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## 1. Introduction, Features and Applications

3225 is a very small size microstepping driver based on most advanced technology in the world today. It is suitable for driving any 2-phase and 4-phase hybrid step motors(current 2.5A). By using advanced bipolar constant-current chopping technique, it can output more speed and power from the same motor, compared with traditional technologies such as L/R drivers. Its 3-state current control technology allows coil currents to be well controlled, with relatively small current ripple and therefore less motor heating.

### Features of this driver

- High performance, low cost
- Supply voltage up to +32VDC, current output up to 2.5A peak
- TTL compatible and optically isolated input signals, pulse frequency up to 100 KHz
- Automatic idle-current reduction
- 3-state current control for less motor heating
- Selectable resolutions in 1, 2, 4, 8
- Suitable for 4,6,8 lead motors
- DIP switch current setting with 7 different value
- CW/CCW mode available (optional)
- Small size (86x55x20.5mm)

### Applications of this driver

Suitable for a wide range of stepping motors of NEMA 17 and 23, and usable for various kinds of machines, such as X-Y tables, labeling machines, laser cutters, engraving machines, and pick-place devices. Particularly useful in applications with low vibration, high speed and high precision are desired.

## 2. Specifications and Operating Environment

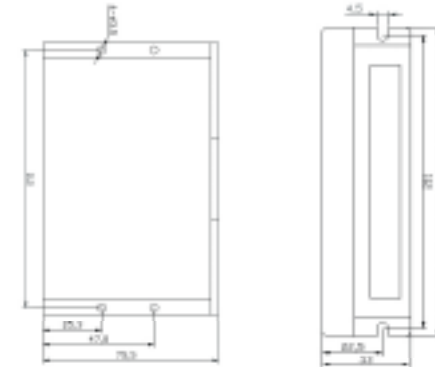
### Electric Specifications (T<sub>i</sub> = 25 °C)

Parameters	3 2 2 5			Unit
	Min.	Typical	Max.	
Output Current	0.39	-	2.5	Amps
Supply voltage (DC)	12	24	32(	VDC
Logic signal current	7	10	16	mA
Pulse input frequency	0	-	100	Khz
Isolation resistance	500			MΩ

### Operating Environment and Parameters

Cooling	Natural cooling or forced convection	
Environment	Space	Avoid dust, oil frost and corrosive gas
	Temperature	0 ° - 50
	Humidity	40 - 90%RH
	Vibration	5.9m/s <sup>2</sup> Max
Storage Temp.	-20 - 125	
Weight	Approx. 0.11 Kg (3.8 oz)	

### Mechanical Dimensions (unit:mm, 1 inch = 25.4 mm)



Front View

Side View

Figure 1: Mechanical dimensions

\*Recommended to use side mounting for better heat dissipation

### Extra Heat Sink

- Driver's reliable working temperature should be  $<65$  , motor temperature  $<80$  ;
- It is recommended automatic half-current mode, i.e. current automatically reduced by 60% when motor stops, so as to decrease driver and motor's heating;
- Please mount the driver vertically to maximize heat sink area.

### 3. Driver Connectors, P1 and P2

The driver has two connectors, P1 for control signals, and P2 for power and motor connections.

The following is a brief description of the two connectors of the driver. More detailed descriptions of the pins and related issues are presented in section 4, 5, 6, 9.

#### Control Signal Connector P1-pins

Signal	Functions
PUL	<u>Pulse signal</u> : in single pulse mode, this input represents pulse signal, effective for each upward – rising edge; in double pulse mode this input represents clockwise(CW)pulse, effective for each upward – rising edge.
DIR	<u>Direction signal</u> : in single-pulse mode, this input represents pulse signal, driving by TTL, used to change motor direction; in double pulse mode, this input represents CCW pulse, effective for each upward-rising edge.
OPTO	power supply driving opto-coupler
ENA	<u>Enable signal</u> : this signal is used for enable/disable, high level for enabling driver and low level for disabling driver. Usually left unconnected(enabled).

