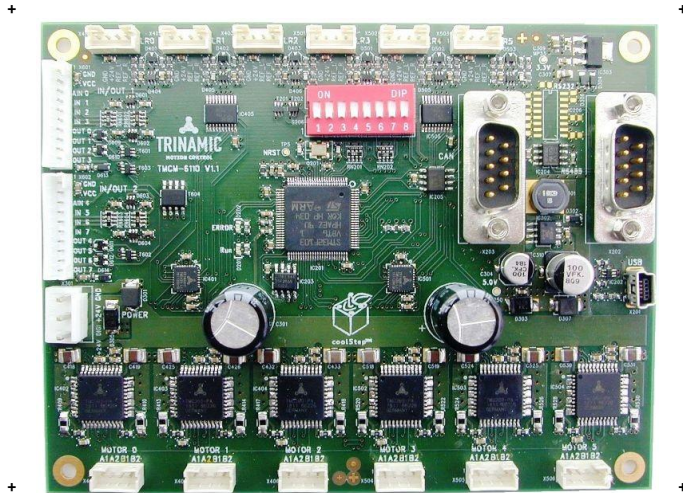


Hardware Version V1.10

HARDWARE MANUAL



TMCM-6110

6 Axes Stepper
Controller / Driver
1.1A RMS / 24V DC
USB, CAN, RS485 [or RS232]



stallGuard²

TRINAMIC Motion Control GmbH & Co. KG
Hamburg, Germany

www.trinamic.com



TRINAMIC
MOTION CONTROL

Table of Contents

1	Features.....	3
2	Order Codes	4
3	Mechanical and Electrical Interfacing	5
3.1	Size of Board.....	5
3.2	Board mounting considerations.....	5
3.2.1	DIN Rail Mounting.....	6
3.3	Connectors.....	7
3.3.1	Power Connector	8
3.3.2	I/O Connector 0.....	8
3.3.3	I/O Connector 1.....	9
3.3.4	Motor Connector 0-5.....	9
3.3.5	Reference Switch Connector 0-5	9
3.3.6	CAN Connector	10
3.3.7	RS485 Connector.....	10
3.3.8	USB Connector.....	10
3.4	Power Supply.....	11
3.5	Communication	11
3.5.1	RS485.....	11
3.5.2	CAN	12
3.5.3	USB.....	13
3.6	Inputs and Outputs.....	13
3.6.1	Reference Switch Inputs	13
3.6.2	General Purpose Inputs.....	14
3.6.3	General Purpose Outputs	15
4	On-board LEDs.....	16
5	Reset to Factory Defaults	17
6	Functional Description	18
7	Operational Ratings	19
8	Life Support Policy.....	20
9	Revision History	21
9.1	Document Revision	21
9.2	Hardware revision	21
10	References.....	21

1 Features

The TMC6110 is a compact 6-axes stepper motor controller/driver standalone board. It supports up to 6 bipolar stepper motors with up to 1.1A RMS coil current. There are separate motor and reference/end switch connectors for each motor. In addition, the module offers 8 general purpose inputs and 8 general purpose outputs.

MAIN CHARACTERISTICS

Motion controller

- Motion profile calculation in real-time
- On the fly alteration of motor parameters (e.g. position, velocity, acceleration)
- High performance microcontroller for overall system control and serial communication protocol handling

Bipolar stepper motor driver

- Up to 256 microsteps per full step
- High-efficient operation, low power dissipation
- Dynamic current control
- Integrated protection
- stallGuard2™ feature for stall detection
- coolStep™ feature for reduced power consumption and heat dissipation

Interfaces

- Up to 8 multi-purpose inputs (+24V compatible, incl. 2 dedicated analog inputs)
- Up to 8 multi-purpose outputs (open-drain, incl. 2 outputs for currents up to 1A)
- RS485 2-wire communication interface
- USB 2.0 full speed (12Mbit/s) communication interface (mini-USB connector)
- CAN 2.0B communication interface (9pin D-SUB)

Features

- Uses TMC429 stepper motor controller for on-the-fly alteration of many motion specific parameters
- Uses TMC260 advanced stepper motor driver IC
- Up to 256 microsteps per fullstep
- Integrated protection: overtemperature/undervoltage

Software

- TMCL remote (direct mode) and standalone operation (memory for up to 2048 TMCL commands)
- Fully supported by TMCL-IDE (PC based integrated development environment)

Electrical data

- Supply voltage: +9V... +28V DC
- Motor current: up to 1.1A RMS (programmable) per axis

Mechanical data

- Board size: 130mm x 100mm, height 30mm max.
- 4 mounting holes for M3 screws

Please see separate TMCL Firmware Manual for additional information

2 Order Codes

Order code	Description	Size of unit
TMC6110- <i>option</i>	6-axes bipolar stepper motor controller and driver module	130mm x 100mm x 30mm

Table 2.1 TMC6110 order codes

The following options are available:

Firmware option	Description	Order code example:
-TMCL	Module pre-programmed with TMCL firmware	TMC6110- <i>TMCL</i>

Table 2.2 TMC6110 firmware options

A version with RS232 interface and 9pin female D-SUB connector instead of RS485 is available as assembly option upon request:

Interface option	Description	Order code example:
-232	Module with RS232 interface instead of RS485	TMC6110-232- <i>TMCL</i>

Table 2.3 TMC6110 interface options

A cable loom set is available for this module.

Order code	Description
TMC6110-CABLE	The cable loom for TMC6110 contains: <ul style="list-style-type: none"> - 1x Cable loom for power connector - 6x cable loom for reference switch connectors 0-5 - 6x cable loom for motor connector 0-5 - 2x cable loom for I/O connector 0+1 - 1x USB type A connector to mini-USB type B connector cable

Table 2.4 Cable loom order code

3 Mechanical and Electrical Interfacing

3.1 Size of Board

The board with the controller / driver electronics has an overall size of 130mm x 100mm and offers four mounting holes for M3 screws (3.2mm diameter). Maximum board height (without mating connectors and cable looms) is about 30mm (approx. 26mm above printed circuit board level).

