Gibbot v4 PCB

Andrew Griesemer

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1 dsPIC Pinout

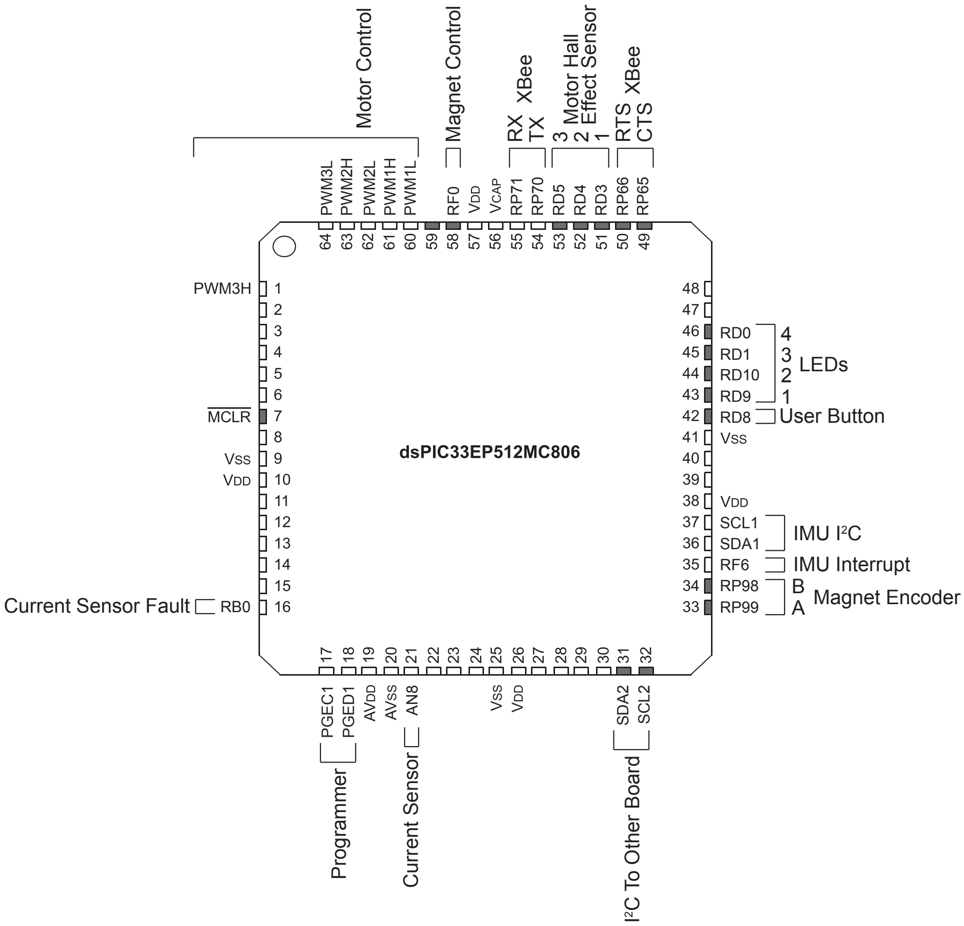


Figure 1: dsPIC Pin Assignments for main board

2 Power Regulation

The board is powered by a 24V power cable.

Component	Current per unit	Total Component	Value Source
5V			
2 Encoders	78mA x 2	156mA	62mA maximum no load current + 8mA x 2 maximum output current[1]

[1]E3 1600 CPR product page http://www.usdigital.com/products/e3

3.3V			
dsPIC		320mA	Absolute maximum rating current from VSS[2]
Status LEDs	3.3mA x 6	20mA	Assuming 3.3V and 1k resistor
IMU		10mA	3.9mA gyro + 6mA magnetometer[3]
IR LEDs	10mA x 6	60 mA	3.3V and 330 ohm resistor
Total		**0.410 A**	

2.1 Digital Isolation

3 Inertial Measurement Unit - MPU9150

The MPU9150 is a 9 axis sensor that draws data from a 3-axis gyroscope, a 3-axis accelerometer and a 3-axis magnetometer. One sensor is attached to each board. Neither sensor has been configured. The supporting circuitry follows is shown in Figure ?? below [4].

