input	Count UP when the B phase is advancing. Count DOWN when the A phase is advancing.
	Up / Down pulse input	Count UP at PMIN pulse input. Count DOWN at PPIN pulse input.

- D12 LMINV** Replaces input pins of hardware limit input signals between LMTP and LMTM.
0: initial setting, 1: pin inversion
When this bit is set to 1, LMTP signal is used as a limit signal for the – direction and LMTM signal is used as a limit signal for the + direction.
- D13 AVTRI** Setting enable / disable of triangle form prevention function in linear acceleration fixed pulse driving.
The triangle form prevention function is enabled at reset.
0: enable, 1: disable
- D14 TMMD** Setting once / repeat timer.
0: once, 1: repeat

D15~D0 will be set to 0 at reset. D15 should always be set to 0.

4.7 Output Register: WR4

This register is used for setting the general purpose input / output signals PIO7~0 as general purpose output. It is Low level output when the bit is set 0, and Hi level output when the bit is set 1.

WR4	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	0	0	0	0	0	0	0	0	PI07	PI06	PI05	PI04	PI03	PI02	PI01	PI00

D15~D0 will be set to 0 at reset. D15~D8 should always be set to 0.

4.8 Data Register: WR6/WR7

Data registers are used for setting the data of commands for writing data. The low-word data-writing 16-bit (WD15~WD0) is for register WR6 setting, and the high-word data-writing 16-bit (WD31~WD16) is for register WR7 setting.

WR6	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	WD15	WD14	WD13	WD12	WD11	WD10	WD9	WD8	WD7	WD6	WD5	WD4	WD3	WD2	WD1	WD0

WR7	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	WD31	WD30	WD29	WD28	WD27	WD26	WD25	WD24	WD23	WD22	WD21	WD20	WD19	WD18	WD17	WD16

The user can write command data with a designated data length into the write register. It does not matter to write WR6 or WR7 first (when 8-bit data bus is used, the registers are WR6L, WR6H, WR7L and WR7H).

The written data is binary and 2's complement is used for negative numbers.

For command data, the user should use designated data length.

The data of WR6 and WR7 registers are unknown at reset.

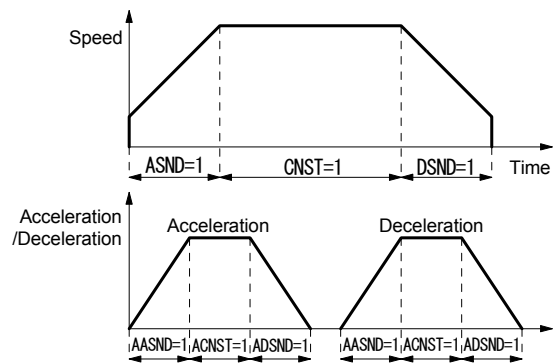
4.9 Main Status Register: RR0

Main status register RR0 is used for displaying: (1). driving and error status, (2). acceleration/deceleration status in acceleration/deceleration driving, (3). acceleration increasing/decreasing status in S-curve acceleration/deceleration, (4).

enable/disable of a synchronous action, (5). timer operating state, (6). split pulse operating state

RR0	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	0	0	SPLIT	TIMER	SYNC3	SYNC2	SYNC1	SYNC0	ADSND	ACNST	AASND	DSND	CNST	ASND	ERROR	DRIVE

- D0 DRIVE** Displaying driving status.
When the bit is 1, drive pulse is outputting. When the bit is 0, the driving is finished. While executing an automatic home search, this bit is set to 1. Once the in-position input signal INPOS for a servomotor is active, INPOS will return to 0 after the drive pulse output is finished.
- D1 ERROR** Displaying error status.
When one or more of D6 to D0 bits of RR2 register are 1, this bit will become 1.
This bit will return to 0 by the error/finishing status clear command or the start of next driving.
- D2 ASND** It becomes 1 when in acceleration.
- D3 CNST** It becomes 1 when in constant speed driving.
- D4 DSND** It becomes 1 when in deceleration.
- D5 AASND** In S-curve, it becomes 1 when acceleration / deceleration increases.
- D6 ACNST** In S-curve, it becomes 1 when acceleration / deceleration keeps constant.
- D7 ADSND** In S-curve, it becomes 1 when acceleration / deceleration decreases.
- D11~8 SYNC3~0** It becomes 1 when SYNC3~0 is active.
To enable a synchronous action, issue a synchronous action enable command (8F~81h). To disable a synchronous action, issue a synchronous action disable command (9F~91h).
- D12 TIMER** It becomes 1 when the timer is in operation.
- D13 SPLIT** It becomes 1 when the split pulse is in operation.



4.10 Status Register 1: RR1

Status register RR1 is used for displaying an interrupt factor. When an interrupt generates, the bit with the interrupt factor becomes 1. To generate an interrupt, interrupt Enable must be set for each factor in WR1 register.

RR1	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	SYNC3	SYNC2	SYNC1	SYNC0	SPLTE	SPLTP	TIMER	H-END	D-END	C-END	C-STA	D-STA	CMR3	CMR2	CMR1	CMR0
Interrupt Factor																

- D3~0 CMR3~0** Indicates that an interrupt generated when the comparison result of multi-purpose register MR3~0 with a comparative object changed to meet the comparison condition.
Use multi-purpose register mode setting command (20h) to set the object which the user wants to compare with MR3~0 and comparison condition.
- D4 D-STA** Indicates that an interrupt generated at the start of driving.
- D5 C-STA** Indicates that an interrupt generated when pulse output started at constant speed area in acceleration /

deceleration driving.

D6	C-END	Indicates that an interrupt generated when pulse output was finished at constant speed area in acceleration / deceleration driving.
D7	D-END	Indicates that an interrupt generated when the driving was finished.
D8	H-END	Indicates that an interrupt generated when the automatic home search was finished.
D9	TIMER	Indicates that an interrupt generated when the timer expired.
D10	SPLTP	Indicates that an interrupt generated at the $\uparrow$ of a pulse in each split pulse. (When the split pulse logic is set to Hi pulse)
D11	SPLTE	Indicates that an interrupt generated when the split pulse was finished.
D15~12	SYNC3~0	Indicates that an interrupt generated when synchronous action SYNC3~0 was activated.

When one of the interrupt factors generates an interrupt, the bit of the register becomes 1, and the interrupt output signal (INTN) will become the Low level. If the host CPU reads RR1 register, the bit of RR1 will be cleared to 0 and the interrupt signal will return to the non-active level.

[Note] In 8-bit data bus, RR1L will be cleared by reading of RR1L register and RR1H will be cleared by reading of RR1H register. RR1H will never be cleared by RR1L register and RR1L will never be cleared by RR1H register.

4.11 Status Register 2: RR2

Status register RR2 is used for displaying the error information and the status of driving finishing. When an error occurs during the driving, the error information bit (one of D6 to D0) is set to 1. When one or more of D6 to D0 bits of RR2 register are 1, ERROR bit of main status register RR0 becomes 1.

When one or more of D6 to D0 bits of RR2 register are 1, the bits keep 1 even though the factor of the error or driving finishing is cleared. All bits will return to 0 by error/finishing status clear command (79h) or the start of next driving.

RR2	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	EMG	ALARM	LMT-	LMT+	STOP2	STOP1	STOP0	SYNC	0	HOME	EMG	ALARM	HLMT-	HLMT+	SLMT-	SLMT+
	Status of Driving Finishing								Error Information							

D0	SLMT+	During the + direction driving with software limit function enabled, when comparative position counter $\geq$ SLMT+ value, it becomes 1 and driving stops.
D1	SLMT-	During the - direction driving with software limit function enabled, when comparative position counter $<$ SLMT- value, it becomes 1 and driving stops.
D2	HLMT+	During the + direction driving with hardware limit signal enabled, when limit signal (LMTP) is on its active level, it becomes 1 and driving stops.
D3	HLMT-	During the - direction driving with hardware limit signal enabled, when limit signal (LMTM) is on its active level, it becomes 1 and driving stops.
D4	ALARM	During the driving with input signal for servo driver alarm enabled, when the alarm signal (ALARM) is on its active level, it becomes 1 and driving stops.
D5	EMG	During the driving, when emergency stop signal (EMGN) becomes Low level, it becomes 1 and driving stops.

D6	HOME	Error occurred at execution of an automatic home search. When the encoder Z-phase signal (STOP2) is already active at the start of Step 3, this bit is set to 1.
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In driving, when hardware / software limit becomes active, the decelerating stop or instant stop is executed. Unless the stop factor of driving is cleared, a driving command is not executed and an error occurs again even if a driving command in the same direction is issued.

The error information bits will not become 1 even if each factor is active during the stop of driving.

About software / hardware limit, an error does not occur even if each factor becomes active in the reverse direction driving.

D8	SYNC	If the driving is stopped by one of synchronous actions (SYNC3 ~ 0), it will become 1.
D11~9	STOP2~0	If the driving is stopped by one of external stop signals (STOP2 ~ 0), it will become 1.
D12	LMT+	If the driving is stopped by +direction limit signal (LMTP), it will become 1.
D13	LMT-	If the driving is stopped by -direction limit signal (LMTM), it will become 1.
D14	ALARM	If the driving is stopped by ALARM from a servo driver, it will become 1.
D15	EMG	If the driving is stopped by external emergency signal (EMGN), it will become 1.

Driving finishing status (D15~D8) is the bit indicates the finishing factor of driving. There are 3 factors that terminate driving as shown below other than the factors that the status of driving finishing (D15~D8) indicate.

- when all the drive pulses are output in fixed pulse driving,
- when deceleration stop or instant stop command is written,
- when software limit is enabled, and is active,

Make sure to check the status of driving finishing (D15~D8) after confirming the driving is finished by the DRIVE bit of RR0 main status register

4.12 Status Register 3: RR3

Status register RR3 is used for displaying the input signal status and automatic home search execution state.

The input signal status bit of each signal is 0 if the input is on the Low level and 1 if the input is on the Hi level. When the functions of D8~D0 input signals are not used, they can be used as general purpose input signals.

In the description below, the number in brackets after signal name indicates the pin number.

RR3	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	EMGN	HSST5	HSST4	HSST3	HSST2	HSST1	HSST0	LMTM	LMTP	ALARM	INPOS	ECB	ECA	STOP2	STOP1	STOP0
	Input signal status				Automatic Home Search Execution State				Input signal status							

D2~0 STOP2~0 Displaying the input status of external stop signals STOP2(39), STOP1(40), STOP0(42).

D3 ECA Displaying the input status of encoder input pulse signal ECA/PPIN(37).
The pin number for this bit does not change even though the pin inversion of encoder pulse input (WR3/D11:PIINV) is set.

D4 ECB Displaying the input status of encoder input pulse signal ECB/PMIN(38).
The pin number for this bit does not change even though the pin inversion of encoder pulse input (WR3/D11:PIINV) is set.

D5 INPOS Displaying the input status of in-position input signal for a servomotor INPOS(48).

- D6 ALARM Displaying the input status of servo alarm input signal ALARM (49).
- D7 LMTP Displaying the input status of hardware limit input signal LMTP (43).
The pin number for this bit does not change even though the pin inversion of hardware limit input (WR3/D12:LMINV) is set.
- D8 LMTM Displaying the input status of hardware limit input signal LMTM (44).
The pin number for this bit does not change even though the pin inversion of hardware limit input (WR3/D12:LMINV) is set.
- D14~9 HSST5~0 The home search execution state indicates the operation currently executed while the automatic home search is performed. See Chapter 2.5.5.
- D15 EMGN Displaying the input status of emergency stop signal EMGN (60).

4.13 Status Register 4: RR4

Status register RR4 is used for displaying the comparison result of a multi-purpose register with a comparative object. The comparative object can be set by multi-purpose register mode setting command (20h).

RR4	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	0	0	0	0	0	0	0	0	$P=MR3$	$P\geq MR3$	$P=MR2$	$P\geq MR2$	$P=MR1$	$P\geq MR1$	$P=MR0$	$P\geq MR0$

D6, 4, 2, 0 $P \geq MRn$ If comparative object $\geq MRn$, then it becomes 1. (n: 3~0)

D7, 5, 3, 1 $P = MRn$ If comparative object $= MRn$, then it becomes 1. (n: 3~0)

$P = MRn(D7, 5, 3, 1)$	$P \geq MRn(D6, 4, 2, 0)$	Comparison result with MRn
0	1	comparative object $> MRn$
x	1	comparative object $\geq MRn$
1	x	comparative object $= MRn$
x	0	comparative object $< MRn$

4.14 PIO Read Register: RR5

PIO read register RR5 is used for displaying the signal status of general purpose input / output signals PIO7~0 and general purpose input signals PIN7~0. The bit is 0 if the signal is on the Low level; the bit is 1 if the signal is on the Hi level.

RR5	H								L							
	D15	D14	D13	D12	D11	D10	D9	D8	D7	D6	D5	D4	D3	D2	D1	D0
	PIN7	PIN6	PIN5	PIN4	PIN3	PIN2	PIN1	PIN0	PI07	PI06	PI05	PI04	PI03	PI02	PI01	PI00

D7~0 PI07~0 Displaying the status of general purpose input / output signals PIO7~0.
When PIO7~0 signals are set as input, it indicates the input state and when set as output, it indicates the output state.

D15~8 PIN7~0 Displaying the status of general purpose input signals PIN7~0.
In 8-bit data bus mode (H16L8=Low), the high word D15~D8 which are not used for the data bus, can be used as general purpose input PIN7~0.
In 16-bit data bus mode, these bits are 0.

4.15 Data-Read Register: RR6 / RR7

According to the data-read command, the data of internal registers will be set into registers RR6 and RR7. The low word 16 bits (RD15 ~ RD0) is set in RR6 register, and the high word 16 bits (RD31 ~ RD16) is set in RR7 register for data reading.

RR6	D15	D14	D13	D12	H				D11	D10	D9	D8	D7	D6	D5	D4	L				D3	D2	D1	D0
	RD15	RD14	RD13	RD12	RD11	RD10	RD9	RD8	RD7	RD6	RD5	RD4	RD3	RD2	RD1	RD0								

RR7	D15	D14	D13	D12	H				D11	D10	D9	D8	D7	D6	D5	D4	L				D3	D2	D1	D0
	RD31	RD30	RD29	RD28	RD27	RD26	RD25	RD24	RD23	RD22	RD21	RD20	RD19	RD18	RD17	RD16								

The data is binary and 2's complement is used for negative numbers.

5. Commands

5.1 Command Lists

■ Commands for Writing Data

Code	Command	Symbol	Data Range	Data Length (byte)
0 0 h	Jerk setting (Acceleration increasing rate)	J K	1 ~ 1, 073, 741, 823 [pps/sec ²]	4
0 1	Deceleration increasing rate setting	D J	1 ~ 1, 073, 741, 823 [pps/sec ²]	4
0 2	Acceleration setting	A C	1 ~ 536, 870, 911 [pps/sec]	4
0 3	Deceleration setting	D C	1 ~ 536, 870, 911 [pps/sec]	4
0 4	Initial speed setting	S V	1 ~ 8, 000, 000 [pps]	4
0 5	Drive speed setting	D V	1 ~ 8, 000, 000 [pps]	4
0 6	Drive pulse number / Finish point setting	T P	-2, 147, 483, 646 ~ +2, 147, 483, 646	4
0 7	Manual deceleration point setting	D P	0 ~ 4, 294, 967, 292	4
0 9	Logical position counter setting	L P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
0 A	Real position counter setting	R P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
0 B	Software limit + setting	S P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
0 C	Software limit - setting	S M	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
0 D	Acceleration counter offsetting	A O	-32, 768 ~ +32, 767	2
0 E	Logical position counter maximum value setting	L X	1 ~ 2, 147, 483, 647 (7FFF FFFFh) 0r FFFF FFFFh	4
0 F	Real position counter maximum value setting	R X	1 ~ 2, 147, 483, 647 (7FFF FFFFh) 0r FFFF FFFFh	4
1 0	Multi-purpose register 0 setting	M R 0	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
1 1	Multi-purpose register 1 setting	M R 1	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
1 2	Multi-purpose register 2 setting	M R 2	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
1 3	Multi-purpose register 3 setting	M R 3	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
1 4	Home search speed setting	H V	1 ~ 8, 000, 000 [pps]	4
1 5	Speed increasing / decreasing value setting	I V	1 ~ 1, 000, 000 [pps]	4
1 6	Timer value setting	T M	1 ~ 2, 147, 483, 647 [μ sec]	4
1 7	Split pulse setting 1	S P 1	Split length : 2 ~ 65, 535 Pulse width : 1 ~ 65, 534	4
1 8	Split pulse setting 2	S P 2	Split pulse number : 0 ~ 65, 535	2

[Note]

- When those parameters are written, the total data length should be completely filled.
- The units described in speed parameters and the timer value are only applied to when input clock (CLK) is 16MHz. When input clock (CLK) is other than 16MHz, please see Appendix B for parameter calculation formula.

■ Commands for Writing Mode

Code	Command	Symbol	Data Length (byte)
2 0 h	Multi-purpose register mode setting	M R M	2
2 1	PIO signal setting 1	P 1 M	2
2 2	PIO signal setting 2 · Other settings	P 2 M	2
2 3	Automatic home search mode setting 1	H 1 M	2
2 4	Automatic home search mode setting 2	H 2 M	2
2 5	Input signal filter mode setting	F L M	2
2 6	Synchronous action SYNC0 setting	S 0 M	2
2 7	Synchronous action SYNC1 setting	S 1 M	2
2 8	Synchronous action SYNC2 setting	S 2 M	2
2 9	Synchronous action SYNC3 setting	S 3 M	2

[Note] When those parameters are written, the total data length should be completely filled.

■ Commands for Reading Data

Code	Command	Symbol	Data Range	Data Length (byte)
3 0 h	Logical position counter reading	L P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
3 1	Real position counter reading	R P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
3 2	Current drive speed reading	C V	0 ~ 8, 000, 000 [pps]	4
3 3	Current acceleration / deceleration reading	C A	0 ~ 536, 870, 911 [pps/sec]	4
3 4	Multi-purpose register 0 reading	M R 0	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
3 5	Multi-purpose register 1 reading	M R 1	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
3 6	Multi-purpose register 2 reading	M R 2	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
3 7	Multi-purpose register 3 reading	M R 3	-2, 147, 483, 648 ~ +2, 147, 483, 647	4
3 8	Current timer value reading	C T	0 ~ 2, 147, 483, 647 [μ sec]	4
3 D	WR1 setting value reading	W R 1	(bit data)	2
3 E	WR2 setting value reading	W R 2	(bit data)	2
3 F	WR3 setting value reading	W R 3	(bit data)	2
4 0	Multi-purpose register mode setting reading	M R M	(bit data)	2
4 1	PIO signal setting 1 reading	P 1 M	(bit data)	2
4 2	PIO signal setting 2 · Other settings reading	P 2 M	(bit data)	2
4 3	Acceleration setting value reading	A C	1 ~ 536, 870, 911 [pps/sec]	4
4 4	Initial speed setting value reading	S V	1 ~ 8, 000, 000 [pps]	4
4 5	Drive speed setting value reading	D V	1 ~ 8, 000, 000 [pps]	4
4 6	Drive pulse number / Finish point setting value reading	T P	-2, 147, 483, 646 ~ +2, 147, 483, 646	4
4 7	Split pulse setting 1 reading	S P 1	Split length : 2 ~ 65, 535 Pulse width : 1 ~ 65, 534	4

■ Driving Commands

Code	Command
5 0 h	Relative position driving
5 1	Counter relative position driving
5 2	+ Direction continuous pulse driving
5 3	- Direction continuous pulse driving
5 4	Absolute position driving
5 6	Decelerating stop
5 7	Instant stop
5 8	Direction signal + setting
5 9	Direction signal - setting
5 A	Automatic home search execution

■ Synchronous Action Operation Commands

Code	Command
8 1 ~ 8 F h	Synchronous action enable setting
9 1 ~ 9 F	Synchronous action disable setting
A 1 ~ A F	Synchronous action activation

■ Other Commands

Code	Command
7 0 h	Speed increase
7 1	Speed decrease
7 2	Deviation counter clear output
7 3	Timer-start
7 4	Timer-stop
7 5	Start of split pulse
7 6	Termination of split pulse
7 9	Error / Finishing status clear
1 F	NOP
0 0 F F	Command reset

[Note] Please do not write the codes not mentioned above. The unknown situation could happen due to IC internal circuit test.

