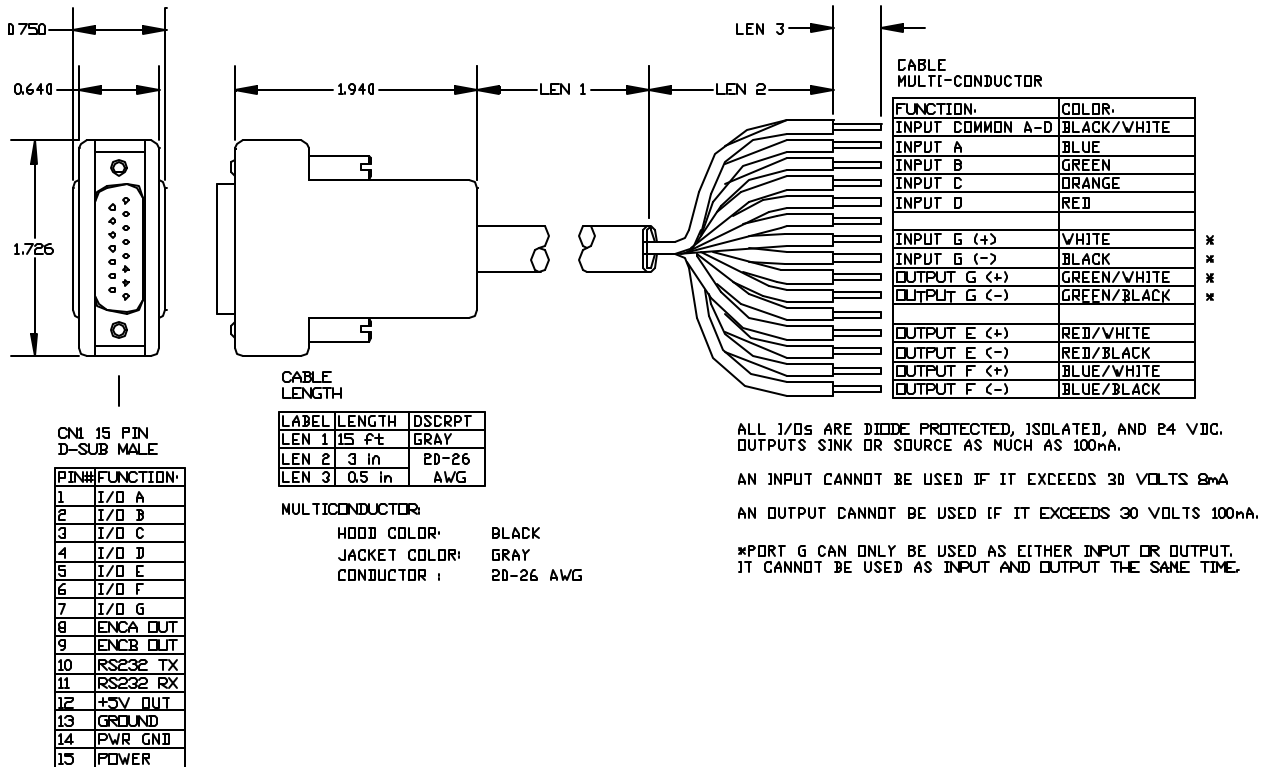


Overview

The CLBIO43-52x¹ is a cable with a DB15 connector that converts 5VDC Servida Motor I/O to 24VDC I/O. The user has the option of using the CLBIO43-52 cable with four digital inputs and three digital outputs or five digital inputs and two outputs. This cable connects directly into the Servida Motor's DB 15 I/O connector (CN2) on the SV23xxD and SV34xxD series.



Inputs A to D can be set to either all sourcing or sinking inputs. Port G input is independent from input A to D. Outputs E, F, and G are wired independently so they can either be sourcing or sinking.

RATING:

Input

min. voltage	24 VDC
max. voltage	30 VDC
min. current	5 mA
max. current	8 mA

Output

max. voltage	30 Vdc
max. current	100 mA

Damage may occur if these maximum ratings are exceeded.

