ESP302

3-Axis Motion Controller and Driver

The ESP302 1 to 3 Axis Motion Controller and Driver is the successor to the popular ESP301 motion controller. The ESP302 provides the same functionality as the ESP301, but with added Ethernet interface, web based GUI, and enhanced front panel functions through an LCD touch screen on the front panel. For maximum backward compatibility, the ESP302 features the same motion commands and control algorithms as the ESP301. The ESP302 drives and controls one, two or three axes of motion using DC or 2-phase stepper motors up to 3A. This capability enables driving a large selection of Newport stages and actuators. Utilizing the full feature LCD touch front panel interface and Newport's unique ESP stage auto-detection and auto-configuration, the ESP302 provides easy operation and excellent functionality at an affordable price. The ESP302 uses a 64-bit, floating point, DSP processor for high precision synchronized control. A digital PID-FF (feedforward) servo loop ensures precise velocity profile tracking and accurate positioning. A 1000x programmable micro-step resolution provides ultrasmooth low-speed stepper positioning capability. and 18-bit DC motor command output ensures improved stability for precision applications.



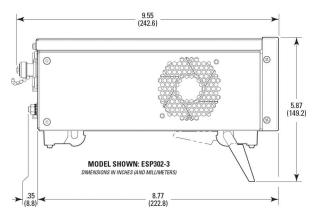
Product Features

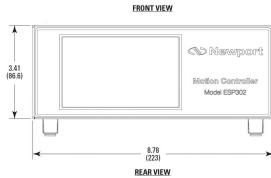
- Up to 3 axis motion control
- LCD touch screen front panel user interface
- Ethernet or serial communication
- Web-based GUI w/ multi user capabilities
- Universal driver card
- AquadB encoder support
- Smaller form factor and light weight
- External GPIB interface through serial port
- Command set backwards compatibility with ESP301

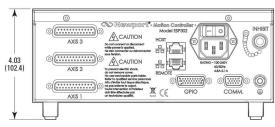
3-Axis Motion Controller and Driver

Specifications

| EATURE | Description 1, 2 or 3 | | | | |
|--|--|--|--|--|--|
| Number of Axis | | | | | |
| Control Interfaces | Front panel touchscreen Serial COM port Ethernet TCP/IP (10/100/1000 Base-T) | | | | |
| Firmware Features | Native user defined units (no need to work with encoder counts Real Time execution of custom tasks using program mode 300 MB of user storage for programs and data Mutli user capability (same as XPS-D) Process sockets for parallel processing Data gathering at rates up to 10 kHz | | | | |
| Motion | S-curve velocity profile. Jogging mode, including on-th-fly changes of speed and acceleration Line and Arc modes for two axis trajectory motion Master/slave, including single master/multiple slaves and custom gear ration Grouping for coordinated motion of multiple axes | | | | |
| Compensation | Backlash Linear error All corrections are taken into account in the servo loop | | | | |
| Servo rate | Fixed at 10 kHz | | | | |
| I/O | 16 TTL, 5 V Configurable as inputs or outputs | | | | |
| Open loop – PI position – PID w/ FF velocity – PID w/ Dual FF voltage Integration limit and integration time Derivative cut-off filter | | | | | |
| Trigger Input | I/O configurable to start/stop inhibit motion, jog or execute program | | | | |
| Voltage, velocity (for DC brush motor control). Position (for stepper motor control) 3A RMS @ 48V per axis 150 W (above 110 VAC) maximum available power for all axes | | | | | |



