



# Alfa MD-01/02 Controller



Revised 12 July 2023  
<http://www.alfaradio.ca>

This manual is for use with units sold by Alfa Radio Ltd. of Edmonton, Alberta, Canada, on or after July 12, 2023 and are equipped with firmware version 2.0 or higher. Units sold by others may have different firmware and may operate from different voltages.

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## 1 Introduction

MD-01/02 is an electronic controller used for turning rotators. It is a multifunctional device, allowing for various combinations of settings. The Controller may be connected to two single rotators (e.g. two Azimuth rotators) or one Azimuth and Elevation rotator and operates with direct current motors. The MD-01 and MD-02 controllers are identical on the inside. The only difference is the case: the MD-01 is in a 19" compatible rack-mountable enclosure, whereas the MD-02 is in a desk-mountable enclosure.

Firmware version v2.0 has improved control algorithms -

- has implemented satellite mode (SATELLITE MODE), dedicated to tracking satellites in LEO orbit, increasing the smooth operation of motors and

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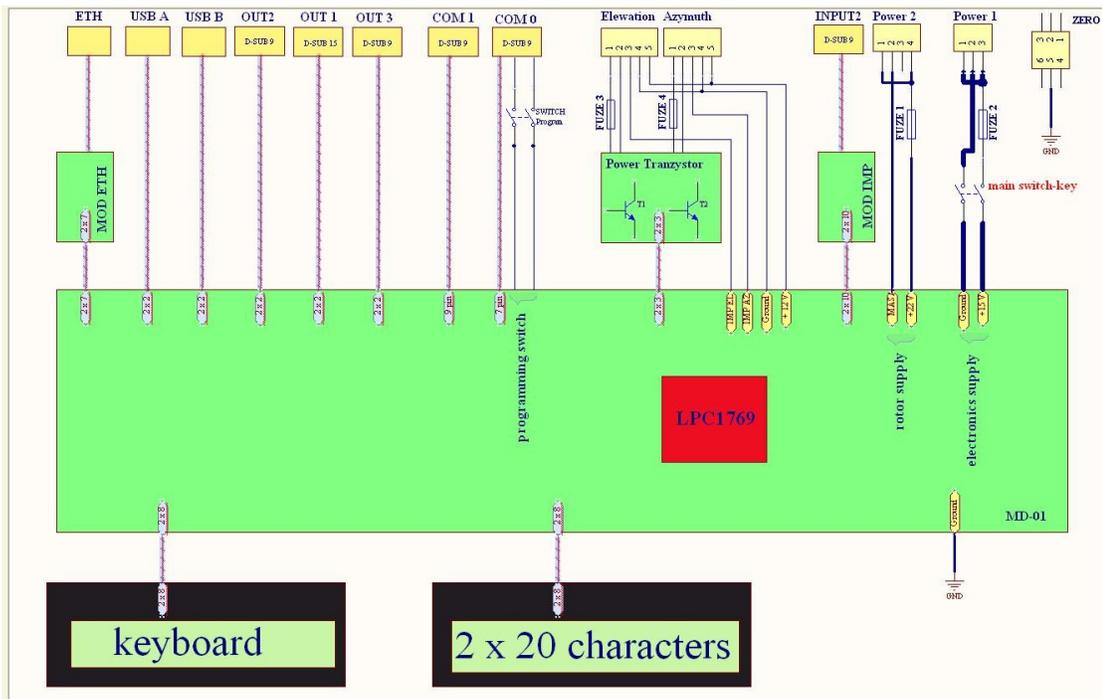
reducing engine loads, gearboxes and relays (note: at the expense of a slight reduction in accuracy) only for rotors with HR sensors,

- optimizes start and stop cycles thanks to the calibration mode of minimum engine power (CALIBRATION).



To verify the installed firmware version before turning on the device, press and hold the F and F2 buttons at the same time, then while holding, turn on the device until the software version is displayed. The installed firmware version is also displayed for a few seconds after starting the device.

## 1.1 Block diagram



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## 1.2 Features of the MD-01/02 Controller

Supply voltage for controller electronics 13.8 to 15 VDC ( $I_{max} = 2$  Amps)

Supply voltage for rotators 14 to 18 VDC ( $I_{max} = 20$  Amps) except BigRAS/HR ( $I_{max} = 12A$ ) or other voltage is specified in the description of the controlled device.

The maximum current of a single motor is up to 20 Amps.

2 x RS-232 ports

1 x USB host port

1 x USB device – visible in the system as a virtual COM port.

1 x Optional RJ-45 Ethernet port.

## 1.3 Photos and description

### 1.3.1 Front MD-01



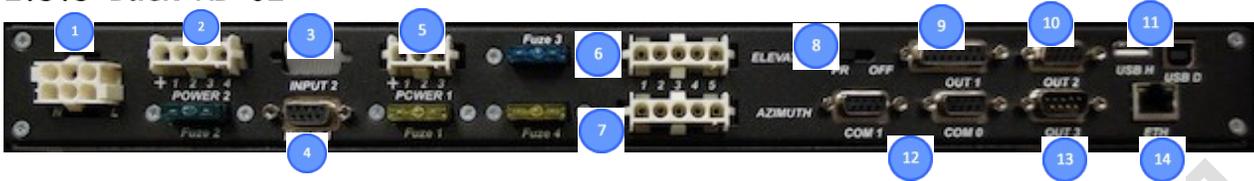
1. Keyboard.
2. 2x20 characters display.
3. Switch-key.

### 1.3.2 Front MD-02

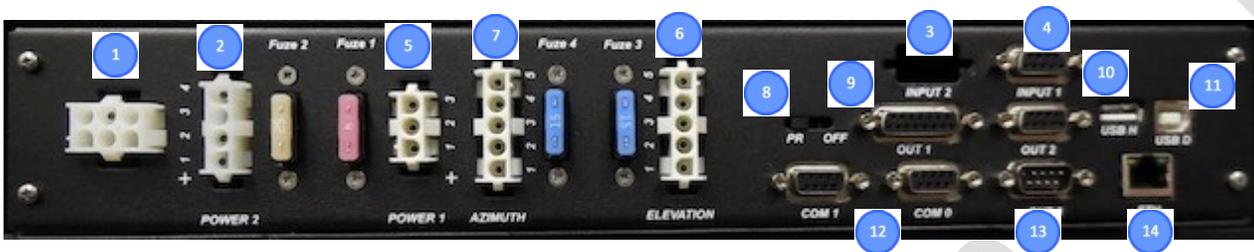




### 1.3.3 Back MD-01



### 1.3.4 Back MD-02



1. Plug-in socket for Ground Connection (the remaining PINS are not provided).
2. Rotator motor supply input (FUSE at 40 Amps Max). On older units this connector may be labeled Input 1
3. Planned future location for connecting modules, e.g. CAN, RS-485, RS-422 or analog inputs.
4. Sensor Input for systems with one or two Hall effect sensors.
5. Power Supply input for Controller Electronics (FUSE 2A). On older units this connector may be labeled Input 2
6. Supply outputs for Elevation Rotator. Pins 1 and 2 are connected to the Rotator motor and pins 3 and 4 are connected to the mechanical sensor on RAU, RAK, Rael and RAS rotators. The motor output is FUSED at 20 Amps maximum depending on the motor used.
7. Supply outputs for Azimuth Rotator. Pins 1 and 2 are connected to the Rotator motor and pins 3 and 4 are connected to the mechanical sensor in RAU, RAK, Rael and RAS rotators. The Motor output is FUSED at 20 Amps maximum depending on the motor used.
8. Switch used to update the controller software (FIRMWARE). To update the software use COM 0 (item 12) with the switch in the OFF position. Normal mode of the controller is when the switch is in the PR position.
9. Universal output – Future use to connect external relays. When implemented, the controller will have the function of an antenna change-over switch.
10. I2C output – used to control SW-01 switch.
11. USB HOST port (type A plug) and DEVICE port (type B plug).
12. RS-232 ports – COM 0 and COM 1. COM 0 is also used to update the controller software (see item 8).
13. Input used for a specially designed (RAS) mouse.

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14. Network input RJ45 (Optional ETHERNET Board).

## CONNECTOR PIN LAYOUT

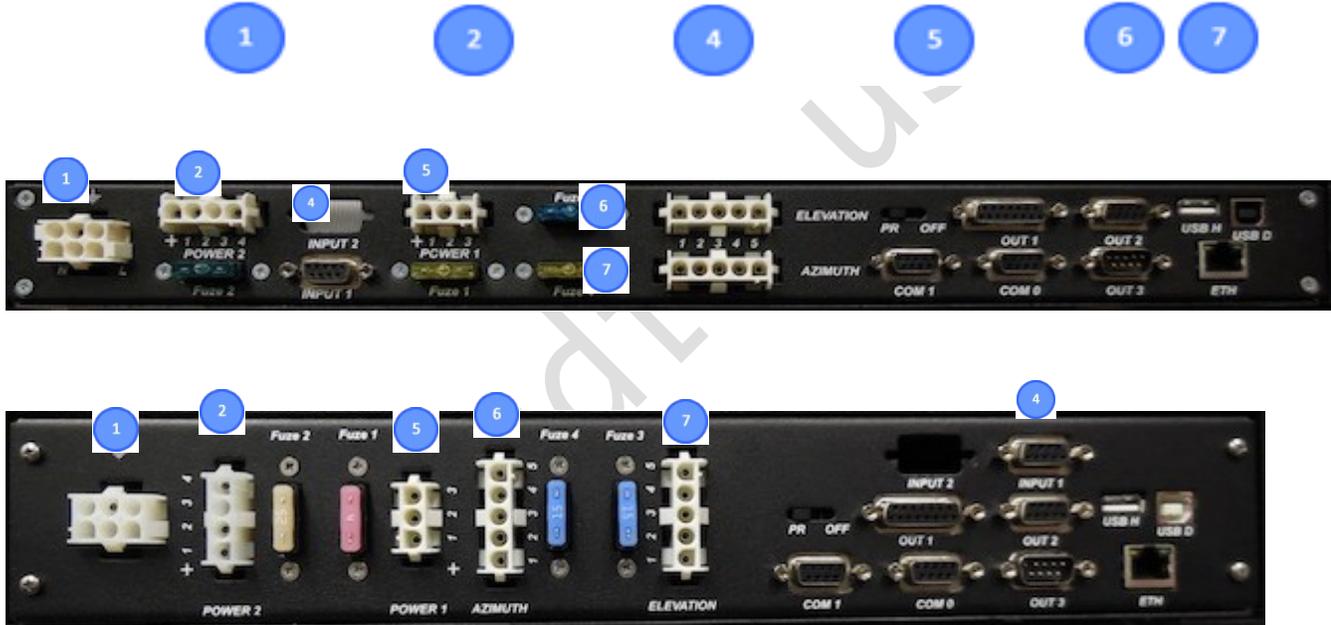
PIN	FUNCTION
1	NC
2	NC
3	NC
4	NC
5	GROUND
6	NC

PIN	FUNCTION
1	U1 +22 VDC
2	GROUND
3	NC
4	U1 +22 VDC

PIN	FUNCTION
1	NC
2	IN imp 2 EL
3	IN imp 1 EL
4	IN imp 2 AZ
5	IN imp 1 AZ
6	12 VDC
7	12 VDC
8	GROUND
9	GROUND

PIN	FUNCTION
1	U2 +15 VDC
2	GROUND
3	U2 +15 VDC

PIN	FUNCTION
1	MOTOR
2	MOTOR
3	IN IMP
4	GROUND
5	+12 VDC



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## 2 INSTALLATION MD-01/02

When supplying power to the MD-01/02 controller, two power cables are required.

The first cable has a 4-pin connector, which should be plugged into the **Power 2** connector on the controller. **This cable is used to supply power to the Rotator Motors.** The cable should be connected to a power supply that can provide from 13.8 to 24 volts DC at a minimum of 20 Amps. Wire gauge for the cable should be at least #14.

**CAUTION.** In the 4-pin connector, Pin 3 is not equipped and not used.

The second cable has a 3-pin connector, which should be plugged into the **Power 1** connector on the controller. **This cable is used to supply power to the controller electronics.** The cable should be connected to a power supply that can provide 13.8 to 15 volts DC at a minimum of 2 Amps. The power supply should not exceed 15 volts, as it could damage the controller. Wire gauge for the cable should be at least #18.

It is highly recommended that a third cable be made. This cable consists of a single wire of the largest gauge that can fit in the connector. This wire has a 6-pin connector, which should be plugged into the ground connector on the controller and the station ground.

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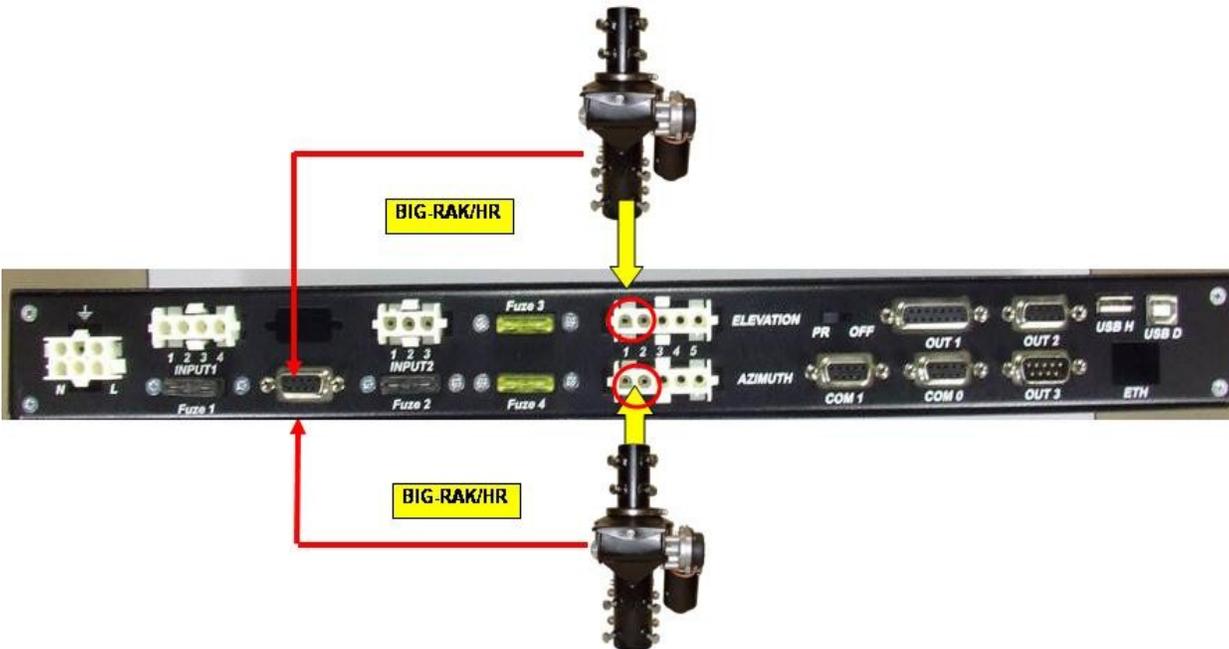


There are a number of different combinations of the MD-01/02 controller and AlfaSpid Rotators as shown below.

