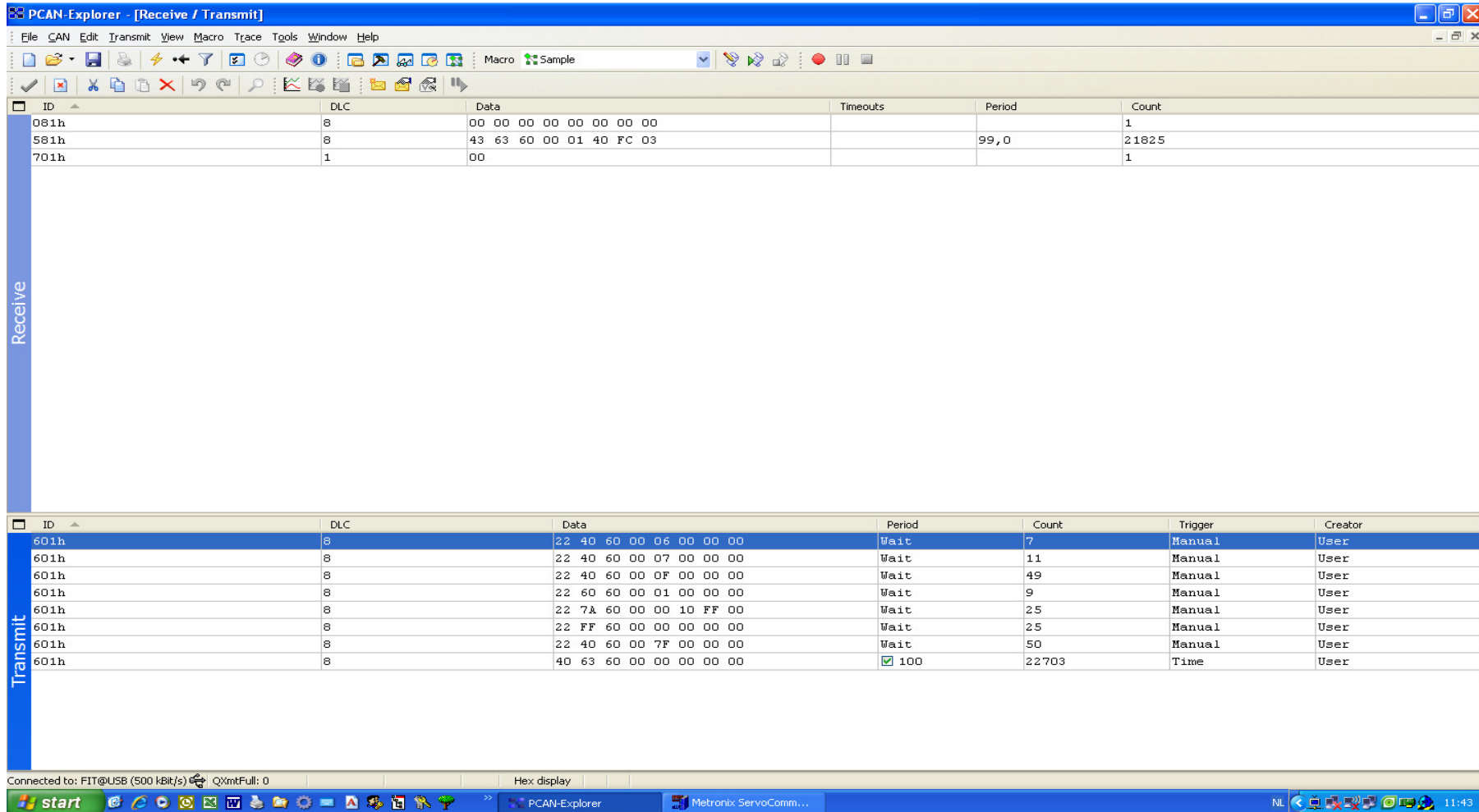


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CAN-open test settings.

Leaf your PLC program touch. Put in the table as shown by using the Can explorer program, just as test.

After the adjustments select the transmit date en enter by using your space button. The dates in following order are described on the next page.



