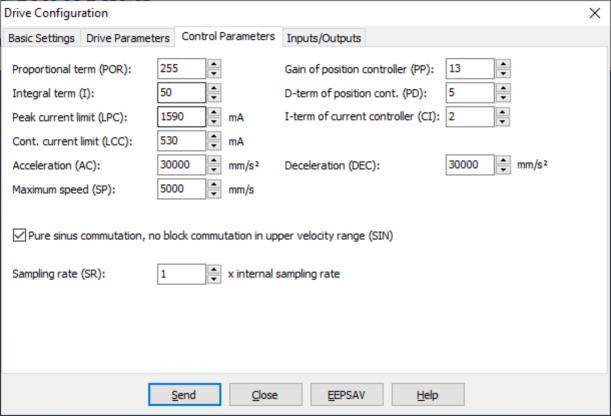
Drive Configur	ration		×				
Basic Settings	Drive Parameters	Control Parameters	Inputs/Outputs				
Operating Mode Continuous Mode (CONTMOD) Stepper Motor Mode (STEPMOD) Analog Position Control Mode (APCMOD) Encoder Mode with encoder as speed sensor Encoder Mode with hall sensor as speed sensor Gearing Mode (GEARMOD) Voltage Mode (VOLTMOD) IXR Speed Control (IXRMOD)		MOD) de (APCMOD) er as speed sensor nsor as speed sensor	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)				
	5	Send Close	EEPSAV Help				

Drive Configuration								×	
Basic Settings	Drive Parameters	Control P	Parameters	Inputs/0	Outputs				
Position range	limits (LL):	from:	-1600 -6.400	mn	to:	1600 6.400	Inc mm		
Maximum allov	vable deviation (DEV):	30000	mm/s		Target win. (COF	RRIDOR):	20	
Stepper Motor Moving direct oright-hand	nd (ADR)		Step width (Step number	. , [1 1000	Steps per	pole pitch		
Linear motor in encoder mode: Resolution of external encoder (ENCRES): 2048 Inc / mm (quad pulse number)									
	Ş	end	Close		<u>E</u> EPSAV	/ <u>H</u> elp			



Drive Configuration		×
Basic Settings Drive Parameters 0	Control Parameters Inputs/Outputs	
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): Number of output pulses per TM (LPN): Input level Input level 5V-TTL compatible (SETTTL) Input level 24V-PLC compatible (SETPLC)	100 sec.
Rising edge resp. high level valid Hard blocking on (HB) Right-hand hard blocking on (HD		
Homing sequence Set position value to 0 (SHA) if e Stop motor (SHL) if edge at Notification (SHN) if edge at Homing Speed (HOSP): 20	edge at	
<u>S</u> er	nd <u>C</u> lose <u>E</u> EPSAV <u>H</u> elp	