5.2 Commands for Writing Data

Commands for writing data is used for setting driving parameters such as acceleration, drive speed, drive pulse number...

If the data length is 2 bytes, WR6 register can be used. If the data is 4 bytes, the high word data can be written into register WR7 and the low word into register WR6. Then, the command code will be written into register WR0 for execution.

Writing data for registers WR6 and WR7 is binary and 2's complement is used for negative numbers. Each data should be set within the permitted data range. If the setting data is out of range, operation cannot be done correctly.

[Note]

a. It requires 125 nSEC (maximum) to access the command code when CLK=16MHz. Please do not write the next command or data during the period of time.

b. Except acceleration offset (AO), logical position counter maximum value (LX), real position counter maximum value (RX) and other parameters are unknown at reset. So, please per-set proper values for those driving related parameters before the driving starts.

c. The unit described in each speed parameter and timer value is for when input clock (CLK) is 16MHz. Please see Appendix B for parameter calculation formula when input clock (CLK) is other than 16MHz.

5.2.1 Jerk Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 0h	Jerk setting	J K	1 ~ 1, 073, 741, 823	4

A jerk setting value is a parameter that determines the acceleration increasing / decreasing rate per unit in S-curve acceleration/deceleration. The unit of the setting value is pps/sec².

$$\text{Jerk} = JK [\text{pps/sec}^2]$$

In S-curve acceleration/deceleration driving (WR3/D1=0) where acceleration and deceleration are symmetrical, this jerk is also used at deceleration.

5.2.2 Deceleration Increasing Rate Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 1h	Deceleration Increasing Rate Setting	D J	1 ~ 1, 073, 741, 823	4

This deceleration increasing rate value is a parameter used to determine a deceleration speed increase/decrease rate per unit time in S-curve acceleration/deceleration driving (WR3/D1= 1) where acceleration and deceleration are non-symmetrical. The unit of the setting value is pps/sec².

$$\text{Deceleration Increasing Rate} = DJ [\text{pps/sec}^2]$$

In S-curve acceleration/deceleration driving (WR3/D1=0) where acceleration and deceleration are symmetrical, the deceleration increasing rate value is not used.

5.2.3 Acceleration Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 2 h	Acceleration setting	A C	1 ~ 536,870,911	4

An acceleration setting value is a parameter that determines acceleration in linear acceleration/deceleration driving. The unit of the setting value is pps/sec.

$$\text{Acceleration} = \text{AC} [\text{pps/sec}]$$

In linear acceleration/deceleration driving (WR3/D1=0) where acceleration and deceleration are symmetrical, this acceleration setting value is also used at deceleration.

For S-curve acceleration/deceleration driving, set the maximum value of 536,870,911 (1FFF FFFFh) to this parameter.

For Partial S-curve acceleration/deceleration driving, set the acceleration at linear acceleration part to this parameter.

In Partial S-curve acceleration/deceleration driving (WR3/D1=0) where acceleration and deceleration are symmetrical, this acceleration setting value is also used at deceleration.

The value of current acceleration can be read by current acceleration / deceleration reading command (33h).

An acceleration setting value can be read by acceleration setting value reading command (43h).

5.2.4 Deceleration Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 3 h	Deceleration setting	D C	1 ~ 536,870,911	4

This parameter is used to set a deceleration speed at deceleration in non-symmetrical linear acceleration/deceleration driving (WR3/D1=1). The unit of the setting value is pps/sec.

$$\text{Deceleration} = \text{DC} [\text{pps/sec}]$$

In non-symmetrical S-curve acceleration/deceleration driving, set the maximum value of 536,870,911 (1FFF FFFFh) to this parameter.

In non-symmetrical Partial S-curve acceleration/deceleration driving, set the deceleration at linear deceleration part to this parameter.

5.2.5 Initial Speed Setting

Code	Command	Symbol	Data Range	Data Length (byte)
O 4 h	Initial speed setting	S V	1 ~ 8,000,000	4

“SV” is the parameter determining the initial speed for the start of acceleration and the termination of deceleration. The unit of the setting value is pps.

$$\text{Initial Speed} = \text{SV [pps]}$$

For a stepper motor, the user should set the initial speed smaller than the self-starting frequency of a stepper motor. If there is the mechanical resonance frequency, set the initial speed to avoid it.

In fixed pulse driving, if the value which is too low is set to initial speed, premature termination or creep pulses may occur.

- In linear acceleration/deceleration driving, set the value more than square root of an acceleration setting value.
- In S-curve acceleration/deceleration driving, set the value more than 1/10 times the square root of a jerk setting value.
- In Partial S-curve acceleration/deceleration driving, set the value more than square root of an acceleration setting value.

Linear acceleration/deceleration driving $\text{SV} \geq \sqrt{\text{AC}}$, S-curve acceleration/deceleration driving $\text{SV} \geq \sqrt{\text{JK}} \times 1/10$,

Partial S-curve acceleration/deceleration driving $\text{SV} \geq \sqrt{\text{AC}}$

An initial speed setting value can be read by initial speed setting value reading command (44h).

5.2.6 Drive Speed Setting

Code	Command	Symbol	Data Range	Data Length (byte)
O 5 h	Drive speed setting	D V	1 ~ 8,000,000	4

“DV” is the parameter determining the speed of constant speed period in trapezoidal driving. In constant speed driving, the drive speed is the initial speed. The unit of the setting value is pps.

$$\text{Drive speed} = \text{DV [pps]}$$

If the drive speed is set a lower value than the initial speed, the acceleration / deceleration will not be performed, and the driving is constant speed. If the user wants to perform instant stop immediately after the signal is detected during such as the encoder Z-phase search (at a low-speed driving), the drive speed must be set lower than the initial speed.

A drive speed can be altered during the driving. When the drive speed of next constant speed period is newly set, the acceleration or deceleration is performed to reach the new setting speed, then a constant speed driving starts.

In automatic home search, this drive speed is used for high-speed search speed of Step 1 and high-speed drive speed of Step 4.

[Note]

- In fixed pulse S-curve acceleration / deceleration driving (when in auto deceleration mode) or in fixed pulse non-symmetrical linear acceleration / deceleration driving (when in auto deceleration mode), there is no way to change the drive speed during the driving.
- In continuous S-curve acceleration / deceleration driving, the drive speed can be changed in the constant speed period during the driving, but changing the drive speed during the acceleration / deceleration will be disabled.
- In fixed pulse symmetrical trapezoidal driving, the drive speed can be changed during the driving, however the frequent changes of drive speed may generate premature termination or creep.

The value of current drive speed during the driving can be read by current drive speed reading command (32h).
A drive speed setting value can be read by drive speed setting value reading command (45h).

5.2.7 Drive pulse number / Finish point setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 6 h	Drive pulse number / finish point setting	T P	-2, 147, 483, 646 ~ +2, 147, 483, 646	4

“TP” is the parameter setting the drive pulse number from the current position for relative position driving. When the positive pulse number is set in the drive pulse number, a drive direction is toward +direction, and when the negative pulse number is set, a drive direction is toward –direction.

In counter relative position driving, when the positive pulse number is set in the drive pulse number, a drive direction is toward –direction.

In absolute position driving, the destination point based on a home (logical position counter = 0) should be set with a signed 32-bit value.

Drive pulse number can be changed during relative position driving or counter relative position driving. However, it cannot be set to a different drive direction. Please note that if it is set to the position already passed, driving will stop immediately.
The finish point cannot be changed during absolute position driving.

5.2.8 Manual Decelerating Point Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 7 h	Manual decelerating point setting	D P	0 ~ 4, 294, 967, 292	4

“DP” is the parameter setting the manual deceleration point in fixed pulse acceleration / deceleration driving when the manual deceleration mode (WR3/D0=1) is engaged. As a manual decelerating point, set the value which subtracts pulse number to be used at deceleration from output pulse number in fixed pulse driving.

$$\text{Manual Decelerating Point} = \text{Output Pulse Number} - \text{Pulse Number for Deceleration}$$

<About output pulse number>

Output pulse number indicates the number of pulses which is actually output in fixed pulse driving.

In relative position driving, output pulse number P is the absolute value of drive pulse number setting value TP.

In absolute position driving, output pulse number P is the absolute value which reduces logical position counter value LP of before driving starts from drive pulse number setting value TP.

$$\begin{aligned} \text{Relative Position Driving} &: \text{Output Pulse Number } P = |TP| \\ \text{Absolute Position Driving} &: \text{Output Pulse Number } P = |TP - LP| \end{aligned}$$

5.2.9 Logical Position Counter Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 9h	Logical position counter setting	L P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“LP” is the parameter setting the value of logical position counter.

Logical position counter counts Up / Down according to the +/- direction pulse output.

A logical position counter setting value can be written anytime, and read by logical position counter reading command (30h) anytime.

5.2.10 Real Position Counter Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 Ah	Real position counter setting	R P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“RP” is the parameter setting the value of real position counter.

Real position counter counts Up / Down according to encoder input pulse.

A real position counter setting value can be written anytime, and read by real position counter reading command (31h) anytime.

5.2.11 Software Limit + Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 Bh	Software limit + setting	S P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“SP” is the parameter setting the value of + direction software limit SLMT+ register.

Enable / disable, an object to set, and stop mode of software limit can be set by WR2 register.

A software limit SLMT+ register setting value can be written anytime.

5.2.12 Software Limit – Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 Ch	Software limit – setting	S M	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“SM” is the parameter setting the value of – direction software limit SLMT– register.

Enable / disable, an object to set, and stop mode of software limit can be set by WR2 register.

A software limit SLMT– register setting value can be written anytime.

5.2.13 Acceleration Counter Offsetting

Code	Command	Symbol	Data Range	Data Length (byte)
0 Dh	Acceleration Counter Offsetting	A O	-32, 768 ~ +32, 767	2

“AO” is the parameter executing acceleration counter offset.

The offset value of acceleration counter will be set to 0 at reset. There is usually no need to change it.

See section C. in 2.1 for details of acceleration counter offset.

The data length of this writing command is 2 bytes. The setting value should only be written in WR6 register.

5.2.14 Logical Position Counter Maximum Value Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 Eh	Logical position counter maximum value setting	L X	1 ~ 2, 147, 483, 647 (7FFF FFFFh) 0r FFFF FFFFh	4

“LX” is the parameter setting the logical position counter maximum value with positive value for the variable ring function of logical position counter.

The value at reset is FFFF FFFFh. When the variable ring function is not used, the value should be default.

5.2.15 Real Position Counter Maximum Value Setting

Code	Command	Symbol	Data Range	Data Length (byte)
0 Fh	Real position counter maximum value setting	R X	1 ~ 2, 147, 483, 647 (7FFF FFFFh) 0r FFFF FFFFh	4

“RX” is the parameter setting the real position counter maximum value with positive value for the variable ring function of real position counter.

The value at reset is FFFF FFFFh. When the variable ring function is not used, the value should be default.

5.2.16 Multi-Purpose Register 0 Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 0h	Multi-purpose register 0 setting	M R 0	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“MR0” is the parameter setting the value of multi-purpose register 0.

Multi-purpose register is used for comparison of position, speed, timer value and large or small, and load / save of each parameter by a synchronous action. Comparison result is used for comparative signal output, synchronous action activation and generating an interrupt.

A multi-purpose register MR0 setting value can be written anytime, and read by multi-purpose register 0 reading command (34h) anytime.

5.2.17 Multi-Purpose Register 1 Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 1 h	Multi-purpose register 1 setting	M R 1	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“MR1” is the parameter setting the value of multi-purpose register 1.

Multi-purpose register is used for comparison of position, speed, timer value and large or small, and load / save of each parameter by a synchronous action. Comparison result is used for outputting of comparison output signal, synchronous action activation and generating an interrupt.

A multi-purpose register MR1 setting value can be written anytime, and read by multi-purpose register 1 reading command (35h) anytime.

5.2.18 Multi-Purpose Register 2 Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 2 h	Multi-purpose register 2 setting	M R 2	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“MR2” is the parameter setting the value of multi-purpose register 2.

Multi-purpose register is used for comparison of position, speed, timer value and large or small, and load / save of each parameter by a synchronous action. Comparison result is used for outputting of comparison output signal, synchronous action activation and generating an interrupt.

A multi-purpose register MR2 setting value can be written anytime, and read by multi-purpose register 2 reading command (36h) anytime.

5.2.19 Multi-Purpose Register 3 Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 3 h	Multi-purpose register 3 setting	M R 3	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

“MR3” is the parameter setting the value of multi-purpose register 3.

Multi-purpose register is used for comparison of position, speed, timer value and large or small, and load / save of each parameter by a synchronous action. Comparison result is used for outputting of comparison output signal, synchronous action activation and generating an interrupt.

A multi-purpose register MR3 setting value can be written anytime, and read by multi-purpose register 3 reading command (37h) anytime.

5.2.20 Home Search Speed Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 4 h	Home search speed setting	H V	1 ~ 8, 000, 000	4

“HV” is the parameter setting the low-speed home search speed that is applied in Steps 2 and 3.
The unit of the setting value is pps.

$$\text{Home Search Speed} = \text{HV} [\text{pps}]$$

Set a value lower than the initial speed (SV) to stop driving immediately when a search signal becomes active.

See Chapter 2.5 for details of automatic home search.

5.2.21 Speed Increasing / Decreasing Value Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 5 h	Speed increasing / decreasing value setting	I V	1 ~ 1, 000, 000	4

“IV” is the parameter setting the value to increase / decrease the current drive speed by speed increase command (70h) and speed decrease command (71h) during the driving. The unit of the setting value is pps.

$$\text{Speed Increasing / Decreasing Value} = \text{IV} [\text{pps}]$$

In acceleration / deceleration driving, once the speed increase / decrease command of next constant speed period is issued, acceleration / deceleration is performed until it reaches the drive speed increased / decreased by the speed increasing /decreasing value setting, and then constant speed driving will start.

5.2.22 Timer Value Setting

Code	Command	Symbol	Data Range	Data Length (byte)
1 6 h	Timer value setting	T M	1 ~ 2, 147, 483, 647	4

“TM” is the parameter setting the time that a timer is up. The unit of the setting value is μsec .

$$\text{Timer Value} = \text{TM} [\mu\text{sec}]$$

The current timer value during the timer operation can be read by current timer value reading command (32h).

5.2.23 Split Pulse Setting 1

Code	Command	Symbol	Data Range		Data Length (byte)
1 7 h	Split pulse setting 1	S P 1	WR6	Split length : 2 ~ 65,535	4
			WR7	Pulse width : 1 ~ 65,534	

“SP1” is the parameter setting a split length and pulse width of a split pulse.

The unit of split length and pulse width is drive pulse. Set a split length to WR6 and pulse width to WR7.

Split length and pulse width can be altered during output of split pulse. When split length and pulse width are newly set, output of split pulse will continue at the new settings.

This data length is 4 bytes, so even if only one of split length and pulse width is altered, the appropriate data should be set in both WR6 and WR7 registers.

The value of split pulse setting 1 (SP1) can be read by split pulse setting 1 reading command (47h).

5.2.24 Split Pulse Setting 2

Code	Command	Symbol	Data Range	Data Length (byte)
1 8 h	Split pulse setting 2	S P 2	Split pulse number : 0, 1 ~ 65,535	2

“SP2” is the parameter setting the split pulse number to output. When the split pulse number is set to 0, it continues to output split pulses until the output of split pulse is stopped by a command or synchronous action.

The split pulse number can be altered during output of split pulse.

This data length is 2 bytes, the setting data should be written in WR6 register.

5.3 Commands for Writing Mode

Commands for writing mode is used for setting driving parameters such as multi-purpose register, automatic home search, synchronous action...

The data length of commands for writing mode is all 2 bytes. Set an appropriate value in each bit of WR6 register and write a command code in WR0 register. As a result, the data of WR6 register will be set in each mode setting register in the IC.

At reset, all the bits of each mode setting register in the IC are cleared to 0.

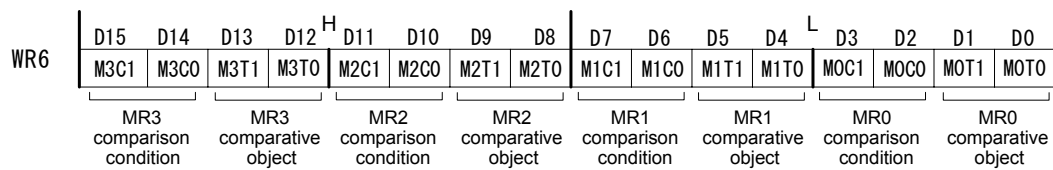
[Note]

- It requires 125 nSEC (maximum) to access the command code when CLK=16MHz. Please don't write the next command or data during the period of time.

5.3.1 Multi-Purpose Register Mode Setting

Code	Command	Symbol	Data Length (byte)
2 0 h	Multi-purpose register mode setting	MRM	2

“MRM” is the parameter setting the comparative object with multi-purpose register MR3~0 and the comparison condition. The user can set the comparative object and comparison condition for each MR3~0 individually. Comparison result can be used for comparative signal output, the factor of synchronous action activation and an interrupt.



D1, 0 M0T1, 0 Setting the comparative object with MR0.

D3, 2 M0C1, 0 Setting the comparison condition with MR0.

D5, 4 M1T1, 0 Setting the comparative object with MR1.

D7, 6 M1C1, 0 Setting the comparison condition with MR1.

D9, 8 M2T1, 0 Setting the comparative object with MR2.

D11, 10 M2C1, 0 Setting the comparison condition with MR2.

D13, 12 M3T1, 0 Setting the comparative object with MR3.

D15, 14 M3C1, 0 Setting the comparison condition with MR3.

(n:0~3)

MnT1 bit	MnT0 bit	MRn comparative object
0	0	Logical position counter (LP)
0	1	Real position counter (RP)
1	0	Current drive speed value (CV)
1	1	Current timer value (CT)

(n:0~3)

MnC1 bit	MnC0 bit	MRn comparative object
0	0	comparative object $\geq$ MRn
0	1	comparative object $>$ MRn
1	0	comparative object $=$ MRn
1	1	comparative object $<$ MRn

Regardless of the comparison condition (MnC1, 0 bits) set by multi-purpose register mode setting, the comparison result of large or small the MR3~0 with each comparative object can be checked by RR4 register.

See Chapter 2.4 for details of multi-purpose register.

[Note]

When the comparative object is set to “current drive speed value (CV)” and comparison condition is set to “comparative object = MRn”, if the acceleration/deceleration exceeds 4,194,304 (400000h) pps/sec in acceleration/deceleration driving, the comparison result may not become active.

When the comparative object is “current drive speed value (CV)” and the acceleration/deceleration is more than this value, set the other conditions such as “comparative object $\geq$ MRn” and not “comparative object = MRn”.

