Drive Configuration ✕

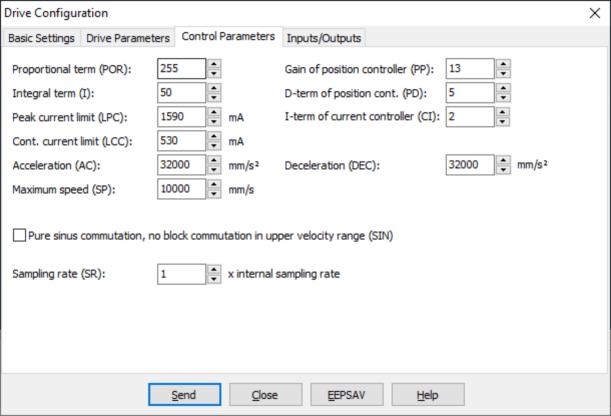**Basic Settings** | Drive Parameters | Control Parameters | Inputs/Outputs

Operating Mode

- ○ Continuous Mode (CONTMOD)
- ○ Stepper Motor Mode (STEPMOD)
- ● Analog Position Control Mode (APCMOD)
- ○ Encoder Mode with encoder as speed sensor
- ○ Encoder Mode with hall sensor as speed sensor
- ○ Gearing Mode (GEARMOD)
- ○ Voltage Mode (VOLTMOD)
- ○ IxR Speed Control (IXRMOD)

Controller mode

- ○ Position cont. (M)
- ○ Velocity cont. (V)

☐ Multiplex Mode (NET)

Command Source (SOR)

- ○ Digital
- ● Analog voltage
- ○ PWM on analog input
- ○ Current limiting on analog voltage
- ○ Current limiting on bipolar analog voltage

[Optimisation for connected motor]

☑ Drive enabled (EN)
☐ Sequence program enabled (ENPROG)
☑ Notify commands enabled (ANSW)
☑ Commands with confirmation (ANSW2)

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Position range limits (LL):   from: `-1800`   to: `1800`   Inc

-7.200   mm   7.200   mm

Maximum allowable deviation (DEV): `30000` mm/s   Target win. (CORRIDOR): `20`

Stepper Motor and Gearing Mode:

Moving direction
- ⦿ right-hand (ADR)
- ◯ left-hand (ADL)

Step width (STW): `1`

Step number (STN): `1000`   Steps per pole pitch

Linear motor in encoder mode:

Resolution of external encoder (ENCRES): `2048`   Inc / mm (quad pulse number)

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Proportional term (POR): `255`

Integral term (I): `50`

Peak current limit (LPC): `1590` mA

Cont. current limit (LCC): `530` mA

Acceleration (AC): `32000` mm/s²

Maximum speed (SP): `10000` mm/s

Gain of position controller (PP): `13`

D-term of position cont. (PD): `5`

I-term of current controller (CI): `2`

Deceleration (DEC): `32000` mm/s²

☐ Pure sinus commutation, no block commutation in upper velocity range (SIN)

Sampling rate (SR): `1` x internal sampling rate

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Function of fault pin:
- ◉ Fault output (ERROUT)
- ○ Pulse output (ENCOUT)
- ○ Digital output (DIGOUT)
- ○ Digital input (REFIN)
- ○ Direction input (DIRIN)
- ○ Target output (POSOUT)

Delayed current error (DCE): `200` 1/100 sec.

Number of output pulses per TM (LPN): `16`

Input level
- ◉ Input level 5V-TTL compatible (SETTTL)
- ○ Input level 24V-PLC compatible (SETPLC)

	Input	1 *(An In)*	2 *(Fault)*	3
Rising edge resp. high level valid on (HP)		☑	☑	☑
Hard blocking on (HB)		☐	☐	☐
Right-hand hard blocking on (HD)		☐	☐	☐

Homing sequence

		1	2	3
Set position value to 0 (SHA) if edge at		☐	☐	☐
Stop motor (SHL) if edge at		☐	☐	☐
Notification (SHN) if edge at		☐ ->"h"	☐ ->"f"	☐ ->"t"

Homing Speed (HOSP): `20` mm/s   ☑ "Power On" - Homing Sequence

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