

DRV8803/04/05/06 Evaluation Module

User's Guide



Literature Number: SLVU574B
September 2011–Revised July 2019

1	Trademarks	4
2	PCB.....	5
2.1	Test Points	6
2.2	Connectors	7
2.3	Jumpers/Resistors	8
2.4	Motor Outputs.....	9
3	GUI Software Installation	10
3.1	System Requirements.....	10
3.2	Installation Procedure	10
4	The Windows Application.....	22
4.1	DRV8803	22
4.2	DRV8804	23
4.3	DRV8805	24
4.4	DRV8806	25
4.5	GUI Description/Functionality	26
4.6	DRV880x GPIO Control Signals	28
4.7	PWM Control	31
4.8	Motor Control.....	32
4.9	Speed Control	34
4.10	Acceleration Control.....	34
4.11	Diagnostic Output.....	35
4.12	Controlling the EVM Using External Signals	35
5	Schematics.....	35

List of Figures

1	DRV8803/04/05/06 PCB	5
2	Test Points	6
3	Power Connectors	7
4	Jumpers/Resistors	9
5	Motor Outputs	10
6	Setup_DRV8803/04/05/06_EVM.exe	11
7	Installation Initialization	11
8	License Agreement	12
9	NI License Agreement	12
10	Installation Directory Screen	13
11	Component Selection	13
12	Configure Proxy	14
13	Ready to Install	14
14	Downloading RTE	15
15	LabVIEW RTE Self Extraction	15
16	LabVIEW RTE Installation Initialization	16
17	Installation of LabVIEW RTE in Progress	16
18	FTDI Installation Initialization	17
19	Driver Installation Wizard	18
20	License Agreement for FTDI Driver	19
21	Driver Installation Completion	19
22	Installation Complete	20
23	Readme Window	20
24	DRV8803 Tab	22
25	DRV8804 Tab	23
26	DRV8805 Tab	24
27	DRV8806 Tab	25
28	Menu	26
29	View	26
30	Schematic Window	27
31	Debug Window	27
32	Help Window	28
33	About Window	28
34	GPIO Control Signals	29
35	SMx	30
36	DRV8803 PWM Control	31
37	Motor Control	32
38	DRV88003/04/05 Motor Control Windows	33
39	DRV88003/04/05 Speed Control Windows	34
40	DRV88003/04/05 Acceleration Control Windows	34
41	Acceleration Control	35

1 Trademarks

All trademarks are the property of their respective owners.

DRV8803/04/05/06 Evaluation Module

This document is provided as a supplement to the [DRV8803/DRV8804/DRV8805/DRV8806](#) datasheets. It details the hardware implementation of the DRV8803/04/05/06 EVM Customer Evaluation Module (EVM).

2 PCB

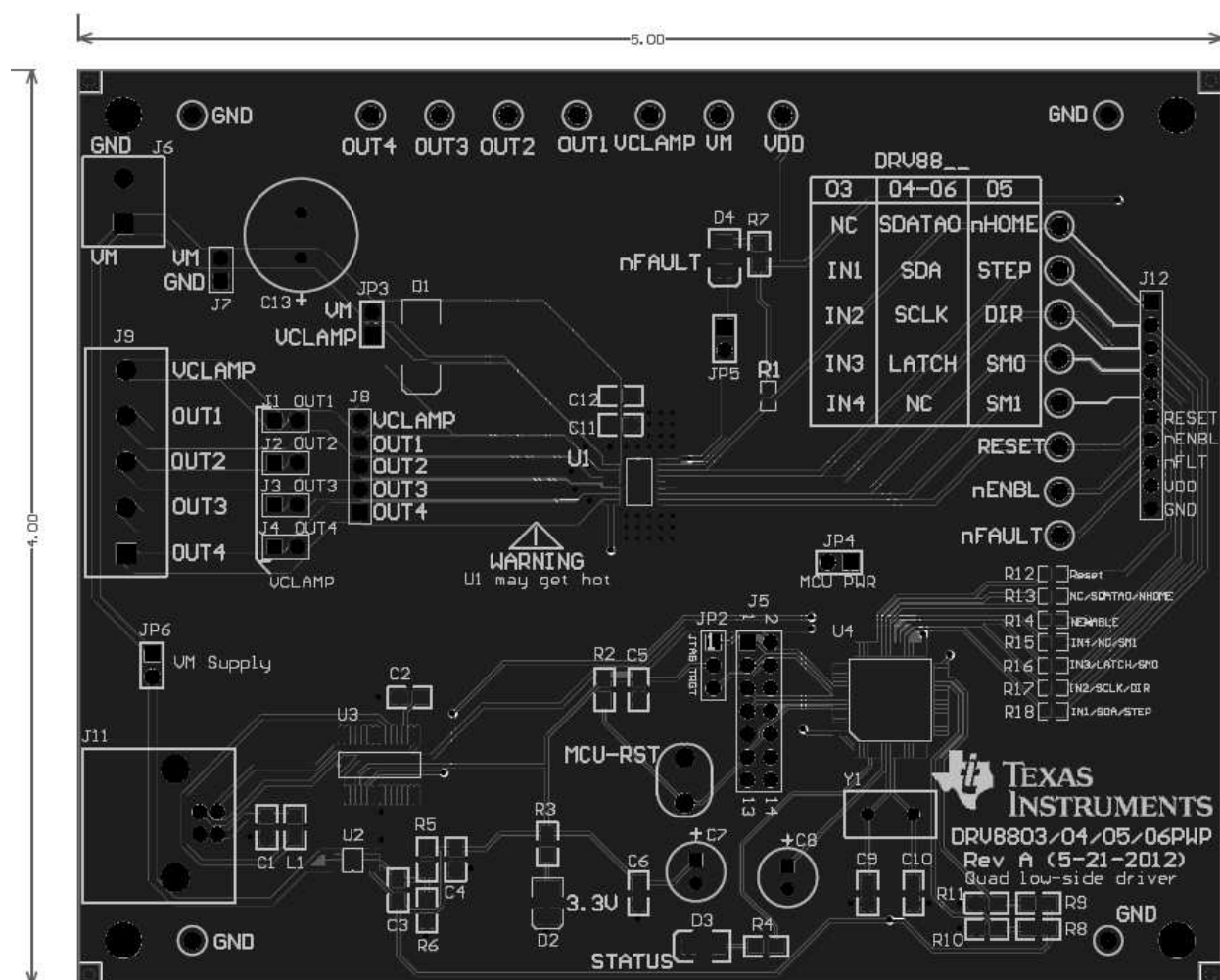


Figure 1. DRV8803/04/05/06 PCB

2.1 Test Points

Every pin on the DRV88xx device has been brought out to a test point, and labels on the silkscreen identify each signal. These are Kelvin connections and are not meant to be used to drive high currents. These can be used as a sense line.

For those pins that change functionality depending on the respective device being used, a table is provided with corresponding function name on its particular column.

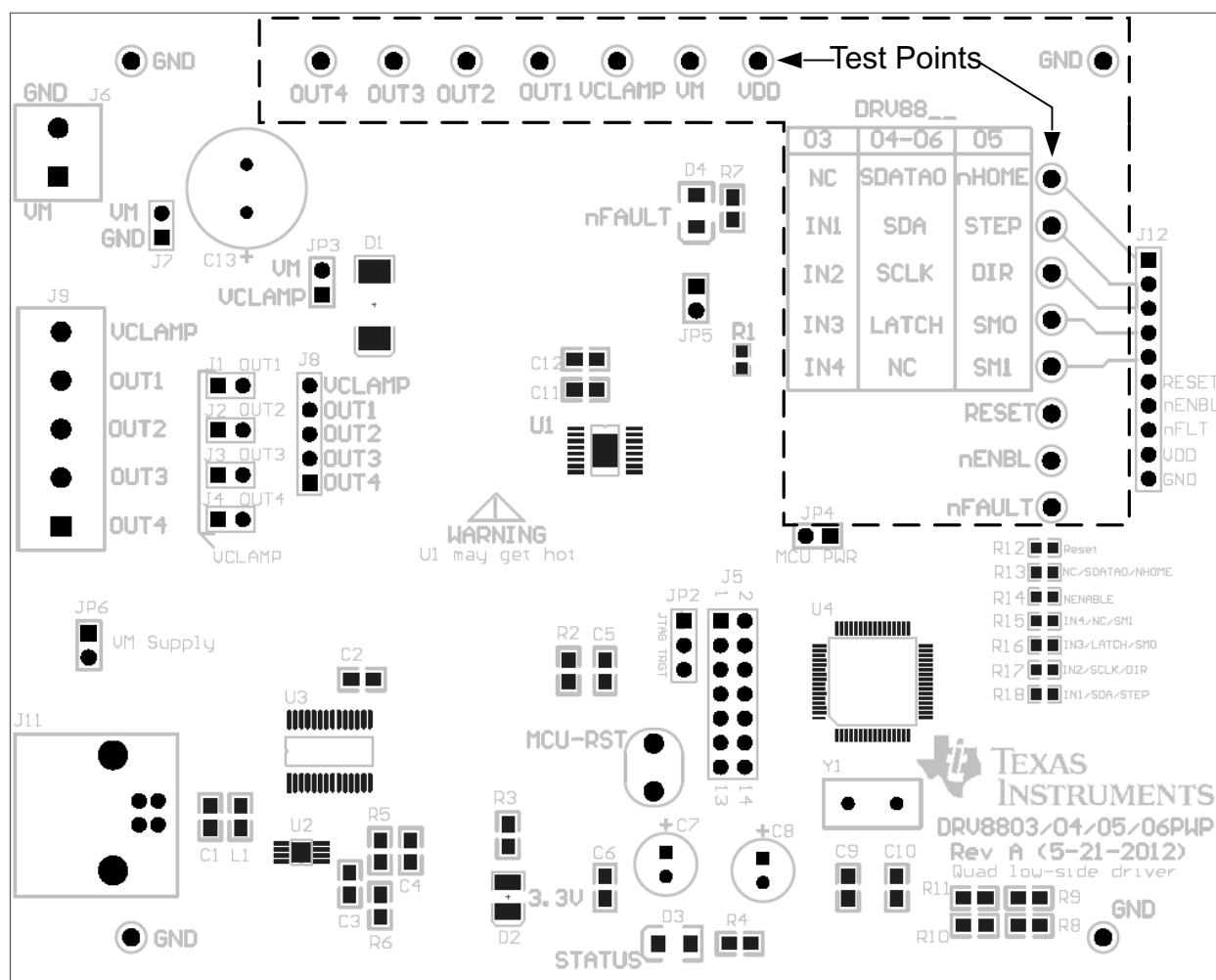


Figure 2. Test Points

2.2.2 Control Signals

The header J12 brings out all the control signals of the IC. For the pins that have multiple functionality depending on the IC used, the various functions are labeled in a table. The correct functionality can be ascertained from this table in the column corresponding to the IC being used. While the signals are being driven using the on-board MCU, these pins can be used to monitor the signals. However, the user can also apply external signals using this header. In such a case, the on-board MCU should be powered off by de-populating the MCU_PWR jumper. This will ensure that there is no conflict between the signals applied externally and the signals being forced by the on-board MCU. If only a few signals are being driven externally and the user wants to retain the on-board MCU for the remaining signals, the corresponding resistors R12-R18 can be de-soldered to ensure that there is no conflict.

2.3 Jumpers/Resistors

nFault – If a jumper is applied at nFault (JP5), the LED (D4) will light in the case of a fault. Even if the jumper is not applied, the voltage of the nFault can be monitored across the two pin headers (JP5 or JP12).

LDO Supply – There is an LDO (TPS7A4001DGNT) on board that can regulate the VM voltage down to 3.3 V. This voltage (VDD) is used to power the on board MCU (MSP430F2617) and is also used as the pull-up for the nFault pin. This voltage is used to light up the nFault LED. If a jumper is not applied to LDO supply (JP6), the onboard MCU is no longer powered. If a jumper is not applied, the user must drive the part using an external MCU by applying signals to the signal headers (J12), and the user must apply a VDD to implement the nFault LED function. If a jumper is applied the onboard MCU is powered on and can be used to drive the part.

NOTE: If the user is applying an external VDD, please ensure that the jumpers JP6 (LDO Supply) and JP4 (MCU_PWR) are de-populated.

MCU_PWR - Applying a jumper at MCU PWR (JP4) enables the MSP430 and logic on the EVM. If the jumper is not applied, the user must implement an MCU or apply signals to the signal headers (J12). If the jumper is not applied nFault still receives VDD (3.3 V). If jumper at (JP4) is applied, MCU-RST works as a manual reset button for the MCU.

