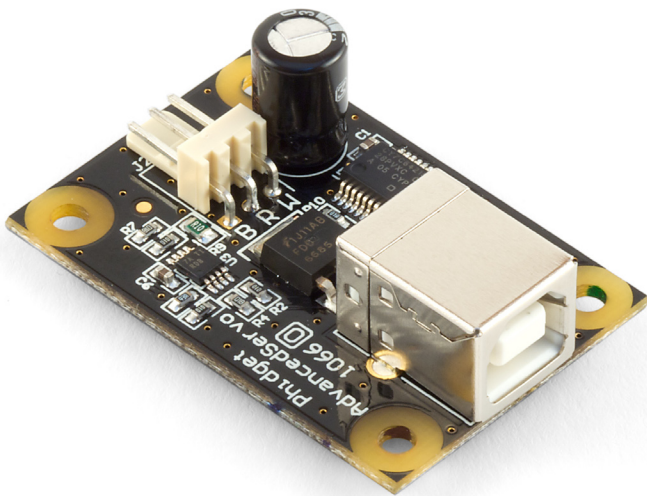


Product Manual

1066 - PhidgetAdvancedServo 1-Motor



Phidgets 1066 - Product Manual
For Board Revision 0
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Product Features

- Control the position, velocity, and acceleration of one RC servo motor.
- The PhidgetsAdvancedServo 1-Motor is powered solely by the USB cable – no additional power source is required!
- High resolution - 125 steps per degree.
- Measures current consumption of the servo.
- Powers servo motors of up to 450 mA.
- Can be used with some motor controllers.

Programming Environment

Operating Systems: Windows 2000/XP/Vista/7, Windows CE, Linux, and Mac OS X

Programming Languages (APIs): VB6, VB.NET, C#.NET, C++, Flash 9, Flex, Java, LabVIEW, Python, Max/MSP, and Cocoa.

Examples: Many example applications for all the operating systems and development environments above are available for download at www.phidgets.com >> Programming.

Connection

The board connects directly to a computer's USB port.

Getting Started

Checking the Contents

You should have received:

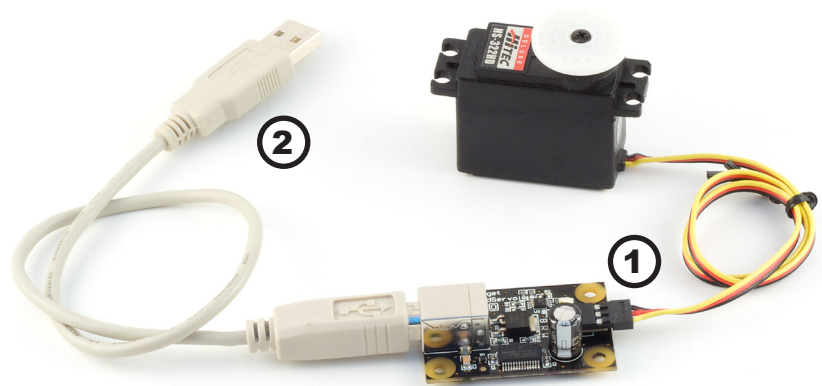
- A PhidgetAdvancedServo 1-Motor
- A USB Cable

In order to test your new Phidget you will also need:

- An RC Servo Motor

Connecting all the pieces

1. Connect the RC servo Motor to the PhidgetAdvancedServo 1-Motor.
2. Connect the PhidgetAdvancedServo 1-Motor to your computer using the USB cable.




Testing Using Windows 2000/XP/Vista/7

Downloading the Phidgets drivers

Make sure that you have the current version of the Phidget library installed on your PC. If you don't, do the following:

Go to www.phidgets.com >> Drivers


Download and run Phidget21 Installer (32-bit, or 64-bit, depending on your PC)

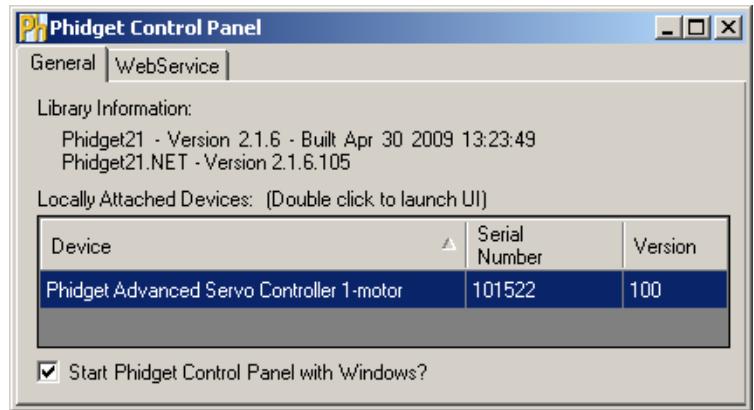
You should see the  icon on the right hand corner of the Task Bar.

