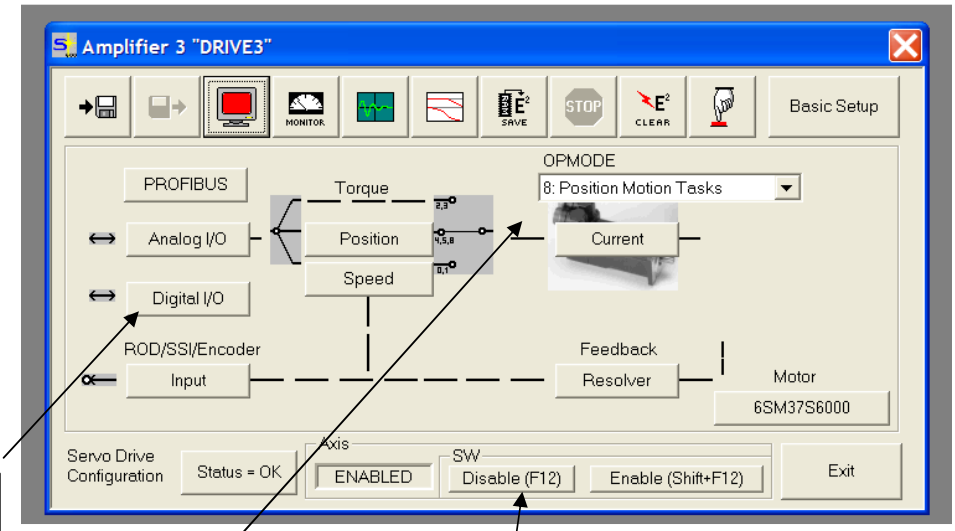
S600 Motion Tasking Example

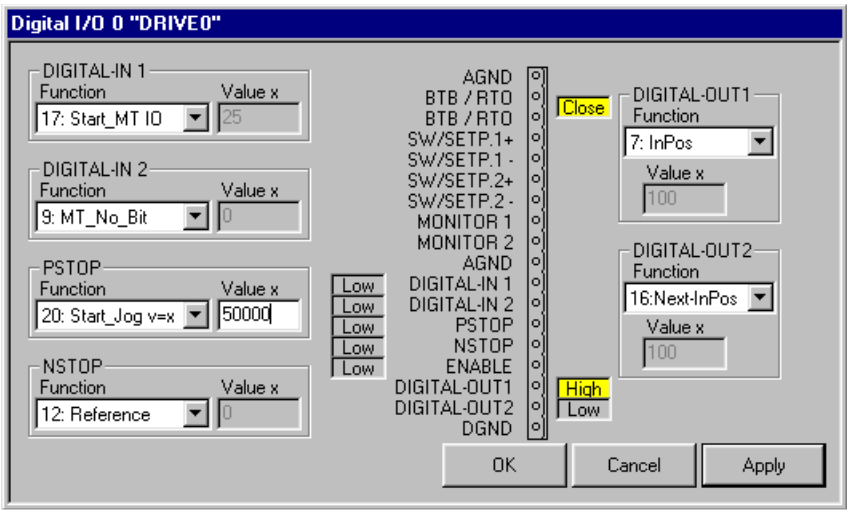
Using ServoStar 600 demo unit

- Start the communication program
- The first window is



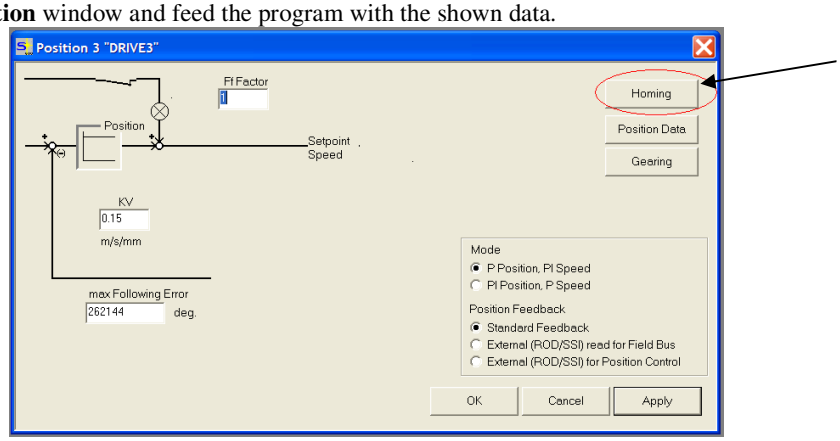
- Disable the drive (if it is enabled)
- Set the **OPMODE** to mode *8: Position Motion Tasks*
- Open the

Digital I/O window and feed the program with the shown data. Not required if commands are giving from the serial port.



