

# **DRV8884 Evaluation Module (EVM) User's Guide**

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This document is provided with the DRV8884 customer EVM as a supplement to the DRV8884 ([SLVSDA5](#)) data sheet. This user's guide details the hardware implementation of the EVM.

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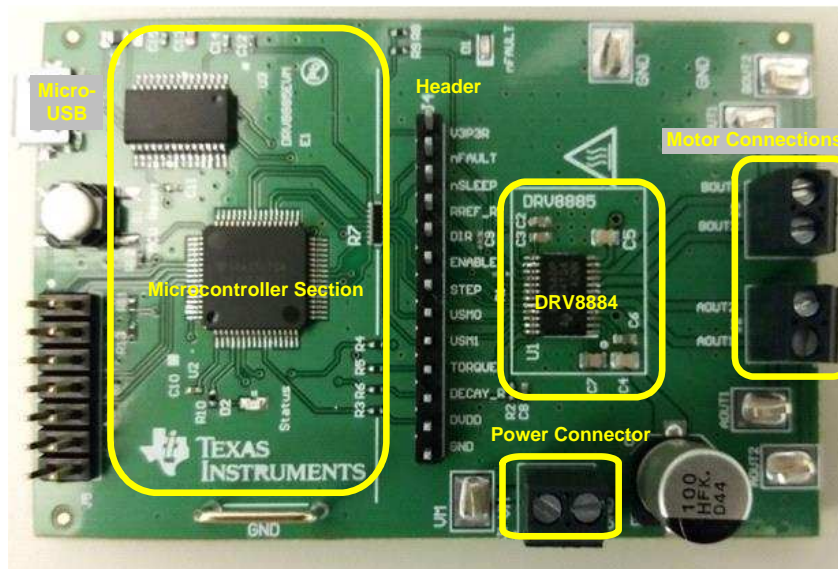
## 1 Introduction

The DRV8884 customer EVM is a platform revolving around the DRV8884, a medium voltage dual H-bridge driver and highly configurable power stage. This device has been optimized to drive a single bipolar stepper with up to 16 degrees of internally generated microstepping.

The EVM houses an MSP430 microcontroller and a USB interface chip. The USB chip allows for serial communications from a PC computer where a Microsoft® Windows® application is used to schedule serial commands. These commands can be used to control each signal of the device, and drive the stepper motor by issuing the step commands at the desired rate.

The microcontroller firmware operates using internal index mode.

This user's guide details the operation of the EVM, as well as the hardware configurability of the EVM.



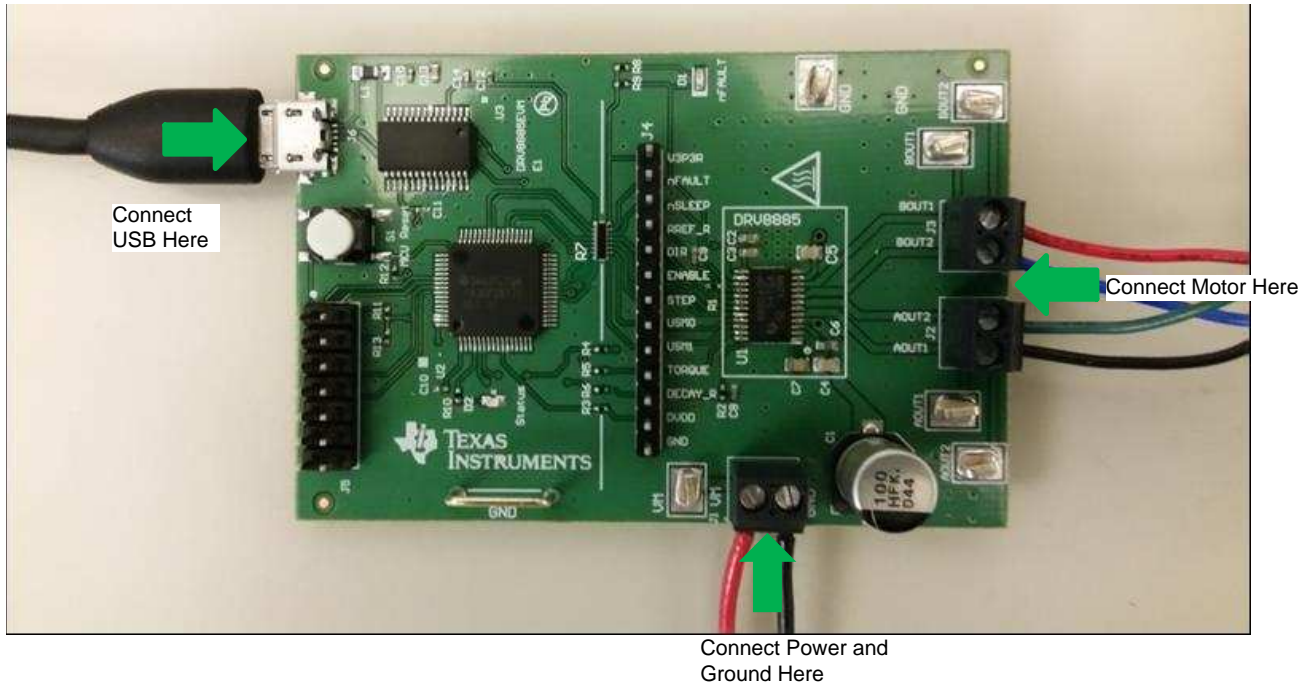
**Figure 1. Top View of Typical Board Configuration (EVM Provided may Vary)**

## 2 Connectors

The DRV8884EVM offers access to motor voltage (VM) power rail through a terminal block (J1). A set of test clips in parallel with the terminal block allows for the monitoring of the input power rail.

User must apply VM according to data sheet recommended parameters.