*Remark 1:* PUL/DIR is the default mode, under-cover jumper JMP1 can be used to switch to CW/CCW double-pulse mode.

*Remark 2:* Please note motion direction is also related to motor-driver wiring match. Exchanging the connection of two wires for a coil to the driver will reverse motion direction. (for example, reconnecting motor A+ to driver A- and motor A- to driver A+ will invert motion direction).

#### Power connector P2 pins

Signal	Functions
Gnd	DC power ground
+V	DC power supply, +12VDC - +32VDC, Including voltage fluctuation and EMF voltage. Recommended to use +24VDC.
A	Motor coil A (leads A+ and A-)

B	Motor coil B (leads B+ and B-)
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### 4. Control Signal Connector (P1) Interface

This driver uses differential inputs to increase noise immunity and interface flexibility. Single-ended control signals from the indexer/controller can also be accepted by this interface. The input circuit has built-in high-speed opto -coupler, and can accept signals in the format of line driver, open-collector, or PNP output. Line driver (differential) signals are suggested for reliability. In the following figures, connections to open-collector and PNP signals are illustrated.

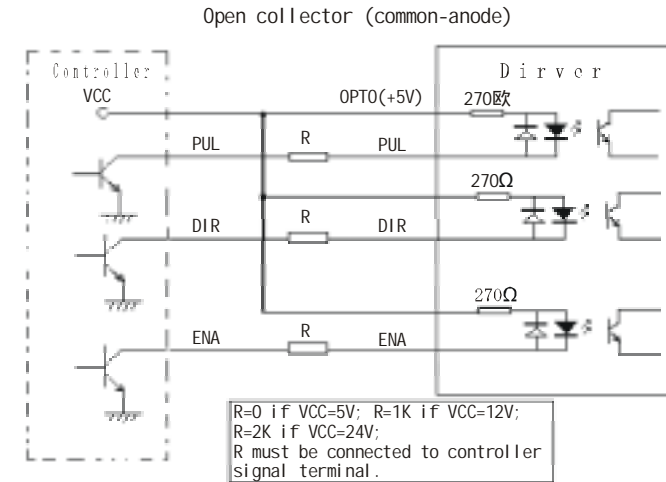


Figure 2: Signal interface (common-anode)

#### PNP Output

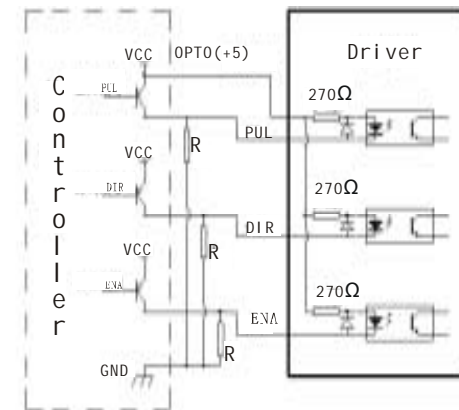


Figure 3: Signal interface (common-cathode)

**Selecting CW/CCW and PUL/DIR Mode**

There is a jumper JMP3 inside the driver specifically for the purpose of selecting pulse signal mode. Settings for one-pulse mode (PUL/DIR) and for double-pulse mode (CW/CCW) are shown on the following. Default mode out of factory is PUL/DIR mode.



J3 open collector  
PUL/DIR mode



J3 short circuit  
CW/CCW mode

**5. Driver Connection to Step Motors**

3225 driver can drive any 4, 6, 8 lead hybrid step motors. The following diagrams illustrate connection to various kinds of motor leads:

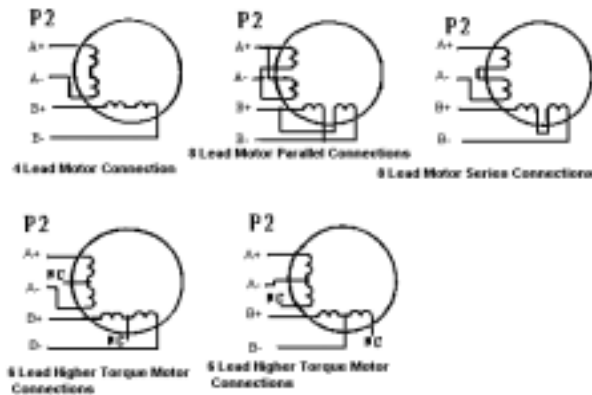


Figure 3: Driver Connection to Step Motor

Note that when two coils are parallelly connected, coil inductance is reduced by half and motor speed can be significantly increased. Serial connection will lead to increased inductance and thus the motor can be run well only at lower speeds.

