

Introduction to Motion Control

ROCHESTER MAKERSPACE

2021

Class Objectives

1. Become familiar common types of motors
2. Focus on motors typically used by hobbyists
3. Understand how to control motors
4. Understand cautions when using motors with microcontrollers/microcomputers
5. Provide projects to demonstrate motor control on Raspberry Pi and Arduino
6. Provide examples of typical motor applications
7. Provide list of resources for learning more

Class notes and code

- ▶ All the class notes and code can be downloaded from GitHub:
 - ▶ <https://github.com/RochesterMakerSpace/MotionControlClass>
 - ▶ Use the following if not found above:
 - ▶ <https://github.com/jszybist/MotionControlClass>
- ▶ Pull down the green “Code” button and select “Download ZIP”

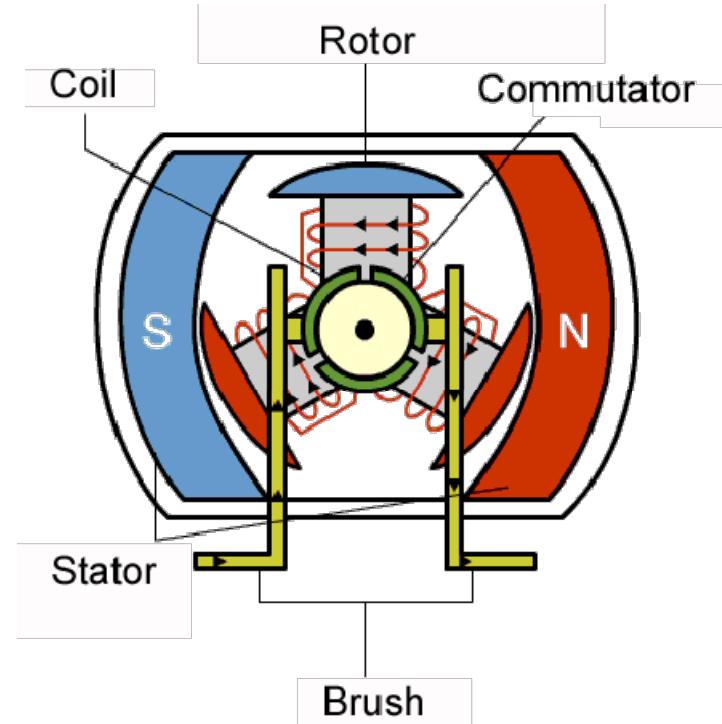
Types of Common Electric Motors

- ▶ There are two main motor classifications, ac and dc, with three application areas, constant speed, variable speed and position (or torque) control.
- ▶ AC Motors
 - AC motors are typically associated with industrial applications and will not be address further in this class.
- ▶ DC Motors
 - Although large DC motor are common in industrial application smaller DC motor are favored by the hobbyist and include:
 - ▶ DC Brushed Motors – simple, cost effective, lightweight and easy to control. Excellent torque at low speed but produce electrical noise. Used as drives for hobby vehicles.
 - ▶ DC Brushless Motors -- mechanically simpler than brushed motors but require more complex controllers and gearboxes and can be found in multicopters and drones.
 - ▶ Servo Motors – good for projects needing precise control of angular or linear position such as robots.
 - ▶ Stepper Motors – move in discrete, precise steps and are found in CNC machines and 3D printers.

Brushed DC Motor Description

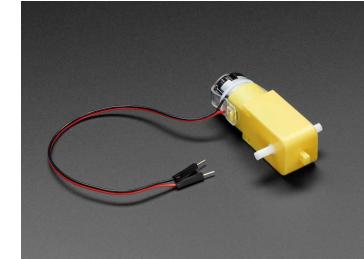
► Components:

- ▶ Stator: Generates a stationary magnetic field that surrounds the rotor
- ▶ Rotor (armature): Made up of one or more windings. Produce a magnetic field when energized
- ▶ Brushes: As the motor turns, carbon brushes slide over the commutator, coming in contact with different segments of the commutator
- ▶ Commutator: Segments are attached to different rotor windings, generating a dynamic magnetic field inside the motor.



Brushed DC Motor Example

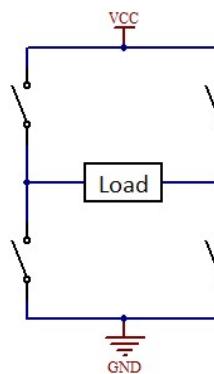
- ▶ DC Gearbox Motor – “TT Motor” – 200 RPM – 3 to 6 VDC
 - ▶ Operating Voltage Range: 3~7.5V
 - ▶ Rated Voltage: 6V
 - ▶ Max No-load Current (3V): 140 mA
 - ▶ Max No-load Current (6V): 170 mA
 - ▶ No-load Speed (3V): 90 rpm
 - ▶ No-load Speed (6V): 160 rpm
 - ▶ Max Output Torque: 0.8 kgf cm
 - ▶ Max Stall Current: 2.8 A
- ▶ Pololu Micro Metal Garmotor
 - ▶ See spec sheet



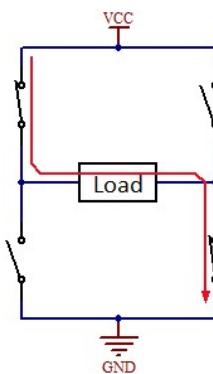
Brushed DC Direction Control: H-Bridge

- ▶ An H-Bridge circuit contains four switches with the motor at the center forming an H-like arrangement.
- ▶ Closing two particular switches at the same time reverses the polarity of the voltage applied to the motor. This causes change in spinning direction of the motor.
- ▶ The control circuit prevents closing both switches on the same side of the H-Bridge, thus preventing a short from Vcc to GND.

