

# EPOS

## Positioning Controller

### Application Note "Device Programming"

April 2009 Edition

**EPOS 24/1, EPOS 24/5, EPOS 70/10, MCD EPOS 60W, EPOS2 50/5  
Firmware version 2000h or higher**

#### Introduction

The EPOS positioning controller is a digital positioning system suitable for DC and EC (brushless) motors with incremental encoders in a modular package. The performance range of these compact positioning controllers ranges from a few watts up to 700 watts.

A variety of operating modes allows all kinds of drive and automation systems to be flexibly assembled using positioning, speed and current regulation. The built-in CANopen interface allows networking to multiple axis drives and online commanding by CAN bus master units.

#### Objectives

This application note shows some typical commanding sequences for different operation modes. The explanations are based on writing and reading commands to access to the object dictionary. For further information about the objects see document 'EPOS Firmware Specification'. Detailed information of the command structure will be also found in the EPOS Graphical User Interface tool (command analyzer).

#### References and Required Tool

The latest editions of maxon motor documents and tools are freely available at <http://www.maxonmotor.com> category «Service & Downloads».

Document	Suitable order number for EPOS Positioning Controller
EPOS Firmware Specification	280937, 302267, 302287, 317270, 275512, 300583
EPOS2 Firmware Specification	347717

Tool	
EPOS Studio Version 1.30 or higher	280937, 302267, 302287, 317270, 275512, 347717, 300583

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## 1 First Step

Before the motor will be activated the motor parameters, the position sensor parameters and the regulation gains are to be set. All objects are described detailed in the document 'EPOS Firmware Specification'.

**Remark:** Detailed information of the command structure will be found in the EPOS Studio tool (command analyzer revision 2.0 or higher).

Diagram	Object name	Object	User value [default value]
<pre> graph TD     A[Set Communication Settings] --&gt; B[Set Motor Parameters]     B --&gt; C[Set Position Sensor Parameters]     C --&gt; D[Set Current Regulator Gains]     D --&gt; E[Set Velocity Regulator Gains]     E --&gt; F[Set Position Regulator Gains]   </pre>	RS232 Baudrate CAN Bitrate	0x2002-00 0x2001-00	User specific [3] User specific [0]
	Motor Type Continuous Current Limit Pole Pair Number Thermal Time Constant Winding	0x6402-00 0x6410-01 0x6410-03 0x6410-05	Motor specific [10] Motor specific [5000] Motor specific [1] Motor specific [40]
	Encoder Pulse Number Position Sensor Type	0x2210-01 0x2210-02	Sensor specific [500] Sensor specific [1]
	Current Regulator P-Gain Current Regulator I-Gain	0x60F6-01 0x60F6-02	Motor specific. Determine the optimal parameter by using the 'Regulation Tuning' of EPOS Studio.
	Speed Regulator P-Gain Speed Regulator I-Gain	0x60F9-01 0x60F9-02	Motor specific. Determine the optimal parameter by using the 'Regulation Tuning' of EPOS Studio.
	Position Regulator P-Gain Position Regulator I-Gain Position Regulator D-Gain	0x60FB-01 0x60FB-02 0x60FB-03	Motor specific. Determine the optimal parameter by using the 'Regulation Tuning' of EPOS Studio.

## 2 Profile Position Mode

### 2.1 Set Position

The axis moves to an absolute or relative position with a motion profile.

Diagram	Object name	Object	User value [default value]
Set Operation Mode	Modes of Operation	0x6060-00	0x01 (Profile Position Mode)
Set Parameter	Max. Following Error Min. Position Limit Max. Position Limit Max. Profile Velocity Profile Velocity Profile Acceleration Profile Deceleration Quick Stop Deceleration Motion Profile Type	0x6065-00 0x607D-01 0x607D-02 0x607F-00 0x6081-00 0x6083-00 0x6084-00 0x6085-00 0x6086-00	User specific [2000 qc] User specific [-2147483648 qc] User specific [2147483647 qc] Motor specific [25000 rpm] Desired Velocity [1000 rpm] User specific [10000 rpm/s] User specific [10000 rpm/s] User specific [10000 rpm/s] User specific [0]
Enable Device	Controlword (Shutdown) Controlword (SwitchOn)	0x6040-00 0x6040-00	0x0006 0x000F
Set Target Position	Target Position	0x607A-00	Desired Position [qc]
Start Positioning	Controlword (absolute positioning) or Controlword (abs. pos., start immed.) or Controlword (rel. pos., start immed.) or Controlword (relative positioning)	0x6040-00 0x6040-00 0x6040-00 0x6040-00	0x001F 0x003F 0x007F 0x005F

### 2.2 Read Status

Diagram	Object name	Object	User value [default value]
Read Statusword	Statusword (Target reached)	0x6041-00	The axis is at the target position if bit 10 is set.

