

User Manual

MP167E, valid for Q-845.140

PMMSc/KSch, 1/18/2019

PI

Q-845

Q-Motion® SpaceFAB



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1 About this Document

This manual contains information on the intended use of the Q-845.140 SpaceFAB (hereafter referred to as "Q-845").

It assumes that the reader has a fundamental understanding of basic servo systems as well as motion control concepts and applicable safety procedures.

1.1 Symbols and Typographic Conventions

The following symbols and typographic conventions are used in this user manual:

CAUTION



Dangerous situation

If not avoided, the dangerous situation will result in minor injury.

- Actions to take to avoid the situation.

NOTICE



Dangerous situation

If not avoided, the dangerous situation will result in damage to the equipment.

- Actions to take to avoid the situation.

INFORMATION

Information for easier handling, tricks, tips, etc.

The following symbols and markings are used in the user manuals of PI:

Symbol	Meaning
1.	Action consisting of several steps whose sequential order must be observed
2.	
➤	Action consisting of one or several steps whose sequential order is irrelevant
▪	List item
S. 5	Cross-reference to page 5
SVO?	Command line or command from PI's General Command Set (GCS) (example: command to get the servo mode)

RS-232



Operating element labeling on the product (example: socket of the RS-232 interface)

Warning sign on the product which refers to detailed information in this manual.

1.2 Figures

For better understandability, the colors, proportions and degree of detail in illustrations can deviate from the actual circumstances. Photographic illustrations may also differ and must not be seen as guaranteed properties.

1.3 Downloading Manuals

INFORMATION

If a manual is missing or problems occur with downloading:

- Contact our customer service department (p.).

INFORMATION

For products that are supplied with software (CD in the scope of delivery), access to the manuals is protected by a password. Protected manuals are only displayed on the website after entering the password.

The password is included on the CD of the product.

For products with CD: Identify the password

1. Insert the product CD into the PC drive.
2. Switch to the Manuals directory on the CD.
3. In the Manuals directory, open the Release News (file including **releasenews** in the file name).
4. Find the user name and the password in the section "User login for software download" in the Release News.

Downloading manuals

1. Open the website **www.pi.ws**.
2. If access to the manuals is protected by a password:
 - a) Click **Login**.
 - b) Log in with the user name and password.
3. Click **Search**.

4. Enter the product code up to the period (e.g., P-882) or the product family (e.g., PICMA® Bender) into the search field.
5. Click **Start search** or press the Enter key.
6. Open the corresponding product detail page in the list of search results:
 - a) If necessary: Scroll down the list.
 - b) If necessary: Click **Load more results** at the end of the list.
 - c) Click the corresponding product in the list.
7. Scroll down to the **Downloads** section on the product detail page.

The manuals are displayed under **Documentation**.
8. Click the desired manual and save it to the hard disk of your PC or to a data storage medium.

2 Safety

2.1 Intended Use

The Q-845.140 SpaceFAB (hereafter referred to as “Q-845”) is a laboratory device in accordance with DIN EN 61010-1. It is intended to be used in interior spaces and in an environment that is free of dirt, oil and lubricants.

Based on its design and realization, the Q-845 is intended for positioning, adjusting and shifting of loads in six axes at various velocities.

The intended use of the Q-845 is only possible in connection with the controller which coordinates all motions of the Q-845.

2.2 Safety Precautions

CAUTION



Risk of crushing by moving parts!

There is a risk of minor injuries from crushing between the motion platform and the base of the Q-845.

- Use protective structures to keep limbs away from areas in which they could be caught by moving parts.
- Observe the safety distances in accordance with DIN EN ISO 13857 when installing protective structures.



Figure 1: Risk of crushing between motion platform and base of the Q-845.140

NOTICE



Damage from collisions during the reference move!

The Q-845 moves unpredictably during a reference move. The approach of the reference position always takes place via the negative or positive hard stop of the linear drives. Soft limits that have been set for the motion platform of the Q-845 with the `NLM` and `PLM` commands are ignored during the reference move. In addition, **no** collision check or prevention takes place. As a result, collisions are possible between the Q-845, the load to be moved, and the surroundings. Collisions can damage the Q-845, the load to be moved, and the surroundings.

- Make sure that no collisions between the Q-845, the load to be moved, and the surroundings are possible during the reference move of the Q-845.
- Make sure that the installation space is sufficient to allow motion along the complete travel range of each axis.
- Do not place any objects in areas where they can be caught by moving parts during the reference move.
- After a successful reference move, supply a command for the corresponding target position in order to return to the reference position (default: zero position) from any given position.

Do **not** start a new reference move, but send a command line as follows:

```
MOV X 0 Y 0 Z 0 U 0 V 0 W 0.
```

NOTICE



Damage due to impermissibly high forces and torques!

Impermissibly high forces and torques that are applied to the motion platform (see Figure 2) can damage the Q-845.140.

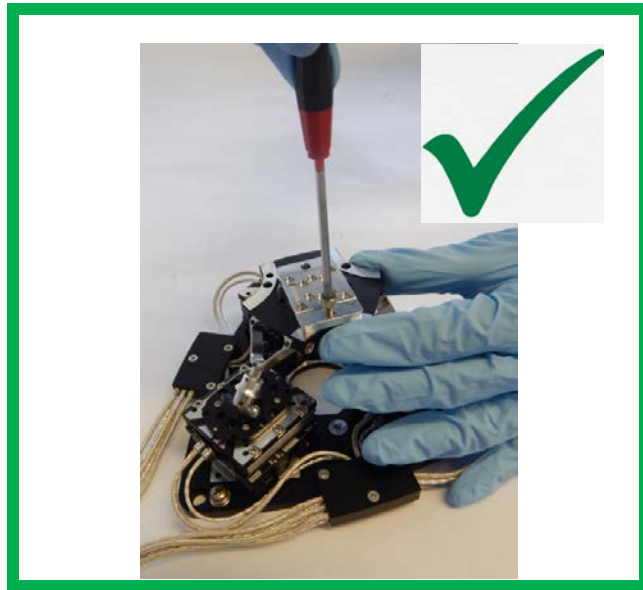
- Do **not** exceed the maximum permissible forces and torques that are allowed to act on the motion platform (see Figure 3 for the coordinate system):
 - Maximum force in Z: **10 N**
 - Maximum force in X and Y: **0.5 N**
 - Maximum torque in Rx, Ry, and Rz: **0.5 Nm**
- Hold the Q-845.140 externally on the base only



Figure 2: Motion platform of the Q-845



Figure 3: Coordinate system for maximum forces and torques



NOTICE



Damage to Q-845.140 without original packaging during transport!