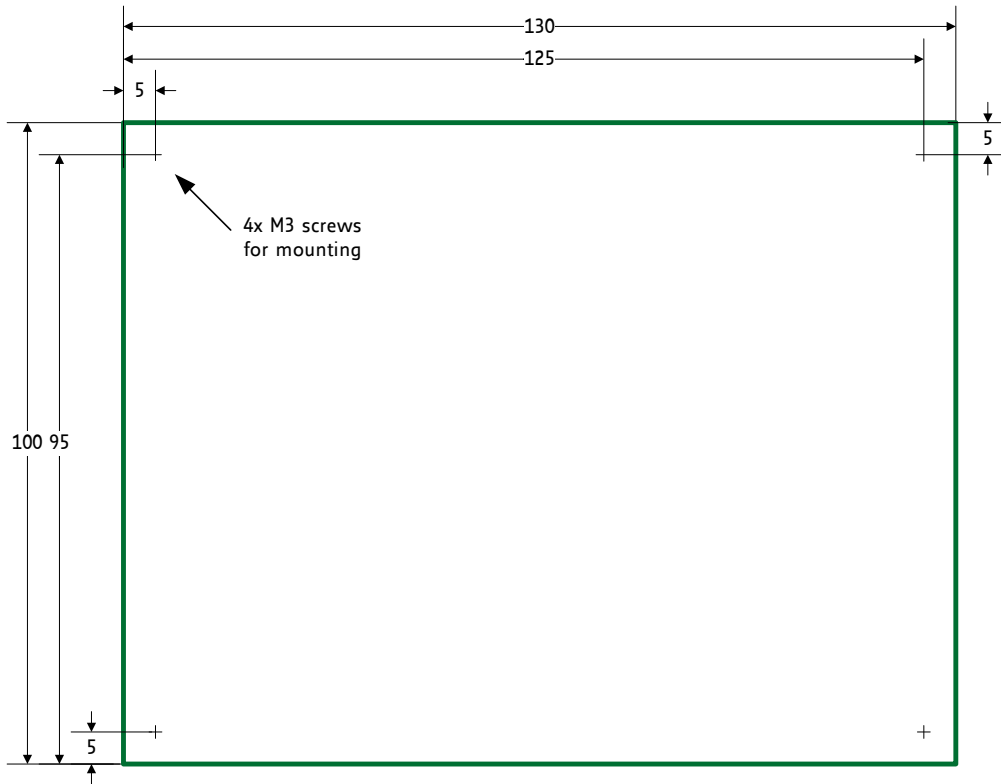


Figure 3.1 Board dimensions and position of mounting holes (all values in mm).

3.2 Board mounting considerations

The TMC6110 offers four metal plated mounting holes. All four mounting holes are connected to system and signal ground (same as power supply ground).

In order to minimize distortion of signals and radiation of HF signals (improve EMC compatibility) especially in sensitive / noisy environments it is important to ensure a solid ground connection within the system. In order to support this, it is recommended to connect all four mounting holes of the board in addition to the supply ground connection to system power supply ground.

Nevertheless, this might not always be an option e.g. in case the metal system chassis / TMC6110 mounting plate is already connected to earth and a direct connection between supply ground (secondary side) and mains supply earth (primary side) is not desired / not an option. In this case plastic (e.g. made of nylon) spacers / distance bolts should be used.

3.2.1 DIN Rail Mounting

The board has been designed in order to support DIN rail mounting. One dimension of the board has been limited to 100mm and there is a minimum border of approx. two millimeters alongside all four corners of the board free of any component. This way, a standard mounting carrier for DIN rails as it is available from several sources might be used as adapter for DIN rail mounting of the board.

EXAMPLE

Mounting carrier for DIN 35 rail from WAGO® (288-003) cut to the length of the TMC6110 board (130mm) with populated TMC6110.



Figure 3.2 DIN rail mounting

3.3 Connectors

The TMC6110 has 18 connectors altogether. There are 6 separate connectors for each motor and corresponding reference switches (Figure 4.4), two I/O connectors, one power connector and 3 connectors for communication incl. Mini-USB, RS485 and CAN.