NOTE: Both JP4 and JP6 must be populated to enable the on board MCU and use the DRV8803/04/05 EVM software.

Resistors – R8, R9, R10, R11 are resistors used to identify which device is being implemented on the EVM (DRV8803, 04, 05 or 06). The MCU powers up based on these resistors. However, the GUI can be used to select the device on the EVM too. If the user changes the DRV8803 to another flavor of the IC (namely DRV8804/05/06) the appropriate tab in the GUI should be selected and 'CONFIGURE DEVICE' should be selected.

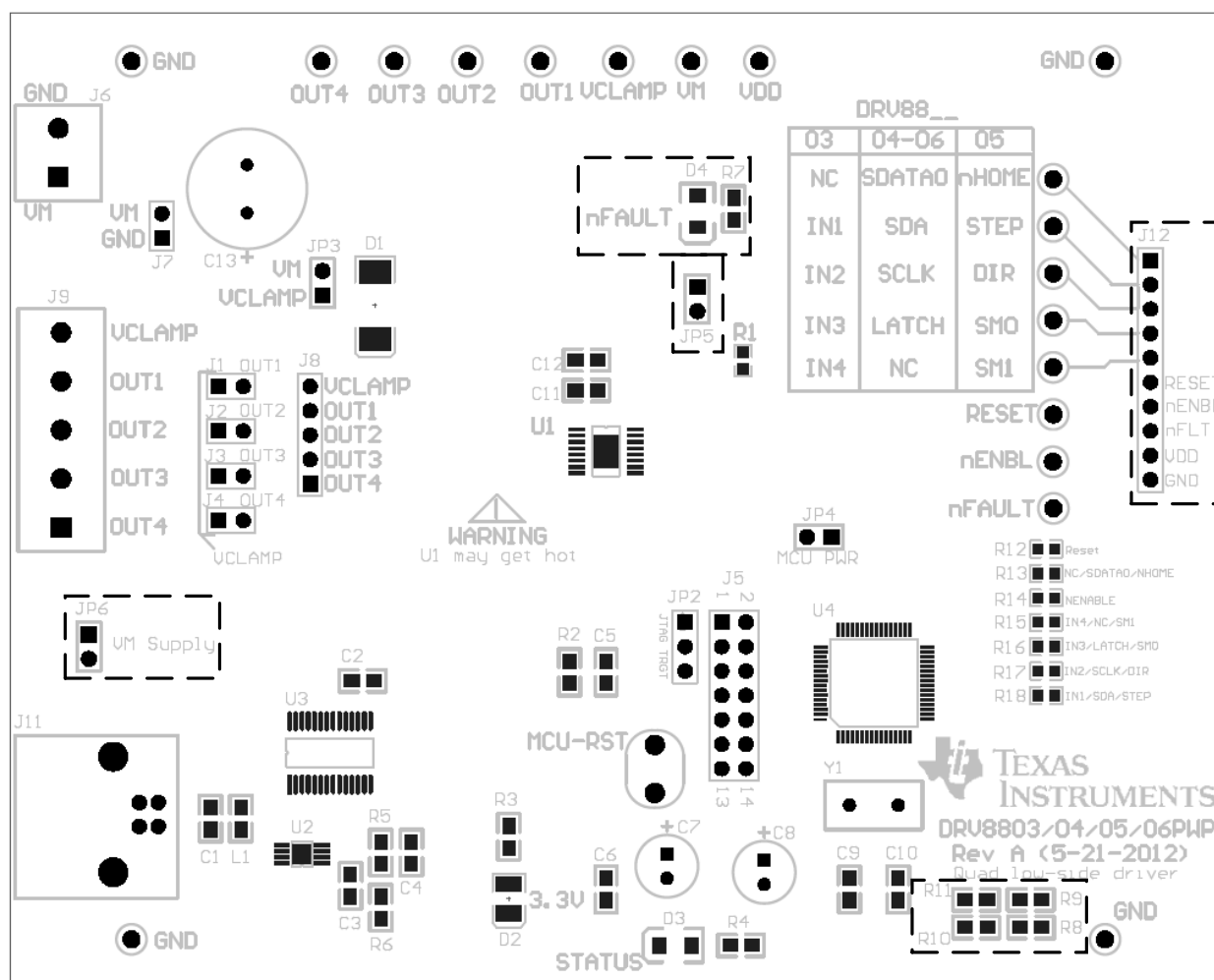


Figure 4. Jumpers/Resistors

2.4 Motor Outputs

There are two ways of connecting a bipolar stepper motor into the EVM: five pin header (J8), and five position terminal block (J9). The optimal way to connect a DC motor is the two pin headers (J1/J2/J3/J4). Although feasible, we do not recommend the connection of any motor into the test clips as these are Kelvin connections and are not rated for high current output. All pins are labeled on the silk-screen for clarity.

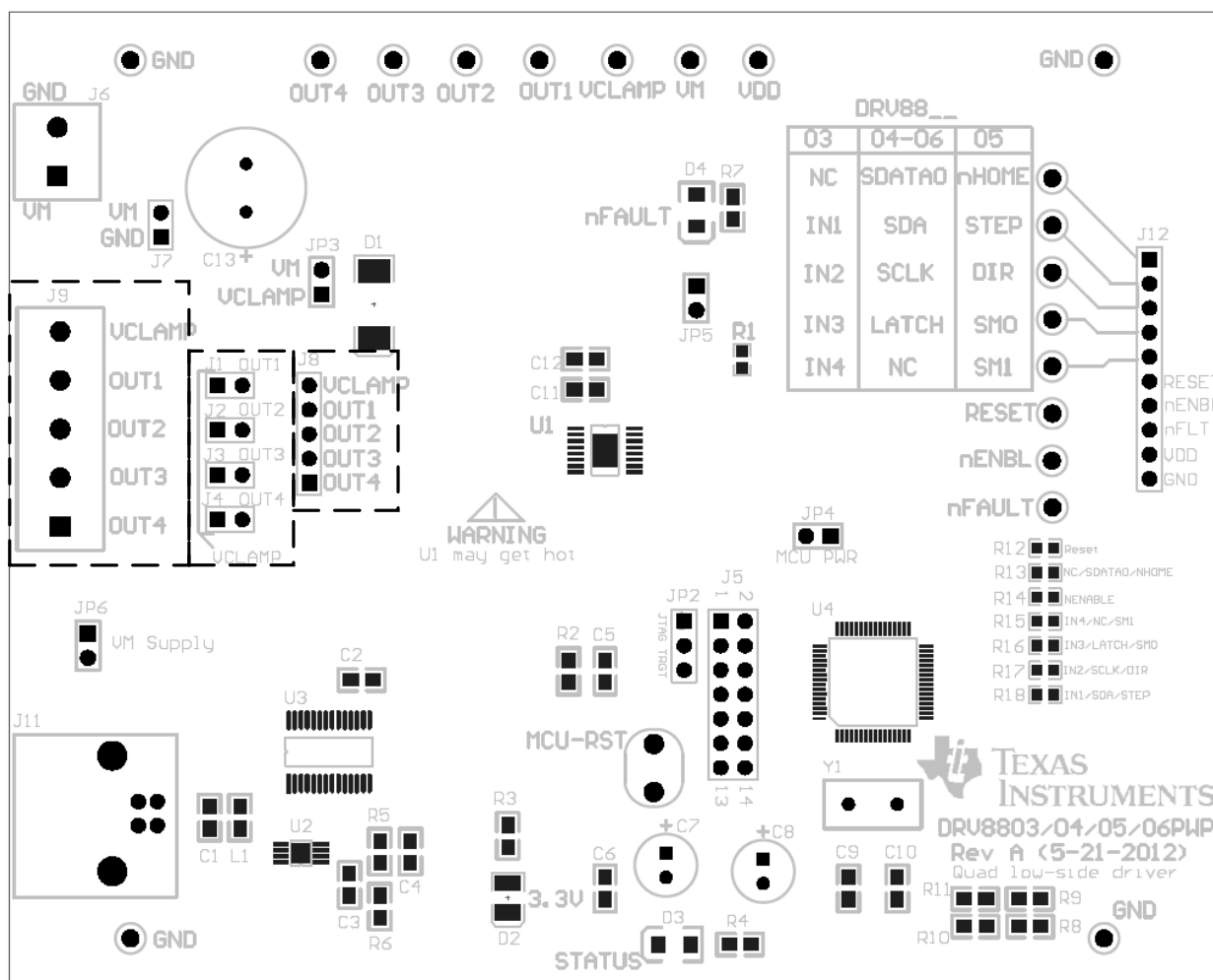


Figure 5. Motor Outputs

3 GUI Software Installation

The following section explains the location of files and the procedure for installing the software correctly.

NOTE: Ensure that no USB connections are made to the EVM until the installation is completed. The installer will also install LabVIEW RTE 2014 and FTDI Driver, along with the GUI.

3.1 System Requirements

- Supported OS – Windows 7 (32 Bit, 64 Bit). The window text size should be Smaller-100% (Default)
- Recommended RAM - 4 GB or higher
- Recommended CPU Operating Speed – 3.3 GHz or higher

3.2 Installation Procedure

The following procedure helps you install the DRV8803/04/05/06 EVM GUI

- Double click on the **Setup_DRV8803/04/05/06_EVM.exe** as in [Figure 6](#).

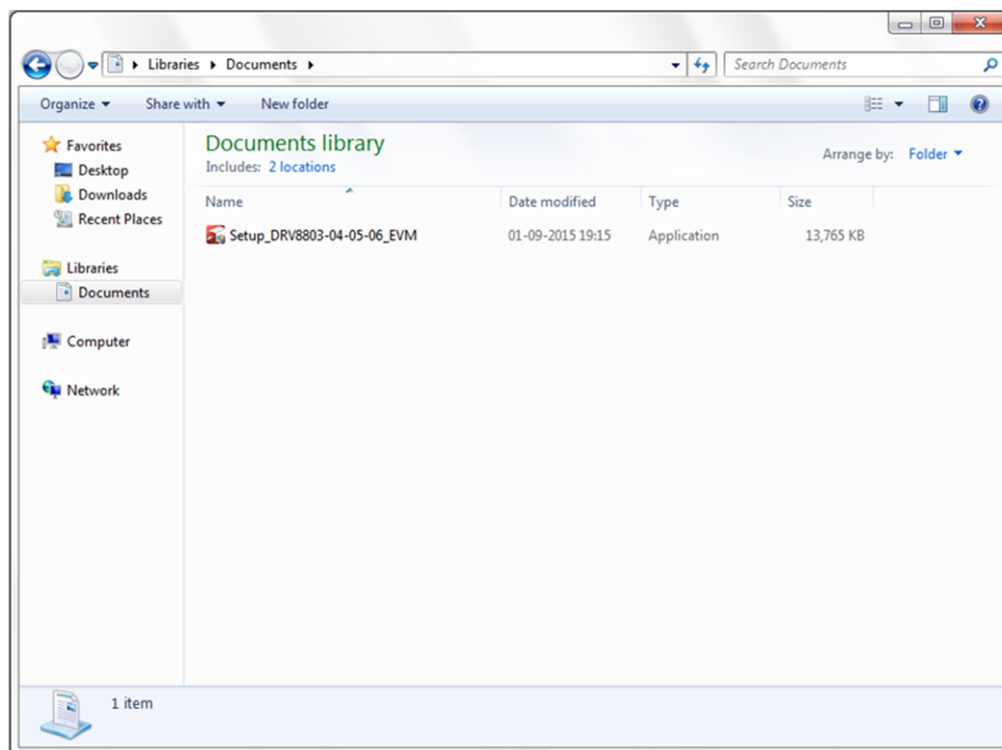


Figure 6. Setup_DRV8803/04/05/06_EVM.exe

2. The screen in [Figure 7](#) appears, indicating installer initialization. Click the **Next** button.

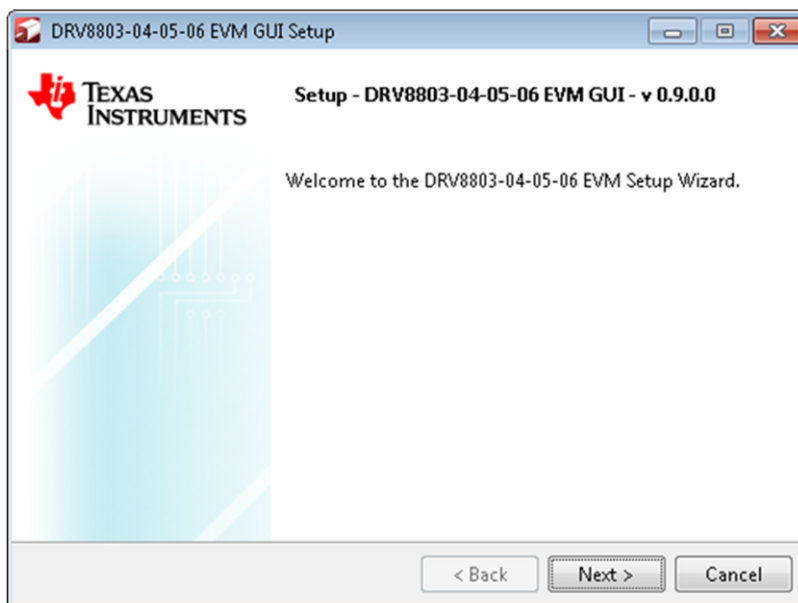


Figure 7. Installation Initialization

3. In the newly open installation pop-up window, click **Next**. The license agreement will be displayed. Please, read through it carefully and enable the "I Accept the Agreement" radio button and press **Next**.