This iteration of the board does not have pull-up resistors on the I^2C communication lines that are required for communication between the MPU9150 and the dsPIC.

4 XBee

5 Magnet Control

6 BLDC Motor Driver

6.1 BLDC Motor Background

A Brushless DC Motor is similar to a brushed DC motor except it lacks the internal brushes that allow a typical DC motor to reverse the direction of current flow as the rotor coil rotates within the magnetic stator. In order to drive a BLDC motor the direction of current flow must be commutated by external control circuitry. The benefit of BLDC motor over brushed motor is they tend to be lighter weight for the same amount of torque and they have increased longevity.

A typical BLDC motor has two or more coils and a sensor that can determine the rotational position of the rotor. A microcontroller reads the state of the sensor and changes the direction of current across the coils in order to maximize torque. The BLDC motor on the Gibbot is the Maxon EC 60 Flat which has 3 coils and 3 Hall Effect sensors that detect the rotational position of the rotor. The commutation pattern from the Maxon E-Paper Catalog is shown in Figure ??a and modified for clarity in Figure ??b.

For a lower power application the control of each coil of the motor could be accomplished by a typical H-bridge. Because the Gibbot requires at least 10A at 24V we were forced to create high powe H-bridges from MOSFETs. Figure ?? shows the H-bridge configuration for a single coil.

6.2 HIP4086 Driver

The driver circuit uses Intersil's HIP4086 3-Phase MOSFET driver[6]. This chip solves two issues with driving the MOSFETs from a dsPIC, (1) stepping up the control voltage for the low side MOSFET from the microcontroller's logic level 3.3V to the 15V required to fully turn on the MOSFET. (2) Because the high side MOSFET's source is connected to the motor coil, the Gate-to-Source voltage must be 15V plus the motor drive voltage to ensure the MOSFET is fully on. The HIP4086 accomplishes this with Bootstrap capacitors (more info in Section ??). The chip also has added functionality such as programmable deadtime and a bootstrap capacitor refresh pulse.

[2]dsPIC33EP512MC806 datasheet http://ww1.microchip.com/downloads/en/DeviceDoc/70616g.pdf
[3]MPU-9150 datasheet http://dlnmh9ip6v2uc.cloudfront.net/datasheets/Sensors/IMU/PS-MPU-9150A.pdf
[4]MPU9150 Product Specification p21 http://www.invensense.com/mems/gyro/documents/PS-MPU-9150A-00v4_3.pdf
[5]Figure ?? is taken from pg 32 of the Maxon E-Paper Catalog http://epaper.maxonmotor.ch/en/
[6]Datasheet http://www.intersil.com/content/dam/Intersil/documents/hip4/hip4086-a.pdf