Running Phidgets Sample Program

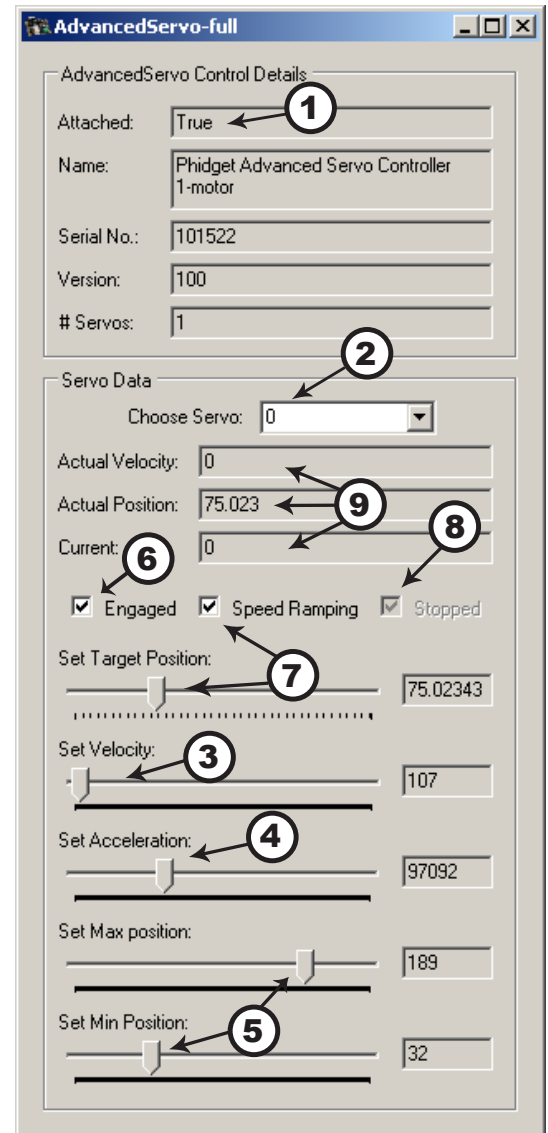
Double clicking on the  icon loads the Phidget Control Panel; we will use this program to make sure that your new Phidget works properly.

The source code for the AdvancedServo-Full sample program can be found under C# by clicking on Phidget.com > Programming.

Double Click on the  icon to activate the Phidget Control Panel and make sure that **Phidget Advanced Servo Controller 1-Motor** is properly attached to your PC.



1. Double click on **Phidget Advanced Servo Controller 1-Motor** in the Phidget Control Panel to bring up AdvancedServo-full and check that the box labelled Attached contains the word True.
2. The "Choose Servo" box shows 0.
3. Use the Velocity slider to set the velocity limit. The servo will try to accelerate to this point during motion.
4. Use the Acceleration slider to set the acceleration.
5. Use the Min/Max Position slider to set the position range. It can prevent the servo from trying to go beyond its actual range of motion.
6. Check the Engaged box to power the servo. If the servo is not already the target position, it should begin to move.
7. Move the Position slider to set a target position. The servo will turn until its actual position equals the target position. If Speed Ramping is enabled, the servo will move using the user set acceleration and velocity.
8. When the servo has reached the target position, a tick mark will appear in the Stopped box.
9. These boxes report the controller's internally calculated position and velocity of the servo, as well as current consumed in amps.



Testing Using Mac OS X

- Click on System Preferences >> Phidgets (under Other) to activate the Preference Pane
- Make sure that the **Phidget Advanced Servo Controller 1-Motor** is properly attached.
- Double Click on **Phidget Advanced Servo Controller 1-Motor** in the Phidget Preference Pane to bring up the AdvancedServo full example. This example will function in a similar way as the Windows version, but note that it does not include an Advanced Sensor Display.

