# SHC Series
# Standalone Controllers

- *Compact size, standalone motion controller*
- *Supports ±10V command or Pulse and Direction command*
- *Dedicated I/Os for each axis (limits, fault, enable, etc.)*
- *Easy to use programming language (3 letter script)*
- *Supports Visual C++, Visual Basic and other applications through DCOM interface*
- *Suitable for all types of servo motors and stepper motors*
- *Error mapping for high precision applications*
- *Multiple controllers can be connected through CAN bus for distributed control*

# SHC95 Series

- PID or PIV control filters with velocity and acceleration feed forward
- High sampling rate
- Position capture and compare by hardware
- Simultaneous execution up to 10 macro threads

## Datasheet

| Specifications \ Model | SHC95-2AS | SHC95-4AS |
|---|---|---|
| Number of axis | 2 (Servo or Stepper) | 4 (Servo or Stepper) |
| Quadrature decoders | 4 (30MHz) | 4 (30MHz) |
| Analog outputs | 2 (13-bit, ±10V) | 4 (16-bit, ±10V) |
| Analog inputs | 2 (12-bit, ±10V) | 4 (12-bit, ±10V) |
| Digital outputs | 4 General Purpose + Inhibit per axis | 8 General Purpose + Inhibit per axis |
| Digital inputs | 8 General Purpose + RLS/FLS/Fault per axis | 16 General Purpose + RLS/FLS/Fault per axis |
| Pulse & Direction outputs | Up to 2 (1MHz) | Up to 4 (1MHz) |
| Position capture inputs | 2 | Up to 4 (Shared with General Purpose Inputs) |
| Position compare outputs | 2 | Up to 4 (Shared with General Purpose Outputs) |
| Communication / Expansion port | RS232, CAN, Ethernet | RS232, CAN, Ethernet |
| Sampling rate, kHz | 8kHz | 16kHz |
| Programming languages | Script (up to 2 threads) | Script (up to 10 threads) |

## Sample Program

```
...
...
...
@if(XIP & 1)       'If bit 1 of digital input port is active
  XAC=60000;   'Set X-axis acceleration
  XDC=60000;   'Set X-axis deceleration
  XSP=30000;   'Set X-axis speed
  XAP=51898;   'Set X-axis destination (absolute position)
  XBG;         'Begin X-axis motion
@endif
...
...
...
```