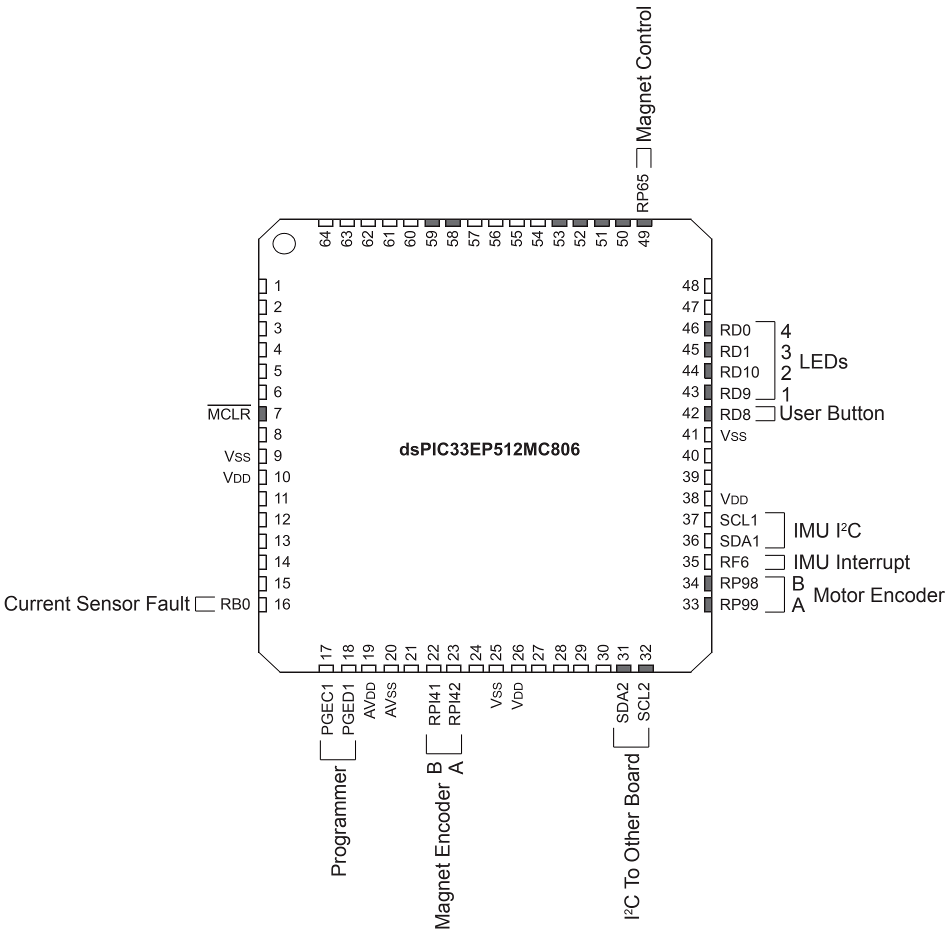


Figure 2: dsPIC Pin Assignments for secondary board

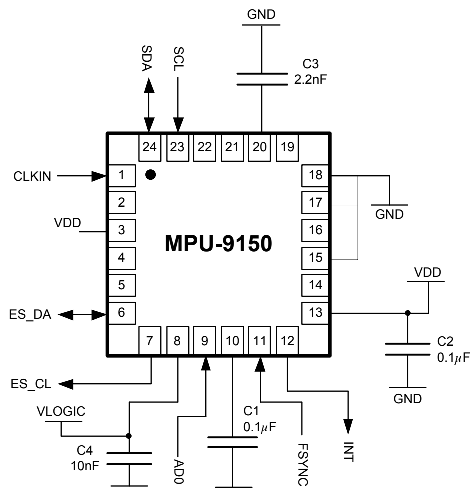
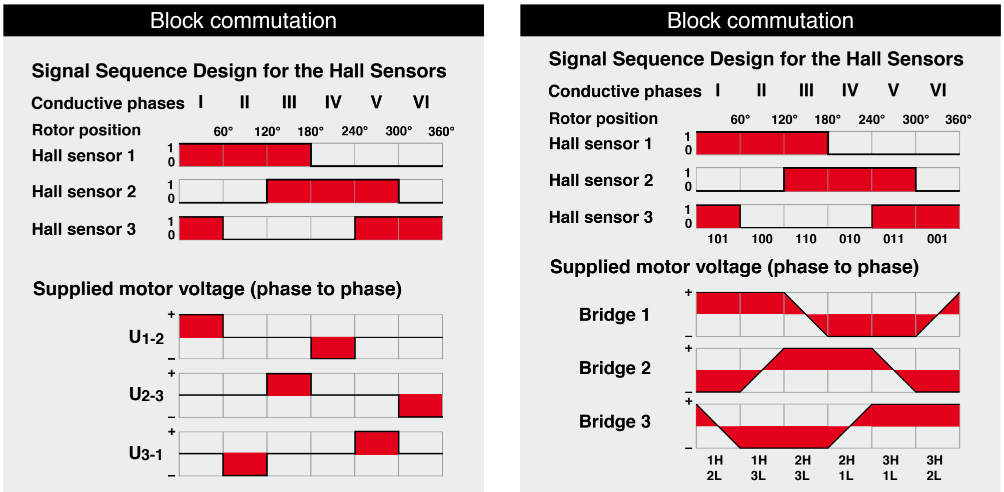


Figure 3: MPU9150 Typical Operating Circuit

6.3 MOSFET Selection

The bridge MOSFETs are the most critical components in the BLDC driver.

