
THORLABS

GVS011 and GVS012

GVS111 and GVS112

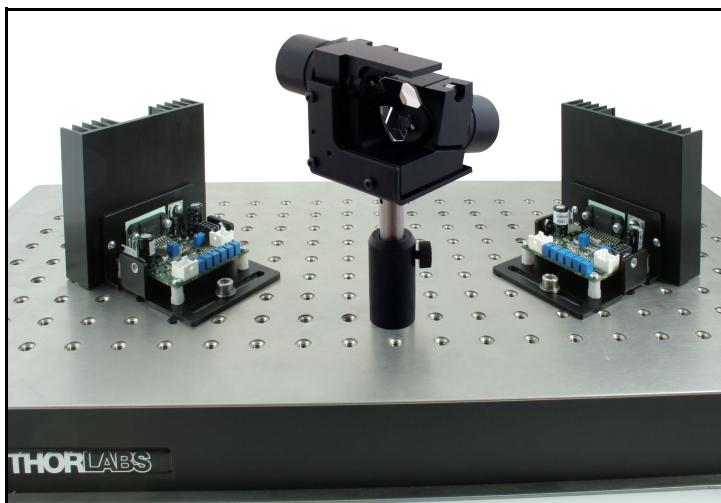
GVS211 and GVS212

GVS311 and GVS312

GVS411 and GVS412

Large Beam Diameter Scanning Galvo Systems

User Guide



Original Instructions

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Chapter 1 Overview

1.1 Introduction

The GVS series scanning galvo systems are board level, mirror positioning systems, designed for integration into OEM or custom laser beam steering applications. The single axis systems consist of a motor and mirror assembly, a mounting bracket, a tuned driver card and a heat sink. The dual axis systems comprise two mirror and motor assemblies, an X-Y mounting bracket, two driver cards with heat sinks and a post mounting plate. The post mounting plate also serves as a tip/tilt platform adapter and allows the system to be fitted to a PY003 tilt platform.

The driver cards feature a small footprint, fixings for easy mounting to a heatsink and a simple analog command signal interface. Typical applications include laser scanning, laser display, and laser marking.

A choice of mirror coating is available as follows:

GVS011 and GVS012: Single- and Dual-Axis Systems with Protected Silver Mirrors

GVS111 and GVS112: Single- and Dual-Axis Systems with Protected Gold Mirrors

GVS211 and GVS212: Single- and Dual-Axis Systems with 400-750 nm Broadband Dielectric Mirrors (E02)

GVS311 and GVS312: Single- and Dual-Axis Systems with High Power Dual Band (532 and 1064 nm) Nd: YAG Mirrors (K13)

GVS411 and GVS412: Single- and Dual-Axis Systems with UV-Enhanced Aluminium Mirrors (F01).

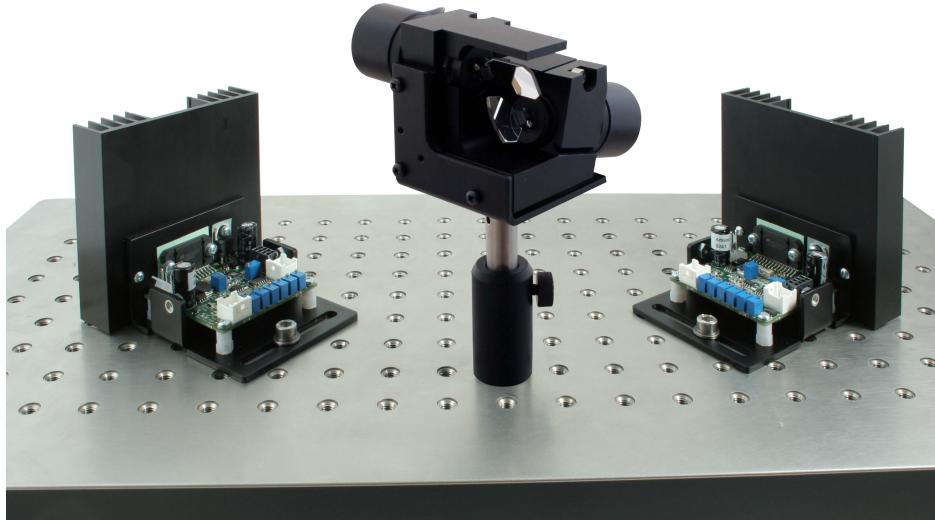


Fig. 1.1 GVS012 2-Axis Galvo System (Post not included)

1.2 System Description

1.2.1 Introduction

Galvo Scanners are widely used in applications such as laser etching, confocal microscopy, and laser imaging.

A galvanometer is a precision motor with a limited travel, usually much less than 360 degrees, whose acceleration is directly proportional to the current applied to the motor coils. When current is applied, the motor shaft rotates through an arc. Motion is stopped by applying a current of reverse polarity. If the current is removed, the motor comes to rest under friction.

Typically, the term 'Galvo' refers only to the motor assembly, whereas a 'Galvo Scanner' would include the motor, together with a mirror, mirror mount and driver electronics.

A description of each component in the system is contained in the following sections.

1.2.2 The Galvanometer

The galvanometer consists of two main components: a motor that moves the mirror and a detector that feeds back mirror position information to the system.

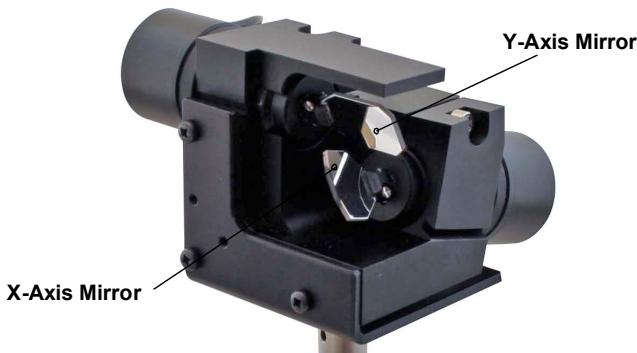


Fig. 1.2 GVS012 Dual Axis Galvo/Mirror Assembly

Our galvo motor features a moving magnet, which means that the magnet is part of the rotor and the coil is part of the stator. This configuration provides faster response and higher system-resonant frequencies when compared to moving coil configurations.

Mirror position information is provided by a capacitive position detector.

1.2.3 The Mirror

The mirror assembly is attached to the end of the actuator, and deflects the light beam over the angular range of the motor shaft. Scanning galvo applications demand high speed and frequencies of the shaft rotation, and so the inertia of the actuator and mirror assembly can have a profound effect on the performance of the system. High resonant frequencies and enhanced stiffness in the mirror assembly also add to system performance by increasing bandwidth and response times.

Wavelength ranges and damage threshold of the different mirror coatings are details below:

Part No	Coating	Wavelength	Damage Threshold
GVS01x	Silver	500 nm - 2.0 μ m	3 J/cm ² at 1064 nm, 10 ns pulse
GVS11x	Gold	800 nm - 20.0 μ m	2 J/cm ² at 1064 nm, 10 ns pulse
GVS21x	E02	400 nm - 750 nm	0.25 J/cm ² at 532 nm, 10 ns pulse
GVS31x	K13	532 nm and 1064 nm	5 J/cm ² at 1064 nm, 10 ns pulse
GVS41x	F01	250nm - 450nm	0.3 J/cm ² at 355 nm, 10 ns, pulse

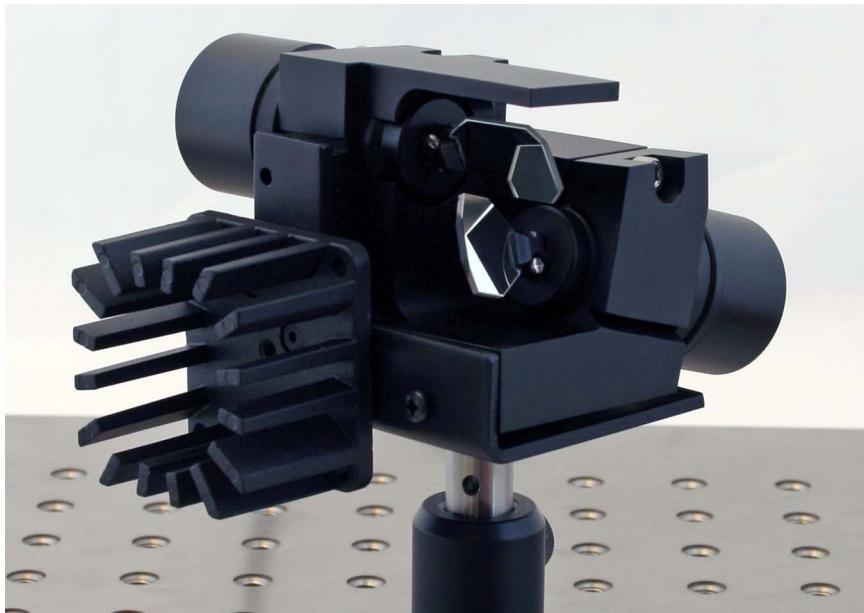


Fig. 1.3 GVS012 Motor/Mirror Assembly with GHS003 Heatsink (available separately)

1.2.4 Servo Driver Board

The servo circuit interprets the signals from the position detector, then uses positional error, speed and integral of current terms to output control voltages to drive the actuator to the demanded position.