An unallowable mechanical load on the Q-845.140 due to transport without original packaging can damage the Q-845.140.

- Only ship the Q-845.140 in its original packaging.

The Q-845.140 is built according to state-of-the-art technology and recognized safety standards. Improper use can result in personal injury and/or damage to the Q-845.140.

- Only use the Q-845.140 for its intended purpose, and only use it if it is in a good working order.
- Read the user manual.
- Immediately eliminate any faults and malfunctions that are likely to affect safety.

The operator is responsible for the correct installation and operation of the Q-845.140.

2.3 Organizational Measures

User manual

- Always keep this user manual available with the Q-845.140.
- Add all information from the manufacturer to the user manual, for example supplements or Technical Notes.
- If you give the Q-845.140 to other users, also include this user manual as well as other relevant information provided by the manufacturer.

- Only use the device on the basis of the complete user manual. Missing information due to an incomplete user manual can result in minor injury and damage to equipment.
- Only install and operate the Q-845.140 after you have read and understood this user manual.

Personnel qualification

The Q-845.140 may only be installed, started up, operated, maintained and cleaned by authorized and appropriately qualified personnel.

3 Product Description

3.1 Product View

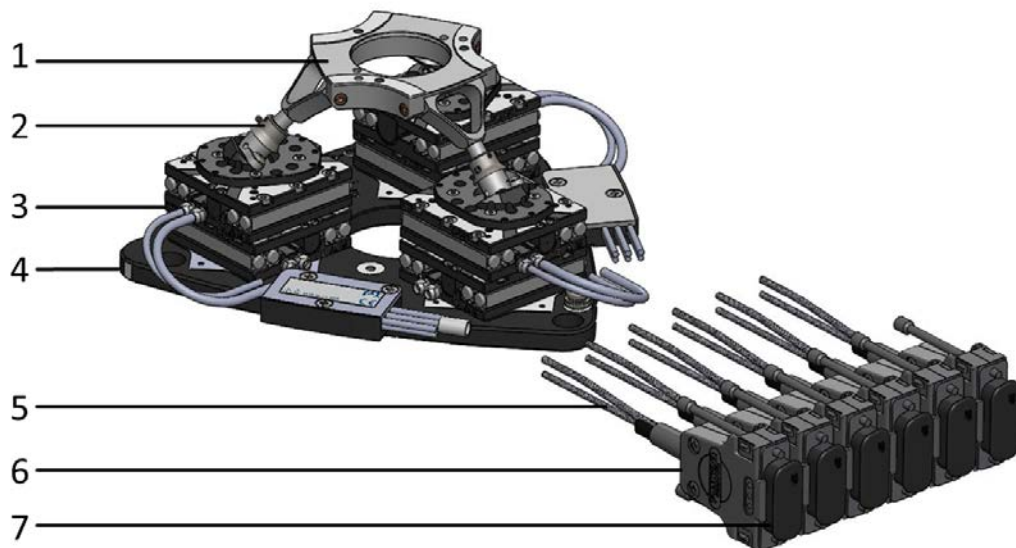


Figure 4: Product view

1. Motion platform
2. Strut
3. XY stage
4. Base plate
5. Cable
6. Connector (sub-D 15-pin (m))
7. ESD protection: ESD protective cap

3.2 Scope of Delivery

The following table contains the scope of delivery of the Q-845.

The scope of delivery of the controller is listed in the user manual of the controller.

Order Number	Items
Q-845.140	6D positioning system
Screw set:	
Q845B0004	Mounting accessories: <ul style="list-style-type: none">▪ 3x M6x10 hex-head cap screws ISO 4762 A2▪ 2 x dowel pins A2 3 m6 x 10 ISO 8734
Documentation:	
MP167E	User manual for the SpaceFAB
Packaging material, consisting of:	
	<ul style="list-style-type: none">▪ Outer box▪ Inner box▪ Foam packaging for the sides of the inner box▪ Internal cushion, bottom▪ Internal cushion, cover▪ Pallet

3.3 Suitable Controller

Controller	Description
C-886	Digital controller for Q-845 SpaceFAB

PC software is included in the scope of delivery of the controllers from PI. The operation of the controllers is described in the corresponding user manuals.

3.4 Technical Features

3.4.1 Reference Point Switch

The Q-845 features a reference point switch without direction sensing.

4 Unpacking and Repacking for Transport

The Q-845.140 is delivered in a special packaging with adapted foam inserts.



NOTICE



Impermissible mechanical load!

An impermissible mechanical load can damage the Q-845.


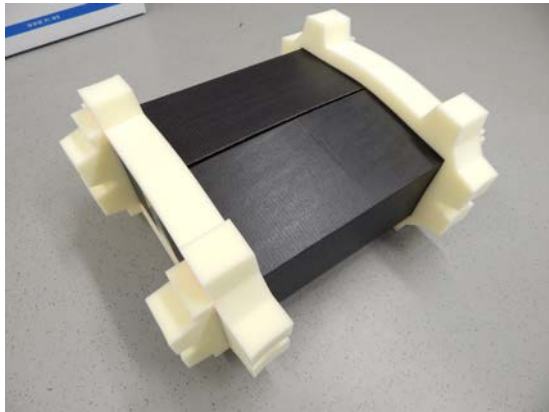
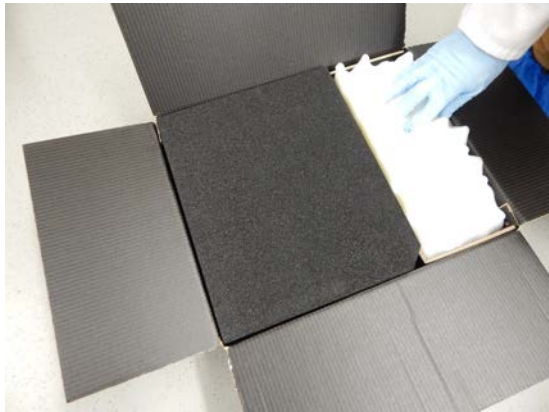
- Only send the Q-845 in the original packaging.
- Only hold the Q-845 by the base plate