Figure 8. License Agreement

4. A screen as shown in [Figure 9](#) appears, displaying the license agreement of National Instruments. Please read through the agreement carefully and enable the “I Accept the License Agreement” radio button and press the **Next** button.

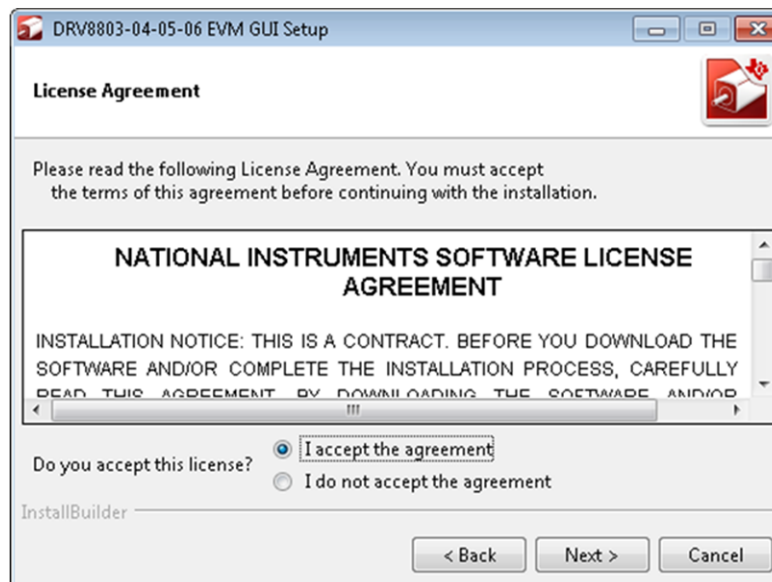


Figure 9. NI License Agreement

5. Set the default directory for the GUI Installation and click **Next**.

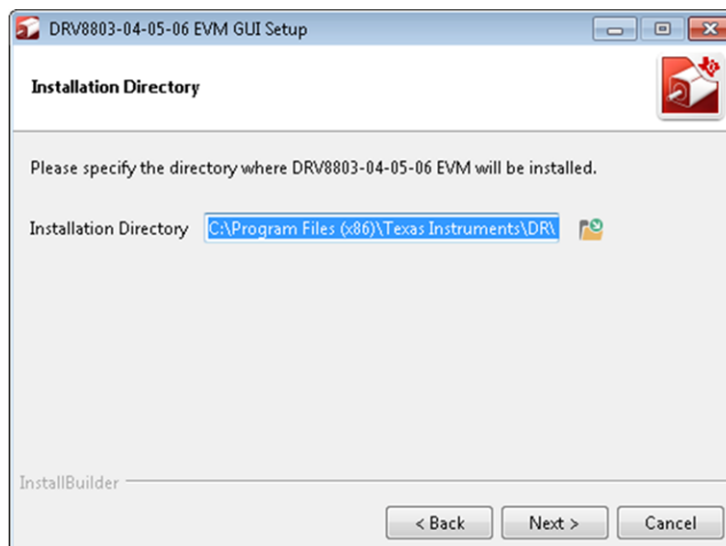


Figure 10. Installation Directory Screen

NOTE: It is highly recommended to keep the default values as provided in the installer.

6. A screen as shown in [Figure 11](#) appears. This screen is to select the components to install. Select the Components to Install and Click **Next** to continue installation. The LabVIEW RTE component checks out if the LabVIEW RTE 2014 is already installed on the PC.

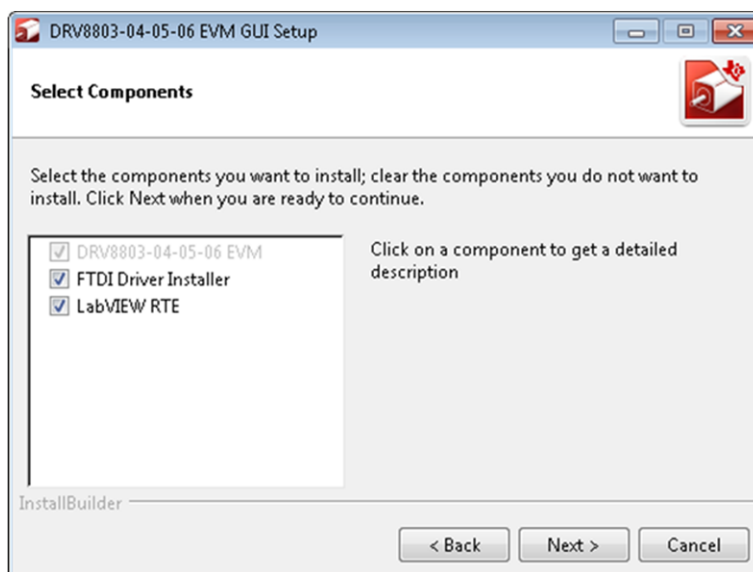


Figure 11. Component Selection

7. If LabVIEW RTE is selected as a component to install, a screen appears as shown in [Figure 12](#). Configure the proxy settings as required. This screen is to download the LabVIEW RTE 2014 from ni.com, Click **Next** to continue the installation.

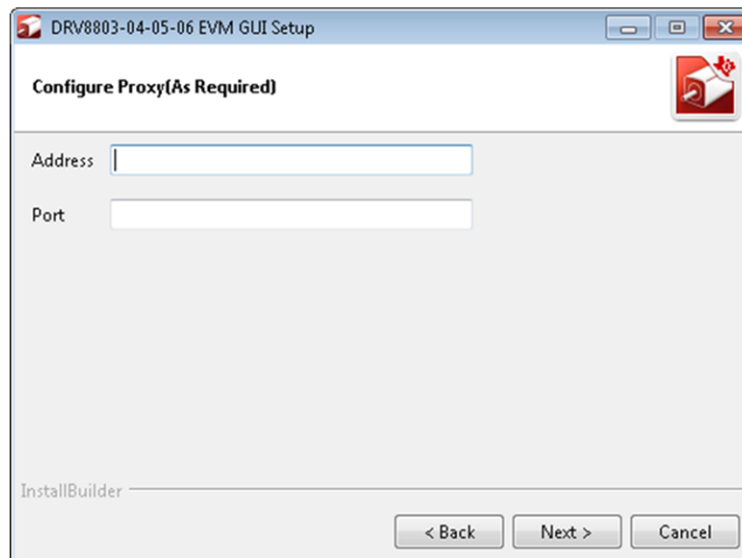


Figure 12. Configure Proxy

8. A screen as shown in [Figure 13](#) appears. Click **Next** to begin the installation.

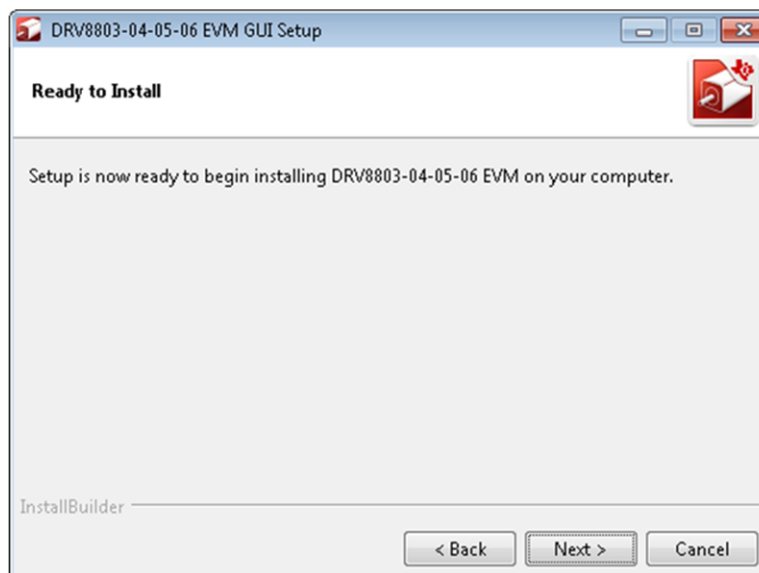


Figure 13. Ready to Install

9. If the LabVIEW RTE 2014 is selected as a component to install, LabVIEW RTE downloads and performs a silent mode installation.