The scanner uses a non-integrating, Class 0 servo, which enables higher system speeds compared to integrating servo systems, and is ideal for use in applications that require vector positioning (e.g. laser marking) or raster positioning (printing or scanning laser microscopy). It can also be used in some step and hold applications.

Furthermore, the proportional derivative circuit gives excellent dynamic performance and includes an additional current term to ensure stability at high accelerations. The diagram below shows the architecture of the driver in more detail.

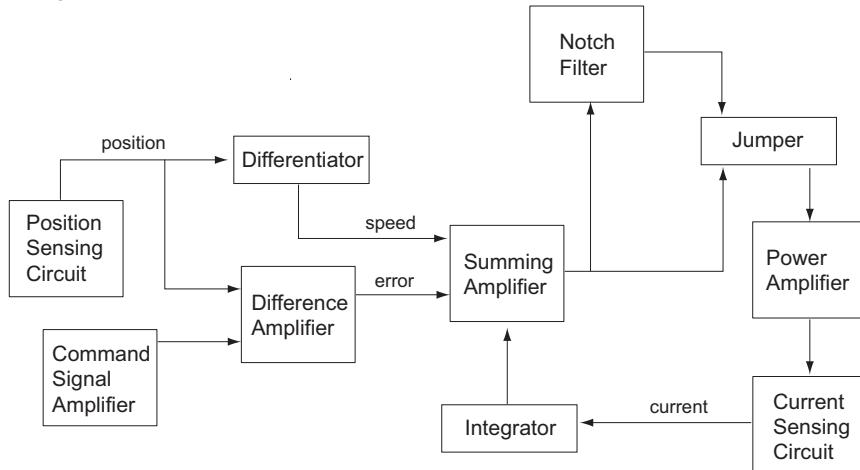


Fig. 1.4 Servo Driver Board Schematic Diagram



Fig. 1.5 Servo Driver Circuit Board

Chapter 2 Safety

2.1 Safety Information

For the continuing safety of the operators of this equipment, and the protection of the equipment itself, the operator should take note of the **Warnings**, **Cautions** and **Notes** throughout this handbook and, where visible, on the product itself.

The following safety symbols may be used throughout the handbook and on the equipment itself.



Warning: Risk of Electrical Shock

Given when there is a risk of injury from electrical shock.



Warning

Given when there is a risk of injury to users.



Caution

Given when there is a risk of damage to the product.



Note

Clarification of an instruction or additional information.

2.2 General Warnings



Warning

If this equipment is used in a manner not specified by the manufacturer, the protection provided by the equipment may be impaired. In particular, excessive moisture may impair operation.

Spillage of fluid, such as sample solutions, should be avoided. If spillage does occur, clean up immediately using absorbant tissue. Do not allow spilled fluid to enter the internal mechanism.



Caution

When connecting the driver boards and motors use only the cables supplied. Do not extend the cables. The driver boards and motors are calibrated with these cables. Using different cables will affect the performance of the system.



Caution

The driver circuit board is shipped calibrated and ready for use. The only adjustments necessary are setting the Volts/Degree Scaling factor (see Section 3.2.5. and if required, setting the device for external enabling see Section 4.2.

Do not attempt to make any other adjustments or remove/fit any other jumpers than those explicitly described in the following sections as this could invalidate the warranty.

Chapter 3 Installation & Initial Set Up

3.1 Mechanical Installation

3.1.1 Introduction

Caution



The Galvo units are set in the clamps at the factory for optimum performance. In particular, the 2-axis GVS012 is set for optimum orientation between the two galvo mirrors. Under normal circumstances the position of the units in the clamp should not be altered. If the need arises for the units to be repositioned, a hex key is provided to adjust the set screw. It should be noted that this set screw is M4, irrespective of whether the galvo units are imperial or metric (/M) versions.

The galvo motor assembly and associated driver board are tuned at the factory before they are shipped and further adjustment is not normally necessary. If the accuracy of the system is in doubt, e.g due to accidental adjustment of trim pots, contact Thorlabs for information on the tuning procedure.

During Installation, ensure that the motors are connected to the driver card to which they were tuned. Both the motor and the driver card should carry the same serial number. Use only the cables supplied.

The location of the serial number labels is shown below

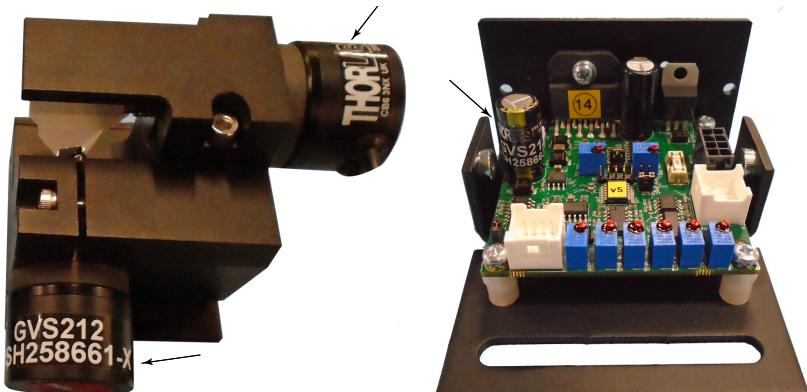


Fig. 3.1 Serial Number Label Location

It is essential that the user mounts heatsinks to the driver board and motor mounts which are suitable for their intended application. If this is not done the devices will overheat and permanent damage may occur. The choice of heatsink will primarily be determined by the power which the devices dissipate, a value which is dependant on the average speed at which the user moves the scanners. The larger the power the heatsink must dissipate the larger the heatsink will need to be.

3.1.2 Fitting The Heatsinks

Servo Driver Board Heatsink

The servo driver board is supplied complete with a large heatsink, suitable for all applications, even those involving more vigorous usage and rapidly changing drive waveforms.

- 1) Secure the heatsink bracket to the heat sink using two M3 x 8 screws and two plain M3 washers (arrowed in the photo below).



Fig. 3.2 Driver Board Heatsink Screws

Motor/Mirror Mount Heat Sink



Caution

Due to the large torque to weight ratio, thermal management is crucial to the successful operation of galvo motors. Consequently the galvo motors must be kept cool (recommended 15 to 35 °C).

For most applications, the mounting bracket will provide adequate heat sinking, however for more vigorous applications, it may be necessary to fit some heatsinking in addition to the galvo motor mount. Thorlabs supply a heatsink (GHS003) suitable for both single and dual axis applications.

If using a third party heatsink, please see Appendix C for details on how to calculate the power dissipation in the motor.

- 1) Note the orientation as shown below, then secure the heatsink to the motor/mirror mount using the two M3 x 5 screws supplied..

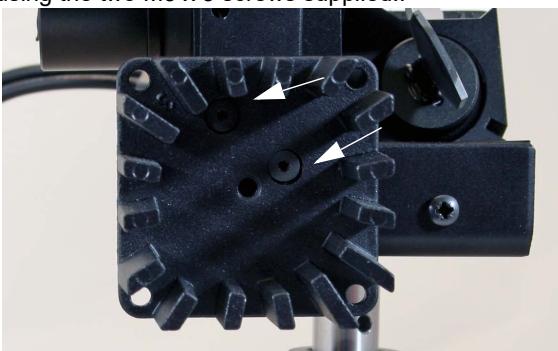
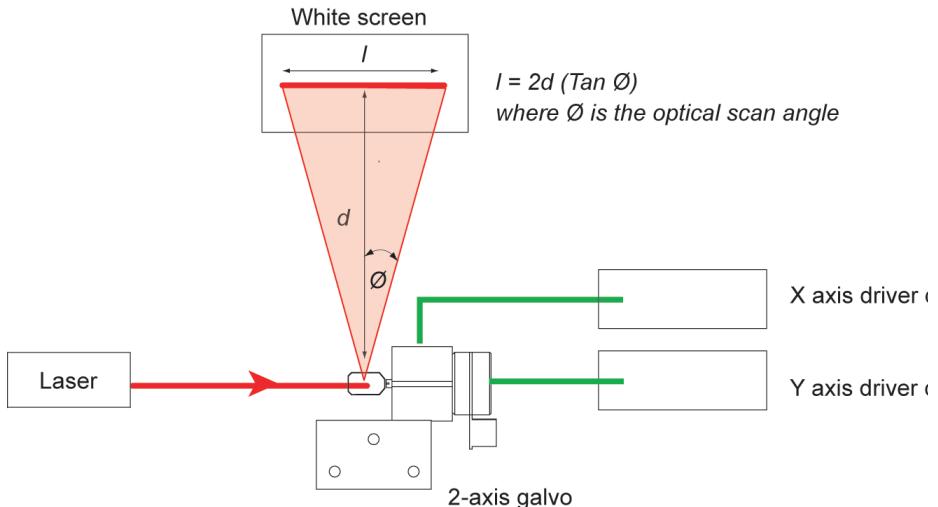


Fig. 3.3 XY Mount Heatsink Screws

3.1.3 Typical System Set Up

- 1) Fit a lens post into the bottom of the mounting bracket, then clamp the motor/mirror assembly to the breadboard.
- 2) Arrange a beam steering system such that a laser beam shines on to the X axis mirror, at right angles to the mount and is then reflected onto a screen, also at right angles to the mount.