Un- packing steps	Repacking steps	Figure	Comment
1	10		<ul style="list-style-type: none"> ➤ Keep all packaging materials in case the product needs to be transported again later. ➤ Only ship the Q-845 in its original packaging.
2	9		<ul style="list-style-type: none"> ➤ Open the outer box

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Un-packing steps	Repacking steps	Figure	Comment
3	8		<ul style="list-style-type: none">➤ Lift the inner box with the foam packaging out of the outer box
4	7		<ul style="list-style-type: none">➤ Remove the foam packaging
5	6		<ul style="list-style-type: none">➤ Open the inner box

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Un-packing steps	Repacking steps	Figure	Comment
6	5		➤ Remove the foam cover
7	4		➤ Remove the foam cover
8	3		➤ Lift the Q-845 by holding the base plate and take it out of the foam insert

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Un-packing steps	Repacking steps	Figure	Comment
9	2		<ul style="list-style-type: none">➤ Remove the bag➤ Compare the contents against the items covered by the contract and against the packing list. If parts are incorrectly supplied or missing, contact PI immediately.➤ Inspect the Q-845 for signs of damage. If you notice signs of damage, contact PI immediately.
10	1		<ul style="list-style-type: none">➤ Hold the Q-845 at the base plate only

5 Installation

5.1 General Notes on Installation

The Q-845 can be mounted in any orientation.

NOTICE



Impermissible mechanical load and collisions!

Impermissible mechanical load and collisions between the Q-845, the load to be moved and the environment can damage the.

- Hold the Q-845 at the base plate only.
- Avoid high forces and torques on the motion platform during installation.
- Ensure an uninterruptible power supply in order to prevent an unintentional deactivation of the Q-845 system and resulting unintentional position changes of the Q-845.
- Make sure that no collisions between the Q-845, the load to be moved and the environment are possible in the working space of the Q-845.

5.2 Determining the Permissible Load

The limit values in the following table are for orientation. They only apply when the center of mass is at the origin of the XYZ coordinate system (0,0,0).

	Servo mode switched on for SpaceFAB – Max. load capacity		Servo mode switched off for SpaceFAB – Max. holding force	
Mounting position of the base plate	Mounted horizontally	Mounted in any orientation	Mounted horizontally	Mounted in any orientation
Q-845.140	1 kg	0.5 kg	1 kg	0.5 kg

5.3 Mounting the Q-845 on a Surface

NOTICE



Impermissible mechanical load!

An impermissible mechanical load can damage the Q-845.

- Only hold the Q-845 by the base plate, see figure of unpacking step 10 on p. 15.

NOTICE



Warping of the base plate!

Incorrect mounting can warp the base plate. Warping of the base plate reduces the accuracy.

- Mount the Q-845 on an even surface. The recommended flatness of the surface is 5 µm.

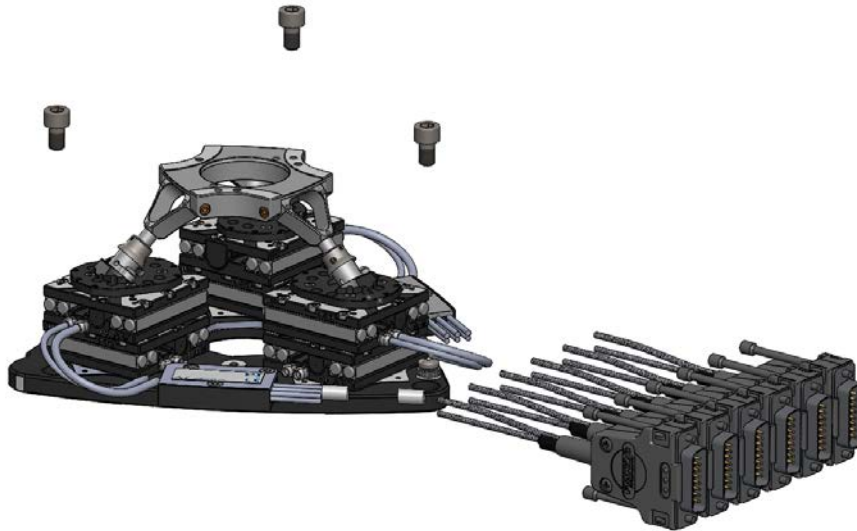


Figure 5: Product view with mounting accessories

Requirements

- ✓ You have read and understood the General Notes on Installation (p. 16).

Tools and accessories

- For the dimensions of the Q-845 and the position and depth of the M6 countersunk holes, see "Dimensions" (p. 30).
- You have provided a suitable surface:
 - Optional: at least 2 mounting holes with $\varnothing 3$ mm H7 for alignment are provided.
 - 3 mounting holes for M6 screws are provided.
 - The flatness of the surface is 5 µm.
- Screw set Q845B0004, included in delivery (p. 11):
 - 3 x M6x10 hex-head cap screws ISO 4762
 - 2 x dowel pins A2 3 m6 x 10 ISO 8734
- Suitable tools

Mounting the Q-845

1. Optional: Align the Q-845 on the surface using the mounting holes at the bottom of the Q-845 intended for this purpose.
2. Mount the Q845 using the 3 countersunk holes intended for this purpose, see figure above or the dimensional drawings on p. 30.

5.4 Affixing the Load onto the Q-845

NOTICE



Impermissible mechanical load and collisions!

Impermissible mechanical load and collisions between the Q-845, the load to be moved, and the environment can damage the Q-845.

- Avoid high forces and torques on the motion platform during installation.
- Make sure that no collisions between the Q-845, the load to be moved and the environment are possible in the work space of the Q-845.