## MD-01/02 controller and BIG-RAS/HR



## MD-01/02 controller and one or two BIG-RAK/HR



## MD-01/02 controller and RAS or BIG-RAS

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MD-01/02 controller and one or two RAK, BIG-RAK, RAU or Rael



**Note:** The pictures on this and the previous page show older units. Refer to sections 1.3.3 and 1.3.4 for current connector labeling

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### 2.1 Wiring for BIG-RAS/HR and/or BIG-RAK/HR

See Applicable Alfa Radio Rotator Manual

### 2.2 Wiring for BIG-RAK, RAK, RAU or RAEL

See Applicable Alfa Radio Rotator Manual

### 2.3 Wiring for BIG-RAS or RAS

See Applicable Alfa Radio Rotator Manual

### 2.4 MD-01/02 connectors

Should additional connectors be needed, the following pictures show the part numbers for the various connector shells and pins used with the MD-01/02 controller. These connectors are standard Tyco Electronics Corp. Mate-N-Lock connectors and are available at most electronics suppliers.

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## Mate-N-Lock Pins



## Mate-N-Lock Housings



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## Table of MD-01/MD-02 connectors

Number of pins	Plug Part Number Natural colour	Plug Part Number White Flame Retardant	Number used by MD-01/MD-02	
3	1-480700-0	350766-1	1	
4	1-480702-0	350779-1	1	
5	1-480763-0	350809-1	2	
6	1-480704-0	350715-1	1	
				Wire Size
Pins	Spid Recommended	926894-1	18	20 - 14
	Alternate	350547-1	18	20 - 14
	Alternate	640309-3		12 - 10
Socket		350550-1		20 - 14

Information from TE Connectivity "MATE-N-LOK Instruction Sheet 408-7714

## Connectors for sense connections to /HR Rotators



Mode 25-728-0



DB9P



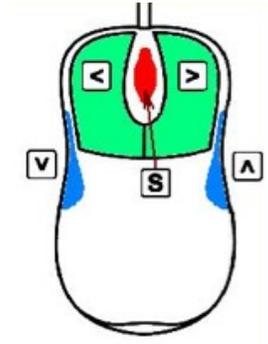
DB9 Hood

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## 2.5 Mouse Controller



The optional mouse controller allows easy desktop access to the most commonly used front panel controls. These buttons are functionally equivalent to the corresponding front panel controls. The “Mouse Control” Switch (section 5.2.7) must be set to “ON” for the mouse controller to work.

-  - Left (Decrease)
-  - Up (Increase)
-  - Down (Decrease)
-  - Right (Increase)
-  Setup Mode or **STOP**

 The mouse controller is a highly modified computer mouse. You cannot use a regular mouse with the AlfaSpid rotator nor vice-versa.

The mouse ball serves no function.

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## 3 SETUP MD-01/02 controller

### 3.1 COMMUNICATION between MD-01/02 and PC

Communication between the MD-01/02 controller and a PC is done with program **SPIDM-D01dde.exe** ( **\*\* This name may change**). You can use this program to configure the MD-01/02 controller as well as use it to communicate between the ORBITRON satellite tracking program and the MD-01/02. More programs will be supported in the future.

How to start communication from MD-01/02 to PC

### 3.2 SETUP MD-01/02 controller

#### 3.2.1 Using USB Communications:

- When power is turned on, the MD-01 display shows: "Mode: Normal".
- Press the [S] button twice.
- You will now enter "Motor configuration".
- Press [Right] button 8 times. Then select "USB" with the [Up] or [Down] buttons.



- Go to "Set Protocol" below

#### 3.2.2 Using Ethernet Communications :(If Ethernet module is installed)

- When power is turned on, the MD-01 display shows: "Mode: Normal".
- Press the [S] button twice.
- You will now enter "Motor configuration".
- Press [Right] button 8 times. Then select "USB" with the [Up] or [Down] buttons.

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### Set Protocol

- Press **[Right]** button 1 more time and select SPID ROT2 with the **[Up]** or **[Down]** buttons (protocol SPID ROT2). The SPID ROT2 protocol is installed as a standard protocol in the MD-01/02 rotator controller.



- To complete and to close this setup, press **[F]** button and choose YES.
- You are now back in the running mode and ready to use the MD-01/02 controller.

**All configurations of the controller are done.**

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## 3.3 SETUP MD-01/02 software

To find out what version of firmware is in the MD-01/02 controller, press the [F2] and [F] buttons on the front of the MD-01/02 controller at the same time. The firmware version and date will be seen on the MD-01/02 display.



### 3.3.1 Using USB Communications:

#1 Install the FTDI USB drivers on the PC (USB D Driver) Use the Driver appropriate for your operating system. Consult FTDI Website <http://www.ftdichip.com/Drivers/VCP.htm>

This USB driver will install a USB Serial Port (COM x).

You can check this in Windows/configuration/device management and search for COM ports.

#2 Connect the MD-01/02 through USB D port to PC with a USB Cable (Port: USB D).

#3 Start program spidMD01dde.exe (this name may change).

#4 Click on the “show” button at the bottom middle then click on the Options Tab.



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#5 For USB connection click on com port.

#6 Double click at "port not selected" to choose the USB Serial port which must be used.

SPTID MD-01 ver. 2.0c No MD01 device found!

M1: 0.0 Send  
M2: 0.0 hide STOP

MODE: NORMAL  
M1: 0.0 M2: 0.0

MD-01 parameters ORBITRON Options

Pooling time (ms): 750  Show power outputs (SW01)  
Timeout (ms): 750  
 COM port  ETH (RJ45) port  
Port: COM3 (not found) IP: 192.168.20.121  
Baudrate: 115 200 Port: 23

Connect

Connection error: Command send error. Check settings and connections.

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#7 Click on the USB Port (COM13 in this example). Do **not** change Baud Rate, Pooling Time or Timeout at this time!

SPID MD-01 ver. 2.0c No MD01 device found!

M1: 0.0 Send

M2: 0.0 hide STOP

MODE: NORMAL  
M1: 0.0 M2: 0.0

MD-01 parameters ORBITRON Options

Pooling time (ms): 750 Show power outputs (SW01)

Timeout (ms): 750

COM port  ETH (RJ45) port

Port: not selected IP: 192.168.20.121

Baud: Port: 13

Cancel  
Clear  
COM1

Connection error: Command send error. Check settings and connections.

#8 Click on Connect Box.

### 3.3.2 Using ETH Communications:

- #1 Connect the MD-01 through ETH port to the local LAN with an Ethernet Cable.
- #2 Start program spidMD01dde.exe (this name may change).
- #3 Click on the down arrow at the bottom middle then click on the Options Tab.

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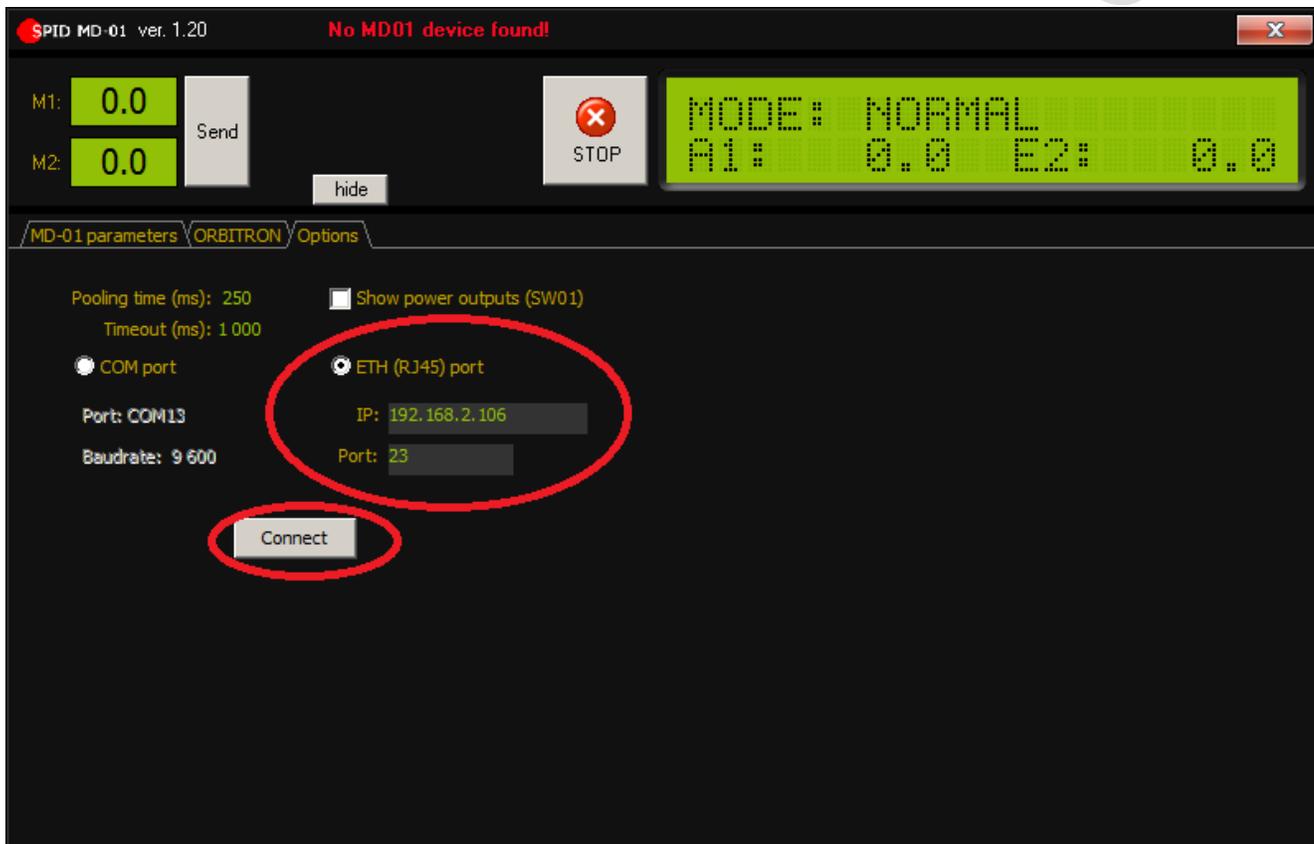
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#4 For ETH connection click on ETH (RJ45) Port.

#5 Determine the IP address of the MD-01/02 controller by using a program such as NETSCAN or KT-ETH-Manager from a PC.

#6 Enter the IP address of the MD-01/02 controller in the IP: Box  
This address can be a numbered address or a DNS address.



#7 Click on Connect Box.

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## COMPLETING the Configuration

Now click at MD-01 parameters / Ports and check if the screen is as below, USB COM or ETHERNET State must be "ON" but **not** both.

The Baud setting for the USB COM port is normally set to 460800. If the USB COM port is to be used in normal operation and the control program used in normal operation uses a different baud rate, then the setting on the screen below will need to be changed to match. When the settings are uploaded to the MD-01/02 controller, communications between the setup program below and the MD-01/02 controller will stop. It is best to restart the PC setup program, as described in section 3.3.1, this time using the new baud rate.



If

the setup is correct and the spidMD01dde.exe ( \*\* this name may change) program is properly connected to the MD-01/02 controller the upper right display on the PC will synchronize with the display on the MD-01.

To test:

Press arrows on the MD-01/02 keypad. The rotator should move and the PC display should update with changes in the MD-01/02 display.

Enter new values in the M1 and/or M2 boxes and click on the Send box. The rotator should move to the selected locations and the PC display should update with changes in the MD-01/02 display.

Be sure all cables are connected to MD-01/02 and rotator!

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## 3.4 More functions available in MD-01/02 software:

With the MD-01/02 software you are able to configure the MD-01/02 controller.

How does this work?



Click at an item you want to change in the MD-01/02 parameters screen. The parameter selected (“Start Powers: 30%” in the example above) will be highlighted in green.

You can now change this value using the arrow keys, [Up], and [Down].

When you change some settings you can now upload them to the MD01/02 controller by pressing the Upload button. Click Yes at the question. Wait for a second, and, if needed, manually check to see if new data is active.

Note: Most values can be changed. Care must be taken, as changing the motor configuration can result in a non-working rotator.

### Possible changes that can be made by the user:

- Soft Start and Stop (3 step)
- Minimal and Maximal turning angle (AZ & EL)
- Protocol change (advance setting / experience)

## 3.5 Pooling time and Timeout

The Options page of the spidMD01dde.exe program has two timing options:

Pooling Time (ms) - This is the interval at which the program will poll the controller for its Azimuth and Elevation status. The default value for this is 250 ms.

Timeout (ms) - This is an interval that the program expects to receive a complete response from the controller. The default value for this is 500 ms.

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The default values generally work out fine for connections on the two COM ports and the USB port at Baud rates of higher than 9600. For baud rates of 9600 and lower, it is suggested that these values be set higher to approximately 750 ms for pooling rate and 1000 ms for Timeout.

With Ethernet connections on a busy network, the user will notice that the program may disconnect. Adjusting the pooling rate and timeout values will lessen the problem.

## 3.6 Rotator Testing

See Applicable Alfa Radio Rotator Manual

## 3.7 Rotator Troubleshooting for non-/HR Rotators

See Applicable Alfa Radio Rotator Manual

## 4 Operation

MD-01/02 controller may be operated from the front panel keyboard or a computer connected to one of the Communication ports. The MD-01/02 controller has three modes (MODE).

- **NORMAL** – standard operating mode

```
MODE: NORMAL  
A1: 0.00 E2: 1.00
```

- **MOTOR ANGLES** – calibration mode of the actual rotator's position relative to geographical directions,
- **SPEED CALIBR.** – calibration for SOFTLY and SATELLITE modes

```
MODE: SPEED CALIBR.  
LONG S TO START
```

To change the mode, push the [F] key.

Before using the controller with the rotator, start procedure for setting the minimum motor power (MIN POWER) which should be able to move and turn the antenna system:

1. Set the SET MOTOR -> MIN POWER [motors 1 and 2] to 100%.
2. Then go to the parameters SET MOTOR -> MAX POWER to determine the minimum power of the motors, which allows the rotator to move both for AZ and for

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- EL motors (overcoming transmission resistance, boom and antenna weight, etc.): by reducing the motor power values from 100%, experimentally look for the lowest possible value that allows the motors to move without causing a TIME OUT error. If an error occurs, restart the controller with the main switch and follow the procedure again.
3. After finding the appropriate values for each of the engines, in order to take into account the possibility of other operating resistances (e.g. due to low temperature, wind, nonlinearity of loads in AZ/EL operation, etc.), the margin (e.g. 10-15%, for possible verification in practice) should be taken into account, and the obtained values should be increased accordingly and entered as appropriate parameters for both motors in the parameter (note!) MIN POWER, then return to MAX POWER set to 100% or in the range between MIN POWER and 100%, at the discretion of the user, if he does not expect the rotator to work at full speed.
  4. The starting base, for a user who does not want to perform the above procedure, may be MIN POWER 50% and MAX POWER 100% respectively (usually sufficient for standard antenna systems), however, it should be taken into account that such settings will not work optimally and may generate errors (e.g. TIME OUT).
  5. Completion of the procedure for setting the minimum motor power (MIN POWER) means that the correct values have been entered for both motors in the MIN POWER and MAX POWER fields. This is the moment when the user can proceed to calibrate the SOFTLY and SATELLITE (SPEED CALIBR.) modes.

