

CONNECTION

1 Install GSDML files

This product uses the standard GSDML file the same as other standard Profinet products. Before configuring the product, you need install the GSDML file.

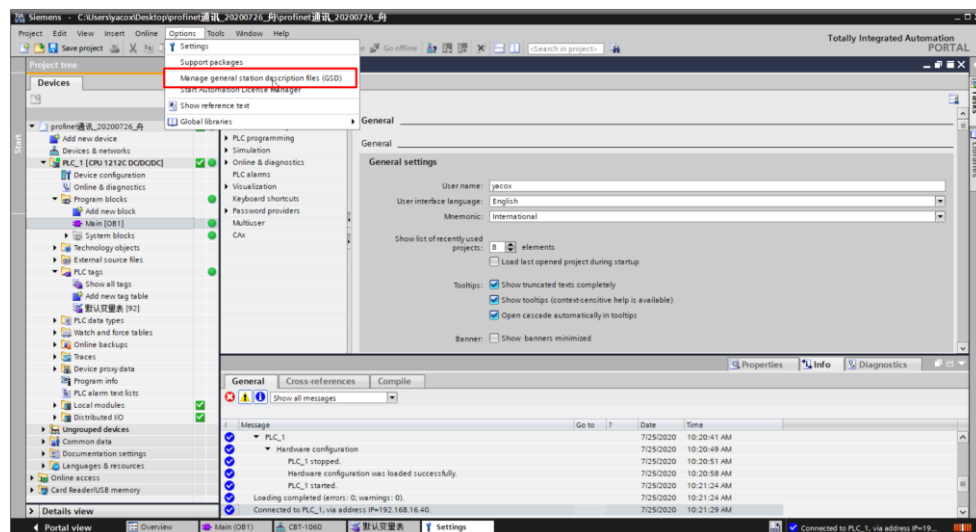


Figure1 install GSDML files

2 Set correct IP address and PROFINET device name

you need change the CBT-1060 hardware IP address and the configuration property IP address and PROFINET device name settings in this project.