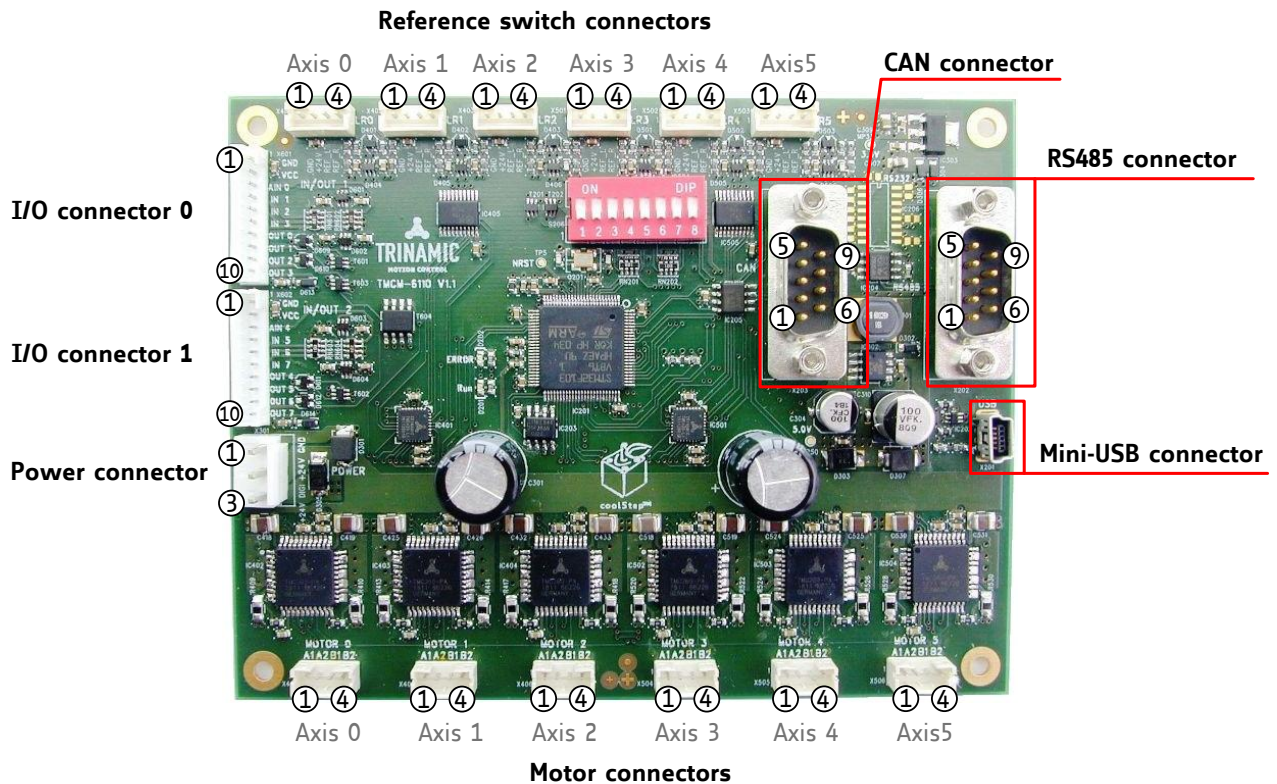


Figure 3.3 TMC6110 connectors

Overview of connector and mating connector types:

Label	Connector type	Mating connector type
Power Connector	JST B3P-VH (JST VH series, 3pins, 3.96mm pitch)	Connector housing: JST VHR-3N Contacts: JST SVH-21T-P1.1 Wire: 0.83mm ² , AWG 18
Motor Connectors	JST B4B-PH-K-S (JST PH series, 4pins, 2mm pitch)	Connector housing: JST PHR-4 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
Reference Switch Connectors	JST B4B-PH-K-S (JST PH series, 4pins, 2mm pitch)	Connector housing: JST PHR-4 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
I/O Connector 0 + 1	JST B10B-PH-K-S (JST PH series, 10pins, 2mm pitch)	Connector housing: JST PHR-10 Contacts: JST SPH-002T-P0.5S Wire: 0.22mm ² , AWG 24
Mini-USB Connector	Molex 500075-1517 Mini USB Type B vertical receptacle	Any standard mini-USB plug
RS485 Connector	Tyco electronics 3-1634218-2 D-SUB socket with 4-40 female screwlocks	Any standard D-SUB female 9-pin
CAN Connector	Male D-SUB 9-pin	Any standard D-SUB female 9-pin

Table 3.1 Connectors and mating connectors, contacts and applicable wire

3.3.1 Power Connector

The module offers a single power connector with the option to have separate supply for driver electronics and digital controller part. A single supply voltage is sufficient, all further voltages required e.g. for the digital components are generated on-board.


	Pin	Label	Direction	Description
	1	GND	Power (GND)	Common system supply and signal ground
	2	V _{DRIVER}	Power (Supply input)	Stepper driver supply voltage. Without this voltage stepper driver ICs and therefore any motor connected will not be energized
	3	V _{DIGITAL}	Power (Supply input)	Supply voltage for everything else apart from the stepper motor driver ICs. On-board voltage regulator will generate the necessary voltages for the digital circuits from this supply. This pin can be left unconnected. In this case a diode between V _{DRIVER} and V _{DIGITAL} will ensure supply of the digital parts. Please note: <ul style="list-style-type: none"> - The diode has a current rating of 3A. As V_{DIGITAL} is available at the I/O connectors and the reference switch connectors also, always connect this pin to positive supply voltage in case substantial amount of current is withdrawn from these pins for external circuits. - It is expected that V_{DIGITAL} and V_{DRIVER} are connected to the same power supply output when both pins are used. Otherwise please ensure that V_{DIGITAL} is always equal or higher than V_{DRIVER} when connected (due to the diode).

Table 3.2 Power connector

3.3.2 I/O Connector 0

The module offers two I/O connectors. The number and type of inputs, outputs and supply is the same for both connectors. Therefore, if only half of the inputs / outputs etc. is required it will be sufficient to use just one of the two connectors and reduce / simplify cabling. Connector type is JST PH series 8pin with 2mm pitch.


	Pin	Label	Direction	Description
	1	GND	Power (GND)	GND
	2	V _{DIGITAL}	Power (Supply output)	Connected to V _{DIGITAL} of Power connector
	3	AIN_0	Input	Dedicated analog input, input voltage range: 0... +10V, resolution: 12bit (0... 4095)
	4	IN_1	Input	Digital input (+24V compatible)
	5	IN_2	Input	Digital input (+24V compatible)
	6	IN_3	Input	Digital input (+24V compatible)
	7	OUT_0	Output	Open-drain output (max. 100mA) Integrated freewheeling diode
	8	OUT_1	Output	Open-drain output (max. 100mA) Integrated freewheeling diode
	9	OUT_2	Output	Open-drain output (max. 100mA) Integrated freewheeling diode
	10	OUT_3	Output	Open-drain output (max. 1A) Integrated freewheeling diode

Table 3.3 I/O connector 0

3.3.3 I/O Connector 1

The module offers two I/O connectors. The number and type of inputs, outputs and supply is the same for both connectors. Therefore, if only half of the inputs / outputs etc. is required it will be sufficient to use just one of the two connectors and reduce / simplify cabling. Connector type is JST PH series 8pin with 2mm pitch.


	Pin	Label	Direction	Description
	1	GND	Power (GND)	GND
	2	V _{DIGITAL}	Power (Supply output)	Connected to V _{DIGITAL} of Power connector
	3	AIN_4	Input	Dedicated analog input, input voltage range: 0... +10V, resolution: 12bit (0... 4095)
	4	IN_5	Input	Digital input (+24V compatible)
	5	IN_6	Input	Digital input (+24V compatible)
	6	IN_7	Input	Digital input (+24V compatible)
	7	OUT_4	Output	Open-drain output (max. 100mA) Integrated freewheeling diode
	8	OUT_5	Output	Open-drain output (max. 100mA) Integrated freewheeling diode
	9	OUT_6	Output	Open-drain output (max. 100mA) Integrated freewheeling diode
	10	OUT_7	Output	Open-drain output (max. 1A) Integrated freewheeling diode

Table 3.4 I/O connector 1

3.3.4 Motor Connector 0-5

For each stepper motor axis a separate 4 pin JST PH series connector is available.