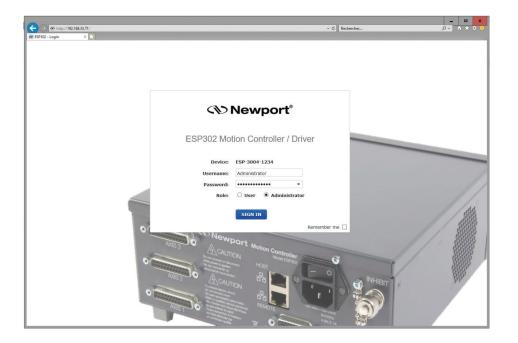






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New GUI through Web Browser

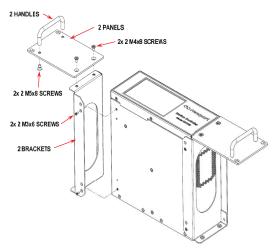


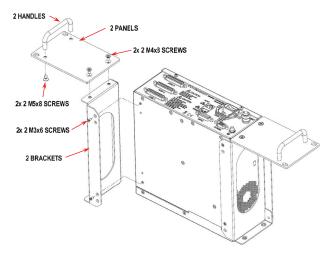
Touch Screen GUI - Examples

| Iome | Mon May 20 2019 16:23 IP: none Axis 1 Power ON | Home | Mon May 20 2019 16:31 IP: none Absolute Relative Cvcle | Home | Absolute Relative Cycle |
|---------|---|---------|---|---------|---|
| Aove | -9.555 | Move | Axis 1 (REF) Axis 2 (REF) Axis 3 (NC) | Move | Axis 1 [REF] Axis 2 [REF] Axis 3 [NC] |
| Gpio | [OFF] | Gpio | 4.7560 -1.1780 | Gpio | 4.7560 -1.1780 |
| | Axis 2 Power ON | - | Position Power OFF Power OFF Power ON | | Position Power OFF Power OFF Power ON |
| status | 0.000 | Status | Velocity 40 20 | Status | Velocity 40 20 |
| setting | Axis 3 | Setting | Move #1 Go Go Go | Setting | 3 Move |
| Program | MO STAGE | Program | 00 00 00 | Program | |
| bout | [NC] | About | Move #2 Go Go Go | About | |
| | Kill all motors | | | | |
| lome | Mon May 20 2019 16:32 IP: none | Home | Mon May 20 2019 16:32 IP: none | Home | Mon May 20 2019 16:32 IP: none |
| | Gpio State | | Errors Status Log | | Motion Display Ethernet Config |
| Move | GPI01 06 1 2 3 4 5 6 7 8 | Move | Axe ZM EOR- EOR+ In Median Motor Fault Following Error 1 | Move | Velocity: Axis 1 Axis 2 Axis 3 OH 20 10 10 10 |
| Gpio | | Gpio | 2 | Gpio | JW 4 2 |
| Status | GPIO2 | Status | Motor ON for at least one axis: | Status | лн 40 20 |
| Setting | OE 1 2 3 4 5 6 7 8 | Setting | At heast one program is executing: At heast one trajectory is executing: | Setting | VA 40 20 |
| Program | | Program | In some one understated to exceeding. | Program | Acceleration: Axis 1 Axis 2 Axis 3 AC 160 80 |
| About | | About | | About | Read parameters Apply parameters |
| | | | | | |
| | Mon May 20 2019 16:33 IP: none | | Mon May 20 2019 16:33 IP: none | | Wed May 22 2019 14:59 IP: none |
| Home | Motion Display Ethernet Config | Home | New history 2019 1MO WT2000 | Status | Motion Display Ethernet Config |
| Move | Host static IP | Move | 10R 1WS | Setting | Axis 1 Axis 2 Axis 3 Stage UTS50CC TRB6CC NO STAG |
| Gpio | Type • dynamic IP | Gpio | | About | Current config UTSOCC TRB6CC UTSSOC |
| Status | IP address | Status | | | |
| Setting | Netmask Gateway | Setting | | | New config UTSSOCC TRBGCC DUMMY_ST apply apply apply apply |
| Program | Remote | Program | | | new config new config new con |
| | IP address : 192.168.254.254 Netmask : 255.255.255.0 | About | | | Reboot |
| About | | | | | |

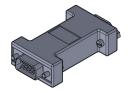
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ESP302 Accessories





ESP302-R - Rack Mounting Kit Front or rear mounting



ESP302-RS232 - Serial port adapter 15-pin D-SUB-HD to 9-pin D-SUB



ESP302-CAB-1.2 - Serial port cable 15-pin D-SUB-HD to 9-pin D-SUB – 3 ft.



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