## 4.0.1 Normal mode (NORMAL)

In this mode, the Controller may be operated with the [Right], [Left], [Up] and [Down] buttons, or from a connected computer. The Controller supports communications protocols such as SPID ROT1, SPID ROT2, SPID MD-01 and YAESU that can be assigned to any communications port (COM 0, COM 1, USB D and ETH) in the settings. YAESU protocol may not support the full capability of AlfaSpid rotators.

The [Right] and [Left] buttons are used to adjust the azimuth of the antenna.

The right direction – the antenna turns in a clockwise direction; the value of the angle in the display increases.

The left direction – the antenna turns in an anticlockwise direction; the value of the angle in the display decreases.

The [Up] and [Down] buttons are used to adjust the elevation of the antenna.

The Up direction – the rotator turns right from a facing perspective; the value of the angle in the display increases.

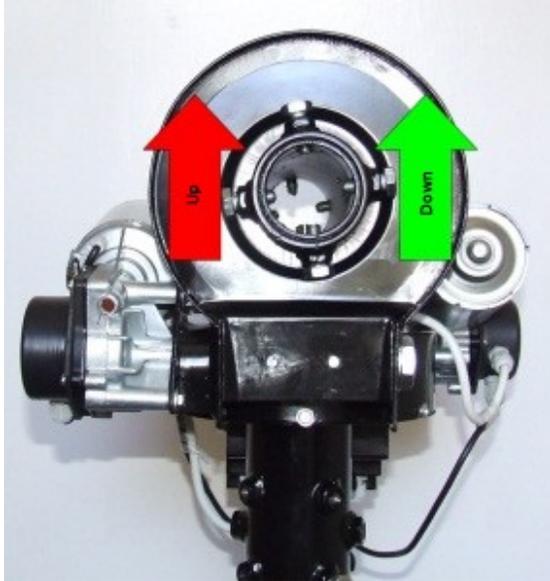
The Down direction – the rotator turns left from a facing perspective; the value of the angle in the display decreases.

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The directions of antenna elevation rotation are shown in the picture:



Use Only



After installation of the optional CCM (Current Measurement Module), the user can observe the value of the motors' current. To activate this function, press the [F2] button once. On the LCD screen, where the rotor position is indicated, the current values of the respective motors will appear. The occurrence of slight fluctuations in current indications during the rotor standstill is a normal situation and results from the internal noise of the measuring sensor. Sample LCD screen during rotor operation:



## 4.0.2 Calibration mode (MOTOR ANGLES)

To switch the controller to the calibration mode, push the [F] button. In this mode you can set the azimuth and elevation angles without turning the antenna. This mode is needed to preset and calibrate the antenna positions. To reset the azimuth angle to zero, push the [F1] and [Left] buttons simultaneously. To reset the elevation angle to zero, push the [F1] and [Down] buttons simultaneously.

To change the azimuth angle, use the buttons [Left] and [Right].  
To change the elevation angle, use the buttons [Up] and [Down].

After completing the calibration, leave calibration mode and return to normal mode by pushing the [F] button.



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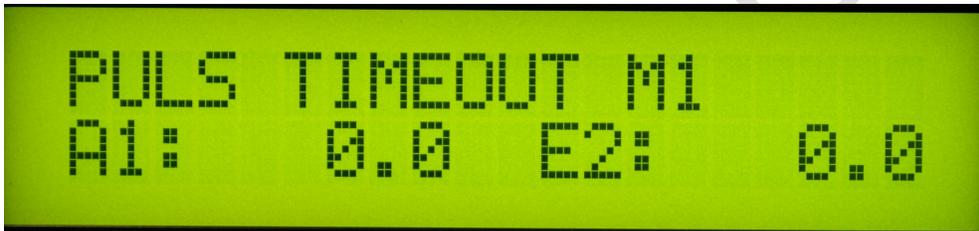
Verification of the actual position of the antenna in relation to the displayed values should also be done preventively. This is to maintain the operation of the antenna and wiring within the assumed angular limits. It is suggested that during the operation of the rotor, observe its operation and the position of the antenna (directly or through the camera) and in the event of irregularities, immediately stop the rotor by switching off the controller.

Part of the overload protection circuitry involves cutting power to the motor, if the controller does not receive a sense indication. If the motor turns for a few seconds and then stops, the motor has either stalled or there is a problem in the impulse sense wiring. The controller has not detected motor movement.

On units with older firmware, there is no indication on the display that this has happened.

On units with the latest firmware, the display screen will show which motor is a fault.

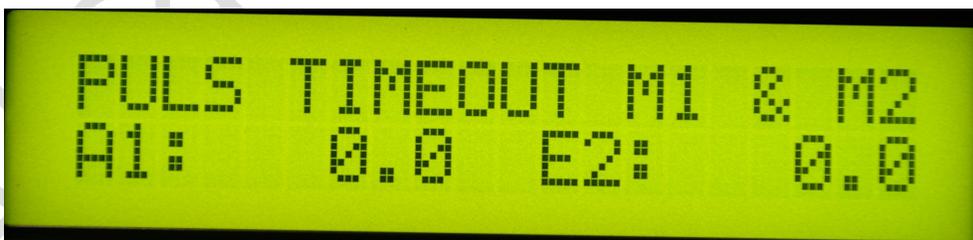
This picture indicates that the motor connected to the Azimuth connector has the fault.



This picture indicates that the motor connected to the Elevation connector has the fault.



This picture indicates that both motors have the fault.



The operator needs to correct whatever condition is causing the fault, Cycle the power to the controller, using the front panel power switch, and try again.



## 4.0.3 Speed Calibration

is a calibration for SOFTLY and SATELLITE modes.

 In order to properly calibrate, the procedure for setting the minimum motor power (MIN POWER) capable of moving the antenna system must be carried out beforehand. Therefore, the rotor should be mounted at the target location and the antenna system installed on the rotator. This is crucial for the proper operation of the SOFTLY function, so it should be carried out with due diligence.

 Note: both the MIN POWER setting and the SOFTLY mode calibration should be carried out whenever the load on the motors may have changed significantly, e.g. a change in the antenna system, a significant change in the outside temperature (due to the higher resistance to movement of the antenna system and the gears themselves), other factors affecting the resistance to movement and the minimum torque capable of moving the antenna system. It should be taken into account that the antenna system may pose different resistance to the rotor motors depending on the selected azimuth and elevation, this may be influenced by, for example, the balance of the antenna system, the tension of antenna wires, etc.

Calibration procedure: c

1. In the MOTOR CONFIGURATION menu for both motors, set START and STOP to SOFTLY. Then approve and save the selection.
2. Start the configuration mode using the F button [MODE: SPEED CALIBR.]. To confirm the choice, press and hold the S button for min. 10s – this will start the calibration procedure. When confirming the start of the calibration procedure, the user must be aware that the controller will automatically start the rotor motors – the antenna system and the objects within its range should be prepared in advance for safe operation. **Remember: at any time, the procedure can be interrupted by turning off the controller with the main power switch!**
3. After starting the calibration mode, the controller:
  - a. will bring the rotor to the position of 0 ° azimuth and 0 ° elevation,
  - b. for each of the motors will carry out a series of tests consisting in starting in work cycles in the range of about 0-10 ° respectively for azimuth and elevation, analysing the actual speed of the set at this time,
  - c. informs about the progress of calibration indicating the percentage of advancement on the screen,
  - d. after the calibration is completed will automatically go to NORMAL mode.

The next step in optimizing the work is to set the ramps of start power gains (START POWER) and stop power (STOP POWER) of the voltage supplying the motors and periods (START TIME and STOP TIME respectively):

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1. Usually, in the case of even complex antenna systems, it is sufficient to set a single-threshold start and stop ramp. Example configuration: START POWER:

```
SET MOTOR 1  
START POWER 2: 50%
```

STOP POWER:

```
SET MOTOR 1  
STOP POWER 2: 50%
```

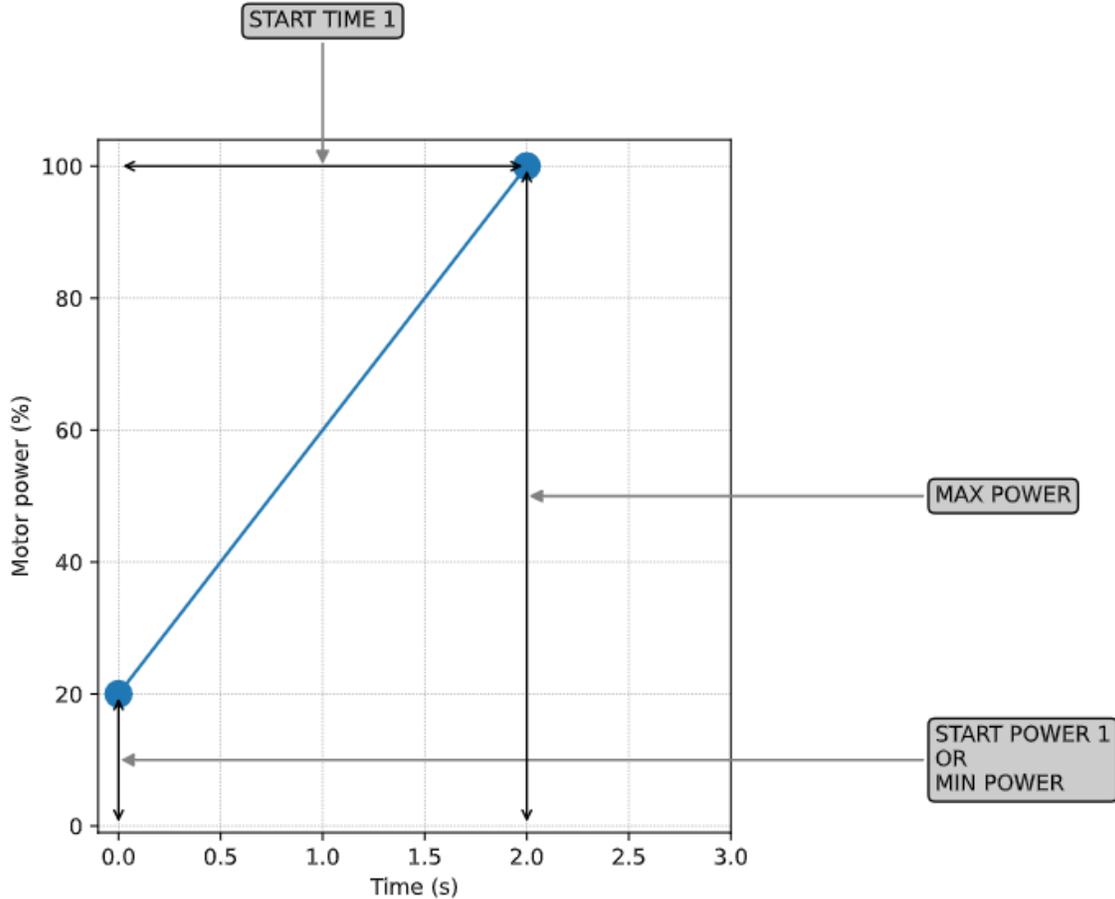
equal to or slightly greater than the previously declared MIN POWER,

START TIME 1: 1s:

```
SET MOTOR 1  
START TIME 1: 1s
```

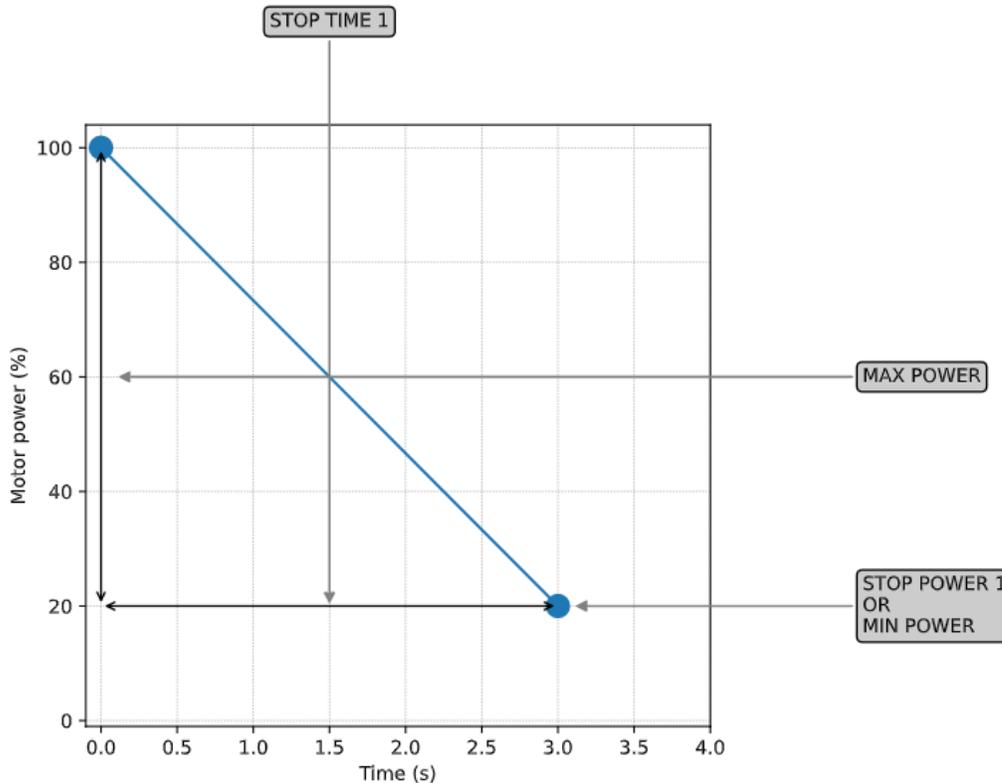
START TIME 2: 0s, START TIME 3: 0s, STOP TIME 1: 1s, STOP TIME 2: 0s,  
STOP TIME 3: 0s.

2. Note: choosing a time other than 0s in subsequent positions START TIME 2, START TIME 3 (respectively STOP TIME 2, STOP TIME 3) activates subsequent ramps allowing the process of starting and/or stopping engines to be spread over more stages.
3. Explanation of the operation of ramps on the example of the following graphs:



4. A diagram (above) of the starting ramp, where the controller will start the motors with a power of START POWER of 20% (in this case such as MIN POWER) and at the time of START TIME 1 (here 2s) will smoothly increase the power to the value of MAX POWER (in this case to 100%).

In the case of approaching the final set position, the controller will start the deceleration process, in which for 1s (selected STOP TIME) it will reduce the power of the motors to MIN POWER and stop them (this last part of the process is not visible on the graph).



A diagram of the stop ramp, where the controller will start the stopping process from MAX POWER (in this case 100%) to STOP POWER (in this case 20%), and this process will take place during STOP TIME 1 (here 3s).

**Comment:** if you select the START POWER and/or STOP POWER value smaller than MIN POWER, the controller will use the MIN POWER value in these places, similarly for the START POWER and/or STOP POWER value greater than MAX POWER, the controller will use the MAX POWER value in these places, which means that the MIN POWER and MAX POWER values declared by the user are superior.

#### Completion of procedures:

1. minimum engine power settings (MIN POWER),
2. calibration of the SOFTLY function,
3. settings for start and stop increment ramps, means that the configuration of the motors in the antenna-rotator-controller system has been completed.

After calibration, save the settings and return to NORMAL mode by pressing the [F] button (a few times if needed).



## 5 MD-01/02 controller configuration

When MD-01/02 controller is in NORMAL mode, you can use the [S] button to enter configuration mode.