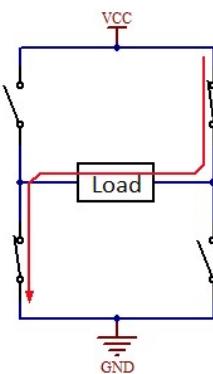
H bridge topology



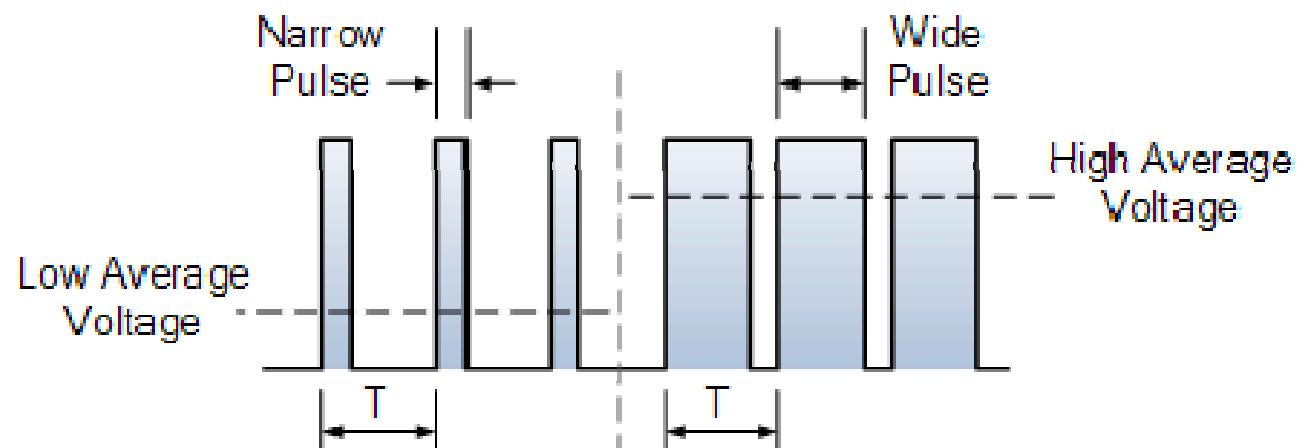
Connecting the load
in one direction



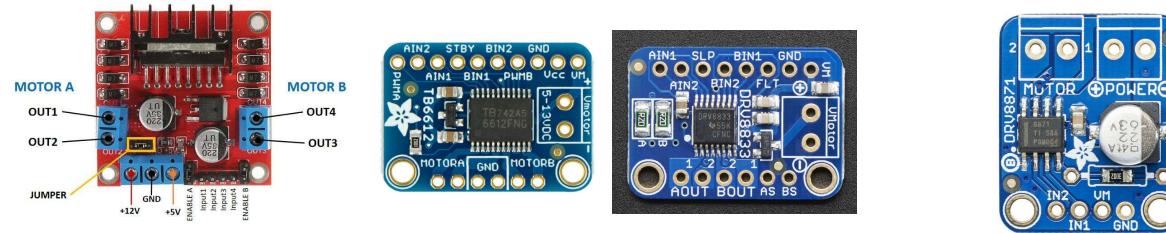
Connecting the load
in the other direction



Brushed DC Speed Control: PWM



Brushed DC Motor Drivers



Model	L298N	TB6612	DRV8833	DRV8871
Current	2A	1.2A	1.5A	2A
Peak Current	3A	3.3A	2A	3.6A
Operating Voltage	3.2 – 40 V	4.5 – 15 V	2.7 – 10.8 V	6.5 – 45 V
Efficiency	40-70%	91-95%	70-90%	
Total MCU pins	6	6	4	2
PWM Pins	2	2	2/4	2
Number of motor outputs	2	2	2	1
Technology	Bipolar	MOSFET	MOSFET	MOSFET
Approximate cost	\$2.50	\$5.00	\$5.00	\$7.50

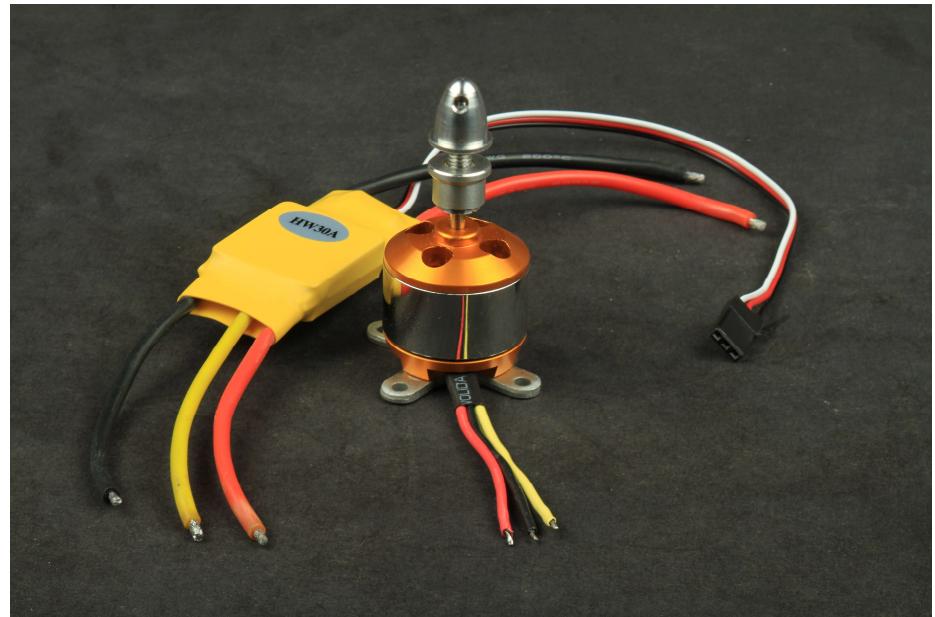
Servo Motor Description

- ▶ Components:
 - ▶ Motor
 - ▶ Potentiometer: Shaft position
 - ▶ Gear Assembly: Reduce RPM to increase torque
 - ▶ Controlling circuit: Feedback
 - ▶ Input signal: PWM pulse width
- ▶ An error signal is generated between the potentiometer and the input signal. The error signal causes the motor shaft to turn, changing the voltage on the potentiometer, thus reducing the error until the motor stops when the error is 0.

