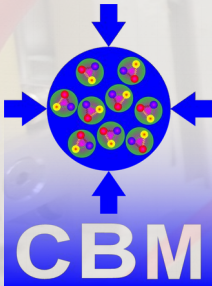
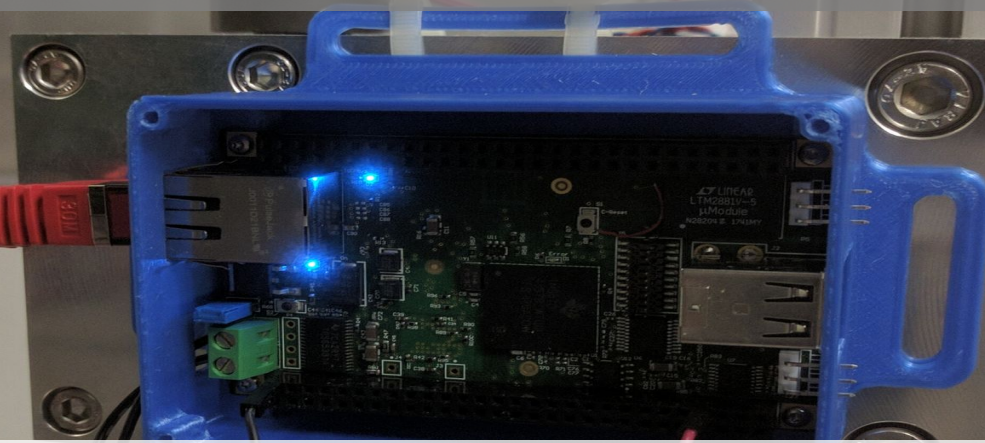


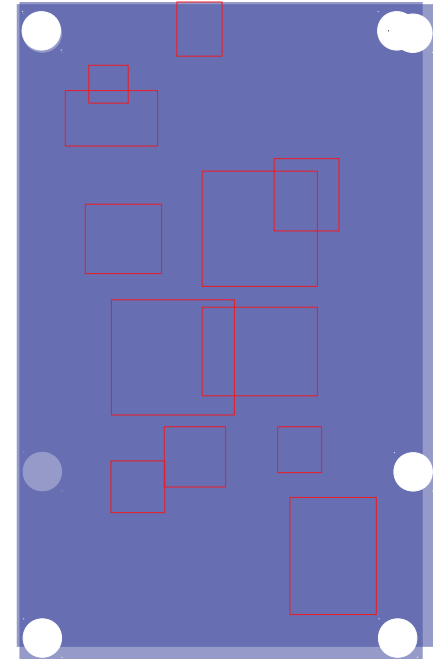
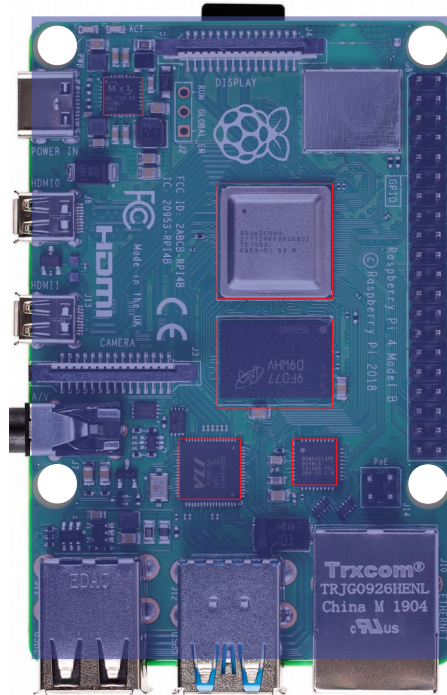
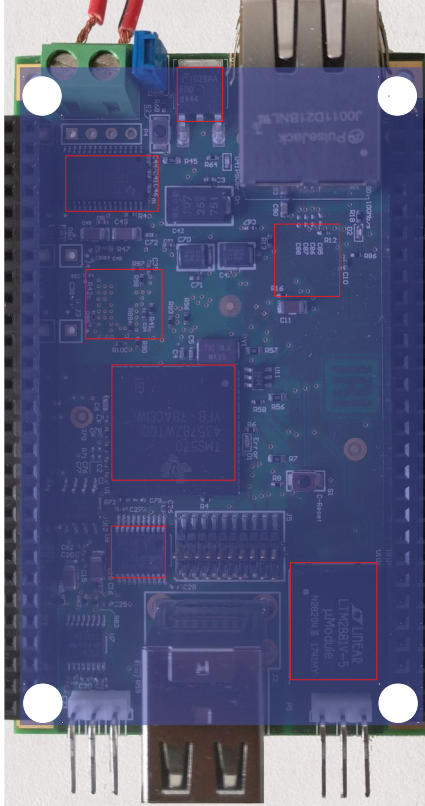
Fault Tolerant Local and Monitoring Control Board



