

# **User Manual**

**Part 1: I-8090 3-axis encoder card**

**Part 2: I-8091 2-axis stepping/servo  
control card**

## **I-8090 Contents**

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# **I-8090**

## **3-axis encoder card**

### **User Manual**

**Version 1.0 06/2001 Edition**

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## I-8090 3-axis encoder card

I-8090 is a 3-axis encoder counter board on I-8000 platform. I-8090 encoder card has internal digital filter, 16 bits counter and high counting rate 1Mpps. The application of I-8090 board is position/distance measurement, velocity measurement, feedback for motor control, handwheel input and so on.

A system including I-8000 (main system), I-8091 (2-axis stepping/servo control card), I-8090 (3-axis encoder card) can be implemented as a standalone motion controller system for low cost automatic machine.

### Features

- I-8000 series.
- 3-axis, 16 bits encoder counter.
- 32 bits encoder counter by software.
- Maximum counting rate : 1M pulse/sec.
- Differential input A+, A-, B+, B-, C+, C-.
- Quadrant counting mode, CW/CCW counting mode, Pulse/Dir counting mode.
- 2500V optical isolation

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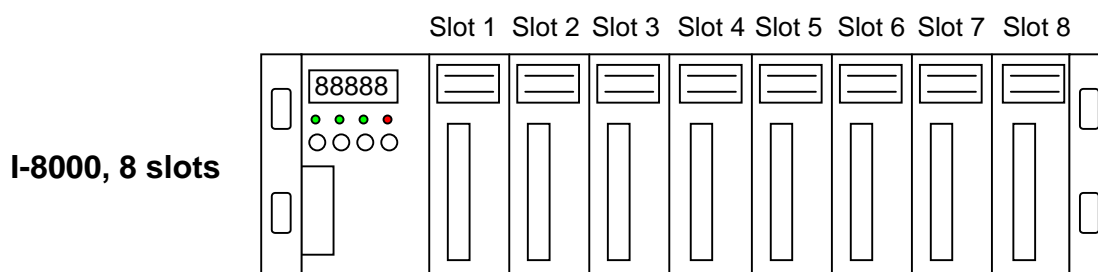
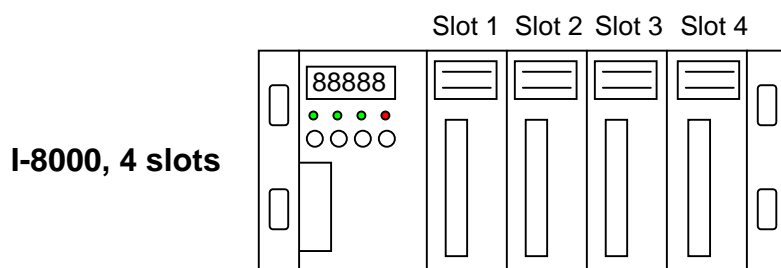
# 1. Hardware

## 1.1 I-8000 hardware address

The hardware address of I-8000 main system is fixed as following table.

There are 4 slots I-8000 and 8 slots I-8000.

	Slot 1	Slot 2	Slot 3	Slot 4	Slot 5	Slot 6	Slot 7	Slot 8
I-8000, 4 slot Address	0x080	0x0A0	0x0C0	0x0E0	---	---	---	---
I-8000, 8 slot Address	0x080	0x0A0	0x0C0	0x0E0	0x140	0x160	0x180	0x1A0



Fig(1) I-8000 hardware address

## 1.2 Registers of I-8090 board

The **I-8090** card's registers table as following.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ID	0x00	R	0x0D							
XDATA	0x01	R	X-axis encoder value							
YDATA	0x02	R	Y-axis encoder value							
ZDATA	0x03	R	Z-axis encoder value							
INDEX	0x04	R						ZI	YI	XI
XCTRL	0x00	W			S1	S0		/RST	/INH	/SEL
YCTRL	0x01	W			S1	S0		/RST	/INH	/SEL
ZCTRL	0x02	W			S1	S0		/RST	/INH	/SEL

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ID	0x00	R	0x0D							

The ID register is read only and its value is fixed as 0x0D. User can check this register to identify I-8090 card or not.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
XDATA	0x01	R	X-axis encoder value							

XDATA: the X-axis encoder counter value can be read out from this register. The low byte value of 16 bits encoder counter can be read out when set /SEL=0 (XCTRL register), the high byte can be read out when set /SEL=1 (XCTRL register).

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
YDATA	0x02	R	Y-axis encoder value							

YDATA : the Y-axis encoder counter value can be read out from this register. The low byte value of 16 bits encoder counter can be read out when set /SEL=0 (YCTRL register), the high byte can be read out when set /SEL=1 (YCTRL register).

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ZDATA	0x03	R	Z-axis encoder value							

ZDATA : the Z-axis encoder counter value can be read out from this register. The low byte value of 16 bits encoder counter can be read out when set



/SEL=0 (ZCTRL register), the high byte can be read out when set /SEL=1 (ZCTRL register).

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
INDEX	0x04	R						ZI	YI	XI

The index input C+/C- can read out from this register. These bits are active high.

XI : indicate the index of X-axis (C+/C- input).

YI : indicate the index of Y-axis (C+/C- input).

ZI : indicate the index of Z-axis (C+/C- input).

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
XCTRL	0x00	W			S1	S0		/RST	/INH	/SEL
YCTRL	0x01	W			S1	S0		/RST	/INH	/SEL
ZCTRL	0x02	W			S1	S0		/RST	/INH	/SEL

The XCTRL, YCTRL and ZCTRL register are control registers for X-axis, Y-axis, Z-axis respectively.

**/RST** : reset counter to zero

**/INH** : inhibit the counter data latch. This bit must be set 0 before read out the counter value to inhibit the counter data latch to DATA registers.

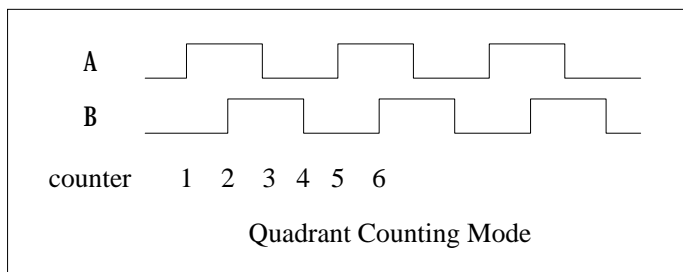
**/SEL** : to select low byte or high byte for reading the counter value.

0 : low byte

1 : high byte

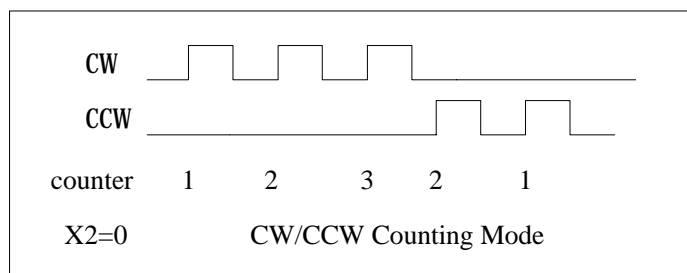
**S1, S0** : to select counting mode

**00** : quadrant counting mode

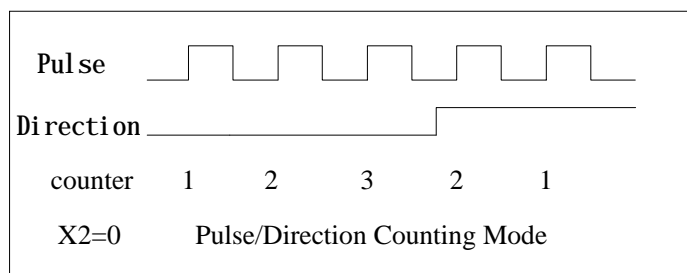


Fig(2) Quadrant counting mode

**01** : CW/CCW counting mode



Fig(3) CW/CCW counting mode

**10** : Pulse/Direction counting mode

Fig(4) Pulse/Direction counting mode

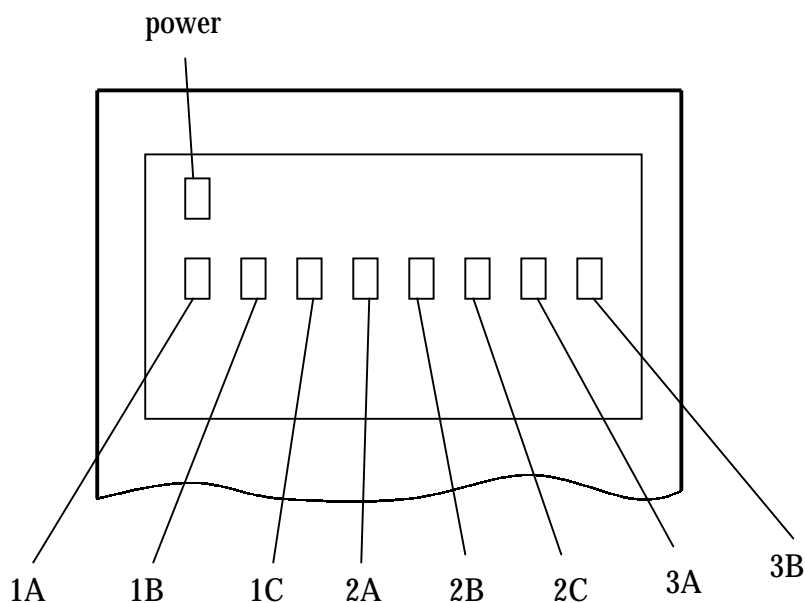
Example: assign counting mode

```
x_mode=y_mode=z_mode=0x00;
card[cardNo].ctrl1 = 0x07 | x_mode;
card[cardNo].ctrl2 = 0x07 | y_mode;
card[cardNo].ctrl3 = 0x07 | z_mode;
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
outportb(card[cardNo].base + WR2, card[cardNo].ctrl2);
outportb(card[cardNo].base + WR3, card[cardNo].ctrl3);
```

Example: read X-axis encoder value

```
card[cardNo].ctrl1 &= 0xFC; //1111 1100 low byte
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
value = inportb(card[cardNo].base + RD1);
card[cardNo].ctrl1 |= 0x01; //0000 0001 high byte
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
value += inportb(card[cardNo].base + RD1)*256;
card[cardNo].ctrl1 |= 0x03; //0000 0011
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
```

### 1.3 LED Indicator



Fig(5) I-8090 LED indicator

Where

1A, 1B, 1C indicate X-axis's 1A+/1A-, 1B+/1B-, 1C+/1C- signal input.

2A, 2B, 2C indicate Y-axis's 2A+/2A-, 2B+/2B-, 2C+/2C- signal input.

3A, 3B, indicate Z-axis's 3A+/3A-, 3B+/3B- signal input.

## 1.4 Connection

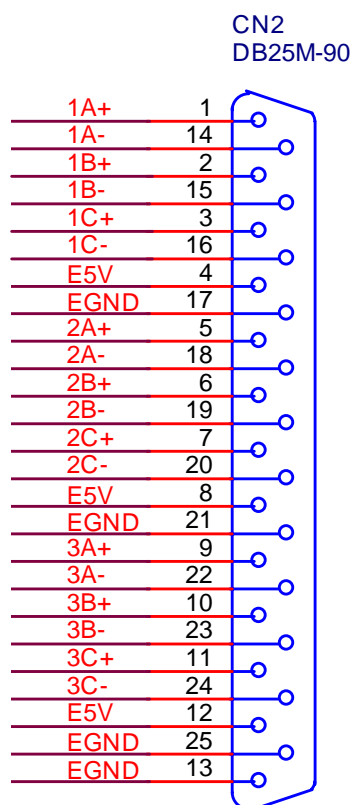


Fig (6) Pin out of CN2 connector

Table of CN2 connector

Pin name	Pin number	description
1A+	1	A+ input of X-axis encoder
1A-	14	A- input of X-axis encoder
1B+	2	B+ input of X-axis encoder
1B-	15	B- input of X-axis encoder
1C+	3	C+ input of X-axis encoder
1C-	16	C- input of X-axis encoder
E5V	4	Isolated 5V supply, max. 50mA (sum of pin 4,8,12)
EGND	17	Signal ground
2A+	5	A+ input of Y-axis encoder
2A-	18	A- input of Y-axis encoder
2B+	6	B+ input of Y-axis encoder
2B-	19	B- input of Y-axis encoder
2C+	7	C+ input of Y-axis encoder
2C-	20	C- input of Y-axis encoder

E5V	8	Isolated 5V supply, max. 50mA (sum of pin 4,8,12)
EGND	21	Signal ground
3A+	9	A+ input of Z-axis encoder
3A-	22	A- input of Z-axis encoder
3B+	10	B+ input of Z-axis encoder
3B-	23	B- input of Z-axis encoder
3C+	11	C+ input of Z-axis encoder
3C-	24	C- input of Z-axis encoder
E5V	12	Isolated 5V supply, max. 50mA (sum of pin 4,8,12)
EGND	25	Signal ground
EGND	13	Signal ground

