

## **2x60A High Performance Dual Channel Forward/Reverse Brushed DC Motor Controller with USB and Encoder Inputs**



Roboteq's MDC2250 controller is designed to convert commands received from an RC radio, Analog Joystick, wireless modem, PC (via RS232 or USB) or microcomputer into high voltage and high current output for driving one or two DC motors. Designed for maximal ease-of-use, it is delivered with all necessary cables and hardware, and is ready to use in minutes.

The controller features a high-performance 32-bit microcomputer and quadrature encoder inputs to perform advanced motion control algorithms in Open Loop or Close Loop (Speed or Position) modes. The MDC2250 features several Analog, Pulse and Digital I/Os which can be remapped as command or feedback inputs, limit switches, or many other functions.

The controller's two motor channels can either be operated independently or mixed to set the direction and rotation of a vehicle by coordinating the motion of each motor.

Numerous safety features are incorporated into the controller to ensure reliable and safe operation. The controller's operation can be extensively automated and customized using Basic Language scripts. The controller can be reprogrammed in the field with the latest features by downloading new operating software from Roboteq.

### **Applications**

- Industrial Automation
- Tracking, Pan & Tilt systems
- Terrestrial and Underwater Robotic Vehicles
- Automatic Guided Vehicles
- Police and Military Robots
- Flight simulators
- Telepresence Systems
- Animatronics

### **Features List**

- USB, RS232, 0-5V Analog, or Pulse (RC radio) command modes
- Auto switch between USB, RS232, Analog, or Pulse based on user-defined priority
- Built-in high-power power drivers for two brushed DC motors at up to 60A output per channel
- Full forward & reverse control on each channel. Four quadrant operation. Supports regeneration
- Operates from a single 10V-50V power source
- Programmable current limit for each channel up to 2x60A for protecting controller, motors, wiring and battery
- Up to 4 Analog Inputs for use as command and/or feedback
- Up to 5 Pulse Length, Duty Cycle or Frequency Inputs for use as command and/or feedback
- Up to 6 Digital Inputs for use as Deadman Switch, Limit Switch, Emergency stop or user inputs
- Dual Quadrature Encoder inputs with 32-bit counters
- 2 general purpose 24V, 1A output for brake release or accessories
- Selectable min, max, center and deadband in Pulse and Analog modes
- Selectable exponentiation factors for each command inputs
- Trigger action if Analog, Pulse or Encoder capture are outside user selectable range (soft limit switches)
- Open loop or closed loop speed control operation
- Closed loop position control with analog or pulse/frequency feedback
- Precise speed and position control when Encoder feedback is used
- PID control loop with separate gains for each channel

- Multi-range PID gains changing on-the-fly according to motor speed
- Optional Mixed control (sum and difference) for tank-like steering
- Configurable Data Logging of operating parameters on RS232 Output for telemetry or analysis
- Built-in Battery Voltage and Temperature sensors
- Optional 12V backup power input for powering safely the controller if the main motor batteries are discharged
- Power Control wire for turning On or Off the controller from external microcomputer or switch
- No consumption by output stage when motors stopped
- Regulated 5V output for powering Encoders, RC radio, RF Modem or microcomputer
- Separate Programmable acceleration and deceleration for each motor
- Separate Programmable maximum forward and reverse power
- Ultra-efficient 3 mOhm High-Efficiency version ON resistance MOSFETs
- Orderable as single channel version up to 120A
- Stall detection and selectable triggered action if Amps is outside user-selected range
- Short circuit protection with selectable sensitivity levels
- 10 to 32kHz user programmable Pulse Width Modulation (PWM) output.
- Overvoltage and Undervoltage protection
- Programmable Watchdog for automatic motor shutdown in case of command loss
- Overtemperature protection
- Diagnostic LED
- Open frame design with heat conducting bottom plate
- Efficient heat sinking. Operates without a fan in most applications
- Power wiring 0.25" Faston tabs
- 5.5" (139.7mm) L, 5.5" W (139.7mm), 1.0" (25mm) H
- -40o to +85o C operating environment
- 0.5 lbs (250g)
- Easy configuration, tuning and monitory using provided PC utility
- Field upgradeable software for installing latest features via the internet

## Orderable Product References

TABLE 1.