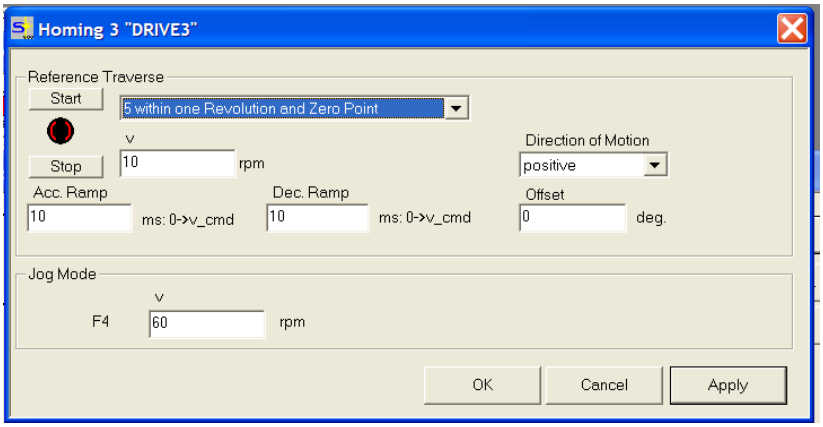
- **Apply**
- Save to EEPROM & Reset Amplifier ? **YES**
- Restart the software again
- Disable the drive again (if it is enabled)

Open the **Position** window and feed the program with the shown data.



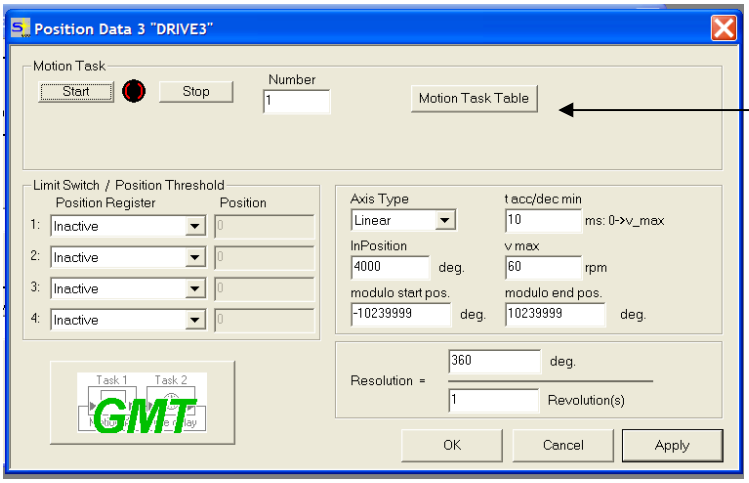
- Press *Apply* and *OK*

- Open the **Homing** window and feed the program with the shown data.



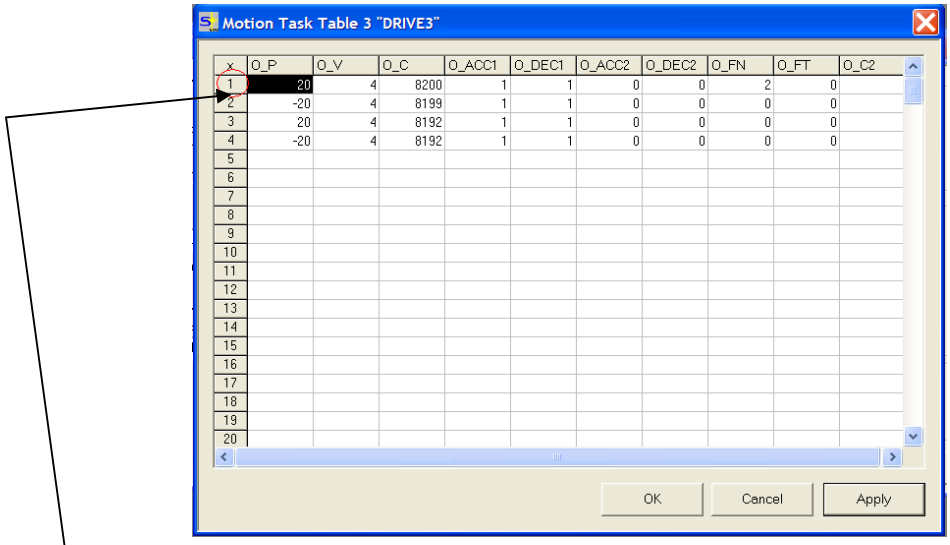
- Press *Apply* and *OK*

Change to the **Position data** window and put in the shown values



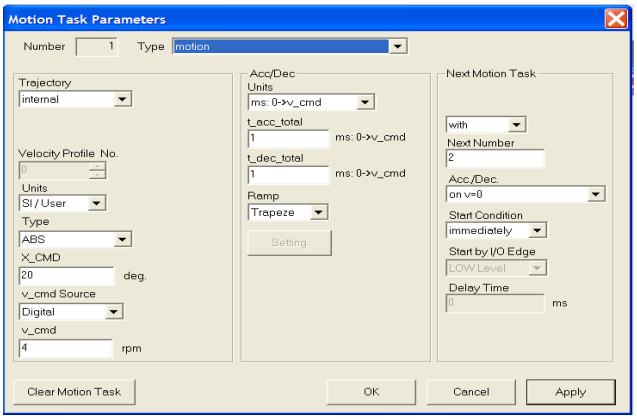
- Click on this arrow to select the motion task input table.