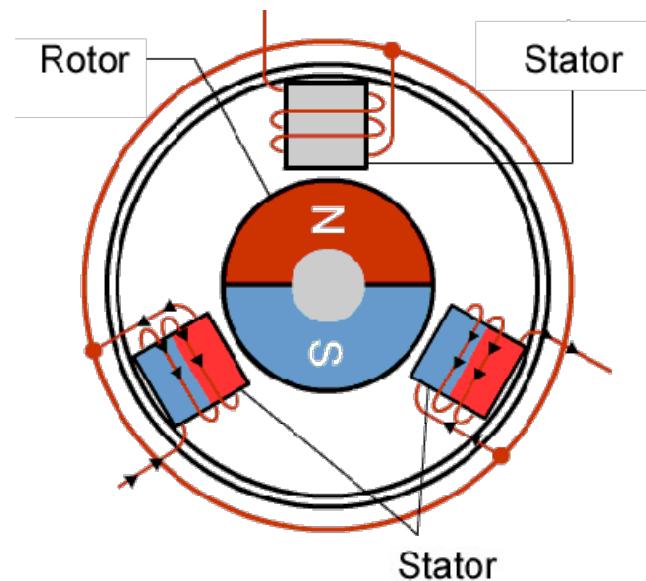
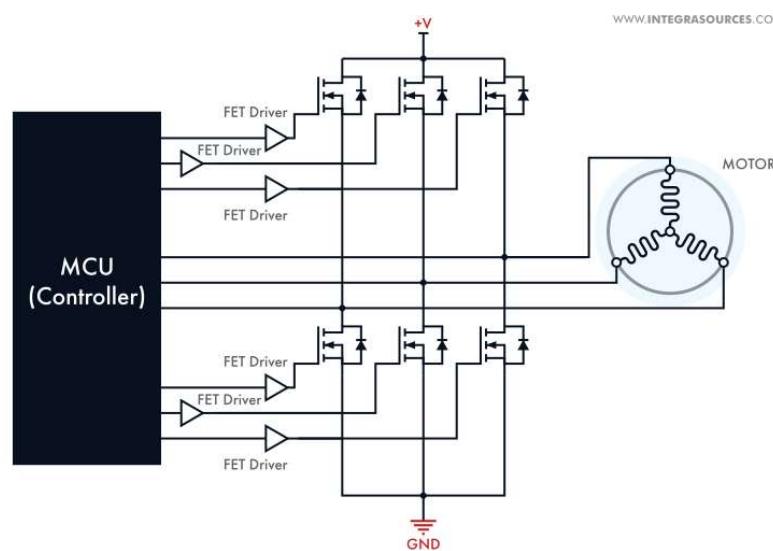


Brushless DC Motor (BLDC) Description

- ▶ Brushless DC motor control is not quite as simple as the regular brushed type. Brushless motors require a controller that can sense the proper time to reverse the voltage to the coils.
- ▶ Some motors have built-in hall-effect sensors that can detect the orientation of the rotor. Controllers for this type of motor require sensor inputs to read these hall sensors.
- ▶ Other 'sensorless' motor controllers sense the back EMF in the motor coils themselves to detect the rotor position. Most ESC (Electronic Speed Controls) for brushless RC motors use this technique.
- ▶ Brushless motors designed for autonomous and remote control aircraft and vehicles typically require a separate controller. These are typically of the sensorless type and use standard servo type pulsed signals for speed control.
- ▶ Applications include RC controlled planes and drones.



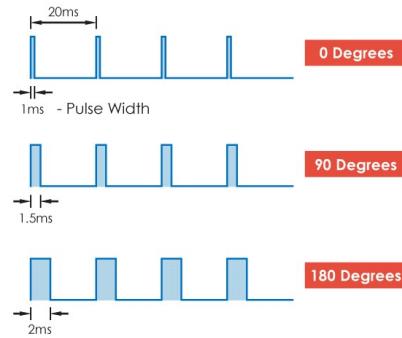
Brushless DC Motor (BLDC) Description



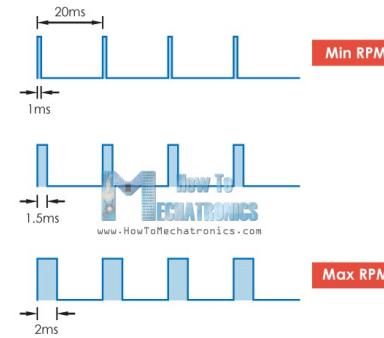
Servo/BLDC Control



SERVO MOTOR CONTROL



BLDC MOTOR CONTROL



Stepper Motor Description

► Advantages

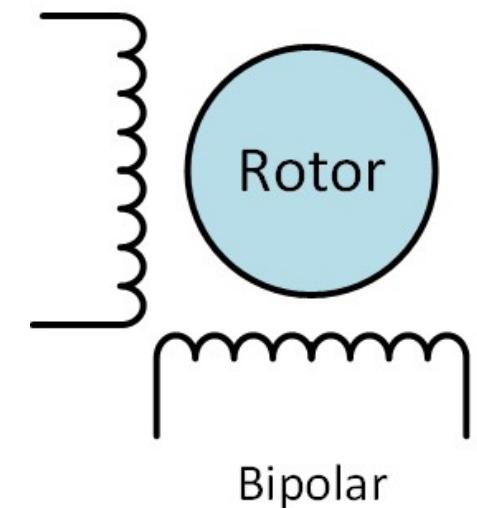
- ▶ Steppers don't require a sensor to detect the motor position since the motor moves by simply counting steps.
- ▶ Although the motor does need a controller it doesn't need complex calculation or tuning to work properly.
- ▶ With micro stepping high positional accuracy can be achieved.
- ▶ Good torque at low speed and great for holding position.