Max Continuous Current The required continuous current for the motor to achieve the desired torque



(a) (b)

Figure 4: The commutation pattern for the Maxon EC 60 Flat Motor.[5]

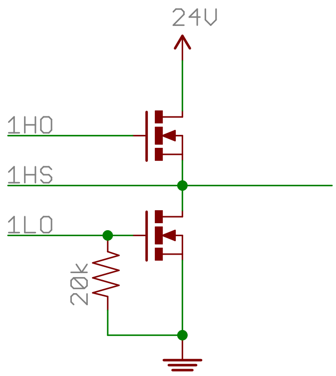


Figure 5: A single H bridge for the BLDC motor

was calculated to be 10A[7].

Max Drain to Source Voltage (V_{DS}) The required drain-to-source voltage is the same as the Motor Supply Voltage, which was 48V, but is now 24V. To keep the design flexible to the higher voltage range V_{DS} is set a value above 48V.

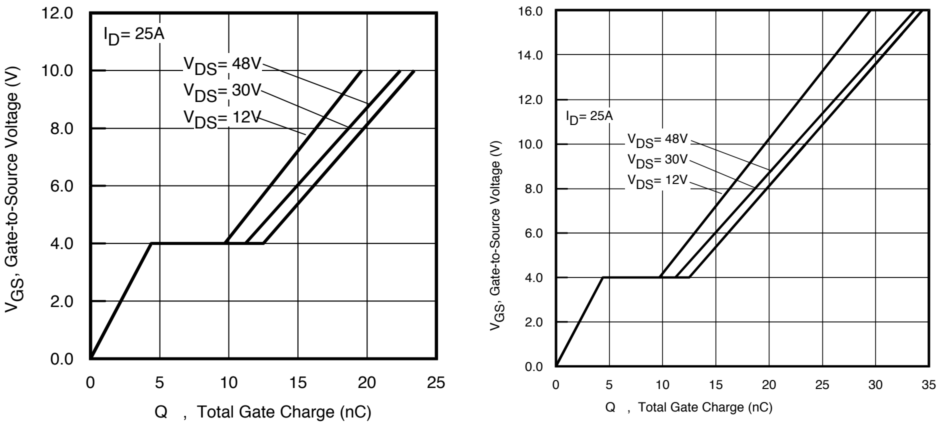
Max Gate-to-Source Voltage (V_{GS}) The required gate-to-source voltage is determined by the gate drive voltage of the HIP4086 driver. This gate drive voltage is the same as the supply voltage for the HIP4086. The recommended maximum operating supply voltage on the HIP4086 datasheet[8] is 15V. To keep the design flexible to supply voltages for the HIP4086 the max gate-to-source voltage should be at least $\pm 15V$.

Gate Charge (Q_G) The turn on speed of the MOSFET is partially determined by the gate charge. The gate charge listed on a datasheet is typically the gate charge at a $V_{GS} = 5V$. If the HIP4086 has a supply voltage of 15V, in this application $V_{GS} = 15V$. The appropriate value of V_{GS} can be determined from Figure **??**. For the configuration From the plot, the Gate Charge is 33nC.

On State Drain-to-Source Resistance ($R_{DS(ON)}$) Should be minimized.