Reference	Number of Channels	Amps/Channel	Volts	Cooling
<b>MDC2250</b>	2	60	50V	Conduction Plate
<b>MDC2250S</b>	1	240	50V	Conduction Plate

## Power Wires Identifications and Connection

The diagram below shows how to wire the controller and how to turn power On and Off.

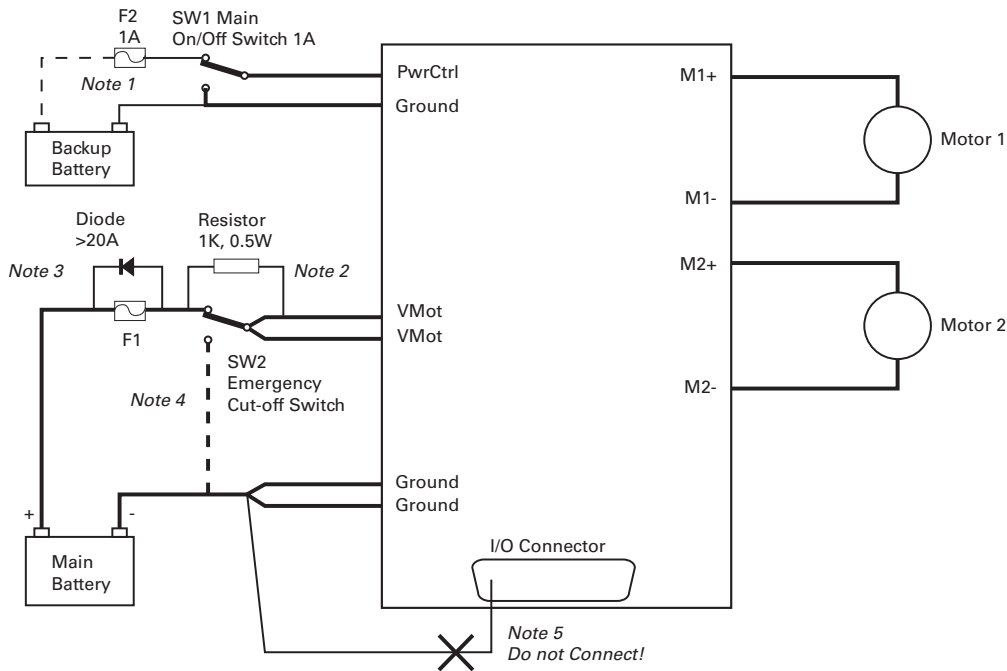


FIGURE 8. Powering the controller. Thick lines identify **MANDATORY** connections

## Important Warning

**Carefully follow the wiring Instructions provided in the Read Me First sheet that comes with the controller, or in the Power Connection section of the User Manual. The information on this datasheet is only a summary.**

### Mandatory Connections

It is imperative that the controller is connected as shown in the above diagram in order to ensure a safe and trouble-free operation. All connections shown as thick black lines are mandatory. The controller must be powered On/ Off using switch SW1 on the Power Control Header. Use a suitable high-current fuse F1 as a safety measure to prevent damage to the wiring in case of major controller malfunction.

The battery must be connected in permanence to the controller's VMot power via an input emergency switch SW2 as additional safety measure.

### Precautions and Optional Connections

Note1: Backup battery to ensure motor operation with weak or discharged batteries, connect a second battery to the Power Control wire/terminal via the SW1 switch.

Note2: Use precharge 1K, 0.5W Resistor to prevent switch arcing.

Note3: Insert a high-current diode to ensure a return path to the battery during regeneration in case the fuse is blown.

Note4: Optionally ground the VMot tabs when the controller is Off if there is any concern that the motors could be made to spin and generate voltage in excess of 50V.

Note5: Beware not to create a path from the ground pins on the I/O connector and the battery minus terminal.