**5.1 Connecting to 8-Lead Motors**

8 lead motors offer a high degree of flexibility to the system designer in that they may be connected in series or parallel, thus satisfying a wide range of applications.

**Series Connection**

A series motor configuration would typically be used in applications where a higher torque at lower speeds is required. Because this configuration has the most inductance, the performance will

start to degrade at higher speeds. Use the per phase (or unipolar) current rating as the peak output current, or multiply the bipolar current rating by 1.4 to determine the peak output current.

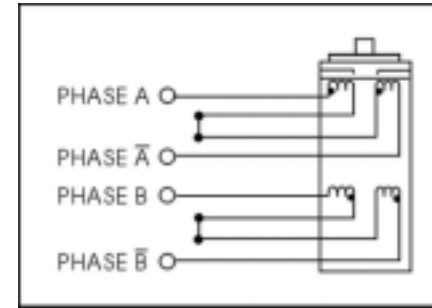


Figure 4: 8 Lead Motor Series Connections

**Parallel Connection**

An 8 lead motor in a parallel configuration offers a more stable, but lower torque at lower speeds. But because of the lower inductance, there will be higher torque at higher speeds. Multiply the per phase (or unipolar) current rating by 1.96, or the bipolar current rating by 1.4, to determine the peak output current.

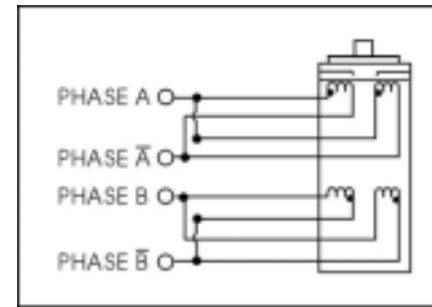


Figure 5: 8 Lead Motor Parallel Connections

**5.2 Connection to 6-Lead Motors**

Like 8 lead stepping motors, 6 lead motors have two configurations available for high speed or high torque operation. The higher speed configuration, or half coil, is so described because it uses one half of the motor's inductor windings. The higher torque configuration, or full coil, use the full windings of the phases.

**Half Coil Configuration**

As previously stated, the half coil configuration uses 50% of the motor phase windings. This gives lower inductance, hence, lower torque output. Like the parallel connection of 8 lead motor, the

torque output will be more stable at higher speeds. This configuration is also referred to as balanced copper. In setting the driver output current multiply the specified per phase (or unipolar) current rating by 1.4 to determine the peak output current.

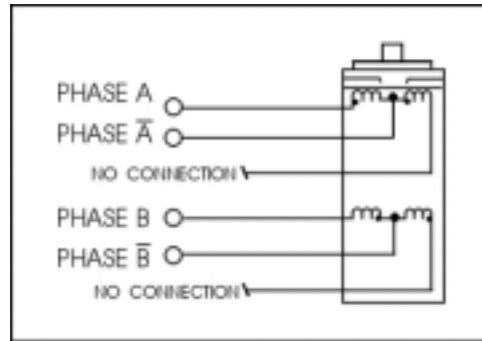


Figure 6: 6 Lead Half Coil (Higher Speed) Motor Connections

#### Full Coil Configuration

The full coil configuration on a six lead motor should be used in applications where higher torque at lower speeds is desired. This configuration is also referred to as full copper. Use the per phase (or unipolar) current rating as the peak output current.