**NOTE:** VDD for the microcontroller is derived from the micro USB connector.



**Figure 2. Connections**

### 3 Test Points

A 0.100 inch pitch header connector (J4) provides access to every device signal in the event a different microcontroller is to be employed. To disconnect the internal MSP430 microcontroller, remove resistors R3, R4, R5, R6, and resistor pack R7. [Table 1](#) describes the connections available on the J4 header. Each header pin is labeled on the evaluation module, and connects to a similarly named pin of the DRV8884.

**Table 1. Connections to DRV8884 Using External Microcontroller**

HEADER LABEL	DESCRIPTION
V3P3R	3.3 V after 0-Ω resistor
nFAULT	Fault output
nSLEEP	Sleep mode input
RREF_R	Chopping current selection
DIR	DIR, direction input
ENABLE	ENABLE, stepper motor enable
STEP	STEP, step input
USM0	M0, step mode
USM1	M1, step mode
TORQUE	TRQ, Output current scale
DECAY_R	Decay Mode select after 0-Ω resistor
DVDD	Internal supply voltage to set DAC voltage
GND	Ground

### 4 Jumpers

There are no jumpers on the DRV8884EVM.

### 5 Motor Outputs

Two motor connectors are provided. Connectors J2 and J3 are available as shown in [Figure 1](#).

## 6 Operation of the EVM

1. Install the drivers and GUI. Refer to [Appendix A](#) for instructions.
2. Connect the wires of the stepper motor to terminals AOUT1, AOUT2, BOUT1, and BOUT2.
3. Connect the VM power supply, but do not apply power at this step.
4. Connect the USB cable between the PC and the EVM. After the USB is connected to the EVM, the Status LED will begin to blink.
5. Open the GUI. The GUI can be found in the start menu at Texas Instruments → DRV8884EVM → DRV8884EVM vX.Y , where X and Y are the revision numbers. If a shortcut was created, the shortcut can also be double clicked to open the GUI. It may take up to 30 seconds to establish the connection. If the connection is not established, select the COM port under the *Options* menu. The BaudRate is 9600.
6. Apply desired voltage (8 to 37 V) to the VM and GND connections.
7. Configure the current settings, step mode, decay mode, and torque as desired as:

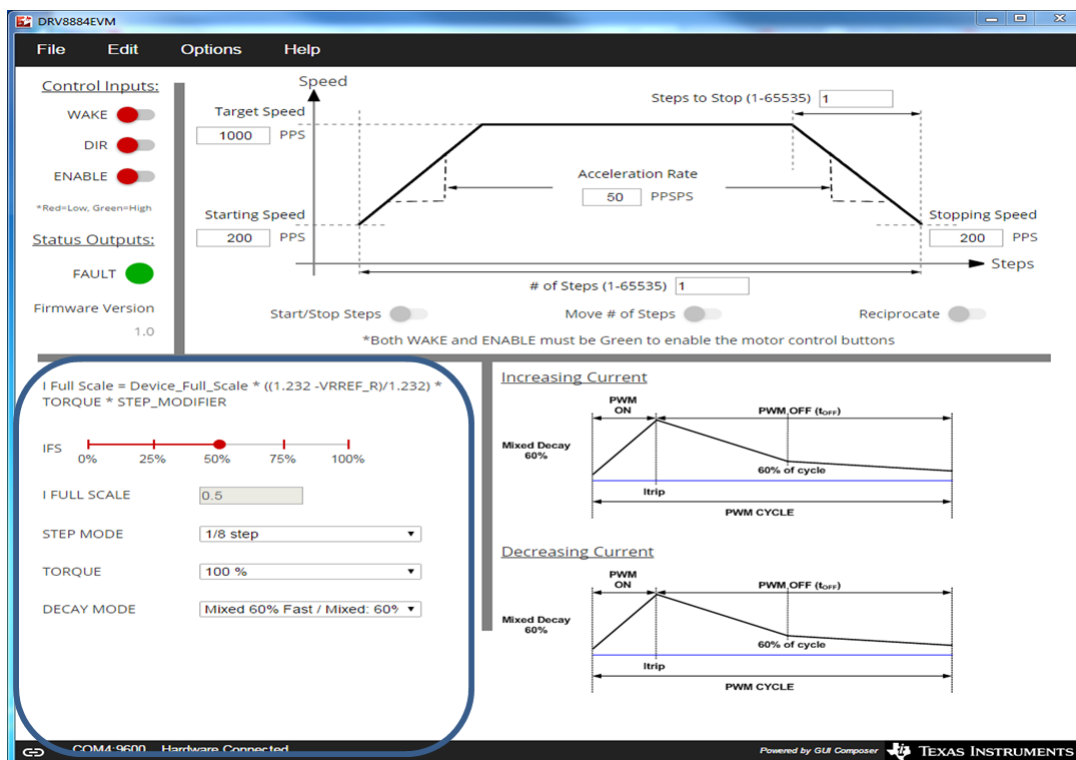


Figure 3. GUI at startup

- (a) The current is calculated using the  $V_{REF}$  slider, the *Sense* resistor value, the *Torque* setting, and the *Step* mode setting using [Equation 1](#).

$$I_{FS} = 1 \text{ A} \left( \frac{1.232 - V_{RREF\_R}}{1.232} \right) \times \text{TORQUE} \times \text{StepModifier}$$

where **StepModifier** is 0.71 for full step and 1.0 for other STEP MODE settings (1)

- (b) The number 1.232 is based on the maximum current allowed using the configuration. If  $V_{RREF} = 0$  V, the maximum current is 1.0 A. The 12-bit DAC channel 1 is connected to the DRV8884 analog input RREF through a 30-k $\Omega$  series resistor. The DAC voltage begins at 1.232 V (0%) and ends at 0V (100%).