Typical example: If the optical scan angle $\Ø = \pm 40^\circ$

$l = 2d \times \tan 40^\circ$ (Note. In this case, the mechanical scan angle is $\pm 20^\circ$)

Fig. 3.4 Typical Beam Steering System

3.2 Electrical Installation

3.2.1 Choosing A Power Supply

Thorlabs recommends using the GPS011 linear power supply to power the galvo controller board(s) as this power supply has been specifically designed for this purpose. The GPS011 can power up to two driver cards under any drive conditions and is supplied with all the cables required to connect to the driver cards.

However, customers also have the option of using a third-party power supply or incorporate the boards into their existing system. In this case care must be taken to ensure that the power supply voltage and current ratings are within the limits specified.

The drive electronics require a split rail DC supply in the range $\pm 15V$ to $\pm 18V$. The cards do not require an accurately regulated supply as the boards themselves have their own regulators. The maximum current drawn by the driver cards will not exceed 1.2 A rms on each rail. In addition to this, for optimum performance the supply should be able to provide peak currents of up to 5A on either rail.



Caution

Both switching and linear power supplies can be used with the Thorlabs galvo systems, however it is important to limit the inrush current when the power supply is turned on, in order to ensure that the power supply reservoir capacitors on the board are not damaged by the large surge currents that can occur on power-up. Most power supplies naturally “soft start” when they are switched on at the mains side and provide inrush current limiting. If, however, the power supply is turned on at the output (DC) side, it can output its peak current instantaneously. In this case it is important to limit this peak current to less than 2 Amps.

3.2.2 Using the GPS011 Linear Power Supply

The unit must be connected only to an earthed (grounded) mains power outlet.

Note

The unit is supplied with the input voltage and fuses configured to be compatible in the region to which it was shipped. No further adjustment should be necessary.

- 1) Connect the power cord to the socket on the rear panel of the unit - see Fig. 3.5.

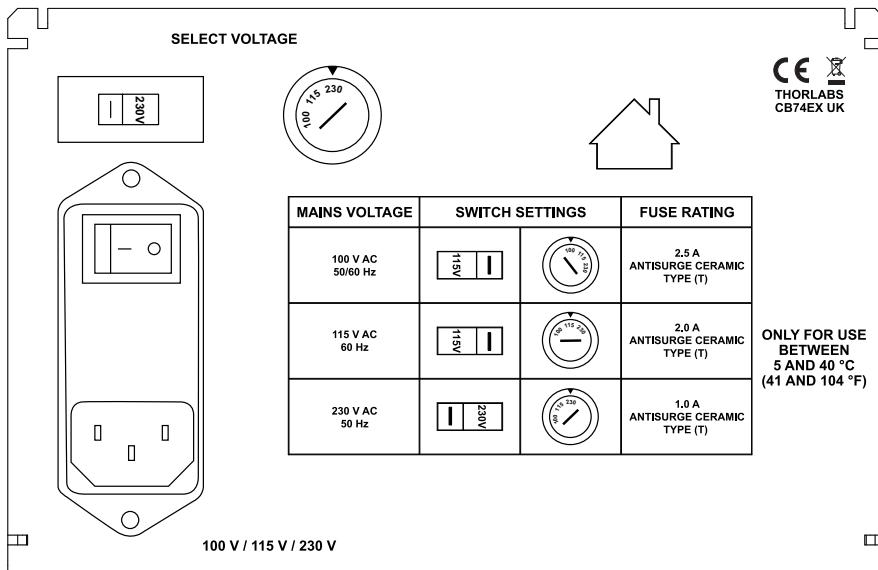


Fig. 3.5 Rear Panel

- 2) Ensure that the correct voltage range and fuse rating for your region is selected.

Caution

 Selecting the incorrect voltage range or fuse will damage the unit. Ensure that both switches are set to the correct position for your region and that the fuse fitted is of the correct rating, as indicated by the screen print on the rear panel.

- 3) Plug the power cord into the wall socket.

3.2.3 Electrical Connections

Caution

 During the electrical installation, cables should be routed such that power and signal cables are separated so that electrical noise pick up is minimized.



Caution

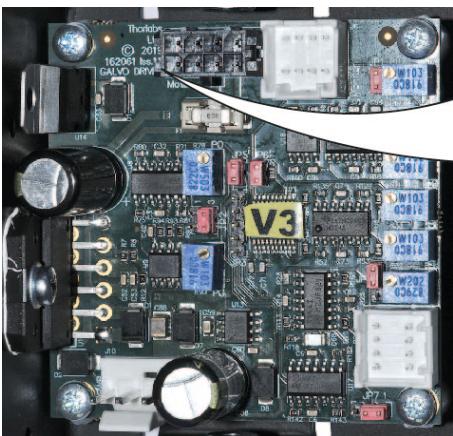
This section is applicable only to driver card units, with a PCB at rev 11 or later.
For details on connecting earlier units, please see Appendix B.

PCB revisions can be identified as follows:

Up to and including issue 10



Issue 11 onwards



Steps (1) to (3) are applicable only if using the Thorlabs GPS011 PSU.

- 1) Ensure the correct voltage range is selected on the PSU - see vc
- 2) The circular 3-pin connector on the power output cable and the OUTPUT socket on the PSU are fitted with alignment key ways to ensure connection in the correct

orientation. Check for correct orientation of the alignment key ways, then make connections as shown in Fig. 3.6.

- 3) Screw the outer casing of the plug clockwise until the connector is fully fastened.

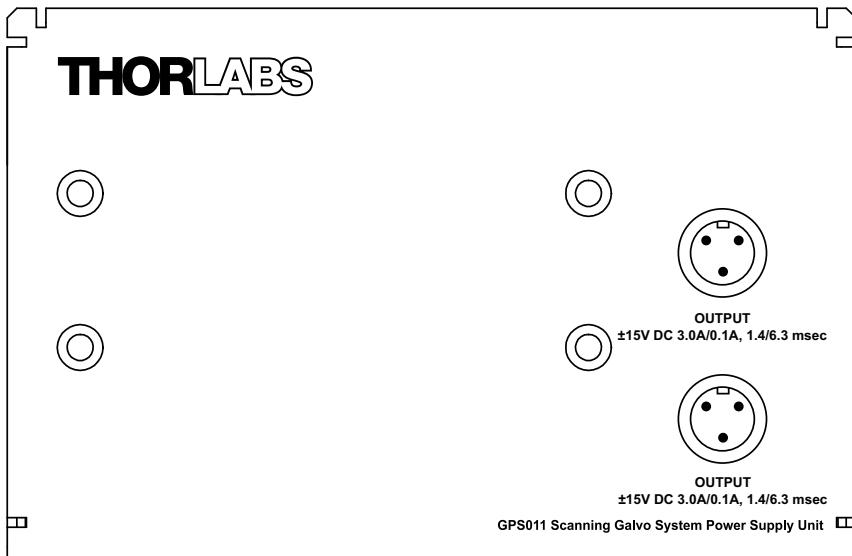


Fig. 3.6 Connecting the Power Cable to the PSU

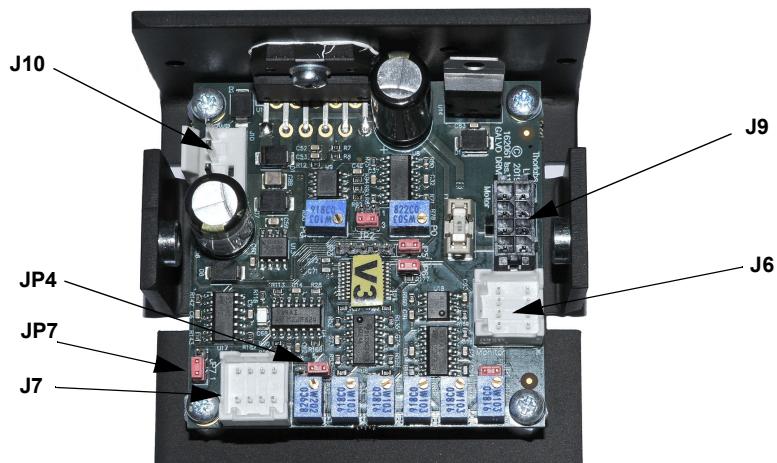


Fig. 3.7 Connector Identification

- 4) Identify connector J10 on each driver board, and make power connections as shown below. Thorlabs supply a suitable PSU (GPS011) for powering a single or dual axis system (see Section 3.2.1.). A bare cable, crimp connectors (Molex Pt No 2478) and housings for use with general lab PSUs is supplied with each driver board.