NOTICE



Screws that are too long!

The Q-845 can be damaged by excessively long screws.

- When selecting the screw length, observe the thickness of the motion platform or the depth of the mounting holes together with the load to be mounted.
- Only use screws that do not project under the motion platform after being screwed in.
- Only mount the Q-845 and the load on the mounting fixtures (holes) intended for this purpose.

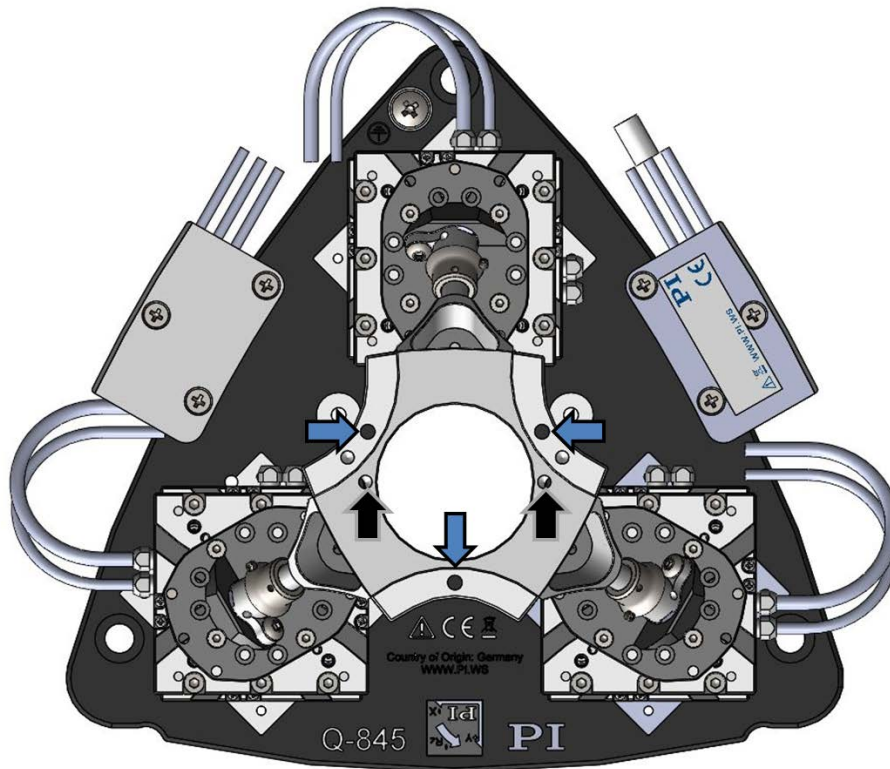


Figure 6: Top view of Q-845, black arrows mark where to align the load, blue arrows mark where to mount the load onto the motion platform

Requirements

- ✓ You have read and understood the General Notes on Installation (p. 16).
- ✓ You have determined the permissible load and the work space of the Q-845 (p. 16).
- ✓ You have designed the load and the environment of the Q-845 so that the permissible load of the Q-845 is observed and no collisions can occur.

Tools and accessories

- A suitable load with mounting holes that correspond to the following mounting holes:
 - Optional: 2 suitably long alignment pins for holes with $\varnothing 3\text{mm H7} \times 2/3$
 - 3 suitably long M4 screws
- Suitable tools

Affixing the Load

1. Optional: align the load onto the Q-845 using the mounting holes intended for this purpose, see the figure above
2. Mount the load onto the Q-845 using the mounting holes intended for this purpose, see the figure above.

5.5 Connecting the Q-845 to the Protective Earth Conductor

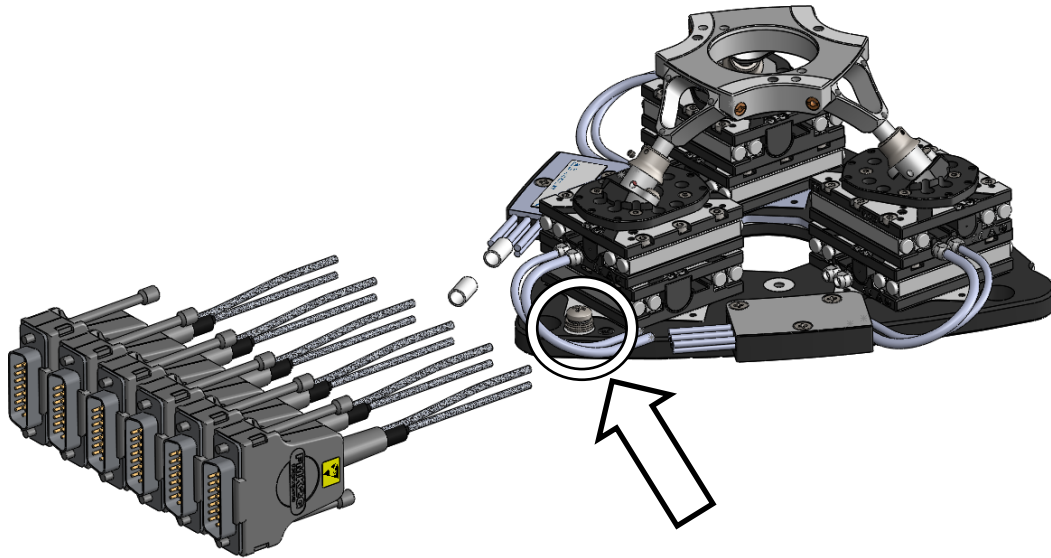


Figure 7: Q-845 with protective earth connection

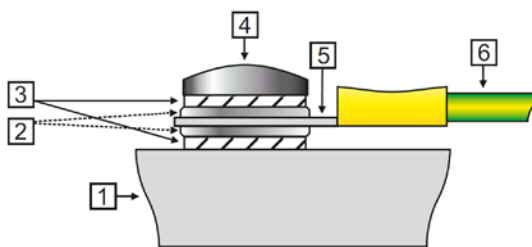


Figure 8: Recommended mounting of the protective earth conductor (profile view)

1. Base of the Q-845
2. Flat washer
3. Safety washer
4. Screw
5. Cable lug
6. Protective earth conductor

Requirements

- ✓ You have read and understood the general notes on installation (p. 16).
- ✓ The Q-845 is **not** connected to the controller.