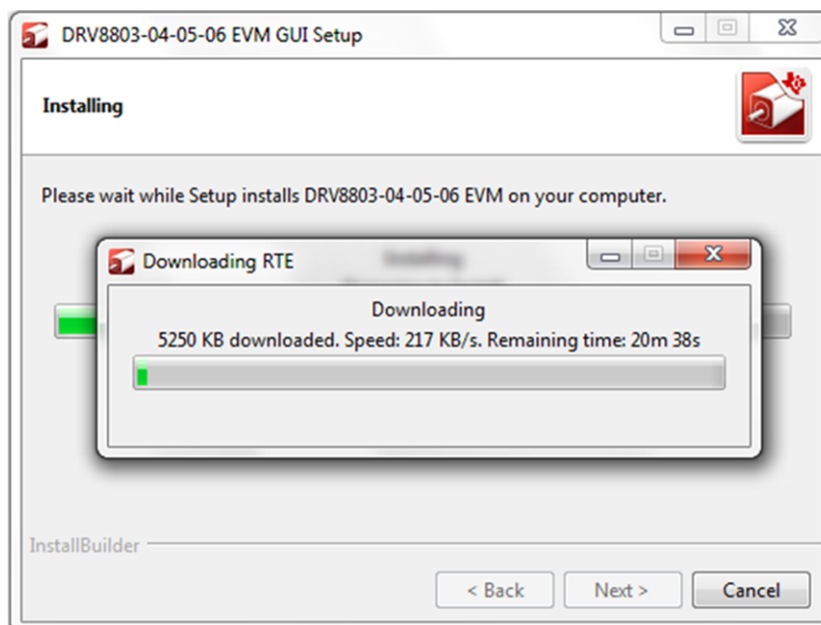


Figure 14. Downloading RTE

10. Once the download completes, LabVIEW begins with the self-extraction as shown in [Figure 15](#).

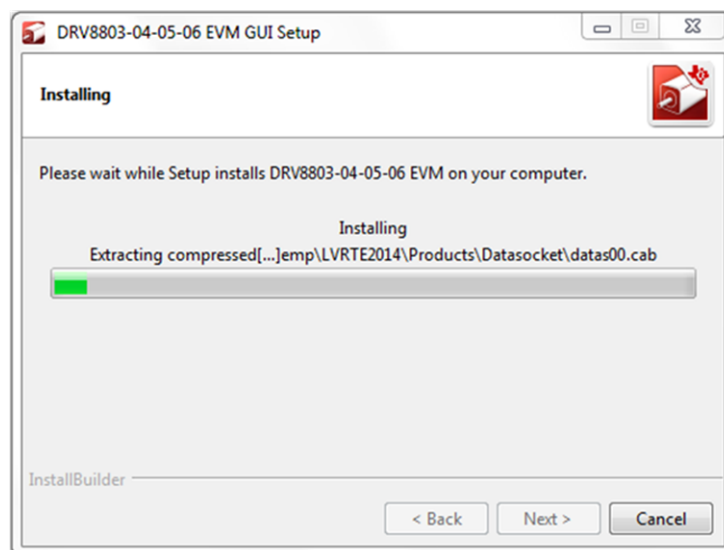


Figure 15. LabVIEW RTE Self Extraction

11. A screen appears as shown in [Figure 16](#). It initializes the LabVIEW RTE Installation.

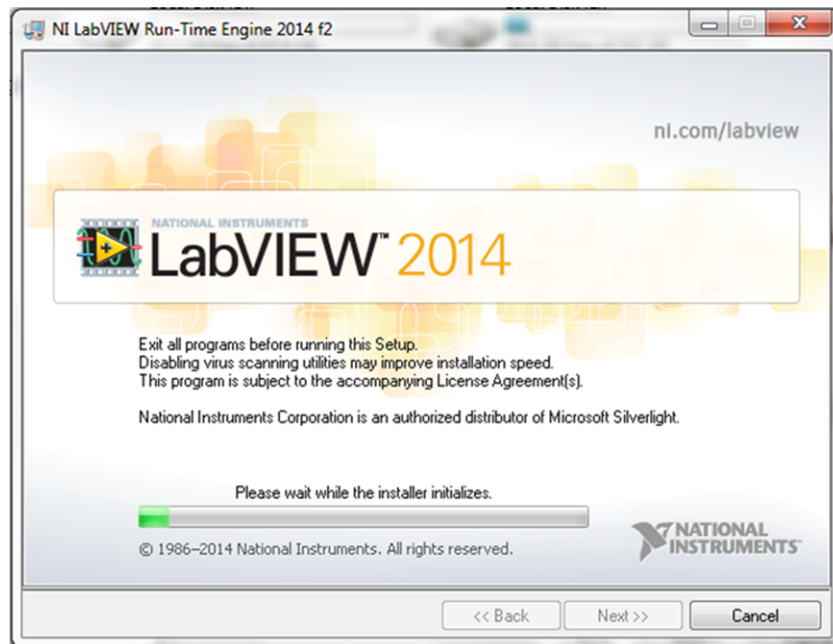


Figure 16. LabVIEW RTE Installation Initialization

12. A display as shown in [Figure 17](#) appears which indicates the progress of LabVIEW RTE installation.

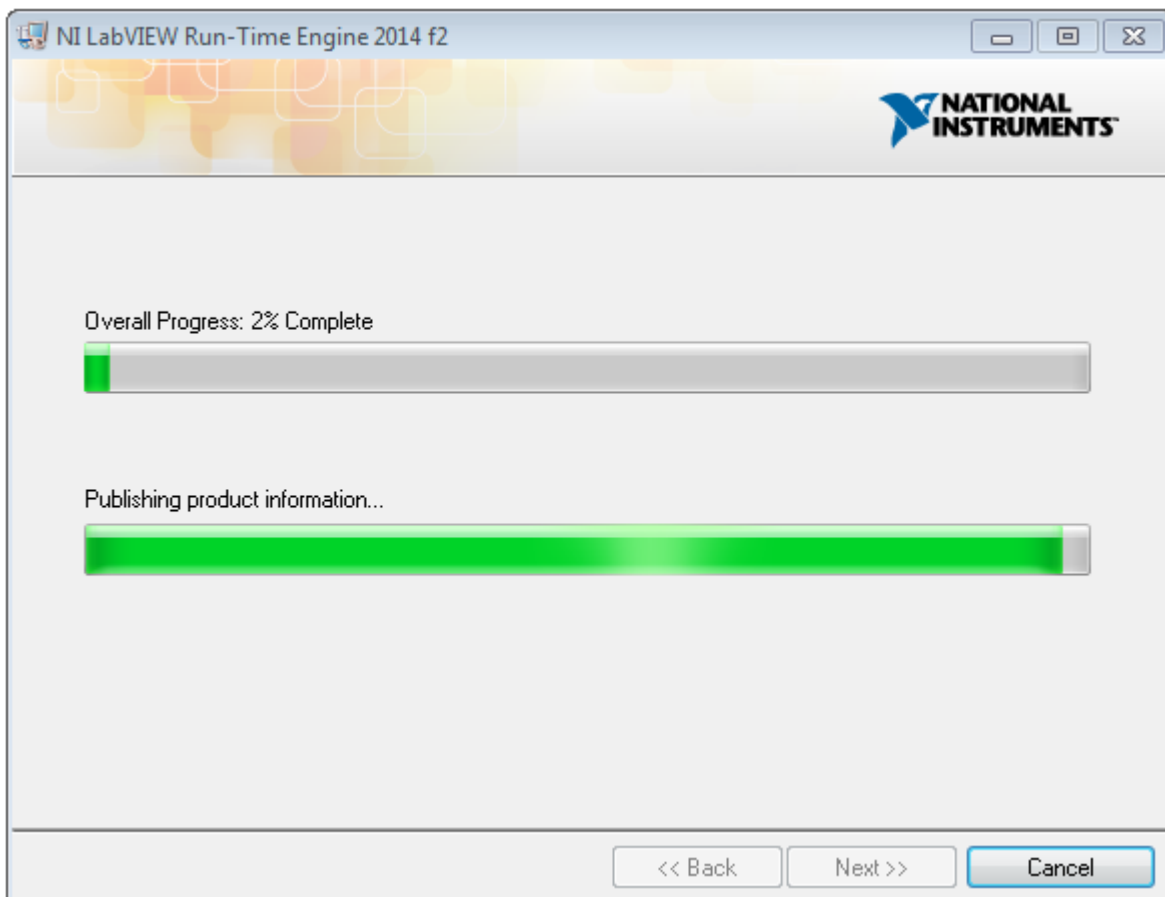


Figure 17. Installation of LabVIEW RTE in Progress

13. Once the LabVIEW RTE 2014 is installed, Setup_DRV8803/04/05/06_EVM GUI component installs.
14. After Setup_DRV8803/04/05/06_EVM Installation, FTDI Installation begins. A screen as shown in [Figure 18](#) appears, click **Extract** to proceed.

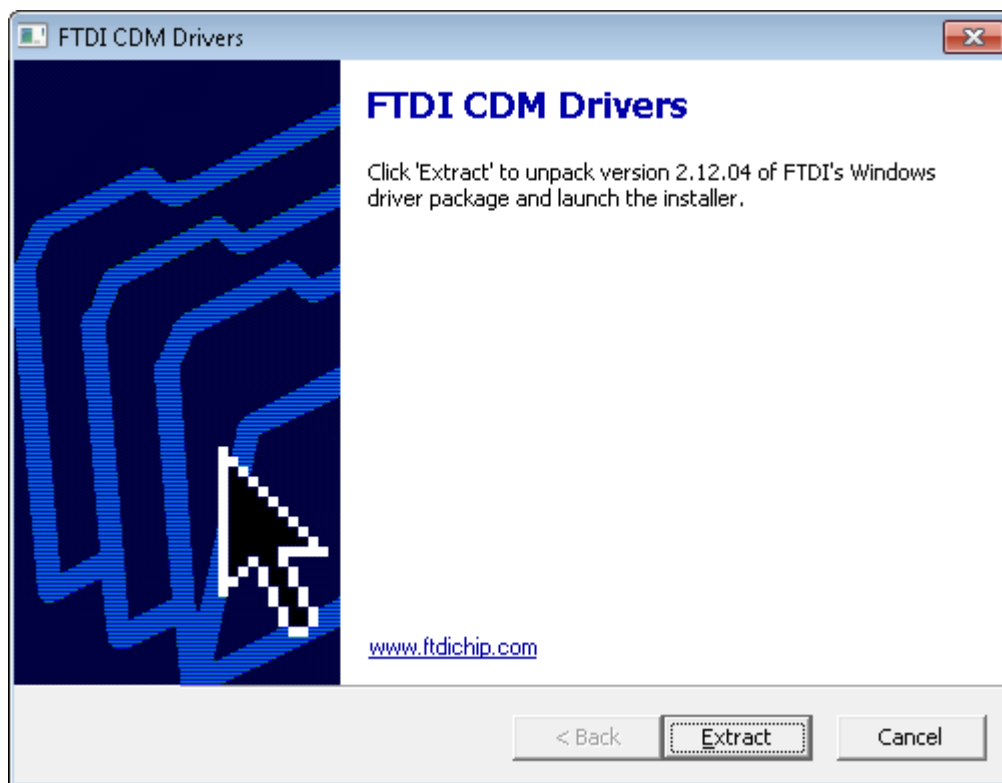


Figure 18. FTDI Installation Initialization

15. A screen as shown in [Figure 19](#) appears, click **Next** to proceed.

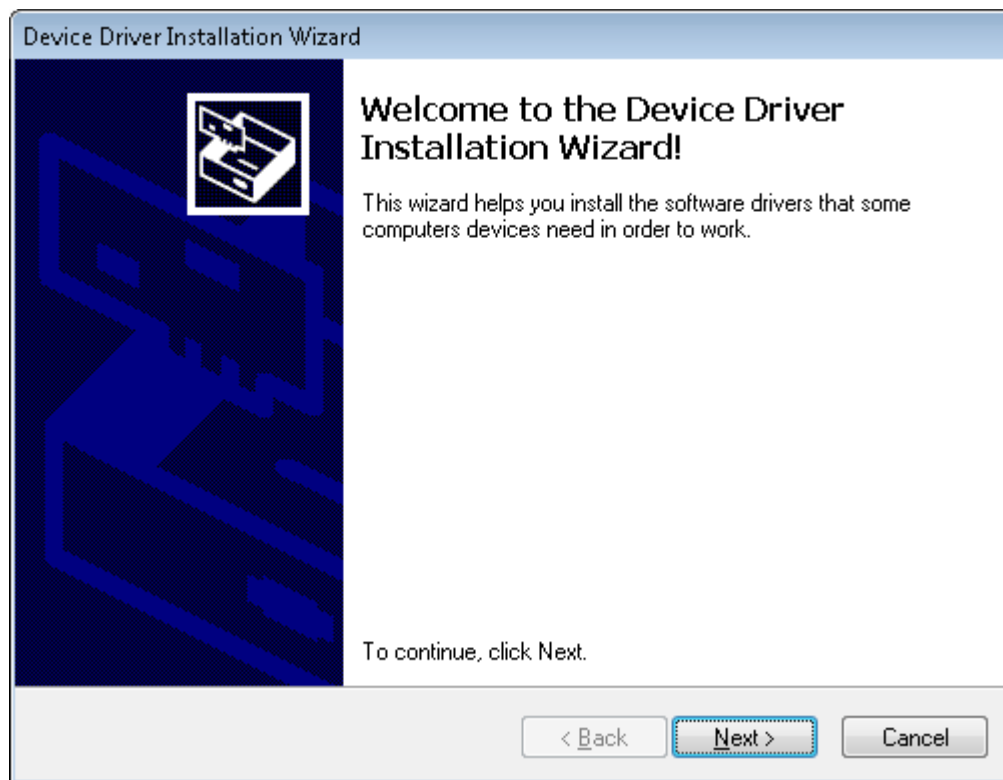


Figure 19. Driver Installation Wizard

16. The License Agreement appears on screen as shown in [Figure 20](#).
17. Read through the License Agreement carefully and enable the "I Accept this Agreement" radio button and Click on **Next**.

