PMC-1202 PC Manager MANUAL

Research & Development Center

2013.03.22

PIEZO TECH

PIEZOELECTRIC TECHNOLOGY

Revision History

Version	Date	Changes	Status	Author/Approver
1	2013/03/22	First revision	draft	Jongmin choi

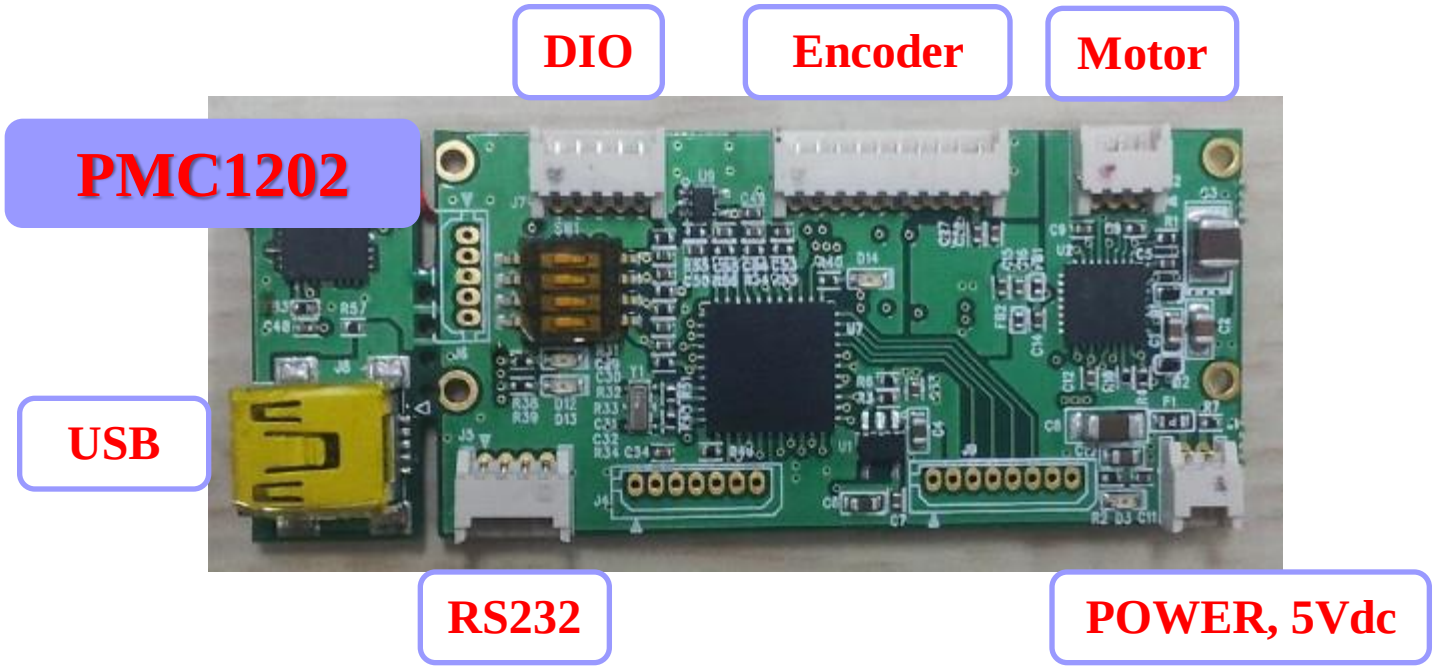
- The information is subject to change without notice for technical improvement.

CONTENTS

1. Introduction
2. USB to Serial Driver Setup
3. How to Install OCX
4. Serial Port setting
5. Configuration
6. Move to Position(PTP)
7. Open-Loop Control
8. Contact Information