► Disadvantages

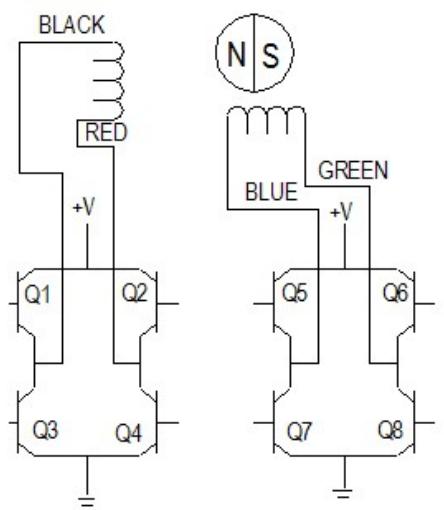
- ▶ Can miss steps if torque load is too high.
- ▶ Always drain maximum current.
- ▶ Low torque and noisy at high speeds.

Bipolar Stepper Motor Example

- ▶ TPP-47-002
 - ▶ NEMA 17
 - ▶ Step Angle: 1.8 degree (200 steps/rev)
 - ▶ Holding Torque: 33Ncm(47oz.in)
 - ▶ Rated Current/phase: 1.2 A
 - ▶ Phase Resistance: 2.4 ohms
 - ▶ Inductance: 4.7 mH
 - ▶ Application: 3D Printer



Bipolar Full Step Sequence



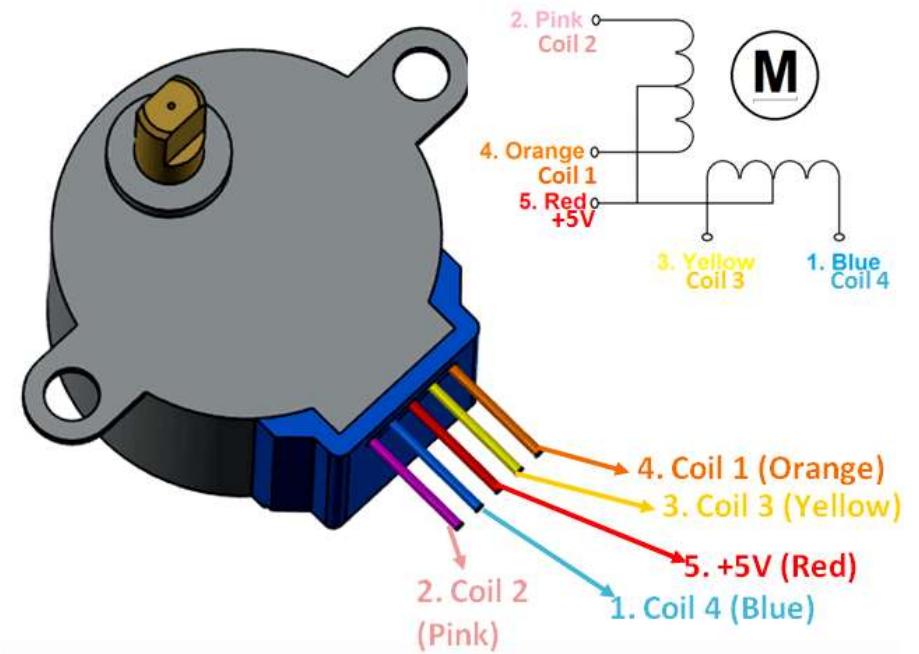
CW Rotation →

Unipolar Step	Q2-Q3	Q1-Q4	Q6-Q7	Q5-Q8
1	ON	OFF	ON	OFF
2	OFF	ON	ON	OFF
3	OFF	ON	OFF	ON
4	ON	OFF	OFF	ON
1	ON	OFF	ON	OFF

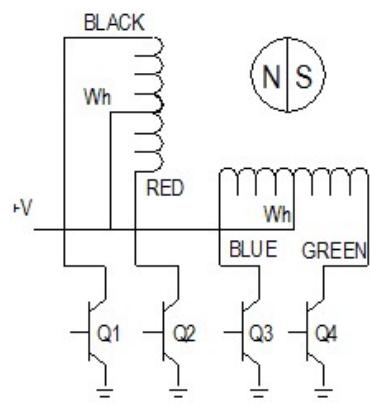
CCW Rotation ↑

Unipolar Stepper Motor Example

- ▶ 28BYJ-48
 - ▶ Rated Voltage: 5V DC
 - ▶ Number of Phases: 4
 - ▶ Stride Angle: $5.625^\circ / 64$
 - ▶ Pull in torque: 300 gf.cm
 - ▶ Insulated Power: 600VAC/1mA/1s
 - ▶ Coil: Unipolar 5 lead coil



