



























The Overdrive motion system is the hub of a network which streams live and recorded motion data. Utilizing high-bandwidth digital technologies, Overdrive offers flexibility and expandability when problem-solving in production environments. As a hard real time constraint system, Overdrive is suitable for Robotics, Motion Control, Animatronics, Virtual Production, Augmented Reality/AR, and Metadata Capture.

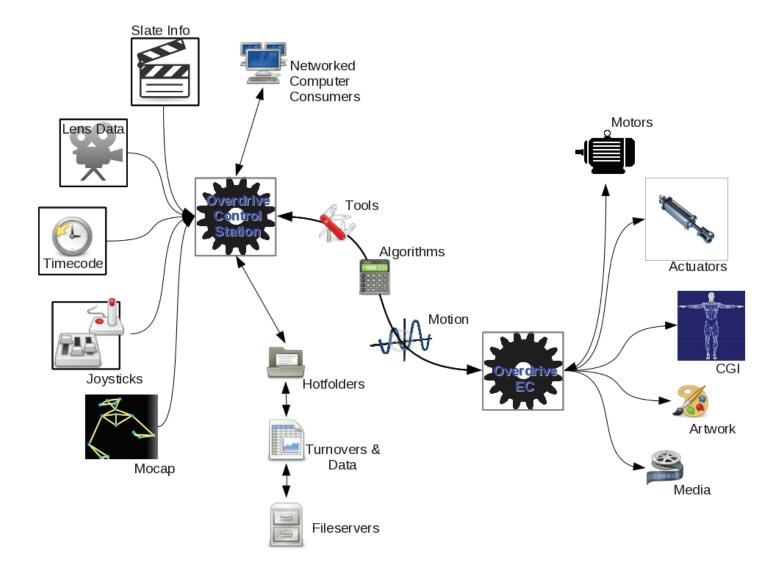
Software Highlights :

- Intuitive graphical user interface runs locally or remotely
- · Motion Editor to record, play, keyframe & edit motion and sound
- Channels, groups and nonlinear-scaling
- 3D graphics scene for pre-visualization
- Math Plugins: from arithmetic to 3D matrices
- Events and Triggers as conditional decision-making
- Collision avoidance and real-time attribute modification
- "Hard Real Time" computing environment no timing glitches
- 127 analog input channels, 64 binary input chans, up to 500 output chans
- 300 virtual chans, 475 Ethernet telemetry chans, 64 attribute chans
- 450 "Mixes" for lookup tables & motion blending (tables up to 4096 points)
- Data resolution: 8, 12, 16, 24, 32 bit channels (64 bit internal resolution)
- Motion framerates up to 250 fps
- Remote administration via network & Internet
- Analog and digital input device support: Serial, CAN, ADC, etc.
- Multiple digital output ports: serial, fiber, DIO, Ethernet, etc.
- Digital Sound : 48KHz, 24 bit, 2chan S/PDIF, AES/EBU, Word clock in/out
- SMPTE time code support, Ethernet time code
- Open architecture: SDK for interfacing new equipment (Serial, Ethernet, CAN, C, C++ Python, Objective C, C#)
- Formats: Autodesk, .FBX, .XML, Kuper, Flair, Overdrive .show for Maya, Motion-Builder, Moco compatibility
- Interfaces for Motion Builder, Maya, Unity, Unreal, Touch Designer, Vizrt, Pixotope, Zero Density, camera heads, Qtake, Faceware, & more

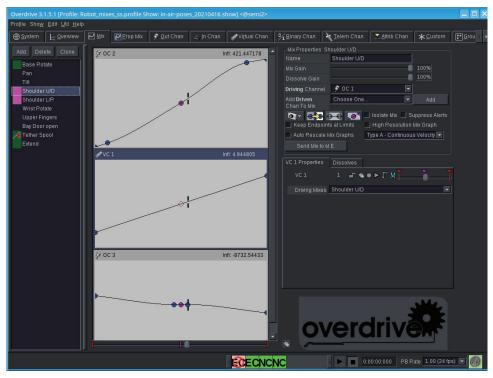
Hardware Highlights :