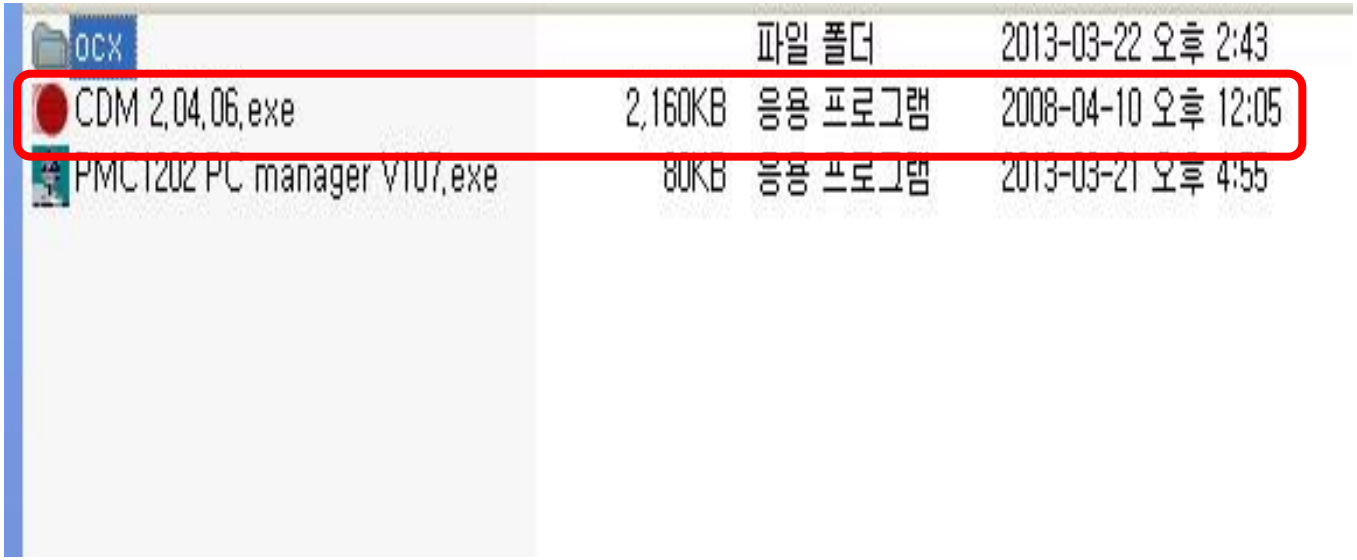
1. INTRODUCTION

1. This user manual provides information about the PC manager of PMC-1202
2. Reference documents
   - PMC1202 Technical description _Vxxx.pdf
   - PMC1202 UART Command reference manual _Vxxx.pdf



2. USB to SERIAL Driver Setup

1. Execute the "CDM 2.04.06.exe" that is attached



2. You can download the file in this website (http://www.ftdichip.com)

3. Once the attached file is executed, you don't need to execute it

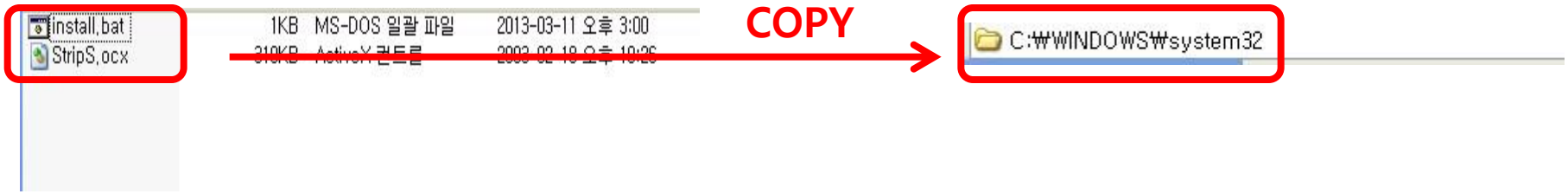
3. How to Install OCX

1. Windows XP

- Step1: Run "install.bat"