Tools and accessories

- Suitable protective earth conductor: Cross-sectional area of the cable $\geq 0.75 \text{ mm}^2$
- M4 protective earth screw set supplied and already inserted for connecting the protective earth conductor
- Suitable screwdriver

Connecting the Q-845 to the protective earth conductor

1. If necessary, attach a suitable cable lug to the protective earth conductor.
2. Use the M4 screw (together with the washers and self-locking washers) to affix the cable lug of the protective earth conductor to the protective earth connection of the Q-845 as shown in the profile view.
3. Tighten the M4 screw with a torque of 1.2 Nm to 1.5 Nm.
4. Make sure that the contact resistance at all connection points relevant for connecting the protective earth conductor is $<0.1 \Omega$ at 25 A.

5.6 Connecting the Q-845 to the Controller

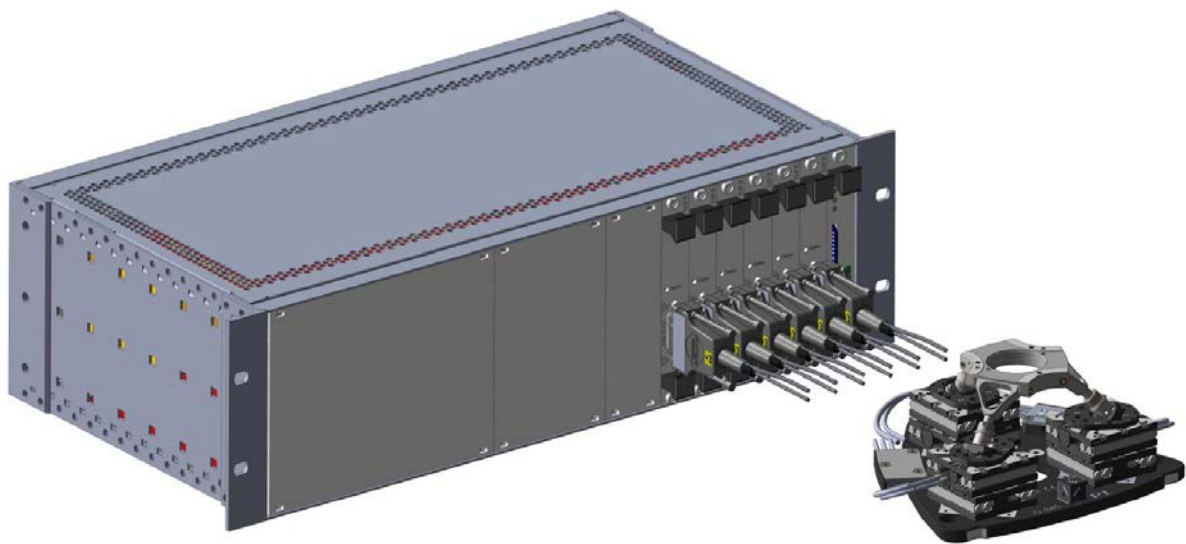


Figure 9: Connect the Q-845 to the controller

Requirements

- ✓ You have read and understood the general notes on installation (p. 16).
- ✓ You have installed the controller.
- ✓ You have read and understood the user manual of the controller.
- ✓ The controller is switched off.

Connecting the Q-845 to the Controller

1. Remove the ESD protection from all connections of the Q-845.
2. Connect the Q-845 and the controller to each other:
Use the integrated screws to secure the connections against accidental disconnection.

6 Start-Up and Operation

6.1 General Notes on Start-Up

CAUTION



Risk of crushing by moving parts!

There is a risk of minor injuries from crushing between the motion platform and the base of the Q-845.

- Use protective structures to keep limbs away from areas in which they could be caught by moving parts.
- Observe the safety distances in accordance with DIN EN ISO 13857 when installing protective structures.

NOTICE



Damage from collisions during the reference move!

The Q-845 moves unpredictably during a reference move. The approach of the reference position always takes place via the negative or positive hard stop of the linear drives. Soft limits that have been set for the motion platform of the Q-845 with the **NLM** and **PLM** commands are ignored during the reference move. In addition, **no** collision check or prevention takes place. As a result, collisions are possible between the Q-845, the load to be moved, and the surroundings. Collisions can damage the Q-845, the load to be moved, and the surroundings.

- Make sure that no collisions between the Q-845, the load to be moved, and the surroundings are possible during the reference move of the Q-845.
- Make sure that the installation space is sufficient to allow motion along the complete travel range of each axis.
- Do not place any objects in areas where they can be caught by moving parts during the reference move.
- After a successful reference move, supply a command for the corresponding target position in order to return to the reference position (default: zero position) from any given position.

Do **not** start a new reference move, but send a command line as follows:

```
MOV X 0 Y 0 Z 0 U 0 V 0 W 0.
```

NOTICE



Overheating during continuous operation!

The highest velocity is achieved at maximum operating frequency; however, the Q-845 can overheat during continuous operation as a result.

- Observe the recommended operating time according to the operating frequency in step mode (p. 29).
- Ensure sufficient ventilation at the place of installation.

NOTICE



Incorrect configuration of the controller!

The configuration data used by the controller (e.g. geometrical data and servo-control parameters) must be adapted to the Q-845. If incorrect configuration data is used, the Q-845 can be damaged by uncontrolled motions or collisions. The configuration data is adapted before delivery.

- Check whether the controller matches the Q-845. A label on the rear panel of the controller indicates for which Q-845 the controller is intended.
- When you have established the communication via TCP/IP, send the `CST?` command. The response shows the Q-845 to which the controller is adapted.
- Only operate the Q-845 with a controller whose configuration data is adapted to the Q-845.

NOTICE



Damage from collisions!

Collisions can damage the Q-845, the load to be moved and the environment.

- Make sure that no collisions between the Q-845, the load to be moved and the environment are possible in the work space of the Q-845.
- Do not place any objects in areas where they can get caught by moving parts.
- If the controller malfunctions, stop the motion immediately.

NOTICE



Damage from unintentional position changes!