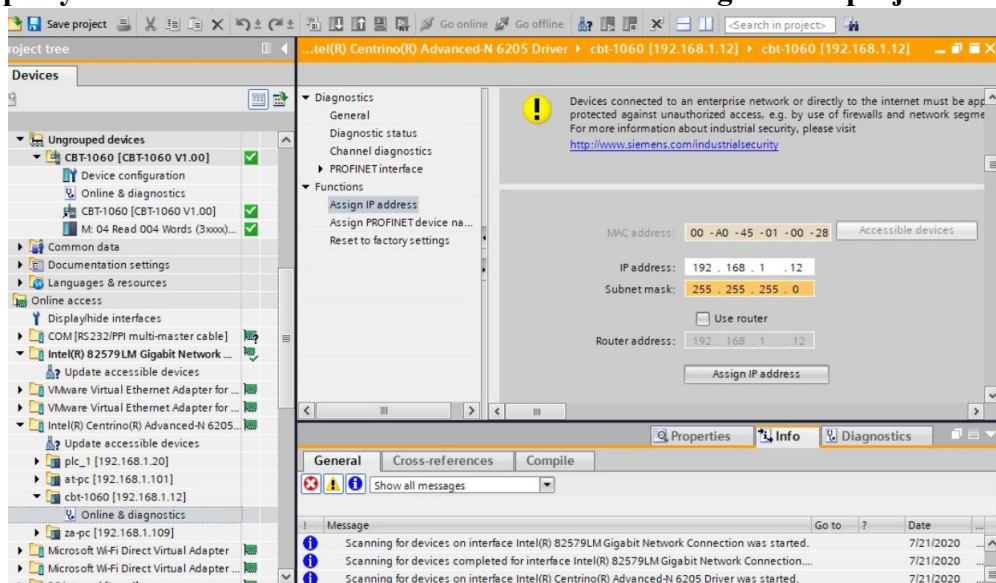


Figure2 SET The IP address

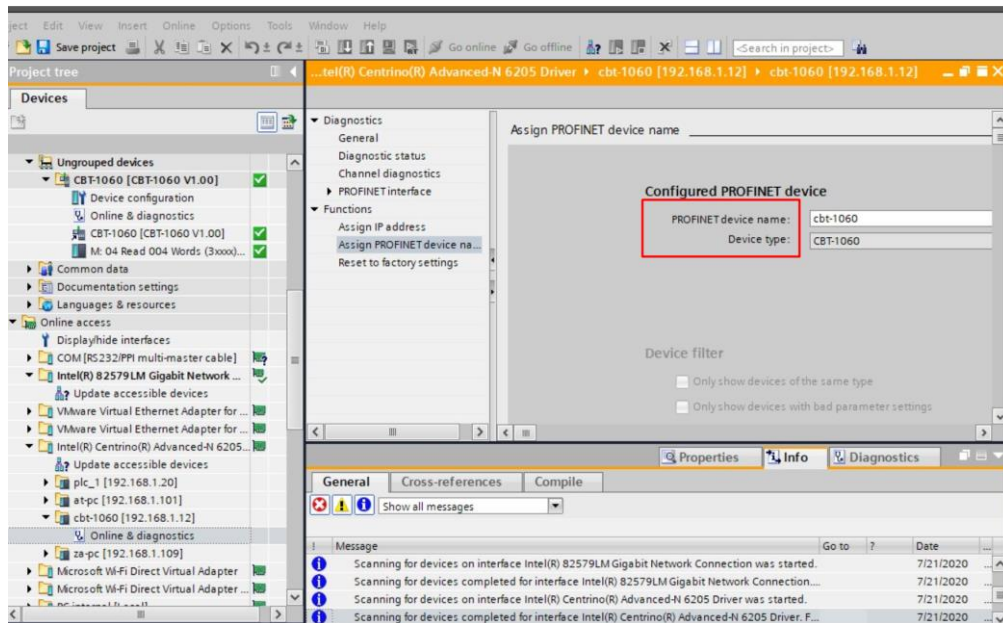


Figure 3 Change device name

3 Building modbus communication

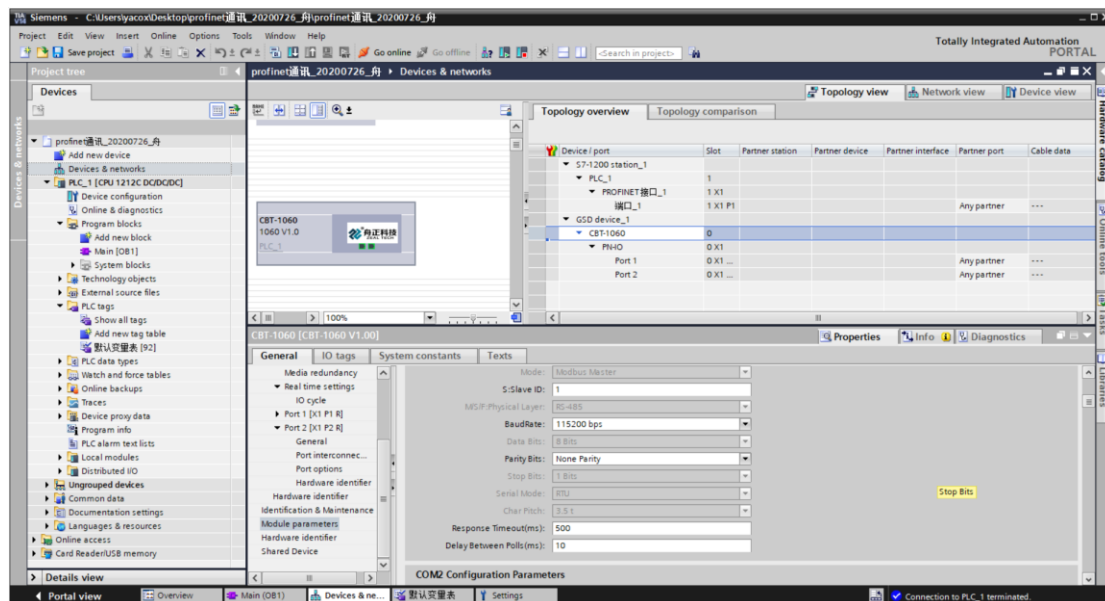


Figure 4 Building modbus communication

The Gripper Default Communication Parameters are as follows:

Slave Address : 1
Baud Rate : 115200
Data Bits : 8 bits
Stop Bits : 1 stop bit

Parity : None

4 Insert 06 03 submodule

When the RS485 port of the CBT-1060 is connected to other MODBUS RTU slave devices, it can be inserted into the sub-slot of the CBT-1060 device by inserting submodule