The structure of the controller configuration mode is modular. Select modules using buttons [Left] or [Right]. When you select a module, you use the [S] button to enter its parameters. Moving between parameters is done with the [Left] or [Right] buttons. The value of the parameter can be changed using the [Up] or [Down] buttons. The [F] button is used for exiting the configuration mode. After pushing the [F] button, the operator is asked about writing the current configuration into memory. To confirm and write the changes to memory, press the [Left] button. To go back to previous configuration, press the [Right] button.

### 5.1 Motor configuration

The number before the ":" in the name of the template determines which connector on the rear panel the motor must be connected:

1. AZIMUTH
2. ELEVATION

### 5.2 Template

The type of motors connected to the controller is pre-set by templates:

- 1:NC, 2:NC - no motors connected to the controller.
- 1:AZ, 2:NC - a motor is connected on the rear panel of controller on connector AZIMUTH. Motor rotates only in azimuth.
- 1:NC, 2:EL - a motor is connected on the rear panel of controller on connector ELEVATION. Motor rotates only in elevation.
- 1:AZ, 2:EL - there are two motors connected to the controller. Motor 1 (connector AZIMUTH) rotates in azimuth, and Motor 2 (connector ELEVATION) rotates in elevation.
- 1:AZ, 2:AZ - there are two motors connected to the controller, which is rotated in azimuth only.
- 1:EL, 2:EL - two motors are connected to the controller, both rotates only in the elevation plane,
  - 1:AX, 2:EY - This setting is for a rotator that is currently not supplied of supported by Alfa Radio.
  - 1:XX, 2:YY - This setting is for a rotator that is currently not supplied of supported by Alfa Radio

#### 5.2.1 Show Azimuth

Azimuth angle display format:

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This angle can assume any value from -180 degree to 540 degrees max, or within the range of the rotator as set with the MAX and MIN Angle settings for each motor.

- **MATH** – show angle from -180 degree to 540 degree,
- **NORMAL** – show angle in 0 – 359 degrees.
- Example:

MATH ANGLE	SHOWN ON DISPLAY
-1 degree	-359 degree
-2 degree	-358 degree
-179 degree	-181 degree
-180 degree	-180 degree
360 degree	+0 degree
361 degree	+1 degree
539 degree	+179 degree
540 degree	+180 degree

## 5.2.2 Short Way

OFF - Disable Shortest Route feature on AZ Rotators or the azimuth portion of an AZEL Rotator

ON - Enables Shortest Route feature on AZ Rotators or the azimuth portion of an AZEL Rotator

## 5.2.3 Use EL MAP

Use elevation map. This is a map of minimum elevation angles at specific azimuth angles. This map can be created with the program “spidMD01dde” (name may change). The map can be used when, for example, high buildings or trees are around the antenna and obscure visibility.

Example: if USE EL. MAP is set (ON) and you set a minimum elevation angle of 20 degrees for azimuth angles from 10 to 100 degrees, and a satellite tracking program (like Orbitron) sends the MD-01/02 an elevation angle less than 20 degree for an azimuth angle in 10 to 100 degree range, the MD-01/02 will only take the elevation angle to 20 degrees. The Elevation map is ignored when the MD-01/02 is controlling manually.

**Note:** MIN ANGLE and MAX ANGLE in SET MOTOR 1 (SET MOTOR 2) have a higher priority than the angles of elevation map. The rotator will not go beyond these limits.

## 5.2.4 Const EL MAP

If this option is set to ON, option USE EL. MAP is ignored, and a minimum elevation angle of 0 degrees azimuth is set for all azimuth angles. This option is ignored when MD-01 is controlling manually.

**Note:** MIN ANGLE and MAX ANGLE in SET MOTOR 1 (SET MOTOR 2) have a higher priority than the angles of elevation map. The rotator will not go beyond these limits.

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### 5.2.5 Start

Motors run mode:

This is set for each motor separately in modules SET MOTOR 1 and SET MOTOR 2, as described later in section 5.3.9,

- **IMMEDIATELY** - motor starts with max speed, soft start is not active.
- **SOFTLY** - soft start is active (See 5.3.9 for details).

### 5.2.6 Stop

Motors stop mode:

This is set for each motor separately in modules SET MOTOR 1 and SET MOTOR 2, as described later in section 5.3.10,

- **IMMEDIATELY** - at once, soft stop not active.
- **SOFTLY** - soft stop is active (See 5.3.10 for details).

### 5.2.7 Satellite Mode

- **ON** - turning on,
- Properties:
  - optimized to track satellites in LEO orbit,
  - increases smooth operation and reduces the load on motors, gears and relays (note: at the expense of a slight reduction in accuracy),
  - works only with sensors type HR and CAN Bus.
- Description of the algorithm: in Satellite Mode, the system is prepared to accept subsequent positions from the satellite tracking program much more often and switching the controller relays after the end of each rotor movement practically does not occur, unless subsequent positions change the direction of movement of one of the motors and the configuration of the motors has been made correctly.



**Note:** with improperly set parameters of ramps and engine power, the frequent exceeding of the set position may occur (e.g. due to system inertia), which will cause the controller to react and correct the position when receiving the next command from the tracking program (the user will observe frequent operation of relays and correction of position during satellite tracking). This is an indicator that the motors (MIN POWER, SOFTLY configuration and ramps) should be performed again. However, it should be taken into account that the correction of the position and thus the operation of relays may also occur with properly configured motors - however, it will occur relatively rarely.

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### 5.2.8 Mouse Control

If you have a specially designed mouse by SPID (RAS Mouse – section 2.5), you can connect it to the MD-01 controller on OUT3 port (13 in back picture of MD01/02). The mouse works if you set this option to ON.

### 5.2.9 External control (CONTROL xx)

This parameter specifies the communication port that is used to control the connected motors. This parameter is not available when template 1: NC, 2: NC is chosen.

If template 1: AZ, 2: AZ, is chosen, the motor can be controlled from either of two ports.

The Controller display will show one or two descriptions depending on the selected motor template:

- CONTROL A1 – motor template 1:AZ, 2:NC or 1:AZ, 2:AZ,
- CONTROL E2 – motor template 1:NC, 2:EL,
- CONTROL AE – motor template 1:AZ, 1:EL,
- CONTROL A2 – motor template 1:AZ, 2:AZ.

CONTROL parameter value:

- **NONE** - no external control. Motor controlled manually with buttons on the controller.
- **COM 0** - external control with selected protocol. Can also be controlled manually.
- **COM 1** - external control with selected protocol. Can also be controlled manually.
- **USB** - controlled through USB D with selected protocol. Can also be controlled manually.
- **ETH** - controlled through ETHERNET with selected protocol. Can also be controlled manually.

### 5.2.10 Protocol (PROT.xx)

Communication protocol available between the controller and the control device (for example, a PC program):

- **SPID ROT1** - Standard communication for all AlfaSpid rotators and controllers in Azimuth mode.
- **SPID ROT2** - Standard communication for all AlfaSpid rotators and controllers in Elevation / Azimuth mode.

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- YAESU - YAESU mode may not support the full capability of AlfaSpid rotators.

## 5.2.11 PAIR

Only when the selected template is in 1: AZ; 2: AZ mode and the MD-01 is controlled from an external program. When the MD-01 receives an azimuth angle from the program, both rotators will go to this angle.

## 5.3 Set motors (SET MOTOR 1, SET MOTOR 2)

### 5.3.1 STATE

Read only. Depends on the TEMPLATE selected (see Motor configuration -> TEMPLATE). It displays whether the motor is switched on or switched off.

### 5.3.2 TYPE

Type of motor return signal:

- **DIGITAL** - controller counts pulses.
- **ANALOG** - future feature where the controller measures voltage.

### 5.3.3 KIND

Read only. Depends on the TEMPLATE selected (see Motor configuration -> TEMPLATE):

- **AZIMUTH** - motor rotates in azimuth.
- **ELEVATION** - motor rotates in elevation.

### 5.3.4 INPUT

Sensor type of controller MD-01/02 (only when the input type is **DIGITAL**):

- **ELECTRONIC** - rotator using electronic motion sensors (Hall Effect).
- **MECHANIC** - rotator using mechanical switches.

### 5.3.5 GEAR

Gear ratio of the rotator motor.

It should be noted that from firmware v2.0 the designation of the rotor gear has changed. During the process of replacing the software with a newer one, the controller itself converts the old values into the correct, new ones and usually no user intervention is required in this regard, however, the gear ratios are key parameters and their correctness should be verified by the user. The following table indicates the appropriate gear ratio values depending on the rotor type and software version:

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ROTATOR MODEL	GEAR NOTATION firmware older than v.2.0	GEAR NOTATION firmware v2.0 or newer	INPUT
BIG RAS HR	0.093750	0.023438	ELECTRONIC
RAS HR	0.125000	0.031250	ELECTRONIC
RAU HR	0.187500	0.046875	ELECTRONIC
SPX 01/02/03 HR	0.140625	0.035156	ELECTRONIC
SPX SDD	-	0.013560	ELECTRONIC
non HR	0.5 or 1.0	0.5 or 1.0	MECHANICAL

If the user uses a different gear, can enter its ratio in the CUSTOM position.



### 5.3.6 MIN ANGLE

Limits the minimum angle to which the motor can turn. Default -180

### 5.3.7 MAX ANGLE

Limits the maximum angle to which the motor can turn. Default +180

### 5.3.8 MAX POWER

Maximum power, as a percentage of full power, that the controller can provide to the rotator motor.

### 5.3.9 MIN POWER

Minimum power, as a percentage of full power, that the controller can provide to the rotator motor that will turn the motor.

### 5.3.10 START POWER, START TIME

Used if you want to obtain a “soft-start”. You can set a one, two, or three-stage motor start

(START POWER 1, START POWER 2, and START POWER 3)  
Power is expressed as a percentage of full power.

(START TIME 1, START TIME 2 and START TIME 3)  
START TIME is expressed in seconds.

#### Example 1: One-step

Set the initial speed of rotation of the motor  
START POWER 1 = 30%.

Set the time to reach maximum power (MAX POWER)  
START TIME 1 = 5 seconds.

In this example set START TIME 2 = 0 seconds. - This will specify that the motor start is a single step.

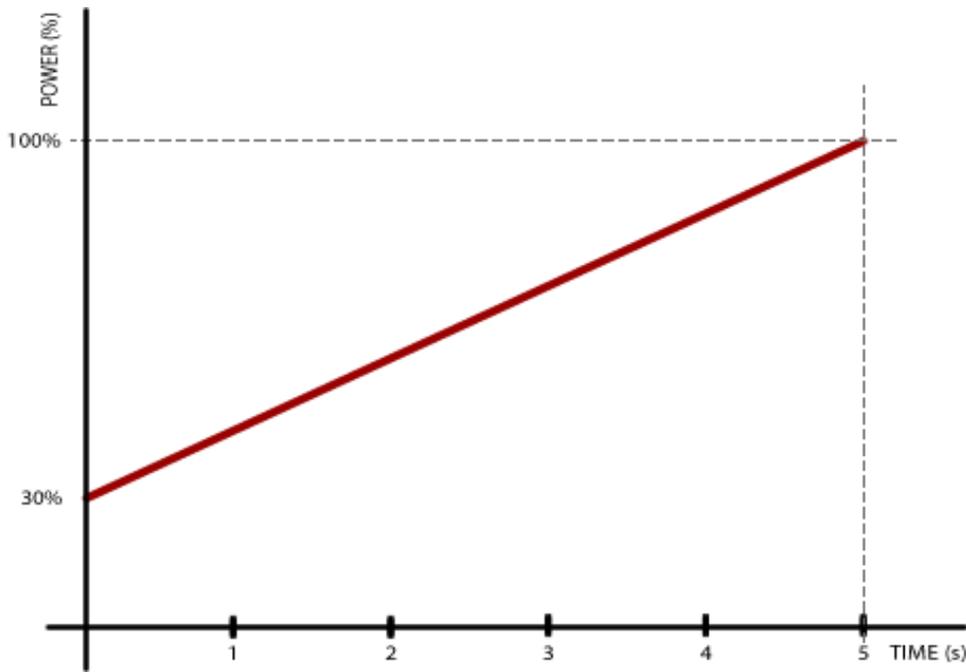
Set MAX POWER to 100%.

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This example shows that the motor is started with 30% power, within five seconds linearly increases power to 100%.



Only

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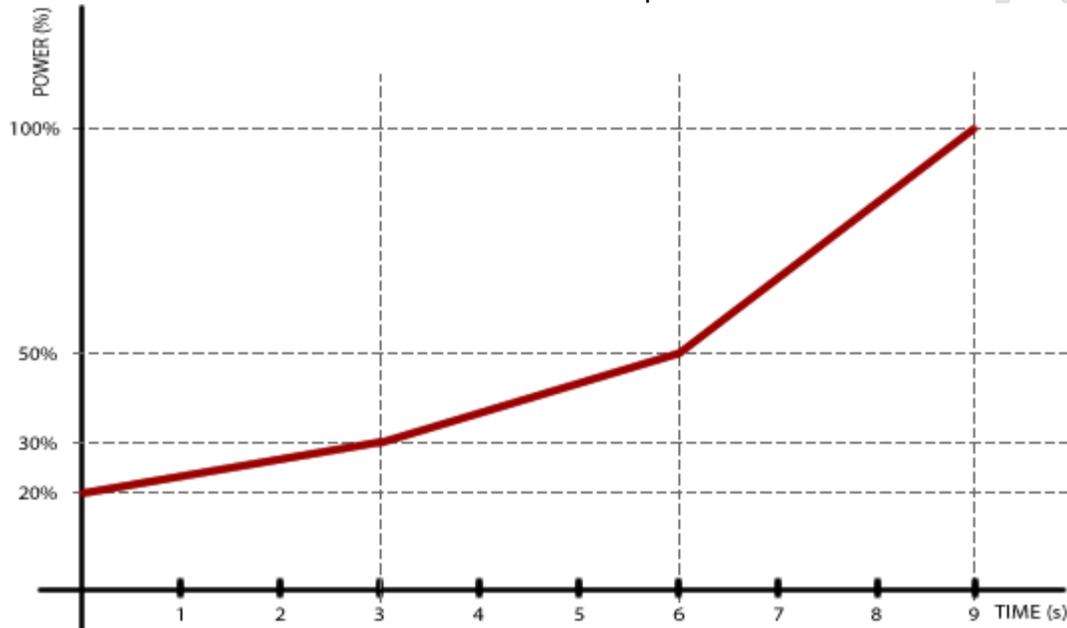
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## Example 2: three-step

- Set the POWER START 1 = 20%
- START POWER 2 = 30%,
- START POWER 3 = 50%,
- START TIME 1 = 3 seconds,
- START TIME 2 = 3 seconds,
- START TIME 3 = 3 seconds,
- MAX POWER = 100%.
- This means that the rotator starts with 20% power, within 3 seconds power reaches 30%, followed by 3 seconds during which power reaches 50% and the last 3 seconds in which power reaches 100%.



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### 5.3.11 STOP POWER, STOP TIME

Used if you want to obtain a so-called “soft stop”. It works the same way as “soft start” but is used to power down and stop the rotator.

### 5.3.12 STOP AT

Specifies how many degrees before the specified angle (for example, sent by a computer program like Orbitron) that the motor should begin shutting down. It only applies when SOFT STOP is selected in MOTOR CONFIGURATION.