If you are using Linux

There are no sample programs written for Linux.

Go to www.phidgets.com >> Drivers

Download Linux Source

- Have a look at the readme file
- Build Phidget21

There is no Control Panel written for Linux, but there are C/C++ and Java code samples available for all Phidgets which will compile and run on Linux without modification.

Notes:

Many Linux systems are now built with unsupported third party drivers. It may be necessary to uninstall these drivers for our libraries to work properly.

Phidget21 for Linux is a user-space library. Applications typically have to be run as root, or udev/hotplug must be configured to give permissions when the Phidget is plugged in.

If you are using Windows Mobile/CE 5.0 or 6.0

Go to www.phidgets.com >> Drivers

Download x86, ARMV4I or MIPSII, depending on the platform you are using. Mini-itx and ICOP systems will be x86, and most mobile devices, including XScale based systems will run the ARMV4I.

The CE libraries are distributed in .CAB format. Windows Mobile/CE is able to directly install .CAB files.

The most popular languages are C/C++, .NET Compact Framework (VB.NET and C#). A desktop version of Visual Studio can usually be configured to target your Windows Mobile Platform, whether you are compiling to machine code or the .NET Compact Framework.

Programming a Phidget

Phidgets' philosophy is that you do not have to be an electrical engineer in order to do projects that use devices like sensors, motors, motor controllers, and interface boards. All you need to know is how to program. We have developed a complete set of Application Programming Interfaces (API) that are supported for Windows, Mac OS X, and Linux. When it comes to languages, we support VB6, VB.NET, C#.NET, C, C++, Flash 9, Flex, Java, LabVIEW, Python, Max/MSP, and Cocoa.

Architecture

We have designed our libraries to give you the maximum amount of freedom. We do not impose our own programming model on you.

To achieve this goal we have implemented the libraries as a series of layers with the C API at the core surrounded by other language wrappers.

Libraries

The lowest level library is the C API. The C API can be programmed against on Windows, CE, OS X and Linux. With the C API, C/C++, you can write cross-platform code. For systems with minimal resources (small computers), the C API may be the only choice.

The Java API is built into the C API Library. Java, by default is cross-platform - but your particular platform may not support it (CE).

The .NET API also relies on the C API. Our default .NET API is for .NET 2.0 Framework, but we also have .NET libraries for .NET 1.1 and .NET Compact Framework (CE).

The COM API relies on the C API. The COM API is programmed against when coding in VB6, VBScript, Excel (VBA), Delphi and Labview.

The ActionScript 3.0 Library relies on a communication link with a PhidgetWebService (see below). ActionScript 3.0 is used in Flex and Flash 9.

Programming Hints

- Every Phidget has a unique serial number - this allows you to sort out which device is which at runtime. Unlike USB devices which model themselves as a COM port, you don't have to worry about where in the USB bus you plug your Phidget in. If you have more than one Phidget, even of the same type, their serial numbers enable you to sort them out at runtime.
- Each Phidget you have plugged in is controlled from your application using an object/handle specific to that phidget. This link between the Phidget and the software object is created when you call the .OPEN group of commands. This association will stay, even if the Phidget is disconnected/reattached, until .CLOSE is called.
- For full performance, the Phidget APIs are designed to be used in an event driven architecture. Applications that require receiving all the data streaming from the device will have to use event handlers, instead of polling.

Networking Phidgets

The PhidgetWebService is an application written by Phidgets Inc. which acts as a network proxy on a computer. The PhidgetWebService will allow other computers on the network to communicate with the Phidgets connected to that computer. ALL of our APIs have the capability to communicate with Phidgets on another computer that has the PhidgetWebService running.

The PhidgetWebService also makes it possible to communicate with other applications that you wrote and that are connected to the PhidgetWebService, through the PhidgetDictionary object.

Documentation

Programming Manual

The Phidget Programming Manual documents the Phidgets software programming model in a language and device unspecific way, providing a general overview of the Phidgets API as a whole. You can find the manual at www.phidgets.com >> Programming.

Getting Started Guides

We have written Getting Started Guides for most of the languages that we support. If the manual exists for the language you want to use, this is the first manual you want to read. The Guides can be found at www.phidgets.com >> Programming, and are listed under the appropriate language.