8. Wake and Enable the device for operation.
  - (a) After setting up the control signals for the DRV8884, enabling the DRV8884 requires selecting both the WAKE and ENABLE toggle buttons. When toggled, WAKE or ENABLE switches between red to green.
  - (b) The WAKE toggle button, which controls the nSLEEP pin, is used to wake the DRV8884. The ENABLE toggle button, which controls the ENABLE pin, is used to enable the DRV8884 outputs.
  - (c) A message which states that “\*Both WAKE and ENABLE must be Green to enable the motor control buttons” is visible until both the WAKE and ENABLE toggle buttons are activated. After these two toggle buttons have been activated, the message disappears and the Start/Stop and Move Steps toggle buttons become available.
  - (d) If the WAKE or ENABLE toggle buttons are selected during motor operation, the motor is immediately stopped and the STEP control signal from the microcontroller is reset.

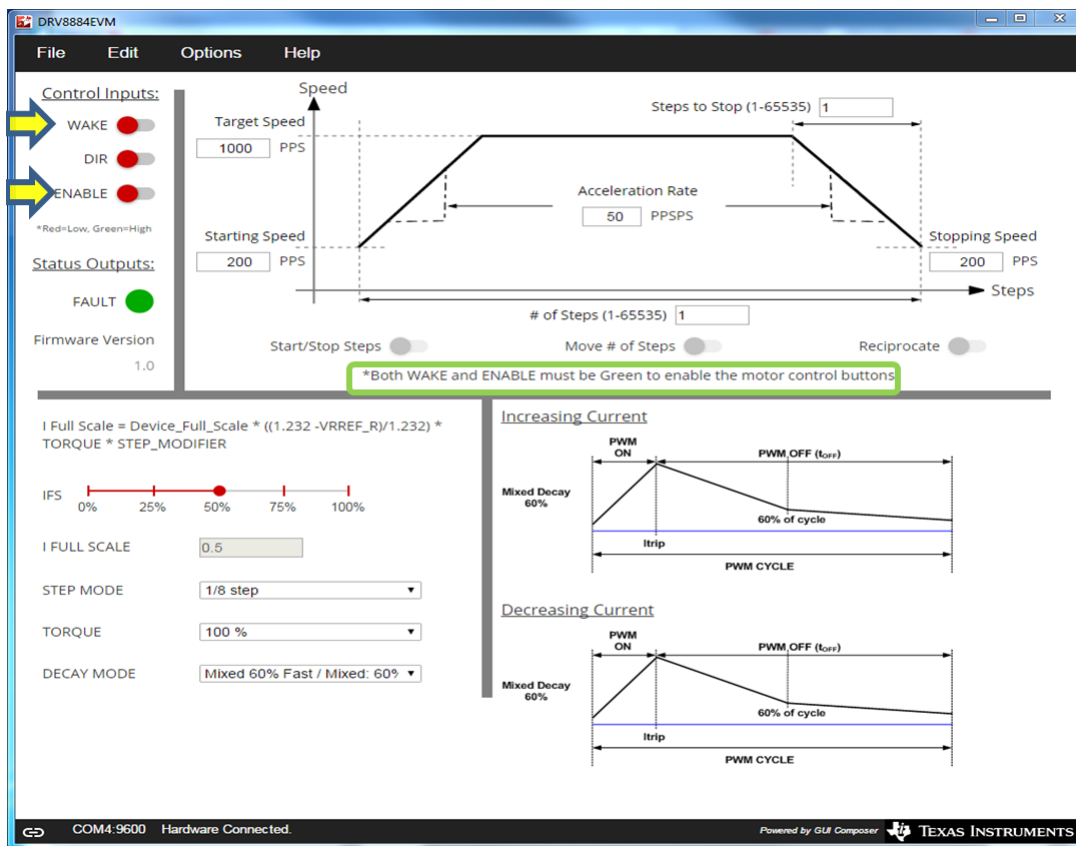


Figure 4. Wake and Enable Toggle Buttons

9. The DRV8884 EVM is now awake and can be commanded to turn the motor. This is done by either selecting *Start/Stop Steps*, *Move # of Steps*, or *Reciprocate*.
  - The *Start/Stop Steps* toggle button is used to run the motor indefinitely. The motor will accelerate to the target speed and run until the *Start/Stop Steps* toggle button is selected. When the *Start/Stop Steps* toggle button is selected, the red button will change to green, and the *Move Steps* and *Reciprocate* toggle buttons will be disabled.
  - The *Move Steps* toggle button is used to allow movement of an exact number of steps. When the *Move Steps* toggle button is selected, *Move Steps* will turn green, and the *Start/Stop Steps* and *Reciprocate* toggle buttons are disabled until the number of steps have completed.
  - The *Reciprocate* toggle button is a special case of the *Move Steps*. When selected, the motor will advance the specified number of steps in the direction initially set by the control inputs. After a short pause, the motor will then advance the same number of steps in the opposite direction. This sequence is repeated until the *Reciprocate* toggle button is selected.
  - When the *Reciprocate* toggle button is selected, *Reciprocate* will turn green, and the *Start/Stop Steps* and *Move # of Steps* buttons are disabled until the *Reciprocate* toggle button is set to red, and the number of steps have completed.