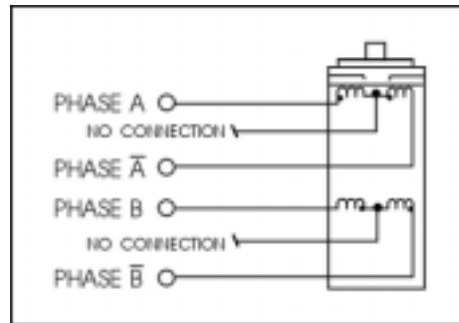


Figure 7: 6 Lead Full Coil (Higher Torque) Motor

### 5.3 Connection to 4-Lead Motors

4 lead motors are the least flexible but easiest to wire. Speed and torque will depend on winding inductance. In setting the driver output current, multiply the specified phase current by 1.4 to determine the peak output current.

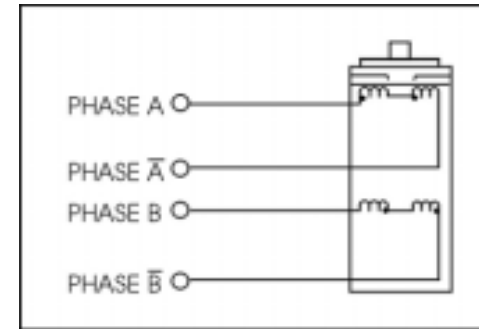


Figure 8: 4 Lead Motor Connections

## 6. Power supply Selection, Driver Voltage and Current Selection

### 6.1 Power Supply Selection

It is important to choose appropriate power supply to make the driver operate properly and deliver optimal performance.

#### Maximum Voltage Input:

The power MOSFETS inside the driver can actually operate within +12V - +32VDC, including power input fluctuation and back EMF voltage generated by motor coils during motor shaft deceleration. Higher voltage will damage the driver. Therefore, it is suggested to use power supplies with theoretical output voltage of no more than +32V, leaving room for power line fluctuation and Back EMF.

#### Regulated or Unregulated power supply:

Both regulated and unregulated power supplies can be used to supply DC power to the driver. However, unregulated power supplies are preferred due to their ability to withstand current surge. If regulated power supply (such as most switching supplies.) is indeed used, it is important to have large current output rating to avoid problems like current clamp, for example using 4A supply for 3A motor-driver operation. On the other hand, if unregulated supply is used, one may use a power supply of lower current rating than that of motor (typically 50% ~ 70% of motor current). The reason is that the driver draws current from the power supply capacitor of the unregulated supply only during the ON duration of the PWM cycle, but not during OFF duration. Therefore, the average current withdrawn from power supply is considerably less than motor current. For example, two 3A motors can be well supplied by one power supply of 4A rating.

**Multiple drivers:**

It is recommended to have multiple drivers to share one power supply to reduce cost, provided that the supply has enough capacity. To avoid cross interference, **DO NOT** daisy-chain the power supply input pin of the drivers. (instead, please connect them to power supply separately.)

Higher supply voltage will allow higher motor speed to be achieved, at the price of more noise and heating. If the motion speed requirement is low, it's better to use lower supply voltage to improve noise, heating and reliability.

NEVER connect power and ground in the wrong direction, as it will damage the driver.

**6.2 Driver Voltage and Current Selection**

This driver can match small and medium size step motors (NEMA 17 and 23) made by Leadshine or other motor manufactures from around the world. To achieve good driving results, it is important to select supply voltage and output current properly. Generally, supply voltage determines the high speed performance of the motor, while output current determines the output torque of the driven motor (particularly at lower speed).

**Selecting Supply Voltage:**

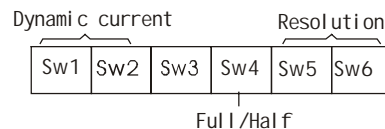
Higher supply voltage can increase motor torque at higher speeds, thus helpful for avoiding losing steps. However, higher voltage may cause more motor vibration at lower speed, and it may also cause over-voltage protection and even driver damage. Therefore, it is suggested to choose only sufficiently high supply voltage for intended applications.