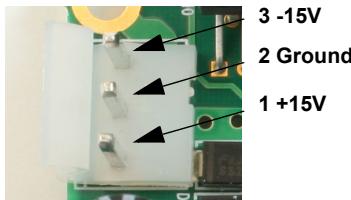


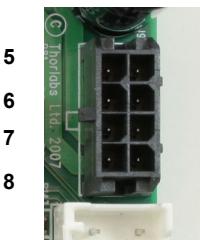
Fig. 3.8 J10 Power Connector Pin Identification

Caution



During items (5) and (6) use only the cables supplied. Do not extend the cables. The driver boards and motors are calibrated with these cables. Using different cables will affect the performance of the system. Longer cables are available as a custom part but the units will require re-calibration if these are not specified at time of order. Contact tech support for more details.

- 5) Connect a motor cable to the connector J9 on each driver board as shown below.



1	Pin 1 Position Sensor A Current
2	Pin 2 Position Sensor Ground
3	Pin 3 Position Sensor Cable Shield
4	Pin 4 Drive Cable Shield
5	Pin 5 Position Sensor B Current
6	Pin 6 Position Sensor Power
7	Pin 7 Motor + Coil
8	Pin 8 Motor -Coil

Fig. 3.9 J9 Motor Connector Pin Identification

- 6) Note the serial numbers then connect the galvo motors to their associated driver boards

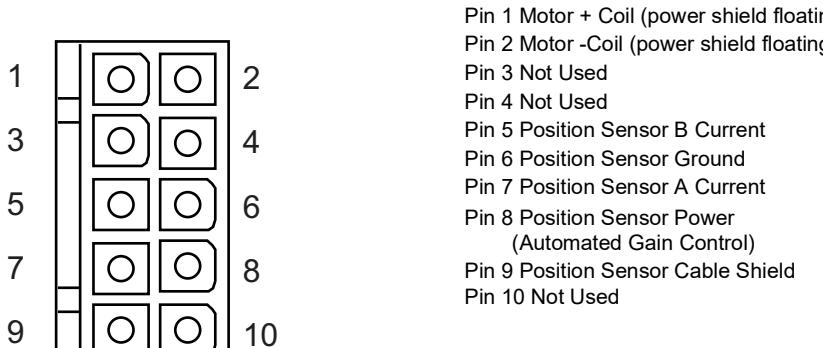


Fig. 3.10 Galvo Assembly Motor Connector Pin Identification

- 7) Connect a command input (e.g. function generator) to J7 of each driver board as shown in Fig. 3.11. J7 accepts Molex pins Pt No 56134-9100.

Note

The scanner accepts a differential analog command input. If the scaling is 0.8 Volt per degree mechanical movement (see Section 3.3.5.), -10 V to +10 V gives -12.5 to +12.5 degrees mechanical movement. The driver will attempt to set the mirror position to the command input value.

Pin 3 (DRV_OK) is an open collector output that is low when the board is operating normally and floating if a fault occurs. To use Pin 3 as a fault indicator, connect a pull-up resistor to give a high signal when the fault occurs. DRV_OK limits are 30 mA 30 V.

Do not connect a relay to this output.

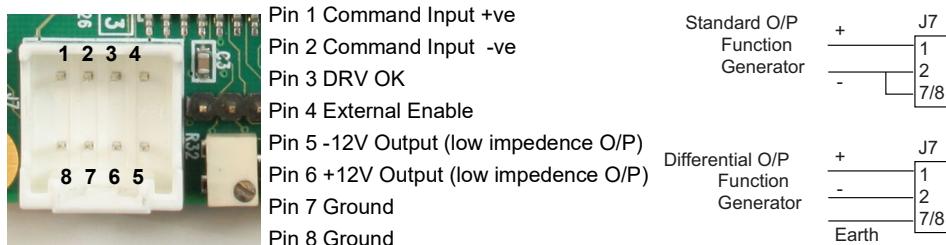
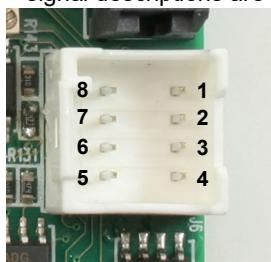


Fig. 3.11 J7 Command Input Connector Pin Identification

- 8) Using a suitable cable, connect the Diagnostic Terminal J6 to the diagnostic device (e.g. oscilloscope) in your application. Pin identification is given below, signal descriptions are detailed in the next section.



Pin 1 Scanner Position
Pin 2 Internal Command Signal
Pin 3 Positioning Error x 5
Pin 4 Motor Drive Current
Pin 5 Not Connected
Pin 6 Test Input (NC)
Pin 7 Motor + Coil Voltage / 2
Pin 8 Ground

Fig. 3.12 J6 Diagnostics Connector Pin Identification

Note

All diagnostic signals from J6 have 1 KW output impedance except Pin 7 (Motor Coil Voltage/2) which has 5 KW.

J6 Diagnostics and J7 Command Input Mating Connector Details

Mating Connector body: Manufacturer: Molex, Mfr. P/N: 513530800

Example Vendor: Farnell, Vendor P/N: 1120387

Crimps (22-26AWG): Manufacturer: Molex, Mfr. P/N: 56134-8100

Example Vendor: Farnell, Vendor P/N: 1120545

Crimps (22-28AWG): Manufacturer: Molex, Mfr. P/N: 56134-9100

Example Vendor: Farnell, Vendor P/N: 1120546

3.2.4 Diagnostic Signal Descriptions

Scanner Position - This signal is proportional to the position of the scanner mirror, with a scaling of 0.5 Volts per degree of mechanical movement.

Internal Command Signal - The command signal following amplification by the input stage. The scaling is 0.5 Volt per degree of mechanical movement.

Note

The Scanner Position and Internal Command signals are scaled internally by the driver circuit and are essentially equivalent to the input signal /2.

Positioning Error x 5 - This signal is proportional to the difference between the demanded and the actual positions - (Position - Command) x 5 (i.e. (Pin 1 - pin 2) x 5).

Motor Drive Current - The drive current of the motor (2V per A), i.e. if drive signal is 2V, the drive current is 1 A.

Motor + Coil Voltage /2 - This pin outputs the drive voltage to the "+" side of the motor coil. It is scaled down by a factor of 2. The drive voltage determines the current, which then determines the acceleration. It is not required if the user only wants to monitor position.

3.2.5 Setting the Volts/Degree Scaling Factor

The servo driver cards have a jumper which is used to set the Volts per Degree scaling factor. The cards are shipped with the scaling set to 0.5 V/ $^{\circ}$, where the max mechanical scan angle is nominally $\pm 20^{\circ}$ for the full ± 10 V input.

To set the scaling factor to 0.8 V/ $^{\circ}$ or 1.0 V/ $^{\circ}$, proceed as follows:

- 1) Identify JP7 as shown in Fig. 3.13.
- 2) Set the jumper position for the corresponding scaling factor as shown below.

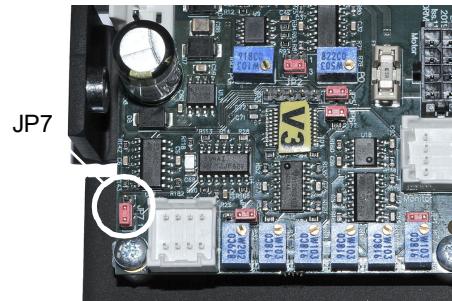
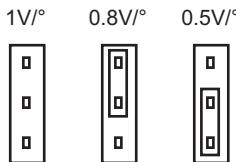


Fig. 3.13 Setting the Volts/Degree Scaling Factor

Chapter 4 Operation

4.1 General Operation

- 1) Connect the system as described in Section 3.2.
- 2) Apply power to the driver boards.
- 3) Input a command signal to each driver board to obtain the desired behaviour.

