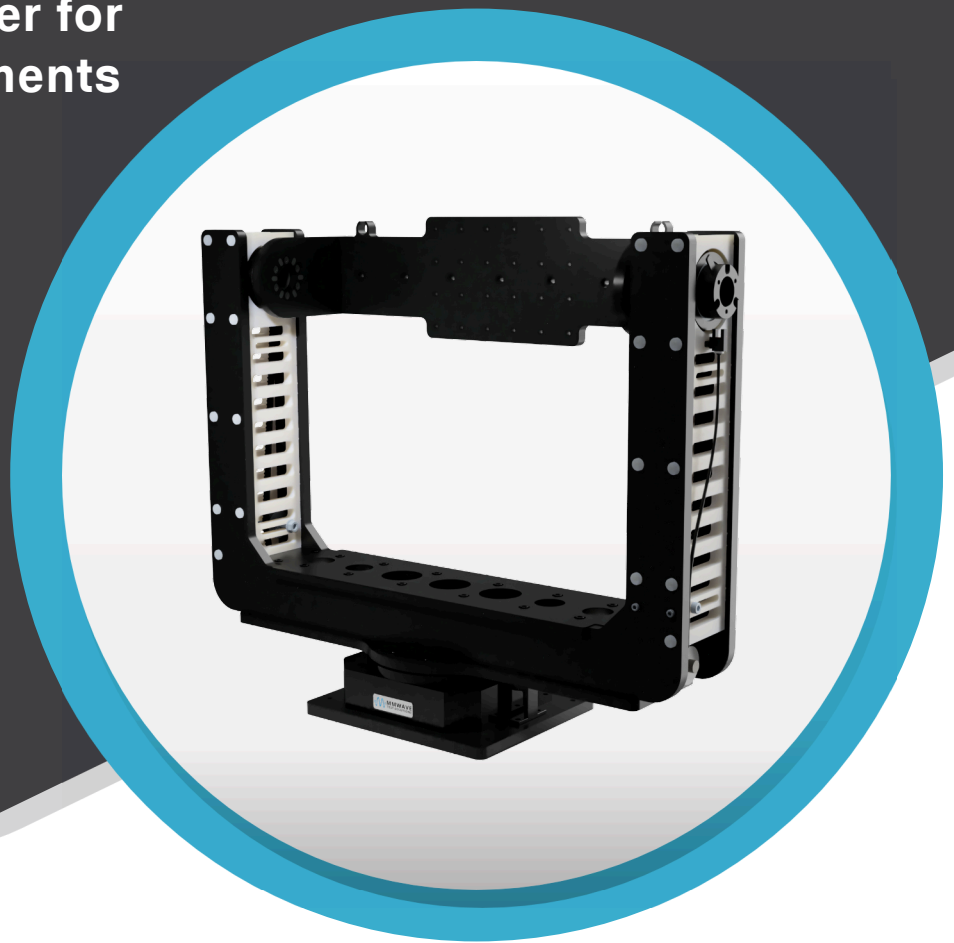


# DUO5

## Precision Positioner for Antenna Measurements



## FEATURES

### Designed for Large Device-Under-Test

DUT size up to 50 cm width (20") and 14 kg (31 lb.)

### High-Quality Components

Heavy-duty instrument turntable, high-torque motors, and precision gears.

### Quality Software

Clear structured Python and MATLAB source code.

### Closed-Loopdrive system

Closed-loop motor control system to guarantee positioning accuracy.

# INTRODUCTION

The DUO5 is the largest positioner in the DUO series, and holds an AUT/DUT up to 14 kg and an impressive 50 cm width.

Like our other positioners in the DUO series, the DUO5 arm system is engineered from polymer plastics and is 100 percent metal free in the upper section to perform well in communications and radar antenna applications.

Quality components are used throughout the design to secure the highest mechanical precision, and the DUO5 will offer high resolution and accuracy year after year.



## HARDWARE

The DUO5 uses over-specified quality components to secure continuous reliable performance. Components have been carefully selected for precision under maximum load, and all motors are running in closed-loop feedback from digital encoders to guarantee the quality.

The azimuth turntable is instrument-grade in cast aluminum, and the 1:180 gearing offers both high precision and high torque. The turntable is rated for 55 kg load, guaranteeing the performance even in the most demanding applications.