The limit value for the load of the Q-845 determined with the simulation program is only valid when the servo mode is switched on for the axes of the motion platform. The maximum holding force when the servo mode is switched off is based on the self-locking of the actuators in the struts of the Q-845.

The maximum holding force with the servo mode switched-off is lower than the limit value when the servo mode is switched on (see "Data Table" on p. 27).

When the actual load of the Q-845 exceeds the maximum holding force based on the self-locking of the actuators, unintentional position changes of the Q-845 can occur in the following cases:

- Switching off the controller
- Rebooting the controller
- Switching off the servo mode for the axes of the Q-845

As a result, collisions are possible between the Q-845, the load to be moved, and the environment. Collisions can damage the Q-845, the load to be moved, or the environment.

- Make sure that the actual load of the motion platform of the SpaceFAB does not exceed the maximum holding force based on the self-locking of the actuators before you switch off the servo mode, reboot or switch off the controller.

NOTICE



Damage from uncontrolled motion of the Q-845!

In the following cases, the velocity and acceleration of the motion platform of the Q-845 are not specified by the trajectory generator of the controller:

- The **Trajectory Source** parameter (ID 0x19001900) has the value 1.
- The **Trajectory Source** parameter has the value 0, and the Q-845 (axes X, Y, Z, U, V, W) is still moving while a new motion command is sent. The previous target position is thereby overwritten without the velocity and acceleration of the motion platform of the Q-845 being recalculated.

The platform of the Q-845 then moves on an undefined path. On this undefined path, collisions with the environment of the Q-845 are possible. Collisions can damage the Q-845, the load to be moved and the environment.

When the **Trajectory Source** parameter has the value 1:

- Only set target positions whose distance from each other is maximally as large as the value of the **Path Control Step Size (mm)** parameter (ID 0x19001504) with consecutive **MOV** commands.

When the **Trajectory Source** parameter has the value 0:

- Avoid sending new target positions while the Q-845 (axes X, Y, Z, U, V, W) is still moving.
- If new target positions have to be sent while the Q-845 is still moving (axes X, Y, Z, U, V, W): Only use motion commands to set target positions that maximally deviate from the current position by the value of the **Path Control Step Size (mm)** parameter (ID 0x19001504).

INFORMATION

The communication interfaces of the controller (user interface, TCP/IP) are active at the same time. Commands are executed in the order that the complete command lines arrive. The simultaneous use of several communication interfaces can cause problems with the PC software, however.

- Always only use one interface of the controller.

INFORMATION

When switched on or rebooted, the controller automatically switches on the servo mode for all axes. When the servo mode is switched off for the axes of the motion platform of the Q-845 (X, Y, Z, U, V, W), it is automatically switched on when the reference move is started.

INFORMATION

For the axes of the motion platform of the Q-845 (X, Y, Z, U, V, W), motions can only be commanded after a successful reference move (also referred to as "initialization"). A common reference move is always performed for the axes of the motion platform of the Q-845 (X, Y, Z, U, V, W).

6.2 Starting Up the Q-845

Requirements

- ✓ You have read and understood the General Notes on Start-Up.
- ✓ You have correctly installed the Q-845, i.e. you have mounted the Q-845 on a surface and affixed the load to the Q-845 according to the instructions in "Installation" (p. 16).
- ✓ You have read and understood the user manual of the controller.
- ✓ You have read and understood the manual of the PC software as, for example, PIMikroMove.
- ✓ The controller and the required PC software have been installed. All connections on the controller have been set up (see user manual of the controller).

Accessories

- Controller
- PC with suitable software (see user manual of the controller)

Starting up the Q-845

1. Connect the Q-845 to the controller (see user manual of the controller).
2. Start up the controller (see user manual of the controller).
3. Start up the software (see software manual).

6.2.1 Performing a Reference Move

INFORMATION

Soft limits that have been set for the motion platform of the Q-845 with the **NLM** and **PLM** commands are ignored during the reference move.

The linear drives of the Q-845 have optical reference point switches **without** direction sensing.

The approach of the reference position always takes place via the negative or positive hard stop of the linear drives.

After a reference move each axis of the Q-845 is in center position.

See the user manual of the controller for more information about the **FRF** command and reference moves.

7 Maintenance

NOTICE



Misalignment from loosening screws!

The Q-845 is maintenance-free and precisely aligned.

- Only loosen screws as mentioned in this document.
- Do not loosen any other screws.

8 Troubleshooting

Problem	Possible Causes	Solution
Unexpected Q-845 behavior.	<ul style="list-style-type: none">▪ Cable broken▪ Connector or soldered joints loosened	<ul style="list-style-type: none">➤ Check the data transmission and power supply cables.➤ Replace the cables by cables of the same type and test the function of the Q-845.➤ Contact our customer service department.
The Q-845 does not achieve the specified accuracy.	Warped base plate	➤ Mount the Q-845 on an even surface. The recommended flatness of the surface is 5 µm.
	Increased wear due to small motions over a long period of time	➤ Carry out a maintenance run over the entire travel range.

If the problem with your Q-845 is not listed in the table or cannot be solved as described, contact our customer service department.

9 Customer Service

For inquiries and orders, contact your PI sales engineer or send us an e-mail (service@pi.de).

If you have questions concerning your system, have the following information ready:

- Product codes and serial numbers of all products in the system
- Firmware version of the controller (if present)
- Version of the driver or the software (if present)
- Operating system on the PC (if present)

The latest versions of the user manuals are available for download (p. 5) on our website.