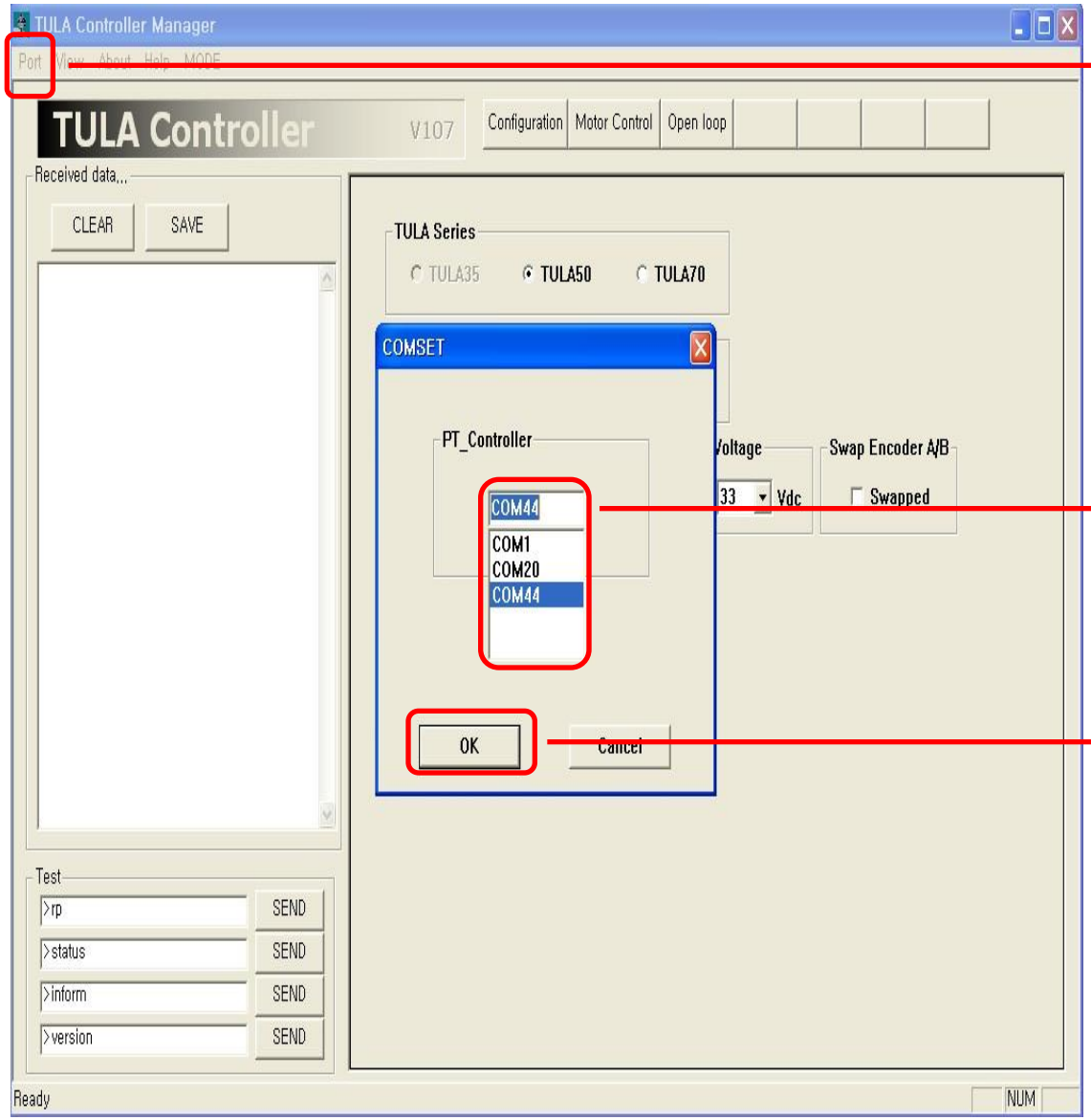
2. Windows 7, 8

- Step1: Copy "strips.ocx" and "install.bat" to "C:₩Windows₩system32."



- Step2: Run "install.bat" in administrator privileges mode which is selected using right-click of mouse.