	Pin	Label	Direction	Description
	1	A1	Output	Pin 1 of motor coil A
	2	A2	Output	Pin 2 of motor coil A
	3	B1	Output	Pin 1 of motor coil B
	4	B2	Output	Pin 2 of motor coil B

Table 3.5 Motor connector

3.3.5 Reference Switch Connector 0-5

For each stepper motor axis a separate reference / limit switch input connector is available. Connector type is JST PH series 4pin with 2mm pitch.

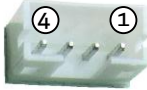
	Pin	Label	Direction	Description
	1	GND	Power (GND)	Signal and system ground
	2	V _{DIGITAL}	Power (Supply input)	Connected to V _{DIGITAL}
	3	REF_L	Input	Input for reference / limit switch left
	4	REF_R	Input	Input for reference / limit switch right

Table 3.6 Reference switch connector

3.3.6 CAN Connector

A CAN 2.0B interface is available via a standard 9-pin male D-SUB connector. Only three pins of this connector are used. Pin assignment of these three pins is according to CiA Draft Recommendation Part 1: Cabling and connector pin assignment.

CAN interface will be de-activated in case USB is connected due to internal sharing of hardware resources.


	Pin	Label	Direction	Description	
	1				
	2	CAN_L	Bi-directional	Differential CAN bus signal (inverting)	
	3	GND	Power (GND)	Signal and system ground	
	4				
	5				
	6				
	7	CAN_H	Bi-directional	Differential CAN bus signal (non-inverting)	
	8				
	9				

Table 3.7 CAN connector

3.3.7 RS485 Connector

An RS485 interface is available via a 9-pin male D-SUB connector.

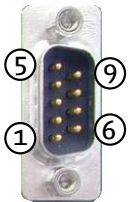
	Pin	Label	Direction	Description	
	1				
	2	RS485-	Bi-directional	Differential RS485 bus signal (inverting)	
	3	GND	Power (GND)	Signal and system ground	
	4				
	5				
	6				
	7	RS485+	Bi-directional	Differential RS485 bus signal (non-inverting)	
	8				
	9				

Table 3.8 RS485 connector

3.3.8 USB Connector

A USB interface is available via a Mini-USB connector. This module supports USB 2.0 Full-Speed (12Mbit/s) connections.

CAN interface will be deactivated as soon as USB is connected (VBUS voltage available)
 On-board digital core logic (mainly processor and EEPROM) will be powered via USB in case no other supply is connected. This can be used to set parameters / download TMCL programs or perform firmware updates with the module connected via USB only or inside the machine while the machine is powered off.


	Pin	Label	Direction	Description
	1	VBUS	Power (+5V input)	+5V supply from Host
	2	D-	Bi-directional	USB Data -
	3	D+	Bi-directional	USB Data +
	4	ID		Connected to signal and system ground
	5	GND	Power (GND)	Signal and System ground

Table 3.9 USB connector

3.4 Power Supply

For proper operation care has to be taken with regard to power supply concept and design. The board offers 2000uF / 35V electrolytic buffer capacitors and additionally about 120uF / 35V ceramic capacitors for supply voltage filtering.

It is important that the power supply voltage (V_{DRIVER} and $V_{DIGITAL}$) is kept below the upper limit of 28V DC. Otherwise the on-board electronics might be seriously damaged! Especially, when the selected operating voltage is near the upper limit a regulated power supply is highly recommended.

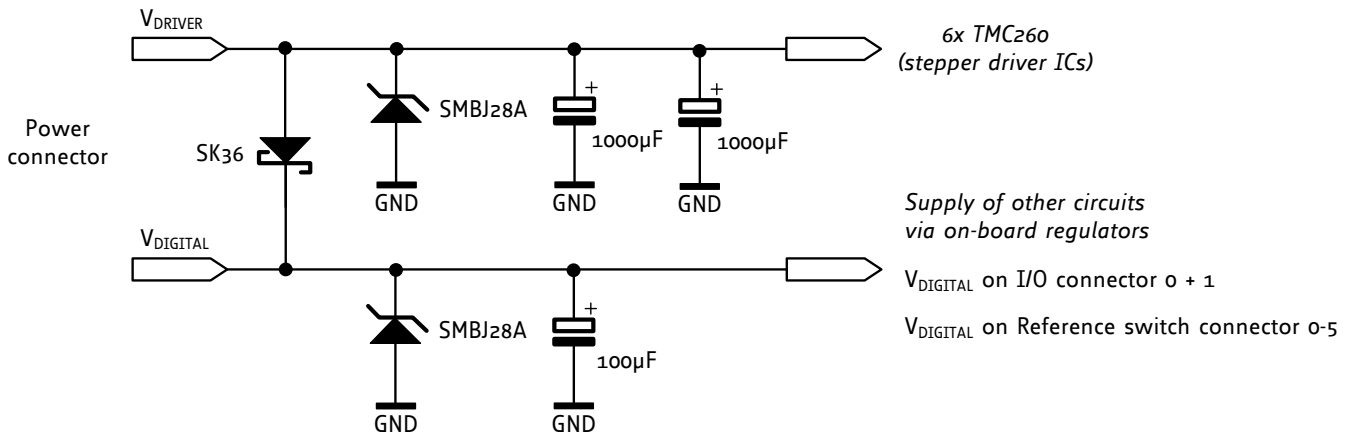


Figure 3.4 TCM-6110 power supply concept

3.5 Communication

3.5.1 RS485

For remote control and communication with a host system the TCM-6110 provides a two wire RS485 bus interface. For proper operation the following items should be taken into account when setting up an RS485 network:

1. **BUS STRUCTURE:**

The network topology should follow a bus structure as closely as possible. That is, the connection between each node and the bus itself should be as short as possible. Basically, it should be short compared to the length of the bus.