**Setting Proper Output Current**

- For a given motor, higher driver current will make the motor to output more torque, but at the same time causes more heating in the motor and driver. Therefore, output current is generally set to be such that the motor will not overheat for long time operation.
- Since parallel and serial connections of motor coils will significantly change resulting inductance and resistance, it is therefore important to set driver output current depending on motor phase current, motor leads and connection methods.
- Phase current rating supplied by motor manufacturer is important to selecting driver current, but the selection also depends on leads and connection.

**7. Selecting Microstep Resolution and Driver Current Output**

This driver uses an 6-bit DIP switch to set microstep resolution, and motor operating current, as shown below:

**7.1 Microstep Resolution Selection**

Microstep resolution is set by SW5, 6 of the DIP switch as shown in the following table:

Microstep	$\mu$ -step/rev.(for 1.8 ° motor)	SW5	SW6
1	200	ON	ON
2	400	OFF	ON
4	800	ON	OFF
8	1600	OFF	OFF

**7.2 Current Setting**

The first three bits (SW1, 2, 3) of the DIP switch are used to set the current during motion (dynamic current). Select a setting closest to your motor's required current.

**● DIP Setting for current during motion:**

Peak current	SW1	SW2	SW3
0.39A	OFF	ON	ON
0.71A	ON	OFF	ON
1.10A	OFF	OFF	ON
1.42A	ON	ON	OFF
1.81A	OFF	ON	OFF
2.13A	ON	OFF	OFF
2.52A	OFF	OFF	OFF

Remarks:

Due to motor inductance the actual current in the coil may be smaller than the dynamic current settings, particularly at higher speeds.

**● DIP setting for current during standstill:**

SW4 is used for this purpose, current setting due to coil inductance. OFF meaning that the standstill current is set to be half of the dynamic current, and ON meaning that standstill current is set to be the same as dynamic current.

The current automatically reduced to 60% of dynamic current setting 0.2 second after the last pulse. This will, theoretically, reduce motor heating to 36% (due to  $I^2R$ ) of the original value. If the application needs a different idle current, please contact Leadshine for minor modification of circuit.

**8. Change microstep resolution on-the-fly**

In case microstep resolution should be changed on-the-fly, please inform Leadshine Technology in advance for special OEM manufacture. Pay attention of:

- SW5, SW6 must be OFF;
- "HOME" must be HIGH, otherwise inposition will be inaccurate.

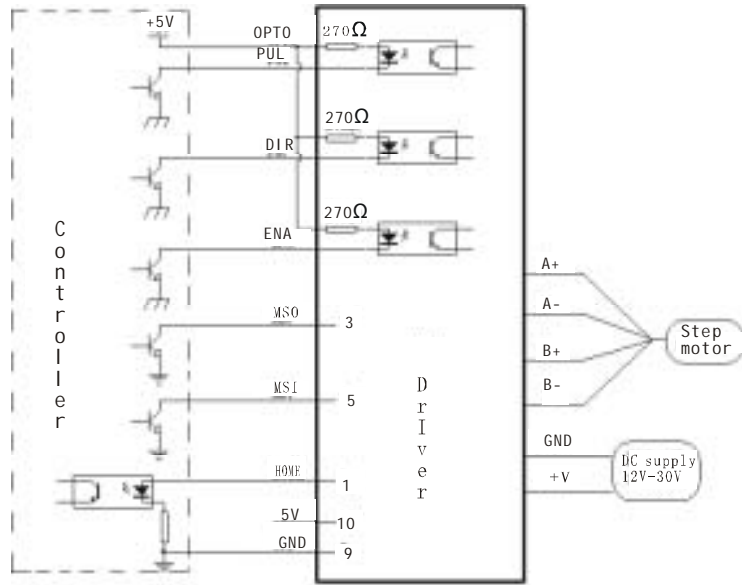


Figure 10: connection diagram

### 9. Connection Diagram for Driver, Motor, Controller

A complete stepping system should include stepping motor, stepping driver, power supply and controller (pulse generator).