API Guides

We maintain API references for COM (Windows), C (Windows/Mac OSX/Linux), Action Script, .Net and Java. These references document the API calls that are common to all Phidgets. These API References can be found under www.phidgets.com >> Programming and are listed under the appropriate language. To look at the API calls for a specific Phidget, check its Product Manual.

Code Samples

We have written sample programs to illustrate how the APIs are used.

Due to the large number of languages and devices we support, we cannot provide examples in every language for every Phidget. Some of the examples are very minimal, and other examples will have a full-featured GUI allowing all the functionality of the device to be explored. Most developers start by modifying existing examples until they have an understanding of the architecture.

Go to www.phidgets.com >> Programming to see if there are code samples written for your device. Find the language you want to use and click on the magnifying glass besides "Code Sample". You will get a list of all the devices for which we wrote code samples in that language.

API for the PhidgetAdvancedServo 1-Motor

We document API Calls specific to this product in this section. Functions common to all Phidgets and functions not applicable to this device are not covered here. This section is deliberately generic. For calling conventions under a specific language, refer to the associated API manual. For exact values, refer to the device specifications.

Structures

```
enum Phidget_ServoType {  
    PHIDGET_SERVO_DEFAULT = 1,  
    PHIDGET_SERVO_RAW_us_MODE,  
    PHIDGET_SERVO_HITEC_HS322HD,  
    PHIDGET_SERVO_HITEC_HS5245MG,  
    PHIDGET_SERVO_HITEC_805BB,  
    PHIDGET_SERVO_HITEC_HS422,  
    PHIDGET_SERVO_TOWERPRO_MG90,  
    PHIDGET_SERVO_HITEC_HS1425CR,  
    PHIDGET_SERVO_HITEC_HS785HB,  
    PHIDGET_SERVO_HITEC_HS485HB,  
    PHIDGET_SERVO_HITEC_HS645MG,  
    PHIDGET_SERVO_HITEC_HS815BB,  
};
```

PHIDGET_SERVO_USER_DEFINED

}

Used with the ServoType [get,set] functions. These are servos that have been quantified by Phidget Inc. for your convenience. The Default setting is included for historical reasons, so that the API will be backwards compatible by default. RAW_us_MODE is used for quantifying new servos, or simply when a microsecond based interface makes more sense than a degree based abstraction. USER_DEFINED should never be set directly with ServoType - this is returned when a custom servo type has been defined with setServoParameters.

Functions

int Count() [get]

Returns the number of servos this PhidgetAdvancedServo can control. In the case of the 1066, this will always return 1. This call does not return the number of servos actually connected.

double Acceleration(int ServoIndex) [get,set]

Acceleration is the maximum change in velocity the PhidgetAdvancedServo uses when speeding up / slowing down a servo.

- The range of valid Acceleration is bounded by AccelerationMax/AccelerationMin.
- There is a practical limit on how fast your servo can accelerate, based on load and the physical design of the motor.
- This property should always be set by the user as part of initialization. The value does not initialize to the value last set on the device.

double AccelerationMax(int ServoIndex) [get] : Constant

AccelerationMax is the upper limit to which Acceleration can be set. For the 1066, this will always return 320000.

double AccelerationMin(int ServoIndex) [get] : Constant

AccelerationMin is the lower limit to which Acceleration can be set. For the 1066, this will always return 19.53125.

double Velocity(int ServoIndex) [get]

Velocity returns the actual velocity that a particular servo is being driven at. A negative value means it is moving towards a lower position. This call does not return the actual physical velocity of the connected motor.

double VelocityLimit(int ServoIndex) [get, set]

Gets or sets the maximum absolute velocity that the PhidgetAdvancedServo controller will drive the servo. If it's changed mid-movement, the controller will accelerate accordingly. If the target position of the controller is near enough, then the VelocityLimit may never be reached.