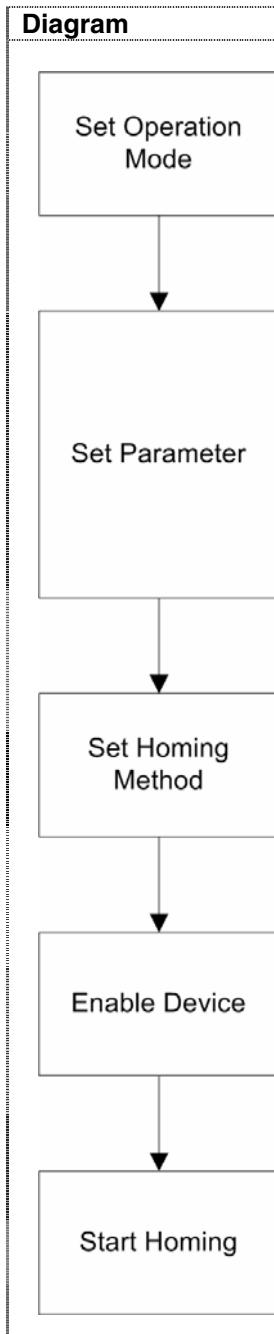
## 2.3 Stop Positioning

Diagram	Object name	Object	User value [default value]
	Controlword (Stop positioning) or Controlword (QuickStop)	0x6040-00 0x6040-00	0x010F 0x000B

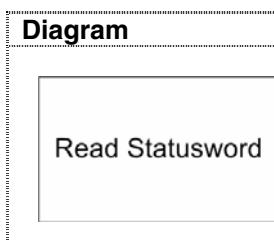
## 3 Homing Mode

### 3.1 Start Homing

The axis references to an absolute position with the selected homing method.

Diagram	Object name	Object	User value [default value]
	Modes of Operation	0x6060-00	0x06 (Homing Mode)
	Max. Following Error Home Offset Max. Profile Velocity Quick Stop Deceleration Speed for Switch Search Speed for Zero Search Homing Acceleration Current Threshold Homing Mode Home Position	0x6065-00 0x607C-00 0x607F-00 0x6085-00 0x6099-01 0x6099-02 0x609A-00 0x2080-00 0x2081-00	User specific [2000 qc] User specific [0 qc] Motor specific [25000 rpm] User specific [10000 rpm/s] User specific [100 rpm] User specific [10 rpm] User specific [1000 rpm/s] User specific [500 mA] User specific [0 qc]
	Homing Method	0x6098-00	Select Homing Method (see document 'EPOS Firmware Specification')
	Controlword (Shutdown) Controlword (SwitchOn)	0x6040-00 0x6040-00	0x0006 0x000F
	Controlword (SwitchOn) Controlword (Start homing mode)	0x6040-00 0x6040-00	0x000F 0x001F

### 3.2 Read Status

Diagram	Object name	Object	User value [default value]
	Statusword (Target reached / Homing attained)	0x6041-00	The home position is reached if bit 10 / bit 12 is set to 1.

### 3.3 Stop Homing

Diagram	Object name	Object	User value [default value]
	Controlword (SwitchOn) or Controlword (HaltHoming) or Controlword (QuickStop)	0x6040-00 0x6040-00 0x6040-00	0x000F 0x011F 0x000B

## 4 Profile Velocity Mode

### 4.1 Start Velocity

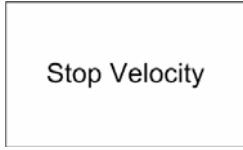
Motor shaft runs with a certain speed with velocity profile.