A typical connection is shown below:

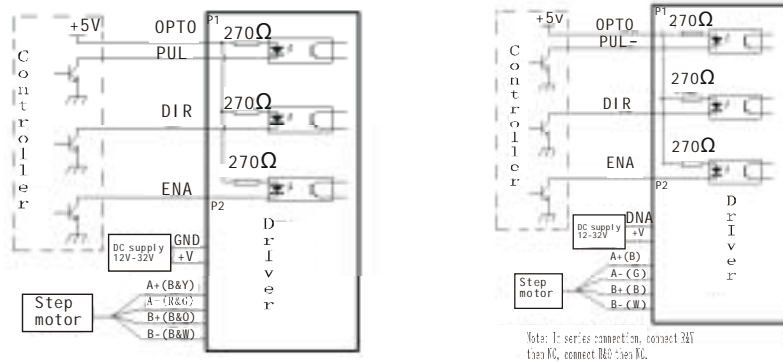
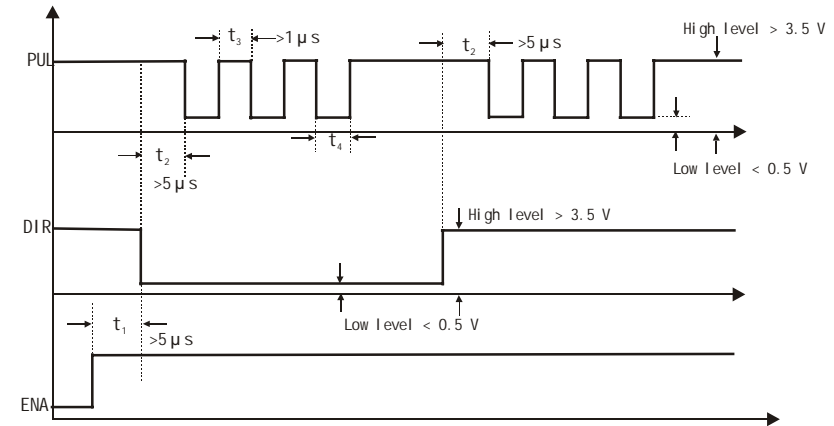


Figure 9: Driver connection in a stepping system

### 10. Control signal Waveform and Timing

In order to avoid some fault operation and deviation, PUL, DIR and ENA must accord with some parameters, as following diagram:



#### Remark:

- (2) t1: ENA must be ahead of DIR by at least 5us, logic HIGH as valid. Generally ENA+ and ENA- is NC (not connected).
- (3) t2: DIR must be ahead of PUL effective falling edge by 5us to ensure correct direction;
- (4) t3: Pulse width not less than 5us;
- (5) t4: low level width not less than 5us.

### 11. Wire Connection

1. In order to improve driver noise rejection, it is recommended to use twisted pair shield cable.
2. To prevent noise incurred in pulse/dir signal, Pulse/direction signal wires and motor wires should not be tied up together. It is better to separate them by at least 10 cm, otherwise the motor noise will easily disturb pulse direction signals, motor position error, system instability and other types of failure.
3. If a power supply serves several drivers, separate connections drivers is recommended instead of daisy-chaining.

4. It is prohibited to pull and plug connector P2 while driver is powered ON, as there is still high current flowing through coil even when motor is stopped. Pulling and plugging P2 with power on will cause extremely high voltage surge EMF, destroy the driver..

particular purpose. Some jurisdictions do not allow limitations on how long and implied warranty lasts, so the above limitation or exclusion may not apply to you. However, any implied warranty of merchantability or fitness is limited to the 12-month duration of this written warranty.

***Shipping Failed Product***

If your product should fail during the warranty period, e-mail customer service at [tech@leadshine.com](mailto:tech@leadshine.com) to obtain a returned material authorization number (RMA) before returning product for service. Please include a written description of the problem along with contact name and address. Send failed product to distributor in your area or: Leadshine Technology Co., Ltd. Floor 6, Block B, Yuehai Building, Nanhai Avenue, Shenzhen, China. Also enclose information regarding the circumstances prior to product failure.