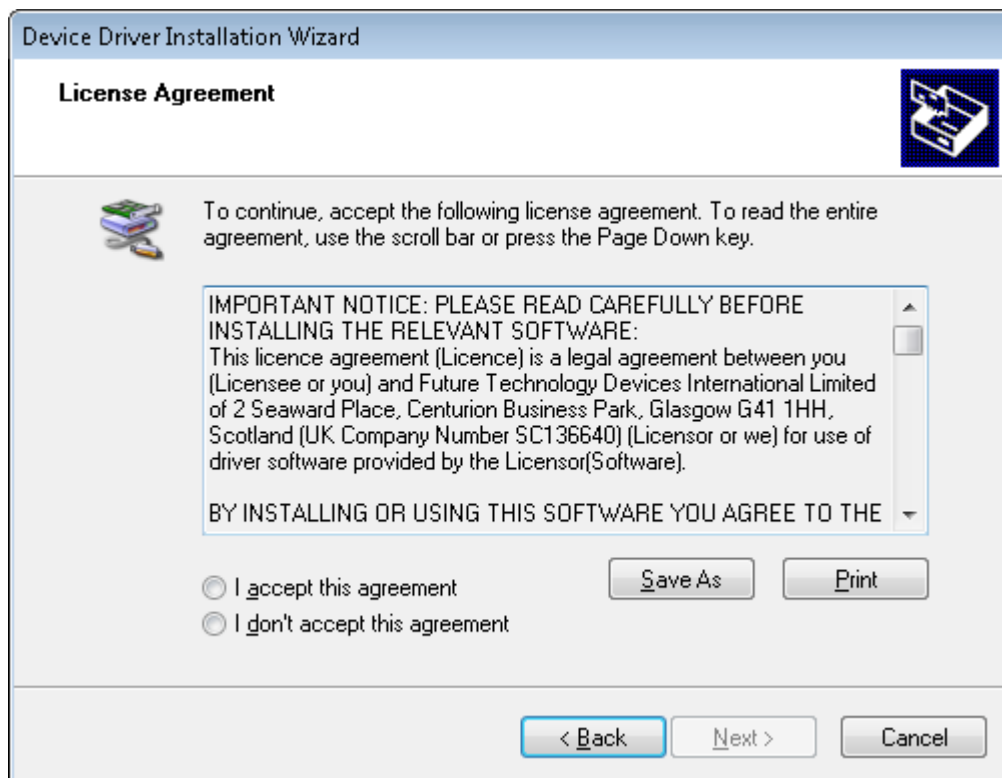


Figure 20. License Agreement for FTDI Driver

18. Click **Finish** to complete the Driver Installation.

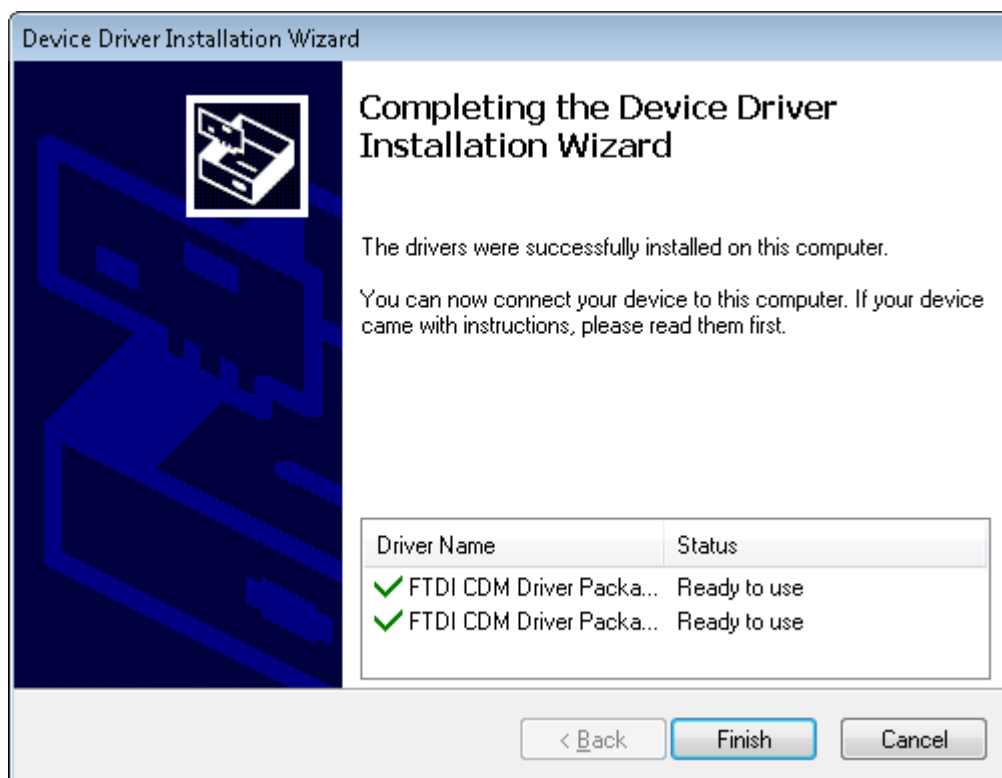


Figure 21. Driver Installation Completion

19. [Figure 22](#) appears denoting the completion of DRV8803/04/05/06 EVM GUI Installation. Click **Finish**.

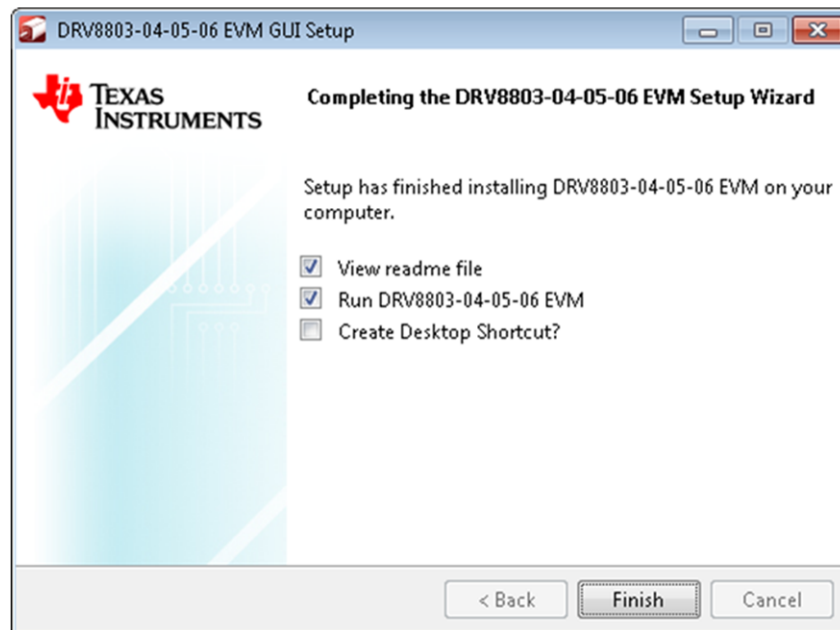


Figure 22. Installation Complete

20. A Readme window as shown in [Figure 23](#) appears displaying the link for LV 2014 RTE.

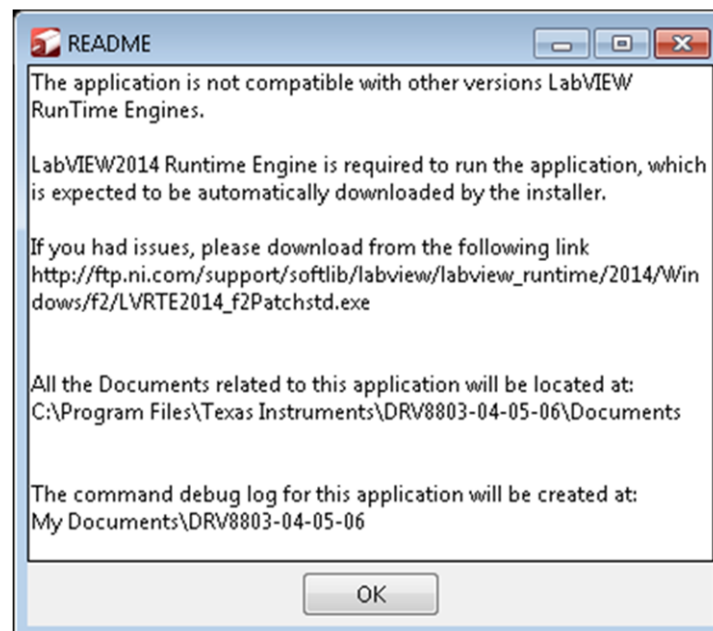


Figure 23. Readme Window

WARNING

The DRV8803/04/05/06 EVM GUI requires the LabVIEW Run-Time Engine 2014 to be installed before the GUI executes. Please note the application is not compatible with other versions of LabVIEW Runtime Engine.

You can download National Instruments LabVIEW Run-Time Engine 2014 from the below link:

[LabVIEW Run-Time Engine 2014](#)

NOTE: DRV8803/04/05/06_EVM GUI executable has been built in LabVIEW 2014 (32-bit) version, and it expects the LabVIEW Run-Time Engine version to be LabVIEW Run-Time Engine (32-bit version).

4 The Windows Application

The DRV8803-04-05-06 EVM Windows application is the software counterpart for the DRV8803/04/05/06. It allows the PC to connect to the MSP430F2617 microcontroller through an USB interface chip. The Graphical User Interface (GUI) has been designed to allow for all of the DRV88xx device's functionality to be tested without having to intervene with the hardware, except for the proper configuration of jumpers, when needed. Figure 24 shows the DRV8803-04-05-06 EVM High-Level Page.

The GUI has four High-Level Pages:

- DRV8803
- DRV8804
- DRV8805
- DRV8806

It contains frames with GPIO control for the DRV8803-04-05-06 control signals, stepper motor control for start/stop and speed, and Acceleration control.

4.1 DRV8803

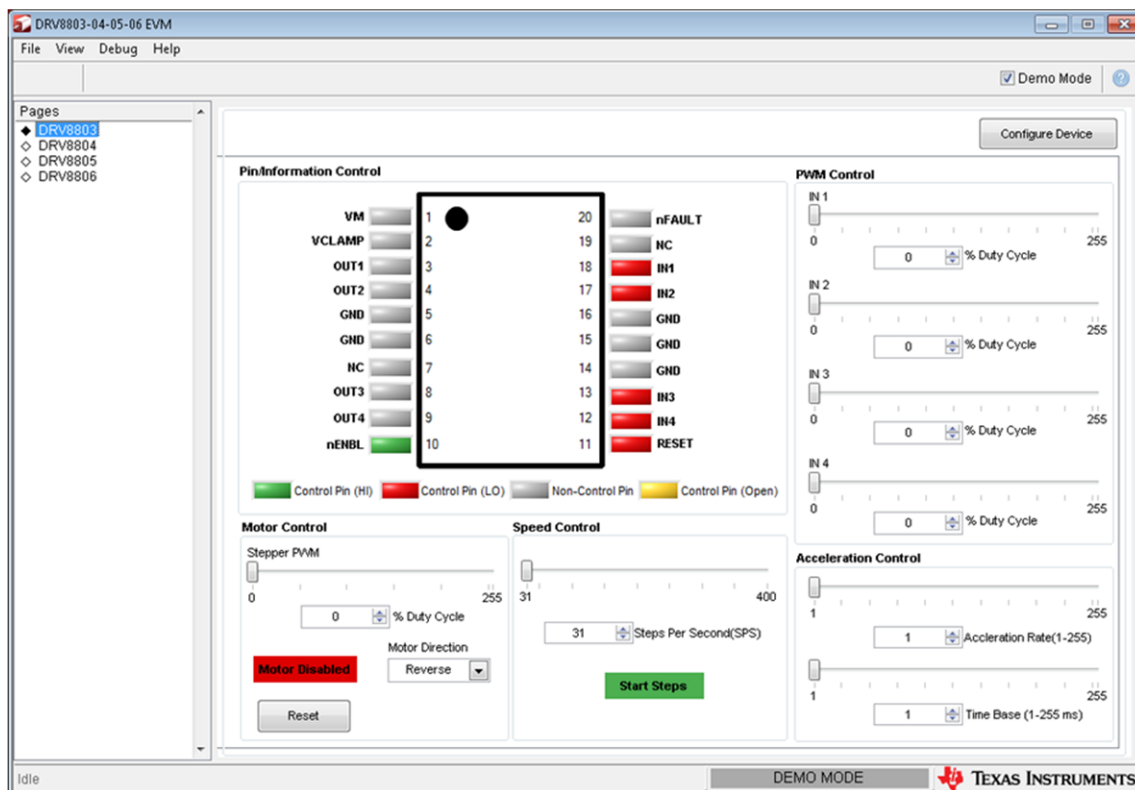


Figure 24. DRV8803 Tab

The DRV8803 tab contains a diagram of the device which includes pin control and information about control signals including: nENBL, RESET, IN1, IN2, IN3, and IN4. It also includes corresponding controls to these pins (Enable Motor button, Reset button, and INx PWM and Duty Cycle number boxes).

Stepper control is implemented by controls in group boxes including: Motor Control, Speed Control, and Acceleration control.