- This property should always be set by the user as part of initialization.
- There is a practical limit on how fast your servo can rotate, based on the physical design of the motor.
- The range of VelocityLimit is bounded by VelocityMax/VelocityMin
- Note that when VelocityLimit is set to 0, the servo will not move.

double VelocityMax(int ServoIndex) [get] : Constant

VelocityMax is the absolute upper limit to which Velocity can be set. For the 1066, this will always return 6400.

double VelocityMin(int ServoIndex) [get] : Constant

VelocityMin is the absolute lower limit to which Velocity can be set. For the 1066, this will always return 0.

double Position(int ServoIndex) [get,set]

Position is used for both the target and actual position for a particular servo. If the servo is currently engaged and a new value is set, then the controller will continuously try to move to this position. Otherwise, this call will return the current position of the servo. This call does not return the actual physical position of the servo.

- The range of Position is bounded by PositionMin/PositionMax
- If the servo is not engaged, then the position cannot be read.
- The position can still be set while the servo is not engaged. Once engaged, the servo will snap to position if it is not there already.
- This property should be set by the user as part of initialization. If not, it will report the last value set on the device (unless the 1066 has been power-cycled).
- Get will return the last value as reported by the device. This means sets to this value will take a small amount of time to propagate.

double PositionMax(int ServoIndex) [get,set]

PositionMax is the upper limit to which Position can be set, and is initialized to 233. It can be used to prevent the controller from going beyond a servo's range of motion. A PhidgetException will be thrown if this is set above 233 or below PositionMin.

double PositionMin(int ServoIndex) [get,set]

PositionMin is the lower limit to which Position can be set, and is initialized to -22.9921875. It can be used to prevent the controller from going beyond a servo's range of motion. A PhidgetException will be thrown if this is set below -22.9921875 or above PositionMax.

double Current(int ServoIndex) [get]

Current returns the power consumption in amps for a particular servo. The value returned for a disconnected or idle servo will be slightly above zero due to noise.

bool SpeedRamping(int ServoIndex) [get,set]

SpeedRamping enables or disables whether the PhidgetAdvancedServo tries to smoothly control the motion of a particular servo. If enabled, then the 1066 will progressively send commands based on velocity, acceleration and position.

- This value is set to false when the 1066 is first connected. This property should be set by the user as part of initialization. If not, it will report the last value set on the device (unless the 1066 has been power-cycled).
- Get will return the last value as reported by the device. This means sets to this value will take a small amount of time to propagate.

bool Engaged(int ServoIndex) [get,set]

Enables a particular servo to be positioned. If this property is false, no power is applied to the motors. Note that when it is first enabled, the servo will snap to position, if it is not physically positioned at the same point.

Engaged is useful for relaxing a servo once it's reached a given position. If you are concerned about keeping accurate track of position, Engaged should not be disabled until Stopped = True.

- This value is set to false when the 1066 is first connected. This property should be set by the user as part of initialization. If not, it will report the last value set on the device (unless the 1066 has been power-cycled).
- Get will return the last value as reported by the device. This means sets to this value will take a small amount of time to propagate.

bool Stopped(int ServoIndex) [get]

Stopped returns false if the servo is currently in motion. It guarantees that the servo is not moving (unless you are moving it by hand), and that there are no commands in the pipeline to the servo. Note that virtually any API calls will cause Stopped to be temporarily false, even changing Acceleration or VelocityLimit on a stopped servo.

Phidget_ServoType ServoType(int ServoIndex) [get,set]

Gets / Sets the servo type for an index. There is a list of some common servos that have been predefined by Phidgets Inc. This sets the PCM range (range of motion), the PCM to degrees ratios used internally and the maximum velocity. This allows the degree based functions to be accurate for a specific type of servo.

Note that servos are generally not very precise, so two servos of the same type may not behave exactly the same. Specific servo motors, as well as servos not in the list, can be independently quantified by the user and set up with the `setServoParameters` function. This is detailed in the technical section.

void setServoParameters(int ServoIndex, double MinUs, double MaxUs, double Degrees, double VelocityMax)

Sets the parameters for a custom servo motor. MinUs is the minimum PCM in microseconds, MaxUs is the maximum PCM in microseconds, Degrees is the degrees of rotation represented by the given PCM range and VelocityMax is the maximum velocity that the servo can maintain, in degrees/second.

Quantifying a custom servo motor is detailed in the technical section.

Events

VelocityChange(int ServoIndex, double Velocity) [event]

An event issued when the velocity changes on a motor.

PositionChange(int ServoIndex, double Position) [event]

An event issued when the position changes on a motor.