D15~D0 will be set to 0 at reset.

5.3.2 PIO Signal Setting 1

Code	Command	Symbol	Data Length (byte)
2 1 h	PIO signal setting 1	P 1 M	2

“P1M” is the parameter setting the function of PIO7~0 signals. PIO7~0 signals can be used for the general purpose input / output signals, synchronous input signals, synchronous pulse output signals, drive status output signals, MRn comparison output signals and driving by external signals.

WR6	D15	D14	D13	D12 ^H	D11	D10	D9	D8	D7	D6	D5	D4 ^L	D3	D2	D1	D0
	P7M1	P7M0	P6M1	P6M0	P5M1	P5M0	P4M1	P4M0	P3M1	P3M0	P2M1	P2M0	P1M1	P1M0	P0M1	P0M0
	PIO7 signal		PIO6 signal		PIO5 signal		PIO4 signal		PIO3 signal		PIO2 signal		PIO1 signal		PIO0 signal	

D1, 0	P0M1, 0	Setting the PIO0 signal function.
D3, 2	P1M1, 0	Setting the PIO1 signal function.
D5, 4	P2M1, 0	Setting the PIO2 signal function.
D7, 6	P3M1, 0	Setting the PIO3 signal function.
D9, 8	P4M1, 0	Setting the PIO4 signal function.
D11, 10	P5M1, 0	Setting the PIO5 signal function.
D13, 12	P6M1, 0	Setting the PIO6 signal function.
D15, 14	P7M1, 0	Setting the PIO7 signal function.

Each function is shown as follows.

(n:0~7)		
PnM1 bit	PnM0 bit	Function
0	0	General purpose input PIO7~0 signals become an input state. The signal level can be read by RR5 register. In synchronous action, it can be activated by the signals $\uparrow$ or $\downarrow$. In driving by external signals, relative position driving or continuous pulse driving can be activated by PIO4, 5 signals.
0	1	General purpose output PIO7~0 signals become an output state. D7~0 values of WR4 register are output to PIO7~0. When D7~0 are 0, it is Low level output and when they are 1, it is Hi level output.

1	0	Drive status output PIO7~0 signals become an output state and each signal outputs the drive status as shown in the table below.
1	1	Synchronous pulse・MRn comparison output PIO7~0 signals become an output state. PIO3~0 output synchronous pulses and PIO7~4 output MRn comparison value. The comparative object and comparison condition can be set by multi-purpose register mode setting command (20h).

The function of each PIO signal is shown as follows.

(n:0~7)

PIO _n Signal (Pin Number)	PnM1,0 = 0,0	PnM1,0 = 0,1	PnM1,0 = 1,0	PnM1,0 = 1,1
	General Purpose Input *Note	General Purpose Output	Drive Status Output (True = Hi)	Synchronous Pulse Output, MRn Comparison Output
PIO0 (58)	Signal level reading with RR5/D0	WR4/D0 value output	Driving	SYNC0 Synchronous pulse output
PIO1 (57)	Signal level reading with RR5/D1	WR4/D1 value output	Error	SYNC1 Synchronous pulse output
PIO2 (55)	Signal level reading with RR5/ D2	WR4/D2 value output	Accelerating	SYNC2 Synchronous pulse output
PIO3 (54)	Signal level reading with RR5/ D3	WR4/D3 value output	Constant speed driving	SYNC3 Synchronous pulse output
PIO4 (53)	Signal level reading with RR5/ D4	WR4/D4 value output	Decelerating	MR0 comparison output (True = Hi)
PIO5 (52)	Signal level reading with RR5/ D5	WR4/D5 value output	Acceleration increasing	MR1 comparison output (True = Hi)
PIO6 (51)	Signal level reading with RR5/ D6	WR4/D6 value output	Acceleration Constant	MR2 comparison output (True = Hi)
PIO7 (50)	Signal level reading with RR5/ D7	WR4/D7 value output	Acceleration decreasing	MR3 comparison output (True = Hi)

See Chapter 2.8 General Purpose Input / Output Signals for details of PIO7~0 signals.

*Note

When PIO7~0 signals are general purpose input mode (PnM1,0 = 0,0), it can be used as activation factor of a synchronous action. See Chapter 2.6 for more details.

When PIO4, 5 signals are general purpose input mode (PnM1,0 = 0,0), it can be used as input signals (EXPP, EXPM input) for driving by external signals. See Chapter 2.12.1 for more details.

D15~D0 will be set to 0 at reset.

5.3.3 PIO Signal Setting 2・Other Settings

Code	Command	Symbol	Data Length (byte)
2 2 h	PIO signal setting 2・Other settings	P 2 M	2

“P2M” is the parameter setting the logical level of a synchronous pulse and pulse width. In addition, it can set the synchronous action disabling when an error occurs, the mode setting for driving by external signals, the logical level of split pulse output and with or without starting pulse.

WR6	D15	D14	D13	D12 ^H	D11	D10	D9	D8	D7	D6	D5	D4 ^L	D3	D2	D1	D0
	0	0	0	0	SPLBP	SPLL	EXOP1	EXOP0	ERRDE	PW2	PW1	PW0	P3L	P2L	P1L	P0L
				Split Pulse				Driving by External Signals				Synchronous Pulse Output				

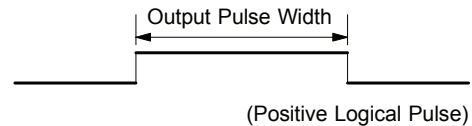
- D3~0 PnL Setting the logical level of pulses for when PION(n:3~0) is used as synchronous pulse output signal.
0: positive logical pulse, 1: negative logical pulse

Positive Logical Pulse :  Negative Logical Pulse : 

- D6~4 PW2~0 Setting the output pulse width of synchronous pulse output signal.

(When CLK=16MHz)

D6~4 (PW2~0)	Output Pulse Width
0	125n sec
1	312n sec
2	1μsec
3	4μsec
4	16μsec
5	64μsec
6	256μsec
7	1msec



- D7 ERRDE Setting for whether the enabling status of synchronous action SYNC3~0 is disabled or not when an error occurs (RR0/D1:ERROR = 1).
0: not disable at the error, 1: disable at the error
When this bit is set to 1, and when ERROR bit of RR0 register becomes 1, synchronous action SYNC3~0 is all disabled immediately.

When ERROR bit of RR0 register is 1, synchronous action SYNC3~0 cannot be enabled again. Clear the error bit by such as the error/finishing status clear command (79h) and then set the synchronous action enable setting.

Error status and enable/disable setting of synchronous action SYNC3~0 can be checked by RR0 register.

- D9, 8 EXOP1, 0 Setting the external input signals (EXPP, EXPM) for driving.

D9(EXOP1)	D8(EXOP0)	Driving mode by external signals
0	0	Driving disabled by external signals
0	1	Continuous driving mode
1	0	Relative position driving mode
1	1	MPG mode

- D10 SPLL The logical level of split pulse output.
0: positive logical pulse, 1: negative logical pulse

Positive Logical Pulse :  Negative Logical Pulse : 

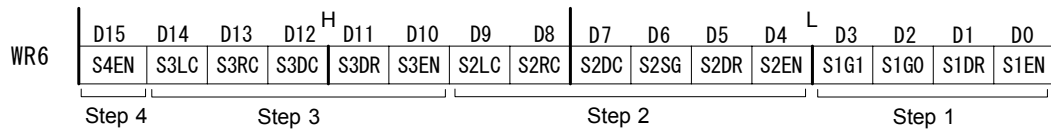
- D11 SPLBP With or without starting pulse of split pulse output.
0: without starting pulse, 1: with starting pulse

D15~D0 will be set to 0 at reset. D15~D12 should always be set to 0.

5.3.4 Automatic Home Search Mode Setting 1

Code	Command	Symbol	Data Length (byte)
2 3 h	Automatic home search mode setting 1	H 1 M	2

“H1M” is the parameter setting the automatic home search mode. Enable / disable of each step for automatic home search, search direction, stop signal selectable, enable / disable of deviation counter clear output and position counter clear.



D0 S1EN Setting for whether “high-speed search” of step 1 in the automatic home search is executed or not.
0: non-execution, 1: execution

D1 S1DR The search direction of step 1.
0: + direction, 1: – direction

D3, 2 S1G1, 0 The search signal of step 1.
Use the WR2 register for logical setting of the input signal that is detected.

D3(S1G1)	D2(S1G0)	Search Signal
0	0	STOP0
0	1	STOP1
1	0	Limit signal *
1	1	(Invalid)

* If a limit signal is specified, the limit signal in the search direction specified by D1(S1DR) will be selected.

D4 S2EN Setting for whether “low-speed search” of step 2 in the automatic home search is executed or not.
0: non-execution, 1: execution

D5 S2DR The search direction of step 2.
0: + direction, 1: – direction

D6 S2SG The search signal of step 2.
Use the WR2 register for logical setting of the input signal that is detected.

D6(S2SG)	Search Signal
0	STOP1
1	Limit signal *

* If a limit signal is specified, the limit signal in the search direction specified by D5(S2DR) will be selected.

D7 S2DC Setting for whether the deviation counter clear (DCC) signal is output or not in the signal detection of step 2.
0: non-output, 1: output

D8 S2RC Setting for whether the real position counter is cleared or not in the signal detection of step 2.
0: non-clear, 1: clear

D9 S2LC Setting for whether the logical position counter is cleared or not in the signal detection of step 2.
0: non-clear, 1: clear

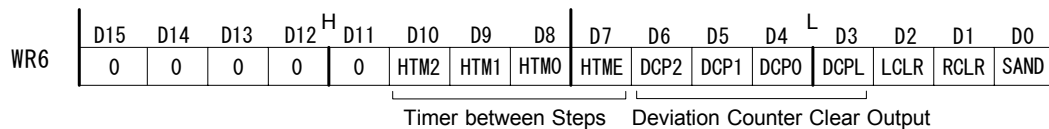
D10	S3EN	Setting for whether “low-speed Z-phase search” of step 3 in the automatic home search is executed or not. 0: non-execution, 1: execution
D11	S3DR	The search direction of step 3. 0: + direction, 1: – direction
D12	S3DC	Setting for whether the deviation counter clear (DCC) signal is output or not in STOP2 signal detection of step 3. 0: non-output, 1: output
D13	S3RC	Setting for whether the real position counter is cleared or not in STOP2 signal detection of step 3. 0: non-clear, 1: clear
D14	S3LC	Setting for whether the logical position counter is cleared or not in STOP2 signal detection of step 3. 0: non-clear, 1: clear
D15	S4EN	Setting for whether “high-speed offset drive” of step 4 in the automatic home search is executed or not. 0: non-execution, 1: execution

For more details of the automatic home search, see Chapter 2.5 and 2.5.4.
D15~D0 will be set to 0 at reset.

5.3.5 Automatic Home Search Mode Setting 2

Code	Command	Symbol	Data Length (byte)
2 4 h	Automatic home search mode setting 2	H 2 M	2

“H2M” is the parameter setting the automatic home search mode. The stop condition for automatic home search of step 3, position counter clear, deviation counter clear output and the timer between steps.

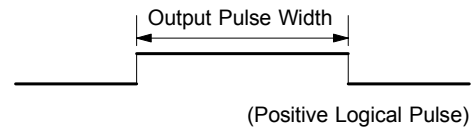


D0	SAND	When this bit is set to 1, and when STOP1 signal is active and STOP2 signal changes to active, the operation of step 3 will stop. This is only enabled when STOP1 signal is selected as the search signal of step 2, when a limit signal is selected, it cannot be enabled.
D1	RCLR	Setting for whether the real position counter is cleared or not at the end of automatic home search. 0: non-clear, 1: clear
D2	LCLR	Setting for whether the logical position counter is cleared or not at the end of automatic home search. 0: non-clear, 1: clear
D3	DCPL	Setting the logical level of deviation counter clear (DCC) output pulses. 0: positive logical pulse, 1: negative logical pulse

Positive Logical Pulse :  Negative Logical Pulse : 

D6~4 DCP2~0 Setting the output pulse width of deviation counter clear (DCC).

(When CLK=16MHz)	
D6~4 (DCP2~0)	Output Pulse Width
0	10μsec
1	20μsec
2	100μsec
3	200μsec
4	1msec
5	2msec
6	10msec
7	20msec



D7 HTME Enables the timer between steps.
0: disable, 1: enable

D10~8 HTM2~0 The interval of the timer between steps.

(When CLK=16MHz)	
D10~8 (HTM2~0)	Timer Time
0	1msec
1	2msec
2	10msec
3	20msec
4	100msec
5	200msec
6	500msec
7	1000msec

For more details of the automatic home search, see Chapter 2.5 and 2.5.4.

D15~D0 will be set to 0 at reset. . D15~D11 should always be set to 0.

5.3.6 Input signal filter mode setting

Code	Command	Symbol	Data Length (byte)
2 5 h	Input signal filter mode setting	F L M	2

“FLM” is the parameter setting the enable / disable of input signal filter and the time constant of 2 filters.

WR6	D15	D14	D13	D12 ^H	D11	D10	D9	D8	D7	D6	D5	D4 ^L	D3	D2	D1	D0
	FL13	FL12	FL11	FL10	FL03	FL02	FL01	FL00	FE7	FE6	FE5	FE4	FE3	FE2	FE1	FE0
	Filter Time Constant B				Filter Time Constant A				Enable / disable of Input Signal Filter							

D7~0 FE7~0 For a number of input signals as shown in the table below, it can set whether the IC built-in filter function is enabled or the signal is passed through.
0: disable (through), 1: enable

Specified bit	Input signal	Applied time constant
D0(FE0)	EMGN	Filter Time Constant A
D1(FE1)	LMTP, LMTM	
D2(FE2)	STOP0, STOP1	
D3(FE3)	INPOS, ALARM	
D4(FE4)	PIO3~0	
D5(FE5)	PIO7~4	
D6(FE6)	STOP2	Filter Time Constant B
D7(FE7)	ECA, ECB	

D11~8 FL03~00 Set the time constant of the input signal filter specified by D5~D0 (FE5~0) to Filter Time Constant A.

D15~12 FL13~10 Set the time constant of the input signal filter specified by D7, D6 (FE7, 6) to Filter Time Constant B.

(When CLK=16MHz)		
Time Constant (Hex)	Removable maximum noise width	Input signal delay time
0	437.5 n sec	500 n sec
1	875 n sec	1μsec
2	1.75μsec	2μsec
3	3.5μsec	4μsec
4	7μsec	8μsec
5	14μsec	16μsec
6	28μsec	32μsec
7	56μsec	64μsec
8	112μsec	128μsec
9	224μsec	256μsec
A	448μsec	512μsec
B	896μsec	1.024msec
C	1.792msec	2.048msec
D	3.584msec	4.096msec
E	7.168msec	8.192msec
F	14.336msec	16.384msec

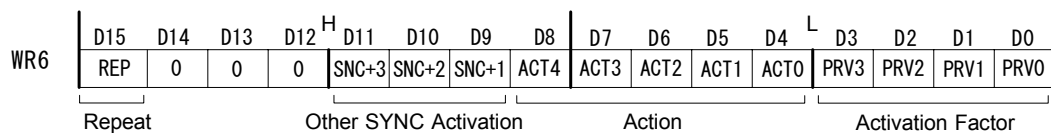
See Chapter 2.11 for details of input signal filter function.

D15~D0 will be set to 0 at reset.

5.3.7 Synchronous Action SYNC0, 1, 2, 3 Setting

Code	Command	Symbol	Data Length (byte)
2 6 h	Synchronous action SYNC0 setting	S 0 M	2
2 7 h	Synchronous action SYNC1 setting	S 1 M	2
2 8 h	Synchronous action SYNC2 setting	S 2 M	2
2 9 h	Synchronous action SYNC3 setting	S 3 M	2

These parameters are used to set the synchronous action SYNC0, 1, 2, 3 mode. The activation factor of each synchronous action set, actions, the activation of other synchronous action sets, the setting for whether the synchronous action is performed once or repeatedly.



D3~0 PRV3~0 It designates the activation factor of a synchronous action by code.

(n : 0,1,2,3)

Code (Hex)	Activation factor in SYNCn	Code (Hex)	Activation factor in SYNCn
0	NOP	8	Termination of split pulse
1	MRn comparison changed to True	9	Output of split pulse
2	Timer is up	A	PIOn input ↑
3	Start of driving	B	PIOn input ↓
4	Start of driving at constant speed area	C	PIO(n+4) input Low and PIOn input ↑
5	Termination of driving at constant speed area	D	PIO(n+4) input Hi and PIOn input ↑
6	Termination of driving	E	PIO(n+4) input Low and PIOn input ↓
7	Start of split pulse	F	PIO(n+4) input Hi and PIOn input ↓

For more details of the activation factor of a synchronous action and setting code, see Chapter 2.6.1.

D8~4 ACT4~0 It designates the action of a synchronous action by code.

(n : 0,1,2,3)

Code (Hex)	Action in SYNCn	Code (Hex)	Action in SYNCn
00	NOP	0C	Start of absolute position driving
01	Load MRn → DV	0D	Start of + direction continuous pulse driving
02	Load MRn → TP	0E	Start of - direction continuous pulse driving
03	Load MRn → SP1	0F	Relative position driving by drive pulse number of MRn value
04	Load MRn → LP(SYNC0), RP(SYNC1), SV(SYNC2), AC(SYNC3)	10	Absolute position driving to the finish point of MRn value
05	Save LP → MRn	11	Decelerating stop
06	Save RP → MRn	12	Instant stop
		13	Drive speed increase

07	Save CT → MRn	14	Drive speed decrease
08	Save CV(SYNC0), CA(SYNC1) → MRn	15	Timer-start
09	Synchronous pulse PION output	16	Timer-stop
0A	Start of relative position driving	17	Start of split pulse
0B	Start of counter relative position driving	18	Termination of split pulse

DV : Drive speed	TP : Drive pulse number / Finish point	SP1 : Split pulse setting 1
LP : Logical position counter	RP : Real position counter	SV : Initial speed
AC : Acceleration	CT : Current timer value	CV : Current drive speed
CA : Current acceleration / deceleration		

For more details of the action of synchronous action and setting code, see Chapter 2.6.2.

D11~9 SNC+3~1 It designates the other synchronous action sets activated by a synchronous action.
0: disable, 1: enable

Self- synchronous action set	D11(SNC+3)	D10(SNC+2)	D9(SNC+1)
SYNC0	SYNC3 activation	SYNC2 activation	SYNC1 activation
SYNC1	SYNC0 activation	SYNC3 activation	SYNC2 activation
SYNC2	SYNC1 activation	SYNC0 activation	SYNC3 activation
SYNC3	SYNC2 activation	SYNC1 activation	SYNC0 activation

D15 REP Setting for whether the enable state of synchronous action set is disabled or not once the synchronous action is activated.

0: disable (once), 1: non-disable (repeat)

When this bit is set to 0, and when the activation factor becomes active, the synchronous action is activated only the first time. When this bit is set to 1, the synchronous action is activated whenever the activation factor becomes active.

To re-enable the synchronous action that is disabled, issue a synchronous action enable command.

Enable / disable setting of synchronous action SYNC3~0 can be checked by RR0 register.

For more details of the synchronous action, see Chapter 2.6.

D15~D0 will be set to 0 at reset. D14~D12 should always be set to 0.

5.4 Commands for Reading Data

Commands for reading data are used to read the internal register.

After a data reading command is written into register WR0, this data will be set in registers RR6 and RR7.