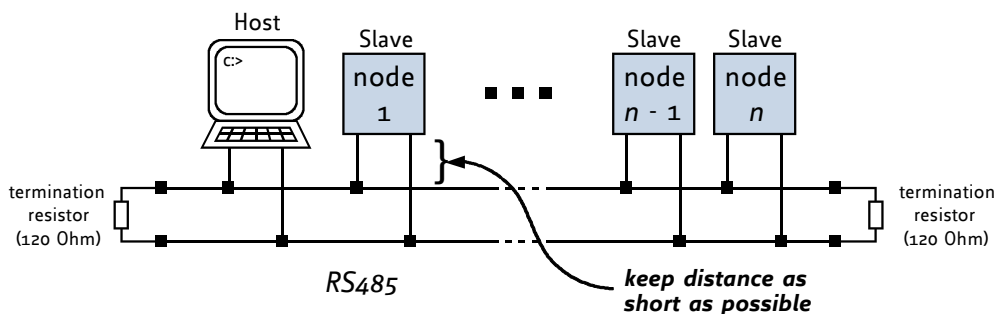


Figure 3.5 RS485 bus structure

2. **BUS TERMINATION:**

Especially for longer busses and/or multiple nodes connected to the bus and/or high communication speeds, the bus should be properly terminated at both ends. The TMC6110 does not integrate any termination resistor. Therefore, 120 Ohm termination resistors at both ends of the bus have to be added externally.

3. **NUMBER OF NODES:**

The RS-485 electrical interface standard (EIA-485) allows up to 32 nodes to be connected to a single bus. The bus transceiver used on the TMC6110 units (SN65HVD3082ED) has just 1/8th of the standard bus load and allows a maximum of 256 units to be connected to a single RS485 bus.

4. **NO FLOATING BUS LINES:**

Avoid floating bus lines while neither the host/master nor one of the slaves along the bus line is transmitting data (all bus nodes switched to receive mode). Floating bus lines may lead to communication errors. In order to ensure valid signals on the bus it is recommended to use a resistor network connecting both bus lines as well defined logic levels. In contrast to the termination resistors this network is normally required just once per bus. Certain RS485 interface converters available for PCs already include these additional resistors (e.g. USB-2-485).

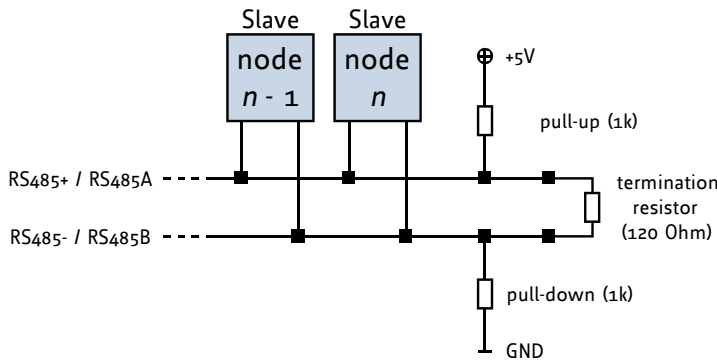


Figure 3.6: RS485 bus lines with resistor network

3.5.2 CAN

For remote control and communication with a host system the TMC6110 provides a CAN bus interface. Please note that the CAN interface is not available in case USB is connected. For proper operation the following items should be taken into account when setting up a CAN network:

5. **BUS STRUCTURE:**

The network topology should follow a bus structure as closely as possible. That is, the connection between each node and the bus itself should be as short as possible. Basically, it should be short compared to the length of the bus.

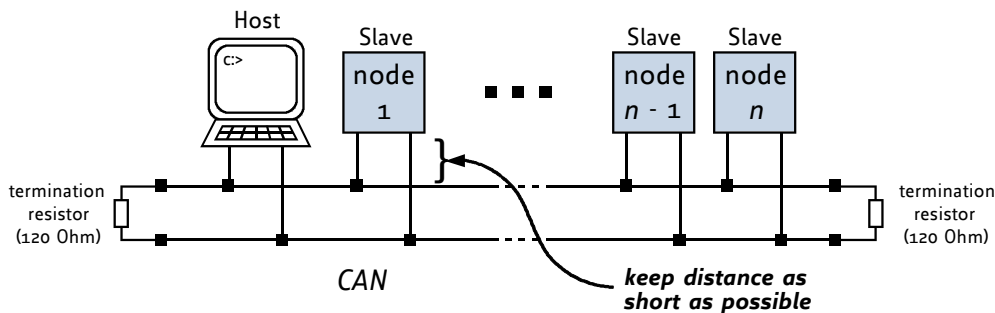


Figure 3.7 CAN bus structure

6. BUS TERMINATION:

Especially for longer busses and/or multiple nodes connected to the bus and/or high communication speeds, the bus should be properly terminated at both ends. The TMC6110 does not integrate any termination resistor. Therefore, 120 Ohm termination resistors at both ends of the bus have to be added externally.

7. NUMBER OF NODES:

The bus transceiver used on the TMC6110 units (TJA1050T) supports at least 110 nodes under optimum conditions. Practically achievable number of nodes per CAN bus highly depends on bus length (longer bus -> less nodes) and communication speed (higher speed -> less nodes).

3.5.3 USB

For remote control and communication with a host system the TMC6110 provides a USB 2.0 full-speed (12Mbit/s) interface (mini-USB connector). As soon as a USB-Host is connected the module will accept commands via USB. The CAN interface will be de-activated then.

The TMC6110 support USB self powered operation (when an external power is supplied via the power supply connector) and USB bus powered operation, also (no external power supply via power supply connector). During USB bus powered operation, only the core digital circuit parts will be operational. That is, the microcontroller itself and also the EEPROM. Motor movements will not be possible. This mode has been implemented in order to enable configuration / parameter setting / read-out, firmware updates etc. by just connecting a USB cable between the module and a host PC. No additional cabling / external devices as e.g. power supply etc. are required in that case.