## Single Channel Wiring

The single channel version of the controller (MDC2250S) requires that the output be parallel and that the load be wired as shown in the diagram below.

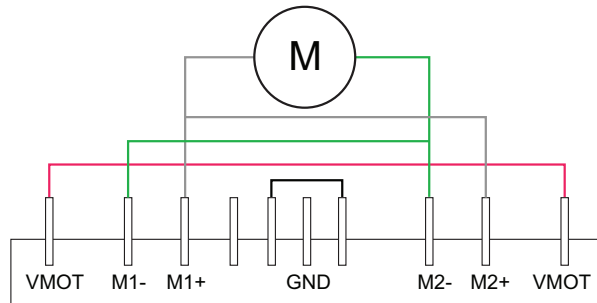


FIGURE 9. MDC2250S wiring diagram

## Important Warning

This wiring is only possible on controllers fitted with the Single Channel version of the controller logic. Dual channel controllers will be damaged if wired as single channel. Verify that the PC utility identifies the controller as MDC2250S before applying power to the load.

## Encoder Wiring

The encoder connector is a 6-pin Molex Microfit 3.0, model 43645. Pin assignment is in the table below.

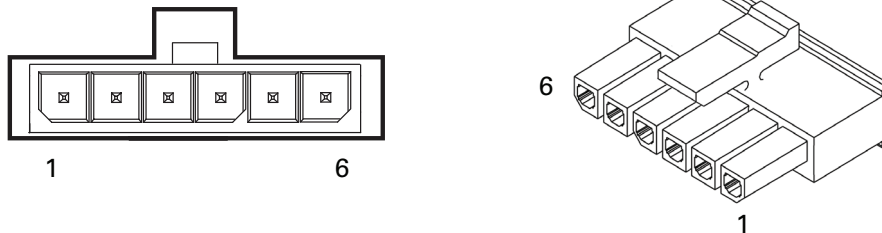


FIGURE 10. Encoder connector

TABLE 4.

Pin Number	1	2	3	4	5	6
Signal	5Vout	Enc1A	Enc1B	Enc2A	Enc2B	GND

## Commands and I/O Connections

Connection to RC Radio, Microcomputer, Joystick and other low current sensors and actuators is done via the 15 connector located in front of the board. The functions of many pins vary depending on user configuration. Pin assignment is found in the table below.

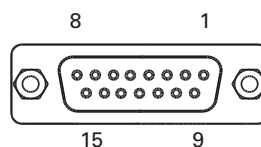


FIGURE 11. Connector pin locations

TABLE 5.

Connector Pin	Power	Dout	Com	RC	Ana	Dinput	Default Config
1		DOUT1					Unused
9		DOUT2					Unused
2			TxOut				RS232Tx
10				RC5	ANA1	DIN5	AnaCmd1
3			RxIn				RS232Rx
11				RC4	ANA4	DIN4	AnaCmd2
4				RC1		DIN1	RCRadio1
12				RC3	ANA3	DIN3	Unused
5	GND						
13	GND						
6			SCL1				Reserved
14	5VOut						
7			SDAI				Reserved
15						DIN6	Unused
8				RC2	ANA2	DIN2	RCRadio2

### Default I/O Configuration

The controller can be configured so that practically any Digital, Analog and RC pin can be used for any purpose. The controller's factory default configuration provides an assignment that is suitable for most applications. The figure below shows how to wire the controller to two analog potentiometers, an RC radio, and the RS232 port. It also shows how to connect the two outputs to motor brake solenoids. You may omit any connection that is not required in your application. The controller automatically arbitrates the command priorities depending on the presence of a valid command signal in the following order: 1-RS232, 2-RC Pulse, 3-Analog. If needed, use the Robo-run+ PC Utility to change the pin assignments and the command priority order.