The user can obtain a specified data by reading the registers RR6 and RR7. When the data length is 2 bytes, the data will be set in register RR6 and when it is 4 bytes, the data will be set in registers RR6 and RR7.

Reading data is binary and 2's complement is used for negative numbers.

[Note]

- a. It requires 125 nSEC (maximum) to access the command code of data reading when CLK = 16MHz. After the command is written and passed that time, read registers RR6 and 7.
- b. The unit described in each speed parameter and timer value is for when input clock (CLK) is 16MHz. Please see Appendix B for parameter calculation formula when input clock (CLK) is other than 16MHz.

5.4.1 Logical Position Counter Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 0 h	Logical position counter reading	L P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

The current value of logical position counter is set in read registers RR6 and RR7.

5.4.2 Real Position Counter Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 1 h	Real position counter reading	R P	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

The current value of real position counter is set in read registers RR6 and RR7.

5.4.3 Current Drive Speed Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 2 h	Current drive speed reading	C V	0 ~ 8, 000, 000	4

The value of current drive speed is set in read registers RR6 and RR7.

When the driving stops, the value becomes 0. The unit of the setting value is pps which is the same as Drive speed setting (DV).

5.4.4 Current Acceleration / Deceleration Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 3 h	Current acceleration / deceleration reading	C A	0 ~ 536,870,911	4

In acceleration / deceleration driving, the value of current acceleration speed during acceleration and current deceleration speed during deceleration is set in read registers RR6 and RR7. While driving stops, 0 will be read out.

The unit of the setting value is pps/sec which is the same as Acceleration setting (AC) and Deceleration setting (DC).

[Note]

In linear acceleration / deceleration driving (symmetrical), the acceleration setting value will always be read out during the driving.

In S-curve acceleration / deceleration driving, the current acceleration / deceleration reading value will be invalid at the constant speed area.

5.4.5 Multi-Purpose Register 0 Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 4 h	Multi-purpose register 0 reading	M R 0	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

The value of multi-purpose register MR0 is set in read registers RR6 and RR7.

It can be used to read out the current position, timer value and speed value saved in MR0 by a synchronous action.

5.4.6 Multi-Purpose Register 1 Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 5 h	Multi-purpose register 1 reading	M R 1	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

The value of multi-purpose register MR1 is set in read registers RR6 and RR7.

It can be used to read out the current position, current timer value and current acceleration / deceleration value saved in MR1 by a synchronous action.

5.4.7 Multi-Purpose Register 2 Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 6 h	Multi-purpose register 2 reading	M R 2	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

The value of multi-purpose register MR2 is set in read registers RR6 and RR7.

It can be used to read out the current position and timer value saved in MR2 by a synchronous action.

5.4.8 Multi-Purpose Register 3 Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 7 h	Multi-purpose register 3 reading	M R 3	-2, 147, 483, 648 ~ +2, 147, 483, 647	4

The value of multi-purpose register MR3 is set in read registers RR6 and RR7.

It can be used to read out the current position and timer value saved in MR3 by a synchronous action.

5.4.9 Current Timer Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 8 h	Current timer value reading	C T	0 ~ 2, 147, 483, 647	4

The value of current timer value in operation is set in read registers RR6 and RR7. While driving stops, 0 will be read out. The unit of the setting value is μ sec which is the same as Timer value setting (TM)

5.4.10 WR1 Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 D h	WR1 setting value reading	W R 1	(Bit data)	2

The setting value of WR1 register is set in read register RR6.

WR1 setting value cannot be read by accessing WR1 register address. To check and read out the WR1 setting value, use this command.

Read register RR7 is set to 0.

5.4.11 WR2 Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 E h	WR2 setting value reading	W R 2	(Bit data)	2

The setting value of WR2 register is set in read register RR6.

WR2 setting value cannot be read by accessing WR2 register address. To check and read out the WR2 setting value, use this command.

Read register RR7 is set to 0.

5.4.12 WR3 Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
3 F h	WR3 setting value reading	W R 3	(Bit data)	2

The setting value of WR3 register is set in read register RR6.

WR3 setting value cannot be read by accessing WR3 register address. To check and read out the WR3 setting value, use this command.

Read register RR7 is set to 0.

5.4.13 Multi-Purpose Register Mode Setting Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 0 h	Multi-purpose register mode setting reading	M R M	(Bit data)	2

The value set by multi-purpose register mode setting command (20h) is set in read register RR6.

Read register RR7 is set to 0.

5.4.14 PIO Signal Setting 1 Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 1 h	PIO signal setting 1 reading	P 1 M	(Bit data)	2

The value set by PIO signal setting 1 command (21h) is set in read register RR6.

Read register RR7 is set to 0.

5.4.15 PIO Signal Setting 2 Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 2 h	PIO signal setting 2 / Other settings reading	P 2 M	(Bit data)	2

The value set by PIO signal setting 2 / other settings command (22h) is set in read register RR6.

Read register RR7 is set to 0.

5.4.16 Acceleration Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 3 h	Acceleration setting value reading	A C	1 ~ 536, 870, 911	4

The value set by acceleration setting command (02h) is set in read registers RR6 and RR7.
The unit of the setting value is pps/sec.

When MR3 value is loaded to acceleration setting value (AC) by a synchronous action, that value will be read out.

5.4.17 Initial Speed Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 4 h	Initial speed setting value reading	S V	1 ~ 8, 000, 000	4

The value set by initial speed setting command (04h) is set in read registers RR6 and RR7.
The unit of the setting value is pps.

When MR2 value is loaded to initial speed setting value (SV) by a synchronous action, that value will be read out.

5.4.18 Drive Speed Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 5 h	Drive speed setting value reading	D V	1 ~ 8, 000, 000	4

The value set by drive speed setting command (05h) is set in read registers RR6 and RR7.
The unit of the setting value is pps.

When MRn value is loaded to drive speed setting value (DV) by a synchronous action, that value will be read out.

5.4.19 Drive Pulse Number / Finish Point Setting Value Reading

Code	Command	Symbol	Data Range	Data Length (byte)
4 6 h	Drive pulse number / Finish point setting value reading	T P	-2, 147, 483, 646 ~ +2, 147, 483, 646	4

The value set by drive pulse number / finish point setting command (06h) is set in read registers RR6 and RR7.

When MRn value is loaded to drive pulse number / finish point setting value (TP) by a synchronous action, that value will be read out.

5.4.20 Split Pulse Setting 1 Reading

Code	Command	Symbol	Data Range		Data Length (byte)
4 7 h	Split pulse setting 1 reading	S P 1	RR6	Split length : 2 ~ 65, 535	4
			RR7	Pulse width : 1 ~ 65, 534	

The value set by Split pulse setting 1 command (17h) is set in read registers RR6 and RR7.

The split length is set in RR6 and the pulse width is set in RR7.

When MRn value is loaded to split pulse setting 1 (SP1) by a synchronous action, that value will be read out.

5.5 Driving Commands

Driving commands include the commands for drive pulse output and other related commands. After the command code is written in command register WR0, the command will be executed immediately.

In driving, the DRIVE bit of main status register RR0 becomes 1. When the driving is finished, DRIVE bit will return to 0.

If INPOS input signal for a servo driver is enabled, the DRIVE bit of main status register RR0 will not return to 0 until INPOS signal is on its active level after the driving is finished.

[Note]

- It requires 125 nSEC (maximum) to access the command code when CLK = 16MHz. Please write the next command after this period of time.

5.5.1 Relative position driving

Code	Command
5 0 h	Relative position driving

The signed drive pulse number that is set will be output from the + direction drive pulse signal (PP) or the – direction drive pulse signal (PM). When the drive pulse number is positive, it will be output from the output signal PP, and when it is negative, it will be output from the output signal PM. (When the pulse output type is independent 2-pulse)

In driving, when one pulse of + direction drive pulses is output, the logical position counter will count up 1, and when one pulse of – direction drive pulses is output, the logical position counter will count down 1.

Before writing the driving command, the user should set the parameters for the outputting speed curve and the drive pulse number appropriately (see the table below).

Parameter	Speed curve to be output					○: Required
	Fixed speed	Symmetrical linear acceleration/ deceleration	Non-symmetrical linear acceleration /deceleration	Symmetrical S-curve acceleration /deceleration	Non-symmetrical S-curve acceleration /deceleration	
Jerk (JK)				○	○	
Deceleration increasing rate (DJ)					○	
Acceleration (AC)		○	○	○ *	○ *	
Deceleration (DC)			○		○ *	
Initial speed (SV)	○	○	○	○	○	
Drive speed (DV)	○	○	○	○	○	
Drive pulse number / Finish point (TP)	○	○	○	○	○	
Manual deceleration point (DP)					○	

*Note: Set the maximum value of 536,870,911 (1FFF FFFFh). However, in Partial S-curve acceleration / deceleration driving, set the acceleration / deceleration at the linear acceleration / deceleration part.

5.5.2 Counter relative position driving

Code	Command
5 1 h	Counter relative position driving

The signed drive pulse number that is set will be output from the + direction drive pulse signal (PP) or the – direction drive pulse signal (PM). When the drive pulse number is positive, it will be output from the output signal PM, and when it is negative, it will be output from the output signal PP. (When the pulse output type is independent 2-pulse)

This command can be used to output the predetermined drive pulse number in the different direction by driving commands. Usually, set the positive pulses to the drive pulse number (TP). When the user needs to drive in the + direction, issue relative position driving command (50h) and when to drive in the – direction, issue counter relative position driving command (51h).

In driving, when one pulse of + direction drive pulses is output, the logical position counter will count up 1, and when one pulse of – direction drive pulses is output, the logical position counter will count down 1.

Before writing the driving command, the user should set the parameters for the outputting speed curve and the drive pulse number appropriately.

5.5.3 + Direction continuous pulse driving

Code	Command
5 2 h	+ Direction continuous pulse driving

Until the stop command or specified external signal becomes active, pulse numbers will be output through the output signal PP continuously. (When the pulse output type is independent 2-pulse)

In driving, when one pulse of drive pulses is output, the logical position counter will count up 1.

Before writing the driving command, the user should set the parameters for the outputting speed curve appropriately.

5.5.4 – Direction continuous pulse driving

Code	Command
5 3 h	– Direction continuous pulse driving

Until the stop command or specified external signal becomes active, pulse numbers will be output through the output signal PM continuously. (When the pulse output type is independent 2-pulse)

In driving, when one pulse of drive pulses is output, the logical position counter will count down 1.

Before writing the driving command, the user should set the parameters for the outputting speed curve appropriately.

5.5.5 Absolute position driving

Code	Command
5 4 h	Absolute position driving

This command performs the driving from present point to finish point.

Before driving, the destination point based on a home (logical position counter = 0) should be set with a signed 32-bit value by drive pulse number / finish point setting command (06h).

Before writing the driving command, the user should set the parameters for the outputting speed curve and finish point appropriately.

5.5.6 Decelerating Stop

Code	Command
5 6 h	Decelerating stop

This command performs the decelerating stop when the drive pulses are outputting.
If the speed is lower than the initial speed during the driving, the driving will stop instantly.

Once the driving stops, this command will not work.

5.5.7 Instant Stop

Code	Command
5 7 h	Instant stop

This command performs the instant stop when the drive pulses are outputting. Also, the instant stop can be performed in acceleration / deceleration driving.

Once the driving stops, this command will not work.

5.5.8 Direction Signal + Setting

Code	Command
5 8 h	Direction signal + setting

This command is used to set the direction signal DIR to the active level of the + direction before driving when the pulse output type is 1-pulse 1-direction.

As shown in 9.2, once the driving is started in the 1-pulse 1-direction type, the first pulse of drive pulses will be output after 1CLK from when the direction signal is determined. This command can be used to determine the direction signal in the + direction when the user needs to take longer time than time to set up the direction signal for drive pulses.

5.5.9 Direction Signal – Setting

Code	Command
5 9 h	Direction signal – setting

This command is used to set the direction signal DIR to the active level of the – direction before driving when the pulse output type is 1-pulse 1-direction.

As shown in 9.2, once the driving is started in the 1-pulse 1-direction type, the first pulse of drive pulses will be output after 1CLK from when the direction signal is determined. This command can be used to determine the direction signal in the – direction when the user needs to take longer time than time to set up the direction signal for drive pulses.

5.5.10 Automatic Home Search Execution

Code	Command
5 A h	Automatic home search execution

This command executes automatic home search.

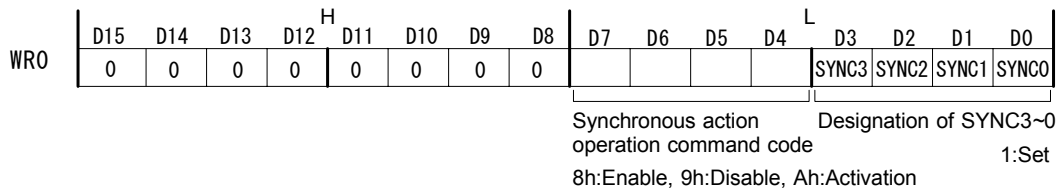
Before execution of the command, the automatic home search mode and correct parameters must be set. See Chapter 2.5 for details of automatic home search.

5.6 Synchronous Action Operation Commands

Synchronous action operation commands are used to enable, disable or activate a synchronous action.

There are 4 synchronous action sets: SYNC0, 1, 2, 3, and any of synchronous action sets can be enabled, disabled or activated at the same time.

For synchronous action operation commands, set the operation command code to the four D7~D4 bits of WR0 command register and set the synchronous action set which the user wants to operate to the four D3~D0 bits of WR0. That is, when the user wants to enable the synchronous action, set 8h to D7~D4, and when to disable it, set 9h to D7~D4, and when to activate it, set Ah to D7~D4. D3~D0 are corresponding to four synchronous action sets: SYNC3, SYNC2, SYNC1, SYNC0, and set 1 to the bit corresponding to the synchronous action set.



These commands are without writing data and executed by writing the command code into WR0 command register.

[Note]

- It requires 125 nSEC (maximum) to access the command code of synchronous action operation commands when CLK=16MHz. Please write the next command after this period of time.

5.6.1 Synchronous Action Enable Setting

Code	Command
8 1 h ~ 8 F h	Synchronous action enable setting

This command sets to enable each synchronous action set which is specified by the lower 4-bit of the command code.

Before the synchronous action enable setting, the mode setting for the synchronous action set which the user wants to enable must be set by synchronous action SYNC3~0 setting command (29h~26h).

■ Example : To enable the synchronous action sets SYNC0 and SYNC2, write 0085h into WR0.

The enable / disable state of synchronous action SYNC3~0 can be checked by RR0 register.

When resetting, all of SYNC3~0 will be disabled.

[Note]

By using PIO signal setting 2/other settings command (22h), when the synchronous action activated by an error is disabled by the setting (D7:ERRDE bit = 1) and when an error occurs (ERROR bit of RR0 register is 1.), this command cannot be set to enable the synchronous action. Issue the synchronous action enable setting command after clearing ERROR bit by such as error/finishing status clear command (79h).

5.6.2 Synchronous Action Disable Setting

Code	Command
9 1 h ~ 9 F h	Synchronous action disable setting

This command sets to disable each synchronous action set which is specified by the lower 4-bit of the command code. Once the synchronous action is set to disable, it cannot be activated by an activation factor or synchronous action activation command.

■ Example : To disable the synchronous action sets SYNC1 and SYNC3, write 009Ah into WR0.

The enable / disable state of synchronous action SYNC3~0 can be checked by RR0 register. When resetting, all of SYNC3~0 will be disabled.

5.6.3 Synchronous Action Activation

Code	Command
A 1 h ~ A F h	Synchronous action activation

This command sets to activate each synchronous action set which is specified by the lower 4-bit of the command code. Before the synchronous action is activated, the mode setting for the synchronous action set which the user wants to activate must be set by synchronous action SYNC3~0 setting command (29h~26h). And the synchronous action set which the user wants to activate must be enabled by synchronous action enable setting command.

The enable / disable state of synchronous action SYNC3~0 can be checked by RR0 register.

■ Example : To activate the synchronous action set SYNC0, write 00A1h into WR0.
To activate all the synchronous action sets SYNC3~0, write 00AFh into WR0.

5.7 Other Commands

These commands are without writing data and executed by writing the command code into WR0 command register.

[Note]

- It requires 125 nSEC (maximum) to access the command code when CLK=16MHz. Please write the next command after this period of time.

5.7.1 Speed Increase

Code	Command
7 0 h	Speed increase

This command increases a speed by the value of the speed increasing / decreasing value setting during the driving.

The speed increasing/decreasing value (IV) must be set by speed increasing/decreasing value setting command (15h) in advance.

This command can be used during continuous pulse driving and cannot be used during fixed pulse driving. If this command is used frequently during fixed pulse driving, premature termination or creep may occur at the termination of driving.

In S-curve acceleration / deceleration driving, this command will be invalid even if issued during acceleration / deceleration. Make sure to use it during constant speed driving (RR0/D3 : CNST=1).

The drive speed setting value (DV) is not updated by this command.

5.7.2 Speed Decrease

Code	Command
7 1 h	Speed decrease

This command decreases a speed by the value of the speed increasing / decreasing value setting during the driving.

The speed increasing/decreasing value (IV) must be set by speed increasing/decreasing value setting command (15h) in advance.

This command can be used during continuous pulse driving and cannot be used during fixed pulse driving. If this command is used frequently during fixed pulse driving, premature termination or creep may occur at the termination of driving.

In S-curve acceleration / deceleration driving, this command will be invalid even if issued during acceleration / deceleration. Make sure to use it during constant speed driving (RR0/D3 : CNST=1).

The drive speed setting value (DV) is not updated by this command.

5.7.3 Deviation Counter Clear Output

Code	Command
7 2 h	Deviation counter clear output

This command outputs deviation counter clear pulses from the DCC output pin.

Before issuing this command, set the logical level of pulses and pulse width by the automatic home search mode setting 2 command (24h). See Chapter 2.5.2 and 2.5.4 for details.

5.7.4 Timer-Start

Code	Command
7 3 h	Timer-start

This command starts a timer.

When a timer is started by this command, the current timer value (CT) starts to count up from 0, and when the count reaches the value specified by the timer value (TM), then the timer is up.

A timer can be used repeatedly after the time is up. To repeat a timer, set D14 bit (TMMD) of WR3 register to 1.

For more details of the timer, see Chapter 2.9.

5.7.5 Timer-Stop

Code	Command
7 4 h	Timer-stop

This command stops a timer.

If a timer is stopped before it expires, the current timer value (CT) returns to 0. And if the timer is started again, it counts up from 0.

5.7.6 Start of Split Pulse

Code	Command
7 5 h	Start of split pulse

This command outputs split pulses.

Split pulses are output from the SPLTP output pin during the driving.

SPLIT bit of RR0 register which indicates the split pulse is in operation becomes 1 by issuing start of split pulse command.

Before issuing this command, each parameter such as a split pulse length must be set appropriately.

For more details of each parameter for the split pulse, see Chapter 2.7.

5.7.7 Termination of Split Pulse

Code	Command
7 6 h	Termination of split pulse

This command stops to output split pulses.

SPLIT bit of RR0 register which indicates the split pulse is in operation becomes 0 by issuing termination of split pulse command.

When termination of split pulse command is issued, if the split pulse output signal is on Hi level, it stops after keeping the Hi level of a specified pulse width. (when the positive logic is set.)

5.7.8 Error / Finishing Status Clear

Code	Command
7 9 h	Error / Finishing status clear

All the error information bits and the driving finishing status bits of RR2 register and the error bit (D1:ERROR) of RR0 register are cleared to 0.

5.7.9 NOP

Code	Command
1 F h	NOP

No operation is performed.

