Differences LAC1 – LCC10

LAC 1	LCC 10
Servo motor controller/driver Position, Velocity, Torque	Brushless & Servo motor controller/driver Position, Velocity, Torque
Position – PID + Feed-Forward / Torque – PI	Position – PID + Feed-Forward + Torque – PI
0.2 milliseconds (5 KHz) control loop rate	1 milliseconds (1 KHz) control loop rate
PWM motor drive (19.5 kHz), 3A RMS, 6A peak	PWM motor drive (39 kHz), 2A RMS, 4A peak
Current resolution 5 mA (DC servo)	Current resolution 2 mA (DC servo), 10 mA (Brushless)
8 Digital Inputs and 8 digital Outputs (TTL)	4 Digital Inputs and 4 digital Outputs (TTL)
3 Analog Inputs (0-5V) (10-bit DAC)	2 Analog Inputs (0-5V, +/-10V), 1 Analog Output (0-5V & 10-bit DAC for LCC-10 or 0-10V & 16-bit DAC for LCC-11)
RS232 (Baud rate 300 to 19200, default 9600)	RS232 (Baud rate 9600 / 115200, default 115200), CAN (CiA 301, CiA 305, CiA 402)
Current output limiter (SQ-value in PM)	Current output limiter, Over-current (I2T) Polarity Inversion Protection,
Stand Alone, Serial Slave	Stand-Alone, Serial Slave / Daisy Chain, CAN bus Slave
Capture Data with 1 selectable variable, up to more than 500 points	Capture Data with 4 fixed variables, 250 points max
16 Kb NVM, 512 Registers	16 Kb NVM, 100 Registers
Program space of 256 Macros	Program space of 64 Macros
PID and default settings in Macro	PID and default settings in Config file

The Ability to do Work & Verify it's Accuracy at the Same Time