Unipolar Full Step Sequence

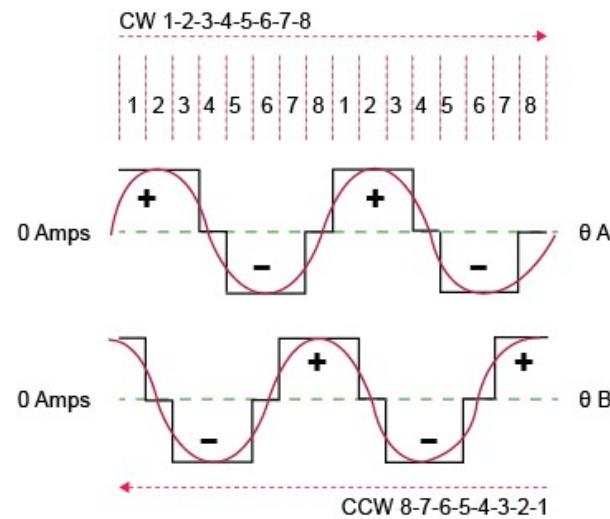


Unipolar Step	Q1	Q2	Q3	Q4
1	ON	OFF	ON	OFF
2	OFF	ON	ON	OFF
3	OFF	ON	OFF	ON
4	ON	OFF	OFF	ON
1	ON	OFF	ON	OFF

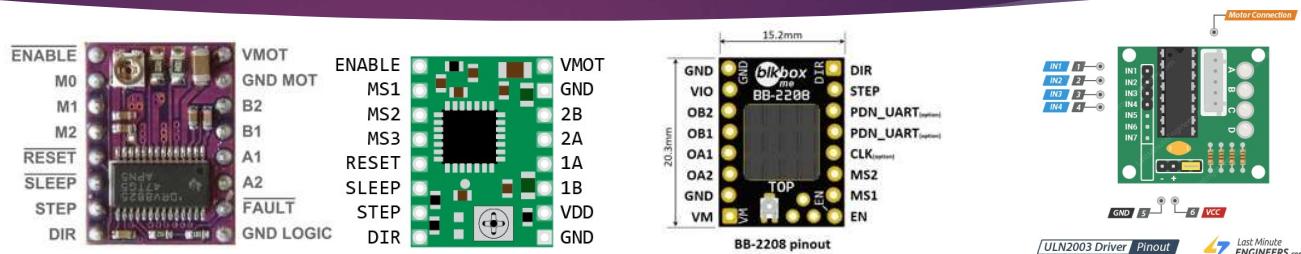
CW Rotation ↑

CCW Rotation ↓

Stepper Motor Half Step Sequence



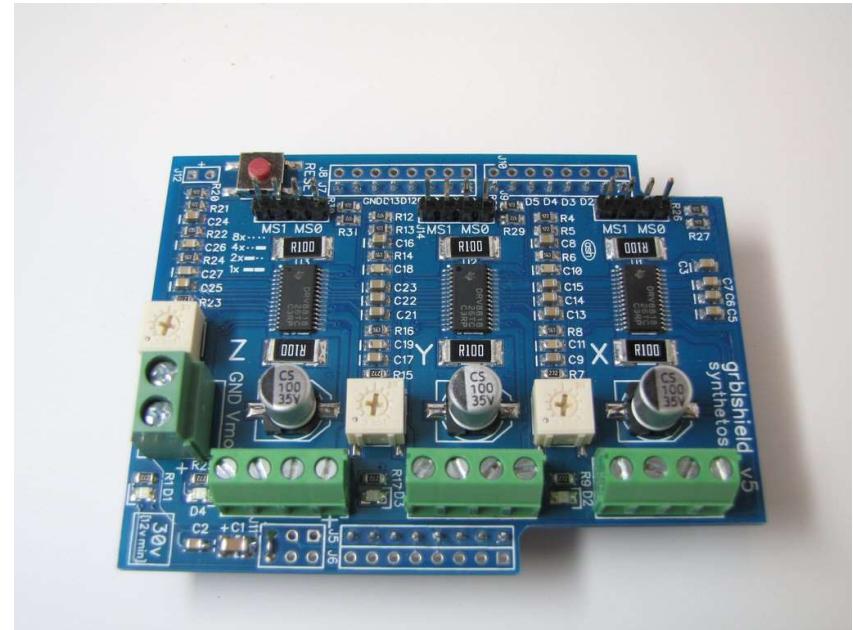
Stepper Motor Drivers



Model	DRV8825	A4988	TMC2208	ULN2003
Type	Bipolar	Bipolar	Bipolar	Unipolar
Max Current per coil	2.2 A	2.0 A	2.0 A	600 mA
Continuous current per coil	1.5 A	1.0 A	1.2 A	
Max step resolution	1/32	1/16	1/256	N/A
Logic range	2.5 – 5.25 V	3 – 5.5 V	3 – 5 V	5 V
Supply Voltage Range	8.2 – 45 V	8 – 35 V	5.5 – 36 V	50 V
Interface	Step/Dir	Step/Dir	Step/Dir	Channels
Approximate cost	\$9.00	\$2.00	\$15.00	\$1.50

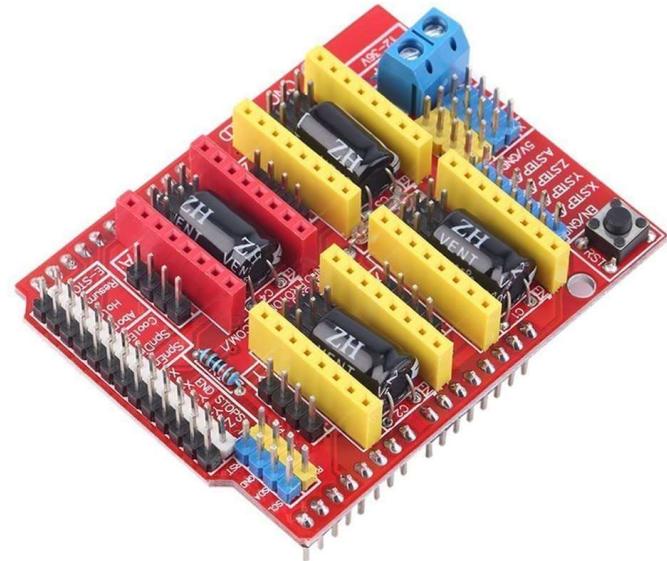
Integrated Stepper Motor Driver

- ▶ gShield v5
 - ▶ ~ \$50
 - ▶ Arduino Uno Shield
 - ▶ 3x TI DRV8818 Stepper Drivers
 - ▶ Runs grbl firmware
 - ▶ <https://github.com/gnea/grbl>
 - ▶ Application: CNC Router