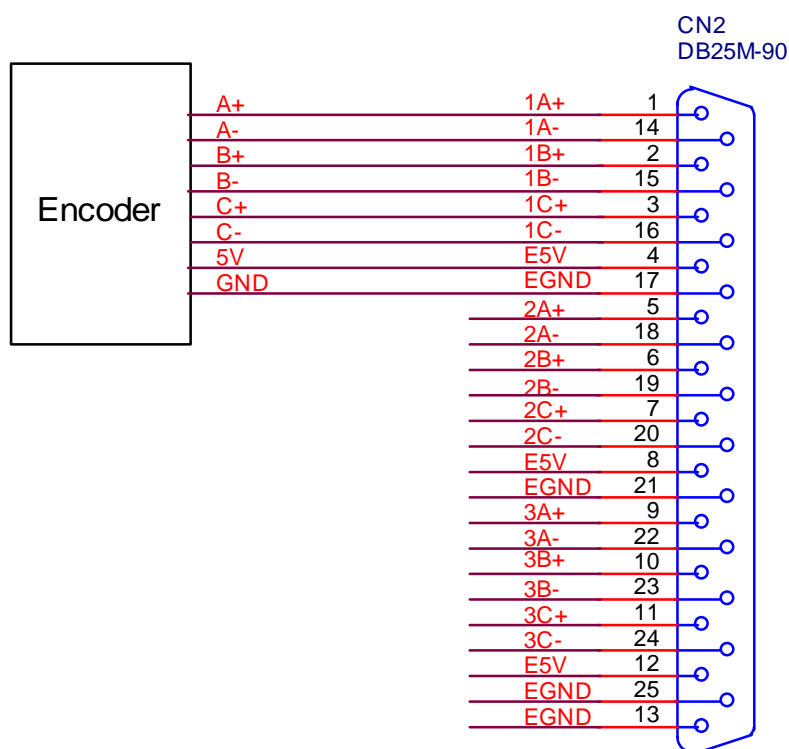


Fig (7) Connection between encoder and I-8090 card

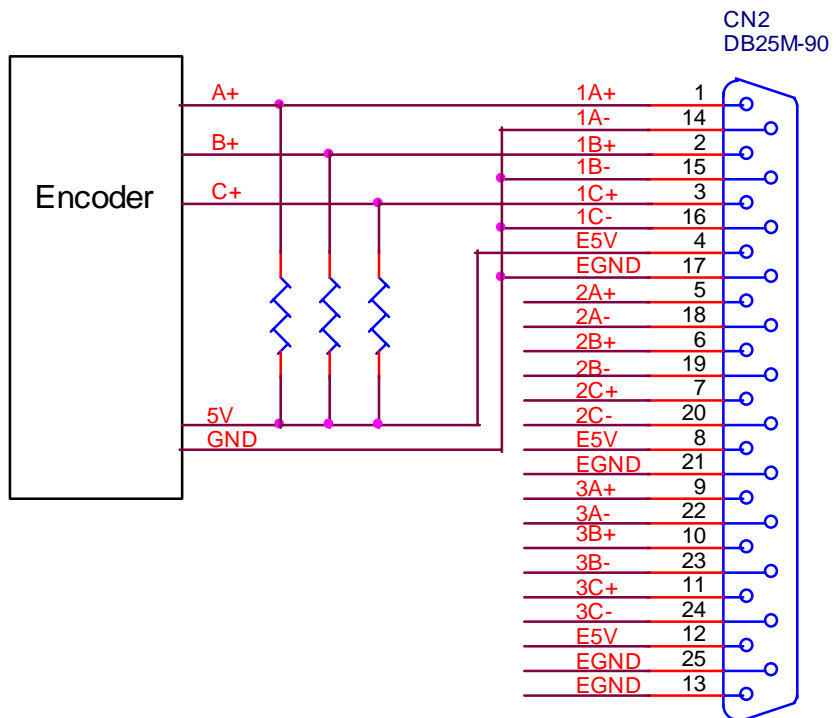


Fig (8) Connection between open collector type encoder and I-8090 card

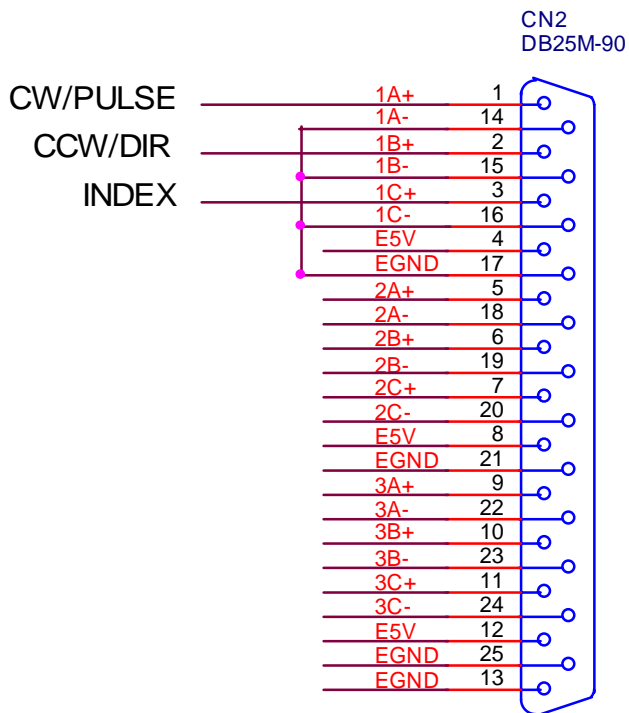


Fig (9) The connection for CW/CCW or Pulse/Direction counting mode

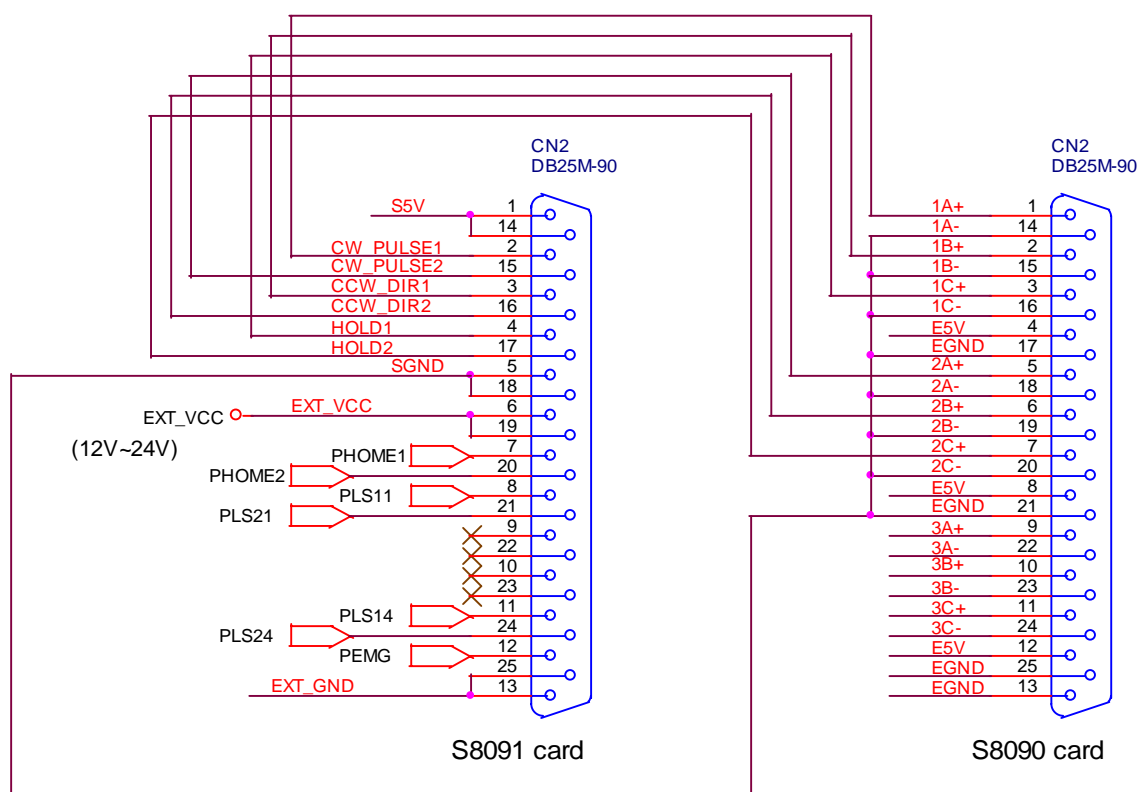


Fig (10) The connection between I-8090 and I-8091 for function testing or pulse feedback by I-8090 encoder card.

## **2. Software**

---

User's applications could be compiled under DOS Turbo/Borland C/C++ environment. It should be include i8090.h and i8090.LIB to compile the target execution file. The execution files can be downloaded under I-8000 main system (execute 7188x.exe), and then run the target execution file as under PC system. About the I-8000's resource or environment, please refer to the manual of I-8000 system or its software programming guide.

The following section will introduce the I-8090's functions and examples.

### **2.1 constants and functions**

#### **Constants**

```
#define YES    1
#define NO     0
#define ON     1
#define OFF    0

#define X_axis    1
#define Y_axis    2
#define Z_axis    3

#define ENC_QUADRANT    0x00
#define ENC_CW_CCW     0x10
#define ENC_PULSE_DIR  0x20
```

#### **Functions**

##### **(1) unsigned char i8090\_REGISTRATION(unsigned char cardNo, unsigned int address)**

In order to distinguish more than one I-8090 card in I-8000 platform, the I-8090 cards should be registrated before using it. This command will assign a card number="cardNo" to I-8090 card address="address" . If there is not I-8090 at the given address, this command will return "NO".

cardNo: 0~19, assign the address as which card.



address: hardware address which defined at chapter 1.1

Return: "YES" : registration successful

"NO" : registration failure.

Example: This example will assign I-8090 card address=0x080 as CARD1 (1). Then initial the I-8090 card and reset X,Y,Z axis encoder counter value to 0.

```
#define CARD1 1
...
i8090_REGISTRATION(CARD1, 0x080);
i8090_INIT_CARD(CARD1, ENC_QUADRANT, ENC_QUADRANT,
                ENC_QUADRANT);
i8090_RESET_ENCODER(CARD1, X_axis);
i8090_RESET_ENCODER(CARD1, Y_axis);
i8090_RESET_ENCODER(CARD1, Z_axis);
```

**(2) void i8090\_INIT\_CARD(unsigned char cardNo,  
                           unsigned char x\_mode,  
                           unsigned char y\_mode,  
                           unsigned char z\_mode)**

This command will reset all three axis's counter value of "cardNo" card, and assign its counting mode. The counting mode (S1,S0) has been explained in registers XCTRL, YCTRL, ZCTRL.

cardNo: 0~19, select which card.

x\_mode, y\_mode, z\_mode: select the counting mode.

0x00 : quadrant counting mode

0x10 : CW/CCW counting mode

0x20 : Pulse/Direction counting mode

Example:

```
#define ENC_QUADRANT 0x00
#define ENC_CW_CCW 0x10
#define ENC_PULSE_DIR 0x20
```

```
i8090_INIT_CARD(CARD1, ENC_QUADRANT, ENC_QUADRANT,
                ENC_QUADRANT);
```

**(3) unsigned int i8090\_GET\_ENCODER(unsigned char cardNo, unsigned char axis)**

This command will return the counter value of the selected “axis” and “cardNo”.

cardNo: 0~19, select which card.

axis : select which axis.

1 : X-axis

2 : Y-axis

3 : Z-axis

return : a 16 bits unsigned integer value.

**(4) void i8090\_RESET\_ENCODER(unsigned char cardNo, unsigned char axis)**

This command will reset the counter value of the selected “axis” and “cardNo”.

cardNo: 0~19, select which card.

axis : select which axis.

1 : X-axis

2 : Y-axis

3 : Z-axis

**(5) unsigned char i8090\_GET\_INDEX(unsigned char cardNo)**

It will return the “INDEX” register’s value of the selected “cardNo” card.

cardNo: 0~19, select which card.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
INDEX	0x04	R						ZI	YI	XI

The index input C+/C- can read out from this register. These bits are active high.

XI : indicate the index of X-axis.

YI : indicate the index of Y-axis.

ZI : indicate the index of Z-axis.

### **32 bits encoder counts command sets**

**(6) void i8090\_ENCODER32\_ISR(unsigned char cardNo)**

**(7) void i8090\_RESET\_ENCODER32(unsigned char cardNo, unsigned char axis)**

**(8) long i8090\_GET\_ENCODER32(unsigned char cardNo, unsigned char axis)**

cardNo: 0~19, select which card.

axis : select which axis.