4. Serial Port Setting

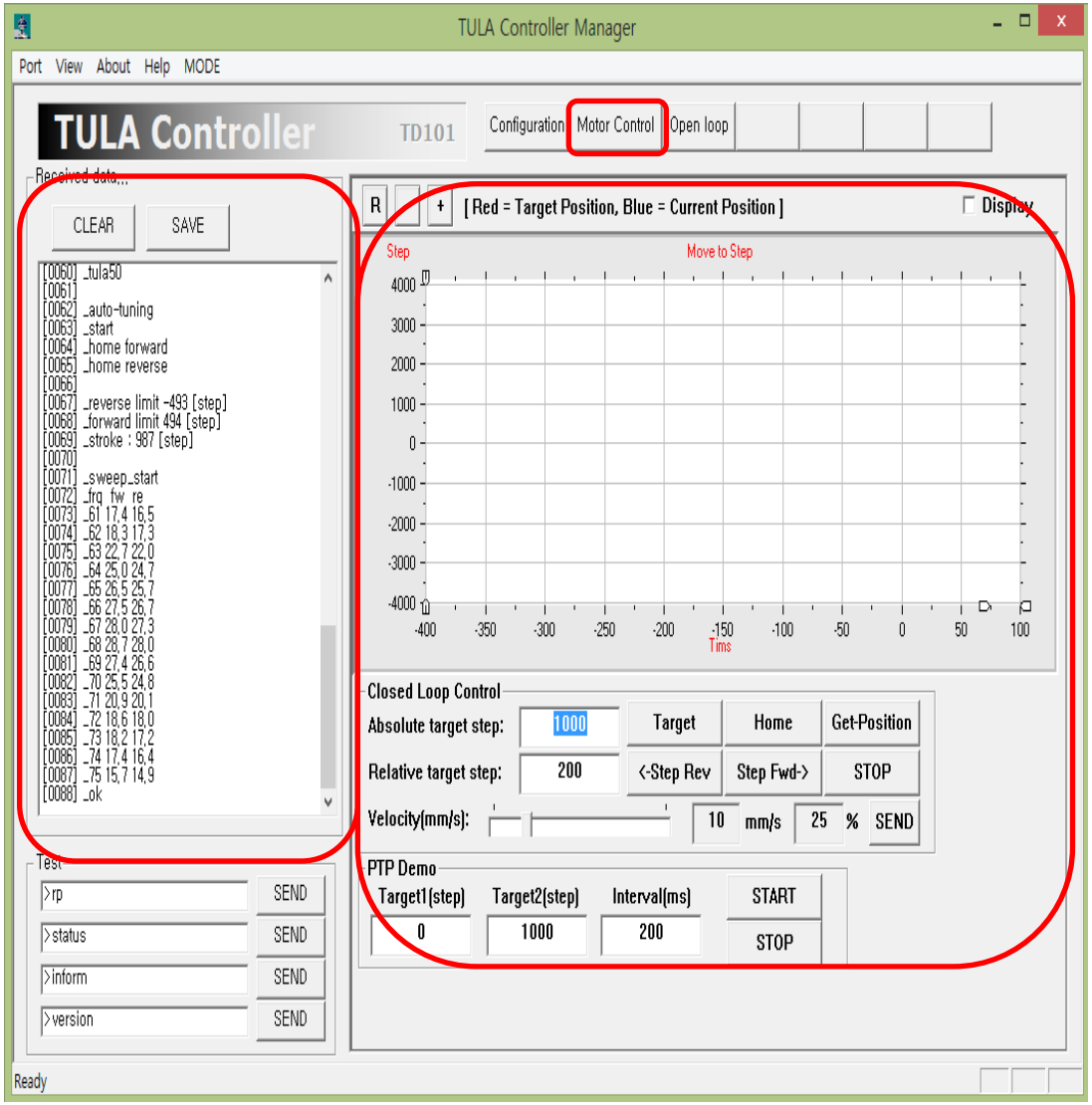


Step1: Click "Port" icon on menu bar

