ServoDog DMX

14 Channel Digital I/O Controller
Protocols: DMX512, LOR & MiniSSC

User Manual
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V1.0
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### NOTE WELL

MiniSSC protocol is NOT active in the current release of the ServoDog firmware. This functionality will be included in firmware released in the 1st quarter of 2010.
**Introduction**

The Light-O-Rama (LOR) ServoDog is a 14 channel digital controller that can perform digital input, digital output, servo control and PWM dimming. It has six single bit input channels and eight single bit output channels. The output channels are independently configurable as digital output or servo output. Two of the output channels can be configured as PWM dimmers. These two channels also have MOSFET buffers which can be used as on/off switches or PWM dimmers. The MOSFETs can sink 2 amps.

The 8 output channels are fully buffered and each is capable of sourcing or sinking 24 ma at 5 VDC. The input channels can be used with simple switch closures or driven with +5 VDC logic.

The ServoDog is configured with the Windows ServoDogUtility. The ServoDog automatically detects and obeys LOR, DMX512 and MiniSSC protocols. Command sequences created with the LOR ShowTime software can be downloaded into the ServoDog’s EEPROM so it can run stand-alone.

The Windows Showtime software is used to design and build Sequences (controller commands that may be choreographed to audio/music.) These user created sequences and/or pre-programmed musical sequences available from LOR are then arranged into Shows. These shows are played by your PC or one of the LOR Show Directors which command the controller(s).

**What’s in the Box**


**ServoDog Utility**

The ServoDog Utility is included with the S2 ShowTime Software suite. The free demo version contains a fully function ServoDog Utility and is available here [http://www.lightorama.com/SoftwareDownloadPage.html](http://www.lightorama.com/SoftwareDownloadPage.html).

To use the ServoDog configuration utility a LOR RS485 adapter is required. The SC485 is a serial port to RS485 adapter. The USB-RS485, USB485 with booster and USB485 Isolated are USB to RS485 adapters. The USB adapters include the Windows drivers on CD and the USB cable to the PC. All are available here: [http://store.lightorama.com/accessories.html](http://store.lightorama.com/accessories.html).

**Hardware Utility**

The Hardware Utility is not strictly required by the ServoDog controller but may be used to set the Unit ID and test it as with other LOR controllers.

Configuration of the ServoDog requires the use of the ServoDogUtility included with the controller.

The version of the Hardware Utility appears in the title bar to the right of “Light-O-Rama Hardware.” If the version number is less than 2.5.0, then you need a new Hardware Utility. The latest version is
Software Control

The ServoDog appears in an LOR Network at the Unit ID Assigned to it. The 8 output channels appear as 8 channels numbered 1 through 8 in the Sequence Editor.

Since the individual output channels can be configured to do different functions (digital output, PWM dimming or servo control) the behavior in response to LOR commands, DMX intensities or MiniSSC position values depends upon how a particular channel is configured.

Digital Input Channels

Digital input channels are used to sense user inputs, and are normally used to provide for interaction in LOR shows. See the How to Connect Input Switches section for information on connecting push-buttons or switches.

Input 1 can also be used to start an internal stand alone animation sequence. See the Stand Alone Operation section for more information.

Digital Output Channels

On an LOR network, a digital output channel is ON for any intensity greater than zero, otherwise it is OFF. Shimmer will rapidly turn ON and OFF a digital output channel. Twinkle will randomly turn ON and OFF a digital output channel.

PWM Channels

Two of the output channels (4 & 5) can be configured as digital out or PWM dimming. These channels also have MOSFETs on them. The MOSFETs ground an attached load when activated. Each MOSFET can sink 2 amps at 50 volts DC. Channels 4 & 5 behave like all other channels when configured as digital outputs or servo outputs.

When configured for PWM dimming, they provide 256 steps in the duty cycle. The PWM duty cycle is about 1/4000 of a second. On an LOR network, the duty cycle will be linearly proportional to the LOR intensity. PWM channels support the full range of LOR effects.

In a DMX universe, the duty cycle will be linearly proportional to the DMX intensity.

In a MiniSSC environment, the duty cycle will be linearly proportional to the position value.

Servo Output Channels

On an LOR network, these channels respond to Sequence Editor commands in the same was as a normal lighting controller. 0% intensity is minimum pulse width (fully left or counterclockwise,) 50% intensity is median pulse width (centered) and 100%
ServoDog

intensity is maximum pulse width (fully right or clockwise.)

Note that shimmer and twinkle are not supported on servo channels.

In a DMX universe, the intensities linearly control the pulse width. Intensity of 0 is minimum pulse width, 128 is median pulse width and 255 is maximum pulse width.