### 5.3.13 PULSE TIMEOUT

Specifies how long the motor will run if it does not receive motion pulses from the rotator. Applies only to motors of type **DIGITAL**.

## 5.4 SET COM 0, SET COM 1

### 5.4.1 STATE

Read only. Possible values: ON or OFF.

### 5.4.2 BAUD

Possible values: 600, 1200, 2400, 4800, 9600, 19200, 38400, 57600, 115200, 230400 and 460800.

### 5.4.3 DATA BITS

Possible values: 4,5,6,7 or 8 bit.

### 5.4.4 STOP BITS

Possible values: 1 or 2 bit.

### 5.5.5 PARITY

Possible values: none, odd or even.

## 5.5 SET USB COM

### 5.5.1 STATE

Read only. Possible values: ON or OFF.

### 5.5.2 BAUD

Possible values: 600, 1200, 2400, 4800, 9600, 19200, 38400, 57600, 115200, 230400 and 460800.

## 5.6 SET ETHERNET – with optional module

The Ethernet port can be set for Dynamic or Static IP address as outlined in section 7.2. Communication with this port is done with the help of one of the protocols (SPID ROT1, SPID ROT2, SPID-MD-01 or YAESU).

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For example, the MD-01/02 controller receives the IP address from a DHCP server (e.g. 192.168.0.10). Connect to it, using a program like HyperTerminal by selecting the type of connection TCP / IP (Winsock), set host address 192.168.0.10 and port number to 23. Try using Yaesu protocol for testing because it is a text based protocol.

### 5.6.1 STATE

Read only. Possible values: ON or OFF.

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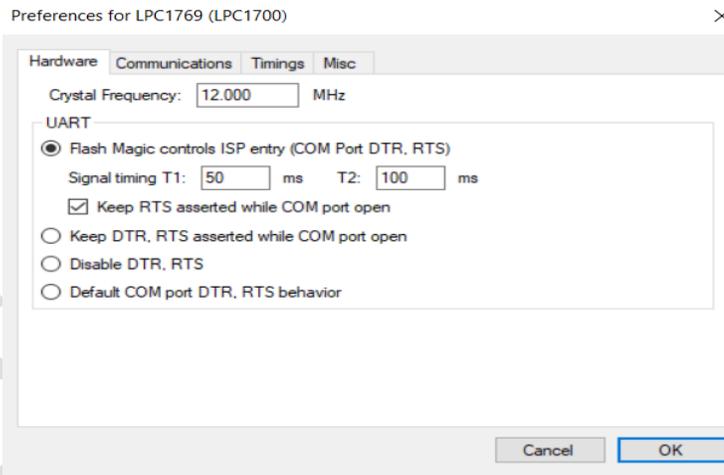
## 6 CONTROLLER FIRMWARE UPDATE

When a firmware update is available from Alfa Radio Ltd. the firmware of the MD-01/02 controller can be updated. It is important to install a flash program; we recommend Flash-Magic. A version is available on the Alfa Radio Ltd. website, or you can go to <http://www.flashmagictool.com/download.html> for the latest version.

Note: A firmware update file will be available on our web-site. Check the MD-01\_MD02 Static Firmware page for the latest version. ~~XXXXXXXXXXXXXXXXXX~~

### 6.1 Update Step by step:

1. Turn the MD-01/02 controller off
2. Set switch #8 to position OFF (back panel of MD-01/02)
3. Connect a serial cable to the Sub-D9-connector "COM 0" on the MD-01 and to a serial port on the PC
4. Turn on the MD-01/02
5. Start Flash-Magic
6. Now choose from menu View->**Preferences**, page **Hardware** and set options as on the screen shot below. Close with **OK** and the main screen comes back.



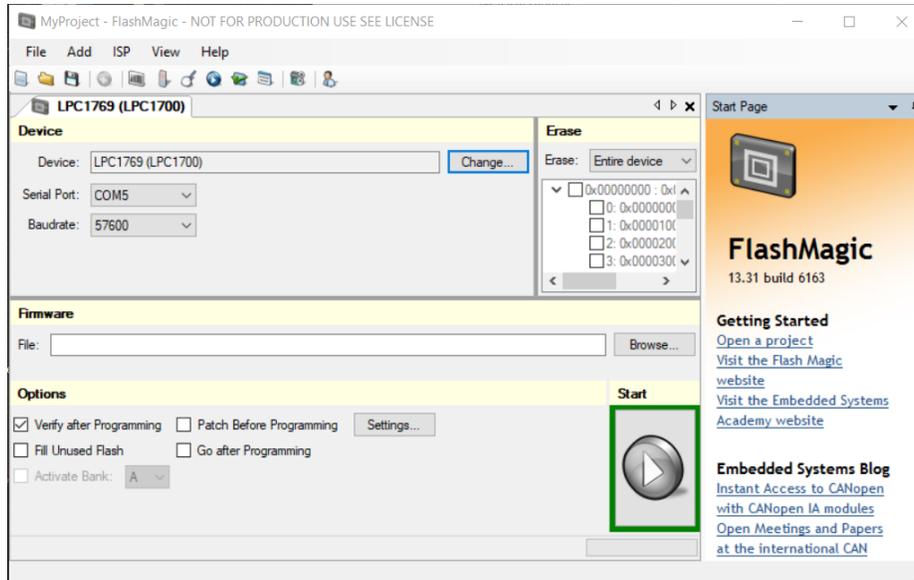
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Back in the Main Screen:.....

- Select Device: LPC1769.
- Select COM port that will be used from your PC to the MD-01/02.
- Select firmware received from Alfa Radio Ltd. i.e. MD01 v1.11.hex.
- Set the rest of parameters as shown in screen shot below.



7. Click Start button to start update firmware. The LCD screen on the MD-01/02 will turn off during update. When update is complete, the screen will light up again.
8. Turn off the MD-01/02 power after the update is finished.
9. Set switch to position from off to PR (back panel of MD-01/02).
10. Turn the MD-01/02 on.
11. New Firmware is installed and MD-01/02 is ready to use.

## 6.2 Firmware versions

The Alfa Radio Website has several versions of firmware for the MD-01/02 Controllers. They are filed in three subdirectories:

**Current** - This is the current version of Firmware approved by Alfa Radio Ltd. for customer use.

**Archive** - These are previous versions if you want to try them. No software support will be provided.

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## 7 Optional Ethernet Module.

### 7.1 Ethernet Module V1

#### 7.1.1 To install the optional Ethernet module V1:

Step 1: Unpack the module and note the MAC address printed on a paper sticker on the RJ45 connector.



Step 2: Remove the top cover of the MD-01/02 controller. Locate the area of the Motherboard near the Ethernet connector. Remove the two screws from the standoffs.

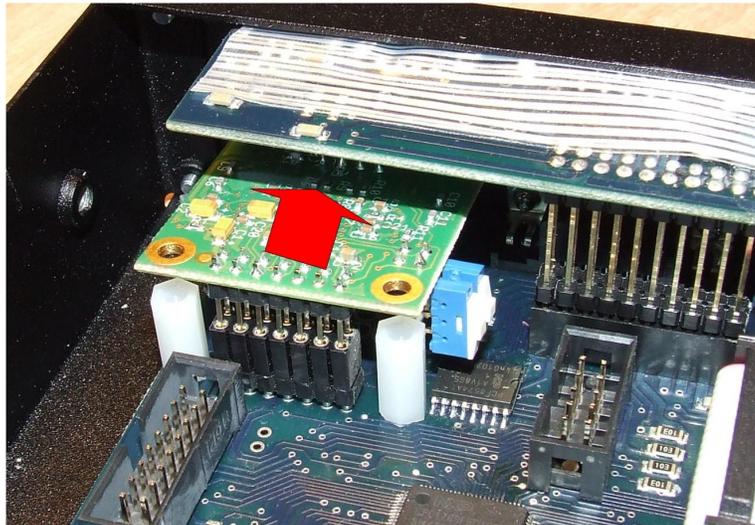


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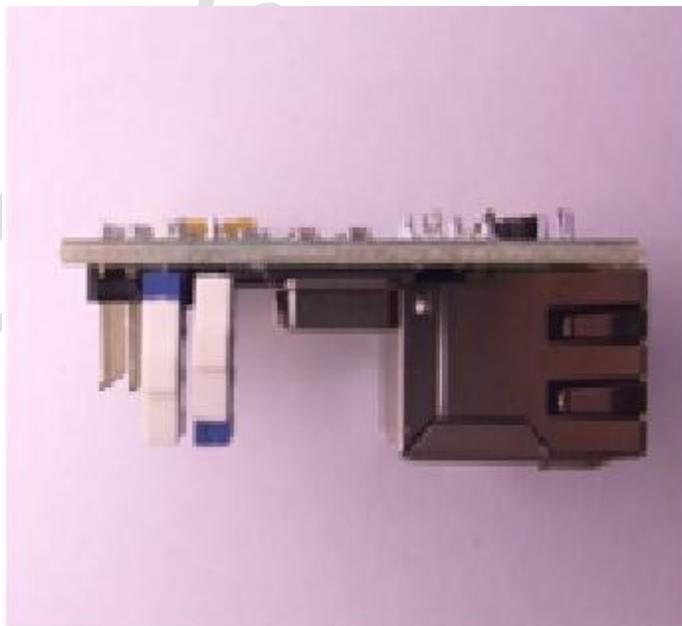
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Step 3: Insert the Ethernet module into the space and align the 14-pin connector with the 14-pin socket on the motherboard. Push the 14-pin connector down and replace the two screws to secure the module.



Step 4: Set the two switches as shown if DHCP IP addresses will be used exclusively. Move both switches down if Static IP addresses will be used.



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## 7.1.2 Setup the Ethernet Module

Connect an Ethernet cable from the MD-01/02 controller to the local LAN Switch. Turn the MD-01/02 controller ON and, with a PC connected to the LAN, determine the IP address of the MC-01/02 controller using a network scanning program such as “nmap.exe”.

Using a Web Browser connect to the MD-01/02. The next screen will appear.

**KRISTECH KT-ETH-UART-1**

### Status & Configuration

Home	Name:	KT-ETH-UART-1	
Port 0	Firmware Revision:	106	
Port 1	IP Address:	192.168.20.100	
Miscellaneous	MAC Address:	00-50-c2-b7-73-e5	

Firmware Update

### Current port setting

Baud Rate:	460800 bits/second	115200 bits/second
Data Size:	8 bits/character	8 bits/character
Parity:	None	None
Stop Bits:	1 bit(s)	1 bit(s)
Flow Control:	None	None
Local Port:	23	26
Remote Port:	N/A	N/A
Mode:	TCP Server	TCP Server
Protocol:	RAW	Telnet
Server IP:	N/A	N/A

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20:25:52

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Click on the “Port 0” link.

	Current	Updated
Port 0	Baud Rate: 460800bits/second	460800 bits/S
Port 1	Data Size: 8 bits/character	8 bits/character
Miscellaneous	Parity: None	None
Firmware Update	Stop Bits: 1bit(s)	1 bit(s)
	Flow Control: None	None
	Local Port: 23	23
	Remote Port: N/A	23
	Mode: TCP Server	TCP Server
	Protocol: RAW	RAW
	Key (16 chars): *****	*****
	Server IP: N/A	0 . 0 . 0 . 0
	Timeout: 0seconds	0 seconds (0 for no timeout)

Make these the default settings.

Submit

To make the new settings apply each time the device is reset, ensure that

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Ensure that all the parameters are set to match the above. When all the parameters are entered, check the “Make these the default settings” box and then click the “Submit” Button.

The setup is complete. Turn off the MD-01/02 controller, re-install the top cover and replace all screws.

The Ethernet module will now operate using DHCP to determine the IP address of the controller.

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To configure the Ethernet controller for a static IP address, access the controller using a web browser as described above. Click on the “Miscellaneous” icon.

Click on the

At the Address Type select “Static IP”

Fill in the “Static IP Address” “Subnet Mask” and “Default Gateway” to match the network to which the controller will be connected. Click on the “Update Settings” button to save the new settings.

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Reset the MD-01/02 controller by cycling the power off then on.

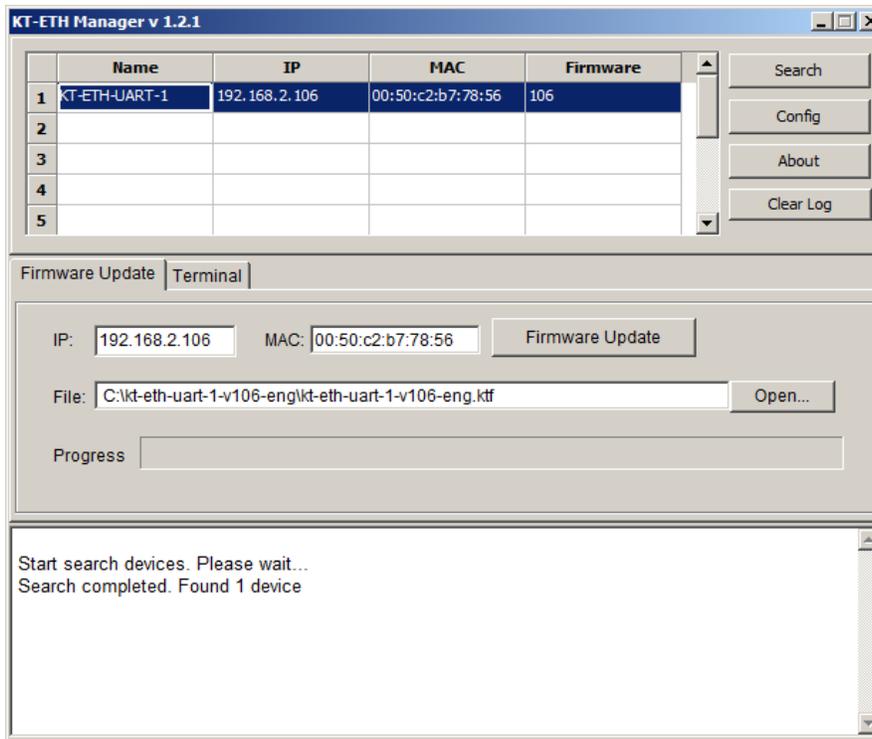
## 7.1.3 Ethernet Board Firmware Update

To update the firmware on the Ethernet Board, first download the Ethernet Manager program (KT-ETH-Manager-1.2.zip) from the Alfa Radio Ltd. website. Unzip the executable and install it on your windows computer.

Then download the latest firmware (kt-eth-uart-1-v106-eng.zip) from the Alfa Radio Ltd. website and unzip the file into a convenient directory.

Connect the controller and the Windows computer to an Ethernet LAN.

Start the ETH-Manager program:



Clicking on the “Search” Button will have the program search for the Controller Ethernet Board. When found, it will display the board’s IP address and MAC address. This feature is handy during Controller Setup.

Click on the “OPEN” button and find the copy of the firmware stored on your Computer.

Highlight the Ethernet board; the IP and MAC addresses will show up next to the “Firmware Update” Button. Click on the “Firmware Update” button and the update will take place.

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When the update is complete, cycle the power on the MD-01/02 controller and the new firmware should be active in the Ethernet Board.