Step2: Select the proper COM-port

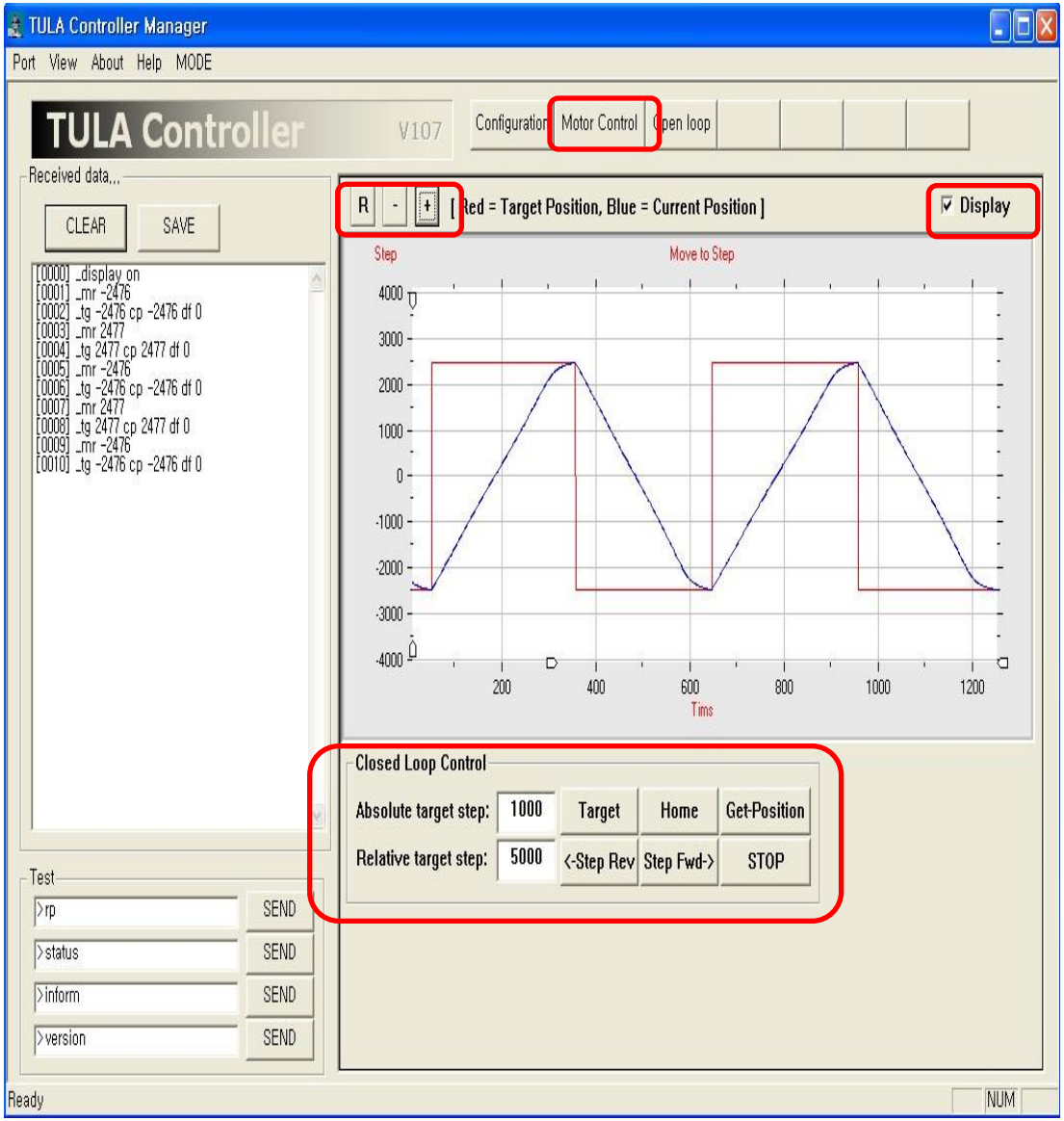
Step3: Click [OK]