In a MiniSSC environment, position values linearly control the pulse width. A position value of 0 is minimum pulse width, 127 is median pulse width and 254 is maximum pulse width.

**Unit ID for Various Protocols**

**LOR Network**
The ServoDog appears as an 8 channel controller at the assigned Unit ID.

**DMX Universe**
The ServoDog appears as 8 consecutive addresses starting at the base specified by the Unit ID. See the LOR Unit ID to DMX Address Table section.

**MiniSSC**
In the MiniSSC protocol, servo numbers 0-7 appear on Unit ID 01, servo numbers 8-15 appear on Unit ID 02, etc.

**Assigning a Unit ID**
You can assign a Unit ID with the ServoDog Utility, see the Unit ID sub-section in the Configuring the Output Channels section.

ServoDog

You can also assign a Unit ID with the Hardware Utility as follows.

If you have not installed the Light O Rama Windows Showtime Software, do it now. You will also need one of the RS485 adapters installed. See the Connecting the ServoDog to a PC section for more information.

Power up the ServoDog. The Status LED will blink about twice/second. This means that the controller has booted and is waiting for the PC to talk to it.

Start the Hardware Utility – click start ► All Programs ► LightORama ► Light-O-Rama Control Panel. There will be a light bulb with a blue halo on the right side of the task bar at the bottom of the screen. Right-click the light bulb and select Hardware Utility from the menu. Make sure the LOR Control tab is selected. You will see this window:

Click the Auto Configure button in the Setup Comm Port section. The Hardware Utility will search for the
COM port that your RS485 adapter is plugged into and select it.

When assigning a unit ID, only one controller may be plugged into the RS485 adapter on the PC. Be sure you do not have more than one controller connected.

Steps to set/change unit ID:

1. In the Change Existing ID section, use the Old Unit ID drop-down menu to select Any Unit, then click OK in the warning box for changing all unit IDs, there should only be one unit attached.

2. Use the New Unit ID drop down menu to select “01” or whatever Unit ID you want.

3. Click the Change Unit ID button to set your ServoDog unit ID. You will see a Unit ID Changed box – click OK.

Configuring the Output Channels

The ServoDog configuration utility is part of the Windows Showtime Software (S2) and is available for free download here:

This utility requires that the ServoDog be connected to the Windows PC with an LOR USB adapter. See the Connecting the ServoDog to a PC section for more information.

The utility allows real time control of the channels to set the motion parameters for each servo. Below is a picture of the Simulator Screen.
**Comm Port**

Use the *Comm Port* drop down menu to select the comm port of the RS485 adapter connected to the ServoDog.

When the ServoDog is powered up but not connected to a PC, the Status LED will blink about twice/second. This means that the controller has booted and is waiting for the PC to talk to it.

Once the ServoDog is physically connected to the PC, the ServoDog Utility is running and the comm port is set correctly, the Status LED will go on solid. This indicates that the ServoDog is receiving polls from the utility.

**Unit ID (Selecting and Setting)**

Use the *Select Unit ID* drop down menus to select a particular ServoDog controller.

You can also set the Unit ID of a connected ServoDog controller by selecting a Unit ID and clicking the *UPDATE Unit ID* button. You must have only one ServoDog controller connected to the comm port for this operation to work properly.

**GET (read) Configuration**

Use the green *GET (read) Configuration* button to retrieve the current configuration from the EEPROM memory of the selected ServoDog controller.

**SEND (write) Configuration**

After changing any parameters for the selected ServoDog controller you must click the red *SEND (write) Configuration* button to write the new configuration to the EEPROM memory of the ServoDog controller.

**Simulator Screen**

The following parameters can be adjusted for each channel using the Simulator screen. Detailed descriptions follow.

- Actual pulse range
- Default position
- Lost communications parameters
- Neutral trim
- Power up parameters
- Virtual pulse range
- Virtual Stops

**Channel Configuration**

Select one of the channels by clicking the images at the bottom of the window. The options for that channel will appear to the right of your selection. You can choose Servo or Digital for any channel. You may also choose PWM for channels 4 and 5.

**Actual Pulse Range**

The actual limits of the servo. These values are used only to provide limits when setting other parameters. The values are not used to calculate any arm positions.

**Channels to apply changes**

If you are currently adjusting Channel 1 parameters, make changes and then want those changes to be applied to other channels, check the appropriate boxes.
Default Position
The optional position for “Power Up” and “Lost Communications” situations. Lost communications is only sensed for LOR and DMX networks.