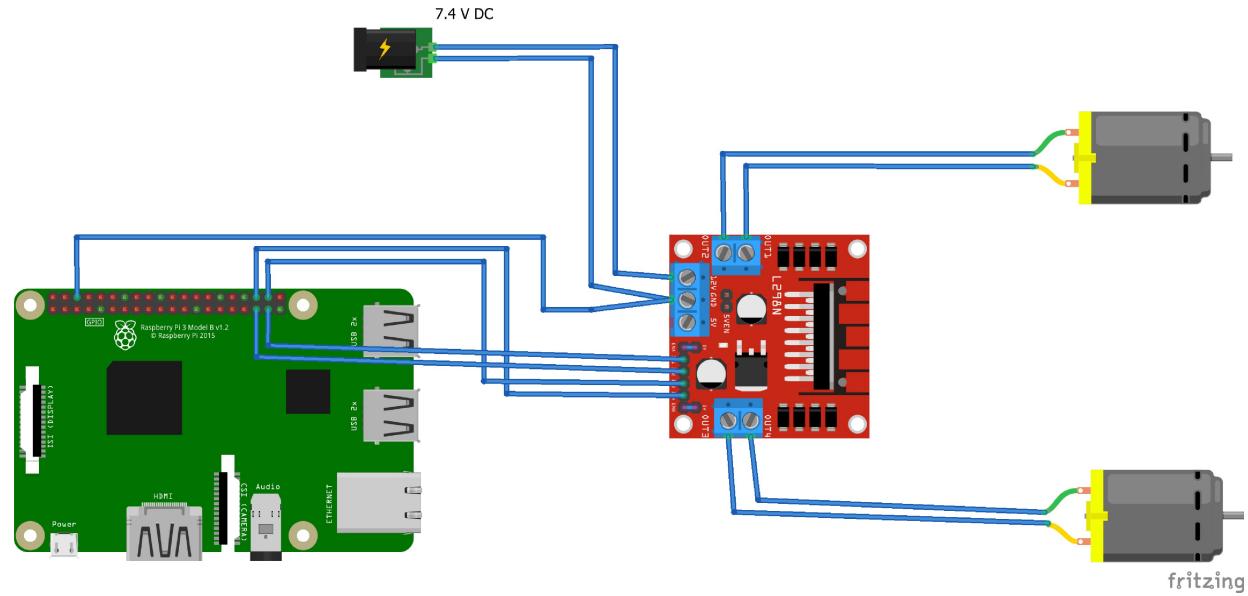
Integrated Stepper Motor Driver

- ▶ RAMPS 1.4
 - ▶ ~ \$20 including DRV8825 Motor Drivers
 - ▶ Arduino Mega Shield
 - ▶ Different drivers may be used
 - ▶ Runs Marlin firmware
 - ▶ <https://marlinfw.org/>
 - ▶ Application: 3D printer



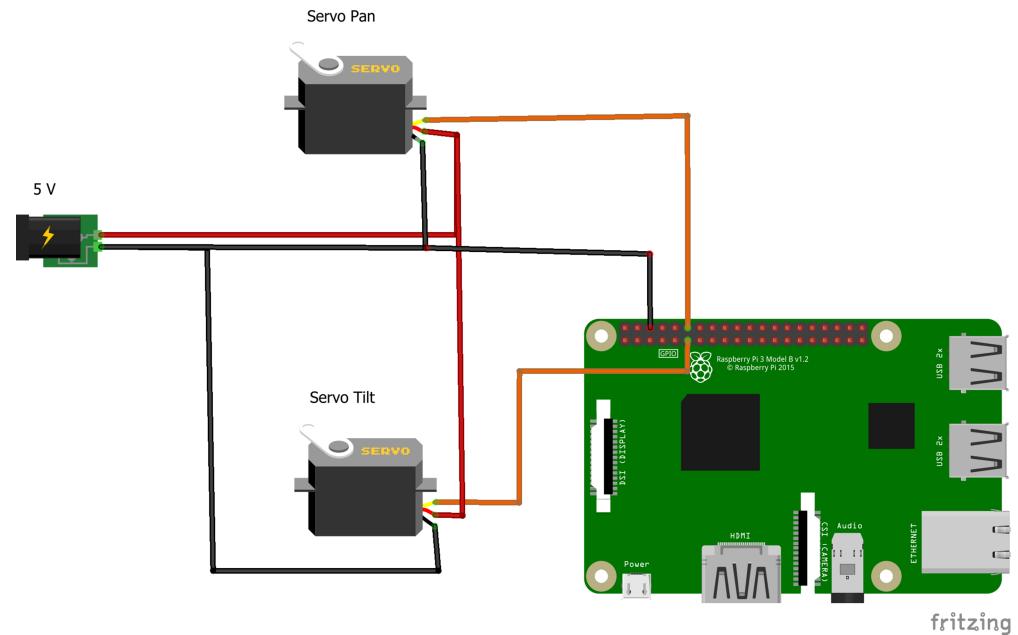
Project – Brushed DC Motor

- ▶ Driver: L298N
- ▶ Raspberry Pi Wiring
 - ▶ IN1 to GPIO26
 - ▶ IN2 to GPIO19
 - ▶ IN3 to GPIO20
 - ▶ IN4 to GPIO16
- ▶ Set power supply output to 7.4 V
- ▶ Open MotionControlClass/BrushedDC/key_brushedDc.py using the Geany IDE
- ▶ Run key_brushedDc.py
- ▶ Put cursor focus in terminal window that pops up.
- ▶ Arrow keys to move motors.
- ▶ Enter key to stop
- ▶ 'q' to terminate program