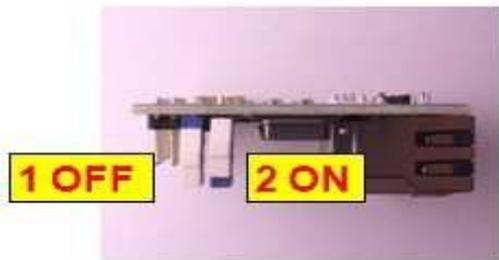
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Different positions of the Ethernet Module:



NO use only

<b>PIN1 OFF</b>	<b>web server is active</b>
<b>PIN1 ON</b>	<b>web server is offline</b>
<b>PIN2 OFF</b>	<b>mode according to user's network configuration</b>
<b>PIN2 ON</b>	<b>DHCP mode</b>

## Alfa Radio Ltd.

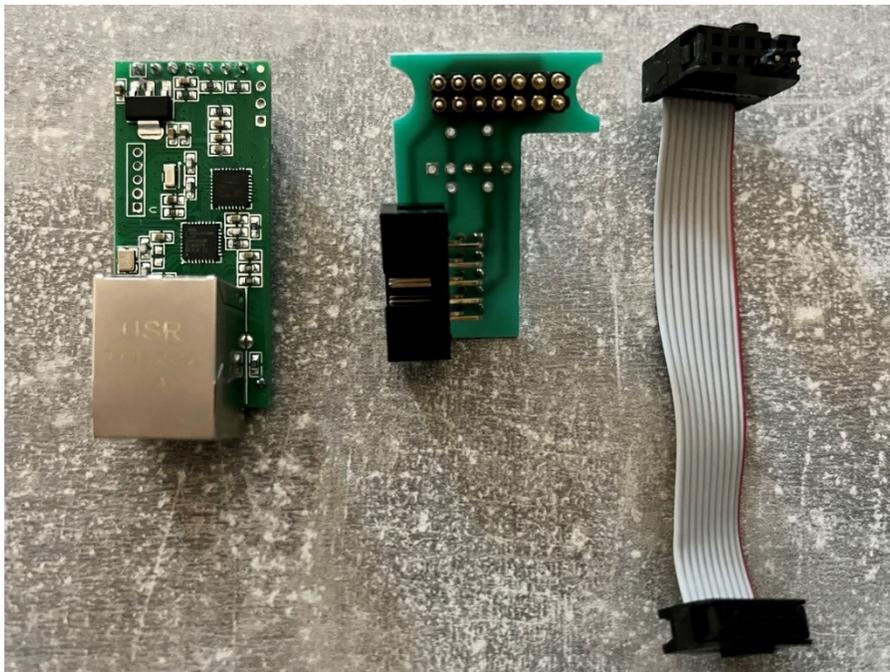
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### 7.2 Ethernet Module V2

#### 7.2.1 To install the optional Ethernet module V2:

The Complete Ethernet module V2 set includes: Main Unit, Mount Board and Connection Cable.



Ethernet module set(Left to Right): main unit, mount board and connection cable

#### Step 1:

Unscrew the screws that fix the top cover of the controller. Open the controller by removing the cover and find the empty space on the left when the display is turned facing the user. Follow hardware installation below:

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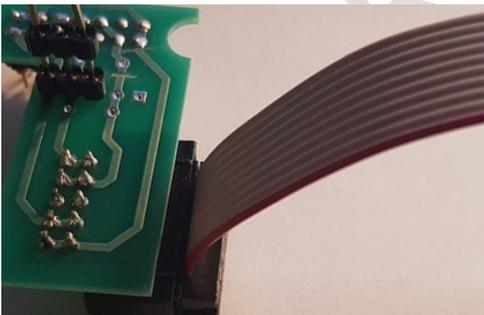
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remove the two screws and the 10 pin extension bar from the photo above as shown in the photo below.



Step 2:

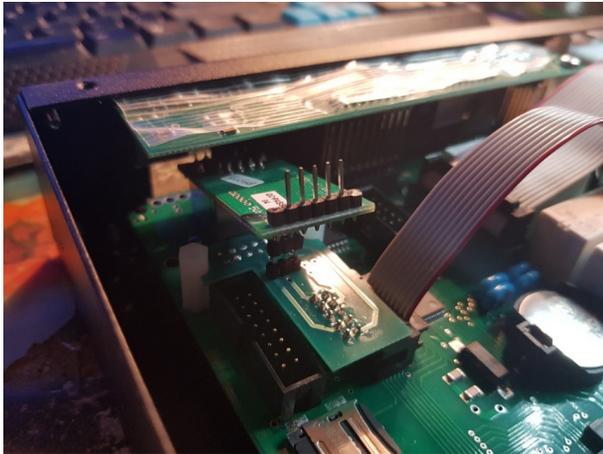


Connect the connection cable to the Mount Board as shown above and install it on the motherboard as shown.

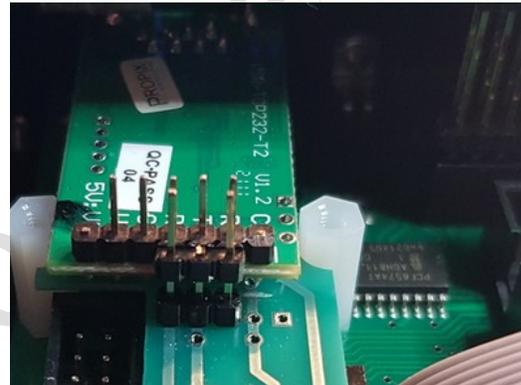
Step 3:

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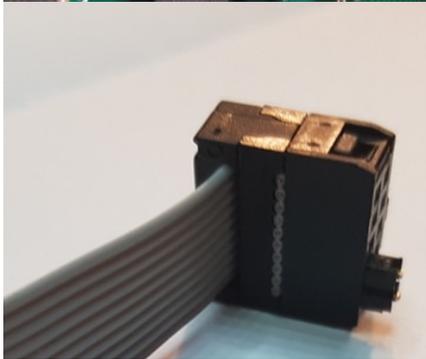
Put the Ethernet main board in as shown above. Gently pull up the upper PCB to allow installation. Align the pins on the main unit and mount board as shown below.



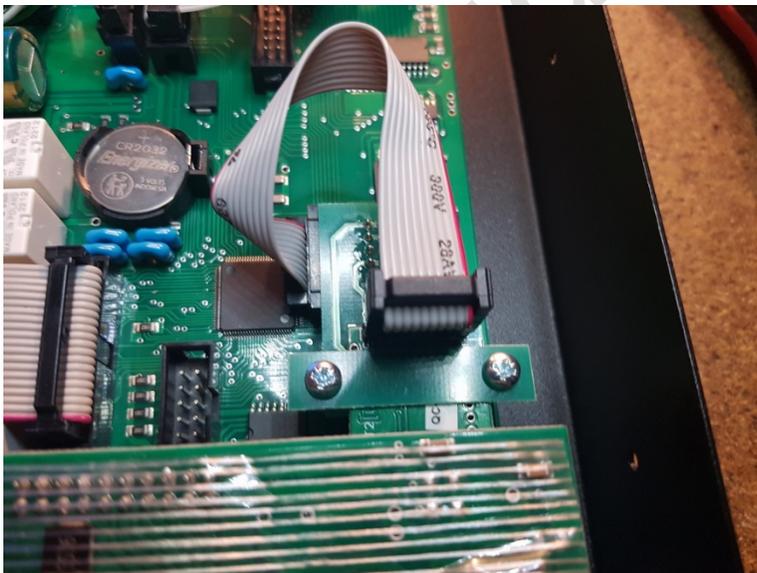
Step 4:

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Attach the free end of the connection cable to the main unit and mount board as shown above. Install the hold down bar as shown below using the screws removed previously



Installation complete

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### 7.2.2 Configuration: In Controller

The Ethernet module is configured by controller's menu. After connecting the LAN cable between computer and controller the IP address is assigned via DHCP. To check assigned IP address go to the SET ETHERNET menu and press arrow right to start checking process:

```
SET ETHERNET  
IP: CHECKING...
```

After a while proper address appear (example here):

```
SET ETHERNET  
IP: 192.168.0.33
```

To communicate with controller via LAN cable user must choose ETH mode at MOTOR CONFIGURATION menu.

To reset Ethernet module simply go to the menu and:

```
SET ETHERNET  
RESET ETHERNET: ON
```

The Ethernet module goes to the default presets.

### 7.2.3 Configuration: Ethernet Main Unit

By default, the module is set in DHCP mode, but after entering the configuration web-site [password: admin, login: admin], you can change it to a static IP:

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By default, the ethernet unit comes from the Factory with the Local IP configured for DHCP as shown below.

con-

The screenshot shows the 'Config' page for the USR module. The 'IP type' is set to 'DHCP'. The 'Static IP' is 192.168.0.7, 'Submask' is 255.255.255.0, and 'Gateway' is 192.168.0.1. The 'DNS Server' is 208.67.222.222. There are 'Save' and 'Cancel' buttons at the bottom of the configuration area.

The user can set a Static IP as shown below.

The screenshot shows the 'Config' page for the USR module. The 'IP type' is set to 'Static IP'. The 'Static IP' is 192.168.12.7, 'Submask' is 255.255.255.0, and 'Gateway' is 192.168.12.1. The 'DNS Server' is 8.8.8.8. There are 'Save' and 'Cancel' buttons at the bottom of the configuration area.

The screenshot shows the 'Config' page for the USR module. The 'Baud Rate' is 460800 bps, 'Data Size' is 8 bit, 'Parity' is None, and 'Stop Bits' is 1 bit. The 'Local Port Number' is 23 and 'Remote Port Number' is 8234. The 'Work Mode' is set to 'TCP Server'. The 'Remote Server Addr' is 0.0.0.0 [192.168.0.201]. There are 'Save' and 'Cancel' buttons at the bottom of the configuration area.

Use Only

Use parameters to suit your own IP network.

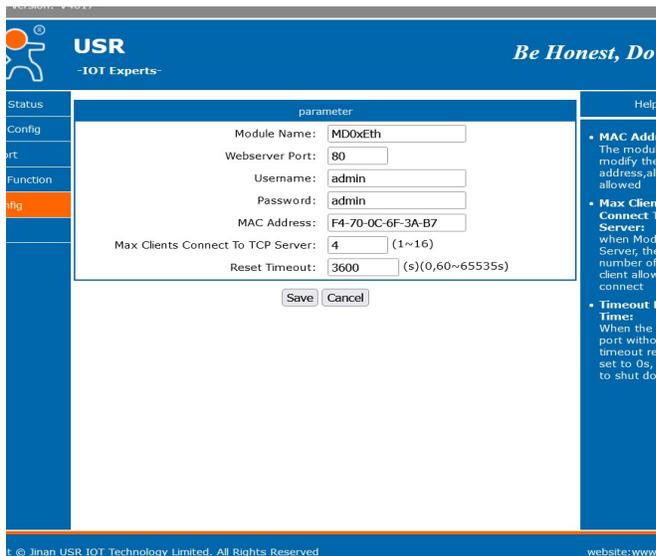
Ensure that the Serial Port is set up as shown below.

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On the Misc Config Page the user can change miscellaneous parameters to help identify the particular controller on the ip network as well as change the Username and password for security.



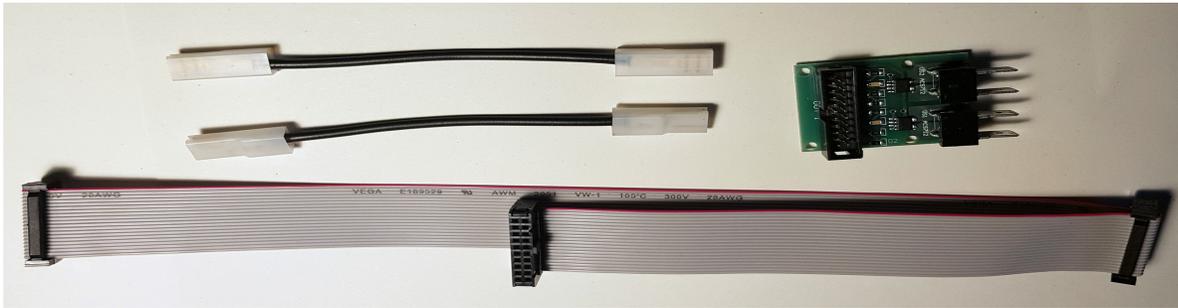
## 8 CCM Current Control Module

### 8.1 CCM Module Installation in MD-01 Controller

The complete Current Control Module Kit is shown below, consisting of the Current Control Module, two wire straps and a ribbon Cable.

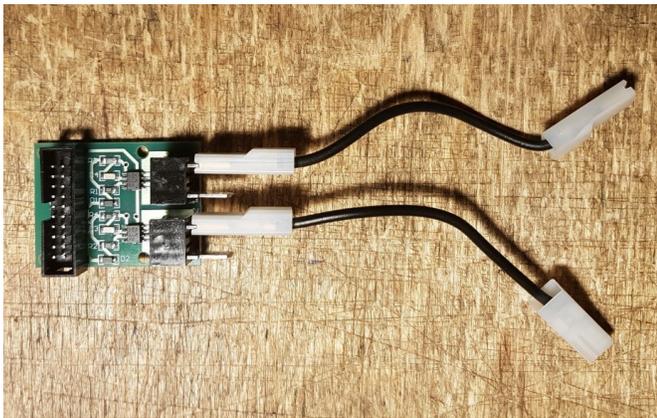
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## Step 1

Attach the two wire straps to the Current Control Module as shown below.



## Step 2.

After removing the cover of the Controller remove the existing ribbon cable between the motherboard and the HR interface board shown in the picture below.



## Step 3

Follow the instructions in section 8.2 below to connect the Current Control Module to the motherboard.

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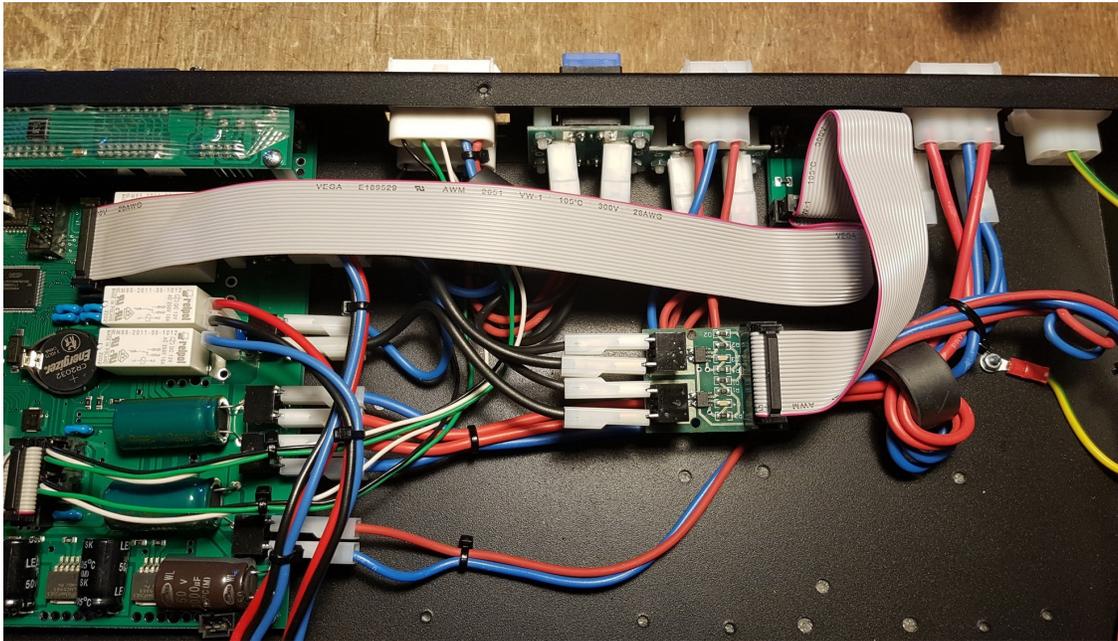
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## Step 4

Install the Current Control Module ribbon cable between the motherboard and the HR interface board and the Current Control Board as shown below.

and



## Step 5

Install and insulate the Current control module so that the module does not touch anything metal.