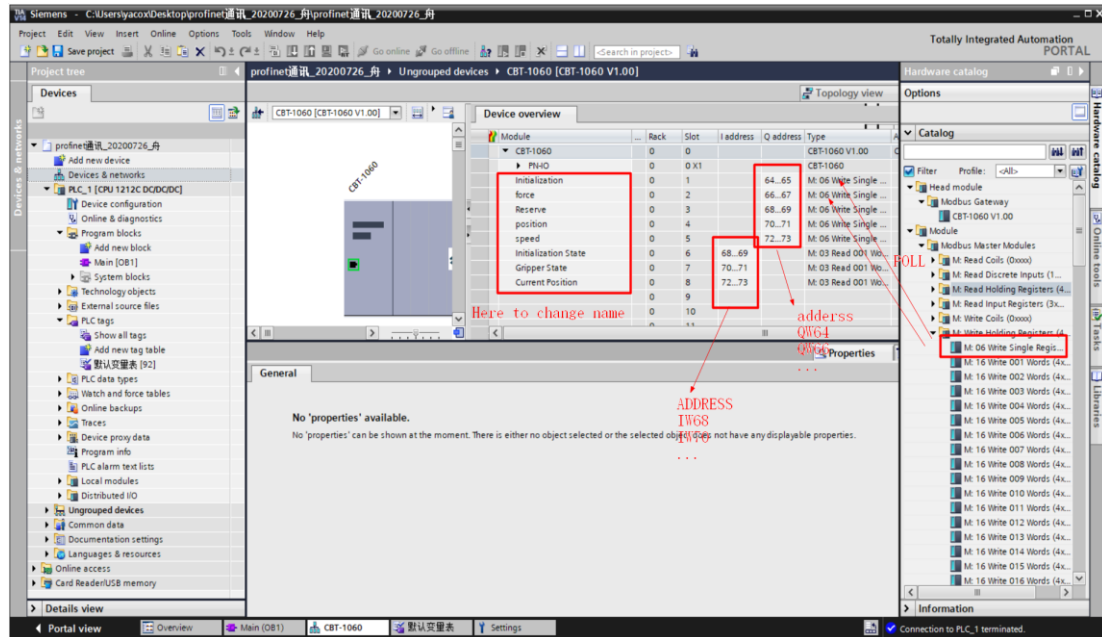
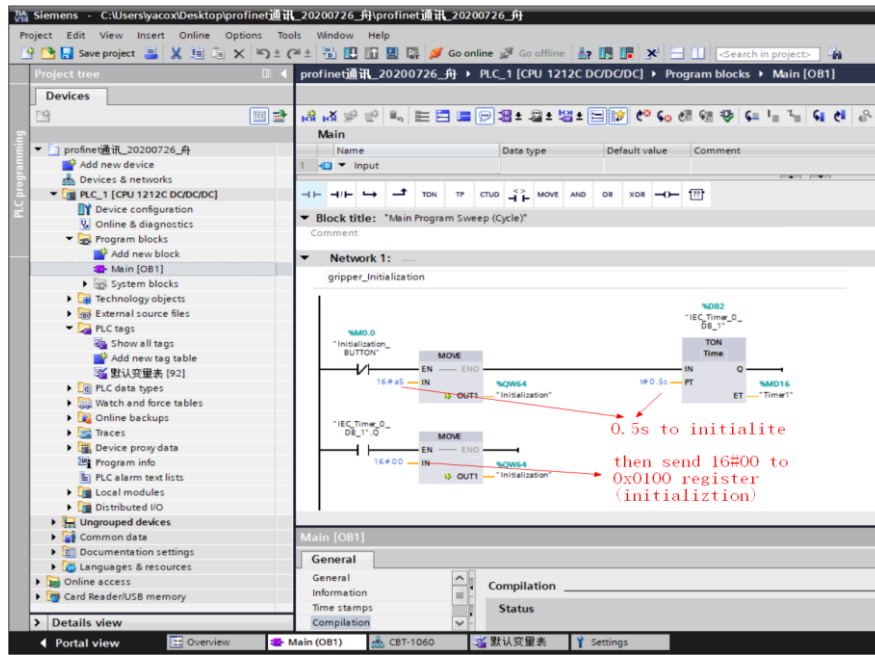


