

Indications

Fault situations are indicated with coded blinking of a red LED. Fault alarm can be forwarded out through combiport (pin.13). Fault situation is reset with a short (<5s) command to RES/F-run input (pin.11).

Some faults are reset automatically with a new position command to opposite direction. Instead of fault indication the combiport can be set to inform the status of the positioning as an "on position" output, or it can be set to give an analog position indication with 0-5V or 0.5-4.5V signal. Configuration of the combiport is done with par.9. Notice: If it is set to give analog information out (par.9 val3/4), also the DIP-switch 3 should be set to ON position. If combiport (pin 13) is selected to be fault output (par.9 val.1), it will also work as fault-disable input when externally pulled down.

Adjustments and settings

Parameter setting is done with EM-236 Interface Unit which is connected to a powered controller unit through the red connector. During the start up routine the Interface Unit will display information about itself and then the name and program version of the target device (driver which it was connected to). Then it will stay on displaying EDIT & LOAD. Pushing the "yes" button will up load and show the parameter list of the driver. Now the user can scroll the list with arrows, and make value changes with + and - buttons. Changed value is effective after few seconds when the display stops the blinking. But notice, that the change will not be saved until you give a long press (>5s) with the "save" button. This will save the changed list also to the EM-236s memory. Now it is easy to copy the same parameters to the next driver. Just connect the unit to the next powered driver and after start up routine just press a long "save". You can repeat this until all needed units have been set.

LIST OF PARAMETERS prog. v1.8 (defaults in parentheses)

- 1 No function (0)
- 2 Limit input logic (1)
 - 1= PNP
 - 2= NPN
 - 3= PNP inverted
 - 4= NPN inverted
- 3 Speed FW: 20-100% / 0-100 (100)
- 4 Speed BW: 20-100% / 0-100 (100)
- 5 Speed for F-driving: 20-100% / 20-100 (60)
- 6 Current limit out, FW: 0.1-20A / 1-200 (30)
- 7 Current limit in, BW: 0.1-20A / 1-200 (30)
- 8 Current tripp delay: 0-255ms / 0-255 (20)
(0=tripp not in use)
- 9 Combiport (pin 13) function: 1-4 (1)
 - 1= used as Fault in/out
 - 2= gives the "on position" information with 0V
 - 3= gives position indication with 0 - 5V
 - 4= gives position indication with 0.5-4.5V and fault =0V
- 10 Over voltage limit: 15-40V / 15-40 (35)
- 11 Load compensation: 0-255 / 0-255 (0)
- 12 Time out cut-off: 1-255s. / 1-255 (0= not in use) (0)
- 13 Hour and start counter reset (0)
set value = 1 and press save -> counters are set to zero
- 14 Forced run function with >5s command to pin 11 (1)
 - 1= makes F-run to BW direction
 - 2= makes F-run to FW direction
- 15 Fault reset conditions 0-1 (1)
 - 0= reset with RESET-input or opposite direction request .
 - 1 = fault reset can be done only with RESET-input (pin 11)
- 16 No function (0)
- 17 Dead zone : 0-5% / 0-50 (10)
- 18 Braking zone : 1 - 8% / 1 - 8 (3)
- 19 Start ramp : 0,1-2,5s / 1-25 (10)
- 20 Stop ramp : 0,1-2,5s / 1-25 (3)
- 21 Set value min. 0...5,50V / 551 (0)
- 22 Set value max. 0...5,50V / 0-551 (550)
- 23 Inner (BW) SW-limit: 0...-50% 0-500 (5)
- 24 Outer (FW) SW-limit: 0...+50% 0-500 (5)
- 25 pwm frequency: 1=2kHz / 2=16kHz (0)
- 26 Serial line configuration, speed, parity, and number of stop bits (1)
 - 1 =9.6kbps 8N1 5 =19.2kbps 8N1
 - 2 =9.6kbps 8N2 6 =19.2kbps 8N2
 - 3 =9.6kbps 8E1 7 =19.2kbps 8E1
 - 4 =9.6kbps 8O1 8 =19.2kbps 8O1
- 27 Modbus address 1-247 (1)
- 28 Input pin 3 options and LOCAL/BUS selection (0)
 - 0 = Pin 3 work as BW limit input, local /bus selection only with bus
 - 1 = Pin 3 defines control mode local/bus, pin open = LOCAL
 - 2 = Pin 3 defines control mode local/bus, pin open = BUS

FAULT LED -blinking codes

- | | |
|----------------------|----------|
| 1. I-trip | 1 blink |
| 2. time out trip | 2 blinks |
| 3. over temperature | 3 blinks |
| 4. over voltage trip | 4 blinks |

Pls. notice:

when card is powered the LED- blinks onse.