4.2 DRV8804

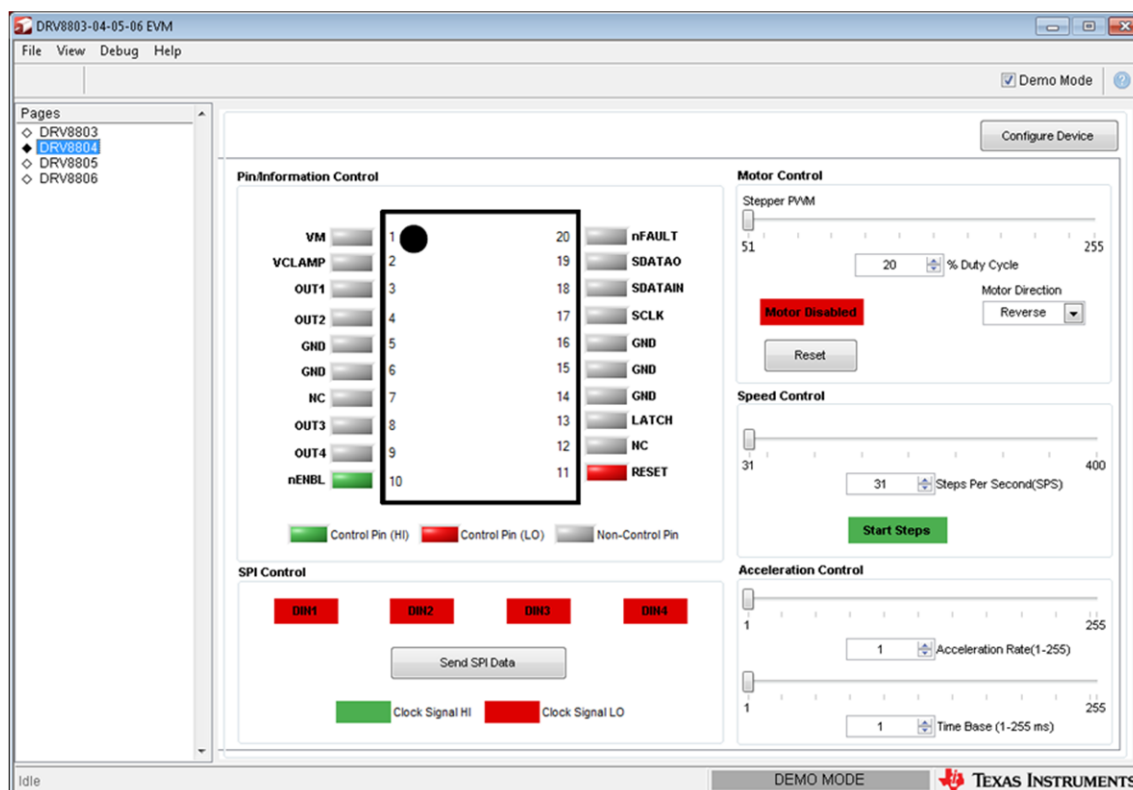


Figure 25. DRV8804 Tab

The DRV8804 tab contains a diagram of the device which includes pin control and information about control signals including: nENBL, and RESET. It also includes corresponding controls to these pins (Enable Motor button, and Reset button).

Stepper control is implemented by controls in group boxes including: Motor Control, Speed Control, and Acceleration control.

The DRV8804 tab also contains SPI package control in group box SPI Control.

4.3 DRV8805

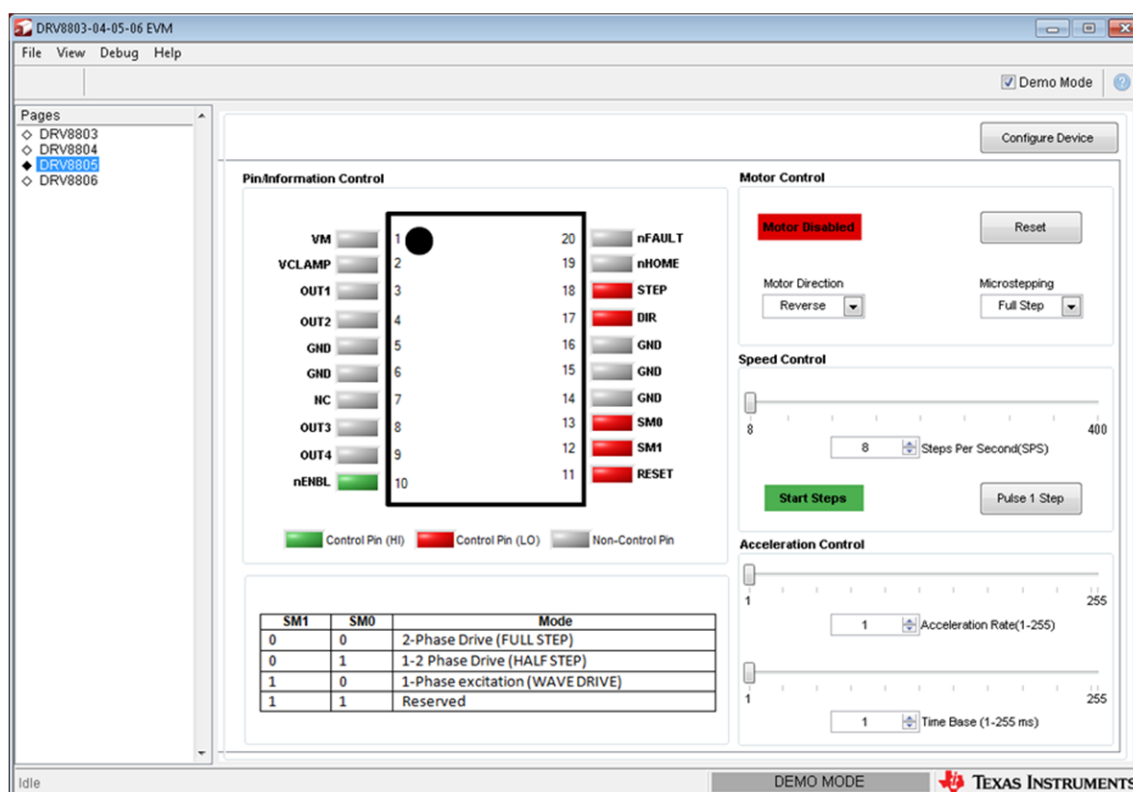


Figure 26. DRV8805 Tab

The DRV8805 tab contains a diagram of the device which includes pin control and information about control signals including: nENBL, RESET, SM1, SM0, DIR, and STEP. It also includes corresponding controls to these pins (Enable Motor button, Reset button, Motor Direction radio buttons, Microstepping radio buttons, and Pulse 1 step button).

Stepper control is implemented by controls in group boxes including: Motor Control, Speed Control, and Acceleration control.

The DRV8805 tab also contains a look up table detailing the functionality of pins SM1 and SM0.

4.4 DRV8806



Figure 27. DRV8806 Tab

The DRV8806 tab contains a diagram of the device which includes pin control and information about control signals. Clicking on the nENBL and RESET will toggle the respective control signal state.

The DRV8806 tab also contains SPI packaging control in the SPI Control box. Since DRV8806 is based around a read back SPI which offers diagnostics information, said output is made available at the Fault Diagnostics group box.

4.5 GUI Description/Functionality

4.5.1 The Menu Bar

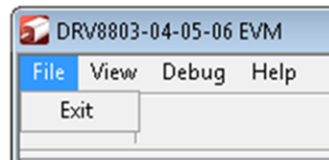


Figure 28. Menu

The menu at the top of the application offers a series of quick options for how the COM port is to behave, and an option to view functional block diagrams of the respective chip. Please refer to the datasheet for the most updated functional block diagrams.

File:

Exit - Terminates the application.

View:

Schematic - which takes the user to a menu of different device schematics that are available for viewing.

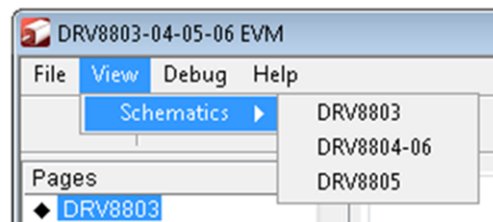


Figure 29. View

This will take you to a window resembling the following:

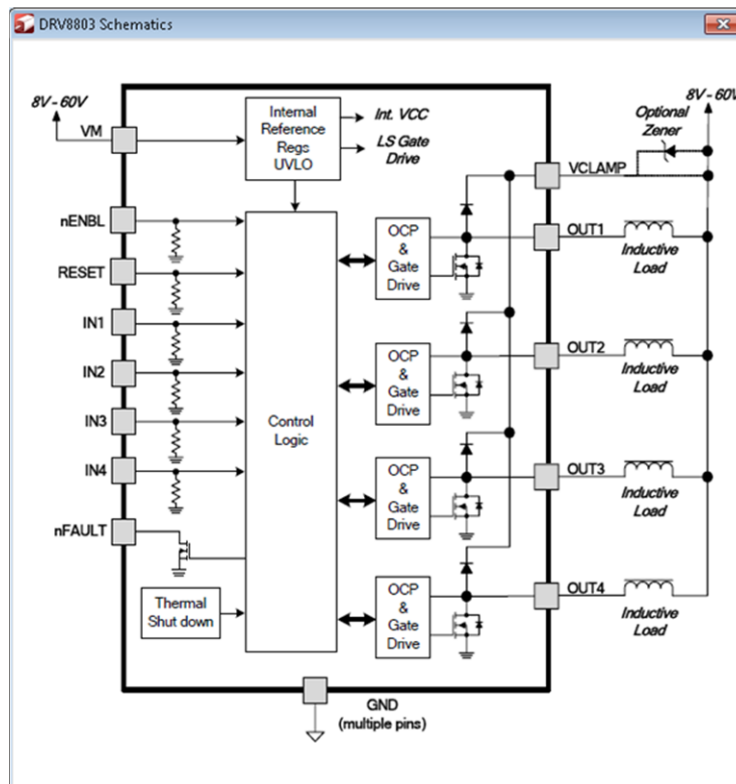


Figure 30. Schematic Window

Debug:

The Debug option can be used for the following operations.

Debug - By selecting the Demo in the submenu, the GUI will run in simulation mode, and by unselecting it, the GUI will run in connected mode.

Debug Log -

The Debug log option will enable to log all the activities of the user. If that is not selected, only the high-level operations will be logged.

Log to File -

The log to file submenu is used to log the GUI activities to a log file that is specified.

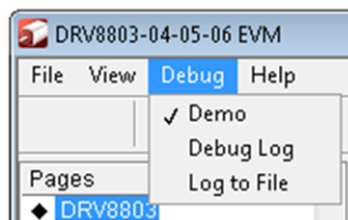


Figure 31. Debug Window

Help:

Clicking the About in the Help Menu.

About -

The About Page provides the details like the Name of the GUI, GUI version, Supported OS and Copyright Information.

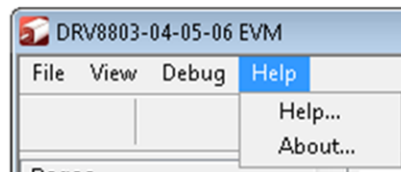


Figure 32. Help Window



Figure 33. About Window

4.6 DRV880x GPIO Control Signals

Once the application is communicating with the interface board, the control signals can be actuated by clicking on pins to send each control hi (green), lo (red), or in special cases open (orange). Each tab will have a different set of control signals depending on the device being interfaced with.

Functionality of control signals is identical across the platform. A green pin translates to a HI level on the respective control signal, a red pin translates to a LO level on the respective control signals, and in special cases, an orange pin translates to an open signal, and a gray pin translates to a non-control pin.

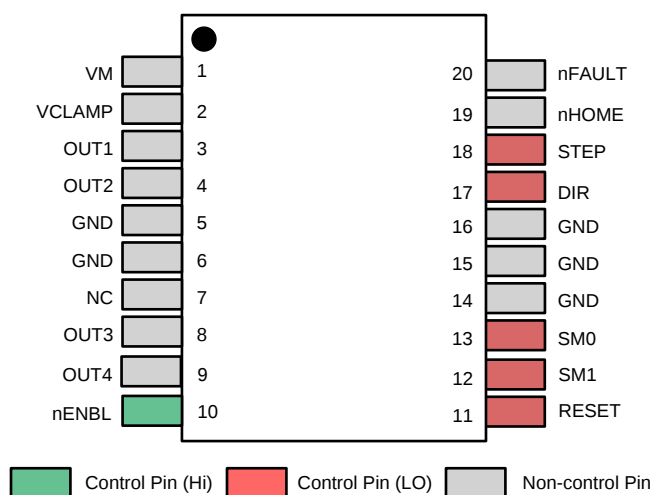
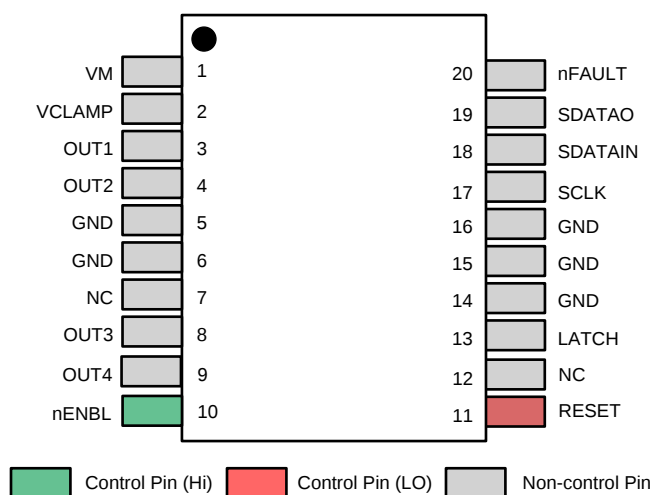
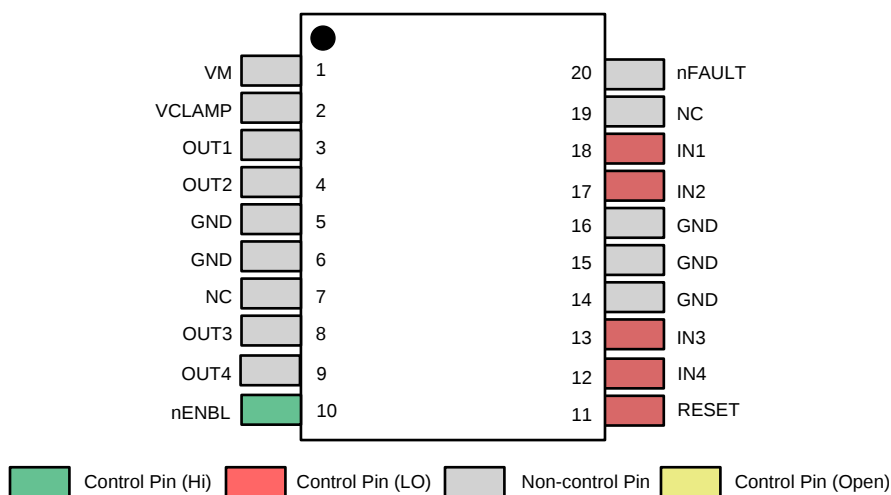


Figure 34. GPIO Control Signals

nENBL – Control appears on all three devices. Toggling it LO (red) enables the chip, and toggling it HI (green) disables the chip. Automatically toggles in correspondence to the Enable Button on all three chips (See motor control).