Figure 5 INSERT 06 03 submodule

5 Set the address to control gripper

Please pay attention to the profinet module will polling all the time.(06 03 comment)

So when you initialize the gripper , the gripper will be in the process of initialization all the time .You can use a TIMER to avoid this problem:When you send 0x0100 register(initializtion) to A5, then send 00 to 0100 register(initializtion),you can see as follows:



默认变量表									
	Name	Data type	Address	Retain	Access...	Write...	Visibl...	Monitor value	Comment
31	FirstScan	Bool	%M1.0		✓	✓	✓	FALSE	
32	DiagStatusUpdate	Bool	%M1.1		✓	✓	✓	FALSE	
33	AlwaysTRUE	Bool	%M1.2		✓	✓	✓	TRUE	
34	AlwaysFALSE	Bool	%M1.3		✓	✓	✓	FALSE	
35	System_Byte(1)	Byte	%MB1		✓	✓	✓	16#04	
36	ET1	Time	%MD10		✓	✓	✓	T#65_251MS	
37	position control4	Bool	%M14.0		✓	✓	✓	TRUE	
38	开始1	Bool	%M14.1		✓	✓	✓	FALSE	
39	2初始化	Bool	%M14.2		✓	✓	✓	FALSE	
40	初始化_2	Word	%QW73		✓	✓	✓	16#0000	
41	2位置控制	Bool	%M14.3		✓	✓	✓	FALSE	
42	位置_2	Word	%QW85		✓	✓	✓	16#0000	
43	2位置控制2	Bool	%M14.4		✓	✓	✓	FALSE	
44	2速度	Bool	%M14.5		✓	✓	✓	FALSE	
45	速度_2	Word	%QW89		✓	✓	✓	16#0000	
46	Timer1	Time	%MD16		✓	✓	✓	T#500MS	
47	Initialization State	Word	%IW58		✓	✓	✓	16#0001	
48	Gripper State	Word	%IW70		✓	✓	✓	16#0000	
49	Current Position	Word	%IW72		✓	✓	✓	16#02FD	
50									

Figure 6 03 comment to read statement

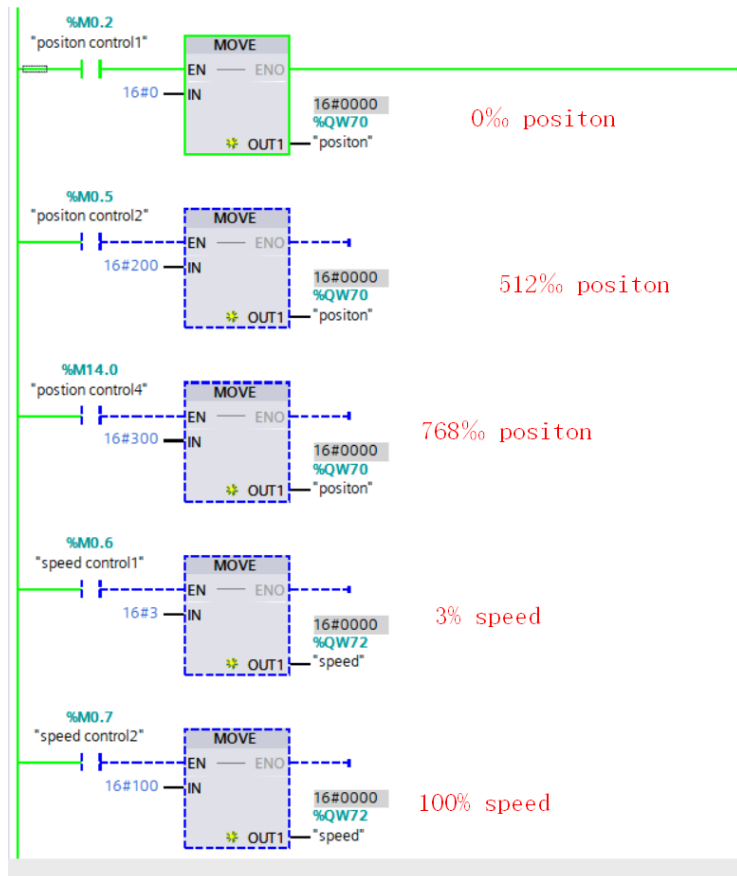


Figure 7 06 commend to control gripper