MONITORABLE VALUES (Can be read with EM-236)

- | | |
|------------------------------------|---------------------------|
| 1 fault code | (see the fault code list) |
| 2 motor current | 0-200 (0-20A) |
| 3 target position | 0-1000 (0-100,0%) |
| 4 realized position | 0-1000 (0-100,0%) |
| 5 hour counter | (max.65535h) |
| 6 start counter | (max.65535 starts) |
| 7 start counters over flow counter | (max. 65535) |
| 8 feedback input | 0-1023 (5.4mV / digit) |

ABOUT PARAMETERS

1. No function.
This parameter position is not is use in this program.
- 2 Limit switch input terminals (pin 2 and 3) can be set to work with positive or negative logic. Positive =PNP, negative=NPN. The effect can also be inverted so that when signal is ON status is OK, and signal OFF status is "disable by limit".
- 3 & 4 are for speed setting of FW (out) and BW (in) directions.
- 5 the speed setting for "Forced run" (F-run).
- 6 & 7 current limit setting for FW (out) and BW (in) directions
- 8 determines the time the current is allowed to be on the limit value before driving is cut off (driver tripps off). Value is in milliseconds and if set to "0", the current tripping feature is disabled.
- 9 Configuring the combiport functions (pin 13). This terminal can work as combined input-output for fault. Or it can give a "position OK" signal after successful positioning. It can also be used to indicate the position with a continuous voltage signal (position signal). If position signal is chosen (val 3 or 4) the DIP3 must be set to "ON".
- 10 Over voltage protection switches the motor to free wheel. This saves the controller or other devices in supply line from over voltage in case the motor generates energy during slowing down or braking. This can happen with eg. in vehicle or lifting applications.
- 11 Load compensation (Rxl-comp) enables good motor torque even with low speeds. It is good to start testing with zero value, but if the motor seems weak when starting with normal load, the value can be increased step by step until there is power enough to start. Notice: Too high value is recognized from oscillation and/or twiching, If it is not possible to see the behavior of the motor and test the effect with momentary loading of a freely running motor the safest value for this parameter is zero.
- 12 Time out tripp will cut off the driving if continuous driving to the same direction exceeds the set value (statet in seconds).
- 13 This parameter is for resetting the start and hour counters. Saving value 1 will set to zero the drivers start and hour counters.
- 14 Parameter for choosing the forced run direction. F-run is started with long >5s command to RES/F-run terminal (pin 11)
- 15 Determines how the controller recovers from fault situation. Val 0. Recovers also with an opposite direction movement request. Val 1. fault requires a short (<5s) reset command to pin 11.
- 16 No function. Value of this parameter position has no effect.
- 17 Dead zone for determining the wanted positioning accuracy. If this window value is small the positioning is tended to be done more accurately. If value is too small the application is not capable to exceed this accuracy, and can not find or maintain the set position steadily. In this case the value should be increased.
- 18 Braking zone value is determined as a percentage of the full movement range. It determines how early driver starts to slow down before reaching the right position. Main rule is that small value for slow applications and high value for fast applications.
- 19 & 20 Start and stop ramps are used to smoothen the speed and direction changes. The parameter value is the time from 0-100% and from 100%-0 speed.
- 21 & 22 are for determining the control signal range limits. Value can be given as Volts, 0 to 550 (0 to 5,5V). The values can also be measured automatically by setting the parameters to value to 551. The card will then measure the range min. and range max. voltages on the POSITION SET input. Pls. read also the chapter "Control range setting".
- 23 & 24 Inner (BW) and outer (FW) SW-limits. With these adjustable limits the movement range can be limited to suite the application. Notice: the forced run will over drive these points.
- 25 16 kHz pwm frequency offer silent function, but cannot offer motor current as much as 2kHz option
- 26 and 27 serial / modbus speed, parity and address settings
- 28 LOCAL or BUS selection options. In Local mode uses only card analog and digital inputs, In Bus mode the Modbus control is active

CONNECTION ADVISE

Supply voltage should be in the limits of 10-35Vdc. Ripple should be lower than 30% even with maximum load.