¹ If x is H, cable is 5m long

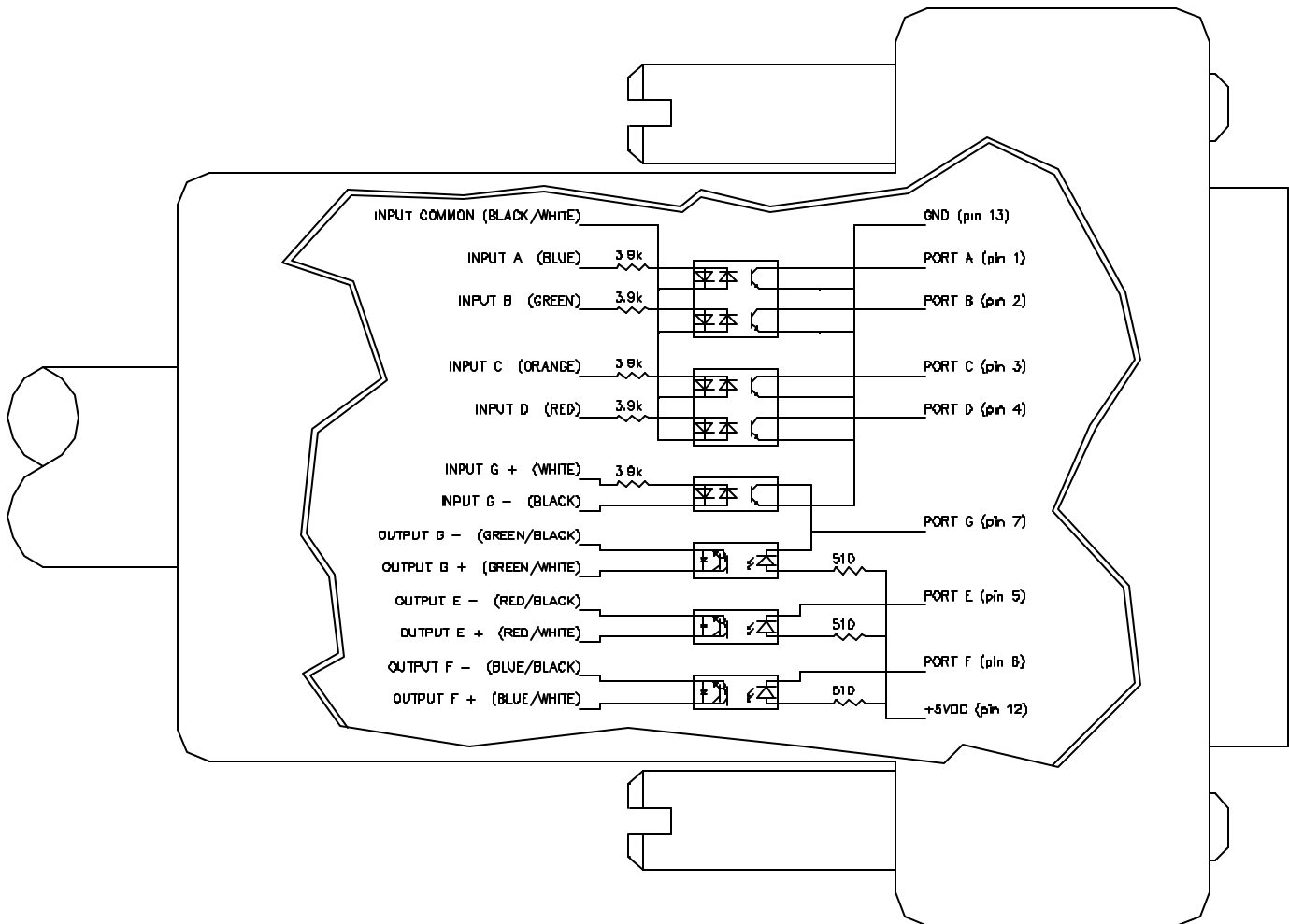
If x is -10M, cable is 10m long

Servida Motor Interface

The CLBIO43-52 cable uses the Servida Motor's I/O pins as listed:

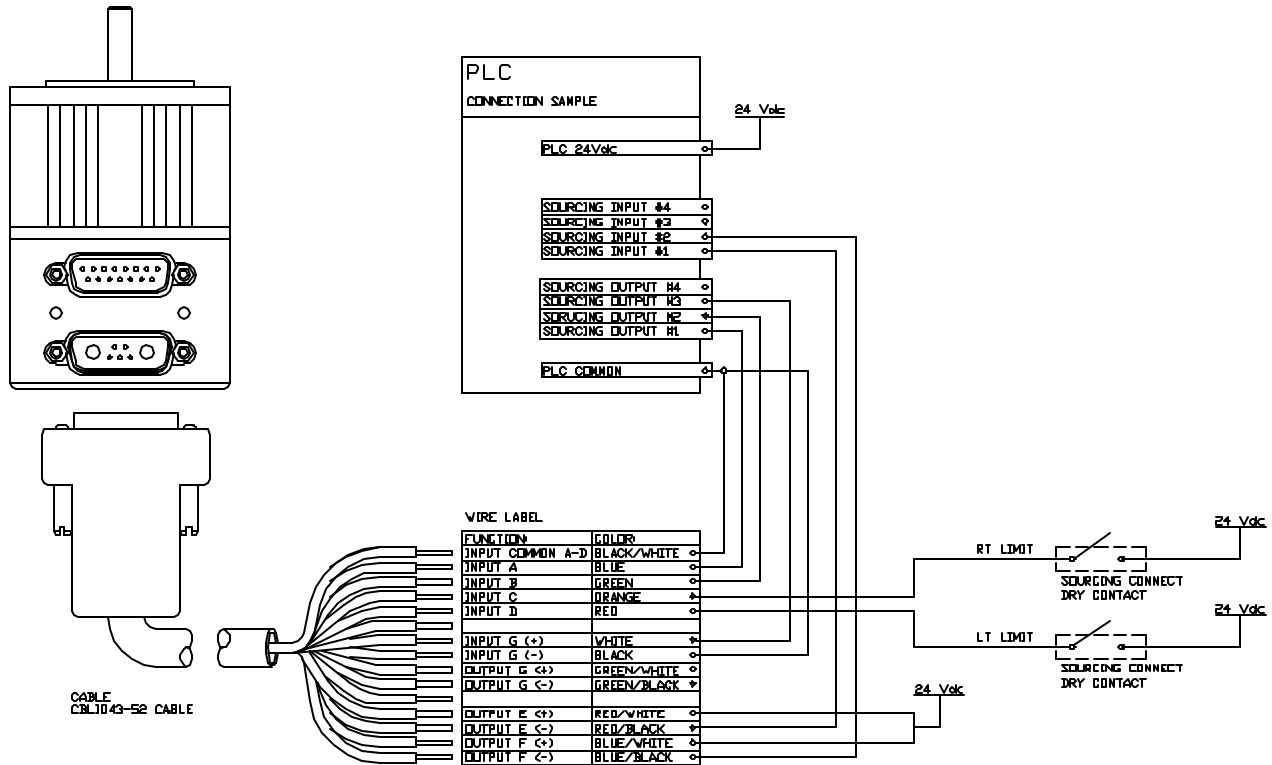
PIN	SIGNAL	DESCRIPTION
1	input A	Digital input A / Encoder input A / Step input (input frequency 50kHz)
2	input B	Digital input B / Encoder input B / direction input (input frequency 50kHz)
3	input C	Digital input C / Positive Limit
4	input D	Digital input D / Negative Limit
5	output E	Digital output E
6	output F	Digital output F
7	input/output G	Digital input G / Digital output G (can only use either input or output)
12	+5Vdc	+5Vdc output
13	GND	Signal Ground

Schematic



Application

The CLBIO43-52 cable is used to interface the Servida Motor with a PLC and some coil relay. A sample application wiring is shown below:



The above diagram is an example of using the CLBIO43-52 cable to interface the Servida Motor with a PLC. The sample program below reads output signal from the PLC to determine which predefined profile to run. After a move completed, the Servida Motor will signal back to the PLC. Also, the Servida Motor will send outputs to if the an error occurred.