- Selecting the Motion Task no.



- Double click on the Motion Task no. to open it

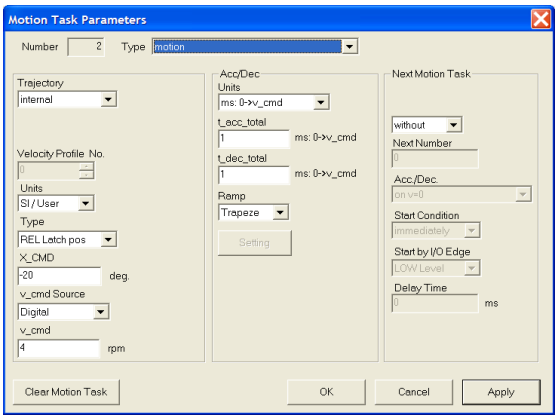
- put in the shown values



- Press *Apply* and *OK*

If you see the button *Apply* only in grey like shown here,
you had forgotten to set the software disable

- Change to the motion task number 2



- Press *Apply* and *OK*

- Save the data to EEPROM
- Reset the drive
  first window (see page 1) button *STATUS* = ... and then button *RESET* and *YES*
- Restart the program
- Set the digital I/O's to low level
- Enable the drive (hardware and software)
- Control the drive by the digital IO

DIGITAL-IN 1	DIGITAL-IN 2	PSTOP	NSTOP	comment
17: Start_MT IO	*9: MT_No_Bit*	*20 Start_Jog v =x*	*12: Reference*	Function of this dig.IO
High	Low	Low	Low	Start Reference Traverse (=Motion Task with the No. 0)
High	Low	Low	**High**	Activate the Home Switch, now the motor will stop and the reference point is set.
Low	Low	Low	Low	
Low	**High**	Low	Low	Set Motion Task No. 1 (2^0)

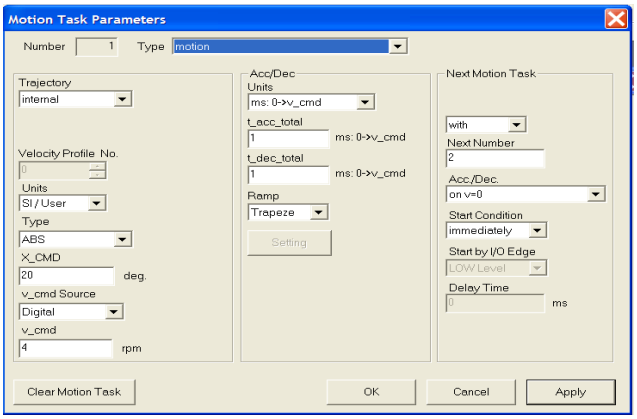
High	**High**	Low	Low	Start Motion Task No. 1
The motor runs from position 0 to 4000 µm (4 resolutions) with 5000 µm/s (300rpm), decelerates to zero, has a brake from 1 second and starts Motion Task 2. It turns anticlockwise back to position 250 µm with 125 µm/s (7.5 rpm). The DIG.-OUT 1 (INPOS) is low, if the actual position is outside the In_Position window range. The DIG.-OUT 2 (Next-INPOS) is low, while Motion Task 1 is active and high after the start of Task 2				
Low	Low	Low	Low	
Low	Low	**High**	Low	Start Jog with 50000 µm/s (3000rpm)
After using the Jog command the motor will go to the defined position from motion task 1, if you start this motion task.				

- Operating the S600 in Serial Positioning from serial commands

- MH (serial command to start homing)
- Motion task higher than 192 can be changed without rebooting by coldstarting the drive information is saved in the RAM, below 192 are saved in the Eeprom.
- Move is the serial command that starts a move from the motion task table . Example (Move 1) Starts Motion Task no. 1

- What is an Order?
- An Order is the serial command for the Motion Task . The Order below has the same information as in the Motion Task table below.

- ORDER 1 20 4 8200 1 1 0 0 2 0



ORDER 1 20 4 8200 1 1 0 0 2 0