## Step 6

Re-install the controller cover and proceed to section 8.3 to configure the module.

## 8.2 CCM Module Installation in MD-02 Controller

The complete Current Control Module Kit is shown below, consisting of the Current Control Module, two wire straps and a ribbon Cable.

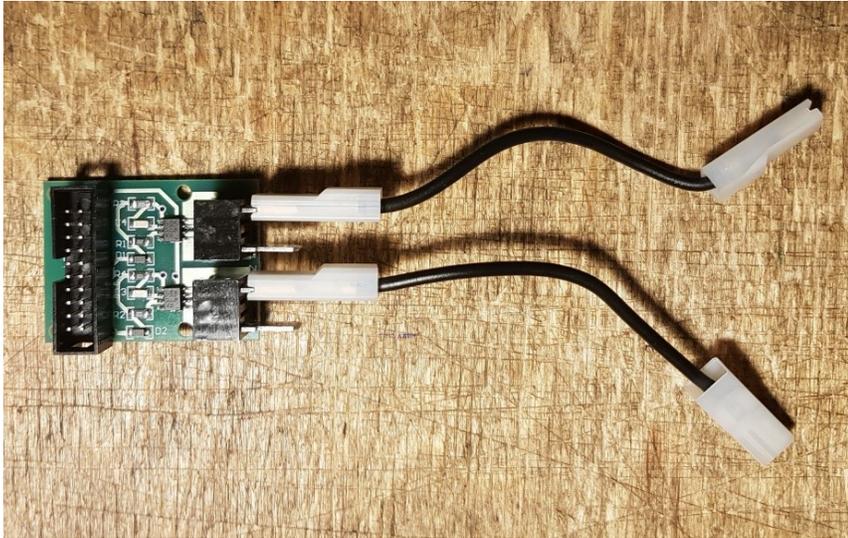


## Step 1

Attach the two wire straps to the Current Control Module as shown below.

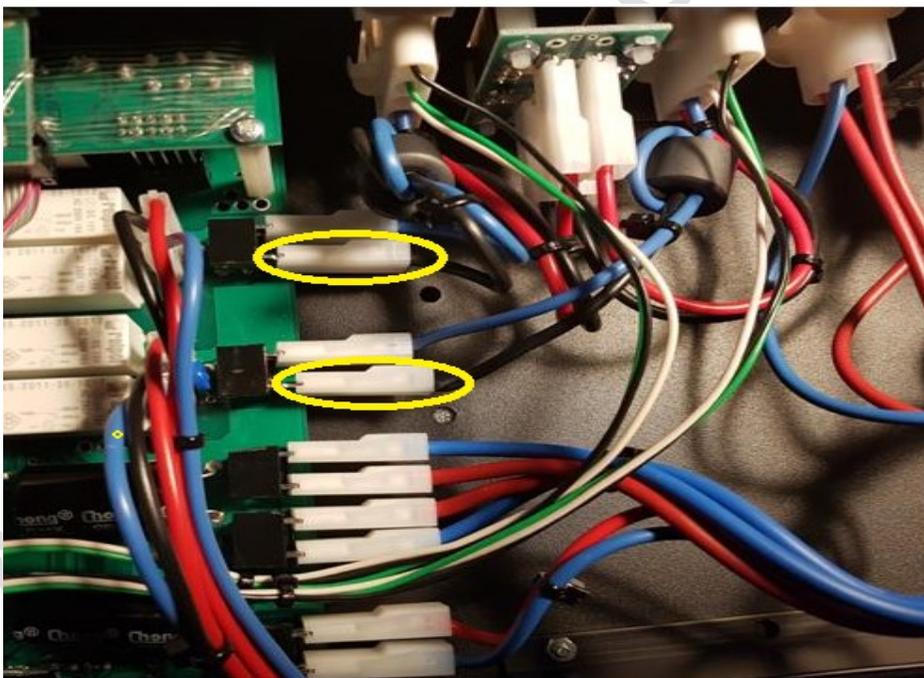
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## Step 2.

After removing the cover of the Controller, remove the two black wires shown below from the motherboard.

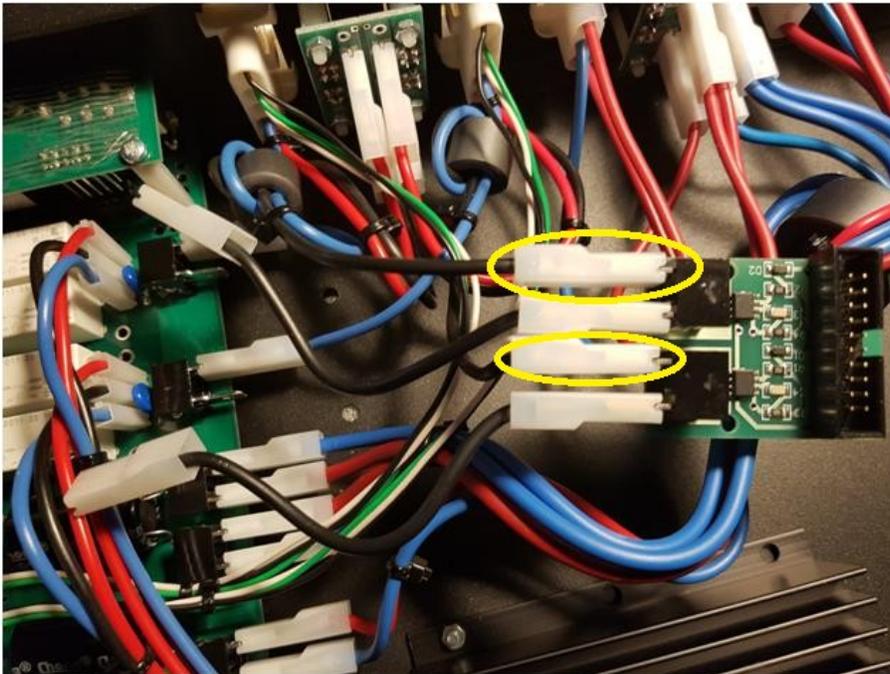


## Step 3

Connect the two black wires removed from the motherboard to the Current Control Module as shown below.

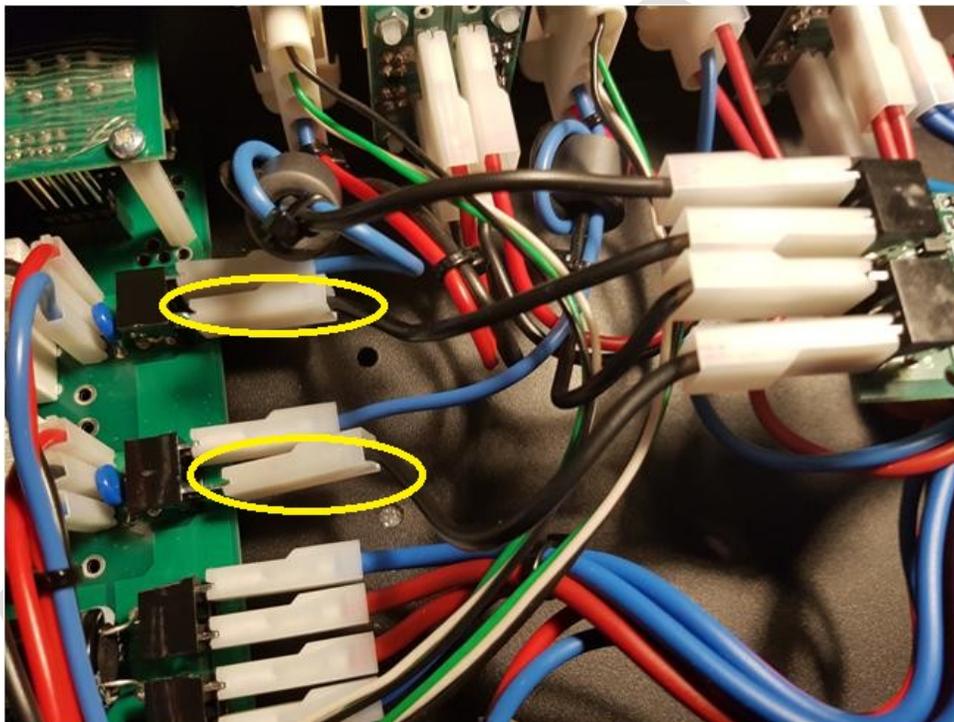
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## Step 4

Connect the free ends of the two wire straps as shown below.



## Step 5

Install the Current Control Module ribbon cable between the motherboard and the HR interface board and the Current Control Board as shown below.

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## Step 6

Install and insulate the Current control module so that the module does not touch anything metal.

## Step 7

Re-install the controller cover and proceed to configure the module.

### 8.3 Configuration of CCM module

1. Choose **SET MOTOR 1** in the controller menu.
2. Turn on CCM module by setting **CURRENT LIMITER** to **ON**.
3. Choose value of module's sensor C. **SENSOR** according to installed CCM module.

```
SET MOTOR 1  
CURRENT LIMITER: ON
```

4. Set **MAX CURRENT** value to the maximum motor supply current at which the protection

```
SET MOTOR 1  
C. SENSOR: 30A
```

will activate.

5. Set **MAX O/C TIME** as the time after which the protection will activate.
6. Repeat steps 1-5 for the second motor.

Save settings and leave menu.

```
SET MOTOR 1  
MAX O/C TIME: 500ms
```

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## 8.4 Operating CCM module

During the operation of the controller, the CCM module controls the current levels of the motors. It happens in the background.



In case of exceeding the declared values of the maximum current **MAX CURRENT** and/or the **MAX O/C TIME**, the controller, depending on which engine is exceeded, will turn off the power supply in an emergency for about 10 seconds with the following message:

```
EM. STOP! O/CURR. M1  
A1: 0.00 E2: 0.00
```



After 10 seconds of emergency power off, the controller is ready to work automatically. However, the operation of the protection should be important information for the user, and as a consequence, the operation of the rotor, antenna carrier system, cable connections and/or the correction of the **MAX CURRENT** parameter should be verified, if it was set too restrictively. These are key issues for the safety of the rotor and the antenna system, therefore extreme care is suggested both when configuring the CCM module and analysing the system status after the current limit message appears.



After installation of the CCM module, the user can observe the value of the motors' current. To activate this function, press the [F2] button once. On the LCD screen, where the rotor position is indicated, the current values of the respective motors will appear. The occurrence of slight fluctuations in current indications during the rotor standstill is a normal situation and results from the internal noise of the measuring sensor. Sample LCD screen during rotor operation:

```
MODE: NORMAL  
A1: 1.4A E2: -2.1A
```

## 9 ORBIITRON Satellite Tracking Program

### 9.1 Using the MD-01/02 with the tracking program ORBITRON

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with the

The MD-01/02 rotator controller has a built in driver to connect Orbitron track software. There are many satellites to track, as well moon and sun, etc.

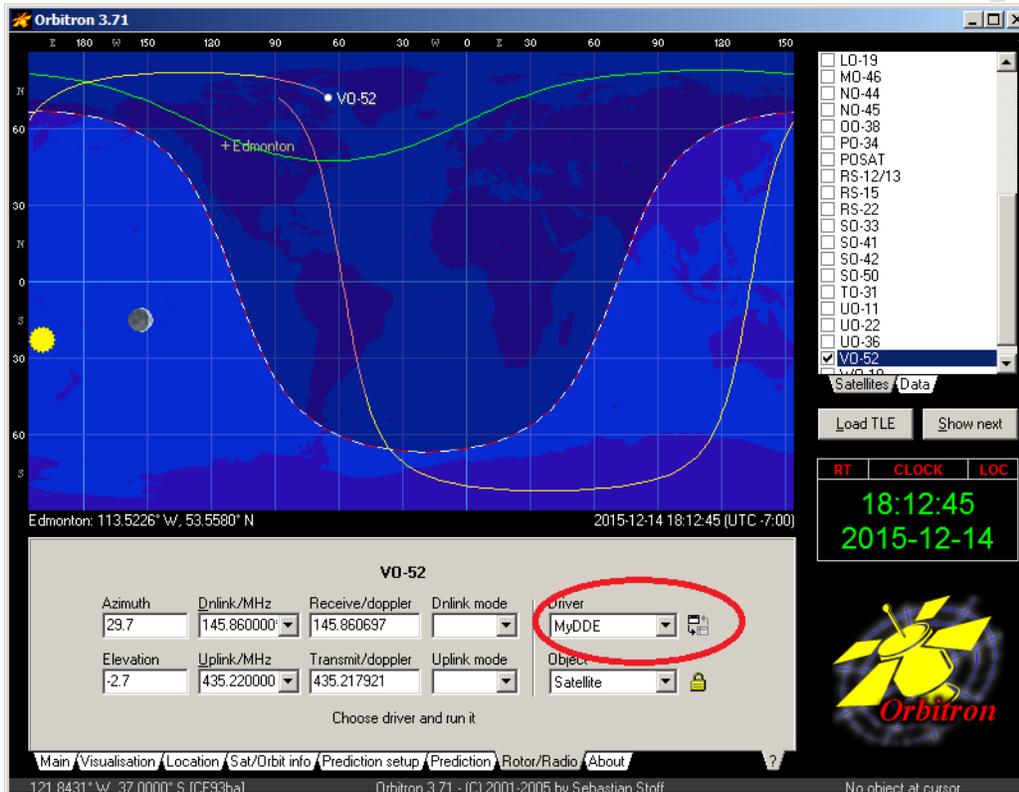
First download the Orbitron program and MyDDE driver from <http://www.stoff.pl/> (links may be found on the Alfa Radio Ltd. website).

Install the program and place the driver in the same directory that the program is installed in. Go through the following steps:

#1 Open the MD-01/02 program and start the ORBITRON program.

#2 Go to the Rotator/Radio tab and select MyDDE from the Driver menu.

#3 Click the refresh button right of the text.



#4 A new screen (My DDE Client) will appear and display tracking data for the satellite selected in Orbitron. Click on "Exit".

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Received string: SN"VO-52" AZ20.9 EL-2.2 DN145860216 UP435219354  
 RA3220.091 RR-0.445 LD287.8121 LA75.7296 AL654.646  
 TU20151215011351 TL20151214181351

Sat name: VO-52      Elevation: -2.2  
 Azimuth: 20.9      Dnlink: 145860216 Hz  
 Uplink: 435219354 Hz      Downlink mode:  
 Uplink mode:      Dnlink mode:  
 Notification: None

DDE conv. status: **Opened**      **Exit**

Parameter	Value
Azimuth	20.9
Elevation	-2.2
Dnlink/MHz	145.860000
Uplink/MHz	435.220000
Receive/doppler	145.860216
Transmit/doppler	435.219354
Dnlink mode	[Dropdown]
Uplink mode	[Dropdown]
Driver	MyDDE
Object	Satellite

DDE conversation with driver is active

Now go back to the MD-01/02 program and select the ORBITRON tab in the MD-01/02 program.