Please note that the module might draw current from the USB +5V bus supply even in USB self powered operation depending on the voltage level of this supply.

3.6 Inputs and Outputs

3.6.1 Reference Switch Inputs

The six reference switch connectors – one for each stepper motor axis – offer two reference switch inputs each, REF_L and REF_R.

Both inputs offer the same input circuit with voltage resistor dividers, limiting diodes against over- and under-voltage and programmable 1k pull-ups to +5V. The programmable pull-ups can be switched on or off separately for the first three axes / first three reference switch connectors 0-2 and the second three axes / reference switch connectors 3-5.

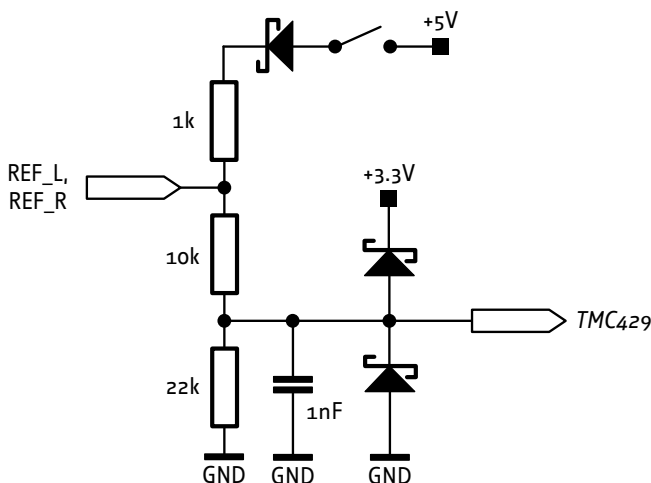


Figure 3.8 Reference switch input circuit (simplified diagram)

3.6.2 General Purpose Inputs

The TMCM-6110 offers two I/O connectors with 8 inputs altogether including two dedicated analog inputs. All inputs offer the same basic input protection circuit. The dedicated analog inputs have different input voltage dividers in order to support a full scale input voltage range of 0...+10V. The other digital inputs have been designed in order to be able to accept +5V and +24V signal levels.

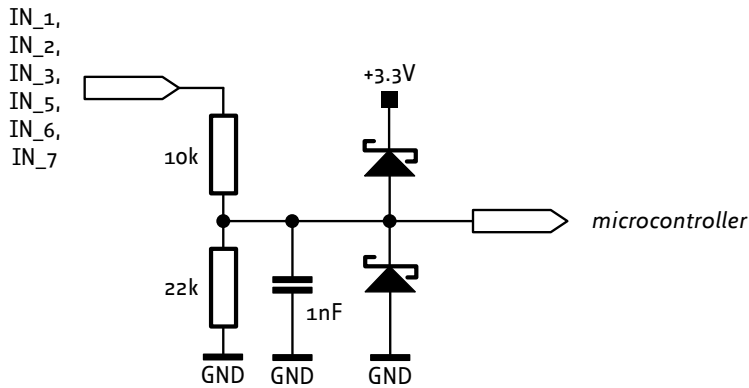


Figure 3.9 General purpose digital input circuit

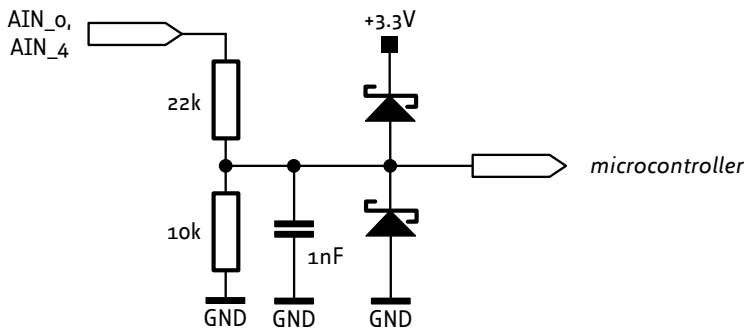


Figure 3.10 General purpose analog input circuit

The function of the inputs might differ depending on firmware version.

3.6.3 General Purpose Outputs

The TMC6110 offers two I/O connectors with 8 outputs altogether. All outputs are open-drain outputs. For all outputs a freewheeling diode (to V_{DIGITAL}) is already integrated.

Nevertheless, two output offer more powerful MOSFET driver transistors supporting currents up to 1A. All other have been designed for currents up to 100mA.

If V_{DIGITAL} connection of the I/O connectors is used for supply of substantial current to any external circuit please make sure to connect V_{DIGITAL} in addition to V_{DRIVER} of the power supply connector.

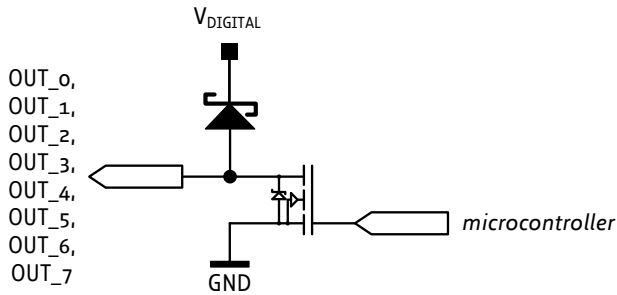


Figure 3.11 General purpose output (open-drain with freewheeling diode)

4 On-board LEDs

The board offers two LEDs in order to indicate board status. The function of both LEDs is dependent on firmware version.

With standard TMCL firmware the green LED should be slowly flashing during operation and the red LED should be off. Please see separate TMC6110 TMCL™ firmware manual for additional information.

When there is no valid firmware programmed into the board or during firmware update the red and green LEDs are permanently on.