10 Technical Data

10.1 Data Table

	Q-845.140	Unit	Tolerance
Motion and positioning			
Active axes	X, Y, Z, θ_x , θ_y , θ_z		
Integrated sensor	Incremental linear encoder		
Travel range* in X, Y	±7	mm	
Travel range* in Z	±5	mm	
Rotation range* in θ_x , θ_y	±7	°	
Rotation range* in θ_z	±8	°	
Sensor resolution	1	nm	
Min. incremental motion in X, Y	6	nm	typ.
Min. incremental motion in Z	20	nm	typ.
Min. incremental motion in θ_x , θ_y , θ_z	0.9	μrad	typ.
Unidirectional repeatability in X, Y	±30	nm	typ.
Unidirectional repeatability in Z	±35	nm	typ.
Unidirectional repeatability in θ_x	±20	μrad	typ.
Unidirectional repeatability in θ_y	±10	μrad	typ.
Unidirectional repeatability in θ_z	±6	μrad	typ.
Backlash in X, Y	40	nm	typ.
Backlash in Z	60	nm	typ.
Backlash in θ_x , θ_y	35	μrad	typ.
Backlash in θ_z	20	μrad	typ.
Max. velocity in X, Y, Z	5	mm/s	typ.
Max. velocity in θ_x , θ_y , θ_z	50	mrads	typ.




	Q-845.140	Unit	Tolerance
Mechanical properties			
Stiffness in X, Y	1	N/μm	
Stiffness in Z	2	N/μm	
Load capacity in X, Y	5	N	max.
Load capacity in Z (base plate horizontal)	10	N	max.
Holding force, power off (base plate horizontal / any orientation)	20 / 10	N	max.
Permissible torque in θ _x , θ _y , θ _z	0.5	Nm	max.
Drive type	Piezoelectric inertia drive		
Miscellaneous			
Operating temperature range	0 to 40	°C	
Connection	6 x Sub-D 15 (m)		
Material	Stainless steel, aluminum		
Mass	1.9	kg	±5%
Mass without cables and connectors	1.2	kg	±5%
Cable length	2	m	±10 mm

Technical data specified at 20±3°C.

* The travel ranges of the individual coordinates (X, Y, Z, θ_X , θ_Y , θ_Z) are interdependent. The data for each axis in this table shows its maximum travel range, where all other axes and the pivot point are at the reference position. If the other linear or rotational coordinates are not zero, the available travel may be less.

10.2 Maximum Ratings

The Q-845 stage is designed for the following operating data:

Maximum operating voltage	Maximum operating frequency	Maximum power consumption
		
48 V	20 kHz	30 W

10.3 Operating Time

The operating time and the operating frequency in step mode affect the lifetime of the stage. In order to prevent overheating and high wear, the operating time with the given operating frequency and 100 % duty cycle must not exceed the values given in the following table.

Operating frequency in Hz ¹	Operating time ² / 48 V, ±0.6 A
20000	10 s (max.)
10000	20 s (max.)
5000	60 s (max.)
≤ 1000	120 s (max.)

¹ For the relevant parameters, see the user manual of the PI controller used.

² With 100 % duty cycle without heat dissipation

10.4 Ambient Conditions and Classifications

The following ambient conditions and classifications must be observed for the Q-845:

Area of application	For indoor use only
Maximum altitude	2000 m
Relative humidity	Highest relative humidity 80 % for temperatures up to 31 °C, non-condensing Decreasing linearly to 50 % relative humidity at 40 °C, non-condensing
Storage temperature	-20 °C to 70 °C
Transport temperature	-20 °C to 70 °C
Overvoltage category (acc. to EN 60664-1:2007 / VDE 0110-1)	II
Protection class (acc. to EN 61140 / VDE 0140 1)	I
Degree of pollution (acc. to EN 60664 1:2007 / VDE 0110 1)	1
Degree of protection (acc. to IEC 60529)	IP20

10.5 Dimensions

All figures show the SpacFAB in the reference position. The reference position equals the center position of all axes.

Dimensions in mm. Note that the decimal places are separated by a comma in the drawings.