CurrentChange(int ServoIndex, double Current) [event]

An event issued when the current consumed changes on a servo.

Technical Section

How RC Servo Motors Work

RC Servos are used for positioning applications. They were originally designed to control Remote Control airplanes and their low cost and high torque makes them very useful as an actuator in prototyping applications.

An RC Servo can be instructed to move to a desired position by the controller. Internally, it monitors the current position, and drives the motor as fast as it can until it reaches the desired position.

This is a very cheap and simple way to control a motor. It has some limitations - there is no way for the controller to know the current position and speed of the motor. Applications that want smooth movement suffer from the aggressive acceleration.



The PhidgetAdvancedServo 1-Motor

The PhidgetAdvancedServo is able to address some of these limitations. Instead of sending the desired position immediately, the PhidgetAdvancedServo sends a series of progressive positions according to acceleration and velocity parameters. In most applications, this dramatically smooths the operation of the servo, and allows reasonably precise control of position, velocity and acceleration.

The PhidgetAdvancedServo 1-Motor does not use an external supply and is powered through the USB, giving it an increased efficiency over externally powered modules due to the current being limited at 450 mA. To prevent the Phidget from resetting due insufficient voltage when using your own USB cable, make sure it is thick enough to supply a higher current. Also, the host might shut down the port if the power consumed exceeds what it can provide. A low power USB bus is limited to 100 mA.

Current Sense

The PhidgetAdvancedServo 1-Motor continuously measures the current consumed by the connected motor. The current roughly corresponds to torque, making it possible to detect several scenarios.

- By monitoring for no current, it's possible to determine if the servo is not connected. It may not be possible to distinguish between a servo at rest and a servo not attached.
- Stalled motors can be detected, by monitoring for the maximum current possible with your motor.
- The position limits of the servo can be programmatically determined by moving the servo until it stalls against the internal or external stops.

Limitations

The PhidgetAdvancedServo does not know the current position of the motor on its own. If your motor is free to move, and is not being driven beyond the physical limitations of the motor, the position returned to your application will be very close to the position of the motor.

Degree Abstraction

The PhidgetAdvancedServo software component uses degrees to specify position, velocity, and acceleration. The degree unit is translated into a pulse sent to the servo, but it's up to the servo to translate this signal into a particular position. This translation varies between servo models and manufacturers, and it is up to the user to set up their particular servo so that the degree abstraction matches up with reality.

Phidgets Inc. has quantified a number of common servo motors (see API section), which can be used with the `ServoType` function for to set these parameters. For servos not in this list, or to quantify a specific servo, the `setServoParameters` function can be used.

Defining a Custom Servo

Servos are driven with a PCM (Pulse Code Modulation) signal. To define a custom servo, you need to find the minimum and maximum PCM values that the servo supports.

The easiest way to do this is by bringing up the example and choosing RAW_us_MODE. This will display all positions in microseconds instead of degrees. Move the servo to both of its extremes, stopping when it hits the stops, then easing up a little (leave a few degrees of leeway), and record these values. You could also choose a specific range in degrees that you require and find the PCM values that correspond. Most servos operate within 500us - 2500us.

Record the degrees of rotation that this PCM range represents (using a protractor, for example).

Calculate the maximum velocity of your servo, in degrees/second. Most servos list their max speed in sec/60 degrees. convert this into degrees/second:

$$\text{Velocity(deg/sec)} = [(1 / (\text{sec}/60\text{deg})) * 60]$$

The actual maximum velocity of your servo may be slightly higher or lower, as velocity depends on voltage.

Feed these four values into the `serServoParameters` function to complete the set up. This should be done before any other function are called (in the attach event ideally).

Note that many servos can operate quite a bit outside of their rated ranges.

Degree Abstraction (historical model)

Historically, our degree abstraction has been based on the Futaba FP-S148 servo. This is the default abstraction used for the `PhidgetAdvancedServo`, to maintain backwards compatibility when the new model was added.

$$\text{PWM(ms)} = [(\text{degrees} + 23) * 4/375]$$

Using the PhidgetAdvancedServo with a Servo Motor

The `PhidgetAdvancedServo 1-Motor` has been designed to be used with a variety of RC servo motors independent of the motor-specific position, velocity and torque limits. Select a motor that suits your application and falls within the `PhidgetAdvancedServo` device specifications.