Maximum Power Dissipation (P_D) This value is not considered in MOSFET selection. While the ability of the MOSFET to dissipate heat from conducting is important, the way in which $P_{D,MAX}$ is

[7]WHAT SIMULATION?
[8]HIP4086 Datasheet pg 5 http://www.intersil.com/content/dam/Intersil/documents/hip4/hip4086-a.pdf
[9]IRFR3806PbF datasheet pg 3 http://www.irf.com/product-info/datasheets/data/irfr3806pbf.pdf

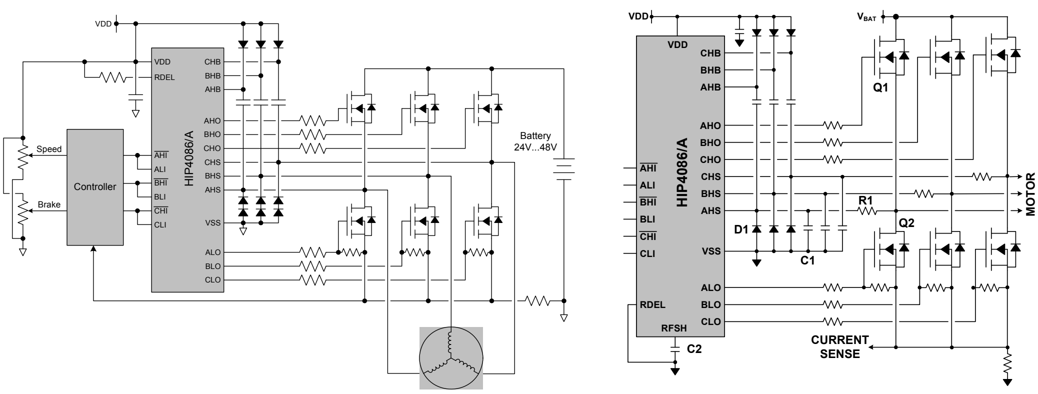


(a) (b)

Figure 6: Typical Gate Charge vs. Gate-to-Source Voltage (a) from the IRFR3806 datasheet [9] (b) linearly extrapolated to $V_{GS} = 15V$.

defined varies widely between manufacturers. Moreover, the ability of a MOSFET to dissipate heat should not vary significantly between different devices in the same physical package. Determining a specification for power dissipation would also be difficult because it involves a combination of the power dissipated during turn-on and turn-off periods when R_{DS} is high and the power dissipated during the fully on state at the much lower $R_{DS(ON)}$.

6.4 Clamping Circuit



(a) HIP4086 Datasheet (b) HIP4086 Demo Board User guide

Figure 7: Alternate clamping circuitry from the HIP4086 documentation[10].

6.5 Calculate Required Deadtime

6.6 Bootstrap Capacitor, Diode and Resistor Selection

The boot capacitor value is chosen not only to supply the internal bias current of the high-side driver but also, and more significantly, to provide the gate charge of the driven FET without causing the boot voltage to sag excessively. In practice, the boot capacitor should have a total charge that is about 20 times the gate charge of the driven power FET for approximately a 5% drop in voltage after charge has been transferred from the boot capacitor to the gate capacitance.

[10]HIP4086 datasheet pg 12 http://www.intersil.com/content/dam/Intersil/documents/hip4/hip4086-a.pdf and HIP4086 Demo Board User Guide, Application Note 1829 pg 7 http://www.intersil.com/content/dam/Intersil/documents/an18/an1829.pdf

$$Q_{total} = Q_{gate} + Period * (I_{HB} + I_{GateLeak})$$

Where:
Q_{gate} = Gate Charge of the MOSFET
$Period$ = On time of the high side MOSFET
I_{HB} = Worst case high side current through the xHB pin of the HIP4086
$I_{GateLeak}$ = Leakage current of the MOSFET gate

$$Q_{total} = 18nC + \frac{1}{20,000Hz} * (100uA + 100nA) = 23nC$$

$$Cboot = \frac{Q_{total}}{RippleVoltage}$$

6.7 Set Dead Time on HIP4086

Because the gate capacitance of the MOSFET keeps the MOSFET on for a period of time after the control signal has gone low, there must be a delay between the turn-off event of one PWM output in a complementary pair and the turn-on event of the other. Otherwise shoot through might occur when both MOSFETs are conducting causing the power to short to ground. The time between transitions of the control PWM signal is called dead time. In the current configurations of the Gibbot dead time is redudantly programmed into both the dsPIC PWM control as well as the HIP4086.