Lost Communications Parameters
Selects how the servo channels behave when communication with a LOR network or DMX universe is lost:
- Hold at current position
- Move to default position
- Move to neutral position
- Stop pulsing, start on first command

Neutral Trim
Shifts everything left or right to “zero” the position of the servo arm.

Power Up Parameters
Selects how the servo channels are handled when the ServoDog first powers up:
- Move to default position
- Move to neutral position
- Start pulsing on first command received

Test Buttons
Send commands to move a servo on the selected channel to the selected position. In the case of testing a range, the servo position is moved back and forth through the range. The actual servo will move much like you see the simulator move.

Virtual Pulse Range
The values used to compute arm position. When an intensity is mapped to a pulse value you have 0% = minimum virtual value and 100% = maximum virtual value 50% = (virtual max - virtual min) / 2, ...

Virtual Stops
Places hard stops that prevent the servo arm from going out of this range even though the Virtual Pulse Range would allow it. You could have a stop that would not allow the arm to go below 20% intensity….

Use slider to test intensity values
If this box is checked then when you move the slider below the large servo simulator graphic, you will send the actual pulse values to the ServoDog to control the servo on the selected channel.

Warning: Actual pulse values are sent to the ServoDog when you are testing. The ServoDog is not receiving intensity commands but rather “Send pulses with duration of 1500 uS” commands, so any limits in the ServoDog are bypassed.
**Hardware Description**

Refer to the following diagram for the hardware description. The upright orientation is shown below. Note that the *Light O Rama, Inc.* silk-screening is upright on the upper left, the network connection jacks are center left and the 24-pin servo header is on the right.

**Reset Header**

The jumper must be on the reset header for the ServoDog to function normally. To reset the ServoDog, power it off, remove the jumper, power it on and wait for the Status LED to start blinking. The ServoDog is reset at this point. Power it off and replace the jumper for normal operation.

**Power Block Diagram**

**Warning:** Be very careful not to switch the polarity when applying power to the ServoDog or you will damage it.

V+ must be at least 6 VDC for the ServoDog to function.

V+ must be at least 9 VDC to use Voltage Regulators 1 and 2.

V+ should not exceed 14 VDC.

V1 & V2 are set to approximately 6 VDC when the unit is shipped.
ServoDog

M1 and M2 MOSFET Terminals

Servo Power Options

Servo power must be provided through screw terminals S1 and S2.

S1 supplies the positive DC voltage to servo header servos 1 through 4. S2 supplies the positive DC voltage to servo header servos 5 through 8.

You can use either, both or neither V1, V2 voltage sources for the servos. A positive voltage must be connected to S1 and S2 to use the servo header.

S1 is jumpered V1 and S2 is jumpered to V2 when the unit is shipped.

RJ45 Network Connections

In order to use your ServoDog, you must connect it to a Windows PC, a LOR Show Director or run it in stand alone mode (see the Stand Alone Operation section.)

ServoDog

LOR Network

These jacks are designed for direct connection to an LOR network using Cat5e LAN cables. You will only be able to set the Unit ID and configure the servo pulse ranges with LOR utilities through an LOR RS485 adapter.

The LOR RS485 adapters appear as ordinary COM ports on the PC and can be used with applications using MiniSSC protocol.

DMX Universe

An RJ45 to XLR3 adapter can be used to connect the ServoDog to a DMX universe. This adapter is available here: http://store.lightorama.com/rjtoxlr3ma.html

More information on using LOR controllers with DMX can be found in this document: http://lightorama.com/Documents/DMX-DOC.pdf

RS232 Serial

The ServoDog understands MiniSSC protocol at 2400 and 9600 bps. An RS232 to RS485 converter or RS485 adapter should be used, but direct connection of the RS232 serial port Transmit to RS485 A and Signal Ground to RS485 B on the ServoDog will work.

You will not be able to use the ServoDog Utility without an LOR RS485 adapter, but you can control the ServoDog channels since there is no back communication from the ServoDog.
**Connecting to a PC**

You will need the following to connect your ServoDog controller to a PC:

- Showtime Windows Software or ServoDog Utility
- LOR RS485 Adapter
- CAT5e LAN cable
- Your ServoDog controller
- Windows PC running 98 SE, 2000, ME, XP or Vista

The following diagram shows how the pieces fit together:

1. Your PC running the Showtime Windows Software
2. Your PC speakers to play the music
3. RS485 Adapter to convert short distance USB to long distance RS485 or RS232 serial to RS485
4. CAT5e LAN cable
5. ServoDog controller

If your USB adapter has more than one jack, you can use either.