To use a servo motor, first select (in software) which attached motor the `PhidgetAdvancedServo` should affect. For the `PhidgetAdvancedServo 1-Motor`, it only has a single motor indexed at 0. Position, velocity and acceleration for the motor can then be controlled using the API calls documented in the next section. The software can also display a readout of the electrical current flowing through the motor.

Using the PhidgetAdvancedServo with Continuous Rotation Servos

A continuous rotation servo is a servo motor that has had its headgear-stop removed and potentiometer replaced by two matched-value resistors. This has the effect of allowing the motor to rotate freely through a full range of motion, but disables the motor's ability to control it's position.

When using the `PhidgetAdvancedServo` with a servo motor modified in this way, the position control in software becomes the motor's speed control. Because the two resistors that replace the motor's potentiometer are matched in value, the motor will always think its shaft is at center position. If the target position in software is set to center, the motor will believe it has achieved the target and will therefore not rotate. The further away from center the target position is set to, the faster the motor will rotate (trying to reach that position, but never doing so). Changing the value above or below center changes the direction of rotation.

Using the 1066 with Electronic Speed Controllers (ESCs)

Electronic Speed Controllers are commonly used in RC hobby planes, cars, helicopters. It's a controller that accepts a PWM input signal, and controls a motor based on that signal. The ESC accepts power from an external source, normally a battery pack.

ESCs can be controlled by the 1066, but the vast majority of ESCs on the market will attempt to power the 1066 and USB bus if they are plugged in without modification. In a hobby RC system, the ESC is responsible for regulating some of the battery current down to ~5V, and supplying it to the radio receiver. An ESC designed to power the receiver will advertise that it has a Battery Eliminator Circuit (BEC). When you plug an ESC into the 1066, the 1066 is acting as the radio receiver. The 1066 was not designed to be powered by the devices it controls, and strange system behaviour will result if a device tries to power it. If the center pin from the 3-wire servo connector between the 1066 and the ESC is disconnected, the BEC on the ESC will not be able to power the 1066, and the voltage regulator will not fail.

How the ESC interprets the PWM signal and controls the motor is a function of the ESC. Higher end ESCs can be configured based on the application.

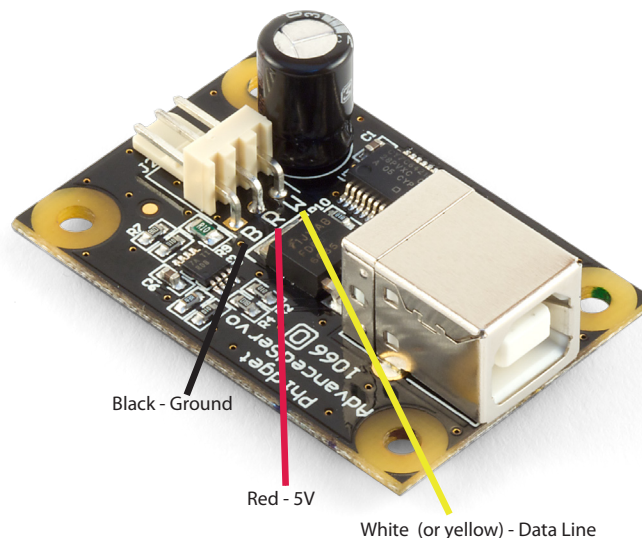
The hobby RC market has transitioned to Brushless DC Motors (BLDC). As you select an ESC, watch that the battery voltage input matches that of your system, and the type of motor controlled is what you have. Brushed DC and Brushless DC Motors are completely different, and require different controllers.

Wiring layout is critical with ESCs. The currents to the motor and on the ground return can be enormous. If these currents end up travelling back through USB cables, the system will not be stable. Some ESCs are optically isolated (OPTO) - a big advantage that reduces interference.

Connecting your servo motor to the 1066

The pins on the 1066 are labelled B R W on the board:

- B for Black is the Ground
- R for Red is 5V
- W for White (or Yellow depending on your servo motor) is the Data Line



Product History

Date	Board Revision	Device Version	Comment
July 2009	0		Product Release

Support

Call the support desk at 1.403.282.7335 9:00 AM to 5:00 PM Mountain Time (US & Canada) - GMT-07:00

or

E-mail us at: support@phidgets.com