1 : X-axis

2 : Y-axis

3 : Z-axis

The above three commands provided a software method to get 32 bits encoder counts.

The **i8090\_ENCODER32\_ISR(unsigned char cardNo)** command calculates the difference pulse between present and last time, and then add this difference into a "*long type*" variable. According to this idea, so, the **i8090\_ENCODER32\_ISR()** command should be executed periodically in 2~10ms by timer interrupt or manually call it.

The **i8090\_RESET\_ENCODER32((unsigned char cardNo, unsigned char axis)** command can reset the "*long type*" variable to zero.

The **long i8090\_GET\_ENCODER32(unsigned char cardNo, unsigned char axis)** command can return the value of the "*long type*" variable.

## 2.2 examples

### 2.2.1 Detect I-8090 card

```
//-----
// detect i8090,i8091,i8092 card
//-----
#include "8000.h"
#include "i8090.h"

#define i8090 0x0d
#define i8091 0x0e
#define i8092 0x0f
#define NOCARD 0x00
#define MAX_SLOT_NO 8
unsigned int PortAddress[8]={0x080, 0x0a0, 0x0c0, 0x0e0, 0x140, 0x160,
0x180, 0x1a0};
//-----
void main ()
{
unsigned char slot,temp;

for (slot=0; slot<MAX_SLOT_NO; slot++)
{
temp=inportb(PortAddress[slot]);
switch (temp)
{
case i8090: //i8090 3-axis encoder card
Print("Slot %d = i8090\r\n",SlotNum);
return i8090;
case i8091: //i8091 2-axis stepping card
Print("Slot %d = i8091\r\n",SlotNum);
return i8091;
case i8092: //i8092
Print("Slot %d = i8092\r\n",SlotNum);
```

```

        return i8092;
    default:
        Print("Slot %d = No Card\r\n",SlotNum);
        return NOCARD;
    };
    Delay(500);
};
}

```

### 2.2.2 Start to use I-8090 card

```

#define CARD1 1
if (i8090_REGISTRATION(CARD1, PortAddress[0])==YES)
{
    i8090_INIT_CARD(CARD1, ENC_QUADRANT, ENC_QUADRANT,
                    ENC_QUADRANT);
    i8090_RESET_ENCODER(CARD1, X_axis);
    i8090_RESET_ENCODER(CARD1, Y_axis);
    i8090_RESET_ENCODER(CARD1, Z_axis);
}
else
{
    Print(" Not found I-8090 card in slot 0!");
    return;
}

```

### 2.2.3 Get X, Y, Z-axis encoder counter's value

```

unsigned int i8090_GET_ENCODER(unsigned char cardNo, unsigned char
axis)
{
    unsigned int value;

    switch (axis)
    {
        case X_axis:

```

```
card[cardNo].ctrl1 &= 0xFC; //1111 1100 low byte
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
value = inportb(card[cardNo].base + RD1);
```

```
card[cardNo].ctrl1 |= 0x01; //0000 0001 high byte
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
value += inportb(card[cardNo].base + RD1)*256;
```

```
card[cardNo].ctrl1 |= 0x03; //0000 0011
outportb(card[cardNo].base + WR1, card[cardNo].ctrl1);
break;
```

case Y\_axis:

```
card[cardNo].ctrl2 &= 0xFC; //1111 1100 low byte
outportb(card[cardNo].base + WR2, card[cardNo].ctrl2);
value = inportb(card[cardNo].base + RD2);
```

```
card[cardNo].ctrl2 |= 0x01; //0000 0001 high byte
outportb(card[cardNo].base + WR2, card[cardNo].ctrl2);
value += inportb(card[cardNo].base + RD2)*256;
```

```
card[cardNo].ctrl2 |= 0x03; //0000 0011
outportb(card[cardNo].base + WR2, card[cardNo].ctrl2);
break;
```

case Z\_axis:

```
card[cardNo].ctrl3 &= 0xFC; //1111 1100 low byte
outportb(card[cardNo].base + WR3, card[cardNo].ctrl3);
value = inportb(card[cardNo].base + RD3);
```

```
card[cardNo].ctrl3 |= 0x01; //0000 0001 high byte
outportb(card[cardNo].base + WR3, card[cardNo].ctrl3);
value += inportb(card[cardNo].base + RD3)*256;
```

```
card[cardNo].ctrl3 |= 0x03; //0000 0011
outportb(card[cardNo].base + WR3, card[cardNo].ctrl3);
```

```

        break;
    default : break;
}

return value;
}

```

#### 2.2.4 Software 32 bits encoder counter programming

```

//-----
// demo1.cpp for I-8090 card
// This program demonstrates the software 32 bits encoder method by
// void i8090_ENCODER32_ISR(unsigned char cardNo);
// void i8090_RESET_ENCODER32(unsigned char cardNo, unsigned char
axis);
// long i8090_GET_ENCODER32(unsigned char cardNo, unsigned char
axis);
//-----
// v1.0 4/7/2001
//
//-----
#include <dos.h>
#include <math.h>
#include "8000.h"
#include "i8090.h"

#define i8090 0x0d
#define i8091 0x0e
#define i8092 0x0f
#define NOCARD 0x00

#define Insert      0x0000
#define BasePort    0x0080
#define SlotOffset  0x0020
#define IDPort      0x0000

```

```
#define CARD1 1
#define CARD2 2
#define MAX_SLOT_NO 8
unsigned int PortAddress[8]={0x080, 0x0a0, 0x0c0, 0x0e0, 0x140, 0x160,
0x180, 0x1a0};
//-----
long    x_value;
long    y_value;
long    z_value;
unsigned char index;
unsigned char x_index;
unsigned char y_index;
unsigned char z_index;

unsigned char i8090Slot;
//-----

//-----
void ShowLedValue(long value,unsigned char axis)
{
long j;
unsigned char negative_value;

if (value<0) negative_value=1;
else    negative_value=0;
value=labs(value);

j=value-10*(value/10);
if (negative_value) Show5DigitLedWithDot(0x05, j);
else    Show5DigitLed(0x05, j);

value=value/10;
j=value-10*(value/10);
```



```

    Show5DigitLed(0x04, j);
    value=value/10;
    j=value-10*(value/10);
    if (axis==Z_axis) Show5DigitLedWithDot(0x03, j);
    else          Show5DigitLed(0x03, j);
    value=value/10;
    j=value-10*(value/10);
    if (axis==Y_axis) Show5DigitLedWithDot(0x02, j);
    else          Show5DigitLed(0x02, j);
    value=value/10;
    j=value-10*(value/10);
    if (axis==X_axis) Show5DigitLedWithDot(0x01, j);
    else          Show5DigitLed(0x01, j);
}
//-----
void ShowCardName(unsigned char SlotNum)
{
    unsigned char temp;

    Show5DigitLed(0x05, SlotNum);
    temp=inportb(PortAddress[SlotNum]);
    switch (temp)
    {
        case i8090: //i8090 3-axis encoder card
            Show5DigitLedSeg (0x01, 0x7F);
            Show5DigitLedSeg (0x02, 0x7E);
            Show5DigitLedSeg (0x03, 0x7B);
            Show5DigitLedSeg (0x04, 0x7E);
            break;

        case i8091: //i8091 2-axis stepping card
            Show5DigitLedSeg (0x01, 0x7F);
            Show5DigitLedSeg (0x02, 0x7E);
            Show5DigitLedSeg (0x03, 0x7B);
            Show5DigitLedSeg (0x04, 0x30);
    }
}

```

```

        break;
    default:
        Show5DigitLedSeg (0x01, 0x01);
        Show5DigitLedSeg (0x02, 0x01);
        Show5DigitLedSeg (0x03, 0x01);
        Show5DigitLedSeg (0x04, 0x01);
        break;
    };
}
//-----
unsigned char CardSearch(unsigned char SlotNum)
{
    unsigned char temp;

    temp=inportb(PortAddress[SlotNum]);
    ShowCardName(SlotNum);
    switch (temp)
    {
        case i8090: //i8090 3-axis encoder card
            Print("Slot %d = i8090\r\n",SlotNum);
            return i8090;
        case i8091: //i8091 2-axis stepping card
            Print("Slot %d = i8091\r\n",SlotNum);
            return i8091;
        default:
            Print("Slot %d = No Card\r\n",SlotNum);
            return NOCARD;
    };
}
//-----
void main ()
{
    unsigned char j;

```

```
int      key,ShowAxis;

i8090Slot=99;
for (j=0; j<MAX_SLOT_NO; j++)
{
    if (CardSearch(j)==i8090) i8090Slot=j;
    Delay(500);
};

if (i8090Slot==99)
{
    Print("Not found i8090 card in 8 slot!\r\n");
    return;
}

i8090_REGISTRATION(CARD1, PortAddress[i8090Slot]);
i8090_INIT_CARD(CARD1,  ENC_QUADRANT,  ENC_QUADRANT,
ENC_QUADRANT);
i8090_RESET_ENCODER(CARD1, X_axis);
i8090_RESET_ENCODER(CARD1, Y_axis);
i8090_RESET_ENCODER(CARD1, Z_axis);
i8090_RESET_ENCODER32(CARD1, X_axis);
i8090_RESET_ENCODER32(CARD1, Y_axis);
i8090_RESET_ENCODER32(CARD1, Z_axis);

Print("-----\r\n");
Print(" i8090 DEMO1 program      demo1.PRJ, demo1.cpp, i8090.lib
\r\n");
Print(" 32 bits encoder demonstration          \r\n");
Print("-----\r\n");
Print("Press any key to stop...\r\n");
ClearSystemKey();
ShowAxis=0;
do
```

```

{
    Delay(5); //delay 5ms
    //-----
    // i8090_ENCODER32_ISR(CARD1) should be called in 2~10ms
    // or call it by a timer interrupt service routine by 2~10ms
    //-----
    i8090_ENCODER32_ISR(CARD1);

    //-----

    x_value = i8090_GET_ENCODER32(CARD1, X_axis);
    y_value = i8090_GET_ENCODER32(CARD1, Y_axis);
    z_value = i8090_GET_ENCODER32(CARD1, Z_axis);
    index = i8090_GET_INDEX(CARD1);
    x_index = index & 0x01;
    y_index = (index & 0x02) >> 1;
    z_index = (index & 0x04) >> 2;

    if (IsSystemKey())
    {
    key=GetSystemKey();
        ClearSystemKey();
        switch (key)
        {
            case SKEY_DOWN:
                ShowAxis++;
                if (ShowAxis>2) ShowAxis=0;
                break;
            case SKEY_UP:
                ShowAxis--;
                if (ShowAxis<0) ShowAxis=2;
                break;
        };
    }
}

```

```
switch (ShowAxis)
{
    case 0: ShowLedValue(x_value,X_axis); break;
    case 1: ShowLedValue(y_value,Y_axis); break;
    case 2: ShowLedValue(z_value,Z_axis); break;
};
if (x_index) LedRunOff(); else LedRunOn();
if (y_index) LedCommOff(); else LedCommOn();
if (z_index) LedBattOff(); else LedBattOn();
} while (!Kbhit());
}
```

# **I-8091**

## **2-axis stepping/servo motor control card**

### **User Manual**

**Version 1.0 06/2001 Edition**

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## I-8091 2-axis Stepping/Servo Motor Control Card

The I-8091 card is a 2-axis command-type stepping motor control card on I-8000 platform, it also can be used as servo motor control (pulse input type). This card has an embedded CPU which performs motion commands transferred from I-8000 main system to increase the system performance. A 2Kbytes-FIFO is introduced as command buffer. This buffer can provide over 700ms buffer time.

A system including I-8000(main system), I-8091(2-axis stepping/servo control card), I-8090(3-axis encoder card) can be implemented as a stand along motion controller system for low cost automatic machine.

### Features

- I-8000 series.
- 2-axis independent, simultaneous stepping motor control / servo motor control (pulse input type).
- Maximum pulse rate: 1Mpps.
- Maximum step counts:  $2^{32} - 1$  steps.
- DOS driver.
- embedded CPU.
- command type interface.
- 2-axis linear, 2-axis circular interpolation.
- automatic trapezoidal acceleration / deceleration.
- output pulse modes : CW/CCW or pulse/direction.
- output polarity can be programmable.
- 2500Vrms optical isolated signal output.
- 3 optical isolated digital inputs per axis for limit switches.
- programmable limit switch initial condition as normal open(N.O.) or normal close(N.C.).

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## 1. Introduction

---

### 1.1 System Block Diagram

The I-8091 stepping motor control card is a micro-computer controlled, 2-axis pulse generation card. It includes a 2Kbytes-FIFO to receive motion command from host, a micro-computer for profile generation and protection, 2-axis DDA chip to execute DDA function when interpolation command is used, 2500Vrms optical isolation inserted for industrial application.