NOTICES!

1. Wrong supply polarity can damage the device.
2. There is no inbuilt fuse in this device. So use an additive outside fuse and choose it according to your application.
3. The meaning of the terminals can change when changing the parameters (pls.see the parameter list and explanations).

TAKING IN TO USE

The setting of the driver is done with parameters, and the parameters can be set and edited with EM-236 Interface Unit or EmenTool Lite PC program and EM-328 USB to serial converter. This makes changing easy and precise. Also the copying of the same parameters to multiple units is simple and same time accurate. The same parameters that are saved to one unit can be copied to an other unit with just one push of an button. Start by checking and setting the hardware related parameters. After that the actuator can be connected and operation fine tuned with other parameters.

Control range setting

Options for max. ranges are 0 to 5,5V, and 4 to 20mA if you place a 250ohm resistor to the resistor socket on the driver board. Using 0 to 11V range requires you to set the DIP switch 2 to "ON" position.

An individual control scale you can either set with parameters 21 and 22 as Volts or you can let the driver to measure your min. and max. control values. If you choose to set the min. and max. as Volts, pls. notice that the values are in ratio to the lowest range 0-5,50V, and with 0-11V range you have to divide the actual voltage with two. With current signal you should use the 0-5,5V range, and the right value can be calculated $I \times 250$. Eg: 4-20mA= 1,0 - 5,0V. Most precise way is to let the driver to measure the values. So first connect and adjust minimum value to set input (pin.12) and change the par.21 to val. 551. After value stops blinking the display shows the measured value. Then adjust the maximum control value to pin.12, and change par.22 to 551. After a while you will see the measured value in display. Always remember to save with long push to save button, before disconnecting EM-236 and taking power off from the driver. Notice: If control min. value is set higher than max. value the movement range will be inverted and set accordingly.

Feedback

Feedback range is always 0 to 5,5V as default. By setting the dip switch 2 to "ON" the range can be multiplied to 0 - 11V. If the actual feedback signal can not reach the ends of the default range, parameters 23 and 24 can be used to accomodate the ranges. Setting the inner and outer software limits to suitable percentage values will compensate the narrow control signal range to the default range.

Forced run (F-run)

Forced run enables the motor to be driven to the mechanical end. That means that the motor or actuator can be driven beyond the determined soft ware limits. The SW-limits are used to determine the operational movement range. But the parameter 14 value and the use of F-run will enable the wider driving range for service use or for use in some special situations of the application. F-run is started with a long command (>5s) to pin 11. The F-run speed is determined with parameter 5 and the driving is stopped with current trip or limit switch that cuts off the motor current. Motor will return to its servo position right after the signal to pin 11 disappears. Notice. The same pin 11 is used also as a reset input with short command (<5s).