Diagram	Object name	Object	User value [default value]
Set Operation Mode	Modes of Operation	0x6060-00	0x03 (Profile Velocity Mode)
Set Parameter	Max. Profile Velocity Profile Acceleration Profile Deceleration Quick Stop Deceleration Motion Profile Type	0x607F-00 0x6083-00 0x6084-00 0x6085-00 0x6086-00	Motor specific [25000 rpm] User specific [10000 rpm/s] User specific [10000 rpm/s] User specific [10000 rpm/s] User specific [0]
Enable Device	Controlword (Shutdown) Controlword (SwitchOn)	0x6040-00 0x6040-00	0x0006 0x000F
Set Target Velocity	Target Velocity	0x60FF-00	Velocity for movement [rpm]
Start Move	Controlword	0x6040-00	0x000F

### 4.2 Read Status

Diagram	Object name	Object	User value [default value]
Read Statusword	Statusword (Target velocity reached)	0x6041-00	The target velocity is reached if bit 10 is set.

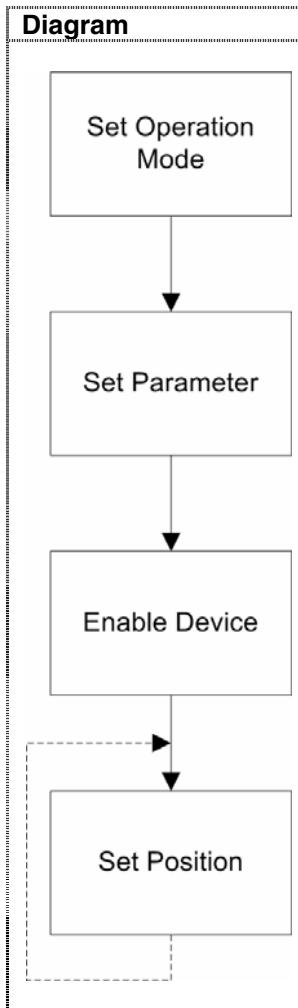
### 4.3 Stop Velocity

Diagram	Object name	Object	User value [default value]
	Controlword (Halt Profile Velocity Mode) or Controlword (QuickStop)	0x6040-00  0x6040-00	0x010F  0x000B

## 5 Position Mode

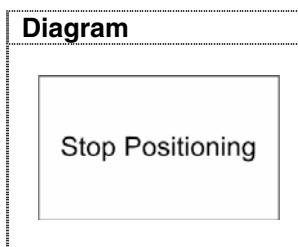
### 5.1 Set Position

The axis moves to new absolute position with maximum acceleration and maximum velocity. There is no trajectory for this movement. When the difference between the new and the actual position is greater than the 'Max Following Error' an Emergency will be launched.

Diagram	Object name	Object	User value [default value]
	Modes of Operation	0x6060-00	0xFF (Position Mode)
	Max. Following Error Min. Position Limit Max. Position Limit	0x6065-00 0x607D-01 0x607D-02	User specific [2000 qc] User specific [-2147483648 qc] User specific [2147483647 qc]
	Controlword (Shutdown) Controlword (SwitchOn)	0x6040-00 0x6040-00	0x0006 0x000F
	Position Mode Setting Value	0x2062-00	New Position [qc]

### 5.2 Stop Positioning

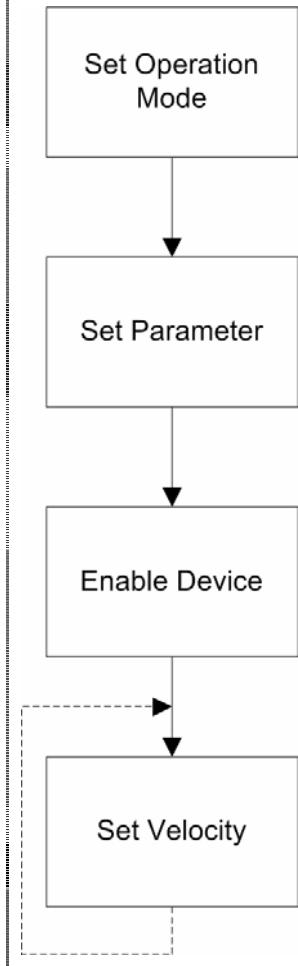
The axis stops with maximum deceleration.

Diagram	Object name	Object	User value [default value]
	Controlword (QuickStop)	0x6040-00	0x000B

## 6 Velocity Mode

### 6.1 Set Velocity

Motor shaft runs with a certain speed with maximum acceleration.