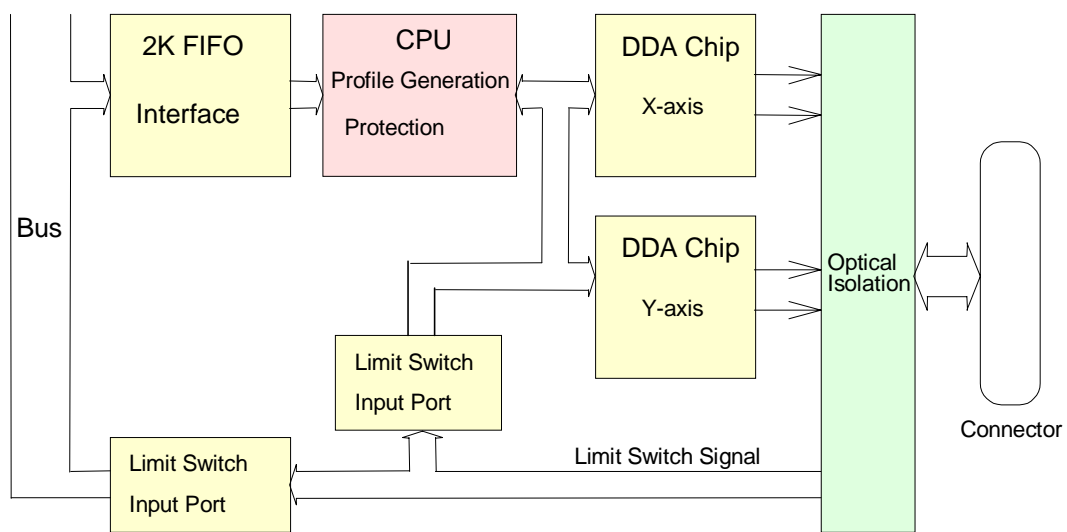


Fig.(1) block diagram of I-8091 card

## 1.2 DDA Technology

The DDA chip is the heart of I-8091 card, it will generate equal-space pulse train corresponding to specific pulse number during a DDA period. This mechanism is very useful to execute pulse generation and interpolation function. The DDA period can be determined by DDA cycle. Table(1) shows the relation among DDA cycle, DDA period and output pulse rate. When DDA cycle set to 1, the DDA period is equal to  $(1+1) \times 1.024\text{ms} = 2.048\text{ms}$ . The output pulse number can be set to 0~2047, therefore the maximum output pulse rate will be 1Mpps. The minimum output pulse rate is 3.83pps when set DDA cycle=254 (DDA period =  $(254+1) \times 1.024\text{ms} = 261.12\text{ms}$ ).

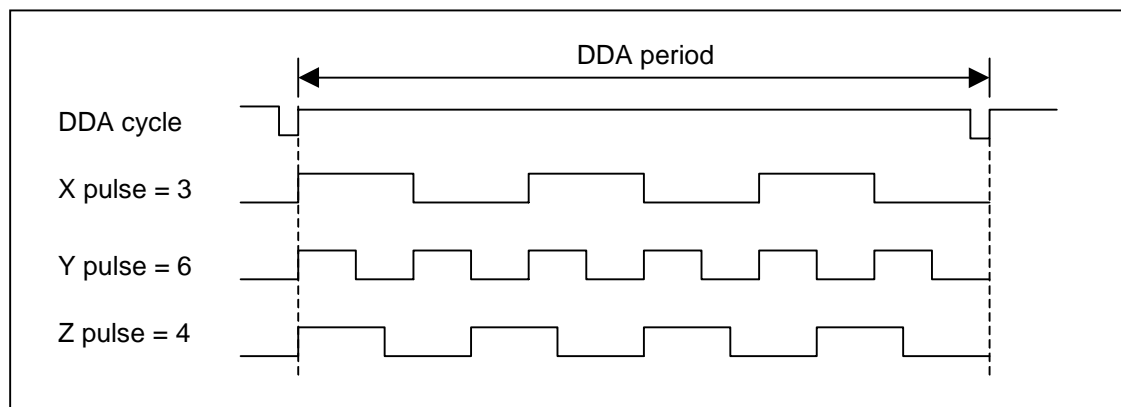


Fig.(2) DDA mechanism

Table(1) The Relation among DDA cycle, DDA period and output pulse rate.

DDA cycle	DDA period	Max. pulse rate(n=2047)	Min. pulse rate (n=1)
1	2.048ms	999511pps	488pps
2	3.072ms	666341pps	325pps
3	4.096ms	.	.
.	.	.	.
N	$(N+1) \times 1.024\text{ms}$	$2047 / (\text{DDA period})$	$1 / (\text{DDA period})$
.	.	.	.
254	261.12ms	7839pps	3.83pps

The DDA cycle can be set by `i8091_SET_VAR()` command which described in chapter 3. The selection criterion of DDA cycle was described as following.

(1) The required max. output pulse rate.

$$PR_{max} = \frac{V_{max} * N / 60}{2047}$$

$$PR_{max} = \frac{(DDA_{cycle} + 1) * 1.024ms}{2047}$$

PRmax : max. output pulse rate.

Vmax : max. speed (rpm).

N : the pulse number of stepping motor per revolution.  
(pulse/rev).

2. The required speed resolution.

The maximum output pulse number is Np(0~2047), therefore the speed resolution is Vmax(max. speed)/Np. The DDA cycle can be obtained by following equation.

$$PR_{max} = \frac{Np}{(DDA_{cycle} + 1) * 1.024ms}$$

3. When choose large DDA cycle (DDA period), it will occur vibration between different pulse input which generally can be observed during acceleration or deceleration. So, the small DDA cycle , the smooth acceleration/deceleration curve as long as the speed resolution is acceptable.

### Example: Stepping Motor

The specification of stepping motor is 500 pulse/rev, max. speed 500 rpm, speed resolution 2 rpm.

The required max. pulse rate

$$PR_{max} = 500 \text{ rpm} * 500 / 60 = 4166.67 \text{ pps}$$

The maximum output pulse

$$Np = 500 \text{ rpm} / 2 \text{ rpm} = 250 \text{ pulse number}$$

The DDA cycle can be calculated by follow equation

$$PR_{max} = \frac{Np}{(DDA_{cycle} + 1) * 1.024ms}$$

$$4166.67 = \frac{250}{(DDA_{cycle} + 1) * 1.024ms}$$

$$DDA \text{ cycle} = 58$$

$$\text{High Speed} = 247 \text{ pulse } (4166.67 * 58 * 0.001024)$$

The above results means that maximum speed is 500rpm when send command `i8091_SET_VAR(0, 58, 2, 2, 247)` to I-8091 card.

### **Example: Pulse type input Servo Motor**

The specification of servo motor is 8000 pulse/rev, max. speed 3000 rpm, speed resolution 2 rpm.

The required max. pulse rate

$$\text{PRmax} = 3000 \text{ rpm} * 8000 / 60 = 400,000 \text{ pps}$$

The maximum output pulse

$$\text{Np} = 3000 \text{ rpm} / 2 \text{ rpm} = 1500 \text{ pulse number}$$

The DDA cycle can be calculated by follow equation

$$\text{PRmax} = \frac{Np}{(DDA\text{cycle} + 1) * 1.024\text{ms}}$$

$$400,000 = \frac{1500}{(DDA\text{cycle} + 1) * 1.024\text{ms}}$$

$$\text{DDA cycle} = 3$$

$$\text{High Speed} = 1638 \text{ pulse } (400,000 * 4 * 0.001024)$$

The above results means that maximum speed is 3000rpm when send command `i8091_SET_VAR(0, 3, 2, 2, 1638)` to I-8091 card.

## 2 Hardware

### 2.1 I-8000 hardware address

The hardware address of I-8000 main system is fixed as following table.  
There are 4 slots I-8000 and 8 slots I-8000.

	Slot 1	Slot 2	Slot 3	Slot 4	Slot 5	Slot 6	Slot 7	Slot 8
I-8000, 4 slot address	0x080	0x0A0	0x0C0	0x0E0	---	---	---	---
I-8000, 8 slot address	0x080	0x0A0	0x0C0	0x0E0	0x140	0x160	0x180	0x1A0

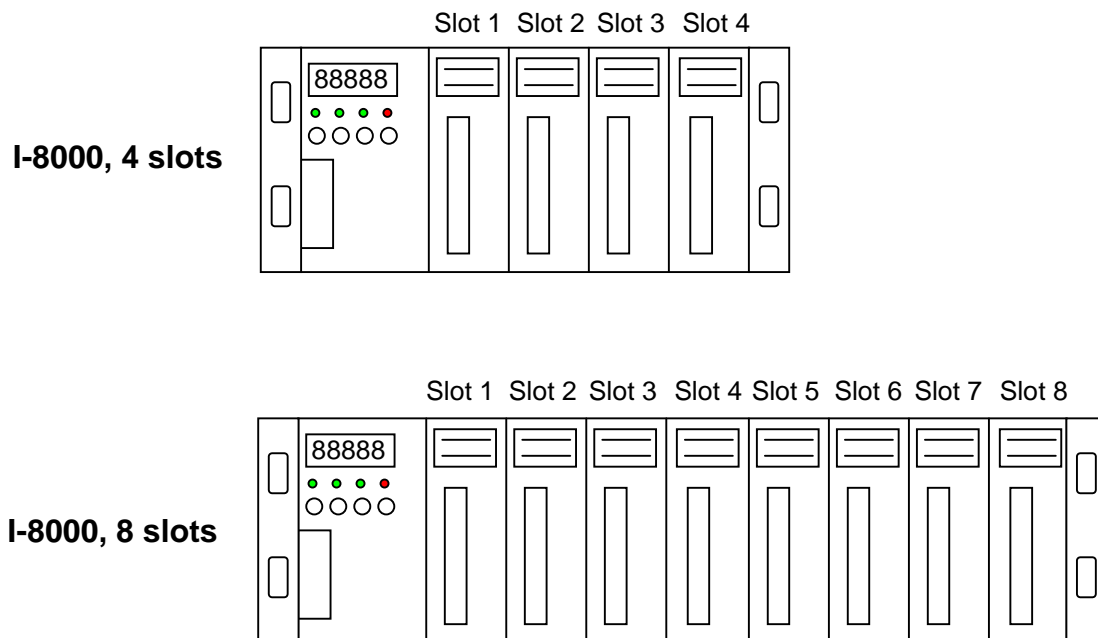


Fig.(3) I-8000 hardware address

## 2.2 Registers of I-8091 board

The I-8091 card's registers table as following.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ID	0x00	R	0x0E							
LIMIT1	0x01	R	/EMG	/FFFF	/FFEF	/LS14			/LS11	/ORG1
LIMIT2	0x02	R	/YSTOP	/XSTOP		/LS24			/LS21	/ORG2
WRFF	0x01	W	Command port							
RSTFF	0x02	W	Reset FIFO							

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ID	0x00	R	0x0E							

The ID register is read only and its value is fixed as 0x0E. User can check this register to identify I-8091 card or not.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
LIMIT1	0x01	R	/EMG	/FFFF	/FFEF	/LS14			/LS11	/ORG1

/ORG1 : original point limit switch of X-axis.

/LS11, /LS14 : limit switches of X-axis, which must be configured as chapter 2.4.1.

/EMG : emergency switch.

/FFEF : active low, indicate FIFO is empty.

/FFFF : active low, indicate FIFO is full.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
LIMIT2	0x02	R	/YSTOP	/XSTOP		/LS24			/LS21	/ORG2

/ORG2 : original point switch of Y-axis.

/LS21, /LS24 : limit switches of Y-axis, which must be configured as chapter 2.4.1.

/XSTOP, /YSTOP : These signals indicate the operating situation of X, Y axis in CPU.

1 : busy, 0 : stop

The commands `i8091_WAIT_X()` and `i8091_WAIT_Y()` just to waiting for

'/XSTOP' or '/YSTOP' signal become to '0'.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
WRFF	0x01	W	Command port							

I-8091 driver will send motion command by way of this register. Please do not use this register to write any thing, or I-8091 will not operate properly.

Register	Add.	R/W	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
RSTFF	0x02	W	Reset FIFO							

This register is used to reset FIFO for clear all of commands pending in the FIFO buffer.