Reset – Control appears on all three devices. Must be toggled LO (red) in order for the device to operate. If toggled HI (green) and then LO (red) it resets the chip. Automatically toggles in correspondence to Reset Button (See motor control).

INx – Control appears on the DRV8803 device. Toggling HI (green) sets PWM of input X to a duty cycle of 100%. Toggling LO (red) sets PWM of input X to a duty cycle of 0%. Automatically toggles in correspondence to INx sliders and % duty cycle combo boxes (See PWM control). The pin will show orange if the user selects anything other than a 0% of 100% duty cycle. If user clicks pin to toggle from orange the pin will go LO (red).

STEP – Control appears on the DRV8805 device. Toggling LO (red) and then HI (green) will enable a bipolar stepper motor to step once. Toggles in correspondence to Pulse 1 Step button (See speed control).

DIR – Control appears on the DRV8805 device. Toggling HI (green) will allow the motor to operate in the forward direction, while toggling LO (red) will allow the motor to operate in the reverse direction. Automatically toggles in correspondence to Motor Direction radio buttons (See Motor Control)

SMx – Control appears on the DRV8805 device. Toggling these pins selects the mode that the motor is operating in (microstepping – full, half, wave mode, reverse). The following look up table shows the combinations and their results:

SM1	SM0	Mode
0	0	2-phase drive (full step)
0	1	1-2 phase drive (half step)
1	0	1-phase excitation (wave drive)
1	1	Reserved

Figure 35. SMx

Automatically toggles in correspondence to microstepping radio buttons (see motor control).

4.7 PWM Control

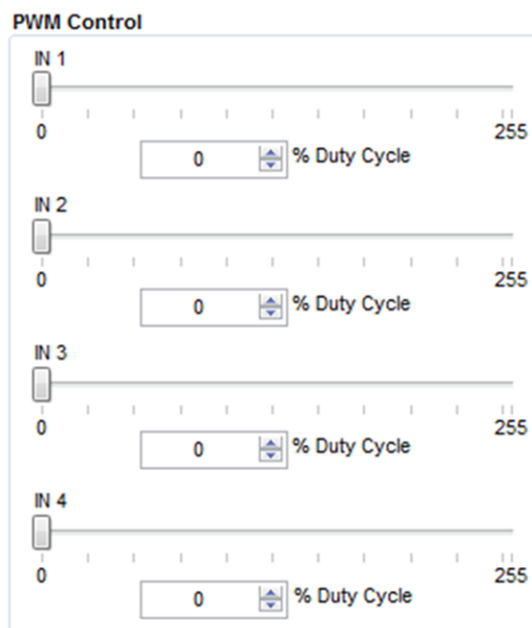


Figure 36. DRV8803 PWM Control

The DRV8803 can be utilized to control DC motors. For the purpose to control DC motor speed, a slider is provided which applies a PWM to each respective input. The PWM slider consists of an 8 bit number so positions from 0 to 255 are obtained. The MSP430 directly transforms this 8 bit number into the respective duty cycle. PWM frequency is around 31.25 KHz.

When the slider bar is moved across, the Duty Cycle indicator is updated accordingly. When the duty cycle is set from the selector, the slide bar is updated accordingly. The resulting duty cycle is an integer number between 0 and 100 and it is computed according to the equation:

$$\% \text{Duty Cycle} = \text{PWM} / 255 \times 100 \quad (1)$$

Each corresponding pin on the chip indicator is toggled automatically. If the duty cycle is 0% the corresponding chip is toggled to LO (red). If the duty cycle is 100% the corresponding pin is toggled to HI (green). If the duty cycle is set to anything besides 100% or 0% the corresponding pin is toggled (orange).

4.8 Motor Control

The Windows Application, in conjunction with the MSP430F2617 microcontroller, utilizes a series of timers to coordinate the rate of steps sent to the device. Once all the control signals are configured accordingly, the motor is ready to be turned.

The DRV8803/04/05 Customer EVM allows for the possibility of coordinating step rates such that accelerating and decelerating profiles are achieved. Both acceleration and deceleration are controlled by the same parameters Acceleration Rate and Time Base.

When the motor starts, the controller will accelerate the motor in order to reach the Pulses Per Second speed. Acceleration Rate is an 8 bit number (0 to 255) that gets added to the current Pulses Per Second speed and Time Base is an 8 bit number (0 to 255) that specifies how many milliseconds will elapse from one speed increase to the next. Once the specified Pulses Per Second has been achieved, the acceleration stops.

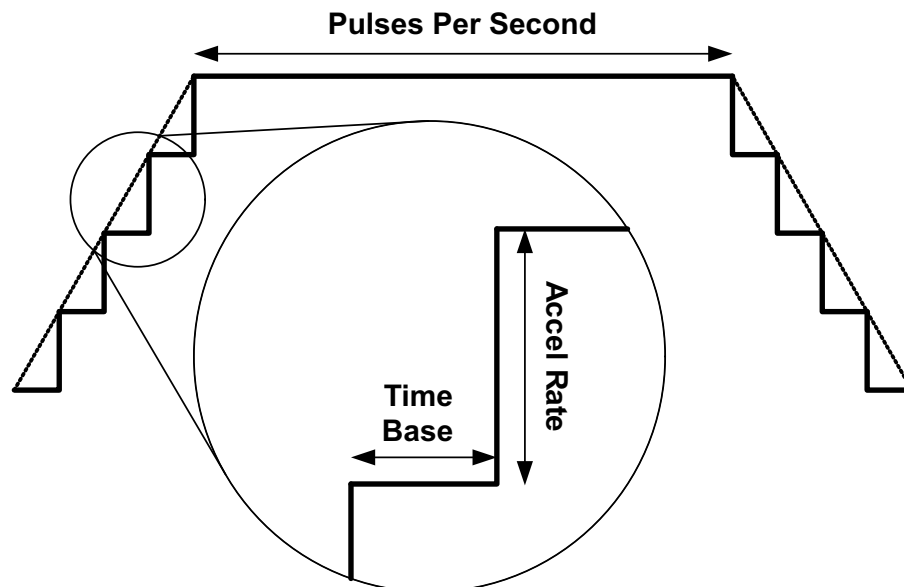


Figure 37. Motor Control

Same as described before but inversed, happens when the motor is commanded to stop.

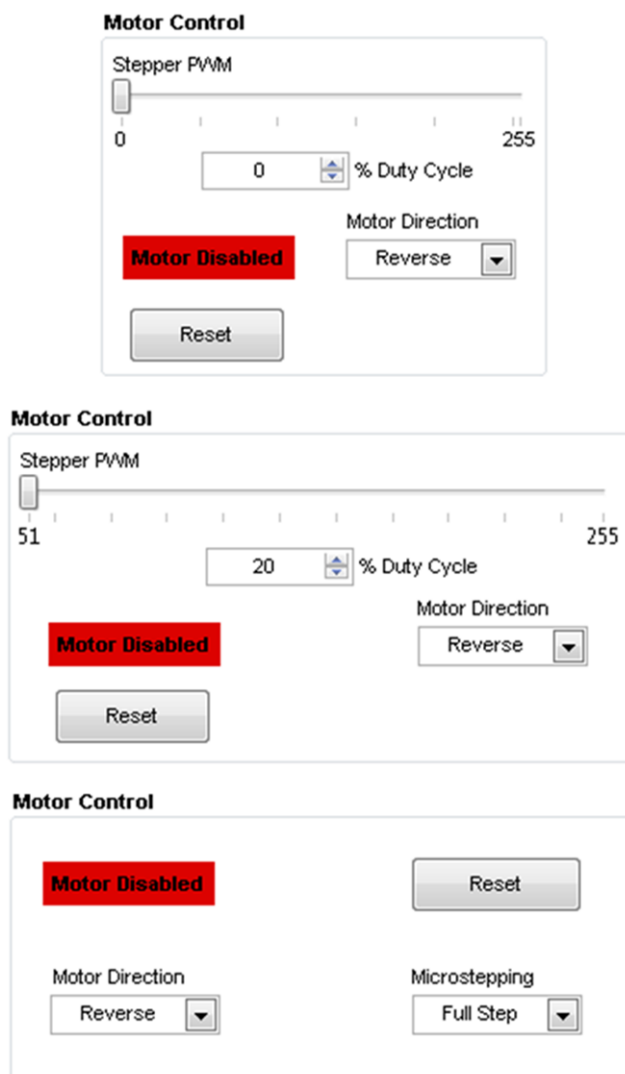


Figure 38. DRV88003/04/05 Motor Control Windows

Stepper PWM Slide Bar – Appears on the DRV8803 and DRV8804. On the DRV8803 this sets all of the INx PWM slide bars to whatever the Stepper PWM slide bar is set to. This controls the PWM rate of the stepper. On the DRV8804, the stepper PWM controls the PWM rate of the stepper and calculates the corresponding duty cycle which updates automatically as the slider is moved. If the user sets the % duty cycle, the position of the slider is updated automatically.

Enable Motor Button – Appears on all three devices. This enables the motor and automatically toggles the corresponding pin (see DRV88xx GPIO signals).

Reset Button – Appears on all three devices. This automatically sends the reset pin either HI (green) then LO (red) or LO (red) then HI (green) effectively resetting your device. (Reset pin must be LO for motor to operate – see DRV88xx GPIO signals).

Motor Direction Radio Buttons – Appears on all three devices. Always defaults to reverse direction on default. Determines whether the motor is operating in forward or reverse direction. Automatically toggles corresponding direction pin in the case of the DRV8805 (see DRV88xx GPIO signals).

Microstepping – Appears on the DRV8805. Determines the mode that the motor is operating in and automatically toggles the corresponding SMx pin (see DRV88xx GPIO signals).

4.9 Speed Control

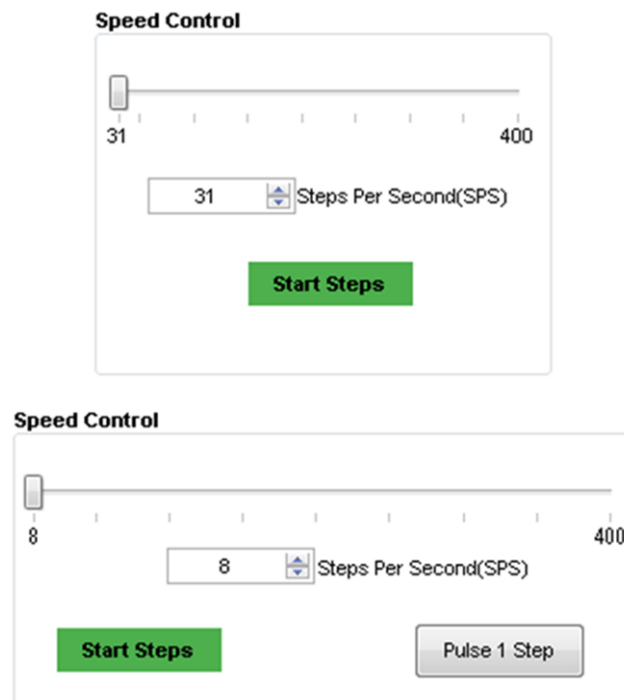


Figure 39. DRV88003/04/05 Speed Control Windows

Speed Control/Start Steps - The speed is set by either using the slide control, or selecting the Steps per Second value in the Steps Per Second number box. Using either control the other will be updated automatically. Pressing the “Start Steps” button, will start the timer and the motor will step at the rate specified by the Steps Per Second number Box/Slider. Once the “Start Steps” button is pressed it becomes the “Stepping (Pause Steps)” button. Press the “Stepping (Pause Steps)” button to stop the stepper motion. The Steps Per Second rate is updated automatically anytime the slider of the number box is used.