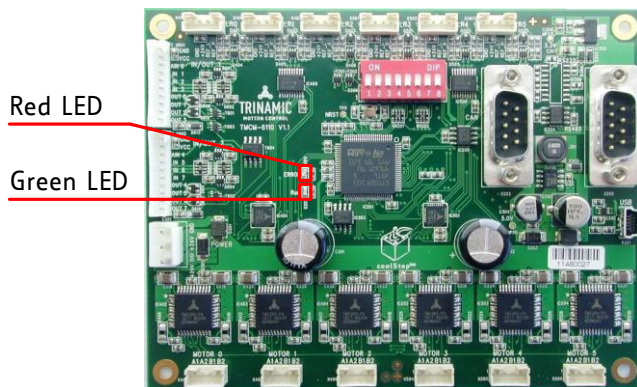


Figure 5.1 On-board LEDs

5 Reset to Factory Defaults

Since TMCL firmware version V1.13 it is possible to reset the TMC6110 module to factory default settings without establishing a communication link. This might be helpful in case communication parameters of the preferred interface have been set to unknown values or got accidentally lost.

PERFORM THE FOLLOWING STEPS:

1. Power supply off and USB cable disconnected
2. Short two pads as marked in Figure 5.1.
3. Power up board (power via USB is sufficient for this purpose)
4. Wait until the on-board red and green LEDs start flashing fast (this might take a while)
5. Power-off board (disconnect USB cable)
6. Remove short between pads
7. After switching on power-supply / connecting USB cable all permanent settings have been restored to factory defaults

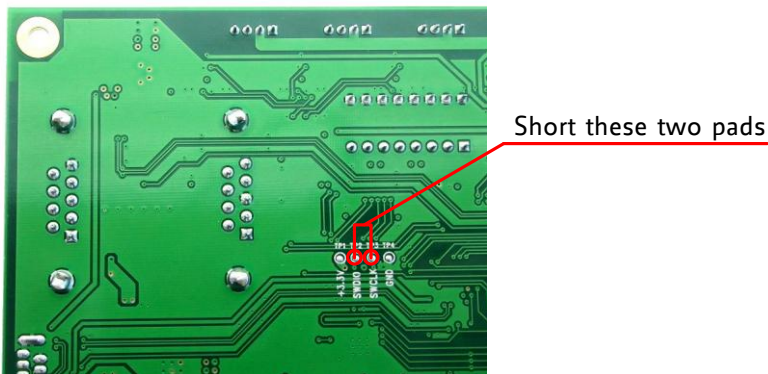


Figure 5.1 Reset to factory default settings

6 Functional Description

The TCM6110 is a highly integrated 6-axes controller / driver module. The TCM6110 can be controlled via CAN, RS485 or USB serial interfaces. The TCM6110 comes with the PC based software development environment TMCL-IDE for the Trinamic Motion Control Language (TMCL). Using predefined TMCL high level commands like *move to position* a rapid and fast development of motion control applications is guaranteed. Communication traffic is kept low since all time critical operations, e.g. ramp calculation are performed on board. Full remote control of device with feedback is possible. The firmware of the module can be updated via any of the serial interfaces.

The TCM6110 module contains the following main components (see figure below, also):

- Microcontroller running at 72MHz
- 16Kbytes EEPROM for storing configuration parameters and TMCL program storage (up to 2048 TMCL commands)
- 2x TMC429 [TMC429] highly integrated 3 axes stepper motor controller
- 6x TMC260 [TMC260] advanced stepper motor driver IC with stallGuard2™ and coolStep™ with integrated MOSFET driver transistors
- RS485, CAN and USB transceivers
- On-board switching and linear voltage regulators for supply of on-board digital circuits