- Rack-mount PC, Portable PC, Laptop, and small Embedded computers
- Fiber optic and Diversity Wireless communications
- Actuators: AC/DC Servo Motor, Hydraulic, RC Servo (PWM & Dynamixel), CANopen, Analog, Pneumatic, EtherCAT
- Redundant fail-safe features including wire-fault detection
- Interface technologies: Analog, CMOS/TTL DIO, RS232 & RS485 serial, SSI, Ethernet/UDP, CANopen, EtherCAT, Step & Direction, Dynamixel, USB input
- Support for over 30 varieties of servo motor drives, encoders, robots, and camera heads
- Metadata, Time code, Genl-ock & Tri-level sync interfaces

Overdrive as the Hub of a Motion and Meta-data Network



Overdrive is a PC-based motion control system. It is typically implemented with two computers. The front-end "Control Computer" runs a hard real time Operating System and is the center of control. It has a graphical user interface, executes constraints and is the recording/playback unit. Analog or Digital user input devices are connected to the Control Computer. Downstream via fiber optic, wireless, or Ethernet link is an "Embedded Computer" (EC). An EC is a hard real time computer which moves real-world actuators or collects telemetrdata. The EC controls outputs in a one-to-many topology. The bidirectional communications link can also send data upstream to the Control Computer from sensors at the EC. In an "OV-one" configuration both the Control Computer and the EC software are together on one small board. A multi-language SDK allows third-party hardware or software modules to become an EC so as to send or receive motion by serial, CAN or Ethernet. Overdrive systems can also be linked together.



Mixes: Define Channel Relationship and Scaling

Curve Editing

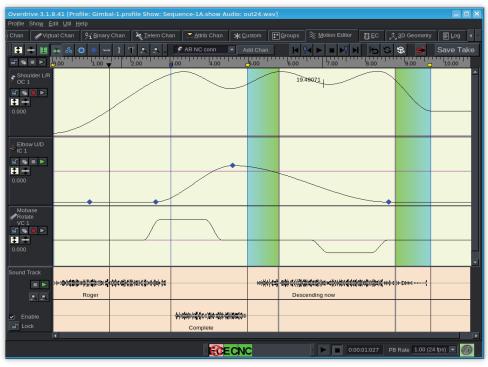
Lookup Tables

Graph Copy
Auto Scaling

Import/Export curves
Transit Mode
Gains

Deadbands

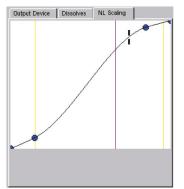




Output Device

Output Device Dissolves NL Scaling			
Type Hydraulic Compliant			
P Gain (Ext.) 4.03			
P Gain (Ret.) 4.03			
Wire-Fault Detect Enable			
Device Pol (+) Compliance Pol (+)			
Number 2 Relative Mode			
I Accelleration			
1 Limit 2047			
D Damping 8%			
Accel. Limit 4095			
Velocity Limit 4095			
Compliance 2.39			

Nonlinear Scaling



Channels: The Pipeline for Constraints and Attributes

🜮 <u>O</u> ut Chan	
Add Delete 🖃 🛸 🖝 🕨 🕅	1.0 💽 🔍 🤝 🔽 Output Channel Properties
Head Gmbi LF 1 = S S O F J M	Head Gmbl RT
Head Rotate 2 = • • • • M	Set Min Set Neutral Set Max
Head Gmbl RT 3 🖃 💊 🕒 🗸 M	Value 2.750 Min 0.500 Max 5.000
Body U/D LF 4 =	Neutral 2.737 T. Min 0.000 T. Max 7.000
	Limits Enforce Enforce Temp Protect Props
BodyU/D RT 5 🔐 🔽 🖝 🖉 🕅 📜	🔄 🔄 🗹 Enforce Transit 🔄 Vel/Accum Mode 🔄 Decel At Min/Max
	3.0 O Damping 85% Vel lim 1,999,999,998
Body Tilt 7 🙆 🔽 🗢 🕨 💭 M	2.2 O Accel lim 1,999,999,998
Tail L/R 9 🙆 🌢 ● ► 🕻 M 👖 🔰	2.6 O Decel lim 1,999,999,998 U U U U U U U U U U U U U U U U U U
Foot Lift FrontLF 10 🔐 🌭 ● ► 🖉 M	1.3 O Lowpass 0
Foot Lift FrontRT 11 🖃 💊 🖝 🗲 M	0.5 O.S Cale: Signed 2 Billion Precision: 0 Advanced Properties
Body Rotate 12 🔐 💊 🖝 🗲 M	1.4 Output Device Dissolves NL Scaling Affecting Motion
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Stride FrontRT 14 🖃 🗞 🖝 🕨 🕅 👖	12.6 DE Enable ChanVal Scaling
	Connected O Discover Disconnect
	Enabled Enable Disable