5.7.10 Command Reset

Code	Command
0 0 F F h	Command reset

This command resets the IC.

All the higher 8 bits (D15~D8) of WR0 register must be set to 0.

The user cannot access the IC for a period of 8CLK (500nsec:CLK=16MHz) after the command code is written.

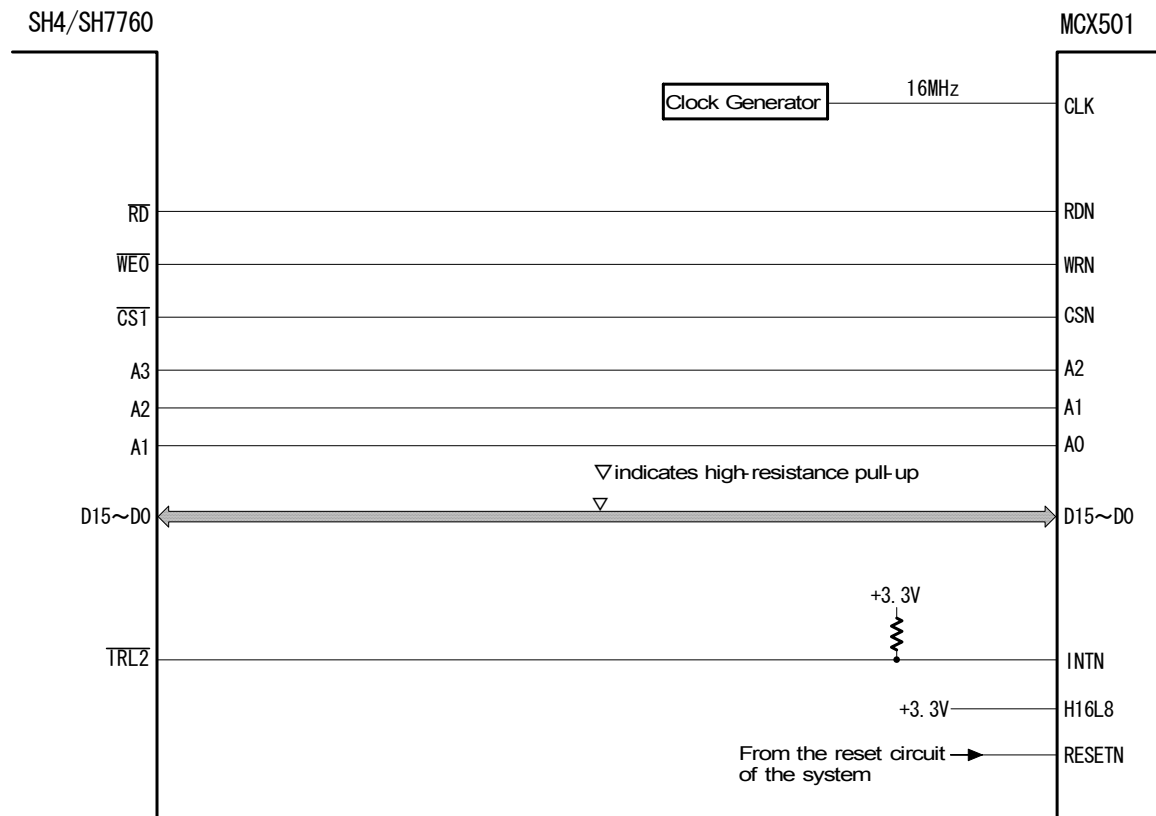
Similarly in 8-bit data bus, this command must write to the high word byte (WR0H).

The user should write 00h into the high word byte (WR0H), and then write FFh into the low word byte (WR0L). Reset will be executed immediately after writing into the low word byte.

6. Connection Examples

6.1 Example of Connection with SH-4 CPU

Example of 16-bit Bus Mode Connection

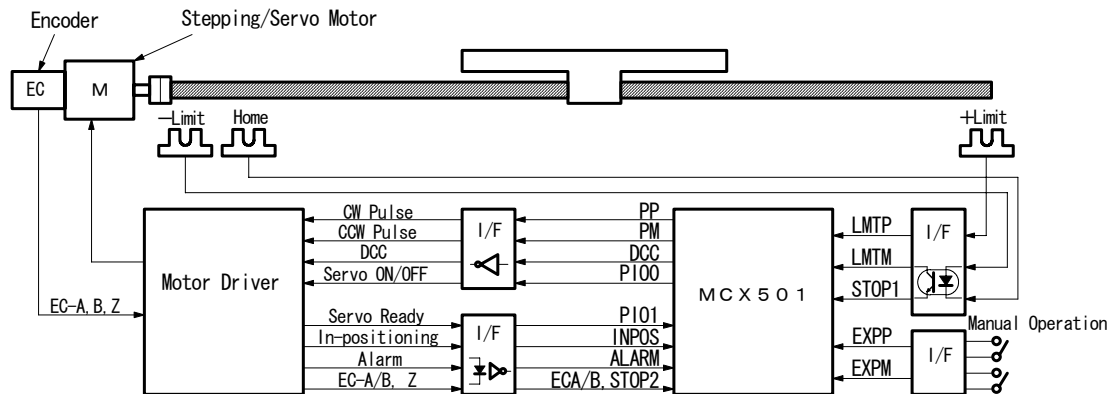


SH-4/SH7760 Examples of Waiting Control

Bus Clock	66.664MHz	—
Setup Waiting	1 cycle insert	Resister set : WCR3/A1S0=1
Access Waiting	2 cycles insert	Resister set : WCR2/A1W2, A1W1, A1W0 = 010
Hold Waiting	1 cycle insert	Resister set : WCR3/A1H1, A1H0 = 01

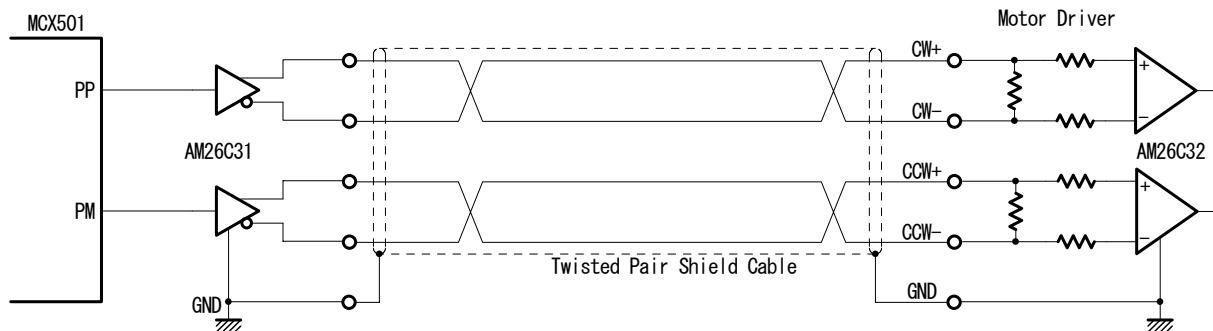
6.2 Connection Example

The figure shown below illustrates the connection example.

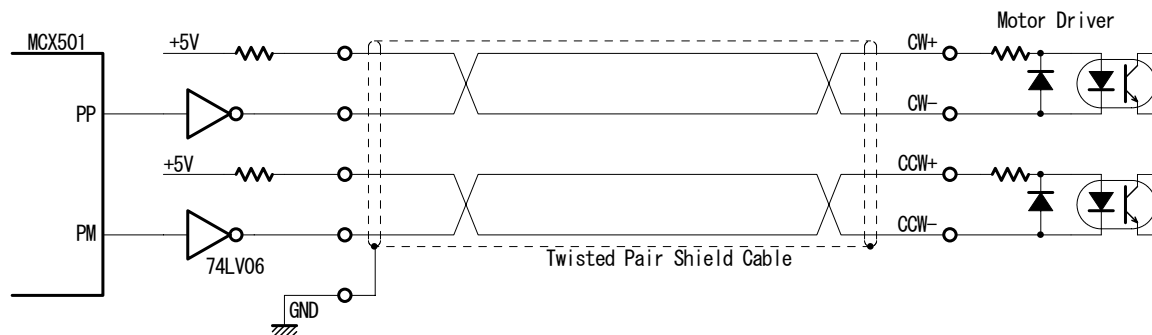


6.3 Pulse Output Interface

■ Output to Motor Driver in Differential Circuit



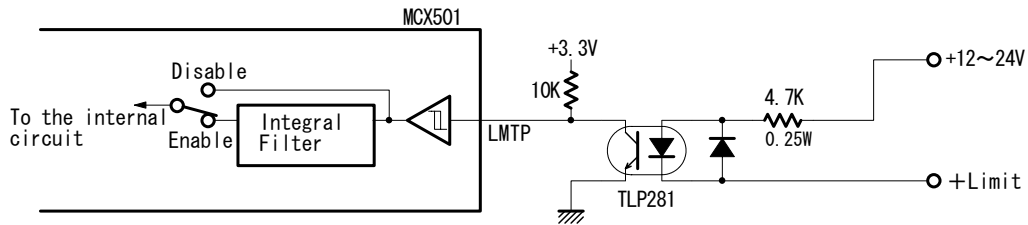
■ Open Collector TTL Output



For drive pulse output signals, we recommend the user to use twisted pair shield cable due to the concern of EMC.

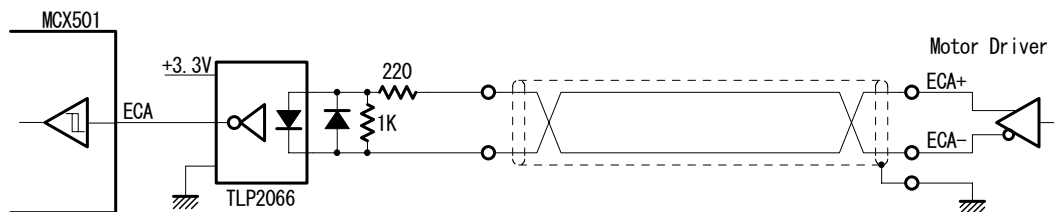
6.4 Connection Example for Input Signals

Limit signals often pick up some noise since complicated cabling is normally involved. A photo coupler alone may not be able to absorb this noise. Enable the filter function in the IC and set an appropriate time constant (FL=Ah, Bh).



6.5 Connection Example for Encoder

The following diagram is the example for the encoder signal which is differential line-drive output, then, this signal can be received through the high speed photo coupler IC which can direct it to MCX501.



7. Example Program

The example of C program for MCX501 is shown in this Chapter. This is a 16-bit bus configuration program.

This program can be downloaded from our web site (<http://www.novaelec.co.jp/eng/index.html>). File name: MCX501Aple.c

```

////////////////////////////////////
// Command code definition
////////////////////////////////////
////////////////////////////////////
// Commands for writing data
////////////////////////////////////
#define          MCX501_CMD00_JK          0x0000          // Jerk setting
#define          MCX501_CMD01_DJ          0x0001          // Deceleration increasing rate setting
#define          MCX501_CMD02_AC          0x0002          // Acceleration setting
#define          MCX501_CMD03_DC          0x0003          // Deceleration setting
#define          MCX501_CMD04_SV          0x0004          // Initial speed setting
#define          MCX501_CMD05_DV          0x0005          // Drive speed setting
#define          MCX501_CMD06_TP          0x0006          // Drive pulse number / Finish point setting
#define          MCX501_CMD07_DP          0x0007          // Manual deceleration point setting
#define          MCX501_CMD09_LP          0x0009          // Logical position counter setting
#define          MCX501_CMD0A_RP          0x000A          // Real position counter setting
#define          MCX501_CMD0B_SP          0x000B          // Software limit + setting
#define          MCX501_CMD0C_SM          0x000C          // Software limit - setting
#define          MCX501_CMD0D_AO          0x000D          // Acceleration counter offset setting
#define          MCX501_CMD0E_LX          0x000E          // Logical position counter maximum value setting
#define          MCX501_CMD0F_RX          0x000F          // Real position counter maximum value setting
#define          MCX501_CMD10_MR0         0x0010          // Multi-purpose register 0 setting
#define          MCX501_CMD11_MR1         0x0011          // Multi-purpose register 1 setting
#define          MCX501_CMD12_MR2         0x0012          // Multi-purpose register 2 setting
#define          MCX501_CMD13_MR3         0x0013          // Multi-purpose register 3 setting
#define          MCX501_CMD14_HV          0x0014          // Home search speed setting
#define          MCX501_CMD15_IV          0x0015          // Speed increasing / decreasing value setting
#define          MCX501_CMD16_TM          0x0016          // Timer value setting
#define          MCX501_CMD17_SP1         0x0017          // Split pulse setting 1
#define          MCX501_CMD18_SP2         0x0018          // Split pulse setting 2

////////////////////////////////////
// Commands for writing mode
////////////////////////////////////
#define          MCX501_CMD20_MRM         0x0020          // Multi-purpose register mode setting
#define          MCX501_CMD21_P1M         0x0021          // P10 signal setting 1
#define          MCX501_CMD22_P2M         0x0022          // P10 signal setting 2・Other settings
#define          MCX501_CMD23_H1M         0x0023          // Automatic home search mode setting 1
#define          MCX501_CMD24_H2M         0x0024          // Automatic home search mode setting 2
#define          MCX501_CMD25_FLM         0x0025          // Input signal filter mode setting
#define          MCX501_CMD26_SOM         0x0026          // Synchronous action SYNC0 setting
#define          MCX501_CMD27_S1M         0x0027          // Synchronous action SYNC1 setting
#define          MCX501_CMD28_S2M         0x0028          // Synchronous action SYNC2 setting
#define          MCX501_CMD29_S3M         0x0029          // Synchronous action SYNC3 setting

////////////////////////////////////
// Commands for reading data
////////////////////////////////////
#define          MCX501_CMD30_LP          0x0030          // Logical position counter reading
#define          MCX501_CMD31_RP          0x0031          // Real position counter reading
#define          MCX501_CMD32_CV          0x0032          // Current drive speed reading
#define          MCX501_CMD33_CA          0x0033          // Current acceleration / deceleration reading
#define          MCX501_CMD34_MR0         0x0034          // Multi-purpose register 0 reading
#define          MCX501_CMD35_MR1         0x0035          // Multi-purpose register 1 reading
#define          MCX501_CMD36_MR2         0x0036          // Multi-purpose register 2 reading
#define          MCX501_CMD37_MR3         0x0037          // Multi-purpose register 3 reading
#define          MCX501_CMD38_CT          0x0038          // Current timer value reading
#define          MCX501_CMD3D_WR1         0x003D          // WR1 setting value reading
#define          MCX501_CMD3E_WR2         0x003E          // WR2 setting value reading
#define          MCX501_CMD3F_WR3         0x003F          // WR3 setting value reading
#define          MCX501_CMD40_MRM         0x0040          // Multi-purpose register mode setting reading
#define          MCX501_CMD41_P1M         0x0041          // P10 signal setting 1 reading
#define          MCX501_CMD42_P2M         0x0042          // P10 signal setting 2・Other settings reading

```

```

#define MCX501_CMD43_AC 0x0043 // Acceleration setting value reading
#define MCX501_CMD44_SV 0x0044 // Initial speed setting value reading
#define MCX501_CMD45_DV 0x0045 // Drive speed setting value reading
#define MCX501_CMD46_TP 0x0046 // Drive pulse number/Finish point setting value reading
#define MCX501_CMD47_SP1 0x0047 // Split pulse setting 1 reading

////////////////////////////////////
// Driving commands
////////////////////////////////////
#define MCX501_CMD50_DRVRL 0x0050 // Relative position driving
#define MCX501_CMD51_DRVNR 0x0051 // Counter relative position driving
#define MCX501_CMD52_DRVVP 0x0052 // + Direction continuous pulse driving
#define MCX501_CMD53_DRVVM 0x0053 // - Direction continuous pulse driving
#define MCX501_CMD54_DRVAB 0x0054 // Absolute position driving
#define MCX501_CMD56_DRVSBRK 0x0056 // Decelerating stop
#define MCX501_CMD57_DRVFBRK 0x0057 // Instant stop
#define MCX501_CMD58_DIRCP 0x0058 // Direction signal + setting
#define MCX501_CMD59_DIRCM 0x0059 // Direction signal - setting
#define MCX501_CMD5A_HMSRC 0x005A // Automatic home search execution

////////////////////////////////////
// Synchronous action operation commands
////////////////////////////////////
#define MCX501_CMD81_SYNC0EN 0x0081 // Synchronous action SYNC0 enable setting
#define MCX501_CMD82_SYNC1EN 0x0082 // Synchronous action SYNC1 enable setting
#define MCX501_CMD84_SYNC2EN 0x0084 // Synchronous action SYNC2 enable setting
#define MCX501_CMD88_SYNC3EN 0x0088 // Synchronous action SYNC3 enable setting
#define MCX501_CMD91_SYNC0DIS 0x0091 // Synchronous action SYNC0 disable setting
#define MCX501_CMD92_SYNC1DIS 0x0092 // Synchronous action SYNC1 disable setting
#define MCX501_CMD94_SYNC2DIS 0x0094 // Synchronous action SYNC2 disable setting
#define MCX501_CMD98_SYNC3DIS 0x0098 // Synchronous action SYNC3 disable setting
#define MCX501_CMDA1_SYNC0ACT 0x00A1 // Synchronous action SYNC0 activation
#define MCX501_CMDA2_SYNC1ACT 0x00A2 // Synchronous action SYNC1 activation
#define MCX501_CMDA4_SYNC2ACT 0x00A4 // Synchronous action SYNC2 activation
#define MCX501_CMDA8_SYNC3ACT 0x00A8 // Synchronous action SYNC3 activation

////////////////////////////////////
// Other Commands
////////////////////////////////////
#define MCX501_CMD70_VINC 0x0070 // Speed increase
#define MCX501_CMD71_VDEC 0x0071 // Speed decrease
#define MCX501_CMD72_DCC 0x0072 // Deviation counter clear output
#define MCX501_CMD73_TMSTA 0x0073 // Timer-start
#define MCX501_CMD74_TMSTP 0x0074 // Timer-stop
#define MCX501_CMD75_SPSTA 0x0075 // Start of split pulse
#define MCX501_CMD76_SPSTP 0x0076 // Termination of split pulse
#define MCX501_CMD79_R2CLR 0x0079 // Error / Finishing status clear
#define MCX501_CMD1F_NOP 0x001F // NOP
#define MCX501_CMDFF_RST 0x00FF // Command reset

////////////////////////////////////
// Address definition
////////////////////////////////////
#define REG_ADDR 0x0000 // Basic address

// Write register, Read register definition
#define MCX501_WRO 0x00
#define MCX501_WR1 0x02
#define MCX501_WR2 0x04
#define MCX501_WR3 0x06
#define MCX501_WR4 0x08
#define MCX501_WR6 0x0c
#define MCX501_WR7 0x0e
#define MCX501_RRO 0x00
#define MCX501_RR1 0x02
#define MCX501_RR2 0x04
#define MCX501_RR3 0x06
#define MCX501_RR4 0x08
#define MCX501_RR5 0x0a
#define MCX501_RR6 0x0c