MODE: NORMAL  
 A1: 0.0      E2: 0.0

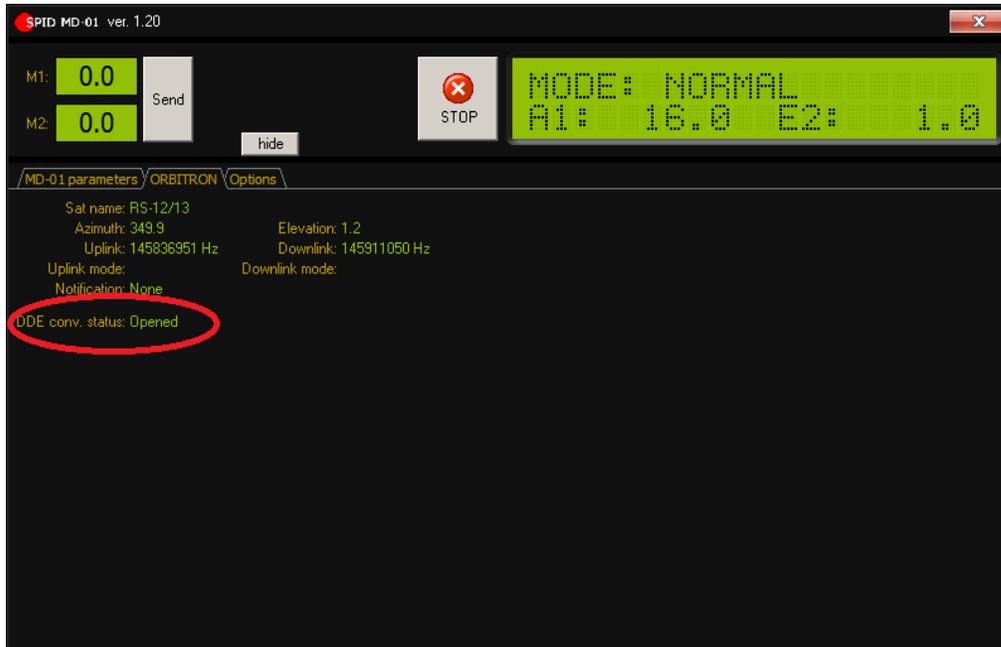
MD-01 parameters: **ORBITRON** Options

Motor configuration	Motor 1	Motor 2
Template: 1:AZ, 2:EL	State: ON	State: ON
Show azimuth: NORMAL	Type: DIGITAL	Type: DIGITAL
Use short way: OFF	Kind: AZIMUTH	Kind: ELEVATION
Use EL map: OFF	Input: MECHANIC	Input: MECHANIC
Const EL map: OFF	Min angle: -180°	Min angle: -15°
Mouse control: OFF	Max angle: +180°	Max angle: 195°
Start: IMMEDIATELY	Gear: 1.000000	Gear: 1.000000
Stop: IMMEDIATELY	Puls timeout: 4 s	Puls timeout: 4 s
Control AE: ETH	Max power: 100%	Max power: 100%
Protocol AE: SPID ROT2	Start powers: 30% 40% 60%	Start powers: 30% 40% 60%
	Start times: 5 s 0 s 0 s	Start times: 5 s 0 s 0 s
	Stop speeds: 50% 40% 30%	Stop speeds: 50% 40% 30%
	Stop times: 2 s 0 s 0 s	Stop times: 2 s 0 s 0 s
	Stop at: 5°	Stop at: 5°

Double click "DDE conv. status:" from closed to open.

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The parameters from Orbitron should now appear in the MD-01/02 screen (AZ & EL) and the rotator should start to move the correct position.

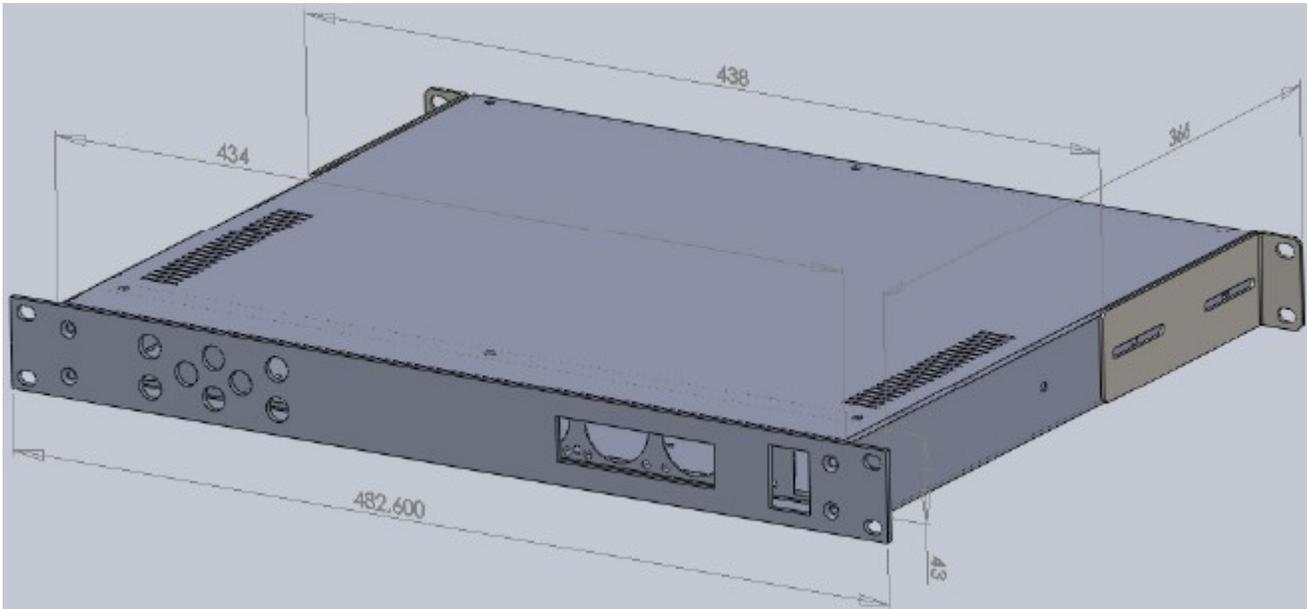
(Parameter AZ & EL must be a positive number.)

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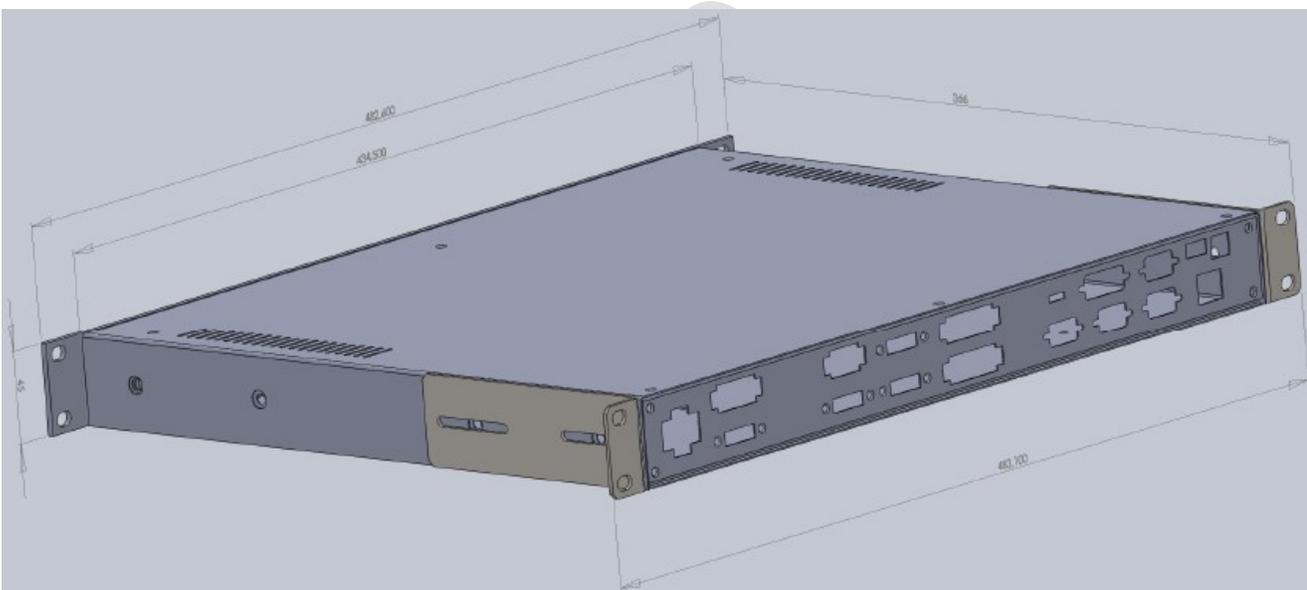
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## MD-01 Controller Dimensions:



*Controller MD-01 Dimensions FRONT*



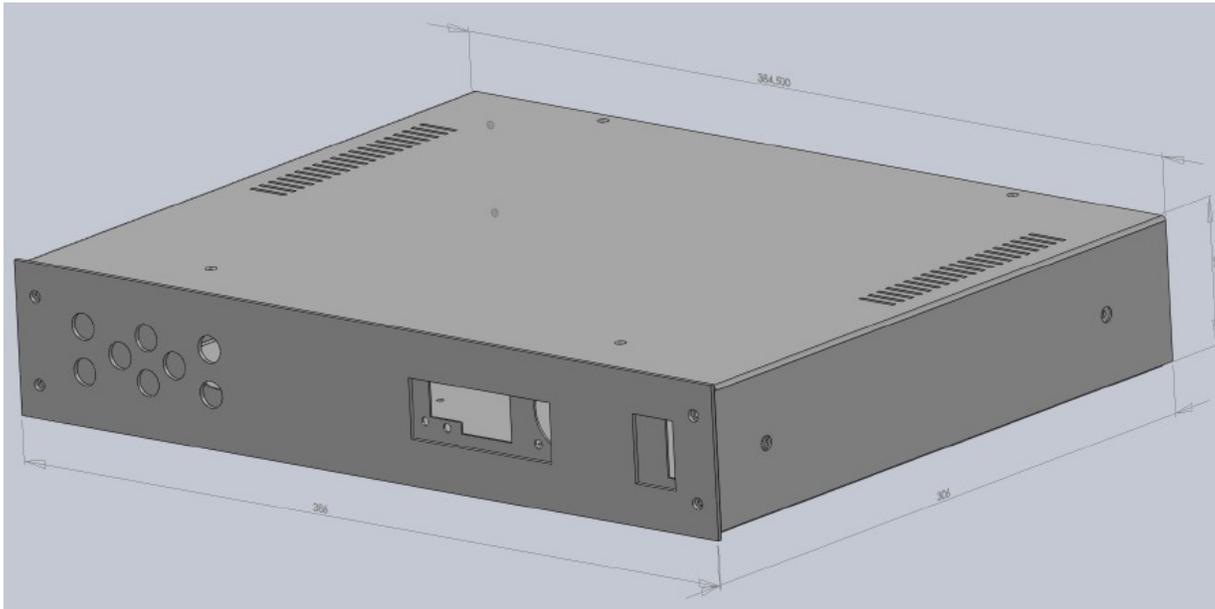
*Controller MD-01 Dimensions BACK*

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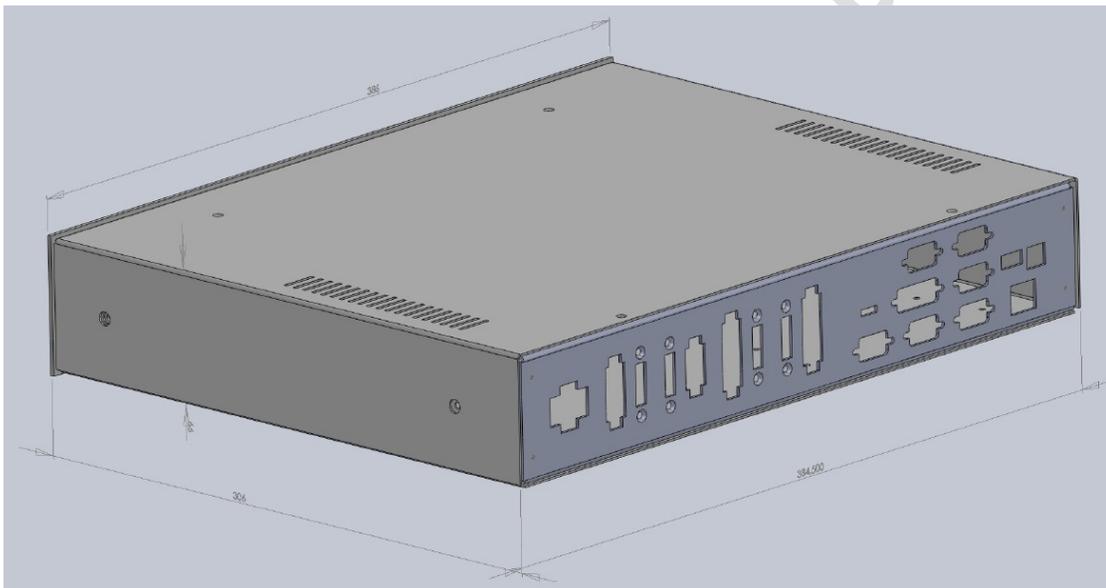
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## MD-02 Controller Dimensions:



*Controller MD-02 Dimensions FRONT*



*Controller MD-02 Dimensions BACK*

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## 12 MONTH LIMITED WARRANTY *AlfaSpid Rotators and controllers*

**Alfa Radio Ltd.** warrants to original purchaser of the product, that the product will be free from defects in material and workmanship for the following periods after such date of purchase: Material - 12 months Workmanship - 12 months.

**Alfa Radio Ltd.** will, at its discretion, repair or replace free of charge such defective products subject to the following conditions:

1. Delivery of the product **prepaid** to **Alfa Radio Ltd.** or its authorized dealer.
2. Determination by the **Alfa Radio Ltd.** that a defect exists and is covered by the limited warranty.
3. Defects due to alteration, repair by an unauthorized person, misuse, accidental damage, lightning strikes, use of the equipment for purposes other than those for which it was designed, and the like, are **NOT COVERED** by this limited warranty. Repairs in these cases will be subject to normal service charges.
4. Damage to a **Alfaspid** rotator or controller caused by using said rotator or controller with a rotator or controller manufactured by any other manufacturer will **NOT BE COVERED** by this limited warranty.
5. Repairs and replacement parts are covered under this limited warranty only for the remaining term of the original limited warranty.
6. Under no circumstances is **Alfa Radio Ltd.** liable for consequential damages to person(s) or property by the use of this product.
7. **Alfa Radio Ltd.** reserves the right to make changes or improvements in design or manufacture without incurring any obligations to install such changes in any of the products previously manufactured.
8. All claims of defect or shortage should be sent prepaid to:

**Alfa Radio Ltd.**

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and must be accompanied by a letter describing the problem in detail along with a copy of your proof-of-purchase.

Contact **Alfa Radio Ltd.** before sending.