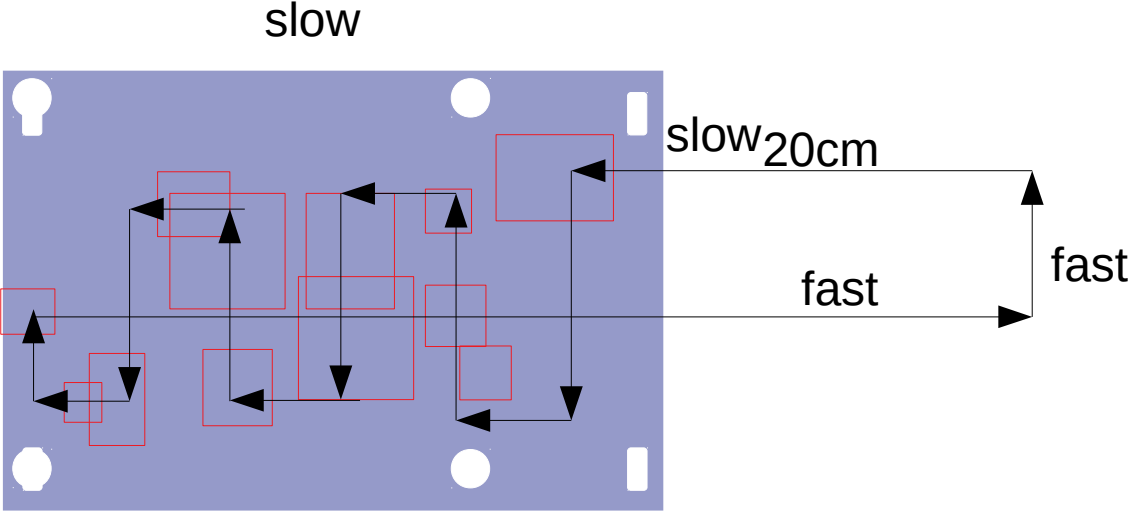
Research group Prof. Udo Kebschull
José Antonio Lucio Martínez

Infrastructure and Computer Systems in Data Processing
Goethe Universität Frankfurt

RECAP



Beamtime Positioning frame



Beamtime Positioning frame

- Fast: ~7.8 mm/s vertical, ~11.7mm/s horizontal
- Slow: ~0.13 mm/s vertical, ~0.2 mm/s horizontal

```
hetSIGNAL_t vSequence[]={slow, slow, fast, slow, fast, fast, slow, fast, fast, slow };  
int hormm[] =      {-24,    0,  -16,    0,    6,    0,    0,  -23,    0,    0};  
int vermm[] =      { 0,    24,    0,  -24,    0,   -5,  -24,    0,   18,   24};
```

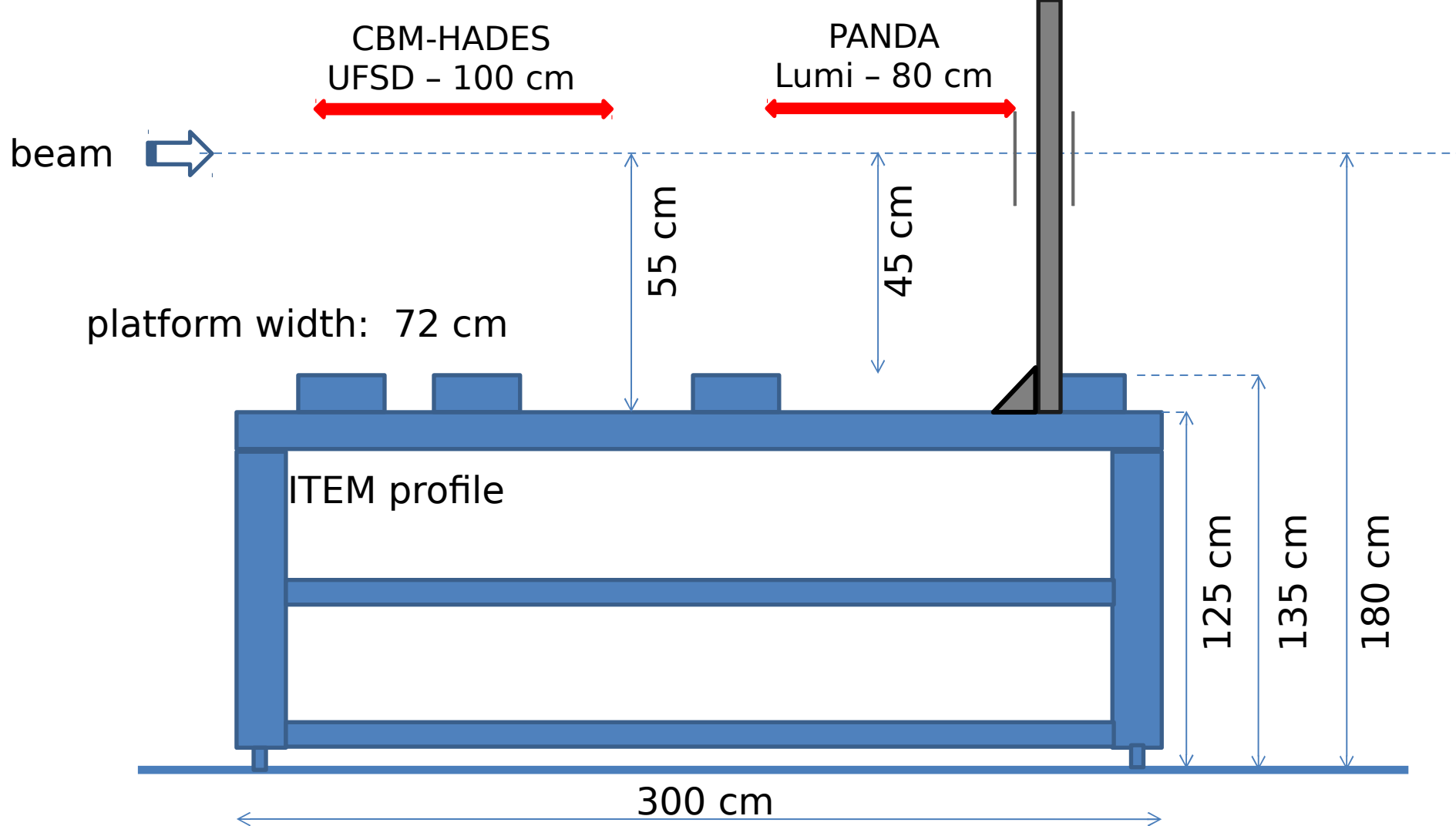
- Controlled by a non-DUT FTLMC far from beam
 - Not EPICS, should be integrated with sequencer to know exact position
- Watch demo video