**Connecting to a Show Director**

You will need the following to connect your ServoDog controller to a Show Director:

- LOR1602MP3 Show-in-a-Box controller (has an internal DC-MP3 Show Director), mDM-MP3 Show Director or DC-MP3 Show Director
- CAT5e LAN cable
- Your ServoDog controller

You can use either jack on the Show Director and either jack on the ServoDog.

The cable connecting a show director to the controller should be 50’ or less in length. Longer cables may result in a voltage drop causing erratic operation of the show director. This 50’ limitation does not apply to the Show Director internal to the LOR1602MP3. It gets its power for the co-housed controller.

**Connecting to another Controller**

You can use Cat5e cable to go from either large jack on one controller to either large jack on the other controller.
**Digital Inputs Header**

1 – Input 1  
2 – Input 2  
3 – Input 3  
4 – Input 4  
5 – Input 5  
6 – Input 6  
7 – Accessory V+  
8 – N/C  
9 – 5 VDC  
10 – Ground

**Digital Outputs Header**

1 – Ground  
2 – 5 VDC  
3 – Output 1  
4 – Output 2  
5 – Output 3  
6 – Output 4  
7 – Output 5  
8 – Output 6  
9 – Output 7  
10 – Output 8

**Servo Control Header**

1-8 are servo pulse outputs  
S1 is the screw terminal for +DC for servos 1-4  
S2 is the screw terminal for +DC for servos 5-8  
G is the screw terminal for ground

**Status LED1**

- Blinks twice per second if the ServoDog has booted correctly  
- Solid on if the ServoDog sees a network director – i.e. a PC, Show Director or DMX universe  
- Blinks one long on and a short off repeatedly if in the bootloader. This means that the firmware is not loaded or corrupted. See the *Updating the ServoDog Firmware* section to load firmware

**How to Connect Input Switches**

The following diagram shows how to connect a few push button (momentary contact) switches to a digital input 10-pin header.
SW1 and SW2 are normally open (NO) switches, meaning they complete the circuit when pressed. SW3 is a normally closed (NC) switch that breaks the circuit when pressed.

Note that inputs on the ServoDog are pulled up to 5 VDC with 10KΩ resistors. This means resistors are not required on switches. These input channels can also be driven by 5 VDC logic if the logic can sink 0.5 mA.

**Input/Output Connection Header**

A header is available for the ServoDog that converts the input and output pin headers to screw terminals where A1-A6 are the inputs and B1-B8 are the outputs:

![Header Image](image)

This header is available here:
http://store.lightorama.com/mp3dicohe.html

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**Stand Alone Operation**

A stand alone animation sequence (sequence with no accompanying audio) can be downloaded into the EEPROM of the ServoDog controller.

This sequence can contain approximately 10,000 commands. These commands can also be for controllers other than this controller, so this controller can direct a network of controllers. There are no restrictions on the types of LOR controllers in this network.

The sequence is designed and tested using the Showtime Software Sequence Editor. When you are happy with the sequence, save it and stop the Sequence Editor.

Start the Hardware Utility and click the **Refresh** button to find the ServoDog. Use the drop down menu next to the **Refresh** button to select the correct ServoDog controller.

Click the **Standalone** button at the bottom of the window. Select one of “Run when power is on,” “Input (norm open switch)” or “Input (norm closed switch.)” Click the **Send Trigger info to Unit** button.

Finally, Use the **Open** button to browse to your sequence and click the **Download** button.

You also use this screen to remove downloaded standalone sequences. Note that all downloaded sequences are removed.
Updating Controller Firmware

Periodically, Light-O-Rama may distribute new firmware for the ServoDog. If you believe you need updated firmware, use the Hardware Utility to determine your current firmware version. Use the Refresh button to find your controller and check its firmware version. The drop-down menu to the right of the Refresh button will be filled in with the attached controllers. The right part of the controller name in this drop-down is the current firmware version.

If the controller type or firmware version is not present, get the latest Hardware Utility from www.lightorama.com ► Support ► (bottom of page) Download Hardware Utility. Run the program downloaded to install the Hardware Utility and devices text file. Retry the Refresh operation.

The latest firmware can be found by going to www.lightorama.com ► Support and scrolling down to the Using the Hardware – Documentation and Firmware section. Find your controller and roll the mouse over the Firmware button – look at the bar in the lower left of the browser window. It will show the name of the firmware file. The file name contains the version at the end. If the version number is greater than what you saw in the Hardware Utility, new firmware is available. Click the Firmware button to download the firmware installer to your PC – remember where you put it.

Run the firmware installer to install the new firmware into the firmware directory. Note the name of the .lhx file.

To load new firmware use a data cable (not wireless) to connect the ServoDog to the PC. Start the Hardware Utility and click the Refresh button to find your controller(s). Select the one you want to update from the drop-down menu to the right of the Refresh button. Click the Firmware button at the bottom of the window.