Dead time on the HIP4086 is set using a resistor between ground and the pin R_{DEL} on the HIP4086. Figure **??** from the HIP4086 datasheet can be used to set R_{DEL} approximately.

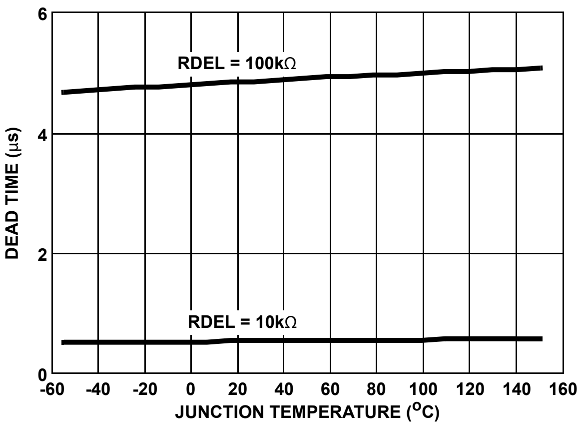


Figure 8: R_{DEL} vs. Dead Time[11]

7 IR LEDs

The Gibbot is mounted with six Optitrack IR LEDs. The LEDs are mounted on the face plate in three clusters (2 above the top magnet, 1 above the motor, 3 above the bottom magnet) so that the Optitrack cameras can detect the position of each magnet and the motor joint.

7.1 IR LED Resistor Values

In this iteration all of the LEDs are powered on 5V lines. The minimum resistor values were calculated as follows:

[11] From HIP4086 3-Phase Bridge Driver Configurations and Applications pg 4
http://www.intersil.com/content/dam/Intersil/documents/an96/an9642.pdf

1 LED

$$\frac{5V - (1 * V_{F,MAX})}{I_{F,MAX}} = \frac{5V - 1.6V}{100mA} = 34\Omega$$

2 LED

$$\frac{5V - (2 * V_{F,MAX})}{I_{F,MAX}} = \frac{5V - 3.2V}{100mA} = 18\Omega$$

3 LED

$$\frac{5V - (3 * V_{F,MAX})}{I_{F,MAX}} = \frac{5V - 4.8V}{100mA} = 2\Omega$$

Where:
$V_{F,MAX} = 1.6V$
$I_{F,MAX} = 100mA$
To avoid the risk of running maximum current through the resistors these value should be increased by about 50%.

8 Current Sensor

The current sensor used on the board is the ACS716KLATR-12CB-T which has an optimized accuracy range of +/- 12.5A and a linear sensing range of +/- 37.5A. The sensor outputs an analog voltage proportional to the current through its sensing path, centered at 1.65V for zero current with a slope of 37mV/A.

8.1 dsPIC ADC Inductor

The dsPIC33EP512MC806 datasheet[12] recommends an inductor between the V_{DD} and A_{VDD} to improve ADC noise rejection. The inductance of this inductor is calculated as follows:

$$L = \left(\frac{1}{2 * \pi * \frac{F_{CNV}}{2} * \sqrt{C}} \right)^2 = \left(\frac{1}{2 * \pi \frac{F_{CNV}}{2} * \sqrt{.1uF}} \right)^2$$

Where:
F_{CNV} = ADC Conversion Rate
Until the ADC is configured and a conversion rate is determined the inductor should be replaced with a 0ohm resistor.

8.2 ACS716 Filter Capacitor

The ACS716 allows for a filter capacitor to limit noise in the sensor. The capacitance is determined from the plot below. Since the motor is driven with a PWM frequency at 20kHz an appropriate bandwidth is between 10 and 20kHz. The corresponding capacitance from Figure **??** is between 5 and 9nF.