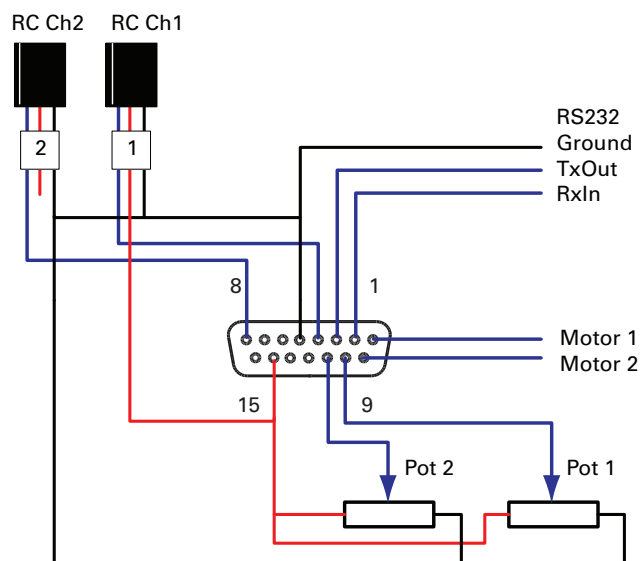


FIGURE 12. Factory default pins assignment



**Power Stage Electrical Specifications (at 25oC ambient)**

TABLE 7.

Parameter	Measure point	Models	Min	Typ	Max	Units
Battery Leads Voltage	Ground to VBat	All	0 (1)		55	Volts
Motor Leads Voltage	Ground to M1+, M1-, M2+, M2-	All	0 (1)		55 (2)	Volts
Power Control Voltage	Ground to Power Control wire	All	0 (1)		65	Volts
Minimum Operating Voltage	VBat or Pwr Ctrl wires	All	9 (3)			Volts
Over Voltage protection range	Ground to VBat	All	5	50 (4)	55	Volts
Under Voltage protection range	Ground to VBat	All	0	5 (4)	55	Volts
Idle Current Consumption	VBat or Pwr Ctrl wires	All	50	100 (5)	150	mA
ON Resistance	VBat to M+, plus M- to Ground at 100% power. Per channel	All		6		mOhm
Max Current per channel for 30s	Motor current	MDC2250			60	Amps
		MDC2250S			120 (6)	Amps
Continuous Max Current per channel	Motor current	MDC2250			50 (6)(7)	Amps
		MDC2250S			100 (6)(7)	Amps
Current Limit range	Ch1 or Ch2 Motor current	MDC2250	10	50(8)	60	Amps
		MDC2250S	10	100 (8)	120 (6)	Amps
Stall Detection Amps range	Ch1 or Ch2 Motor current	MDC2250	10	60(8)	60	Amps
		MDC2250S	10	120 (8)	120 (6)	Amps
Stall Detection timeout range	Ch1 or Ch2 Motor current	All	1	65000 (9)	65000	milliseconds
Short Circuit Detection threshold (10)	Between Motor wires or Between Motor wire and Ground	MDC2250	140 (11)		400 (11)	Amps
		MDC2250S	280		800	Amps
Short Circuit Detection threshold	Between Motor wires and VBat	All	No Protection. Permanent damage will result			
Motor Acceleration/Deceleration range	Ch1 or Ch2	All	100	500 (12)	65000	milliseconds

- Note 1: Negative voltage will cause a large surge current. Protection fuse needed if battery polarity inversion is possible
- Note 2: Maximum regeneration voltage in normal operation. Never inject a DC voltage from a battery or other fixed source
- Note 3: Minimum voltage must be present on VBat or Power Control wire
- Note 4: Factory default value. Adjustable in 0.1V increments
- Note 5: Current consumption is lower when higher voltage is applied to the controller's VBat or PwrCtrl wires
- Note 6: Current is sum of both synchronized channels. Current must be balanced between channel to obtain max current.
- Note 7: Estimate. Limited by case temperature. Current may be higher with better cooling
- Note 8: Factory default value. Adjustable in 0.5A increments
- Note 9: Factory default value. Time in ms that Stall current must be exceeded for detection
- Note 10: Controller will stop until restarted in case of short circuit detection
- Note 11: Sensitivity selectable by software
- Note 12: Factory default value. Time in ms for power to go from 0 to 100%

## Command, I/O and Sensor Signals Specifications

TABLE 8.