## 2.3 LED Indicator

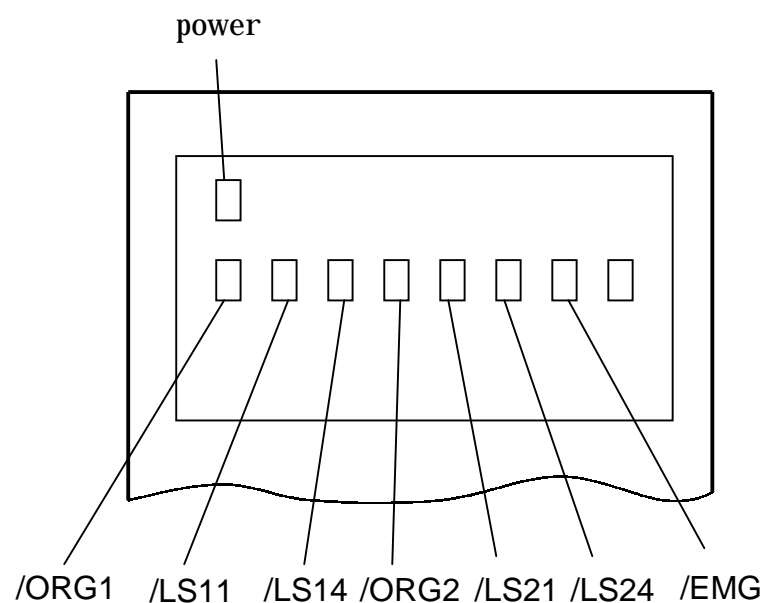


Fig.(4) I-8091 LED indicator

Where

/ORG1: X-axis's original limit switch for machine home position.

/LS11, /LS14 : X-axis's negative and positive limit switches.

/ORG2: Y-axis's original limit switch for machine home position.

/LS21, /LS24 : Y-axis's negative and positive limit switches.

/EMG : system's emergency signal input.

## 2.4 Hardware Configuration

### 2.4.1 Limit switch configuration

Because the profile generation and protection is executed by the CPU on I-8091 card, the limit switches must configure as following diagram. The motion command just can work properly.

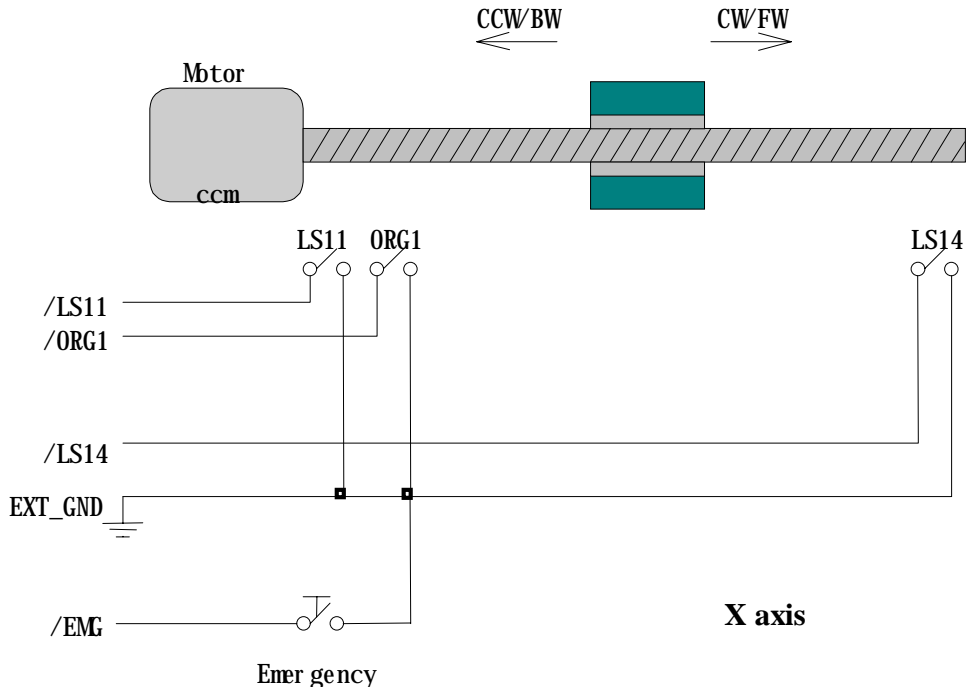


Fig.(5) Limit switch configuration of X axis

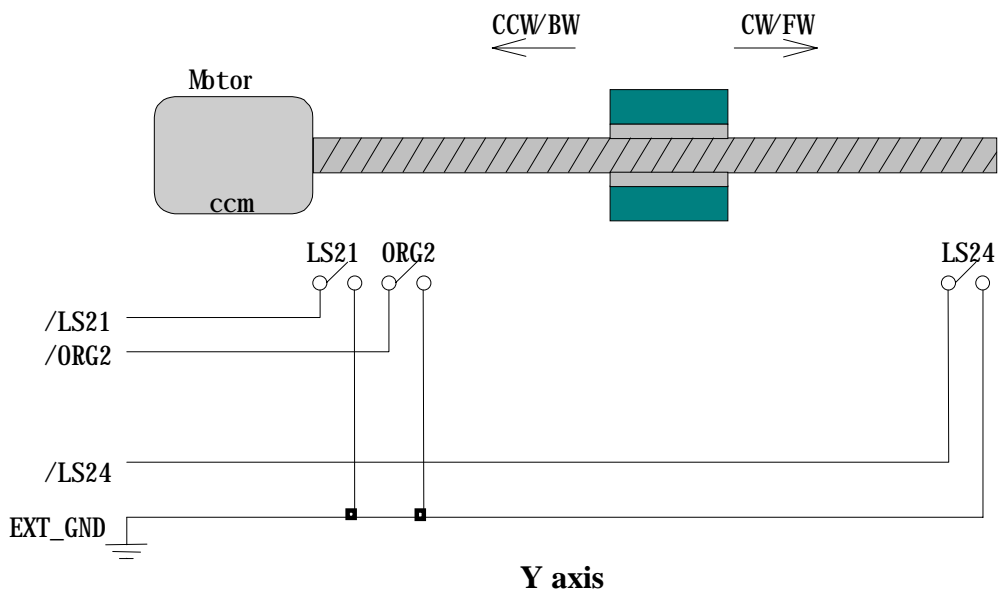


Fig.(6) Limit switch configuration of Y axis



## 2.4.2 Output pulse mode configuration

I-8091 card provide two kind output method.

- (a) CW/CCW mode
- (b) Pulse/Direction mode

The command `i8091_SET_MODE(cardNo, modeX, modeY)` provide parameters `CW_CCW` (0) and `PULSE_DIR` (1) to define output pulse mode.

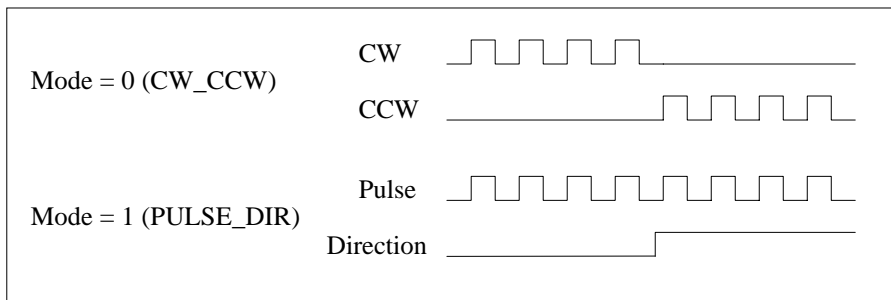


Fig.(7) Output pulse mode

## 2.4.3 Direction configuration

Sometimes, the output direction of X-axis, Y-axis is not in the desired direction due to the motor's connection or gear train. It is recommended to unify the output direction as shown in Figure(5)(6). The CW/FW direction is defined as toward outside from motor and the CCW/BW direction is defined as toward inside to motor. The `i8091_SET_DEFDIR(cardNo, defdirX, defdirY)` command provides parameters `NORMAL_DIR` (0) and `REVERSE_DIR` (1) to define the rotating direction of motor.

## 2.4.4 Turn Servo ON/OFF (Hold ON/OFF)

To turn servo motor into servo ON(OFF) state, or turn stepping motor into hold ON(OFF) state, the command `i8091_SET_SERVO_ON(cardNo, sonX, sonY)` provide parameters `ON` (1) and `OFF` (0) to turn ON or OFF.

## 2.4.5 Automatic protection

The I-8091 card has a automatic protected system.

- (a) If X-axis command is executing and moving toward CW/FW direction,

- X-axis will immediately stop when LS14 is touched. To release this protection as long as X-axis move toward CCW/BW direction.
- (b) If X-axis command is executing and moving toward CCW/BW direction, X-axis will immediately stop when LS11 is touched. To release this protection as long as X-axis move toward CW/FW direction.
  - (c) If Y-axis command is executing and moving toward CW/FW direction, Y-axis will immediately stop when LS24 is touched. To release this protection as long as Y-axis move toward CCW/BW direction.
  - (d) If Y-axis command is executing and moving toward CCW/BW direction, Y-axis will immediately stop when LS21 is touched. To release this protection, as long as Y-axis move toward CW/FW direction.
  - (e) If the signal of the emergency limit switch /EMG was found in CPU firmware, all motion will be terminated and stop.

#### **2.4.6 Set limit switch as normal close condition**

The limit switches /EMG, /LS11, /LS14, /LS21, /LS24, /ORG1, /ORG2 is initially normal open condition, that is, these signal is active when connect it to ground. In industrial application, it might be recommended normal close condition, that is, these signal is active when open from ground.

The `i8091_SET_NC(cardNo, sw)` command can be set `sw=0` (default), for normal open condition. When set `sw=1`, for normal close condition.

## 2.5 Connection

### 2.5.1 Pin assignment of connector CN2

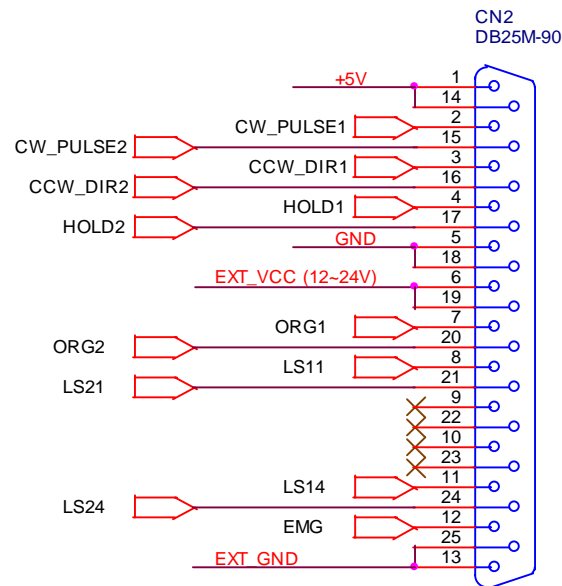


Fig.(8) CN2 connector

Table of CN2 connector's pin assignment

pin name	pin number	Description
+5V	1	Internal +5V power, Max. output current: 50mA
CW_PULSE1	2	X-axis CW (Pulse) output pin
CCW_DIR1	3	X-axis CCW (Direction) output pin
HOLD1	4	X-axis HOLD (servo on) output pin
GND	5	Signal ground of pin 2,3,4
EXT_VCC	6	External power(12~24V) for limit switches
/ORG1	7	X-axis original (home) limit switch
/LS11	8	X-axis limit switch
	9,10	No used
/LS14	11	X-axis limit switch
/EMG	12	Emergency input
EXT_GND	13	External ground for limit switch
+5V	14	Internal +5V power, Max. output current: 50mA
CW_PULSE2	15	Y-axis CW (Pulse) output pin
CCW_DIR2	16	Y-axis CCW (Direction) output pin
HOLD2	17	Y-axis HOLD (servo on) output pin
GND	18	Signal ground of pin 15,16,17

EXT_VCC	19	External power(12~24V) for limit switches
/ORG2	20	Y-axis original (home) limit switch
/LS21	21	Y-axis limit switch
	22,23	No used
/LS24	24	Y-axis limit switch
EXT_GND	25	External ground for limit switch

### 2.5.2 The internal circuit of CW\_PULSE, CCW\_DIR, HOLD

When output these signal as 1, it can source 15mA(max.).

When output these signal as 0, it can sink 50mA(max.).

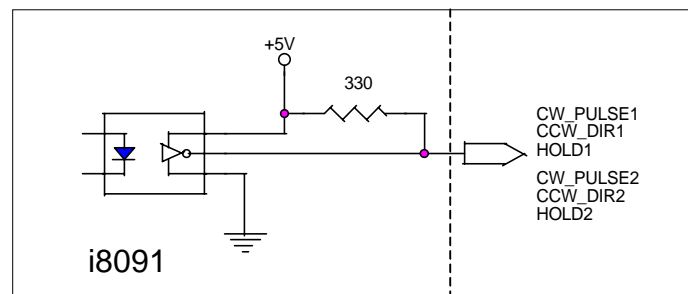


Fig.(9) internal circuit of pulse output pin

### 2.5.3 The internal circuit of limit switch input

Initially, the limit switch inputs of I-8091 board are normal open (N.O.), the I-8091 board will automatic protect when limit switch pin connect to EXT\_GND. The user can use the command i8091\_SET\_NC (cardNo, YES) to let those limit switch input as normal close condition at the beginning of the user's program.