```

```

#define MCX501_RR7                0x0e
unsigned short reg_read (unsigned short n);

#define reg_write(n,c)      (*(volatile unsigned short *)n = ((volatile)c))
#define reg_read(n)        (*(volatile unsigned short *)n)

/////////////////////////////////////////////////////////////////
// Common functions definition
/////////////////////////////////////////////////////////////////
int WriteReg(volatile unsigned short *Adr, unsigned short Data);      // Common function of writing WR register
int ReadReg(volatile unsigned short *Adr, unsigned short *Data);      // Common function of reading RR register
int SetData(unsigned short Cmd, long Data);                          // Common function of commands for writing data
int SetModeData(unsigned short Cmd, unsigned short Data);            // Common function of commands for writing mode
int GetData(unsigned short Cmd, long *Data);                        // Common function of commands for reading data
int ExeCmd(unsigned short Cmd);                                       // Common function of command execution

/////////////////////////////////////////////////////////////////
// Write functions for WR register
/////////////////////////////////////////////////////////////////
int WriteReg0(unsigned short Data) {                                  // Writes into WR0 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR0), Data));
}
int WriteReg1(unsigned short Data) {                                  // Writes into WR1 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR1), Data));
}
int WriteReg2(unsigned short Data) {                                  // Writes into WR2 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR2), Data));
}
int WriteReg3(unsigned short Data) {                                  // Writes into WR3 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR3), Data));
}
int WriteReg4(unsigned short Data) {                                  // Writes into WR4 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR4), Data));
}
int WriteReg6(unsigned short Data) {                                  // Writes into WR6 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR6), Data));
}
int WriteReg7(unsigned short Data) {                                  // Writes into WR7 register
    return(WriteReg((volatile unsigned short*)(REG_ADDR + MCX501_WR7), Data));
}

/////////////////////////////////////////////////////////////////
// Read functions for RR register
/////////////////////////////////////////////////////////////////
int ReadReg0(unsigned short *Data) {                                  // Reads out RR0 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR0), Data));
}
int ReadReg1(unsigned short *Data) {                                  // Reads out RR1 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR1), Data));
}
int ReadReg2(unsigned short *Data) {                                  // Reads out RR2 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR2), Data));
}
int ReadReg3(unsigned short *Data) {                                  // Reads out RR3 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR3), Data));
}
int ReadReg4(unsigned short *Data) {                                  // Reads out RR4 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR4), Data));
}
int ReadReg5(unsigned short *Data) {                                  // Reads out RR5 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR5), Data));
}
int ReadReg6(unsigned short *Data) {                                  // Reads out RR6 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR6), Data));
}
int ReadReg7(unsigned short *Data) {                                  // Reads out RR7 register
    return(ReadReg((volatile unsigned short*)(REG_ADDR + MCX501_RR7), Data));
}

```

```

////////////////////////////////////
// Functions of commands for writing data
////////////////////////////////////
int SetStartSpd(long Data) {                                     // Initial speed setting
    return(SetData(MCX501_CMD04_SV, Data));
}
int SetSpeed(long Data) {                                       // Drive speed setting
    return(SetData(MCX501_CMD05_DV, Data));
}
int SetJerk(long Data) {                                         // Jerk setting
    return(SetData(MCX501_CMD00_JK, Data));
}
int SetDJerk(long Data) {                                        // Deceleration increasing rate setting
    return(SetData(MCX501_CMD01_DJ, Data));
}
int SetAcc(long Data) {                                          // Acceleration setting
    return(SetData(MCX501_CMD02_AC, Data));
}
int SetDec(long Data) {                                          // Deceleration setting
    return(SetData(MCX501_CMD03_DC, Data));
}
int SetPulse(long Data) {                                        // Drive pulse number / Finish point setting
    return(SetData(MCX501_CMD06_TP, Data));
}
int SetDecP(long Data) {                                         // Manual deceleration point setting
    return(SetData(MCX501_CMD07_DP, Data));
}
int SetLp(long Data) {                                           // Logical position counter setting
    return(SetData(MCX501_CMD09_LP, Data));
}
int SetRp(long Data) {                                           // Real position counter setting
    return(SetData(MCX501_CMD0A_RP, Data));
}
int SetCompP(long Data) {                                        // Software limit + setting
    return(SetData(MCX501_CMD0B_SP, Data));
}
int SetCompM(long Data) {                                        // Software limit - setting
    return(SetData(MCX501_CMD0C_SM, Data));
}
int SetAccOfst(long Data) {                                       // Acceleration counter offsetting
    return(SetData(MCX501_CMD0D_AO, Data));
}
int SetHomeSpd(long Data) {                                       // Home search speed setting
    return(SetData(MCX501_CMD14_HV, Data));
}
int SetLpMax(long Data) {                                        // Logical position counter maximum value setting
    return(SetData(MCX501_CMD0E_LX, Data));
}
int SetRpMax(long Data) {                                        // Real position counter maximum value setting
    return(SetData(MCX501_CMD0F_RX, Data));
}
int SetMRO(long Data) {                                          // Multi-purpose register 0 setting
    return(SetData(MCX501_CMD10_MRO, Data));
}
int SetMR1(long Data) {                                          // Multi-purpose register 1 setting
    return(SetData(MCX501_CMD11_MR1, Data));
}
int SetMR2(long Data) {                                          // Multi-purpose register 2 setting
    return(SetData(MCX501_CMD12_MR2, Data));
}
int SetMR3(long Data) {                                          // Multi-purpose register 3 setting
    return(SetData(MCX501_CMD13_MR3, Data));
}
int SetSpeedInc(long Data) {                                      // Speed increasing / decreasing value setting
    return(SetData(MCX501_CMD15_IV, Data));
}
int SetTimer(long Data) {                                        // Timer value setting
    return(SetData(MCX501_CMD16_TM, Data));
}

```

```

int SetSplit1(unsigned short Data1, unsigned short Data2) {           // Split pulse setting 1
    long Data;

    Data = ((Data1 << 16) | Data2);
    return(SetData(MCX501_CMD17_SP1, Data));
}
int SetSplit2(long Data) {                                           // Split pulse setting 2
    return(SetData(MCX501_CMD18_SP2, Data));
}

////////////////////////////////////
// Functions of commands for writing mode
////////////////////////////////////
int SetModeMRn(unsigned short Data) {                                // Multi-purpose register mode setting
    return(SetModeData(MCX501_CMD20_MRM, Data));
}
int SetModePIO1(unsigned short Data) {                                // PIO signal setting 1
    return(SetModeData(MCX501_CMD21_P1M, Data));
}
int SetModePIO2(unsigned short Data) {                                // PIO signal setting 2・Other settings
    return(SetModeData(MCX501_CMD22_P2M, Data));
}
int SetModeHMSrch1(unsigned short Data) {                            // Automatic home search mode setting 1
    return(SetModeData(MCX501_CMD23_H1M, Data));
}
int SetModeHMSrch2(unsigned short Data) {                            // Automatic home search mode setting 2
    return(SetModeData(MCX501_CMD24_H2M, Data));
}
int SetModeFilter(unsigned short Data) {                             // Input signal filter mode setting
    return(SetModeData(MCX501_CMD25_FLM, Data));
}
int SetModeSync0(unsigned short Data) {                              // Synchronous action SYNC0 setting
    return(SetModeData(MCX501_CMD26_SOM, Data));
}
int SetModeSync1(unsigned short Data) {                              // Synchronous action SYNC1 setting
    return(SetModeData(MCX501_CMD27_S1M, Data));
}
int SetModeSync2(unsigned short Data) {                              // Synchronous action SYNC2 setting
    return(SetModeData(MCX501_CMD28_S2M, Data));
}
int SetModeSync3(unsigned short Data) {                              // Synchronous action SYNC3 setting
    return(SetModeData(MCX501_CMD29_S3M, Data));
}

////////////////////////////////////
// Functions of commands for reading data
////////////////////////////////////
int GetLp(long *Data) {                                              // Logical position counter reading
    return(GetData(MCX501_CMD30_LP, Data));
}
int GetRp(long *Data) {                                              // Real position counter reading
    return(GetData(MCX501_CMD31_RP, Data));
}
int GetCV(long *Data) {                                              // Current drive speed reading
    return(GetData(MCX501_CMD32_CV, Data));
}
int GetCA(long *Data) {                                              // Current acceleration / deceleration reading
    return(GetData(MCX501_CMD33_CA, Data));
}
int GetCT(long *Data) {                                              // Current timer value reading
    return(GetData(MCX501_CMD38_CT, Data));
}
int GetMRO(long *Data) {                                             // Multi-purpose register 0 reading
    return(GetData(MCX501_CMD34_MRO, Data));
}
int GetMR1(long *Data) {                                             // Multi-purpose register 1 reading
    return(GetData(MCX501_CMD35_MR1, Data));
}

```

```

int GetMR2(long *Data){ // Multi-purpose register 2 reading
    return(GetData(MCX501_CMD36_MR2, Data));
}
int GetMR3(long *Data){ // Multi-purpose register 3 reading
    return(GetData(MCX501_CMD37_MR3, Data));
}
int GetWR1(long *Data){ // WR1 setting value reading
    return(GetData(MCX501_CMD3D_WR1, Data));
}
int GetWR2(long *Data){ // WR2 setting value reading
    return(GetData(MCX501_CMD3E_WR2, Data));
}
int GetWR3(long *Data){ // WR3 setting value reading
    return(GetData(MCX501_CMD3F_WR3, Data));
}
int GetMRM(long *Data){ // Multi-purpose register mode setting reading
    return(GetData(MCX501_CMD40_MRM, Data));
}
int GetP1M(long *Data){ // PIO signal setting 1 reading
    return(GetData(MCX501_CMD41_P1M, Data));
}
int GetP2M(long *Data){ // PIO signal setting 2 - Other settings reading
    return(GetData(MCX501_CMD42_P2M, Data));
}
int GetAc(long *Data){ // Acceleration setting value reading
    return(GetData(MCX501_CMD43_AC, Data));
}
int GetStartSpd(long *Data){ // Initial speed setting value reading
    return(GetData(MCX501_CMD44_SV, Data));
}
int GetSpeed(long *Data){ // Drive speed setting value reading
    return(GetData(MCX501_CMD45_DV, Data));
}
int GetPulse(long *Data){ // Drive pulse number/Finish point setting value reading
    return(GetData(MCX501_CMD46_TP, Data));
}
int GetSplit(long *Data){ // Split pulse setting 1 reading
    return(GetData(MCX501_CMD47_SP1, Data));
}

////////////////////////////////////
// Driving command functions
////////////////////////////////////
int ExeDRVRL(void){ // Relative position driving
    return (ExeCmd(MCX501_CMD50_DRVRL));
}
int ExeDRVNR(void){ // Counter relative position driving
    return (ExeCmd(MCX501_CMD51_DRVNR));
}
int ExeDRVVP(void){ // + Direction continuous pulse driving
    return (ExeCmd(MCX501_CMD52_DRVVP));
}
int ExeDRVVM(void){ // - Direction continuous pulse driving
    return (ExeCmd(MCX501_CMD53_DRVVM));
}
int ExeDRVAB(void){ // Absolute position driving
    return (ExeCmd(MCX501_CMD54_DRVAB));
}
int ExeDRVSBRK(void){ // Decelerating stop
    return (ExeCmd(MCX501_CMD56_DRVSBRK));
}
int ExeDRVFBRK(void){ // Instant stop
    return (ExeCmd(MCX501_CMD57_DRVFBRK));
}
int ExeDIRCP(void){ // Direction signal + setting
    return (ExeCmd(MCX501_CMD58_DIRCP));
}
int ExeDIRCM(void){ // Direction signal - setting
    return (ExeCmd(MCX501_CMD59_DIRCM));
}

```

```

int ExeHMSRC(void ) {                                     // Automatic home search execution
    return (ExeCmd(MCX501_CMD5A_HMSRC));
}

/////////////////////////////////////////////////////////////////
// Synchronous action operation command function
/////////////////////////////////////////////////////////////////
int ExeSYNC(unsigned short Cmd) {                         // Command related to synchronous action
    return (ExeCmd(Cmd));
}

/////////////////////////////////////////////////////////////////
// Other Commands functions
/////////////////////////////////////////////////////////////////
int ExeVINC(void ) {                                     // Speed increase
    return (ExeCmd(MCX501_CMD70_VINC));
}
int ExeVDEC(void ) {                                     // Speed decrease
    return (ExeCmd(MCX501_CMD71_VDEC));
}
int ExeDCC(void ) {                                     // Deviation counter clear output
    return (ExeCmd(MCX501_CMD72_DCC));
}
int ExeTMSTA(void ) {                                    // Timer-start
    return (ExeCmd(MCX501_CMD73_TMSTA));
}
int ExeTMSTP(void ) {                                    // Timer-stop
    return (ExeCmd(MCX501_CMD74_TMSTP));
}
int ExeSPSTA(void ) {                                    // Start of split pulse
    return (ExeCmd(MCX501_CMD75_SPSTA));
}
int ExeSPSTP(void ) {                                    // Termination of split pulse
    return (ExeCmd(MCX501_CMD76_SPSTP));
}
int ExeR2CLR(void ) {                                    // Error / Finishing status clear
    return (ExeCmd(MCX501_CMD79_R2CLR));
}
int ExeNOP(void ) {                                      // NOP
    return (ExeCmd(MCX501_CMD1F_NOP));
}
int ExeSRST(void ) {                                     // Command reset
    return (ExeCmd(MCX501_CMDFF_RST));
}

/////////////////////////////////////////////////////////////////
// Common functions
/////////////////////////////////////////////////////////////////
// Common function of writing WR register (I/O port access. The following is the example of SH microcomputer.)
int WriteReg(volatile unsigned short *Adr, unsigned short Data) {
    reg_write(Adr, Data);
    return 0;
}
// Common function of reading RR register (I/O port access. The following is the example of SH microcomputer.)
int ReadReg(volatile unsigned short *Adr, unsigned short *Data) {
    *Data = reg_read(Adr);
    return 0;
}

```

```

// Common function of commands for writing data
// Data can be written by writing data into WR6, WR7, and then writing a command into WR0.
int SetData(unsigned short Cmd, long Data) {

    long mask_data = 0x0000ffff;
    unsigned short write_data;

    // Writes the lower 16-bit of data into WR6
    write_data = (unsigned short )(Data & mask_data);
    WriteReg6(write_data);

    // Writes the upper 16-bit of data into WR7
    write_data = (unsigned short )(Data >> 16);
    WriteReg7(write_data);

    // Writes a command (into WR0)
    WriteReg0(Cmd);

    return 0;
}

// Common function of commands for writing mode
// Data can be written by writing data into WR6, and then writing a command into WR0.
int SetModeData(unsigned short Cmd, unsigned short Data) {

    // Writes the lower 16-bit of data into WR6
    WriteReg6(Data);

    // Writes a command (into WR0)
    WriteReg0(Cmd);

    return 0;
}

// Common function of commands for reading data
// Data can be read by writing a command into WR0, and then read  RR6, RR7.
int GetData(unsigned short Cmd, long *Data) {

    unsigned short rdata1, rdata2;
    long retdata = 0x00000000;

    if (Data == NULL) return 0;

    // Writes a command (into WR0)
    WriteReg0(Cmd);

    // Reads RR7
    ReadReg7(&rdata1);

    // Reads RR6
    ReadReg6(&rdata2);

    // Create data for reading
    retdata = (long )rdata1;           // Sets RR7 value to the upper 16-bit
    *Data = (retdata << 16);
    retdata = (long )rdata2;           // Sets RR6 value to the lower 16-bit
    *Data = *Data + retdata;

    return 0;
}

// Common function of command execution
int ExeCmd(unsigned short Cmd) {

    // Writes a command (into WR0)
    WriteReg0(Cmd);

    return 0;
}

```

```

// Waiting for termination of driving
void waitdrive(void) {

    unsigned short rrData;

    ReadReg0(&rrData);                // Reads RR0
    while ((rrData & 0x0001)) {        // If during the driving
        ReadReg0(&rrData);            // Reads RR0
    }
}

// Waiting for termination of split pulse
void waitsplit(void) {

    unsigned short rrData;

    ReadReg0(&rrData);                // Reads RR0
    while ((rrData & 0x2000)) {        // If split pulse is in operation
        ReadReg0(&rrData);            // Reads RR0
    }
}

////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////
// Operation example functions
////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////
// Automatic home search
// Performs "Example 1 Home search using a home signal" in "2.5.8 Examples of Automatic Home Search".
void homesrch(void) {

    WriteReg2(0x0800);                // Home signal logical setting STOP1 Low active
                                     // Enables hardware limit
    SetModeFilter(0x0A0F);            // STOP1 Enables the filter
                                     // Filter delay 512μsec
    SetModeHMSrch1(0x8037);           // Step 4 Execution
                                     // Step 3 Non-execution
                                     // Step 2 Execution
                                     //      Detection signal STOP1
                                     //      Search direction —direction
                                     //      LP, RP clear Disable
                                     //      DCC clear Disable
                                     // Step 1 Execution
                                     //      Detection signal STOP1
                                     //      Search direction —direction
    SetModeHMSrch2(0x0000);           // Timer between steps Disable
                                     // At the termination of home search, LP, RP clear Disable
    SetAcc(95000);                    // Acceleration 95,000 pps/sec
    SetStartSpd(1000);                // Initial speed 1000pps
    SetSpeed(20000);                  // Speed of step 1 and 4 20000pps
    SetHomeSpd(500);                  // Speed of step 2 500pps
    SetPulse(3500);                   // Offset driving pulse count 3500
    ExeHMSRC();                       // Automatic home search execution
    waitdrive();                      // Waiting for termination of driving
}

// S-curve acceleration / deceleration driving
void drive(void) {

    SetStartSpd(10);                  // Initial speed 10pps
    SetSpeed(40000);                  // Drive speed 40Kpps
    SetAcc(536870911);                // Acceleration (maximum in specification)
    SetJerk(89300);                   // Jerk 89.3Kpps/sec2
    SetPulse(70000);                  // Drive pulse number 70000
    SetLp(0);                         // Logical position counter clear
    WriteReg3(0x0004);                // Specifies S-curve acceleration/deceleration driving
    ExeDRVRL();                       // Relative position driving
    waitdrive();                      // Waiting for termination of driving
}

```

```

// Synchronous action
// Performs "Example 3 Calculates the time passing through from position A (10000) to position B (55000) during the
// driving." in "2.6.6 Examples of Synchronous Action" .
void sync(void) {

    // Constant speed driving at 10kpps
    SetStartSpd(8000000); // Initial speed 8Mpps (maximum in specification)
    SetSpeed(10000);      // Drive speed 10Kpps
    SetLp(0);             // Logical position counter 0
    SetPulse(60000);      // Drive pulse number 60000
    SetMR0(10000);        // MR0 10000
    SetMR1(55000);        // MR1 55000
    SetTimer(2147483647); // Timer value (maximum in specification)
    WriteReg1(0x2000);    // WR1 Synchronous action set 1 activation
    SetModeMRn(0x0000);   // Compares MR0 with LP. Comparison condition  $\geq$ 
                        // Compares MR1 with LP. Comparison condition  $\geq$ 
    SetModeSync0(0x0151); // SYNC0 setting
                        // Activation factor MRn object changed to True
                        // Action Timer-start
    SetModeSync1(0x0071); // SYNC1 setting
                        // Activation factor MRn object changed to True
                        // Action Save CT→MRn
    ExeSYNC((MCX501_CMD81_SYNC0EN | MCX501_CMD82_SYNC1EN));
                        // SYNC0,1 Enable
    ExeDRVRL();          // Relative position driving
    waitdrive();         // Waiting for termination of driving
}

// Split pulse
// Performs in "Example 1 Split pulse starts from the start of driving." in "2.7.6 Examples of Split Pulse" .
void split(void) {

    // Constant speed driving at 1000pps
    SetStartSpd(8000000); // Initial speed 8Mpps (maximum in specification)
    SetSpeed(1000);        // Drive speed 1000pps
    SetLp(0);             // Logical position counter
    SetSplit1(9,5);        // Split length 9, Pulse width 5
    SetSplit2(10);         // Pulse number 10
    SetModePI02(0x0800);   // Pulse logic Positive, With starting pulse
    ExeSPSTA();            // Start of split pulse
    ExeDRVVP();            // +direction continuous pulse driving
    waitsplit();           // Waiting for termination of split pulse
    ExeDRVFBRK();          // Instant stop
    waitdrive();           // Waiting for termination of driving
}

// Main functions
void main(void) {

    ExeSRST();             // Command reset

    homesrch();            // Automatic home search

    drive();               // S-curve acceleration / deceleration driving

    sync();                // Synchronous action

    split();               // Split pulse
}