Parameter	Measure point	Min	Typ	Max	Units
Main 5V Output Voltage	Ground to 5V pins on	4,6	4,75	4,9	Volts
5V Output Current	5V pins on Hall Connector and DSub15			200 (1)	mA
Digital Output Voltage	Ground to Output pins			30	Volts
Digital Output Current	Output pins, sink current			1	Amps
Output On resistance	Output pin to ground		0,75	1,5	Ohm
Output Short circuit threshold	Output pin	1,05	1,4	1,75	Amps
Input Impedances	AIN/DIN Input to Ground		53		kOhm
Digital Input 0 Level	Ground to Input pins	-1		1	Volts
Digital Input 1 Level	Ground to Input pins	3		15	Volts
Analog Input Range	Ground to Input pins	0		5,1	Volts
Analog Input Precision	Ground to Input pins		0,5		%
Analog Input Resolution	Ground to Input pins		1		mV
Pulse durations	Pulse inputs	20000		10	us
Pulse repeat rate	Pulse inputs	50		250	Hz
Pulse Capture Resolution	Pulse inputs		1		us
Frequency Capture	Pulse inputs	100		10000	Hz
Encoder count	Internal	-2.147		2,15	10 <sup>^</sup> 9 Counts
Encoder frequency	Encoder input pins			250	kHz
Note 1: Sum of all 5VOut outputs					

## Operating & Timing Specifications

TABLE 9.

Parameter	Measure Point	Min	Typ	Max	Units
Command Latency	Command to output change	1	0,5	1	ms
PWM Frequency	Ch1, Ch2 outputs	10	18 (1)	32	kHz
Closed Loop update rate	Internal		1000		Hz
USB Rate	USB pins			12	MBits/s
RS232 baud rate	Rx & Tx pins		115200 (2)		Bits/s
RS232 Watchdog timeout	Rx pin	1 (3)		65000	ms
Note 1: May be adjusted with configuration program					
Note 2: 115200, 8-bit, no parity, 1 stop bit, no flow control					
Note 3: May be disabled with value 0					



## Scripting

TABLE 10.

Parameter	Measure Point	Min	Typ	Max	Units
Scripting Flash Memory	Internal		8192		Bytes
Max Basic Language programs	Internal	1000		1500	Lines
Integer Variables	Internal		1024		Words (1)
Boolean Variables	Internal		1024		Symbols
Execution Speed	Internal	50 000	100 000		Lines/s
Note 1: 32-bit words					

## Thermal Specifications

TABLE 11.

Parameter	Measure Point	Model	Min	Typ	Max	Units
Board Temperature	Heatsink	All	-40		85 (1)	oC
Thermal Protection range	Heatsink	All	80		90 (2)	oC
Power Dissipation	Case	All			30	Watts
Thermal resistance	Power MOSFETs to heatsink	All			2	oC/W
Note 1: Thermal protection will protect the controller power						
Note 2: Max allowed power out starts lowering at minimum of range, down to 0 at max of range						

## Mechanical Specifications

TABLE 12.

Parameter	Measure Point	Min	Typ	Max	Units
Weight	Board		250 (0.5)		g (lbs)
Power Connectors width	Terminal tab		0,25		Inches