The arm design is CNC-machined to precision, offers maximum strength, and uses Polyoxymethylene (POM/Acetal/Delrin™), Polyethylene terephthalate (PET), and FR4/FRP. These materials all offer a low dielectric constant to limit stray reflections, and will withstand high chamber temperatures.

The arm uses a dual motor setup, one for each side, combined with quality single-stage gears for high accuracy, low backlash and holding torque. The belt drive system uses dual timing belts, a significant upgrade from the traditional single 6 mm belt, guaranteeing high precision under all loads.

A USB-connected controller controls the motor system (Serial-over-USB) and comes with reference applications in both Python and MATLAB. The controller's clean native instruction set makes it easy to develop a new application in any language.

# SOFTWARE

A Python control applications is included with the system.

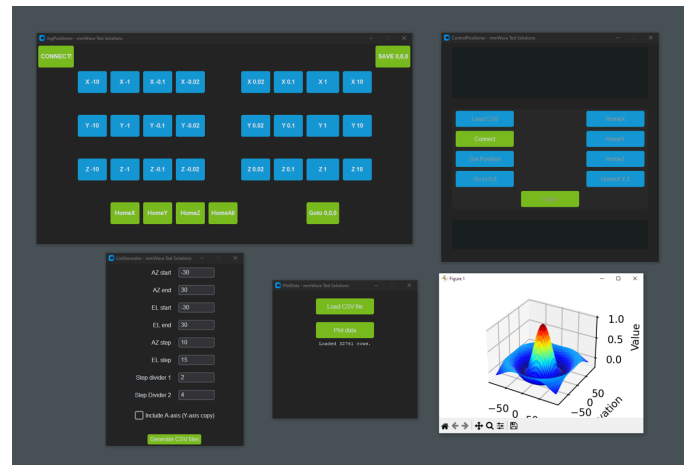
Both reference implementations utilize a clean structure of a frontend with UI setup and manual control. A backend controls the controller board and instruments, and a settings file contains all default values for instruments, communication, and positioner range and velocity.

The applications are delivered in source code, and the clear structure and documentation allows an easy adaptation to any other software environment.

The hardware controller system is chosen for its simplicity, and its native instruction set is designed for controlling multi-axis positioners. It makes it uncomplicated to develop a new application in any other software language.



```
mm_frontend.m mm_backend.m mm_settings.m mm_measurement_initialization.m mm_measurement_execution.m
47 str = obj.controller.write('?');
48 tokens = strsplit(str, ',');
49 wpos = strsplit(tokens(2), ',');
50 xyz = strsplit(wpos(2), ',');
51 az = str2double(xyz(1));
52 el = str2double(xyz(2));
53 az_el = [az el];
54 end
55
56 %
57 % Performs a move to an absolute orientation. All values are given in degrees.
58 %
59 % Arguments
60 % az Desired azimuth angle.
61 % el Desired elevation angle.
62 %
63 function move_absolute(obj, az, el)
64 obj.controller.write(sprintf('G1 x%f y%f z%f', az, el, obj.velocity));
65 while max(abs([az el]-obj.read_orientation())) > obj.resolution/2
66 pause(0.1) % add a slight delay between polls to avoid busy waiting
67 end
68 end
69
70 %
71 % Performs a move relative to the current orientation. All values are given in degrees.
72 %
73 % Arguments
74 % az_displacement Desired azimuth angle displacement.
75 % el_displacement Desired elevation angle displacement.
76 %
77 function move_relative(obj, az_displacement, el_displacement)
78 az_el = obj.read_orientation();
79 obj.move_absolute(az_el(1) + az_displacement, az_el(2) + el_displacement)
80 end
```