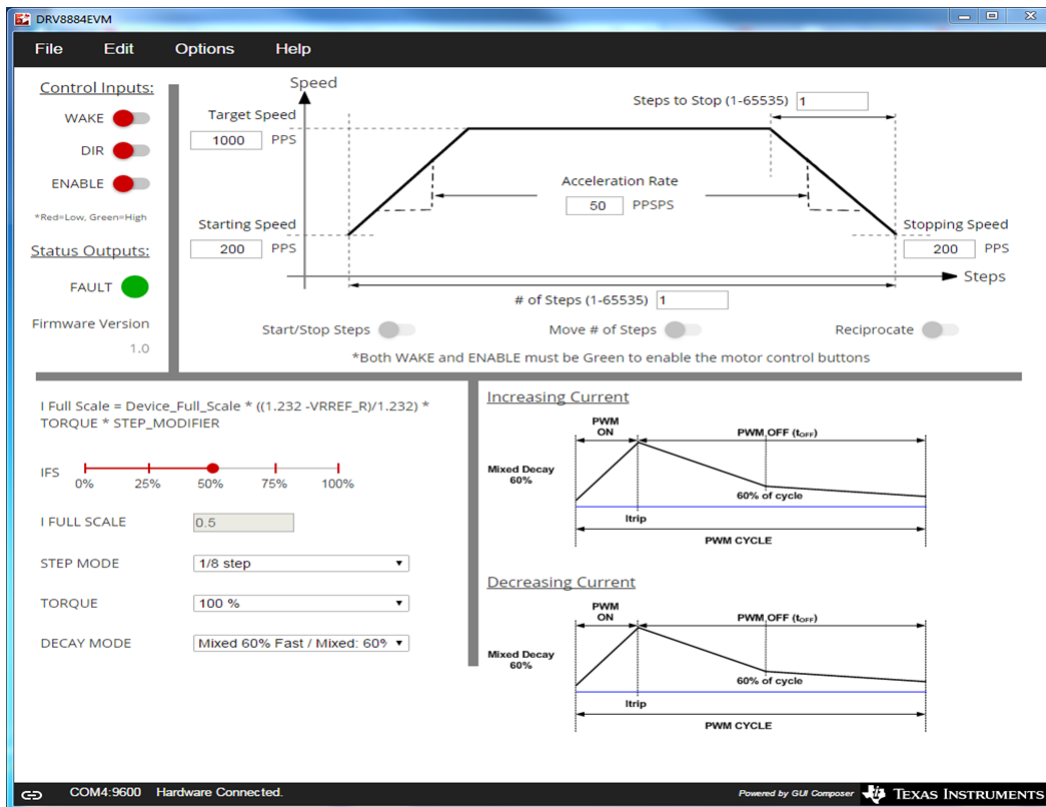
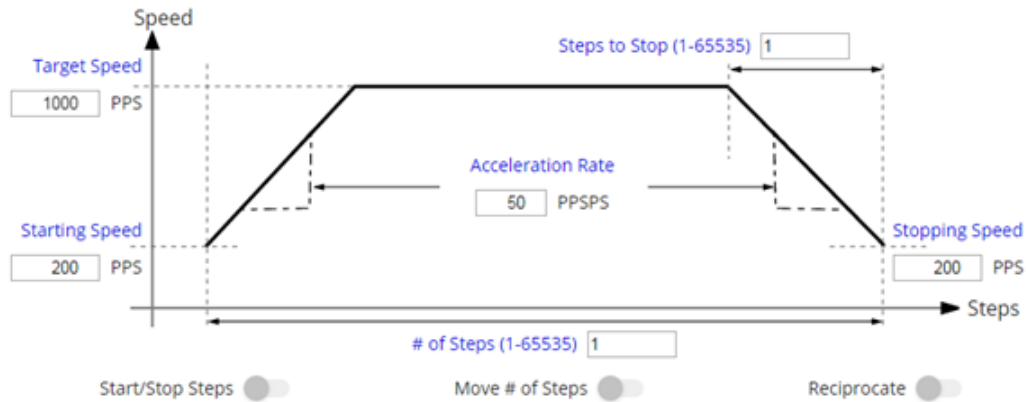


Figure 5. Reciprocate Toggle Button

As an extra precaution, the motor can be stopped by selecting either the *WAKE* or *ENABLE* toggle buttons. When either is selected, the STEP commands are stopped, and the motor control buttons are disabled. To re-enable motor control, set the *WAKE* and *ENABLE* toggle buttons to green.

## 7 Motion Control Frame (Includes Start/Stop Steps and Move Steps)

The GUI has an area which offers access to a series of useful stepper control algorithms. This area allows for determining the best current settings during running at various speeds and when holding torque is applied.



\*Both WAKE and ENABLE must be Green to enable the motor control buttons.

**Figure 6. Motor Motion Profile**

Motor motion only happens by using an acceleration profile which is detailed later in this section. A detailed explanation of each stepper control is provided in the following sections.

This frame allows the configuration and running of the stepper with the direction as specified by the *DIR* checkbox, with the current decay mode as specified under the *Decay Mode* checkbox and the microstepping resolution as specified under the *Step Mode* drop-down box.

The *Motion Control* frame gathers user information regarding stepping rate or motor speed. An acceleration profile is employed to start at a programmable speed and increase stepping rate until reaching the programmable desired speed.

An internal 8-MHz timer is used to measure time and generate the steps in a timely manner. The GUI will send the information to the microcontroller as PPS, and the microcontroller will transform it into the respective clock cycles needed for the timer to generate accurate STEP pulse timing.



### 7.1 Start/Stop Steps

The acceleration profile is coded inside the microcontroller to accept both the starting speed PPS and target speed PPS as a clock cycle number. When the start steps command is issued (*Starts/Steps* button is selected), the PWM timer generates steps at a rate specified by the start speed PPS parameter.

When accelerating or decelerating, PPS is adjusted every 32 ms based on the integer value of PPSPS / 32 ms. If a non-zero value of PPSPS is entered, a minimum value of 1 is used. The step rate is increased by the calculated value until the target speed is reached.