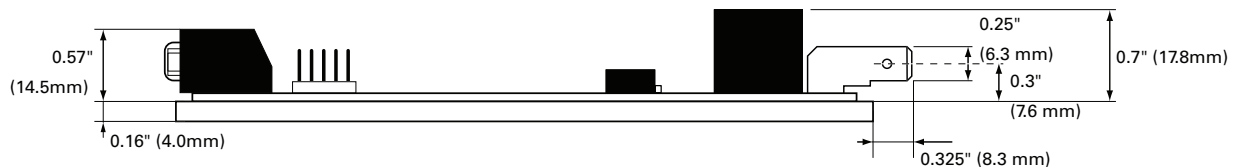


FIGURE 15. MDC2250 front view and dimensions

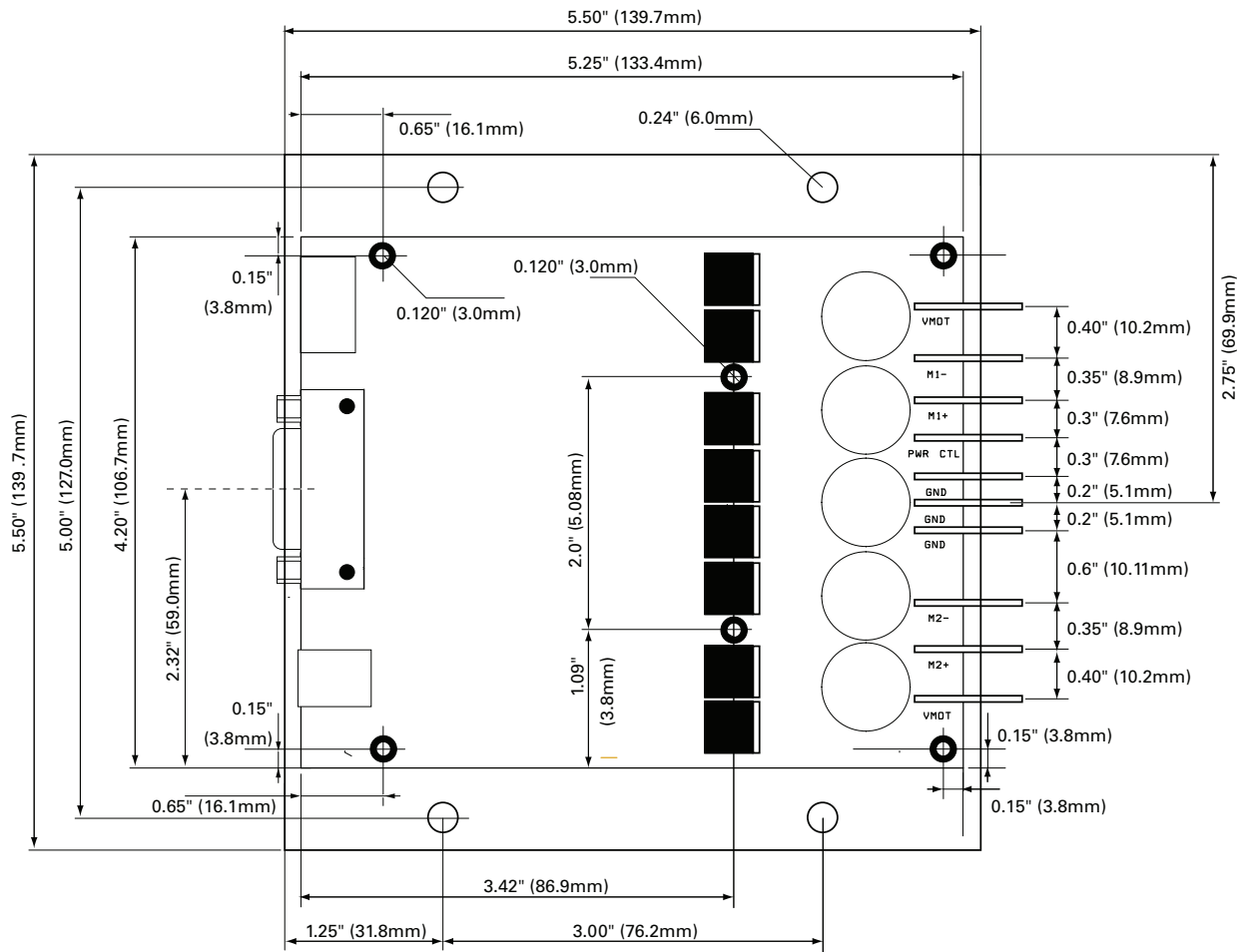


FIGURE 16. MDC2250 top view and dimensions