Voltage Surveillance

- Use the 5 ADC available on a non DUT FTLMC (0-5V)
 - 2 for Raspberry 5V and 3.3V
 - 3 for FTLMC: 5V,3.3V and 1.2V
- 0-5V, Vref(-) is an input (DUTs GND), vref(+) is at local 5V
- Use an EPICS Analog input record for each
- Scan period: 1 Second
- Already implemented and tested

Other interfaces test

- RS485,RS232 to send continuous strings (to be done)
- Ethernet send continuous TCP binary data (to be done)

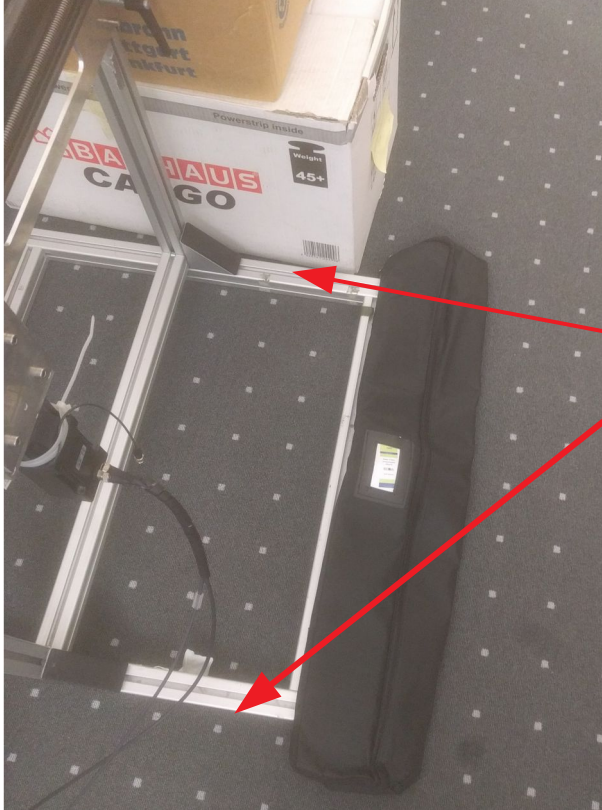


Notes on beam-time

September							
KW	Mo	Di	Mi	Do	Fr	Sa	So
35							1
36	2	3	4	5	6	7	8
37	9	10	11	12	13	14	15
38	16	17	18	19	20	21	22
39	23	24	25	26	27	28	29
40	30						

- Item24 Profiles: Allows us to use only ~ 40 cm of z axis space
- motor mobility:
 - Y: 10cm, fixed height frame adjustable
 - X: 58cm.

Notes on beam-time



- Height poles too long $>1\text{m}$
- Platform- Beam distance sketch 55cm
- Take only the base (longest, 72 cm)
- Use two of them as height poles
- Fits in the bag pictured
- Sufficient for beam height

Thank you!



Thank you!