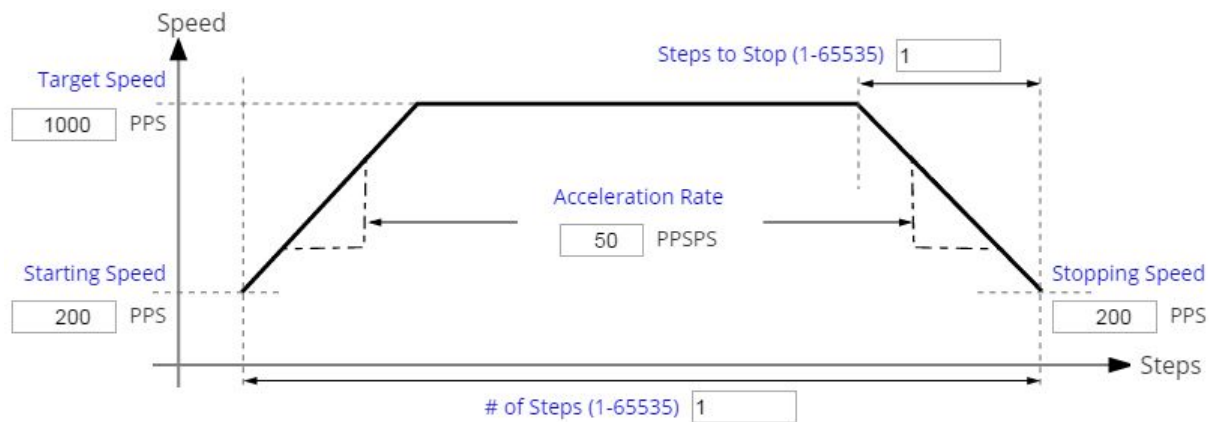
**NOTE:** If the starting speed is greater than or equal to the target speed, the acceleration rate is set to 0. This will prevent further speed changes until the motor is stopped, and new starting and target speeds are entered. TI recommends setting the starting speed to one-half the target speed to avoid this scenario.

The very same start steps command computes how frequent automatic speed updates are issued and a second timer is used to change the speed according to the programmed acceleration rate profile.

When the target speed PPS is reached, the acceleration profile ends and the motor continues running until the stop stepper command is issued (*Start/Stop Steps* button is selected again). When the stepper is commanded to stop, the controller does exactly as it did while accelerating, but in reverse to decelerate until the stop speed PPS is reached, in which case the motor fully stops.

A second motor actuation is provided by the *Move # of Steps* and *Reciprocate* commands in which a programmed number of steps are issued and then the motor stopped. The acceleration and deceleration profiles work similarly as before, except when the deceleration starts and when the motor actually stops are a function of the *Steps to Stop* and deceleration rate parameters.

Figure 7 shows the acceleration profile and the role each parameter plays during speed computation.



\*Both WAKE and ENABLE must be Green to enable the motor control buttons.

**Figure 7. Acceleration Profile**

## 7.2 Move Steps

When moving the stepper a certain number of steps, use the move steps function. Parameters from the other frames are reused as explained previously. Two new parameters are added to properly control the limited number of steps actuation.

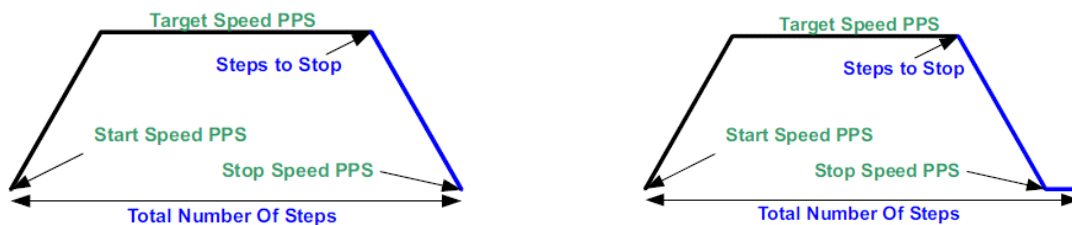
**Number of Steps**—Number of steps the controller issues.

**Steps to Stop**—The controller is continuously monitoring the step being issued and when the current step is equal to the steps to stop parameter, a deceleration profile is issued. If *Steps to Stop* is larger than the number of steps, then the motor stops abruptly and without undergoing a deceleration profile.

When a deceleration profile is issued, the controller decreases the speed until reaching the stop speed value. If the number of steps parameter is met before the deceleration profile is complete, then the motor stops at the current speed. If the stop speed is met before all the number of steps is issued, then the motor rotates at the stop speed value until all the steps are executed.

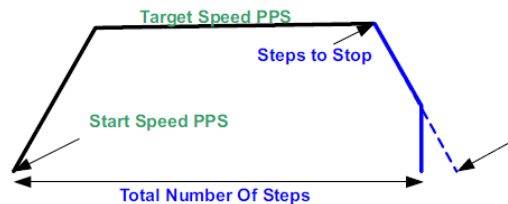
Ideally, the system should be tuned to resemble the case in which the controller executes all the commanded steps at a speed as close as possible to the stop speed. In the event this is not possible, due to the particular parameters being chosen, stopping the motor at a speed very close to the stop speed is often sufficient to ensure good motion quality and application performance.

Figure 8 shows the three conditions possible when stopping and what action results.



1. Motor reaches stop speed at the stop speed.

2. Motor reaches stop speed before the stop speed is reached.



3. Motor runs out of steps before reaching stop speed.

**Figure 8. Stop Conditions**

## 8 EVM Documentation

The EVM schematics, layout, and bill of materials (BOM) are provided in the hardware file ([SLVC657](#)). The GUI, USB drivers, and MSP430F2617 source code are provided in the software file ([SLVC658](#)).

## A.1 Driver and GUI Installation Instructions

### 1. Installing the FTDI Driver:

In many cases, connecting the EVM to the computer automatically installs the FTDI driver.