```

8. Electrical Characteristics

8.1 DC Characteristics

■ Absolute Maximum Ratings

Item	Symbol	Condition	Value	Unit
Power Voltage	V_{DD}	—	-0.5 ~ +4.6	V
Input voltage	V_I	$V_I < V_{DD} + 3.0V$	-0.5 ~ +6.6	V
Output voltage	V_O	$V_O < V_{DD} + 3.0V$	-0.5 ~ +6.6	V
Output Current	I_O	D15~D0 signal PIO7~PIO0 signal	±20	mA
		Other signals except D15~D0, PIO7~PIO0	±10	
Preservation Temperature	T_{STG}		-65 ~ +150	°C

■ Recommend Operation Environment

Item	Symbol	Value	Unit
Power Voltage	V_{DD}	3.3±0.3	V
Ambient Temperature	T_a	-40 ~ +85	°C

■ DC Characteristics

($T_a = -40 \sim +85^{\circ}\text{C}$, $V_{DD} = 3.3\text{V} \pm 10\%$)

Item	Symbol	Condition	Min.	Typ.	Max.	Unit	Remark
High level input voltage	V_{IH}		2.0		5.5	V	
Low level input voltage	V_{IL}		0		0.8	V	
High level input current	I_{IH}	$V_{IN} = V_{DD}$			1.0	μA	
Low level input current	I_{IL}	$V_{IN} = 0V$			-1.0	μA	
High level output voltage	V_{OH}	$I_{OH} = 0\text{mA}$	$V_{DD} - 0.2$			V	Note1
		$I_{OH} = -9\text{mA}$	2.4			V	D15~D0 signal PIO7~PIO0 signal
		$I_{OH} = -6\text{mA}$	2.4			V	Other signals except those above
Low level output voltage	V_{OL}	$I_{OL} = 0\text{mA}$			0.1	V	
		$I_{OL} = 9\text{mA}$			0.4	V	D15~D0 signal PIO7~PIO0 signal, INTN signal
		$I_{OL} = 6\text{mA}$			0.4	V	Other signals except those above
Output leakage current	I_{OZ}	$V_{OUT} = V_{DD}$ or GND	-10		10	μA	D15~D0, PIO7~PIO0, INTN
Schmitt hysteresis voltage	V_H		0.3		1.5	V	
Consumption current	I_{DD}	$I_{IO} = 0\text{mA}$, CLK=16MHz		27	44	mA	
		$I_{IO} = 0\text{mA}$, CLK=20MHz		34	56		

Note1: INTN output signal has no items for high level output voltage due to the open drain output.

■ Pin Capacity

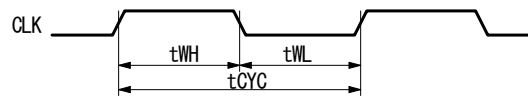
Item	Symbol	Condition	Min.	Typ.	Max.	Unit	Remark
Input/ Output capacity	C_{IO}	$T_a = 25^{\circ}\text{C}$, $f = 1\text{MHz}$			7	pF	D15~D0 signal PIO7~PIO0 signal
Input capacity	C_I				7	pF	Other input pins

8.2 AC Characteristics

($T_a = -40 \sim +85^{\circ}\text{C}$, $V_{DD} = +3.3\text{V} \pm 10\%$, Output load condition: D15~D0, INTN: 85pF, Others: 50pF)

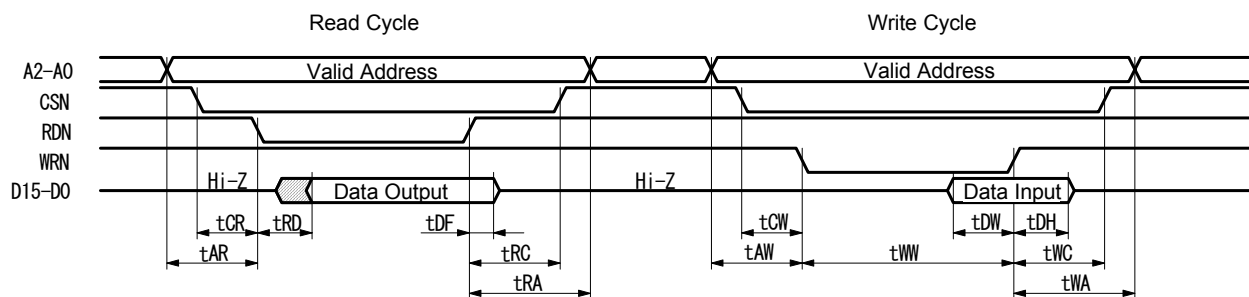
8.2.1 Clock

■ CLK Input Signal



Symbol	Item	Min.	Typ.	Max.	Unit
t_{CYC}	CLK Cycle	50	62.5		nS
t_{WH}	CLK Hi Level Width	15			nS
t_{WL}	CLK Low Level Width	15			nS

8.2.2 Read / Write Cycle

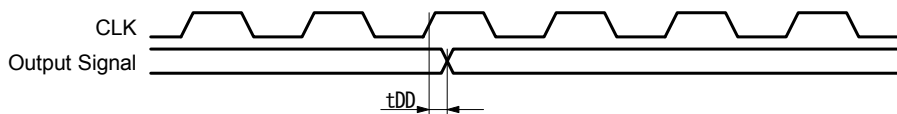


The figure shown above is used for 16-bit data bus accessing (H16L8 = Hi). For 8-bit data bus (H16L8 = Low), the address signals shown in the figure become A3~A0, and data signals become D7~D0.

Symbol	Item	Min.	Max.	Unit
t_{AR}	Address Setup Time (to RDN ↓)	0		nS
t_{CR}	CSN Setup Time (to RDN ↓)	0		nS
t_{RD}	Output Data Delay Time (from RDN ↓)		30	nS
t_{DF}	Output Data Hold Time (from RDN ↑)	0	30	nS
t_{RC}	CSN Hold Time (from RDN ↑)	0		nS
t_{RA}	Address Hold Time (from RDN ↑)	3		nS
t_{AW}	Address Setup Time (to WRN ↓)	0		nS
t_{CW}	CSN Setup Time (to WRN ↓)	0		nS
t_{WW}	WRN Low Level Pulse Width	30		nS
t_{DW}	Setup Time of Input Data (to WRN ↑)	10		nS
t_{DH}	Hold Time of Input Data (from WRN ↑)	0		nS
t_{WC}	CSN Hold Time (from WRN ↑)	0		nS
t_{WA}	Address Hold Time (from WRN ↑)	3		nS

8.2.3 CLK / Output Signal Timing

The following output signals are synchronized with CLK signal. The level will be changed at CLK $\uparrow$.



Output signals: PP, PM, DCC, SPLTP, PIO7~0 (according to the function selected)

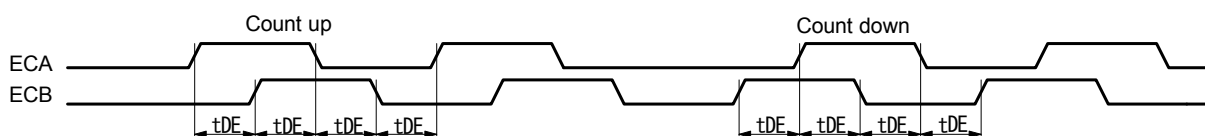
Symbol	Item	Min.	Max.	Unit
tDD	CLK $\uparrow$ → Output Signal $\uparrow \downarrow$ Delay Time	6	19	nS

Output signals: INTN

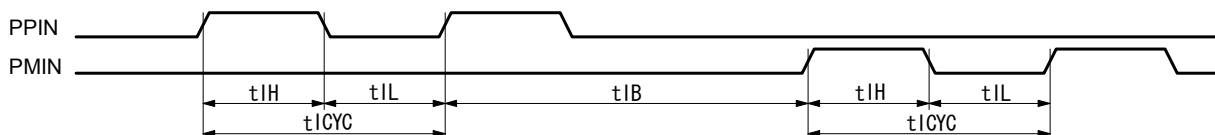
Symbol	Item	Min.	Max.	Unit
tDD	CLK $\uparrow$ → INTN Signal $\downarrow$ Delay Time	8	19	nS

8.2.4 Input Pulses

■ Quadrature Pulses Input Mode (A/B phases)



■ Up / Down Pulses Input Mode



- In quadrature pulses input mode, when ECA, ECB input pulses are changed, the value of real position counter will be reflected in the value of after a maximum of 4 CLK cycles.
- In UP/DOWN pulses input mode, the value of real position counter will be reflected in the value of after a maximum of 4 CLK cycles from PPIN, PMIN input $\uparrow$.

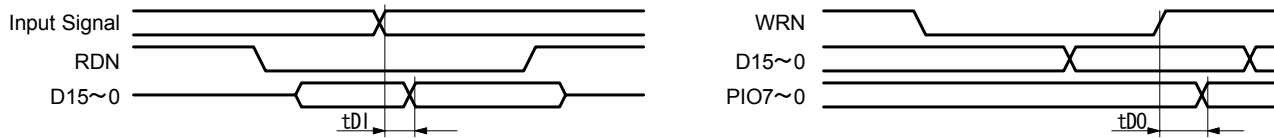
Symbol	Item	Min.	Max.	Unit
tDE	ECA, ECB Phase Difference Time	tCYC +20		nS
tIH	PPIN, PMIN Hi Level Width	tCYC +20		nS
tIL	PPIN, PMIN Low Level Width	tCYC +20		nS
tICYC	PPIN, PMIN Cycle	tCYC×2 +20		nS
tIB	PPIN $\uparrow$ ↔ PMIN $\uparrow$ between Time	tCYC×2 +20		nS

tCYC is a cycle of CLK.

8.2.5 General Purpose Input / Output Signals (PIO7~0)

The figure shown at the lower left hand side illustrates the delay time when PIO7~0 input signals are read through RR5 register. The IC built-in filter is disabled.

The figure shown at the lower right hand side illustrates the delay time when writing PIO7~0 output signals data into WR4 register.



Symbol	Item	Min.	Max.	Unit
t_{DI}	Input Signal $\rightarrow$ Data Delay Time		30	nS
t_{DO}	WRN $\uparrow \rightarrow$ Data Setup Time		13	nS

8.2.6 Split Pulse

The delay time from the rising edge of the drive pulse that starts the split pulse to when the split pulse becomes Hi (Split pulse is positive logic).

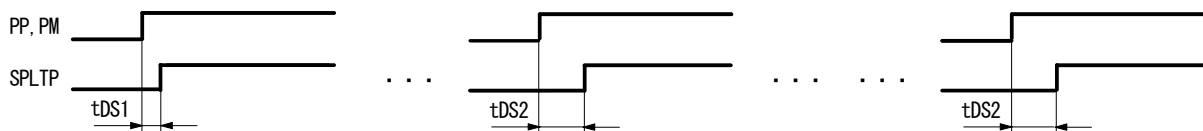
When with starting pulse, only the first split pulse is output together with the drive pulse. The second or later split pulses are output with 1 CLK delay from the drive pulse.

When without starting pulse, all the split pulses are output with 1 CLK delay from the drive pulse.

■ When with starting pulse is enabled in split pulse mode setting

This is, when with starting pulse is enabled in split pulse mode setting, the delay time from the rising edge of the drive pulse that starts the split pulse to when the split pulse becomes Hi.

t_{DS1} is the delay time of the first split pulse. t_{DS2} indicates the delay time of the second or later split pulses.

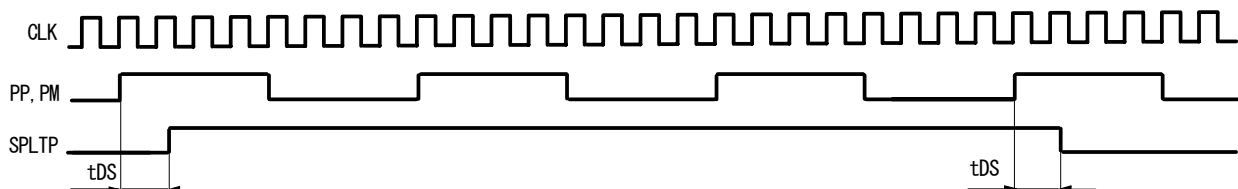


Symbol	Item	Min.	Max.	Unit
t_{DS1}	PP, PM $\uparrow \rightarrow$ SPLTP $\uparrow$ Delay Time		20	nS
t_{DS2}	PP, PM $\uparrow \rightarrow$ SPLTP $\uparrow$ Delay Time		$t_{CYC} + 20$	nS

t_{CYC} is a cycle of CLK.

■ When without starting pulse is enabled in split pulse mode setting

This is, when without starting pulse is enabled in split pulse mode setting, the delay time from the rising edge of the drive pulse that starts the split pulse to when the split pulse becomes Hi.

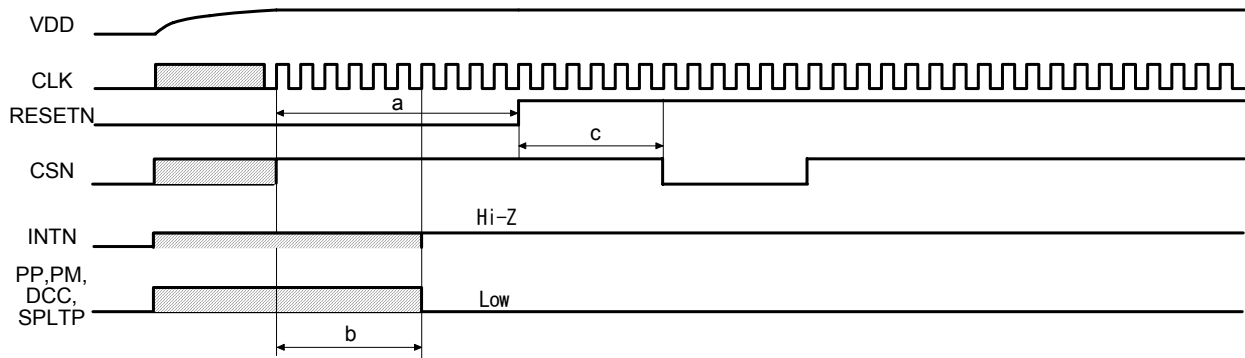


Symbol	Item	Min.	Max.	Unit
t_{DS}	PP, PM $\uparrow \rightarrow$ SPLTP $\uparrow$ Delay Time		$t_{CYC} + 20$	nS

t_{CYC} is a cycle of CLK.

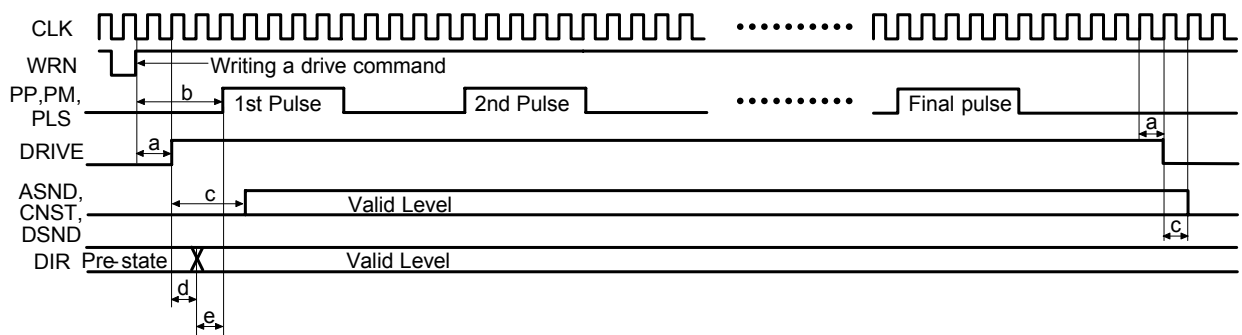
9. Timing of Input / Output Signals

9.1 Power-On Reset



- a. The reset signal input to pin RESETN needs to keep on the Low level for at least 8 CLK cycles.
- b. When RESETN is on the Low level for 6 CLK cycles maximum, the power-on output signal is determined to the level shown in the figure above.
- c. For a maximum of 4 CLK cycles after RESETN is on the Hi level, this IC cannot be read/written.

9.2 Fixed Pulse or Continuous Pulse Driving

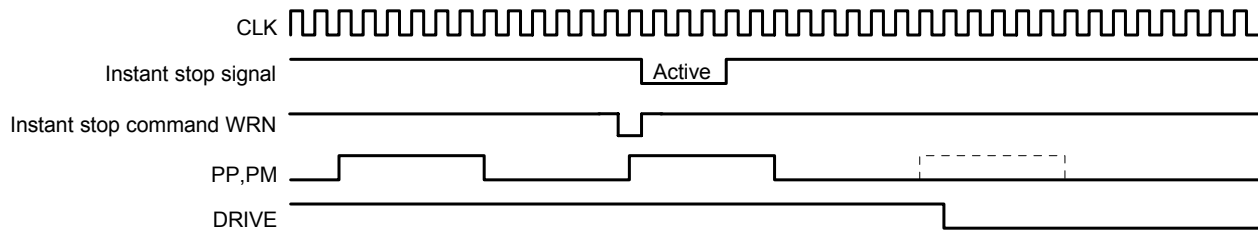


- a. Drive status output signal (DRIVE) is on the Hi level after a maximum of 2 CLK cycles from WRN ↑ when a driving command is written. And it returns to low level after 1 CLK cycle from when the cycle of final pulse output has finished.
- b. Driving pulses (PP, PM and PLS) shown above are positive logic pulses. The first driving pulse will be output after a maximum of 4 CLK cycles from WRN ↑ when a driving command is written.
- c. ASND, CNST and DSND are on valid level after 3 CLK cycles from DRIVE ↑ and they return to low level after 1 CLK cycle from DRIVE ↓.
- d. DIR (direction) signal is valid after 1 CLK cycle from DRIVE ↑ and keeps its level until the next command is written after the driving is finished.
- e. The first pulse of the drive pulse (PLS) will be output after 1 CLK cycle from when DIR (direction) signal is valid.

9.3 Instant Stop

The following figure illustrates the timing of instant stop. Instant stop input signals are EMGN, LMTP/M (When setting the instant stop mode) and ALARM.

When an instant stop input signal becomes active, or an instant stop command is written, the output of pulses will be stopped instantly.

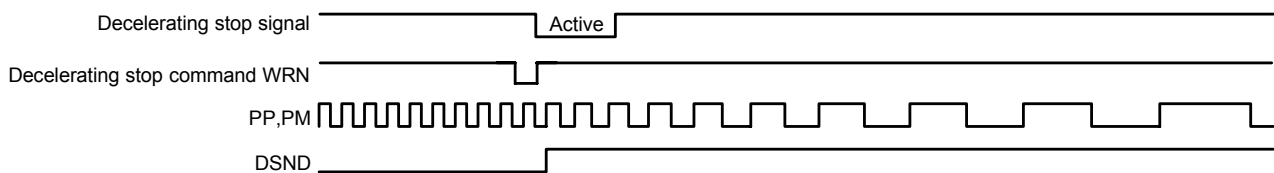


An instant stop input signal requires a pulse width of 2 CLK cycles or more even if the input signal filter is disabled. When the input signal filter is enabled, the input signal will be delayed according to the time constant of the filter.