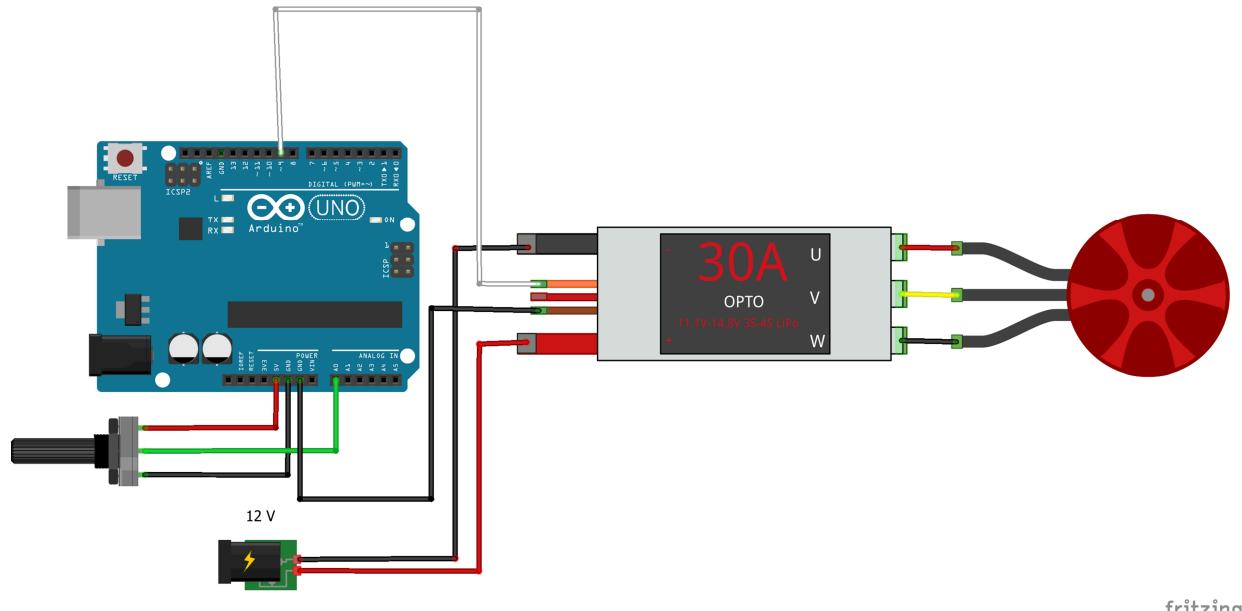
Project – Servo Motor

- ▶ Use mechanical crane
- ▶ Raspberry Pi Wiring:
 - ▶ Servo Pan: GPIO18
 - ▶ Servo Tilt: GPIO17
- ▶ Set power supply output to 5V
- ▶ Open MotionControlClass/ServoMotor/key_ServoMotor.py using the Geany IDE
- ▶ Run key_ServoMotor.py
- ▶ Put cursor focus in terminal window that pops up.
- ▶ Arrow keys to move motors.
- ▶ Enter key to stop
- ▶ 'q' to terminate program



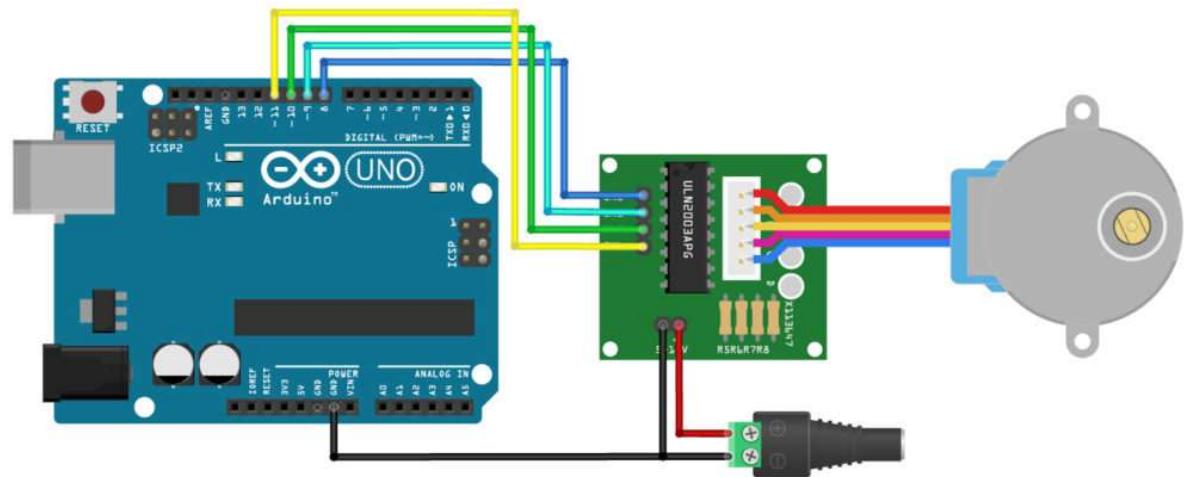
Project – Brushless DC Motor

- ▶ Driver: ESC
- ▶ Guide:
<https://howtomechatronics.com/tutorials/arduino/arduino-brushless-motor-control-tutorial-esc-bldc/>
- ▶ Arduino Wiring:
 - ▶ Speed control: Pin 9 (White)
 - ▶ Pot Wiper: A0 (Green)
- ▶ Set power supply output to 12V but do not enable the power supply
- ▶ Open MotionControlClass/BldcMotor/BldcMotor.ino using the Arduino IDE
- ▶ Upload the sketch
- ▶ Turn pot full clockwise
- ▶ Enable the power supply
- ▶ The motor speed is controlled with the pot. If the pot is full on (counter clockwise) on then the motor will not start and must be calibrated (see Guide).