If necessary, download the driver from the software file. Unzip the software file and install the USB driver:

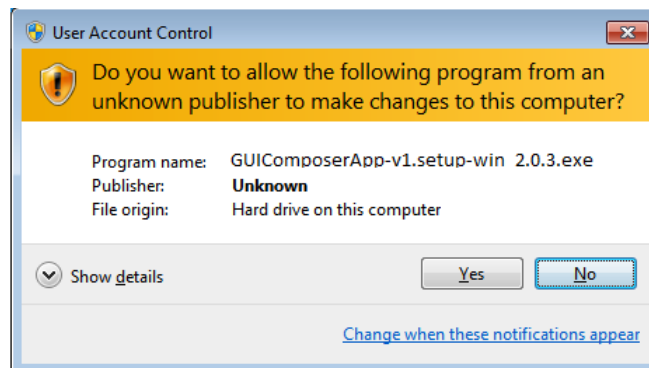
- If using Windows XP, run \USB driver\CDM v2.10.00 WHQL Certified.exe.
- If using Windows 7, go to folder \USB driver\, right-click *CDM v2.10.00 WHQL Certified.exe*, select *Properties*, go to the *Compatibility* tab, check *Run this program in compatibility mode for*, select *Windows XP (Service Pack 2)*, and click *OK*. Then, run *CDM v2.10.00 WHQL Certified.exe*, and click *Yes* on the popup window.

### 2. Installing the GUI:

Locate the file *DRV8884EVM\_installer.zip* in the Application folder. Unzip the file to any location, then double click the file *GUIComposerApp-v1.setup-win\_2.0.3.exe* in the unzipped folder.

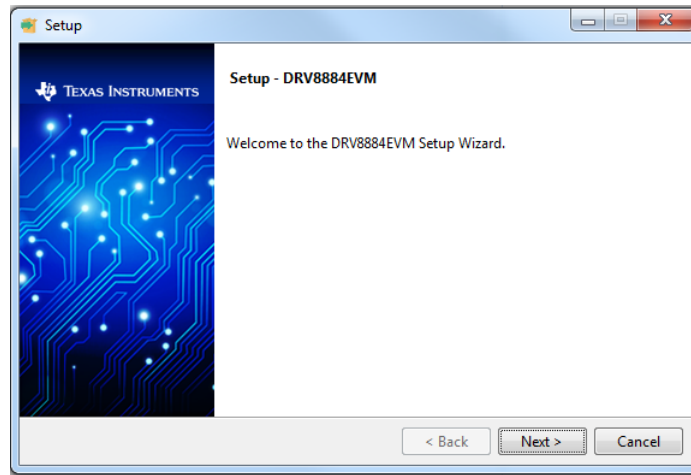
The installer begins. The following popup windows appear.

Select *Yes* to continue (see [Figure 9](#)).



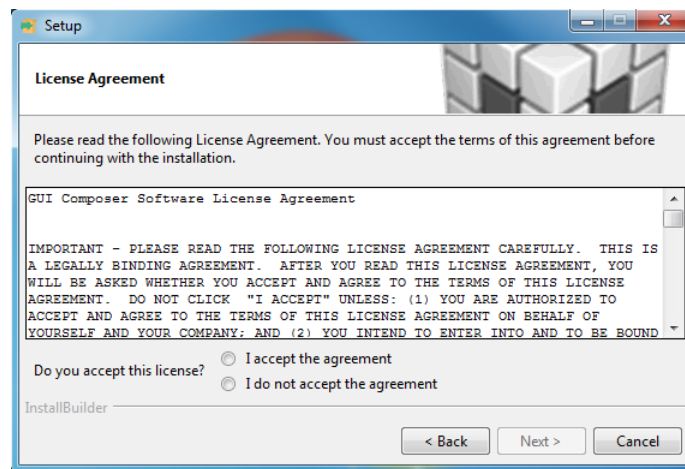
**Figure 9. User Account Control Window**

Select *Next* to continue (see [Figure 10](#)).



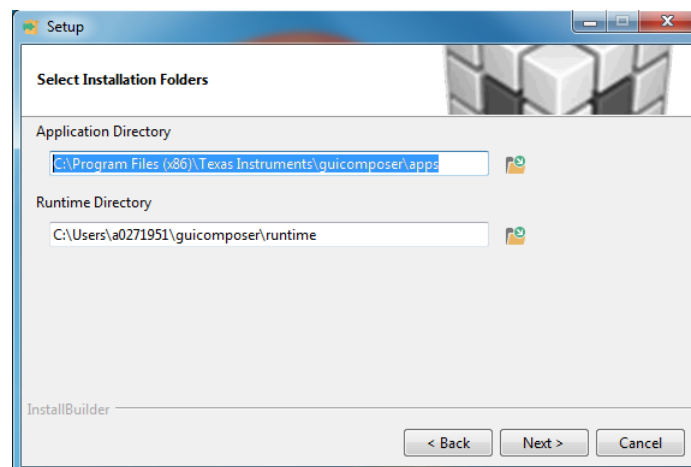
**Figure 10. EVM Setup Wizard**

Select *I accept the agreement* and *Next* to continue (see [Figure 11](#)).



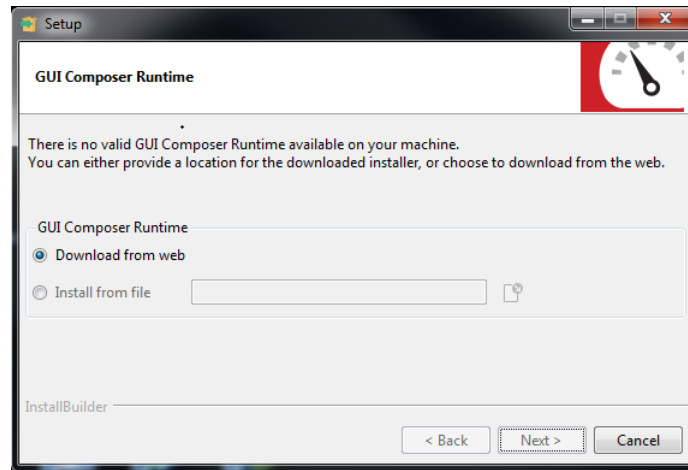
**Figure 11. License Agreement**

Select *Next* to continue (see [Figure 12](#)).