The screenshot shows the PCAN-Explorer application window. The title bar reads "PCAN-Explorer - [Receive / Transmit]". The menu bar includes File, CAN, Edit, Transmit, View, Macro, Trace, Tools, Window, and Help. The toolbar contains various icons for file operations, CAN configuration, and data viewing. The main window is divided into two sections: "Receive" (top) and "Transmit" (bottom), each with a vertical label on the left side.

**Receive Table:**

ID	DLC	Data	Timeouts	Period	Count
081h	8	00 00 00 00 00 00 00 00			1
581h	8	43 63 60 00 01 40 FC 03		99,0	21825
701h	1	00			1

**Transmit Table:**

ID	DLC	Data	Period	Count	Trigger	Creator
601h	8	22 40 60 00 06 00 00 00	Wait	7	Manual	User
601h	8	22 40 60 00 07 00 00 00	Wait	11	Manual	User
601h	8	22 40 60 00 0F 00 00 00	Wait	49	Manual	User
601h	8	22 60 60 00 01 00 00 00	Wait	9	Manual	User
601h	8	22 7A 60 00 00 10 FF 00	Wait	25	Manual	User
601h	8	22 FF 60 00 00 00 00 00	Wait	25	Manual	User
601h	8	22 40 60 00 7F 00 00 00	Wait	50	Manual	User
601h	8	40 63 60 00 00 00 00 00	<input checked="" type="checkbox"/> 100	22703	Time	User

The status bar at the bottom indicates "Connected to: FIT@USB (500 kBit/s) QXmtFull: 0". The taskbar shows the Windows Start button and several open applications, including PCAN-Explorer and Metronix ServoComm...

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After order inputs is the handling as follows.

Start of enable (available motor torque).

1° 40 60 00 06 00 00 00 start 1

2° 40 60 00 07 00 00 00 start 2

3° 40 60 00 0F 00 00 00 enable/reset new position

Now the enable is high and the motor is active.

Choice commands

Take

60 60 00 01 00 00 00 - positioning

60 60 00 03 00 00 00 - speed control

60 60 00 06 00 00 00 - homing

Take speed controller (03)

Put in your speed

FF 60 00 EA 00 00 00 = 234 rpm enter and running

Go to

FF 60 00 00 00 00 00 = 0 rpm

Then

60 60 00 01 00 00 00 – positioning

Put in your position

7A 60 00 00 10 FF 00 = 255,063

make your choice

40 60 00 3F 00 00 00 – absolute

40 60 00 5F 00 00 00 – relative Finished first old position **See remarks last page.**

40 60 00 7F 00 00 00 – relative go direct to new position.

40 60 00 choose 1 is by command homing start homing.

take 7F (relative) he go's directly to the following position from the actual position we he is.

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Go on with

40 60 00 0F 00 00 00 - internal reset

and

40 60 00 7F 00 00 00

and

40 60 00 0F 00 00 00 - internal reset

and

40 60 00 7F 00 00 00

and

40 60 00 0F 00 00 00 - internal reset

Take now

40 60 00 3F 00 00 00 – absolute positioning.

Give “enter” with space bar and he go to absolute position (255,063).

This is only one time possible because absolute is his actual position.

Again 40 60 00 0F 00 00 00 and 40 60 00 3F 00 00 00 he go's again internal. Because he is on his absolute actual position..

take

40 60 00 03 00 00 00 – speed controller

put in your speed and enter with your space bar. The motor rotate directly with this rotation speed.

All other combination are applicable.

### **Remark.**

By using 5F he finished first old position order and go directly to the following position. So f.a. 255 rpm is every time his next position.

By using 7 F and a new position order he moves directly to this new position. F.a. he is running on 100,045 rpm his new position is 355,045 a.s.o.

Be sure to want this!

6-12-2012

Motorcurrent adjustment over Can.

75 60 00 00 01 00 00 = 0,26 A current in mA input

73 60 00 D0 07 00 00 = 1000 (factor).

Error reset

40 60 00 80 00 00 00 error reset.

03 10 01 00 00 00 00 Error 0 erase from memory.