'SAMPLE PROGRAM USING I/O

```
'INPUT A to C for PLC profile selection
'INPUT D for read ready
'OUTPUT G motor signal PLC after motion completed
'OUTPUT E and F to turn on/off pump and value
'
'initialize I/O ports
UAI      'initialize port A as input, signal input bit 0
UBI      'initialize port B as input, signal input bit 1
UCP      'initialize port C as RT Limit input
UDM      'initialize port D as LT Limit input
UE=1     'set output E off
UEO      'initialize port E as output, trajectory start(high)/ended(low)
UF=1     'set output F off
UFO      'initialize port F as output, fault(high)
UGI      'initialize port G as input, read ready trigger

'set Acceleration/velocity
MP       'set motor to ModePosition
A=8*100  'set acceleration to 100 rps^2 for motors with 500 line encoder
V=32212*30 'set velocity to 30 rps for motors with 500 line encoder
```

```

'read/check input loop
WHILE 1
  WHILE UGI==1 LOOP
    UF=1
    ab[0]=UAI
    ab[1]=UBI*2
    a=ab[0]+ab[1]
    SWITCH a
      CASE 0
        PRINT("CASE 0 move to P=8000",#13)
        P=8000
        GOSUB0
      BREAK
      CASE 1
        PRINT("CASE 1 move to P=10000",#13)
        P=10000
        GOSUB0
      BREAK
      CASE 2
        PRINT("CASE 2 move to P=-8000",#13)
        P=-8000
        GOSUB0
      BREAK
      CASE 3
        PRINT("CASE 3 move to P=-10000",#13)
        P=-10000
        GOSUB0
      BREAK
    ENDS
  LOOP
END

C0
UE=0
G
TWAIT
UE=1
IF Be
  PRINT("excessive position error ocured",#13)
  UF=0
ENDIF
IF Bp
  PRINT("RT Limit reached",#13)
  UF=0
ENDIF
IF Bm
  PRINT("LT Limit reached",#13)
  UF=0
ENDIF
IF Bh
  PRINT("Over Temperature Occured",#13)
  UF=0
ENDIF
RETURN

```

'infinite WHILE LOOP
'gate, waiting for PLC read ready signal
'reset the fault output if any
'if input A triggered, UAI will read 0,
' otherwise ab[0] is 1
'if input B triggered, UBI will read 0,
' otherwise ab[1] is 2
'summing up the binary values
'comparing each binary value with the
' SWITCH/CASE
' statement
'CASE 0 when B A triggered (0 0)
'set position value
'GO to SUBroutine C0 to start motion and
' error handling
'BREAK out of SWITCH statement
'CASE 1 when B _ triggered (0 1)
'set position value
'GO to SUBroutine C0 to start motion and
' error handling
'CASE 2 when _ A triggered (1 0)
'set position value
'GO to SUBroutine C0 to start motion and
' error handling
'CASE 3 when _ _ triggered (0 0)
'set position value
'GO to SUBroutine C0 to start motion and
' error handling
'ENDS for closing SWITCH statement
'LOOP for closing WHILE statement

'END marks end of program

'Label for subroutine C0
'output high, trajectory started
'start trajectory (motion)
'wait until trajectory ends (motion stopped)
'reset signal to RESET MOTION (low) signal to PLC
'checking excessive position error bit
'print to terminal window
'set fault signal (high)

'checking RT limit bit
'print to terminal window
'set fault signal (high)

'checking LT limit bit
'print to terminal window
'set fault signal (high)

'checking over temperature bit
'print to terminal window
'set fault signal (high)

'RETURN to main program

You probably noticed that the motor is reading the signal low when high signal is being sent to the CLBIO43-52 cable. If you prefer the motor to read a high signal when high signal is being sent to the cable, you can mask the input value by using the following command:

```
a=UAI==0          'this sets a to 1 if UAI is true, which in this case if UAI is 0
                  ' (low)
```

I/O Commands:

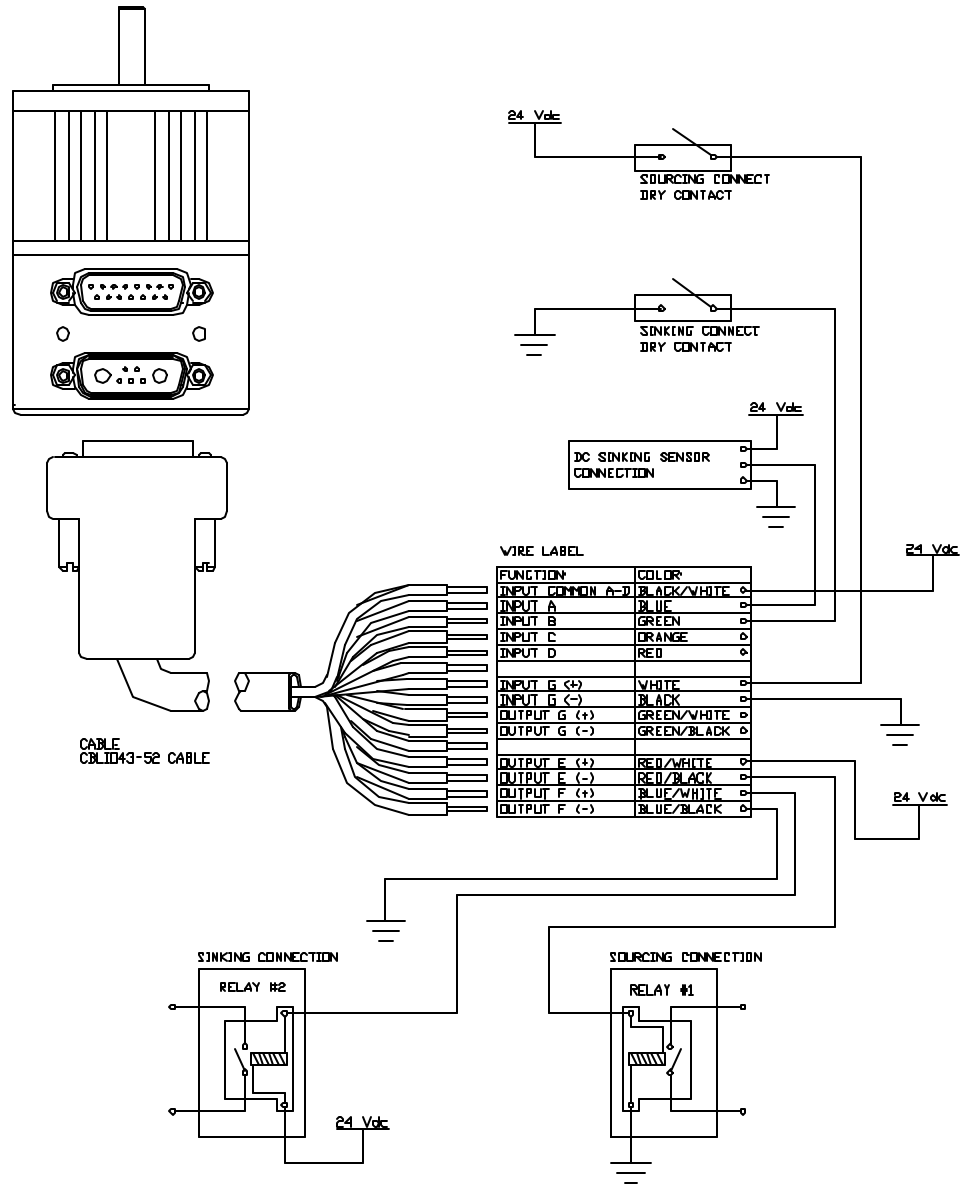
```
UAI          'initialize port A as input
UBI          'initialize port B as input
UCI          'initialize port C as input
UDI          'initialize port D as input
UCP          'initialize port C as Right Limit (Port C is right limit by default)
UDM          'initialize port D as Left Limit (Port D is left limit by default)
UGI          'initialize port G as input (port G can only be used as either
UGO          'initialize port G as output   input or output)
UG=1        'set output G off (output line open)
UG=1        'set output G on (output line close)
UEO          'initialize port E as output
UE=1        'set output E off (output line open)
UE=0        'set output E on (output line close)
UFO          'initialize port F as output
UF=1        'set output F off (output line open)
UF=0        'set output F on (output line close)

d=UCI       'store the input state value of port C into variable d

IF UAI
ENDIF

IF UAI==0
ENDIF
```

Sample Wiring Diagram:



For further details about I/O commands and program flows, please refer to the Servida Motor Users Guide.