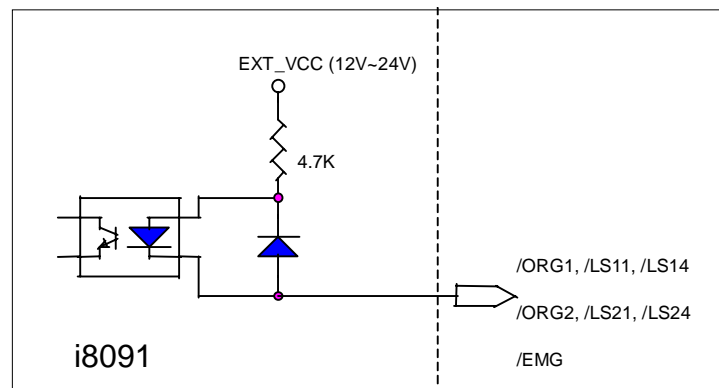


Fig.(10) internal circuit of limit switch input pin

### 2.5.4 Example of connection

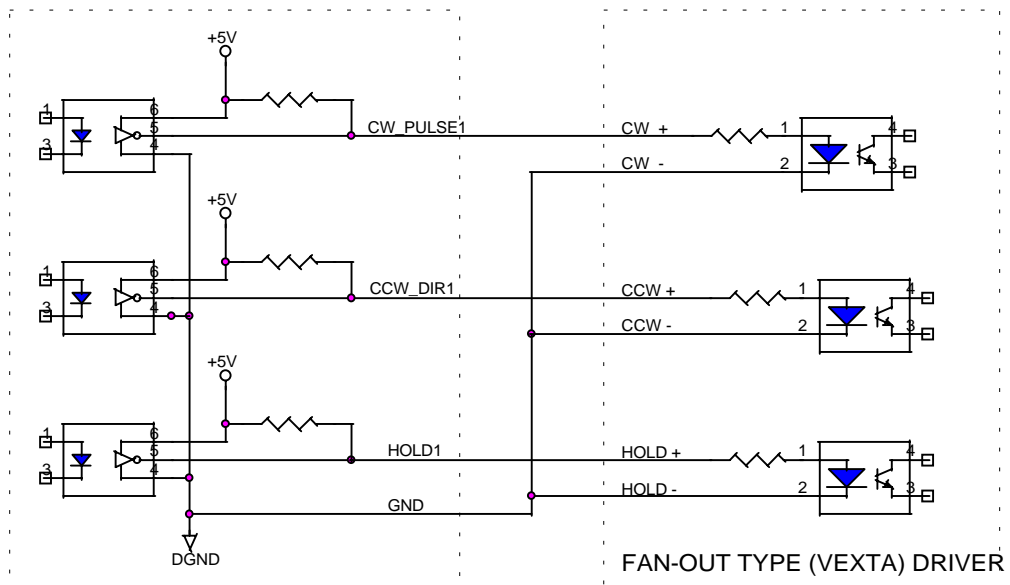


Fig.(11) fan-out driver (VEXTA's motor driver)

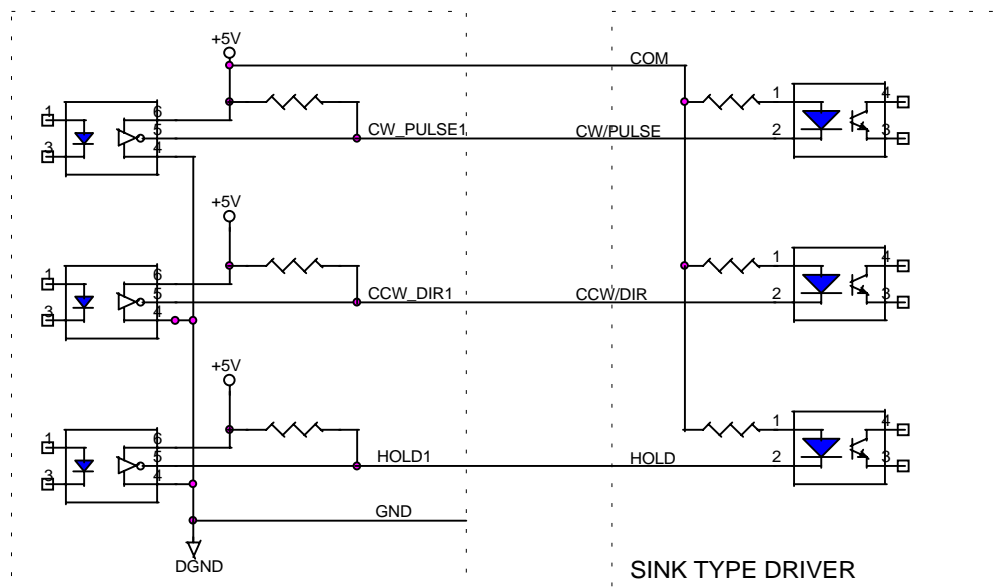


Fig.(12) Sink type driver

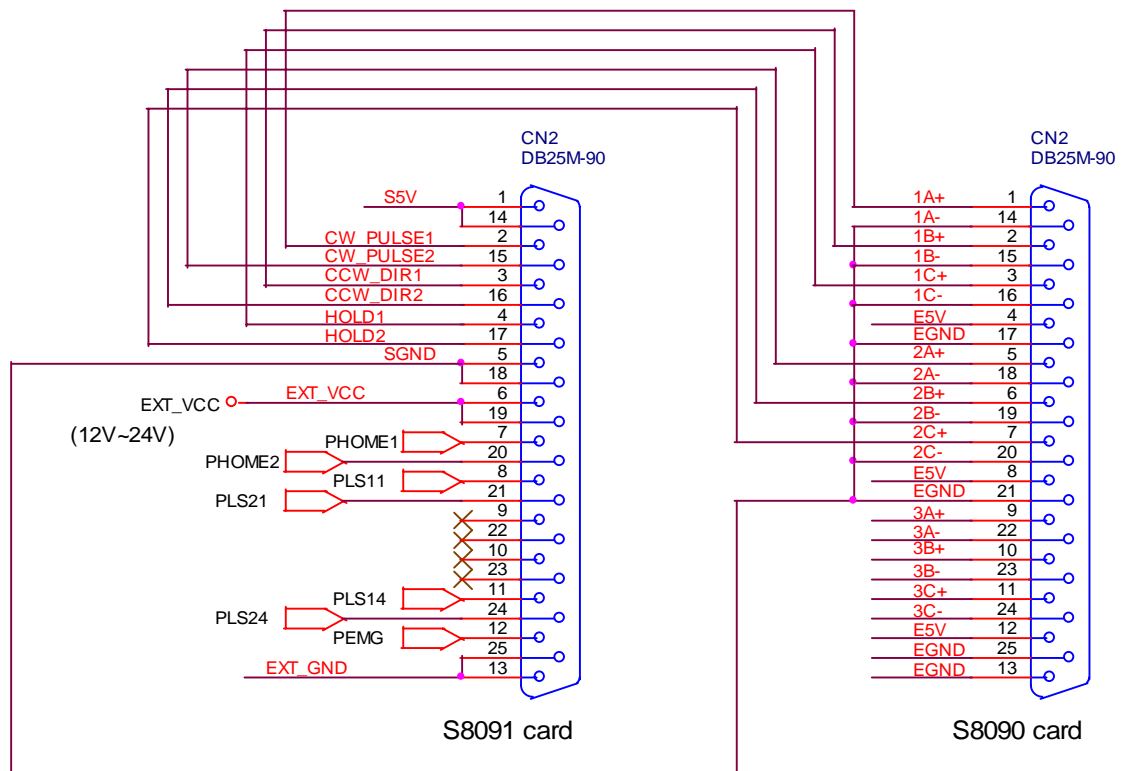


Fig.(13) The connection between I-8090 and I-8091 for function testing or pulse feedback by I-8090 encoder card.

### 3. Software

---

User's applications could be compiled under DOS Turbo/borland C/C++ environment. It should be include i8091.h and i8091.LIB to compile the target execution file. The execution files can be downloaded under I-8000 main system (execute 7188x.exe), and then run the target execution file as under PC system. About the I-8000's resource or environment, please refer to the manual of I-8000 system or its software programming guide.

The following section will introduce the I-8091's functions and examples.

#### 3.1 Functions

##### Constants

#define i8091	0x0e
#define YES	1
#define NO	0
#define READY	0
#define BUSY	1
#define ON	1
#define OFF	0
#define CW_CCW	0
#define PULSE_DIR	1
#define NORMAL_DIR	0
#define REVERSE_DIR	1
#define FW	0
#define BW	1
#define CW	0
#define CCW	1
#define X_axis	1
#define Y_axis	2
#define Z_axis	3

I-8091 card is a automatic protected system.

- (a) If X-axis command is executing and moving toward CW/FW direction, X-axis will immediately stop when LS14 is touched. To release this protection as long as X-axis move toward CCW/BW direction.

- (b) If X-axis command is executing and moving toward CCW/BW direction, X-axis will immediately stop when LS11 is touched. To release this protection as long as X-axis move toward CW/FW direction.
  
- (c) If Y-axis command is executing and moving toward CW/FW direction, Y-axis will immediately stop when LS24 is touched. To release this protection as long as Y-axis move toward CCW/BW direction.
  
- (d) If Y-axis command is executing and moving toward CCW/BW direction, Y-axis will immediately stop when LS21 is touched. To release this protection, as long as Y-axis move toward CW/FW direction.



### 3.1.1 Setting commands

#### (1) unsigned char i8091\_REGISTRATION(unsigned char cardNo, unsigned int address);

In order to distinguish more than one I-8091 card in I-8000 platform, the I-8091 cards should be registered before using it. This command will assign a card number="cardNo" to I-8091 card address="address" . If there is not I-8091 at the given address, this command will return "NO".

cardNo : board number 0~19.

address : select the address as well as hardware selected in chapter 2.1.

**return NO** : board not exist

**YES** : board exist

Example:

```
i8091_REGISTRATION(1, 0x080);
```

#### (2) i8091\_RESET\_SYSTEM( unsigned char cardNo )

To reset I-8091 card, this command will terminate the running command in I-8091 card. User can use this command as software emergency stop.

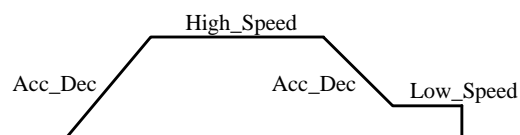
i8091\_RESET\_SYSTEM command also will clear all of setting, so, all I-8091 card's parameter should be set again.

cardNo : board number 0~19.

#### (3) i8091\_SET\_VAR(unsigned char cardNo, unsigned char DDA\_cycle, unsigned char Acc\_Dec, unsigned int Low\_Speed, unsigned int High\_Speed)

to set DDA cycle, accelerating/decelerating speed, low speed and high speed value.

cardNo : board number 0~19.



**Restriction:**

$1 \leq DDA\_cycle \leq 254$   
 $1 \leq Acc\_Dec \leq 200$   
 $1 \leq Low\_Speed \leq 200$   
 $Low\_Speed \leq High\_Speed \leq 2047$   
 $Low\_Speed \geq Acc\_Dec$   
 default value  
 DDA\_cycle = 10  
 Acc\_Dec = 1  
 Low\_Speed = 10  
 High\_Speed = 100

**Example:**

```
i8091_SET_VAR(1, 5, 2, 10, 150);
```

where

DDA\_cycle = 5      --> DDA period = (5+1)\*1.024ms = 6.144ms  
 Acc\_Dec = 2        --> Acc/Dec speed = 2/(6.144ms)^2 = 52981 p/s^2  
 Low\_Speed = 10    --> low speed = 10/6.144ms = 1628pps  
 High\_Speed = 150 --> high speed = 150/6.144ms = 24414pps

**(4) i8091\_SET\_DEFDIR(unsigned char cardNo,  
                           unsigned char defdirX,  
                           unsigned char defdirY)**

Sometimes, the output direction of X-axis, Y-axis is undesired direction due to the motor's connection or gear train. In order to unify the output direction as shown in Fig.(5) and Fig.(6). Where CW/FW direction is defined as toward outside from motor, CCW/BW direction is defined as toward inside from motor. i8091\_SET\_DEFDIR( ) command provide parameters to define the rotating direction of motor.

cardNo : board number 0~19.

defdirX : X axis direction definition

defdirY : Y axis direction definition

0 : NORMAL\_DIR

1 : REVERSE\_DIR

**(5) i8091\_SET\_MODE(unsigned char cardNo,  
                          unsigned char modeX,  
                          unsigned char modeY)**

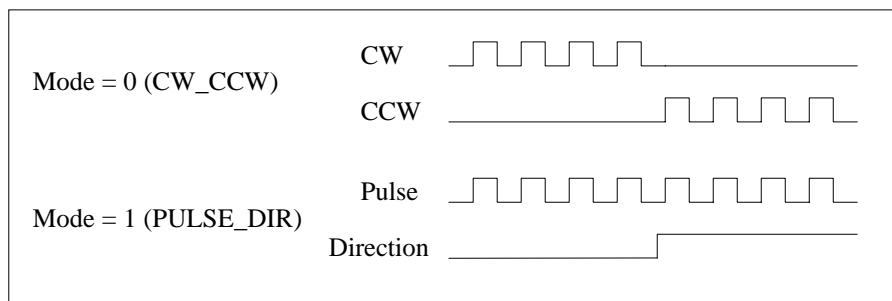
I-8091 card provide two kind output method.

cardNo : board number 0~19.

modeX : X axis output mode

modeY : Y axis output mode

0 : CW\_CCW                    CW/CCW mode  
1 : PULSE\_DIR                Pulse/Direction mode



Example:

```
i8091_SET_MODE(1,CW_CCW, PULSE_DIR);
```

**(6) i8091\_SET\_SERVO\_ON(unsigned char cardNo,  
                          unsigned char sonX, unsigned char sonY)**

To turn servo motor into servo ON(OFF) state, or turn stepping motor into hold ON(OFF) state.

cardNo : board number 0~19.

sonX : X axis servo/hold on switch

sonY : Y axis servo/hold on switch

1 : ON

0 : OFF

**(7) i8091\_SET\_NC(unsigned char cardNo, unsigned char sw);**

To set all of the following limit switches as N.C.(normal close) or N.O.(normal open). If set as N.O., those limit switches are active low. If

set as N.C., those limit switches are active high. The auto-protection will automatically change the judgement whatever it is N.O. or N.C..