Live/Play/Record

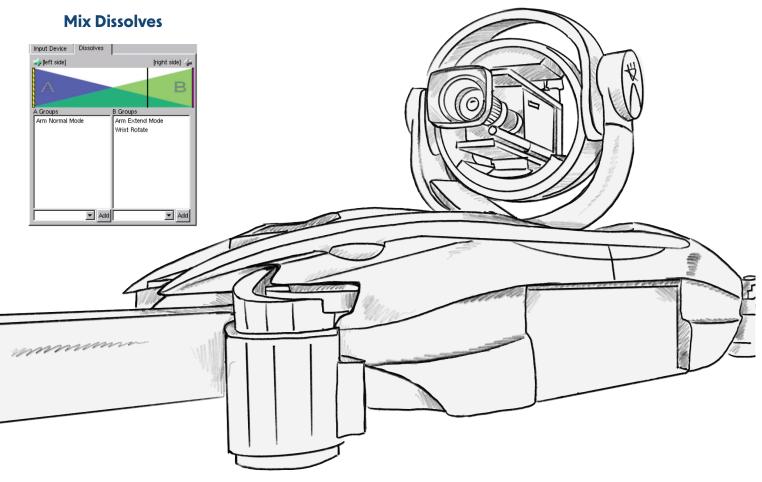
Limits & Decel
Temp Limits
Mouse Override

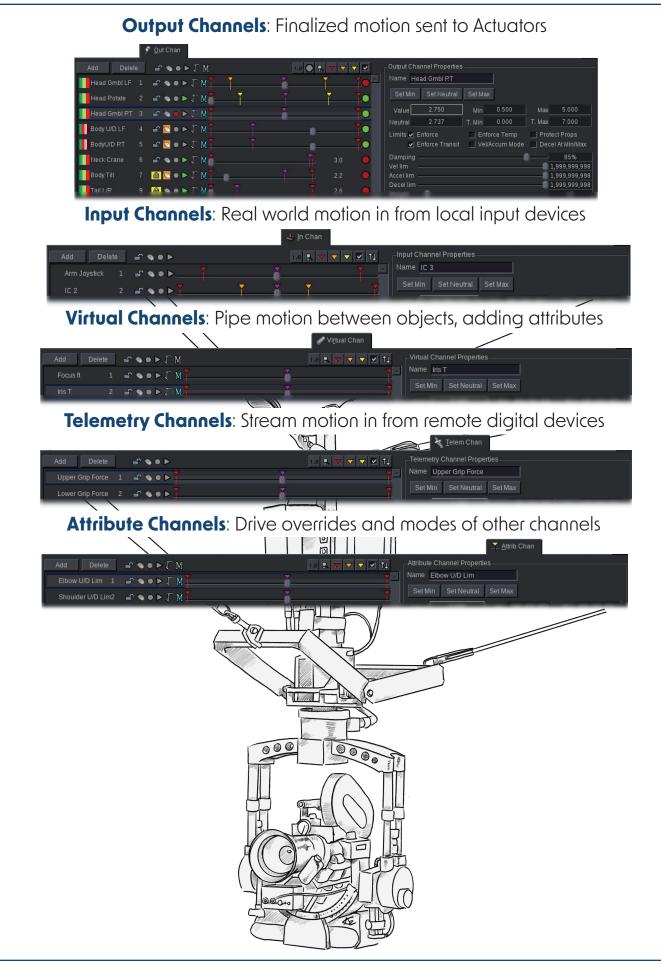
Transit Safety Mode

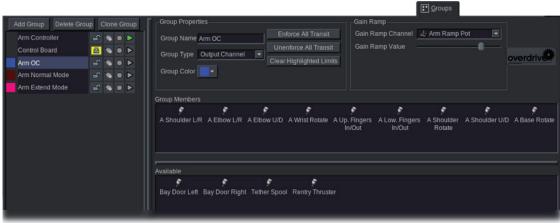
Attribute Copy
Wire Fault Detection

Dynamic Attributes

Smoothing Physics
Remote Device Tuning
Nonlinear Scaling
Drive Mix Gain
Drive Dissolve