5. Configuration



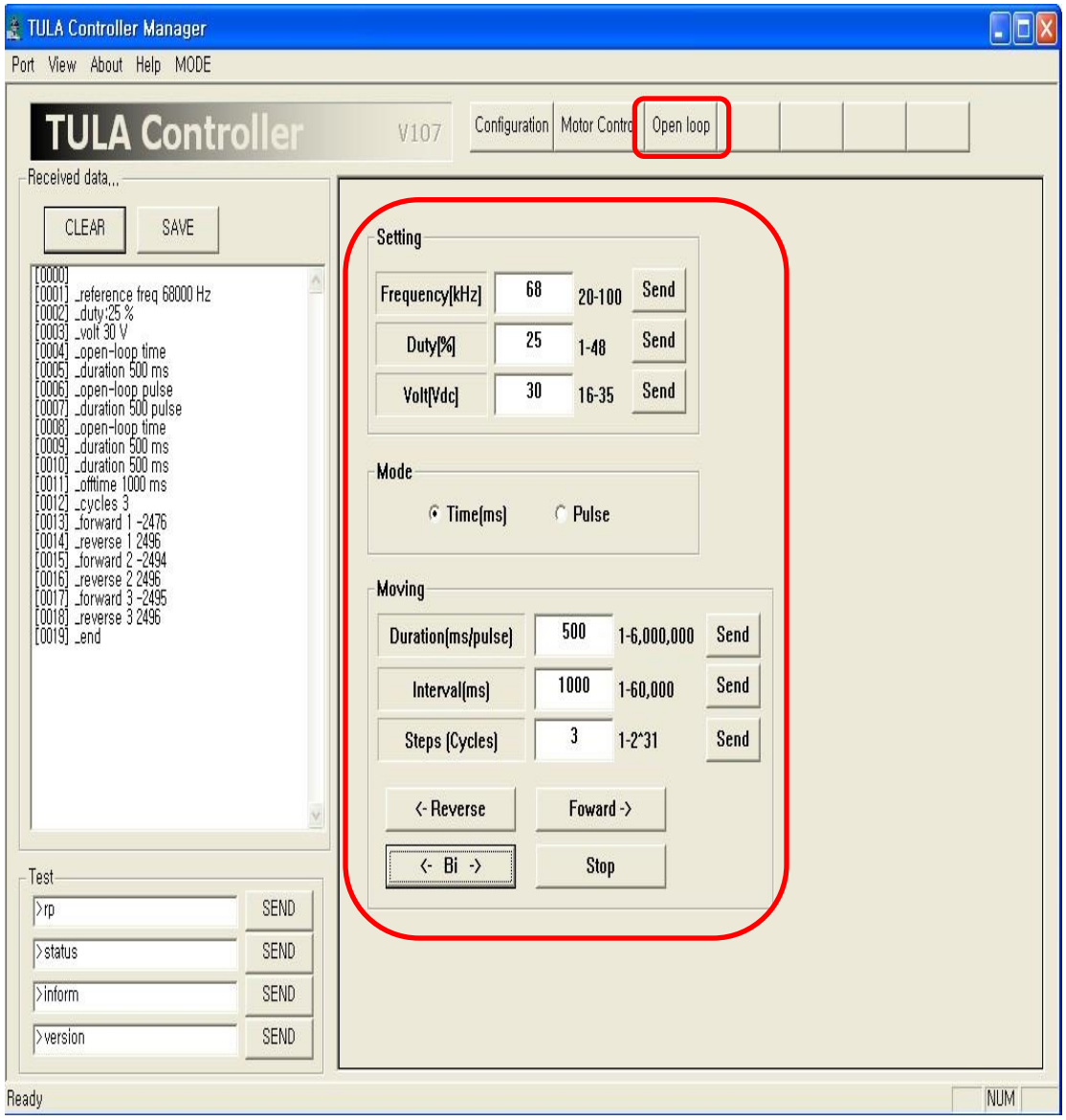
- [TULA Series]:Define the motor type
- [Encoder Type]:Define the encoder type
- [Resolution]:Define the resolution of encoder
- [Reference Frequency]:Define the driving frequency
- [Voltage]:Define the voltage
- [Swap Encoder A/B]:Swap encoder A and encoder B inputs
- [Configuration]:Configuration commands input
- [Auto-Tuning]:Automatic tuning
- [STOP]:Aborts the motion immediately.
- [Get-Information]:Reports the internal setting of controller

6. Move to Position(PTP)



- [Display]: During motion, the motion status can be continuously monitored.
- Red = Target Step.
- Blue = Current Step.
- [+]: Zoom in
- [-]: Zoom out
- [R]: Reset to the scale
- [Home]: Move to the home position.
- [Target]: Move to the absolute target position. The target position can be specified absolute position, using the absolute position parameter.
- [<Step Rev],[Step Fwd>]: Move to the relative target position. The target position can be specified relatively to the current desired position, using the relative position parameter.
- [STOP]: Aborts the motion immediately.
- [Get-Position]: Reports the actual controller position.(Encoder value)

7. Open-Loop Control



- [Frequency]: Define the driving frequency (20~100kHz)
- [Duty]: Define the duty(1~48%)
- [Volt]: Define the voltage(16~35Vdc)
- [Time]: Time Duration.
- [Pulse]: Pulse Duration.
- [Duration]: The moving on-time.
- [Interval]: The time between the start of each step.
- [Steps]: The optional number of run.
- [<Reverse]: Motor runs in reverse.
- [Forward>]: Motor runs forward.
- [<Bi>]: Move to both direction.
- [Stop]: Aborts the motion immediately

8. Contact Information

1. Contact your local distributor or Piezoelectric Technology Co., Ltd.

2. Head Office

Room 501, 503 Sinnae Technotown, 485 Sangbogn1dong, Jungrang-gu, Seoul, Korea. 131-863

Tel: +82-2-3421-0370~3

Fax: +82-2-3421-0374

Web site: www.piezo-tech.com

Email: piezo-tech@piezo-tech.com