Note

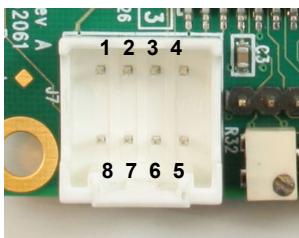
After powering the boards, there may be a delay of up to 10 seconds before the motors start to follow the command signal.

4.2 External Enabling of the driver board

- 1) The drive electronics can be configured for external enabling by placing a jumper across pins 2 and 3 of JP4.



- 2) Once this has been done the user can enable or disable the drive electronics by applying a 5V CMOS signal to J7 pin 4.



- Pin 1 Command Input +ve
Pin 2 Command Input -ve
Pin 3 No Connect
Pin 4 External Enable
Pin 5 -12V Output
Pin 6 +12V Output
Pin 7 Ground
Pin 8 Ground

Fig. 4.1 J7 Command Input Connector Pin Identification

If a logic high or no signal is applied the drive electronics will be enabled. If a logic low signal is applied then the driver will be disabled.

4.3 Using a DAQ Card

Typically, users will deploy a DAQ card with DAC analogue outputs in order to drive the servo drivers supplied with the galvos. The minimum recommended specifications for the DAC outputs are:-

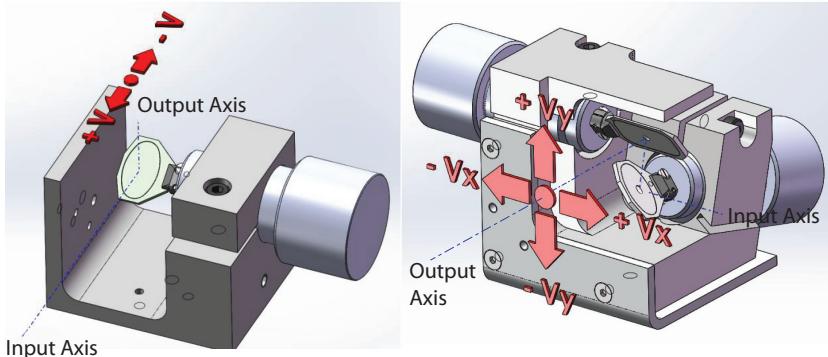
Dual bipolar **-10V to 10V DAC** analogue output channels (differential).

DAC clocking frequency higher than 20kS/s (Kilo Samples/Second), higher sampling frequencies like 100 kS/s are recommended (inputs have a 7 kHz low pass filter).

16 Bit DAC resolution and low out impedance (<= 50 Ω).

4.4 Recommended Scanning Angles

Although the maximum mechanical scan angle is stated as $\pm 20^\circ$ in Section 3.2.5, the maximum angle achievable without interference is dependent upon a number of conditions. Firstly, the larger the diameter of the input laser beam, the smaller the achievable scanning angle. Secondly, the applied input voltage causes the laser beam to move away from the center of the mirrors. The larger the input voltage then the greater the movement from the center, as shown below.



Lastly, on dual-axis systems, there is an offset alignment between the X and Y axis mirrors that also limits the scan angle.

The table below gives recommended scanning angles for various beam diameters.

GVS011, GVS111, GVS211, GVS311 and GVS411		
Input Beam Diameter	Mechanical Scan Angle	Optical Scan Angle
7 mm and less	$\pm 20^\circ$	$\pm 40^\circ$
8 mm	$+ 20^\circ, -16^\circ$	$+ 40^\circ, -32^\circ$
10 mm	$+ 20^\circ, -8^\circ$	$+ 40^\circ, -16^\circ$

GVS012, GVS112, GVS212, GVS312 and GVS412				
Input Beam Diameter	Mechanical Scan Angle X	Optical Scan Angle X	Mechanical Scan Angle Y	Optical Scan Angle Y
2 mm	$\pm 15.5^\circ$	$\pm 31^\circ$	$\pm 20^\circ$	$\pm 40^\circ$
4 mm	$\pm 13.5^\circ$	$\pm 27^\circ$	$\pm 20^\circ$	$\pm 40^\circ$
6 mm	$\pm 11.5^\circ$	$\pm 23^\circ$	$+ 20^\circ, - 17.5^\circ$	$+ 40^\circ, - 35^\circ$
8 mm	$\pm 10^\circ$	$\pm 20^\circ$	$\pm 15^\circ$	$\pm 30^\circ$
10 mm	$\pm 8.5^\circ$	$\pm 17^\circ$	$+ 5^\circ, - 13^\circ$	$+ 10^\circ, - 26^\circ$

Chapter 5 Troubleshooting

5.1 Common Problems

Some of the more common problems encountered when using galvanometers are details below.

Motor fails to respond to the command signal

This can occur for a number of reasons. The most likely are:

- 1) power is not correctly applied to the board
- 2) one of the cables is faulty or not connected properly
- 3) a fault has been triggered
- 4) the device has been disabled either by placing a jumper across JP4 pins 1 and 2 or by placing a jumper across JP4 pins 2 and 3 and pulling J7 pin 4 to ground.

Note

After powering the boards, there may be a delay of up to 10 seconds before the motors start to follow the command signal.

Instability of the scanner

If uncontrolled, instability of the scanner will cause a whistling or schreeching noise and uncontrolled movement of the scanner. It will also cause large current to be drawn by the motor and the motor will move spontaneously and unpredictably. If this occurs the user should turn off power to the driver boards immediately to prevent damage to the scanners.

However under normal circumstances the instability should be detected by the fault control circuitry. In this case the behaviour most likely to be observed by the user is the following: The mirror will suddenly jump from one position to another (probably with a short burst of whistling) and stop and remain still. After a delay of a few seconds the mirror will jump to another position and so on. Here when the mirror is stopped a fault has been triggered and the driver board is disabled. The only movement is during the brief period when the fault control circuitry tries to resume normal operation.

Instability can occur for a number of reasons. The most common is if the driver board is incorrectly tuned to the motor. This can occur if the board is connected to a different motor to the one it was originally sold with or if one of the potentiometers have been tampered with. Another common cause for instability is if the motor is driven at large amplitudes and high frequencies then the electronics may be unable to control the scanner.

Mirror periodically shoots off to one side and then stops

If the mirror suddenly shoot off to one side and then stops it is likely that either the position sensing circuitry is not functioning correctly or the motor cable is incorrectly wired. When this happens most likely either the drive electronics will output a constant drive voltage or the loop feedback will be positive. Consequently the motor jumps to one extreme and an overposition fault is triggered. Once the drive electronics is disabled the scanner will bounce freely backwards and come to rest. After a delay the electronics will attempt to resume operation and the process will repeat.

Galvo mostly behaves normally but periodically becomes unstable

If the galvo driver card is incorrectly tuned it is possible that the galvo system can appear to be behaving correctly most of the time, but with a brief period where the system suddenly becomes unstable repetitively occurring. This can be caused if the maximum error signal value is exceeded. The fault control circuitry responds by lowering the error gain which may cause the system to behave normally. However, once the system tries to resume normal operation the system is likely to become unstable again and the process will repeat.

Oscillation in the galvo motor current

If the galvo system is drawing more current than expected, if the scanners or the driver cards are overheating, if the scanners are making a hissing noise or if the position accuracy is less than expected, this may be due to oscillations in the galvo motor current. This can be identified by viewing the coil current signal J6 pin 4 on an oscilloscope. The problem will manifest itself as a high frequency ($>1\text{kHz}$) sinusoidal oscillation in the current, unrelated to the position signal. Normally the scanner will still appear to be correctly following the command signal, but the oscillation may show up in the position signal if the effect is very strong.

This effect is normally caused by crosstalk between the position sensing circuitry and the motor drive current. Repositioning the motor drive cable will normally help to avoid this problem. If the user replaces the motor cables with their own cables they should ensure that they keep the wires as short as possible and use separate shielded cables for the position sensing and motor drive signals.

Cross talk between axes

Cross talk between the two motors will normal show up as a slight movement in one axis when one motor is moved quickly. This typically occurs if both the motors are run off a same power supply and the power supply cannot deliver the peak currents demanded by the galvos. There will then be a drop in the power supply voltage which will then affect the behaviour of the remaining axis. Choosing a different power supply with sufficient peak drive current capability should solve this problem.

Overshoot in position signal which grows over time

It is possible that the position of the motor may show an overshoot when driven with a large square wave or similar, and that this overshoot will grow with time until a fault is triggered. There is usually a certain frequency and amplitude above which this starts to occur. This behaviour is caused by choosing a power supply which cannot deliver enough current for the intended application. The oscillation builds up because the power supply voltage is dropping on the rising edge of the position signal and effecting the board's behaviour. With every rising edge the effect becomes slightly greater as the overshoot grows.