Positioning dynamics

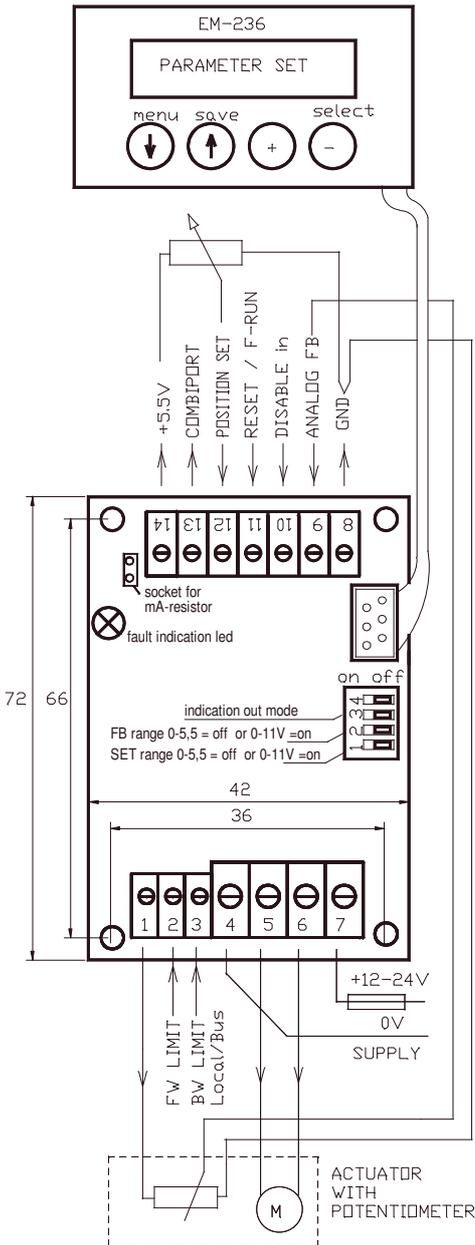
Dead zone (par.17) is to determine the accuracy of positioning. This parameter has the major effect to positioning accuracy. The smaller it is determined the more accurately the positioning is done. Notice. If it is set too small compared to accuracy level of the mechanics an oscillation or unstability in positioning will occur.

Braking zone (par. 18) is used to optimize the time needed for positioning. Too high value slows down too early, and too low value will cause a fast position passing and needs a corrective return driving.

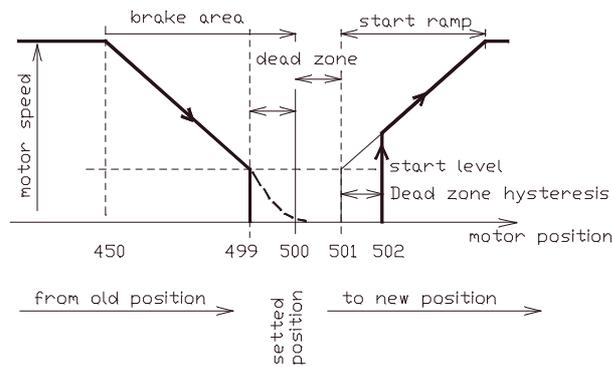
Start and stop ramp (par. 19 & 20) are to smoothen the direction change. Often suitable value for stop ramp is half of start ramp. Too long stop ramp can make the direction change too time consuming and too short can cause mechanical stress and non desired aggressivity.

Load compensation (par.11) when set to right value, will ensure the needed force to start driving and to taking the load in to the right position. With high load and too low load compensation value, the motor dont have force enough to reach the right position. Start testing with zero value and increase value untill motor behaves unstable and twitching. Thumb rule in this point is to decrease the value with 25%.

Current limits (par. 6 and 7)should be set according to the motor nominal max. current or according to the required current of the application.



POSITIONING WINDOW EXAMPLE



PARAMETERS SETTINGS:

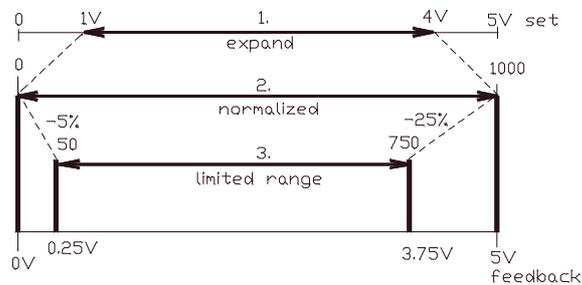
Dead zone 0.1% (= 1)

Braking area 5% (=50)

SET position changes 0 to new position 500
 Motor run speed FW until position reach value 450. Motors starts slowing down, until position reach value 499 and motor shut down and motor should stopped to value 500.

Motor will start again when position SET changes over 502

RANGE SCALING EXAMPLE



POSITION SET signal range is 1..4V
 Range is scaled with set parameters
 $21 = 100$ and $22 = 400$

Now the 1..4V signal is internally normalized to the range 0-1000.
 This normalized value corresponds to 0-5V feedback range

Feedback range can be compressed with parameter 23 and 24, in this example inner limit -5% and outer -25%.

Final result is that control range 1-4V match to 0.25...3.75V feedback range