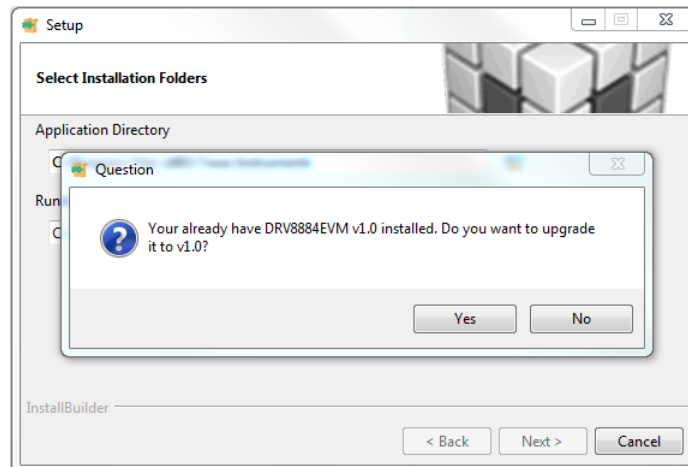
**Figure 12. Installation Folders**

At this point, a few options may appear. If the GUI Composer Runtime has not been previously installed, select *Download from web* and *Next* to continue (see [Figure 13](#)).



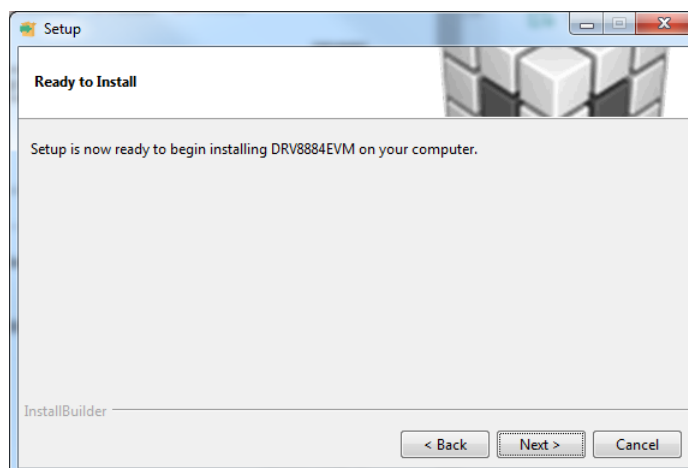
**Figure 13. GUI Composer Runtime Selection**

If the GUI has been previously installed a message similar to [Figure 14](#) may appear. If so, select *Yes*, then *Next* to continue (see [Figure 14](#)).



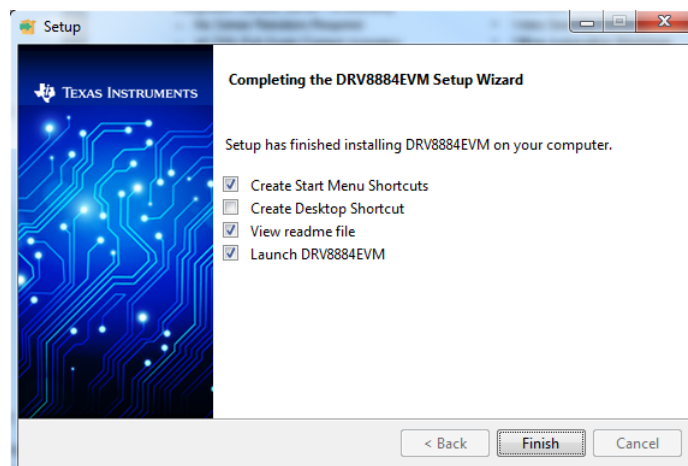
**Figure 14. Possible Upgrade Question**

Select *Next* to continue (see [Figure 15](#)).



**Figure 15. Ready to Install**

Click the desired results, then select *Finish* to complete (see [Figure 16](#)).



**Figure 16. Completed**

## STANDARD TERMS AND CONDITIONS FOR EVALUATION MODULES

1. *Delivery:* TI delivers TI evaluation boards, kits, or modules, including any accompanying demonstration software, components, or documentation (collectively, an "EVM" or "EVMs") to the User ("User") in accordance with the terms and conditions set forth herein. Acceptance of the EVM is expressly subject to the following terms and conditions.
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  - 1.2 EVMs are not intended for consumer or household use. EVMs may not be sold, sublicensed, leased, rented, loaned, assigned, or otherwise distributed for commercial purposes by Users, in whole or in part, or used in any finished product or production system.
2. *Limited Warranty and Related Remedies/Disclaimers:*
  - 2.1 These terms and conditions do not apply to Software. The warranty, if any, for Software is covered in the applicable Software License Agreement.
  - 2.2 TI warrants that the TI EVM will conform to TI's published specifications for ninety (90) days after the date TI delivers such EVM to User. Notwithstanding the foregoing, TI shall not be liable for any defects that are caused by neglect, misuse or mistreatment by an entity other than TI, including improper installation or testing, or for any EVMs that have been altered or modified in any way by an entity other than TI. Moreover, TI shall not be liable for any defects that result from User's design, specifications or instructions for such EVMs. Testing and other quality control techniques are used to the extent TI deems necessary or as mandated by government requirements. TI does not test all parameters of each EVM.
  - 2.3 If any EVM fails to conform to the warranty set forth above, TI's sole liability shall be at its option to repair or replace such EVM, or credit User's account for such EVM. TI's liability under this warranty shall be limited to EVMs that are returned during the warranty period to the address designated by TI and that are determined by TI not to conform to such warranty. If TI elects to repair or replace such EVM, TI shall have a reasonable time to repair such EVM or provide replacements. Repaired EVMs shall be warranted for the remainder of the original warranty period. Replaced EVMs shall be warranted for a new full ninety (90) day warranty period.
3. *Regulatory Notices:*
  - 3.1 *United States*
    - 3.1.1 *Notice applicable to EVMs not FCC-Approved:*

This kit is designed to allow product developers to evaluate electronic components, circuitry, or software associated with the kit to determine whether to incorporate such items in a finished product and software developers to write software applications for use with the end product. This kit is not a finished product and when assembled may not be resold or otherwise marketed unless all required FCC equipment authorizations are first obtained. Operation is subject to the condition that this product not cause harmful interference to licensed radio stations and that this product accept harmful interference. Unless the assembled kit is designed to operate under part 15, part 18 or part 95 of this chapter, the operator of the kit must operate under the authority of an FCC license holder or must secure an experimental authorization under part 5 of this chapter.
    - 3.1.2 *For EVMs annotated as FCC – FEDERAL COMMUNICATIONS COMMISSION Part 15 Compliant:*

### CAUTION

This device complies with part 15 of the FCC Rules. Operation is subject to the following two conditions: (1) This device may not cause harmful interference, and (2) this device must accept any interference received, including interference that may cause undesired operation.