Pulse 1 Step – Control only applies to the DRV8805. Clicking this button will step the motor once, and also toggle the corresponding STEP pin HI (green) then LO (red) or LO (red) then HI (green) (see DRV88xx GPIO signals). A step takes place when the pin goes from LO (red) to HI (green)

4.10 Acceleration Control

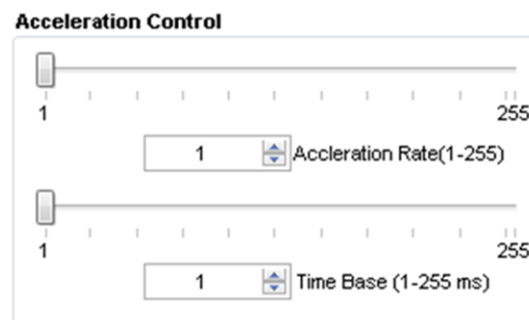


Figure 40. DRV88003/04/05 Acceleration Control Windows

Each respective control (slide bar or number box) automatically updates the other when it is being used.

When the motor starts, the controller will accelerate the motor in order to reach the Steps Per Second speed (see Speed Control). Acceleration Rate is an 8 bit number (0 to 255) that gets added to the current Pulses Per Second speed and Time Base is an 8 bit number (0 to 255) that specifies how many milliseconds will elapse from one speed increase to the next. Once the specified Pulses Per Second has been achieved, the acceleration stops.

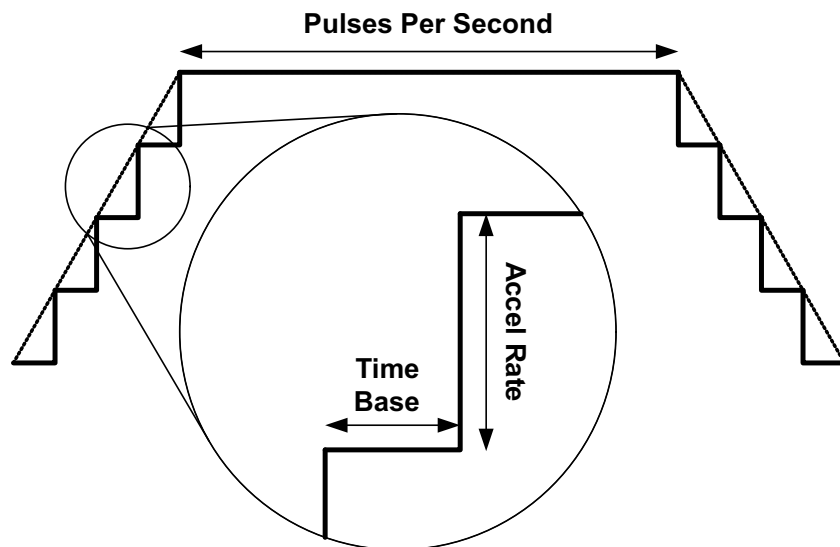


Figure 41. Acceleration Control

Same as described before but inversed, happens when the motor is commanded to stop.

Acceleration profile automatically updates when either slide bar or number box is changed.

4.11 Diagnostic Output

The DRV8806 will return data on every SPI transaction. This data contains valuable information as to whether each output was subjected to a fault or not. If a fault was present, the logic state is the SPI data packet is HI (green), whereas no fault present are represented by LO (red).

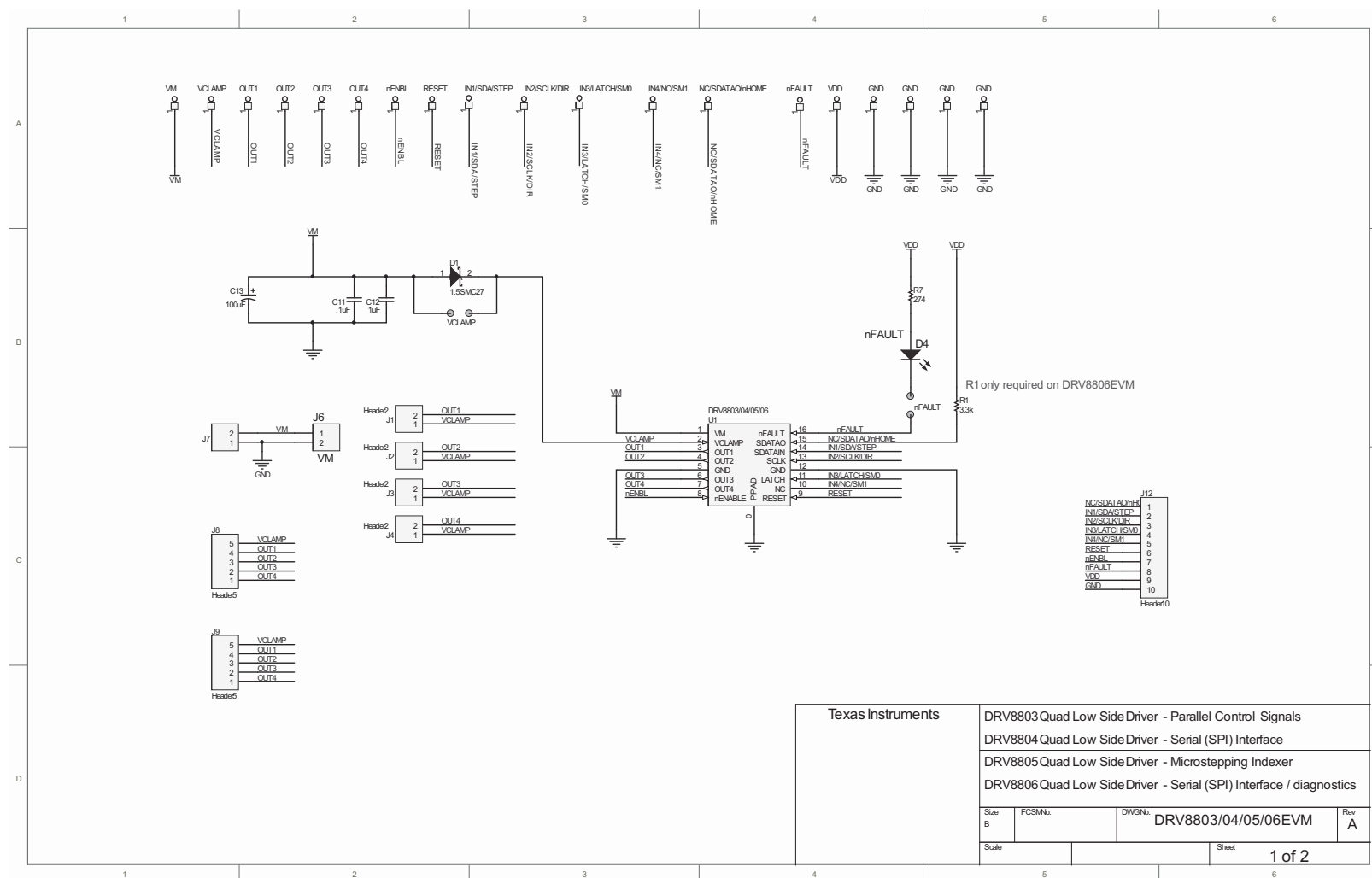
Faults generated on a per output basis could be caused by an open load or by over current. User must refer to the device's datasheet for more details on how the fault scheme operates.

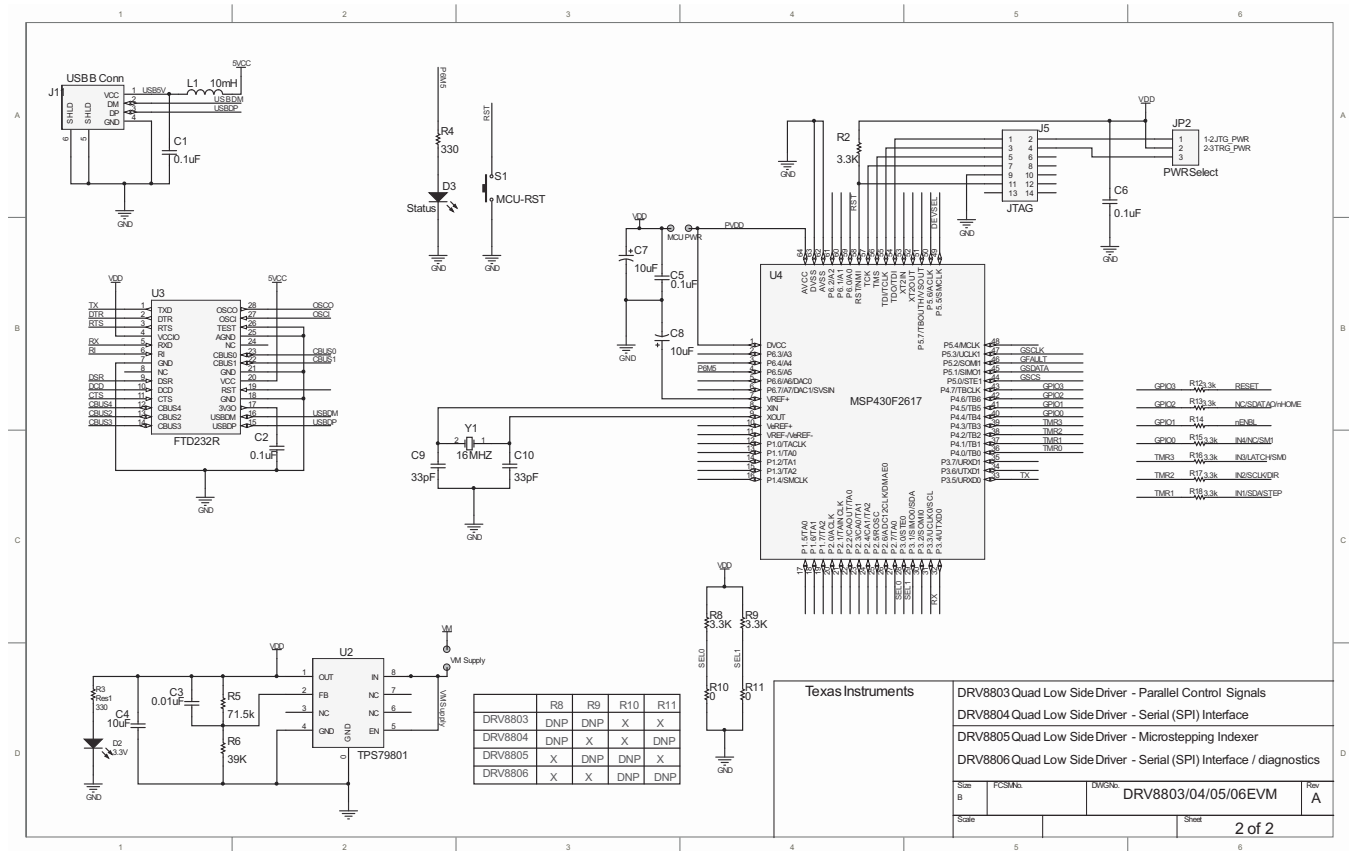
4.12 Controlling the EVM Using External Signals

If the user wishes to run the IC using their own external signals/MCU, this can be achieved easily. The only thing the user needs to do is powered down the MCU using the jumper JP4 labeled MCU_PWR on the EVM. This removes the power to the MCU and allows the user to control the input signals using the header J12. The silkscreen can be used to identify the various signals. The resistors R12-18 are meant to protect the MCU from 5V signals (if applied) to the input pins. The user can de-solder them for better performance. Please note that once these resistors are de-soldered, the user cannot use the on-board MCU.

5 Schematics

Schematics for the DRV8803/04/05/06 can be found on the following pages.





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