5.2 Galvanometer Faults

The driver electronics monitor numerous signals to ensure the scanners operate safely and the fault protection circuitry will normally prevent any damage.

However, the user should be aware that the galvanometer may become permanently damaged if the system becomes unstable (manifested by a screeching noise, self excitation and unpredictable movement of the scanner). In addition the user should also be aware that the system has no protection against the galvanometer scanners overheating, and it is left to the user to ensure that they are fitted to an adequate heatsink (see Section 3.1.1.).

It is worth noting that a fault state may be triggered on applying power to the driver boards and the power amplifier will be disabled. However in this case the board will commence normal operation after a delay of a few seconds. The table below shows the various faults states which can be triggered in the fault control circuitry.

Table 5.1 Galvo System Faults and Associated Fault Protection Circuit Action

Fault	Possible Causes	Action Taken by Fault Control Circuit
Maximum scanner position exceeded	Drive signal too large, instability of scanner	Power amplifier turned off
Maximum peak current Exceeded	Incorrect tuning, instability of the scanner or overly vigorous drive waveforms	Power amplifier turned off
Maximum position error exceeded	Incorrect tuning, instability of the scanner or overly vigorous drive waveforms	Loop gain reduced
AGC voltage out of normal range	Broken motor position sensor, problem with motor cable connection	Power amplifier turned off
Power supply voltage drops below minimum value	Poor choice of power supply	Power amplifier turned off
Maximum RMS coil current exceeded	Incorrect tuning, instability of the scanner or overly vigorous drive waveforms	Power amplifier turned off
Maximum junction temperature of power amplifier IC exceeded	Inadequate heatsinking of driver board	Power amplifier turned off

Appendix A Specifications and Associated Parts

A.1 Specifications

Note. All specifications measured more than 60 secs after power up.

Parameter	Value
Mirror	
Maximum Beam Diameter	10 mm
Input/Output Beam Vertical Offset ^a	14.7 mm (0.58")
Finish	GVS01x: Protected Silver Coated GVS11x: Protected Gold Coated GVS21x: Broadband, E02 GVS31x: Dual Band Hi Power, K13 GVS41x: UV-Enhanced Aluminum
Damage Threshold	GVS01x: 3 J/cm ² at 1064 nm, 10 ns pulse GVS11x: 2 J/cm ² at 1064 nm, 10 ns pulse GVS21x: 0.25 J/cm ² at 532 nm, 10 ns pulse GVS31x: 5 J/cm ² at 1064 nm, 10 ns pulse GVS41x: 0.3 J/cm ² at 355 nm, 10 ns pulse
Wavelength Range	GVS01x: 500 nm to 2 µm GVS11x: 800 nm to 20 µm GVS21x: 400 nm to 750 nm GVS31x: 532 nm to 1064 nm GVS41x: 250 nm to 450 nm
Parallelism	< 3 arcmin
Surface Quality	40 to 20 Scratch/Dig
Front Surface Flatness (@633 nm)	λ
Clear Aperture	>90% of Dimension

Notes

- a. The input and output beams are offset by 90°.

The way our mirrors are tested is continually updated, please consult www.thorlabs.com for more information.

Parameter	Value
Motor & Position Sensor	
Linearity(50% Full Travel)	99.9%
Scale Drift ^b	<200 PPM/°C(Max)
Zero Drift ^b	<20 µRad/°C(Max)
Repeatability	15 µRad
Resolution With GPS011 Linear PSU With standard switch mode PSU	0.00086 ° (15 µRad) 0.004° (70 µRad)
Average Current	1 A
Peak Current	10 A
Load Mirror Aperture	10 mm
Maximum Scan Angle (Mechanical Angle)	±20° (with 0.5V/° scaling factor)
Motor Weight (inc cables, excl bracket)	94 g
Recommended Operating Temperature Range	15 to 35° C
Position Sensor Output Range	40 to 80 µA
Motor Cable Length	30 cm (11.81")

Notes

^b Measured after leaving the unit powered up for at least 8 hours (max drift is <0.8 mrad in 8hrs upon power on)

Parameter	Value
Drive Electronics	
Full Travel Bandwidth ^c	25Hz Square wave, 35 Hz Sinewave
Bandwidth (50% Full Travel) ^d	65Hz Square wave, 130 Hz Sinewave
Small Angle ($\pm 0.2^\circ$) Bandwidth ^d	1kHz
Small Angle Step Response ^e	400 μ s
Power Supply	+/-15V to +/-18V dc (1.25 A rms, 10A peak MAX)
Analog Signal Input Resistance	20k Ω \pm 1% (Differential Input)
Position Signal Output Resistance	1K \pm 1%
Analog Position Signal Input Range	$\pm 10V$
Mechanical Position Signal Input Scale Factor	switchable 0.5V/ $^\circ$, 0.8V/ $^\circ$ or 1.0V/ $^\circ$
Mechanical Position Signal Output Scale Factor	0.5V/ $^\circ$
Operating Temperature Range	15 to 35 $^\circ$ C
Servo Board Size (L x W x H)	85 mm x 74 mm x 44 mm (3.35" x 2.9" x 1.73")

Notes

c The unit can operate beyond these limits with reduced performance until protections trigger (250 Hz <10 sec). For a safe operation stay below 50 Hz 20Vpp sinewave

d Using heat sink to keep temp <35°C (see Section 3.1.2.).

e The settling time for the mirror to stop moving once the drive signal is removed.

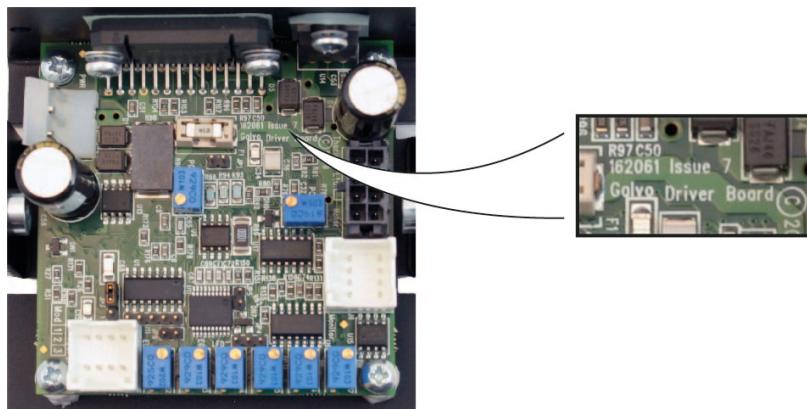
Appendix B Connecting Legacy Driver Units

Caution

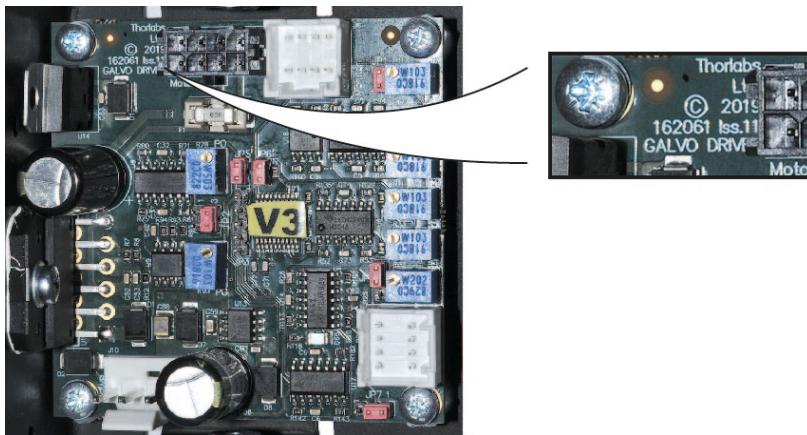
This section is applicable only to driver card units, with a PCB earlier than rev 11. For details on connecting later units, please see Section 3.3.3.