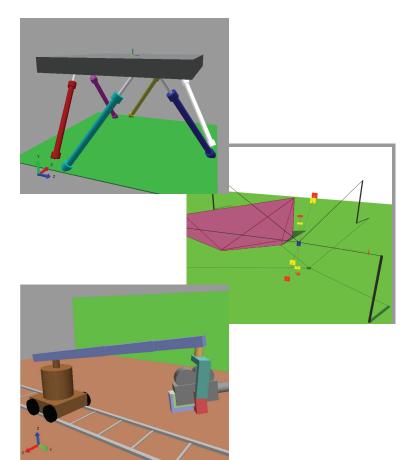


Groups: Perform actions on multiple objects at once

Proportional Mixing: Tune the way motion combines



3D Simulation Scene and Collision Avoidance

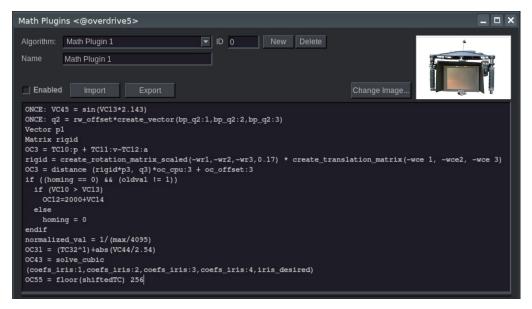


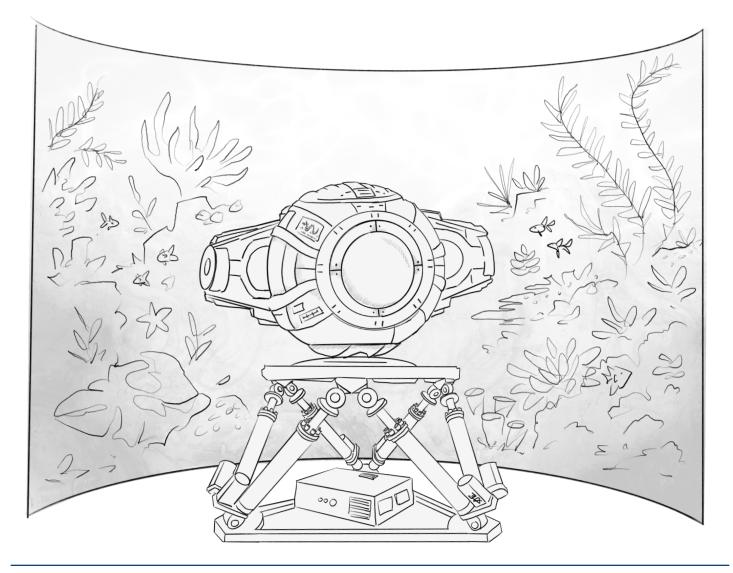
Overview: Browse object influences

E: Overview			
Profile	Channe		
🕂 📌 Output Channels	areaso		
🕂 🚽 A Shoulder L/R	OC 1		
Member of Group Arm OC			
+- 🖻 A Elbow L/R	OC 2		
🕂 🖗 A Elbow U/D	OC 3		
 Priven by A Elbow U/D 			
🛄 🛶 Driven by: A Elbow U/D Pot	IC 2		
+ - Priven by A Elbow L/R			
+ - Priven by A Extend	11101120		
Temp Max driven by Elbow U/D Lim [ENABLED]	AC 1		
Member of Group Arm OC			
+- 🆻 A Wrist Rotate	OC 4		
+- 🎐 A Up. Fingers In/Out	OC 5		
+- 🌮 A Low. Fingers In/Out	OC 6		
– 🦻 Bay Door Left	OC 7		
+			
+ - 🗹 Driven by Bay Door Open Alt			
- PropMixed between Bay Door Open and Bay Door Open Alt			
Bay Door Open:Low, Bay Door Open Alt:High = 0			
🖻 Bay Door Right	OC 8		
👰 Tether Spool	OC 9		
🌮 Rentry Thruster	OC 10		
+ 🖓 A Shoulder Rotate	OC 11		
+- 🖻 A Shoulder U/D	OC 12		
🗄 🖗 A Base Rotate	OC 13		
+- 👍 Input Channels			

- Double Precision 64bit
- Standard Math Libraries
- Functions & Control Flow
- User Constants & Variables
- Matrices & Vectors
- Curve Lookups
- Channel Values/Attributes
- State Machines
- Edge Triggers
- Indexable Channels
- Execute at Framerate
- Closed Loops

Math Engine: Hard Real Time User Plugins







Contact **Concept Overdrive** today to plan your motion system 818-980-6691 • info@conceptoverdrive.com



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