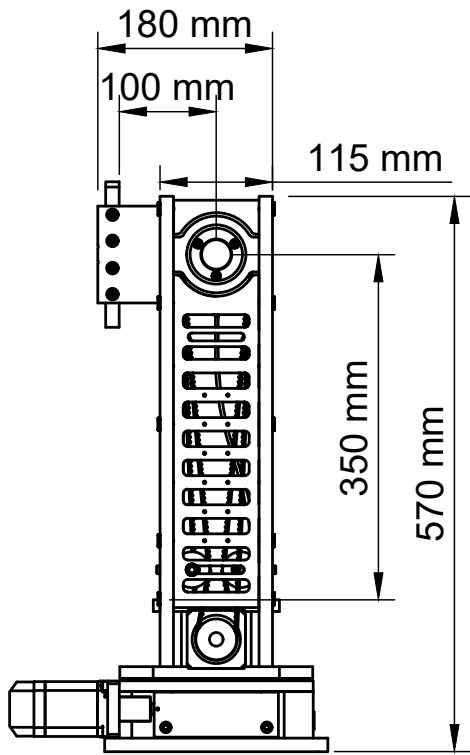
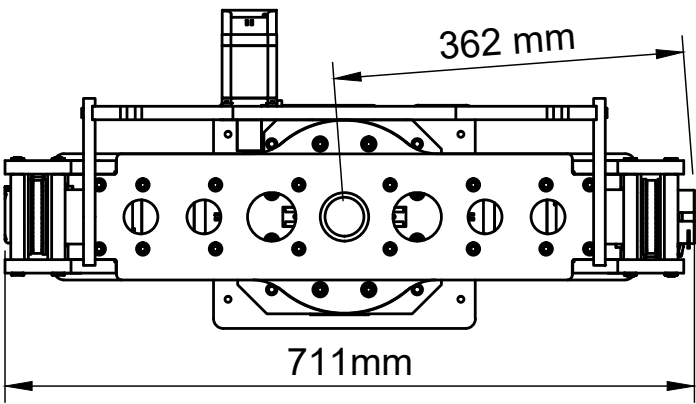
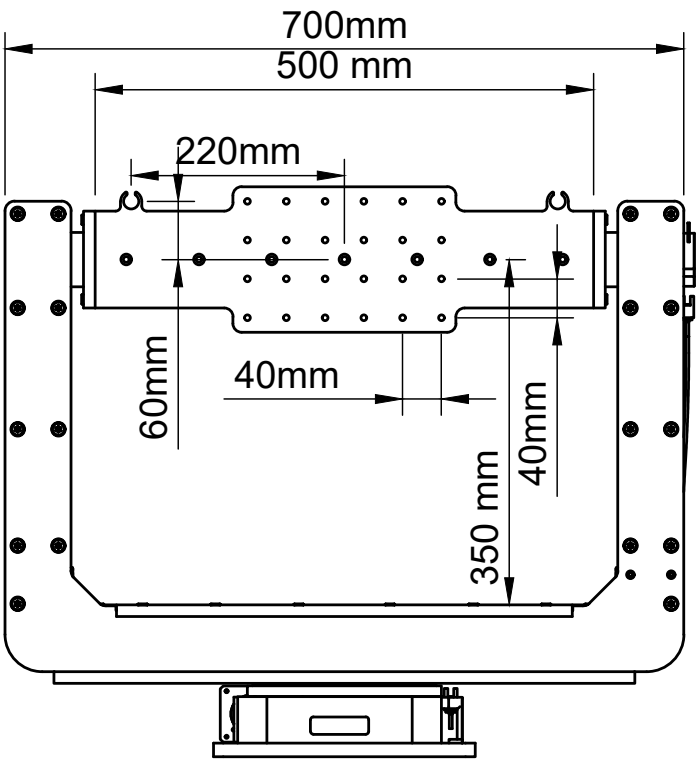


## DUO5 SPECIFICATIONS

AUT/ DUT dimensions	Up to 50 cm width (20") and 14 kg (31 lb)
Positioner dimensions	W 70 x H 46 x D 27 cm, weight 26 kg (57 lb)
Horizontal / Azimuth	Resolution 0.01° full-step (1:180), 0.0025° micro-step Holding torque 90.0 N-m (122 lb-ft) Weight capacity up to 55 kg Max rotation speed 25° per second Built from brass and aluminum, black anodized
Vertical / Elevation	Resolution 0.1° full step (1:18), 0.025° microstep Holding torque 58.0 N-m (78.6 lb-ft) Max rotation speed 35° per second Built from Delrin/POM, PET, aluminum in lower part Built from Delrin/POM, ABS, PET and FR4 in upper part Dual POM bearings in each arm Upper arm is 100 % metal free
Controller system	Multi-axis microprocessor-based controller Controlled via Serial-over-USB Python control UI USB 1.1 connected, Type A connector Closed-loop drive stage for each of the three motors Detachable precision calibrated laser for DUT alignment Azimuth electrical slipping included
Power supply	24 Volt, 12.5 Amp – 100-240 Volt mains
Configuration options	Customized arm length and DUT backplate layout

Contact us at [info@mmwavetest.com](mailto:info@mmwavetest.com) for more information

# MAIN DIMENSIONS



## MOUNT HOLE PATTERN