PCB revisions can be identified as follows:

Up to and including issue 10



Issue 11 onwards



B.1 Electrical Connections

Caution

During the electrical installation, cables should be routed such that power and signal cables are separated so that electrical noise pick up is minimized

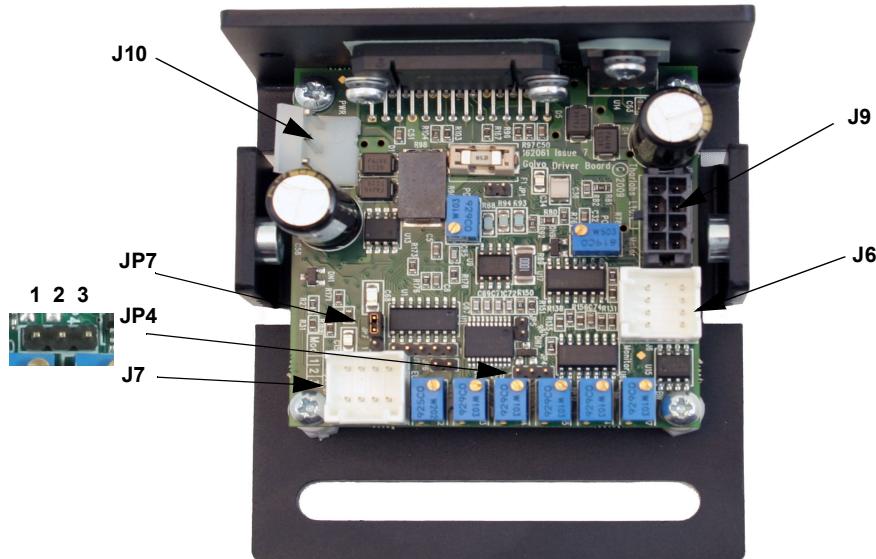


Fig. B.1 Connector Identification

- 1) Identify connector J10 (see Fig. B.2) on each driver board, and make power connections as shown below. Thorlabs supply a suitable PSU (GPS011) for powering a single or dual axis system (see Section 3.2.1.). A bare cable, crimp connectors (Molex Pt No 2478) and housings for use with general lab PSUs is supplied with each driver board.

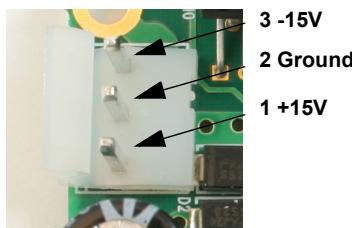
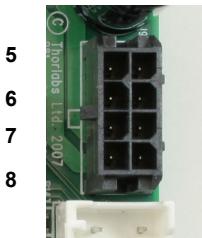


Fig. B.2 J10 Power Connector Pin Identification

**Caution**

During item (2) use only the cables supplied. Do not extend the cables. The driver boards and motors are calibrated with these cables. Using different cables will affect the performance of the system. Longer cables are available as a custom part but the units will require re-calibration if these are not specified at time of order. Contact tech support for more details.

- 2) Note the serial numbers of the galvo motors and driver boards, then connect the motors to their associated driver boards. (see Section 3.1.1.).



1	Pin 1 Position Sensor A Current
2	Pin 2 Position Sensor Ground
3	Pin 3 Position Sensor Cable Shield
4	Pin 4 Drive Cable Shield
5	Pin 5 Position Sensor B Current
6	Pin 6 Position Sensor Power
7	Pin 7 Motor + Coil
8	Pin 8 Motor -Coil

Fig. B.3 J9 Motor Connector Pin Identification.

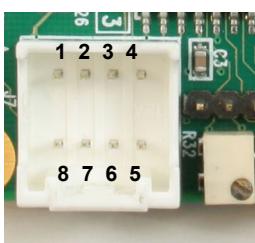
- 3) Connect a command input (e.g. function generator) to J7 of each driver board as shown below. J7 accepts Molex pins Pt No 56134-9100.

Note

The scanner accepts a differential analog command input. If the scaling is 0.5 Volt per degree mechanical movement (see Section 3.2.5.), -10 V to +10 V gives -20 to +20 degrees mechanical movement. The driver will attempt to set the mirror position to the command input value.

Pin 3 (DRV_OK) is an open collector output that is low when the board is operating normally and floating if a fault occurs. To use Pin 3 as a fault indicator, connect a pull-up resistor to give a high signal when the fault occurs. DRV_OK limits are 30 mA 30 V.

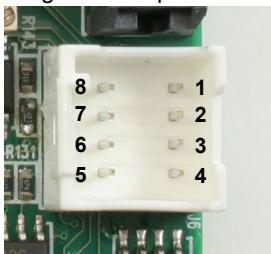
Do not connect a relay to this output.



Pin 1 Command Input +ve	Standard O/P Function Generator	+	J7
Pin 2 Command Input -ve		-	2
Pin 3 DRV OK			1
Pin 4 External Enable			7/8
Pin 5 -12V Output (low impedance O/P)	Differential O/P Function Generator	+/-	J7
Pin 6 +12V Output (low impedance O/P)			1
Pin 7 Ground			2
Pin 8 Ground			7/8

Fig. B.4 J7 Command Input Connector Pin Identification

- 4) Using a suitable cable, connect the Diagnostic Terminal J6 to the diagnostic device (e.g. oscilloscope) in your application. Pin identification is given below, signal descriptions are detailed in the next section.



- Pin 1 Scanner Position
Pin 2 Internal Command Signal
Pin 3 Positioning Error x 5
Pin 4 Motor Drive Current
Pin 5 Not Connected
Pin 6 Test Input (NC)
Pin 7 Motor + Coil Voltage / 2
Pin 8 Ground

Fig. B.5 J6 Diagnostics Connector Pin Identification

Note

All diagnostic signals from J6 have $1\text{ k}\Omega$ output impedance except Pin 7 (Motor Coil Voltage/2) which has $5\text{ k}\Omega$

J6 Diagnostics and J7 Command Input Mating Connector Details

Mating Connector body: Manufacturer: Molex, Mfr. P/N: 513530800

Example Vendor: Farnell, Vendor P/N: 1120387

Crimps (22-26AWG): Manufacturer: Molex, Mfr. P/N: 56134-8100

Example Vendor: Farnell, Vendor P/N: 1120545

Crimps (22-28AWG): Manufacturer: Molex, Mfr. P/N: 56134-9100

Example Vendor: Farnell, Vendor P/N: 1120546

2.1.1 Diagnostic Signal Descriptions

Scanner Position - This signal is proportional to the position of the scanner mirror, with a scaling of 0.5 Volts per degree of mechanical movement.

Internal Command Signal - The command signal following amplification by the input stage. The scaling is 0.5 Volt per degree of mechanical movement.

Note

The Scanner Position and Internal Command signals are scaled internally by the driver circuit and are essentially equivalent to the input signal /2.

Positioning Error x 5 - This signal is proportional to the difference between the demanded and the actual positions - (Position - Command) x 5 (i.e. (Pin 1 - pin 2) x 5).

Motor Drive Current - The drive current of the motor (2V per A), i.e. if drive signal is 2V, the drive current is 1 A.

Motor + Coil Voltage / 2 - This pin outputs the drive voltage to the "+" side of the motor coil. It is scaled down by a factor of 2. The drive voltage determines the current, which then determines the acceleration. It is not required if the user only wants to monitor position.

2.1.2 Setting the Volts/Degree Scaling Factor

The servo driver cards have a jumper which is used to set the Volts per Degree scaling factor. The cards are shipped with the scaling set to 0.5 V° , where the max mechanical scan angle is nominally $\pm 20^{\circ}$ for the full $\pm 10 \text{ V}$ input.

To set the scaling factor to 0.8 V° or 1.0 V° , proceed as follows:

- 1) Identify JP7 as shown in Fig. 3.13.
- 2) Set the jumper position for the corresponding scaling factor as shown below.

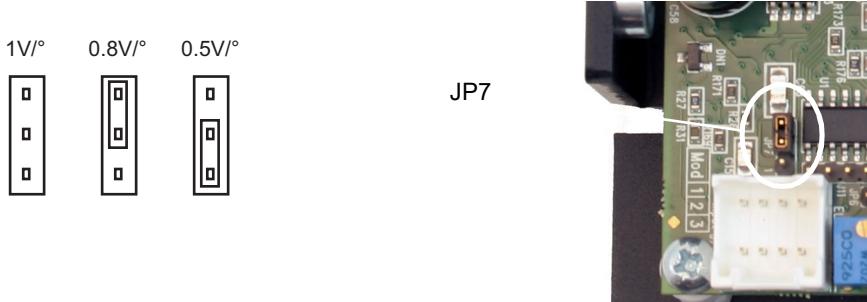


Fig. B.6 Setting the Volts/Degree Scaling Factor

Appendix C Calculating the Power Dissipation

3.1 Motor Heatsink

The power dissipated in the motor can be estimated by measuring the RMS current drawn from the PSU and then using the following equation:

$$P_{\text{mot}} = R_{\text{mot}} \times [(I_{\text{rms+}} + I_{\text{rms-}} - I_{q+} - I_{q-}) / 2]^2$$

Where P_{mot} is the power dissipated in the motor, R_{mot} is the motor coil resistance (2.2Ω), $I_{\text{rms+}}$ is the rms current drawn from the positive supply rail, $I_{\text{rms-}}$ is the rms current drawn from the negative supply rail, I_{q+} is the quiescent current drawn on the +ve rail (0.15A under all circumstances) and I_{q-} is the quiescent current drawn on the -ve rail (0.10A under all circumstances).