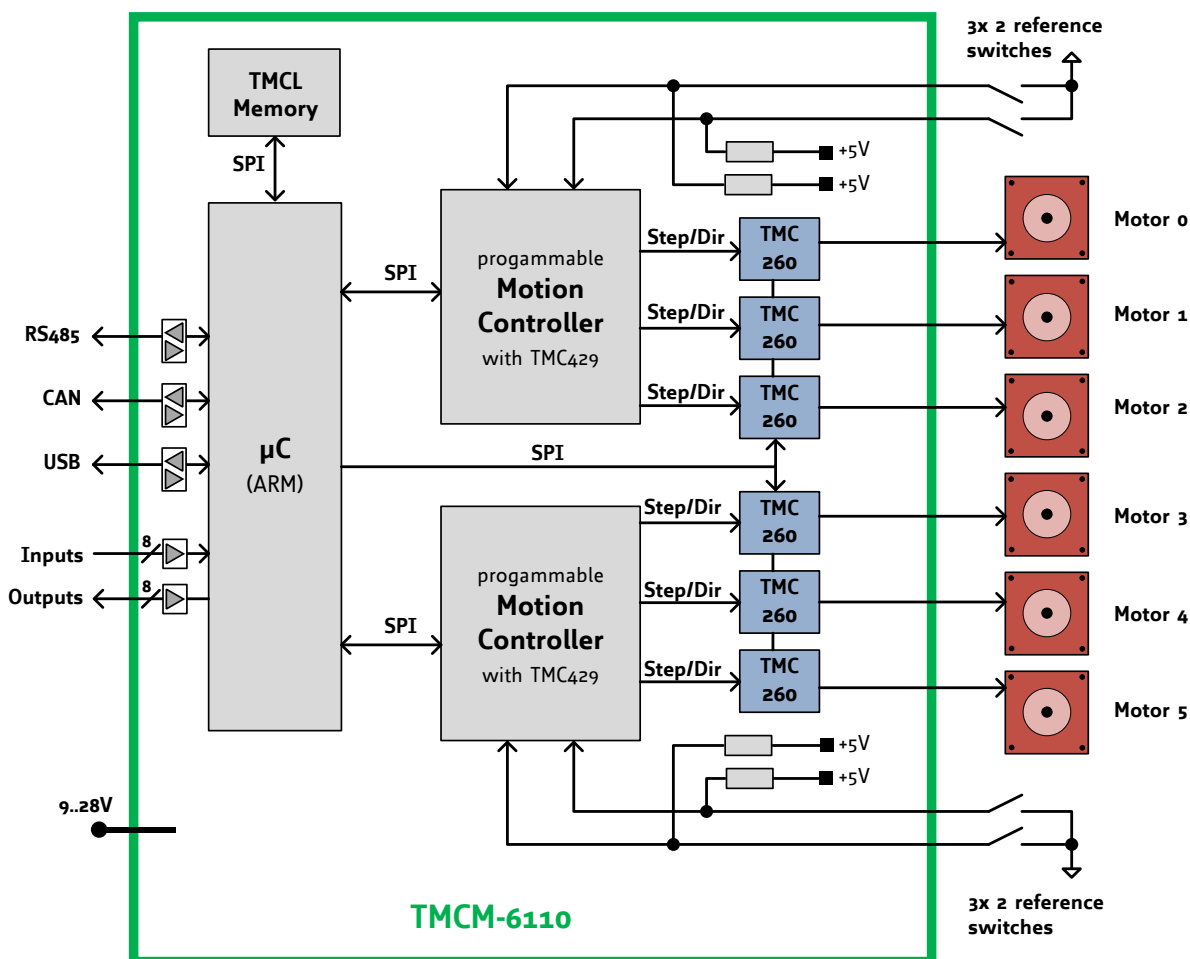


Figure 7.1: TCM6110 block diagram

Please refer to the TCM6110 Firmware Manual for more information about TMCL commands.

7 Operational Ratings

The operational ratings show the intended or the characteristic ranges and should be used as design values.

In no case shall the maximum values be exceeded.

Symbol	Parameter	Min	Typ	Max	Unit
V_{DRIVER}	Power supply voltage for driver	9	12 ... 24	28	V
$V_{DIGITAL}$	Power supply voltage for controller (option, can be left unconnected)	V_{DRIVER}			V
V_{USB}	Power supply via USB connector		5		V
I_{USB}	Current withdrawn from USB supply when USB bus powered (no other supply connected)		85		mA
I_{COIL}	Motor coil current for sine wave peak (chopper regulated, adjustable via software)	0		1600	mA
I_{MC}	Continuous motor current (RMS)	0		1100	mA
I_S	Power supply current		$\ll 6x I_{COIL}$	$1.4x 6x I_{COIL}$	A
T_{ENV}	Environmental temperature at maximum current (all six axes, no forced cooling)	-34°		60	$^{\circ}C$

Table 7.1 General operational ratings of the module

^{*)} limited by test equipment. Includes power-up / cold start at this temperature. It can be expected that the module will work down to $-40^{\circ}C$.

Symbol	Parameter	Min	Typ	Max	Unit
$V_{REF_L/R}$	Input voltage for reference switch inputs REF_L / REF_R	0		28	V
I_{REF_L/R_L}	Low level voltage for reference switch inputs REF_L / REF_R	0		1.1	V
I_{REF_L/R_H}	High level voltage for reference switch inputs REF_L / REF_R	2.9		28	V

Table 7.2 Operational ratings of the reference switch inputs

Symbol	Parameter	Min	Typ	Max	Unit
$1V_{OUT_0..7}$	Voltage at open collector output	0		$V_{DIGITAL}$	V
$I_{OUT_0/1/2/4/5/6}$	Output sink current for OUT_0/1/2 and OUT_4/5/6			100	mA
$I_{OUT_3/7}$	Output sink current for OUT_3 and OUT_7			1	A
$V_{IN_1/2/3/5/6/7}$	Input voltage for general purpose digital inputs IN_1/2/3 and IN_5/6/7	0		28	V
$V_{IN_1/1/2/3/5/6/7_L}$	Low level voltage for general purpose digital inputs IN_1/2/3 and IN_5/6/7	0		1.1	V
$V_{IN_1/2/3/5/6/7_H}$	High level voltage for general purpose digital inputs IN_1/2/3 and IN_5/6/7	2.9		28	V
$V_{AIN_0/4}$	Full scale input voltage range for analog voltage inputs	0		10	V

Table 7.3 Operational ratings of the general purpose I/Os

Symbol	Parameter	Min	Typ	Max	Unit
N_{RS485}	Number of nodes connected to single RS485 network			256	

Table 7.4 Operational ratings of the RS485 interface

8 Life Support Policy

TRINAMIC Motion Control GmbH & Co. KG does not authorize or warrant any of its products for use in life support systems, without the specific written consent of TRINAMIC Motion Control GmbH & Co. KG.

Life support systems are equipment intended to support or sustain life, and whose failure to perform, when properly used in accordance with instructions provided, can be reasonably expected to result in personal injury or death.

© TRINAMIC Motion Control GmbH & Co. KG 2012

Information given in this data sheet is believed to be accurate and reliable. However, responsibility is neither assumed for the consequences of its use nor for any infringement of patents or other rights of third parties, which may result from its use.

Specifications are subject to change without notice.

All trademarks used are property of their respective owners.



9 Revision History

9.1 Document Revision

Version	Date	Author	Description
0.90	2011-AUG-17	GE	Preliminary version
1.00	2011-SEP-13	SD	First complete version, minor changes
1.01	2011-NOV-11	SD	Minor changes, T _{ENV} in chapter 7 added.
1.10	2012-JAN-25	GE	<ul style="list-style-type: none"> - DIN rail mounting option added - Basic description of on-board LEDs - Reset to factory default in hardware added - Lower environmental operating temperature added
1.11	2012-DEC-20	SD	Changes related to wording and design.

Figure 9.1 Document Revision

9.2 Hardware revision

Version	Date	Description
TMCM-6110_V10	2011-MAY-12	Initial version
TMCM-6110_V11	2011-AUG-02	Several corrections and enhancement: <ul style="list-style-type: none"> - Corrected / modified clock concept - Connection of reference switch corrected - 8x DIP switch THT instead of 4x SMT - Separate power supplies for driver stage and other electronic

Figure 9.2 Hardware Revision

10 References

- [JST] JST connector
<http://www.jst.com>
- [USB-2-485] USB-2-485 interface converter
Manual available on <http://www.trinamic.com>
- [TMCL-IDE] TMCL-IDE User Manual
Manual available on <http://www.trinamic.com>.