9.4 Decelerating Stop

The following figure illustrates the timing of decelerating stop. Decelerating stop signals are STOP2~0 and LMTP/M (When setting the decelerating stop mode).

When a decelerating stop input signal becomes active, or a decelerating stop command is written, decelerating stop will be performed after the output of pulses.

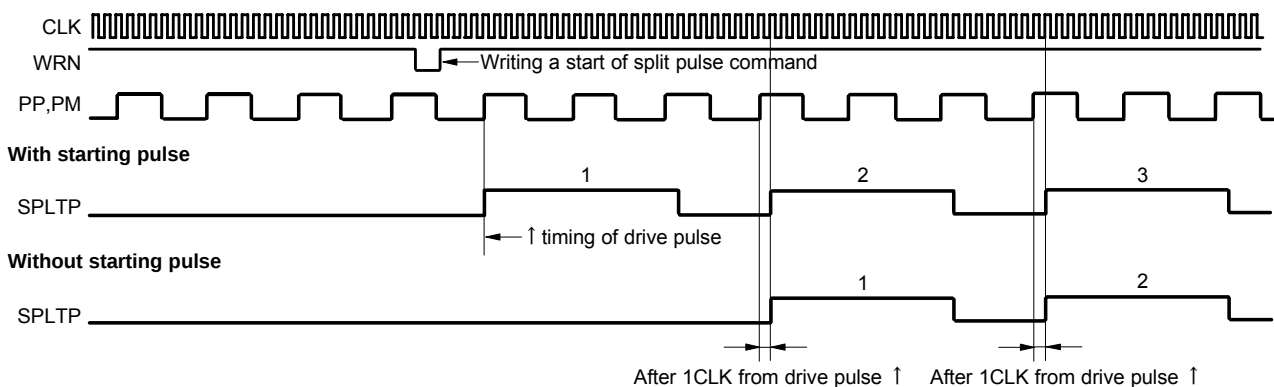


When the input signal filter is enabled, the input signal will be delayed according to the time constant of the filter.

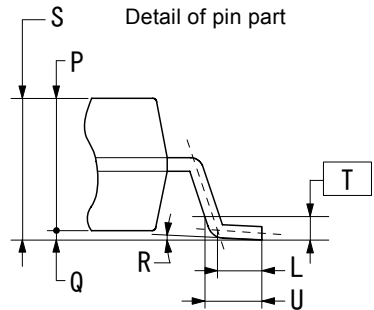
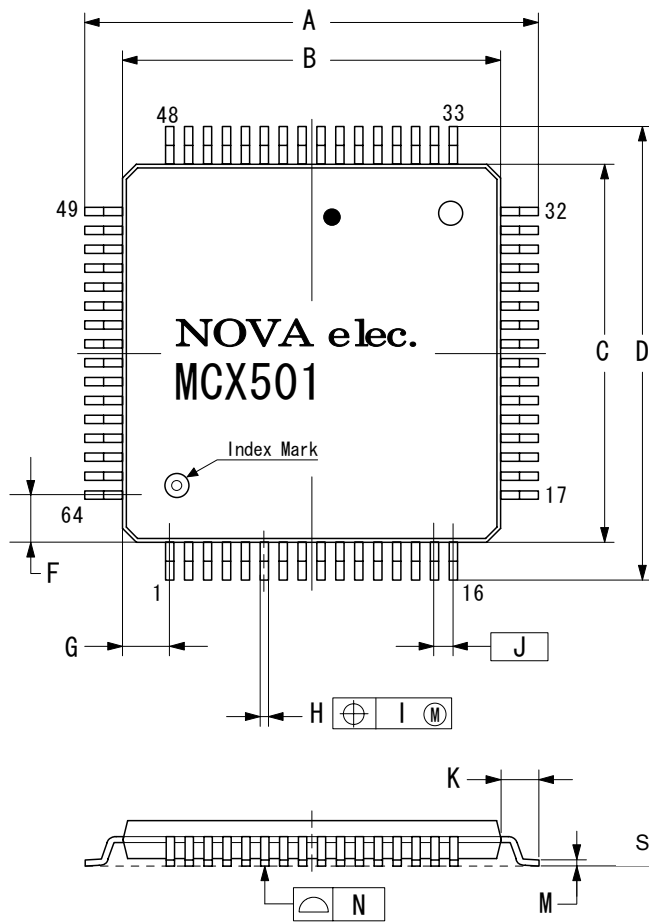
9.5 Detailed Timing of Split Pulse

When with starting pulse is enabled in split pulse mode setting, only the first split pulse is on the Hi level at the timing of the drive pulse $\uparrow$. The second or later split pulses are on the Hi level after 1 CLK cycle from the drive pulse $\uparrow$. Therefore, the Hi level width of the first split pulse is 1 CLK cycle longer than that of the second or later split pulses.

When without starting pulse is enabled in split pulse mode setting, all the split pulses are on the Hi level after 1 CLK cycle from the drive pulse $\uparrow$ (when the positive logic is set).



10.Package Dimensions



Note :
In maximum material condition, the center line of each pin is positioned within 0.08mm of the true position (TP).

Symbol	Size (mm)	Description
A	12.0 ± 0.2	Dimension including pin length in package length direction
B	10.0 ± 0.2	Length of package main unit
C	10.0 ± 0.2	Width of package main unit
D	12.0 ± 0.2	Dimension including pin length in package width direction
F	1.25	Distance from the center of the outer-most pin in width direction to the edge of package main unit
G	1.25	Distance from the center of the outer-most pin in length direction to the edge of package main unit
H	0.22 ± 0.05	Pin width (including plating)
I	0.08	Permissible value of pin center position error, maximum material condition (MMC) is applied
J	0.5 (TP)	Distance between true positions, Pin pitch
K	1.0 ± 0.2	Length from the end of pin to package main unit, which is projected seating plane
L	0.5	Effective projected length of pin flat section
M	$0.17^{+0.03}_{-0.07}$	Pin thickness (including plating)
N	0.08	Maximum deviation in vertical direction between the bottom of each pin and seating plane, Uniformity of the bottom of pin
P	1.0	Height from the top end to the bottom end of package main unit
Q	0.1 ± 0.05	Distance from seating plane to the bottom end of package main unit
R	$3^{\circ}^{+4^{\circ}}_{-3^{\circ}}$	Angle between pin flat section and seating plane
S	1.10 ± 0.10	Height from seating plane to the top end of package main unit
T	0.25	Standard height 0.25mm from seating plane
U	0.6 ± 0.15	Length of the soldered section of pin

11. Storage and Recommended Installation Conditions

11.1 Storage of this IC

Note the following items in regard to the storage of this IC.

- (1) Do not throw or drop the IC. Otherwise, the packing material could be torn, damaging the airtightness.
- (2) Store the IC sealed damp-proof package under the temperature 5~35°C and humidity 85%RH or lower and use the IC within 12 months.
- (3) If the IC usage date has expired, remove any dampness by baking it at the temperature 125°C±5°C for 10 hours or more and 72 hours or less. The total baking time must not exceed 96 hours. If damp-proofing is damaged before expiration, also apply damp removal processing.
- (4) Protect the device from static electricity before applying damp removal processing.
- (5) After opening the damp-proof package, store the IC under 5~30°C / 70%RH or lower and install it within seven days. If the allowable storage period described above has been exceeded, baking must be applied before installation of the IC.

11.2 Standard Installation Conditions by Soldering Iron

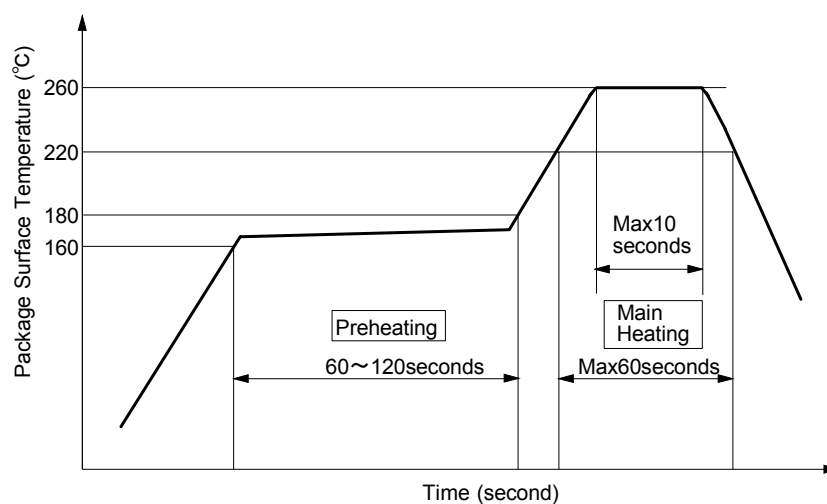
The standard installation conditions for the IC by soldering iron are as follows.

- (1) Installation method: Soldering iron (heating pin section)
- (2) Installation conditions: The temperature of the pin: 350°C or lower, Time: 3 seconds or less (per side of the device)

11.3 Standard Installation Conditions by Solder Reflow

The standard installation conditions for the IC by solder reflow are as follows.

Maximum reflow temperature (package surface temperature)	260°C or less
Time of maximum temperature	10 seconds or less
Time of over 220°C	60 seconds or less
Time of 160°C~180°C (Preheating temperature)	60~120 seconds
Solder reflow count	Up to 3 times

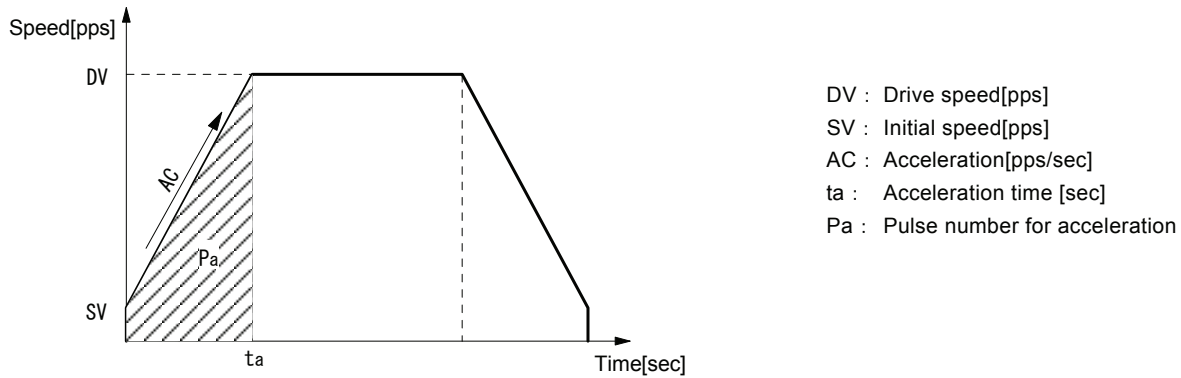


MCX501 Standard Soldering Reflow Heat-proof Profile

Appendix A Calculation Formula of Acceleration/Deceleration Drive

A-1 Case of Trapezoidal Acceleration/Deceleration Driving

(CLK = 16MHz)



◎Calculation Formula of acceleration AC when initial speed SV, drive speed DV and acceleration time ta are given

$$\text{Acceleration} \quad AC = \frac{DV - SV}{t_a} \quad [\text{pps/sec}]$$

◎Calculation Formula of acceleration time ta when initial speed SV, drive speed DV and acceleration AC are given

$$\text{Acceleration time} \quad t_a = \frac{DV - SV}{AC} \quad [\text{sec}]$$

◎Calculation Formula of pulse number for acceleration Pa when initial speed SV, drive speed DV and acceleration AC are given

$$\text{Pulse number for acceleration} \quad P_a = \frac{DV^2 - SV^2}{2 \times AC}$$

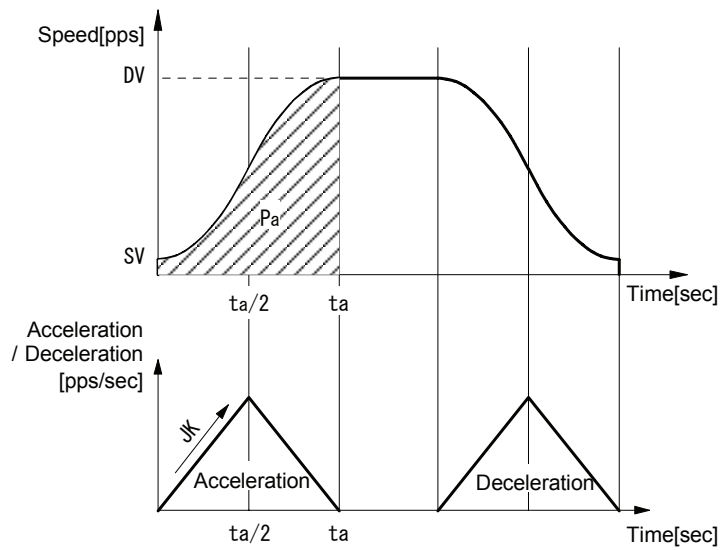
Deceleration DC, deceleration time td and pulse number for deceleration Pd can be calculated by replacing acceleration AC, acceleration time ta and pulse number for acceleration Pa with deceleration DC, deceleration time td and pulse number for deceleration Pd respectively.

[Note]

- The above calculation formula is an ideal expression and slight differences will be made in the actual IC operation.

A-2 Case of S-curve Acceleration/Deceleration Driving

(CLK = 16MHz)



DV : Drive speed[pps]
SV : Initial speed[pps]
JK : Jerk[pps/sec²]
ta : Acceleration time [sec]
Pa : Pulse number for acceleration

Acceleration AC is fixed to 1FFF FFFFh.

©Calculation Formula of jerk JK when initial speed SV, drive speed DV and acceleration time ta are given

$$\text{Jerk JK} = \frac{4(DV - SV)}{t_a^2} \quad [\text{pps/sec}^2]$$

©Calculation Formula of acceleration time ta when initial speed SV, drive speed DV and jerk JK are given

$$\text{Acceleration time } t_a = 2 \sqrt{\frac{DV - SV}{JK}} \quad [\text{sec}]$$

©Calculation Formula of pulse number for acceleration Pa when initial speed SV, drive speed DV and jerk JK are given

$$\text{Pulse number for acceleration } P_a = (DV + SV) \sqrt{\frac{DV - SV}{JK}}$$

Deceleration increasing rate DJ, deceleration time td and pulse number for deceleration Pd can be calculated by replacing jerk JK, acceleration time ta and pulse number for acceleration Pa with deceleration increasing rate DJ, deceleration time td and pulse number for deceleration Pd respectively.

[Note]

- The above calculation formula does not hold true in partial S-curve acceleration/deceleration driving.
- The above calculation formula is an ideal expression and slight differences will be made in the actual IC operation.

Appendix B Parameter Calculation Formula when Input Clock except 16MHz

When MCX501 input clock frequency is f_{CLK} (Hz), setting values of each speed and timer are as follows.

$$\begin{aligned}
 \text{Initial speed [pps]} &= SV \times \frac{f_{CLK}}{16 \times 10^6} \\
 \text{Drive speed [pps]} &= DV \times \frac{f_{CLK}}{16 \times 10^6} \\
 \text{Acceleration [pps/sec]} &= AC \times \left(\frac{f_{CLK}}{16 \times 10^6} \right)^2 \\
 \text{Deceleration [pps/sec]} &= DC \times \left(\frac{f_{CLK}}{16 \times 10^6} \right)^2 \\
 \text{Jerk [pps/sec}^2] &= JK \times \left(\frac{f_{CLK}}{16 \times 10^6} \right)^3 \\
 \text{Deceleration increasing rate [pps/sec}^2] &= DJ \times \left(\frac{f_{CLK}}{16 \times 10^6} \right)^3 \\
 \text{Home search speed [pps]} &= HV \times \frac{f_{CLK}}{16 \times 10^6} \\
 \text{Speed increasing / decreasing value [pps]} &= IV \times \frac{f_{CLK}}{16 \times 10^6} \\
 \text{Timer value [\mu sec]} &= TM \times \frac{16 \times 10^6}{f_{CLK}}
 \end{aligned}$$

[Symbol]

- SV : Initial speed setting
- DV : Drive speed setting
- AC : Acceleration setting
- DC : Deceleration setting
- JK : Jerk setting
- DJ : Deceleration increasing rate setting
- HV : Home search speed setting
- IV : Speed increasing / decreasing value setting
- TM : Timer value setting

Synchronous pulse output width (synchronous action), deviation counter clear output signal width (automatic home search), timer time between steps (automatic home search) and input signal delay time (input signal filter) require correction by using

$$\frac{16 \times 10^6}{f_{CLK}} \text{ respectively.}$$

Appendix C Differences with MCX300 series

Main differences between MCX300 series and MCX501 are as follows.

For details of functions, please refer to each description in this manual.

	Item	MCX300 series	MCX501
1	Treatment of unused input pins	Can open. (pulled up to VDD in the IC)	Must be connected to VDD or GND. (not pulled up in the IC)
2	Width of reset signal (RESETN)	Requires more than 4 CLK cycles	Requires more than 8 CLK cycles
3	Command reset	Writes 8000h (D15 bit: 1) into WR0 register.	Writes 00FFh into WR0 register.
4	Setting of speed parameter	Speed range setting is provided. (multiple: 1~500) Speed parameter should be set based on the actual value and multiple.	No speed range setting (speed range-free) Speed parameter is set the actual value.
5	Fixed pulse driving	• + Direction fixed pulse driving Specifies output pulse number as positive value. When executed, it drives specified pulses in the + direction. • - Direction fixed pulse driving Specifies output pulse number as positive value. When executed, it drives specified pulses in the - direction.	• Relative position driving Specifies output pulse number as positive value and when executed, it drives specified pulses in the + direction. Specifies output pulse number as negative value and when executed, it drives specified pulses in the - direction. • Counter relative position driving Specifies output pulse number as positive value and when executed, it drives specified pulses in the - direction. This is a driving command corresponding to - direction fixed pulse driving of MCX300 series. • Absolute position driving As the finish point of driving, specifies logical position counter value that is a destination point
6	RR2 register / Error information display (Software limit and hardware limit signal, alarm signal from a servo driver and emergency stop signal)	Even though driving stops, if error factor becomes active, error information bit becomes 1. And when error factor is cleared, error information bit returns to 0.	If error factor becomes active during the driving (or error factor is active at the start of driving), error information bit becomes 1 and will keep 1 even after error factor is cleared. If error factor becomes active at the termination of driving, it does not error. All the bits return to 0 by error/finishing status clear command (79h) or the start of next driving.
7	Enable / disable of hardware limit function	Function of hardware limit signals (nLMTP and nLMTM) (LMT+ and LMT- in MCX305) cannot be disabled.	Function of hardware limit signals (LMTP and LMTM) can be enabled / disabled.
8	Setting of software limit value	Sets software limit value to compare register (COMP+, COMP-) Because of this, when using compare register as software limit, the other function of compare register cannot be used.	Sets software limit value to a dedicated register (SLMT+, SLMT-).
9	Stop type of software limit	Only decelerating stop	Selectable from decelerating stop or instant stop.
10	Trapezoid triangle form prevention	At reset: Disabled	At reset: Enabled
11	Acceleration counter offsetting	At reset: 8	At reset: 0
12	Command code and mode setting bit	—	Differs from MCX300 series.