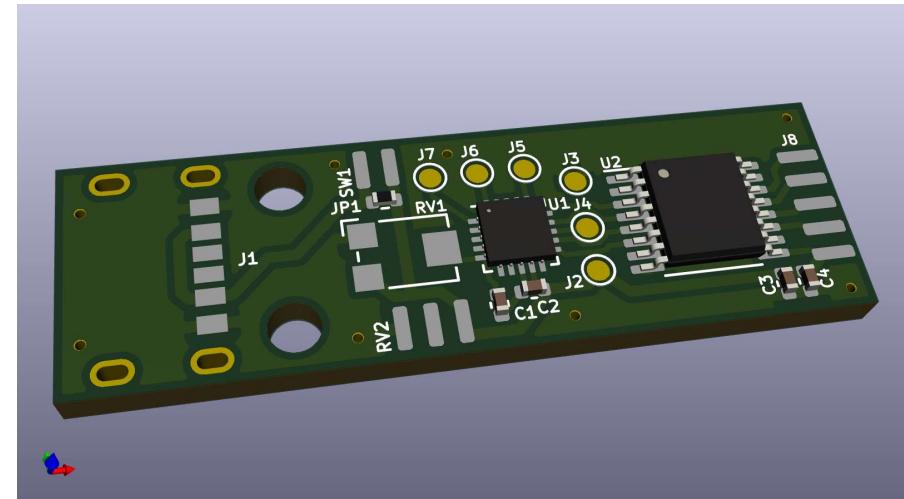
Project – Unipolar Stepper Motor

- ▶ Driver: ULN2003
- ▶ Guide: <https://www.makerguides.com/28byj-48-stepper-motor-arduino-tutorial/>
- ▶ Arduino Wiring
 - ▶ IN1 to Pin 11
 - ▶ IN2 to Pin 10
 - ▶ IN3 to Pin 9
 - ▶ IN4 to Pin 8
- ▶ Set power supply output to 5V
- ▶ Open MotionControlClass/UnipolarStepper/BasicUnipolarStepper/BasicUnipolarStepper.ino using the Arduino IDE
- ▶ Upload the sketch
- ▶ The motor will rotate 1 revolution, reverse and rotate 1 revolution in the opposite direction and repeat forever.



Project: Unipolar with ATTiny

- ▶ Driver: ULN2003
- ▶ Plug in 28BYJ-48 motor with red wire nearest C3/C4
- ▶ Power board with USB-C power block
- ▶ The motor will rotate in the clockwise direction looking at the shaft side of the motor.



Project: Unipolar with ATTiny

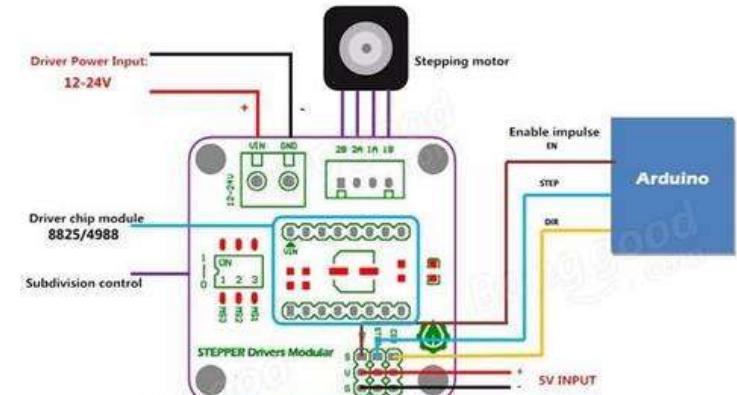
This ATTiny code snippet demonstrates how to half-step sequence the ULN2003 driver. This function is called in a forever loop that includes a delay:

```
// ----- Event loop ----- //
while (1) {
    _delay_us( StepDelay_us );
    decrMotor();
}
```

```
static inline void decrMotor( void ){
    switch( MotorState ){ //prior to decrement
    case 7: //1001->X__->0001
        clear_bit( S1_PORT, S1 );
        break;
    case 6: //0001->_ ^_->0011
        set_bit( S3_PORT, S3 );
        break;
    case 5: //0011->_ X->0010
        clear_bit( S4_PORT, S4 );
        break;
    case 4: //0010->_ ^_->0110
        set_bit( S2_PORT, S2 );
        break;
    case 3: //0110->_ X_->0100
        clear_bit( S3_PORT, S3 );
        break;
    case 2: //0100->_ ^_->1100
        set_bit( S1_PORT, S1 );
        break;
    case 1: //1100->_ X_->1000
        clear_bit( S2_PORT, S2 );
        break;
    case 0: //1000->_ ^->1001
        set_bit( S4_PORT, S4 );
        MotorState = 8;
        break;
    } MotorState--;
}
```

Project – Bipolar Stepper Motor

- ▶ Driver: DRV8825
- ▶ Guide: <https://www.makerguides.com/drv8825-stepper-motor-driver-arduino-tutorial/>
- ▶ Arduino Wiring:
 - ▶ EN (Enable impulse): jumper to GND
 - ▶ DIIR: Arduino Pin 3
 - ▶ STEP: Arduino Pin 2
 - ▶ 5V INPUT: Arduino 5V and GND
- ▶ Set power supply output to 12V but do not enable the power supply
- ▶ Adjust current limit according to Guide: Current Limit = Vref X 2 (will have to enable power supply)
- ▶ Open MotionControlClass/BipolarStepper/BasicBipolarStepper/BasicBipolarStepper.ino using the Arduino IDE
- ▶ Upload the sketch
- ▶ Enable the power supply output
- ▶ The motor will slowly in both directions for one revolution and then faster in both directions for several revolutions
- ▶ Try changing subdivision control: Disable power supply, change DIP switch, Enable power supply



Note:

This module need two sets of power supply. Steping motor voltage: 12-24V.
Logic power supply voltage: 5V

There is a port in control terminal, En is enable impulse(Active Low).
Step is step impulse input. Dir is direction impulse.