In the Firmware section of the window, under Step 1 – Select Unit, chose Selected unit listed above. Under Step 2 – Select Firmware File, use the Open button to browse to the firmware file you downloaded. Under Step 3 – Press Download Button click the Download button. Do not interrupt this process. Your controller will reboot after the download completes.

You can click the Refresh button to see that the new firmware was loaded into your controller. Repeat this process for additional controllers.
LOR Unit ID to DMX Address Table

The Hardware Utility is used to set the Unit ID of the ServoDog. See the section Assigning a Unit ID for more information. The controller must be set to one of the LOR Unit IDs listed in the following table to recognize DMX protocol. E.g. setting the LOR Unit ID to "06" will result in the first DMX address for the controller being 41.

<table>
<thead>
<tr>
<th>LOR Unit ID</th>
<th>DMX Address</th>
<th>LOR Unit ID</th>
<th>DMX Address</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;01&quot;</td>
<td>1</td>
<td>&quot;21&quot;</td>
<td>257</td>
</tr>
<tr>
<td>&quot;02&quot;</td>
<td>9</td>
<td>&quot;22&quot;</td>
<td>265</td>
</tr>
<tr>
<td>&quot;03&quot;</td>
<td>17</td>
<td>&quot;23&quot;</td>
<td>273</td>
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<tr>
<td>&quot;04&quot;</td>
<td>25</td>
<td>&quot;24&quot;</td>
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<td>&quot;05&quot;</td>
<td>33</td>
<td>&quot;25&quot;</td>
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<td>&quot;06&quot;</td>
<td>41</td>
<td>&quot;26&quot;</td>
<td>297</td>
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<td>&quot;07&quot;</td>
<td>49</td>
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<td>&quot;29&quot;</td>
<td>321</td>
</tr>
<tr>
<td>&quot;0A&quot;</td>
<td>73</td>
<td>&quot;2A&quot;</td>
<td>329</td>
</tr>
<tr>
<td>&quot;0B&quot;</td>
<td>81</td>
<td>&quot;2B&quot;</td>
<td>337</td>
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<tr>
<td>&quot;0C&quot;</td>
<td>89</td>
<td>&quot;2C&quot;</td>
<td>345</td>
</tr>
<tr>
<td>&quot;0D&quot;</td>
<td>97</td>
<td>&quot;2D&quot;</td>
<td>353</td>
</tr>
<tr>
<td>&quot;0E&quot;</td>
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<td>&quot;2E&quot;</td>
<td>361</td>
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<td>&quot;1F&quot;</td>
<td>241</td>
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<td>&quot;20&quot;</td>
<td>249</td>
<td>&quot;40&quot;</td>
<td>505</td>
</tr>
</tbody>
</table>
# Specifications

<table>
<thead>
<tr>
<th>Specifications</th>
<th>Details</th>
</tr>
</thead>
<tbody>
<tr>
<td>Dimensions</td>
<td>4½”w x 2¼”h x 1”d</td>
</tr>
<tr>
<td>Channels</td>
<td>14 = 6 input + 8 output</td>
</tr>
<tr>
<td>Configuration</td>
<td>Outputs individually configured as digital output or servo control</td>
</tr>
<tr>
<td>High current and PWM</td>
<td>Two outputs with MOSFETs</td>
</tr>
<tr>
<td></td>
<td>Also configurable as PWM</td>
</tr>
<tr>
<td>Servo Update Rate</td>
<td>50 Hz</td>
</tr>
<tr>
<td>PWM Speed</td>
<td>4 KHz</td>
</tr>
<tr>
<td>Trigger Sensitivity</td>
<td>Minimum pulse width to sense a trigger input is 10 ms</td>
</tr>
<tr>
<td>Input Voltage</td>
<td>6 to 14 VDC</td>
</tr>
<tr>
<td>Source/Sink current for digital/servo outputs</td>
<td>24 ma maximum</td>
</tr>
<tr>
<td>MOSFET Sink current</td>
<td>2 amps @ 50 VDC</td>
</tr>
<tr>
<td>Channel Input/Output voltages</td>
<td>Approximately 0 and 5 VDC</td>
</tr>
<tr>
<td>V1 &amp; V2 Voltage Regulators</td>
<td>1 amp each</td>
</tr>
<tr>
<td></td>
<td>Voltage range: 4 to 9 VDC</td>
</tr>
</tbody>
</table>

Light-O-Rama, Inc.  
Tel: (518) 539-9000  
Fax: (518) 538-0067  
info@lightorama.com