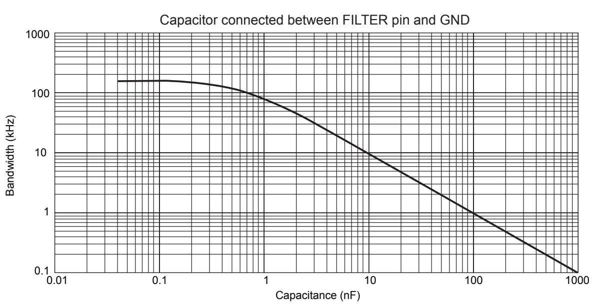


Figure 9: ACS716 Bandwidth versus External Capacitor Value, C_F[13]

[12] dsPIC33EPXXX(GP/MC/MU)806/810/814 datasheet pg 32
http://ww1.microchip.com/downloads/en/DeviceDoc/70616g.pdf
[13] From ACS716 Datasheet pg 10 http://www.allegromicro.com/~/media/Files/Datasheets/ACS716-Datasheet.ashx

8.3 Overcurrent Threshold

The overcurrent threshold voltage allows us to detect if the current level is above a user-set limit, likely because of a short. The overcurrent limit is set using a voltage divider composed of R_H and R_L to set a reference voltage on pin V_{OC}. When the current through the current path is detected to be higher than

$$C_{OC} = I_{OC} * 37mV/A$$

the ACS716 drives the output of the FAULT pin high. We chose to set the current threshold at 30A.

$$C_{OC} = 30A * 37mV/A = 1.1V$$

Resistors values of $R_H = 2k$ and $R_L = 1k$ set V_{OC} at

$$V_{OC} = 3.3V * \frac{1k}{1k + 2k} = 1.1V$$

To prevent the fault detection from triggering because of noise a capacitor is connected between fault and ground. The maximum recomended value of 22nF is used. In previous iterations this features was configured, but the FAULT pin was not connected to the PIC. The pin is now connected to pin B0 on the PIC.

9 Wire Gages

9.1 Wire Sources

The standard wire gages on purchased connectors are:

Orbex Slip Ring 2A: AWG26 or AWG28

Sparkfun JST PH Jumper Wire: 24 AWG

Sparkfun JST SH Jumper Wire: 28 AWG

Mechatronics Lab Red & Black 22 AWG

Nick's stores Red, Blue & Green 30 AWG

NxR 30 AWG Black
22 AWG Green
16-19 AWG Lime Green
22 AWG Black, Blue, Red White, Green, Orange in Grey case
16 AWG Blue, Brown Green
Unknown AWG Red, Black, White shielded clear
22 AWG Striped

9.2 Wire Requirements

24V Power
Current Sensor
Main Board 5V Power 22 AWG Red & Black
Secondary Board 5V Power 22 AWG Red & Black
1 LED Power 30 AWG Red & Black
2 LED Power 30 AWG Red & Black
3 LED Power 30 AWG Red & Black
Top Magnet Control 30 AWG Red, Green, Blue & Red
Bottom Magnet Power 22 AWG Red & Black
Top Magnet (Slip Ring) 28 AWG Red, Yellow & Black
Bottom Magnet (Slip Ring) 28 AWG Red, Yellow & Black
Top Magnet Encoder 30 AWG Black, Red, Green & Blue
Bottom Magnet Encoder 30 AWG Black, Red, Green & Blue
Motor Encoder 30 AWG Black, Red, Green & Blue
I2C 30 AWG Green & Blue