The power dissipated in the driver boards can then be calculated using the following equation:

$$P_{\text{drv}} = (V_+ \times I_{\text{rms+}}) + (V_- \times I_{\text{rms-}}) - P_{\text{mot}}$$

Where P_{drv} is the power dissipated in the driver boards, V_+ is positive supply voltage and V_- is the negative supply voltage.

3.1.1 Calculating the Required Thermal Conductivity

The ability of a heatsink to transfer heat to its surroundings is parameterised either by its thermal conductivity, k or its thermal resistance, \emptyset . The lower the thermal resistance the more effectively the heatsink can transfer heat. The required thermal resistance can be calculated from the following equation:

$$\emptyset = 1/k = (T_{\text{hs}} - T_a) / P_{\text{max}}$$

In the above equation T_{hs} is the maximum permissible heatsink temperature, T_a is the ambient temperature and P_{max} is the maximum power the device being cooled will dissipate. For the motors it is desireable to keep T_{hs} below 45°C .

The following equation can be used to calculate T_{hs} for the driver IC:

$$T_{\text{hs}} = T_j - P_{\text{max}} \times \emptyset_{jhs}$$

Here, \emptyset_{jhs} is the thermal resistance between the semiconductor junction of the power amplifier IC and the heatsink. T_j is the maximum temperature allowable at the junction, about 150°C (although the lifetime of the driver IC will be longer if the junction is kept at a lower temperature). The value of \emptyset_{jhs} is $1.3 \text{ }^\circ\text{C/W}$.

Appendix D Reasons For Image Distortion

The deflection of a laser beam with a two-mirror system results in three effects:

- (1) The arrangement of the mirrors leads to a certain distortion of the image field – see Fig. D.1 below.

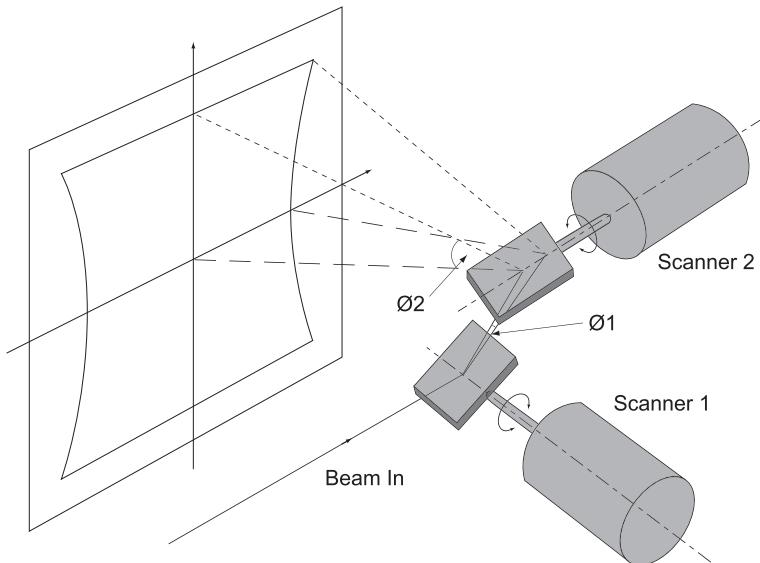


Fig. D.1 Field Distortion in a Two-way Mirror Deflection System

This distortion arises from the fact that the distance between mirror 1 and the image field depends on the size of the mechanical scan angles of mirror 1 and mirror 2. A larger scan angle leads to a longer distance.

- (2) The distance in the image field is not proportional to the scan angle itself, but to the tangent of the scan angle. Therefore, the marking speed of the laser focus in the image field is not proportional to the angular velocity of the corresponding scanner.
- (3) If an ordinary lens is used for focusing the laser beam, the focus lies on a sphere. In a flat image field, a varying spot size results.

As a result, you will find the scanning field turn out to be a "pillow-shaped" image, see Fig. D.2 below.

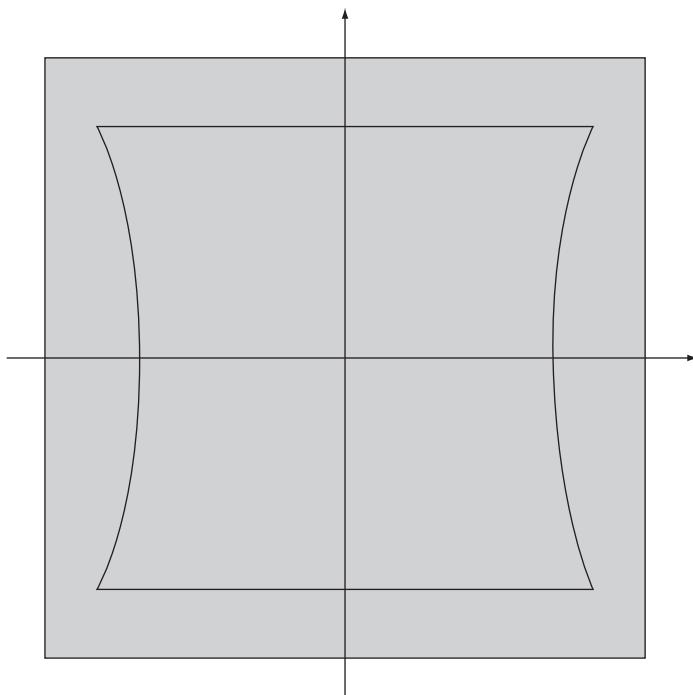


Fig. D.2 Pillow-shaped Field Distortion Caused by the Arrangement of Mirrors

Appendix E Regulatory

E.1 Declarations Of Conformity

E.1.1 For Customers in Europe

See Section E.2.

E.1.2 For Customers In The USA

This equipment has been tested and found to comply with the limits for a Class A digital device, pursuant to part 15 of the FCC rules. These limits are designed to provide reasonable protection against harmful interference when the equipment is operated in a commercial environment. This equipment generates, uses and can radiate radio frequency energy and, if not installed and used in accordance with the instruction manual, may cause harmful interference to radio communications. Operation of this equipment in a residential area is likely to cause harmful interference in which case the user will be required to correct the interference at his own expense.

Changes or modifications not expressly approved by the company could void the user's authority to operate the equipment.

E.2 CE Certificates



THORLABS

www.thorlabs.com

EU Declaration of Conformity

in accordance with EN ISO 17050-1:2010

We: Thorlabs Ltd.

Of: 1 St. Thomas Place, Ely, CB7 4EX, United Kingdom

in accordance with the following Directive(s):

2006/42/EC Machinery Directive (MD)

2014/30/EU Electromagnetic Compatibility (EMC) Directive

2011/65/EU Restriction of Use of Certain Hazardous Substances (RoHS)

hereby declare that:

Model: **GVS X1X Series**

Equipment: 1D or 2D 10mm Beam Galvo System (Imperial or Metric) - Various Mirrors

is in conformity with the applicable requirements of the following documents:

EN ISO 12100	Safety of Machinery. General Principles for Design. Risk Assessment and Risk Reduction	2010
EN 61326-1	Electrical Equipment for Measurement, Control and Laboratory Use - EMC Requirements	2013

and which, issued under the sole responsibility of Thorlabs, is in conformity with Directive 2011/65/EU of the European Parliament and of the Council of 8th June 2011 on the restriction of the use of certain hazardous substances in electrical and electronic equipment, for the reason stated below:

does not contain substances in excess of the maximum concentration values tolerated by weight in homogenous materials as listed in Annex II of the Directive

I hereby declare that the equipment named has been designed to comply with the relevant sections of the above referenced specifications, and complies with all applicable Essential Requirements of the Directives.

Signed:

On: 20 December 2013

Name: Keith Dhese

Position: General Manager

EDC - GVS X1X Series -2013-12-20



Appendix F Thorlabs Worldwide Contacts

For technical support or sales inquiries, please visit us at www.thorlabs.com/contact for our most up-to-date contact information.



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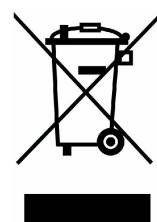
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Thorlabs verifies our compliance with the WEEE (Waste Electrical and Electronic Equipment) directive of the European Community and the corresponding national laws. Accordingly, all end users in the EC may return "end of life" Annex I category electrical and electronic equipment sold after August 13, 2005 to Thorlabs, without incurring disposal charges. Eligible units are marked with the crossed out "wheelie bin" logo (see right), were sold to and are currently owned by a company or institute within the EC, and are not disassembled or contaminated. Contact Thorlabs for more information. Waste treatment is your own responsibility. "End of life" units must be returned to Thorlabs or handed to a company specializing in waste recovery. Do not dispose of the unit in a litter bin or at a public waste disposal site.



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