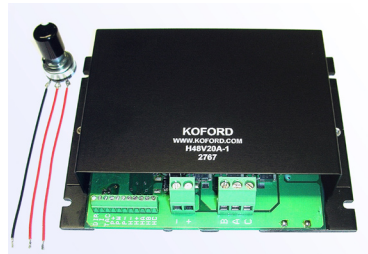
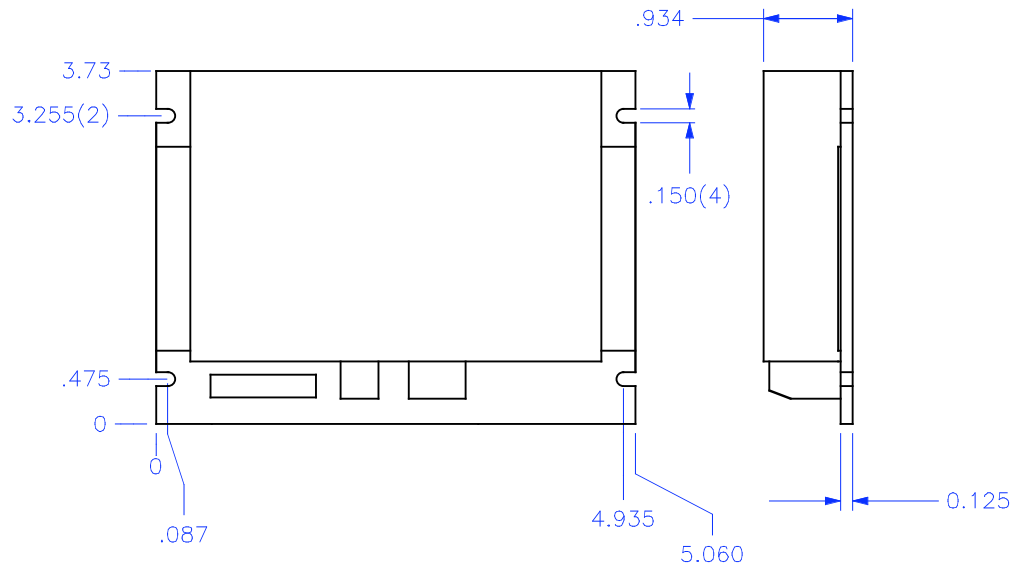


Ultra high efficiency miniature hall sensor drive with 56k pwm frequency, designed for stand alone, digital or analog operation. The drive has no minimum inductance and will operate slotless or ironless brushless motors without the need for bulky, cumbersome inductors. Three types are available, a full featured -1 model which include tach and current output, speed control and direction control, and a lower cost -2 which deletes the tach and current output, the -3 model offers digital closed loop speed control, direction, and tach output. For stand alone operation the optional speed pot P1 should be ordered.



Once power supply, motor and speed pot are connected, the motor can be operated without the need for any adjustments, set up or programming. If reversible operation is required a SPDT switch can be added between Dir and P-. For digital operation the unit will interface with a customers microcontroller. The microcontroller should be 5v or be a 3.3v with 5v interface capabilities. Speed input can be accomplished with a 0-5v analog input (less then 1mA) or a 100 hz to 100k Hz square wave with variable duty cycle. The input signal should be adjusted so as to close the loop with the TAC output which outputs a 4v square wave with a fixed on time. The frequency equals 6 pulses per revolution for a 2 pole motor, 12 for a 4 pole etc. The direction is controlled by 0v (reverse) or 5v (forward) to the DIR input. The current output is a DC voltage at .25v per amp of motor current (not power supply current). For analog operation the TAC output can be filtered and a DC voltage proportional to the rpm will result. The drive weighs 6.5 oz.



Terminal block positions (motor lead hook up for Koford motors)

DIR=leave unconnected for forward direction, hook to P- for reverse

I=current output, .5V = 1A of motor current

TAC=tach/encoder output 6 pulses per revolution per magnet pole pair (1,000 hz=10,000 rpm 2 pole motor)

P+=connect to one side of pot (6.2v)

PW=connect to pot wiper (center terminal)

P-=connect to other side of pot (ground)

H-=black motor wire (hall ground)

H+=red motor wire (hall power)

HA=yellow motor wire

HB=orange motor wire

HC=green motor wire

-=Connect to black (-) lead of power supply

=Connect to red (+) lead of power supply

B=white motor wire

A=blue motor wire

C=brown motor wire

## **Ordering information:**

mail@koford.com•phone 937-695-1275•fax 937-695-0237•www.koford.com

Part number: H48V20A-1 Open loop with current and tach functions

H48V20A-2 Open loop, no current or tach

H48V20A-3 Closed loop, with speed control and tach

H48V20A-4 Open loop with brake and tach

H48V20A-5 Closed loop with brake and tach

P1 Control pot with know and lead wires

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### Notes

1. Open loop drives vary the duty cycle in response to the control voltage or control knob position. At 0V the motor is off, at 5 volts the motor is at maximum speed. Open loop drives will work with any motor independent of the motors rpm/volt. Closed loop drives vary the duty cycle to hold the speed commanded by the control voltage or control knob position. Usually 0V is off and 5 volts is a rpm determined by the customer. Closed loop drives are usually custom programed for a specific customer.

2. When using a microcontroller to operate the drive a 5 volts output should be used and the pwm frequency should be 8Khz or more, otherwise filtering of the output will be required.

3. The drives current output shows motor current, this is not the same as power supply current. A pwm drive acts much like a variable transformer to reduce the voltage and at the same time increase the current delivered to the motor. For example if the speed pot is set to 10% of maximum speed and the power supply shows 1 amp and 24 volts, the motor will see approximately 10 amps and 2.4 volts. This current sense output is approximate and is most accurate near full load current.

4. The current limiting of the drive limits the current delivered to the motor to slightly above 20 amps, this means that the current at the power supply will reach a maximum of slightly above 20 amps with the speed turned to maximum, if the speed is reduced then the maximum current at the power supply will be porportionately reduced so as to maintain the current at the motor at a maximum of 20 amps.

5. The drive should preferable be mounted to an aluminum chassis or frame, or an aluminum heat sink. Drive heat rise is greatest at high currents, low duty cycles and continuous operation. If the application is 100% duty cycle, with normal indoor ambient temperature, the current is low compared to the rated current, or if the application is intermittent with on times for example of 1 minute and off times of at least 1 minute, then a heat sink will probably not be necessary. For high ambients forced air cooling directed at the board can help. For long term reliability, it is recommended that sufficient cooling be provided to prevent the case from exceeding 60C. This can be checked with a portable infrared thermometer.

6. Reversing direction while the motor is spinning (4 quadrant operation) should be normally be avoided. If the motor is running at maximum speed and the direction is reversed then currents as high as twice the stall current of the motor can flow damaging the drive and motor. The energy stored in the load will be dumped into the power source for the drive. If this is a battery the battery will be recharged, however if a power supply is used internal diodes will prevent the energy from transferring to the AC line power and instead the output capaciator of the power supply will be charged up. This can result in destruction of the power supply and or the drive due to overvoltage. If the application requires 4 quadrant operation then a shunt resistor and relay must be added to the power supply