10 PCB Bill of Materials

Part Number	Quantity	Description
Microcontrollers & Sensors		
PIC1, PIC2	2	DSPIC33EP512MC806
X1	1	XBee Series 1 Wired Antenna
CS1	1	ACS716KLATR-**6BB**-T Current Sensor
IMU1, IMU2	2	MPU-9150 (Out of Stock)
	2	MPU-6000 (Replacement)
MD1	1	HIP4086 BLDC Motor Driver
Resistors		
R40, R41, R43	3	0 ohm
R70	1	3.3 Ω
R34, R35, R36, R37, R38, R39	6	10 Ω
R25	1	22 Ω
R24	1	47 Ω
R2, R7, R8, R9, R10, R11, R12, R13, R17, R18, R19, R31, R66, R67, R68, R69, R77, R78	18	1k Ω
R1	1	2k Ω
R14, R42, R61, R73	4	2.2k Ω
R16	1	10kΩ
R4, R5, R6	3	20k Ω
R3	1	330k Ω
Capacitors		
C34, C35, C36, C37, C50, C51, C52, C53, C61	9	.01uF 0603
C1, C11, C12, C13, C21, C22, C25, C26, C28, C29, C31, C32, C33, C38, C40, C41, C42, C43, C54, C55, C56, C57, C59, C60, C62	25	.1uF 0603
C7, C8	2	.1uF 0603 25V Rated
C39	1	.1uF 0603 50V Rated
C6, C46, C47	3	.1uF 1206
C17, C18, C19	3	.03uF 0603 16V Rated
C2	1	1nF 0603
C64	1	1uF 1206
C23, C27	2	2.2nF 0603
C20, C24	2	10nF 0603
C15, C48, C49, C63	4	10uF 0603 Polarized
C5, C30	2	10uF 0603
C14, C44, C45, C58, C65	5	10uF 1206
C66, C67	2	10uF 1206
C4	1	22nF 0603
C9, C10	1	22uF 0603 15V Rated
C3	1	7nF 0603
Diodes		
D1, D2, D3, D4, D5, D7, D8, D9, D10, D11, D12	11	ES1B 100V, 1A
Power Converters		
P2	1	24V to 5V DC-DC Converter
P3	1	24V to 15V & 5V Linear Regulator
P1, P4	2	5V to 3.3V LDO Regulator
P5	1	15V to 5V Linear Regulator
Digital Isolators		
DI2, DI3	2	1 Channel

Part Number	Quantity	Description
DI1	1	6 Channel
MOSFETs		
1H, 1L, 2H, 2L, 3H, 3L	6	IRFR3806
M1, M2	2	SSM3K329RLFCT-ND, 30V, Logic Level
LEDs		
	12	0603 LED
Switches & Buttons		
SW1	1	SPDT Slide Switch
RESET1, USER1, RESET2, USER2	4	Momentary, Normally Off, Tactile Switch
Connectors		
J1, J6, J7, J8, J9, J14, J15, J20, J21	9	JST PH 2pos Right Angle Header
	9+	JST PH 2pos Housing
	5+	JST KR 2pos IDC
J4, J13	2	JST PH 3pos Right Angle Header
	2+	JST PH 3pos Housing
	5+	JST KR 3pos IDC
J2, J17, J18	3	JST PH 4pos Right Angle Header
	2	JST PH 4pos Housing
	5+	JST KR 4pos IDC
J3, J12	2	JST PH 8pos Right Angle Header
	2	JST PH 8pos Housing
	2	JST PH 8pos IDC
	40+	JST PH Contact 22-26AWG
	40+	JST PH Contact 24-30AWG
	40+	JST PH Contact 28-32AWG
J10, J11, J16, J19	4	JST SH/SR 2pos Right Angle Header
	4+	JST SR 2pos IDC
J5	1	JST SH/SR 5pos Right Angle Header
	1	JST SR 5pos IDC
	20+	JST SH Contacts 28-32AWG
JP1, JP2, JP3, JP4, JP5	5	Molex Mini Fit Jr. 2pos Right Angle Header
	5	Molex Mini Fit Jr. 2pos Vertical Header
	5	Molex Mini Fit Jr. 2pos Housing
JP6	1	Molex Mini Fit Jr. 3pos Right Angle Header
	1	Molex Mini Fit Jr. 3pos Housing
	15	Molex Mini Fit Jr. Contacts 16AWG
	15	Molex Mini Fit Jr. Contacts 18-24AWG
	15	Molex Mini Fit Jr. Contacts 22-28AWG
Miscellaneous		
	10	18650 Battery Holder