Limit switches: ORG1, LS11, LS14, ORG2, LS21, LS24, EMG.

cardNo : card number 0~19.

sw: 0(NO) normal open (default).

1(YES) normal close.

### 3.1.2 Stop Commands

#### **(8) i8091\_STOP\_X(unsigned char cardNo)**

to stop X axis.

cardNo : board number 0~19.

#### **(9) i8091\_STOP\_Y(unsigned char cardNo)**

to stop Y axis.

cardNo : board number 0~19.

#### **(10) i8091\_STOP\_ALL(unsigned char cardNo)**

to stop X, Y axis immediatly.

cardNo : board number 0~19.

This command will clear all of commands pending in the FIFO.

The i8091\_RESET\_SYSTEM can be used as software emergency stop.

The i8091\_RESET\_SYSTEM command will terminate the running command and clear all of setting, so, all I-8091 card's parameter should be set again after call i8091\_RESET\_SYSTEM command.

#### **(11) i8091\_EMG\_STOP(unsigned char cardNo);**

This function is the same as i8091\_STOP\_ALL(), but i8091\_EMG\_STOP() only can be used in interrupt routine.

cardNo : card number 0~19.

This command will clear all of commands pending in the FIFO.

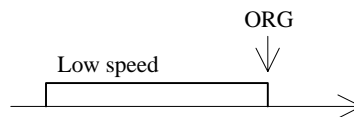
The i8091\_RESET\_SYSTEM can be used as software emergency stop.

The i8091\_RESET\_SYSTEM command will terminate the running command and clear all of setting, so, all I-8091 card's parameter should be set again after call i8091\_RESET\_SYSTEM command.

### 3.1.3 Simple motion commands

**(12) i8091\_LSP\_ORG(unsigned char cardNo,  
unsigned char DIR, unsigned char AXIS)**

Low speed move , and stop when **ORG1/ORG2** limit switch is touched.  
cardNo : board number 0~19.

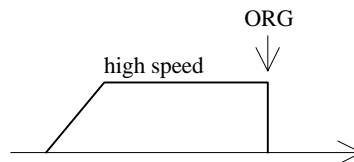


Example:

```
i8091_LSP_ORG(1, CCW, X_axis);
i8091_LSP_ORG(1, CCW, Y_axis);
```

**(13) i8091\_HSP\_ORG(unsigned char cardNo, unsigned char DIR,  
unsigned char AXIS)**

High speed move , and stop when **ORG1/ORG2** limit switch is touched.  
cardNo : board number 0~19.

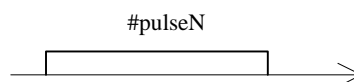


Example:

```
i8091_HSP_ORG(1, CCW, X_axis);
i8091_HSP_ORG(1, CCW, Y_axis);
```

**(14) i8091\_LSP\_PULSE\_MOVE(unsigned char cardNo,  
unsigned char AXIS, long pulseN)**

Low speed move #pulseN  
cardNo : board number 0~19.



Example:

```
i8091_LSP_PULSE_MOVE(1, X_axis, 20000);
```

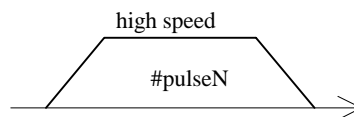
```
i8091_LSP_PULSE_MOVE(1, X_axis, -2000);
i8091_LSP_PULSE_MOVE(1, Y_axis, 20000);
i8091_LSP_PULSE_MOVE(1, Y_axis, -2000);
```

where

when pulseN>0, move toward CW/FW direction  
 when pulseN<0, move toward CCW/BW direction

**(15) i8091\_HSP\_PULSE\_MOVE(unsigned char cardNo,  
 unsigned char AXIS, long pulseN)**

High speed move #pulseN.  
 cardNo : board number 0~19.



Example:

```
i8091_HSP_PULSE_MOVE(1, X_axis, 20000);
i8091_HSP_PULSE_MOVE(1, X_axis, -2000);
i8091_HSP_PULSE_MOVE(1, Y_axis, 20000);
i8091_HSP_PULSE_MOVE(1, Y_axis, -2000);
```

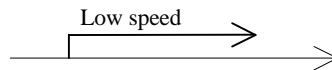
where

when pulseN>0, move toward CW/FW direction  
 when pulseN<0, move toward CCW/BW direction

**(16) i8091\_LSP\_MOVE(unsigned char cardNo,  
 unsigned char DIR, unsigned char AXIS)**

Low speed move toward direction DIR. It can be stop by i8091\_STOP\_X  
 or i8091\_STOP\_Y or i8091\_STOP\_ALL command.

cardNo : board number 0~19.



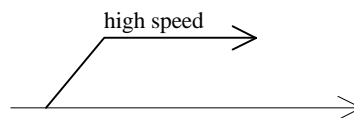
Example:

```
i8091_LSP_MOVE(1, CW, X_axis);
getch( );
i8091_STOP_X(1);
i8091_LSP_MOVE(1, CCW, Y_axis);
getch( );
i8091_STOP_Y(1);
```

**(17) i8091\_HSP\_MOVE(unsigned char cardNo,  
unsigned char DIR, unsigned char AXIS)**

High speed move toward direction DIR. It can be stop by i8091\_STOP\_X or i8091\_STOP\_Y or i8091\_STOP\_ALL command.

cardNo : board number 0~19.



Example:

```
i8091_HSP_MOVE(1, CW, X_axis);
getch( );
i8091_STOP_X(1);
i8091_HSP_MOVE(1, CCW, Y_axis);
getch( );
i8091_STOP_Y(1);
```

**(18) i8091\_CSP\_MOVE(unsigned char cardNo, unsigned char dir,  
unsigned char axis, unsigned int move\_speed)**

This command will accelerate/decelerate the selected axis's motor to the "move\_speed". This command can be continuously send to I-8091 to dynamicly change speed. The rotating motor can be stop by the



command `i8091_STOP_X()`, `i8091_STOP_Y()`, `i8091_STOP_ALL()`, or `i8091_SLOW_STOP()`.

`cardNo` : board number 0~19.

`axis` : selected axis.

1 : X axis

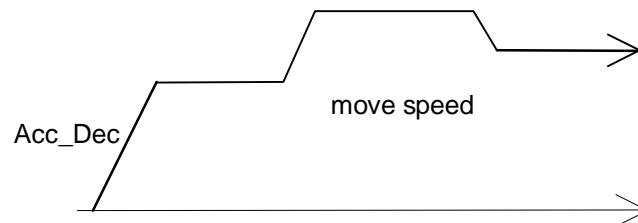
2 : Y axis

`dir` : moving direction.

0 : CW

1 : CCW

$0 < \text{move\_speed} \leq 2040$

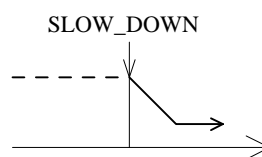


Example:

```
i8091_CSP_MOVE(1, CW, X_axis, 10);
delay(10000);
i8091_CSP_MOVE(1, CW, X_axis, 20);
delay(10000);
i8091_CSP_MOVE(1, CW, X_axis, 30);
delay(10000);
```

### (19) `i8091_SLOW_DOWN(unsigned char cardNo, unsigned char AXIS)`

to decelerate to slow speed until `i8091_STOP_X()` or `i8091_STOP_Y()` or `i8091_STOP_ALL` is executed.



Example:

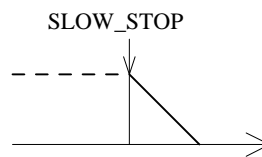
```
i8091_HSP_MOVE(1, CW, X_axis);
```

```
getch( );  
i8091_SLOW_DOWN(1, X_axis);  
getch( );  
i8091_STOP_X(1);
```

**(20) i8091\_SLOW\_STOP(unsigned char cardNo, unsigned char AXIS)**

to decelerate to stop.

cardNo : board number 0~19.



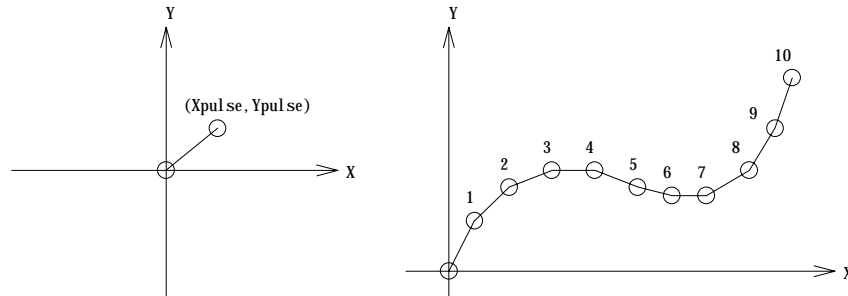
Example:

```
i8091_HSP_MOVE(1, CW, Y_axis);  
getch( );  
i8091_SLOW_STOP(1, Y_axis);
```

### 3.1.4 Interpolation commands

#### (21) i8091\_INTP\_PULSE(unsigned char cardNo, int Xpulse, int Ypulse)

This command will move a short distance (interpolation short line) in X-Y plane. This command provided a method for user to generate an arbitrary curve in X-Y plane.



cardNo : board number 0~19.

Restriction:

$$-2047 \leq \# Xpulse \leq 2047$$

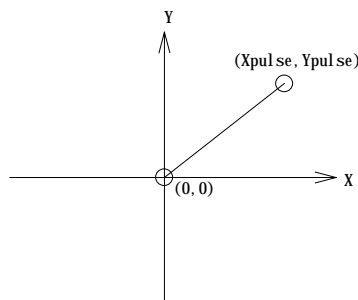
$$-2047 \leq \# Ypulse \leq 2047$$

Example:

```
i8091_INTP_PULSE(1,20,20);
i8091_INTP_PULSE(1,20,13);
i8091_INTP_PULSE(1,20,7);
i8091_INTP_PULSE(1,20,0);
i8091_INTP_PULSE(1,15,-5);
```

#### (22) i8091\_INTP\_LINE(unsigned char cardNo, long Xpulse, long Ypulse)

This command will move a long distance (interpolation line) in X-Y plane. The CPU on I-8091 card will generate a trapezoidal speed profile of X-axis and Y-axis, and execute interpolation by way of DDA chip.



cardNo : board number 0~19.