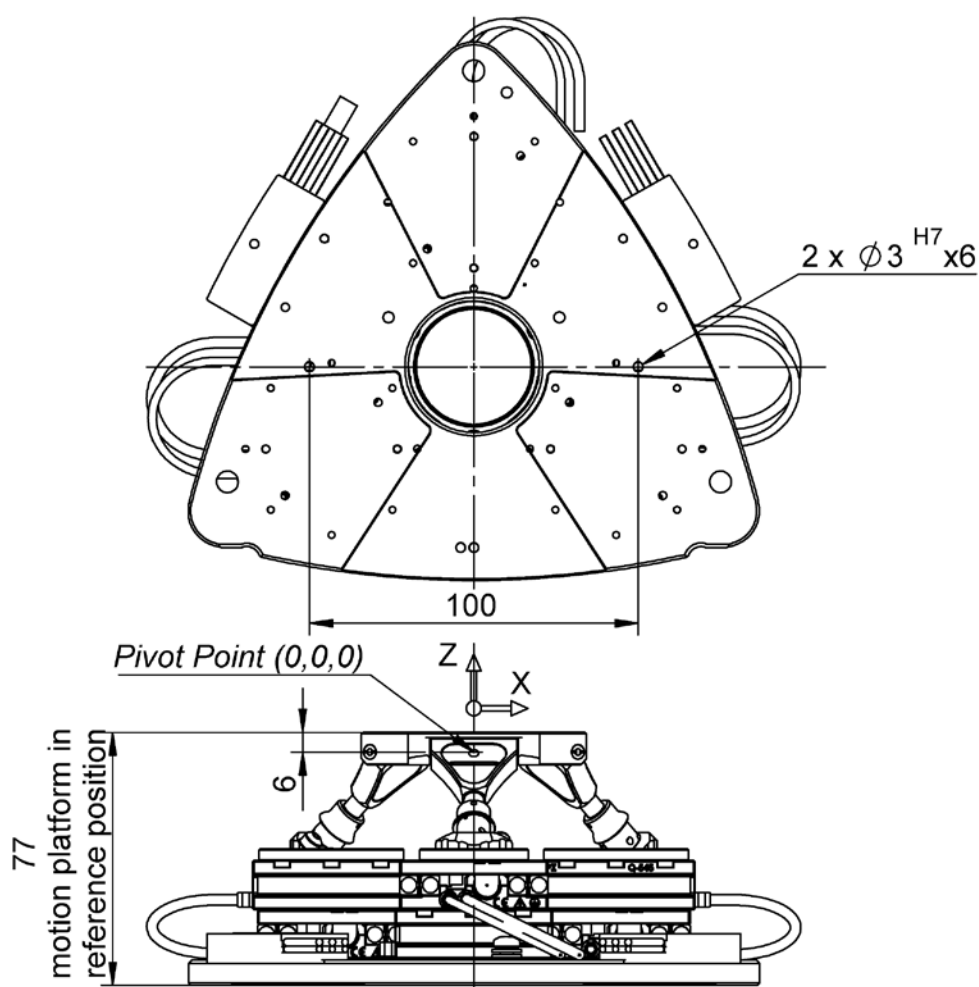


Figure 10: Top: View at bottom side, bottom: lateral view of Q-845.140

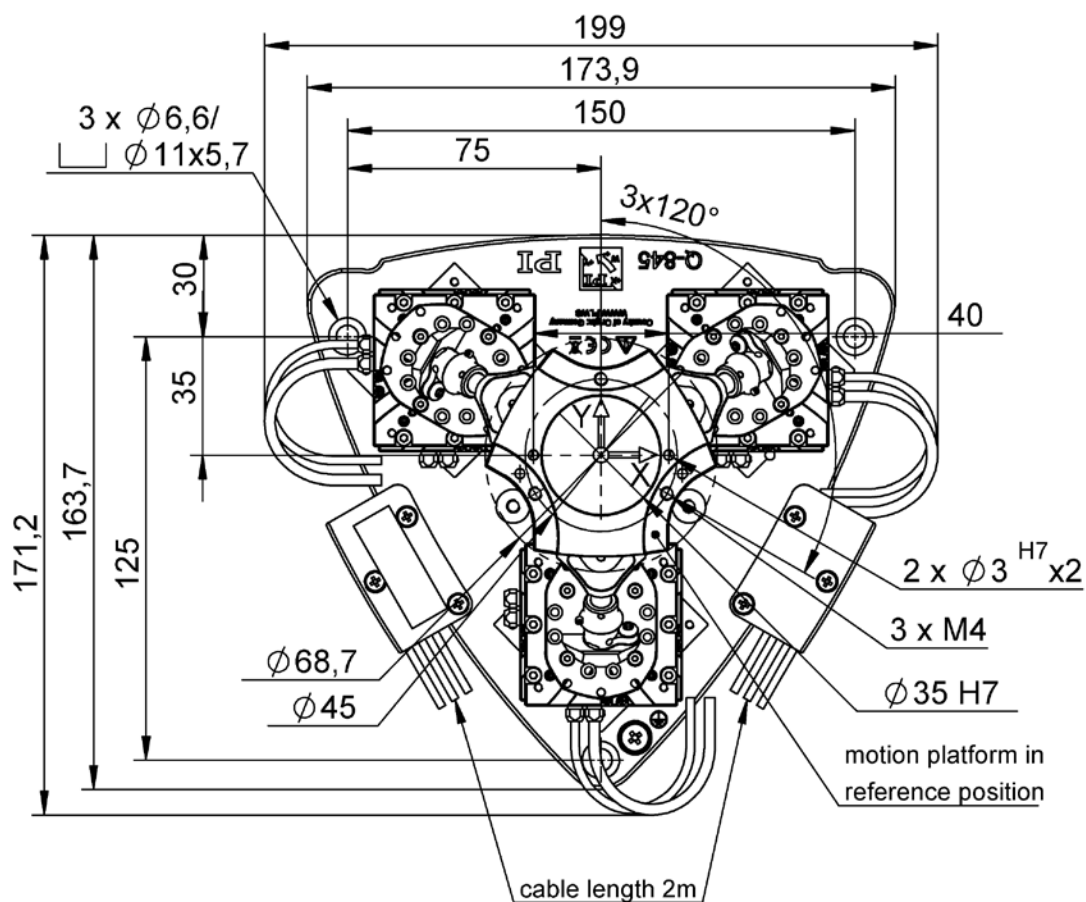


Figure 11: Top view of Q-845.140

10.6 Pin Assignment

10.6.1 Sub-D 15 (m) Controller Connection

The Sub-D 15 (m) connector transmits the signals of the drive, the signals of the sensor and of the ID chip.

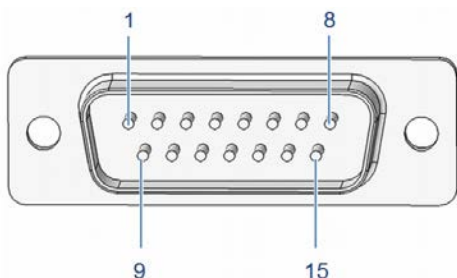


Figure 12: Sub-D 15 (m) connector

Pin	Signal ¹	Function	Direction
1	REF -	Reference signal differential (-)	Output
2	Motor (-)	Motor signal differential (-)	Input
3	Motor (+)	Motor signal differential (+)	Input
4	V _{DD}	Supply voltage (+5 V)	Input
5	-	-	-
6	ID chip data ²	ID chip data	Output
7	SIN -	Encoder A (-)	Output
8	COS -	Encoder B (-)	Output
9	Motor (-)	Motor signal differential (-)	Input
10	GND	GND	GND
11	Motor (+)	Motor signal differential (+)	Input
12	-	-	-
13	REF +	Reference signal differential (+)	Output
14	SIN +	Encoder A (+)	Output
15	COS +	Encoder B (+)	Output

11 Old Equipment Disposal

In accordance with EU law, electrical and electronic equipment may not be disposed of in EU member states via the municipal residual waste.

Dispose of your old equipment according to international, national, and local rules and regulations.

In order to fulfil the responsibility as the product manufacturer, PI miCos GmbH undertakes environmentally correct disposal of all old PI miCos equipment made available on the market after 13 August 2005 without charge.

Any old PI miCos equipment can be sent free of charge to the following address:

PI miCos GmbH

Freiburger Strasse 30

79427 Eschbach, Germany



12 EC Declaration of Conformity

For the Q-845, an EC Declaration of Conformity has been issued in accordance with the following European directives:

Low Voltage Directive

EMC Directive

RoHS Directive

The applied standards certifying the conformity are listed below.

Safety (Low Voltage Directive): EN 61010-1

EMC: EN 61326-1

RoHS: EN 50581