Changes or modifications not expressly approved by the party responsible for compliance could void the user's authority to operate the equipment.

### FCC Interference Statement for Class A EVM devices

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

## **FCC Interference Statement for Class B EVM devices**

*NOTE: This equipment has been tested and found to comply with the limits for a Class B digital device, pursuant to part 15 of the FCC Rules. These limits are designed to provide reasonable protection against harmful interference in a residential installation. This equipment generates, uses and can radiate radio frequency energy and, if not installed and used in accordance with the instructions, may cause harmful interference to radio communications. However, there is no guarantee that interference will not occur in a particular installation. If this equipment does cause harmful interference to radio or television reception, which can be determined by turning the equipment off and on, the user is encouraged to try to correct the interference by one or more of the following measures:*

- Reorient or relocate the receiving antenna.
- Increase the separation between the equipment and receiver.
- Connect the equipment into an outlet on a circuit different from that to which the receiver is connected.
- Consult the dealer or an experienced radio/TV technician for help.

### 3.2 Canada

#### 3.2.1 For EVMs issued with an Industry Canada Certificate of Conformance to RSS-210

##### **Concerning EVMs Including Radio Transmitters:**

This device complies with Industry Canada license-exempt RSS standard(s). Operation is subject to the following two conditions: (1) this device may not cause interference, and (2) this device must accept any interference, including interference that may cause undesired operation of the device.

##### **Concernant les EVMs avec appareils radio:**

Le présent appareil est conforme aux CNR d'Industrie Canada applicables aux appareils radio exempts de licence. L'exploitation est autorisée aux deux conditions suivantes: (1) l'appareil ne doit pas produire de brouillage, et (2) l'utilisateur de l'appareil doit accepter tout brouillage radioélectrique subi, même si le brouillage est susceptible d'en compromettre le fonctionnement.

##### **Concerning EVMs Including Detachable Antennas:**

Under Industry Canada regulations, this radio transmitter may only operate using an antenna of a type and maximum (or lesser) gain approved for the transmitter by Industry Canada. To reduce potential radio interference to other users, the antenna type and its gain should be so chosen that the equivalent isotropically radiated power (e.i.r.p.) is not more than that necessary for successful communication. This radio transmitter has been approved by Industry Canada to operate with the antenna types listed in the user guide with the maximum permissible gain and required antenna impedance for each antenna type indicated. Antenna types not included in this list, having a gain greater than the maximum gain indicated for that type, are strictly prohibited for use with this device.

##### **Concernant les EVMs avec antennes détachables**

Conformément à la réglementation d'Industrie Canada, le présent émetteur radio peut fonctionner avec une antenne d'un type et d'un gain maximal (ou inférieur) approuvé pour l'émetteur par Industrie Canada. Dans le but de réduire les risques de brouillage radioélectrique à l'intention des autres utilisateurs, il faut choisir le type d'antenne et son gain de sorte que la puissance isotrope rayonnée équivalente (p.i.r.e.) ne dépasse pas l'intensité nécessaire à l'établissement d'une communication satisfaisante. Le présent émetteur radio a été approuvé par Industrie Canada pour fonctionner avec les types d'antenne énumérés dans le manuel d'usage et ayant un gain admissible maximal et l'impédance requise pour chaque type d'antenne. Les types d'antenne non inclus dans cette liste, ou dont le gain est supérieur au gain maximal indiqué, sont strictement interdits pour l'exploitation de l'émetteur.

### 3.3 Japan

3.3.1 *Notice for EVMs delivered in Japan:* Please see [http://www.tij.co.jp/lstds/ti\\_ja/general/eStore/notice\\_01.page](http://www.tij.co.jp/lstds/ti_ja/general/eStore/notice_01.page) 日本国内に輸入される評価用キット、ボードについては、次のところをご覧ください。  
[http://www.tij.co.jp/lstds/ti\\_ja/general/eStore/notice\\_01.page](http://www.tij.co.jp/lstds/ti_ja/general/eStore/notice_01.page)

3.3.2 *Notice for Users of EVMs Considered "Radio Frequency Products" in Japan:* EVMs entering Japan may not be certified by TI as conforming to Technical Regulations of Radio Law of Japan.

If User uses EVMs in Japan, not certified to Technical Regulations of Radio Law of Japan, User is required by Radio Law of Japan to follow the instructions below with respect to EVMs:

1. Use EVMs in a shielded room or any other test facility as defined in the notification #173 issued by Ministry of Internal Affairs and Communications on March 28, 2006, based on Sub-section 1.1 of Article 6 of the Ministry's Rule for Enforcement of Radio Law of Japan,
2. Use EVMs only after User obtains the license of Test Radio Station as provided in Radio Law of Japan with respect to EVMs, or
3. Use of EVMs only after User obtains the Technical Regulations Conformity Certification as provided in Radio Law of Japan with respect to EVMs. Also, do not transfer EVMs, unless User gives the same notice above to the transferee. Please note that if User does not follow the instructions above, User will be subject to penalties of Radio Law of Japan.



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