Restriction:

$$-524287 \leq \# Xpulse \leq 524287$$

$$-524287 \leq \# Ypulse \leq 524287$$

Example:

```
i8091_INTP_LINE(1,2000,-3000);
```

```
i8091_INTP_LINE(1,-500,200);
```

**(23) i8091\_INTP\_LINE02(unsigned char cardNo, long x, long y  
, unsigned int speed  
, unsigned char acc\_mode)**

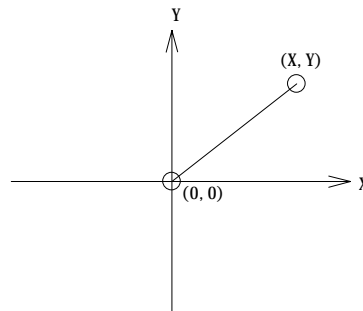
This command will move a long interpolation line in X-Y plane. Host will automatically generate a trapezoidal speed profile of X-axis and Y-axis by state-machine-type calculation method. The **i8091\_INTP\_LINE02()** only set parameters into the driver. User can directly call the **do { } while (i8091\_INTP\_STOP() !=READY)** to execute the computing entity.

cardNo : board number 0~19.

speed : 0~2040

acc\_mode: 0: enable acceleration and deceleration profile

1: disable acceleration and deceleration profile



Example:

```
i8091_INTP_LINE02(CARD1,1000,1000,100,0);
```

```
do { } while( i8091_INTP_STOP() !=READY) ; //call state machine
```

**(24) i8091\_INTP\_CIRCLE02(unsigned char cardNo, long x, long y,  
unsigned char dir, unsigned int speed,  
unsigned char acc\_mode)**

This command will generate an interpolation circle in X-Y plane. Host will

automatically generate a trapezoidal speed profile of X-axis and Y-axis by state-machine-type calculation method. The **i8091\_INTP\_CIRCLE02()** only set parameters into the driver. User can directly call the **do { } while (i8091\_INTP\_STOP() !=READY)** to execute the computing entity.

cardNo : board number 0~19.

x, y : center point of circle relate to present position.

dir : moving direction.

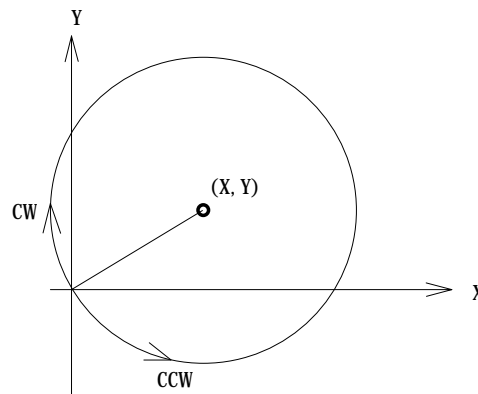
0 : CW

1 : CCW

speed : 0~2040

acc\_mode: 0: enable acceleration and deceleration profile

1: disable acceleration and deceleration profile



where r radius =  $\sqrt{X^2 + Y^2}$

Example:

```
i8091_INTP_CIRCLE02(CARD1,2000,2000,100,0);
```

```
do { } while( i8091_INTP_STOP() !=READY) ; //call state machine
```

**(25) i8091\_INTP\_ARC02(unsigned char cardNo, long x, long y, long R, unsigned char dir, unsigned int speed, unsigned char acc\_mode)**

This command will generate an interpolation arc in X-Y plane. Host will automatically generate a trapezoidal speed profile of X-axis and Y-axis by state-machine-type calculation method. The **i8091\_INTP\_ARC02()** only set parameters into the driver. User can directly call the **do { } while (i8091\_INTP\_STOP() !=READY)** to execute the computing entity.

cardNo : board number 0~19.

x, y : end point of arc relate to present position.

R : radius of arc.

if  $R > 0$  , the arc  $< 180$  degree

if  $R < 0$  , the arc  $> 180$  degree

dir : moving direction.

0 : CW

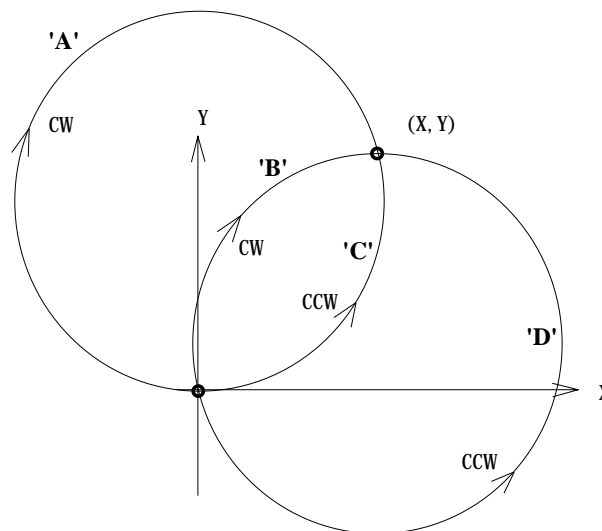
1 : CCW

R	dir	path of curve
$R > 0$	CW	'B'
$R > 0$	CCW	'C'
$R < 0$	CW	'A'
$R < 0$	CCW	'D'

speed : 0~2040

acc\_mode: 0: enable acceleration and deceleration profile

1: disable acceleration and deceleration profile



Restriction:

$$-2^{32} + 1 \leq x \leq 2^{32} - 1$$

$$-2^{32} + 1 \leq y \leq 2^{32} - 1$$

$$-2^{32} + 1 \leq R \leq 2^{32} - 1$$

$$R \geq \frac{\sqrt{x^2 + y^2}}{2}$$

Example:

```
i8091_INTP_ARC02(1,2000,-2000,2000,CW,100,0);  
do { } while( i8091_INTP_STOP()!=READY) ; //call state machine
```

## **(26) unsigned char i8091\_INTP\_STOP()**

The above 3 state-machine-type interpolation commands **i8091\_INTP\_LINE02()**, **i8091\_INTP\_CIRCLE02()** and **i8091\_INTP\_ARC02()** must use **i8091\_INTP\_STOP()** simultaneously. The state-machine-type interpolation commands are only set parameters into the driver. The computing entity is in **i8091\_INTP\_STOP()**.

This command will compute the interpolation profile. It will return READY(0) for interpolation command completed. And retrun BUSY(1) for not yet complete.

### 3.1.5 Others

#### (27) unsigned char i8091\_LIMIT\_X(unsigned char cardNo)

to request the condition of X-axis limit switches

cardNo : board number 0~19.

MSB 7	6	5	4	3	2	1	0 LSB
/EMG	/FFFF	/FFEF	/LS14	xx	xx	/LS11	/ORG1

/ORG1 : original point switch of X-axis, low active.

/LS11, /LS14 : limit switches of X-axis, low active, which must be configured as Fig.(5).

/EMG : emergency switch, low active.

/FFEF : active low, FIFO is empty

/FFFF : active low, FIFO is full

Example:

```
unsigned char limit1;
limit1 = i8091_LIMIT_X(1);
```

#### (28) unsigned char i8091\_LIMIT\_Y(unsigned char cardNo)

to request the condition of Y-axis limit switches

cardNo : board number 0~19.

MSB 7	6	5	4	3	2	1	0 LSB
ystop	xstop	xx	/LS24	xx	xx	/LS21	/ORG2

/ORG2 : original point switch of Y-axis, low active.

/LS21, /LS24 : limit switches of Y-axis, low active, which must be configured as Fig.(6).

xstop: 1:indicate X-axis is stop

ystop: 1:indicate Y-axis is stop

Example:

```
unsigned char limit2;
limit2 = i8091_LIMIT_Y(1);
```

#### (29) i8091\_WAIT\_X(unsigned char cardNo)

to wait X-axis going to STOP state.

cardNo : board number 0~19.



**(30) i8091\_WAIT\_Y(unsigned char cardNo)**

to wait Y-axis going to STOP state.

cardNo : board number 0~19.

**(31) unsigned char i8091\_IS\_X\_STOP(unsigned char cardNo)**

To check whether X axis is STOP or not.

**Return value**      0 (NO) : not yet stop  
                         1 (YES) : stop

**(32) unsigned char i8091\_IS\_Y\_STOP(unsigned char cardNo)**

To check whether Y axis is STOP or not.

**Return value**      0 (NO) : not yet stop  
                         1 (YES) : stop

## 3.2 Start up and end of program

### Start up program

When you are going to use I-8091 card, there are some commands must be implement in previous.

#### **i8091\_REGISTRATION(CARD1,0x80)**

set CARD1 address, (where CARD1=1)

#### **i8091\_RESET\_SYSTEM(CARD1);**

reset system

#### **i8091\_SET\_VAR(CARD1, DDA, AD, LSP, HSP);**

set DDA cycle, accelerating/decelerating speed, low speed and high speed value

#### **i8091\_SET\_DEFDIR(CARD1, xdir, ydir);**

define direction.

#### **i8091\_SET\_MODE(CARD1, xmode, ymode);**

define output mode.

#### **i8091\_SET\_SERVO\_ON(CARD1, xson, yson);**

set servo ON/OFF.

define output mode.

#### **i8091\_SET\_NC(CARD1, nc);**

To config limit switch as N.C. or N.O.

### end of program

#### **i8091\_RESET\_SYSTEM(CARD1);**

To reset system

### Example

```
//-----
-
#define CARD1      1
typedef struct {
    int          address;
    unsigned char DDA,AD;
    unsigned int  LSP,HSP;
    unsigned char xmode,ymode;
    unsigned char xdir,ydir;
    unsigned char xson,yson;
    unsigned char NCmode;
```

```
} i8091CardType;
i8091CardType card1;
//-----
void main ()
{
    card1.address=PortAddress[i8091Slot];
    card1.DDA    = 10;
    card1.AD     = 5;
    card1.LSP    = 5;
    card1.HSP    = 100;
    card1.xmode  = CW_CCW;
    card1.ymode  = CW_CCW;
    card1.xdir   = NORMAL_DIR;
    card1.ydir   = NORMAL_DIR;
    card1.xson   = ON;
    card1.yson   = ON;
    card1.NCmode= OFF;
    i8091_REGISTRATION(CARD1, card1.address);
    i8091_RESET_SYSTEM(CARD1);
    i8091_SET_VAR(CARD1, card1.DDA, card1.AD, card1.LSP, card1.HSP);
    i8091_SET_DEFDIR(CARD1, card1.xdir, card1.ydir);
    i8091_SET_MODE(CARD1, card1.xmode, card1.ymode);
    i8091_SET_SERVO_ON(CARD1, card1.xson, card1.yson);
    i8091_SET_NC(CARD1, card1.NCmode);
    Delay(100);
    .
    .
//--- end of program -----
    i8091_RESET_SYSTEM(CARD1);
}
}
```

## 4. Example

### 4.1 Detect I-8091 card

```
//-----
// detect i8090,i8091,i8092 card
//-----
#include "8000.h"
#include "s8090.h"

#define i8090 0x0d
#define i8091 0x0e
#define i8092 0x0f
#define NOCARD 0x00
#define MAX_SLOT_NO 8
unsigned int PortAddress[8]={0x080, 0x0a0, 0x0c0, 0x0e0, 0x140, 0x160,
0x180, 0x1a0};
//-----
void main ()
{
unsigned char slot,temp;

for (slot=0; slot<MAX_SLOT_NO; slot++)
{
temp=inportb(PortAddress[slot]);
switch (temp)
{
case i8090: //i8090 3-axis encoder card
Print("Slot %d = i8090\r\n",SlotNum);
return i8090;
case i8091: //i8091 2-axis stepping card
Print("Slot %d = i8091\r\n",SlotNum);
return i8091;
case i8092: //i8092
Print("Slot %d = i8092\r\n",SlotNum);
```

```

        return i8092;
    default:
        Print("Slot %d = No Card\r\n",SlotNum);
        return NOCARD;
    };
    Delay(500);
};
}

```

## 4.2 Example: DEMO.cpp

```

//-----
// demo.cpp for I-8091 card
//
// This program can test all of following command
// -----I-8091 testing kit-----
// (0)Exit          (A)i8091_IS_X_STOP      (K)i8091_CSP_MOVE
// (1)i8091_RESET_SYSTEM  (B)i8091_IS_Y_STOP      (L)i8091_SLOW_DOWN
// (2)i8091_SET_VAR      (C)i8091_LIMIT_X        (M)i8091_SLOW_STOP
// (3)i8091_SET_DEFDIR   (D)i8091_LIMIT_Y        (N)i8091_INTP_PULSE
// (4)i8091_SET_MODE     (E)i8091_LSP_ORG        (O)i8091_INTP_LINE
// (5)i8091_SET_SERVO_ON (F)i8091_HSP_ORG        (P)i8091_INTP_LINE02
// (6)i8091_SET_NC       (G)i8091_LSP_PULSE_MOVE (Q)i8091_CIRCLE02
// (7)i8091_STOP_X       (H)i8091_HSP_PULSE_MOVE (R)i8091_ARC02
// (8)i8091_STOP_Y       (I)i8091_LSP_MOVE        (S)User Define Testing
// (9)i8091_STOP_ALL     (J)i8091_HSP_MOVE
//
// The output pulse amount can be monitored from i8090 card. When directly
// connect the CW/PULSE, CCW/DIR of i8091 to i8090. The encoder value
// can be shown on the LED display. Its format as following.
// ex:    0.2 1 2 8 : X-axis encoder value
//         5 3.4 0 2 : Y-axis encoder value
//         1 0 0.1 0 : Z-axis encoder value
// the dot(.) stands for which axis.
//-----

```

## 4.3 Example: DEMO1.cpp

```

//-----
// demo1.cpp for I-8091 card
//
// This a simple program to test I-8091 command
// i8091_INTP_LINE()
// i8091_INTP_LINE02()
//-----

```

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