Diagram	Object name	Object	User value [default value]
	Modes of Operation	0x6060-00	0xFE (Velocity Mode)
	-	-	-
	Controlword (Shutdown) Controlword (SwitchOn)	0x6040-00 0x6040-00	0x0006 0x000F
	Velocity Mode Setting Value	0x206B-00	Velocity for movement [rpm]

### 6.2 Stop Velocity

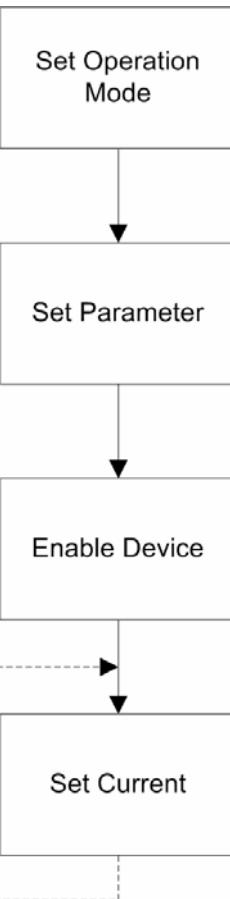
The axis stops with maximum deceleration.

Diagram	Object name	Object	User value [default value]
	Velocity Mode Setting Value or Controlword (QuickStop)	0x206B-00 0x6040-00	0x00000000 0x000B

## 7 Current Mode

### 7.1 Set Current

This command applies a certain current on the motor winding.

Diagram	Object name	Object	User value [default value]
	Modes of Operation	0x6060-00	0xFD (Current Mode)
	Continuous Current Limit Max. Speed in Current Mode Thermal Time Constant Winding	0x6410-01 0x6410-04 0x6410-05	Motor specific for all parameters (see catalogue motor data)
	Controlword (Shutdown) Controlword (SwitchOn)	0x6040-00 0x6040-00	0x0006 0x000F
	Current Mode Setting Value	0x2030-00	User specific current [mA]

### 7.2 Stop Current

Diagram	Object name	Object	Value
	Current Mode Setting Value or Controlword (QuickStop)	0x2030-00 0x6040-00	0x0000 0x0002

## 8 State Machine

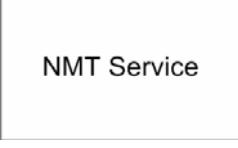
### 8.1 Clear Fault

Resetting "Fault" condition sends the 'Controlword' with value 0x0080.

Diagram	Object name	Object	User value [default value]
	Controlword (FaultReset)	0x6040-00	0x0080

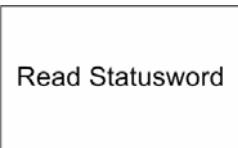
### 8.2 Send NMT Service

This command sends a NMT protocol from a master to a slave. It is a command without acknowledge.

Diagram	Parameters	Command specifier
	Node-ID (Unique Node-ID or 0 for all nodes) Command specifier	0x01 Start Remote Node 0x02 Stop Remote Node 0x80 Enter Pre-Operational 0x81 Reset Node 0x82 Reset Communication

## 9 Motion Info

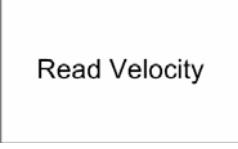
### 9.1 Get Movement State

Diagram	Object name	Object	Value
	Read Statusword	0x6041-00	Bit 10 tells you if the target is reached. For more detail see operation mode above or 'EPOS Firmware Specification' documentation

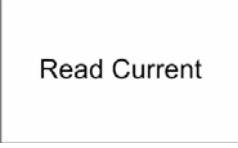
### 9.2 Read Position

Diagram	Object name	Object	Value
	Read Position	0x6064-00	Position [qc]

### 9.3 Read Velocity

Diagram	Object name	Object	Value
	Read Velocity	0x2028-00	Velocity [rpm]

### 9.4 Read Current

Diagram	Object name	Object	Value
	Read Current	0x6078-00	Current [mA]

## 10 Utilities

### 10.1 Store all parameters

Saves all parameters.

Diagram	Object name	Object	Value
	Save All Parameters	0x1010-01	0x65766173 "save"

### 10.2 Restore all default parameters

Restores all parameters to factory default.

Diagram	Object name	Object	Value
	Restore All Default Parameters	0x1011-01	0x64616F6C "load"

### 10.3 Restore default PDO COB-ID's

Set all COB-IDs of the PDOs to the default (Node-ID based) value.

Diagram	Object name	Object	Value
	Restore Default COB-IDs	0x1011-05	0x64616F6C "load"