Upgrade Information of MPE720 Version6.04

1. Add Function / Item Improvements

1.1 Ver. 6.04 upgrade information

The add function and the improvement from MPE720 version 6.03 to MPE720 version 6.04 are as follows.

| No. | Item of Function | Classification |
|-----|--|----------------|
| 1 | Controller model (MP2310·MP2300S·MP2400) Addition | Add function |
| 2 | PC-LINK module addition | Add function |
| 3 | AFMP-02-C module addition | Add function |
| 4 | 218IF-02 module addition | Add function |
| 5 | Automatic logical port setting to Communication process | Add function |
| 6 | Controller retrieval by 218IF-02 | Add function |
| 7 | New motion instruction addition (ASCII/ SSEE/ FUNC/ C-TSK/ C-FUNC) | Add function |
| 8 | For sequence program | Add function |
| 9 | Motion program instruction input support | Add function |
| 10 | Motion program instruction input support (Servo On / Servo Off) | Add function |
| 11 | Motion program instruction input support (Alarm Clear) | Add function |
| 12 | Driving control panel | Add function |
| 13 | Addition of program execution registration screen | Add function |
| 14 | Set parameter addition | Add function |
| 15 | The motion alarm analysis screen is added | Add function |
| 16 | System window addition | Add function |
| 17 | Test run (Servo On (Off) /JOG /STEP /Alarm) | Add function |
| 18 | Axis monitor | Add function |
| 19 | Alarm monitor | Add function |
| 20 | Compile option setting from environment setting | Improvement |
| 21 | Trouble shooting function | Improvement |
| 22 | Change of name of variable in contradiction to rule | Bug fix |
| 23 | It makes an error when the MAL file made with Ver.5 is converted with Ver.6 | Bug fix |
| 24 | Trouble that B and W register become unused treatments because of display of map of register list used by ladder application | Bug fix |
| 25 | When the MAL file made with Ver.5 is converted with Ver.6, the comment on the IO variable is not converted | Bug fix |

1.2 Past upgrade information

| No. | Upgrade information | Remarks |
|-----|-------------------------------------|------------------------|
| 1 | MPE720 Ver.6.02 upgrade information | Ver. 6. 01->Ver. 6. 02 |
| 2 | MPE720 Ver.6.03 upgrade information | Ver. 6. 02->Ver. 6. 03 |

2. Description of change of specification

No.1 Controller model (MP2310·MP2300S·MP2400) Addition

The following controller models were added.

*MP2310 *MP2300S *MP2400

No. 2 PC-LINK module addition

The PC-LINK function was added.

| Module Configuration | GROUP\ORDER | PLC MP2300 | Offline Local | | | |
|---|-----------------------|----------------------|---------------|-------------|----------------------------------|---|
| PT#:- CPU#:- | | | | | | |
| Controller | | | | | | |
| Slot Number | 00 | 01 | 02 | 03 | | DLC MD2300 Offline Local |
| Module Type | MP2300 - | PCLINK-01 | UNDEFINED - | UNDEFINED - | | Cree mr 2500 Onnine Edean |
| Controller Number | | | | | PT#:- CPU#:- | |
| Circuit Number | | | | | | × × × |
| I/O Start Register | | | | | Transmission Parameters 1/0 As | signment I/OMap Status |
| I/O End Register | | | | | | |
| Disable Input | - | - | - | - | | |
| Disable Output | - | - | - | · · | Chaling Ma | |
| Motion Start Register | | | | | Station No | P ([· 32] |
| Motion End Register | | | | | | |
| Details | | | | | Course No. | 129 (100 100) |
| Status | | | | | Group No | [123 · 160] |
| | PC/EINIX/Senar Comm | ianication fanction. | | | Token Hold Timer | 10 📩 ms (1- 65) |
| Module Details PCLINK-01 | SLOT#01 | 1 | | | Token Receive Timer | 500 🔹 ms (50 · 2550) |
| Slot Number Module Type Controller Number Circuit Number | 1 PC-LINK - | | | | Station Search Interval | 1000 • ms (100 - 25500) |
| 1/0 Start Register 1/0 End Register | 0402 0C81 | | | | Discrete Offset | 800 📩 HEX (H000 · H800) |
| Motion Start Register | | | | | | |
| Motion End Register | | | | | MEMORUS Monitoring | 0 - 0 25500) |
| Details | | | | | MEMUBUS Monitoring | - · · · · · · · · · · · · · · · · · · · |
| Status | | | | | Retry Count | 0 📩 Time (0- 3) |
| PC-LINK:Real-Time Core Ne | twork Functions for G | L Seriese. | | | Transmission Speed | 4 Mbps |

No. 3 AFMP-02-C module addition

The AFMP-02-C module that was the CC-LINK module (slave) made by the Anywire Corporation was added.

| <u> </u> | odule Configuration | GROUP\ORDER | PLC MP2300 | Offline Local | | |
|----------|-----------------------------|-----------------------|------------|---------------|-----------|---|
| PT#: | :- CPU#:- | | | | | |
| E Co | ontroller | | | | | |
| | Slot Number | 00 | 01 | 02 | 03 | |
| ΙF | Module Type | MP2300 - | AFMP-02-C | UNDEFINED - | UNDEFINED | - |
| | Controller Number | • | <u> -</u> | <u> </u> | • | _ |
| ۱ŀ | URCUIT NUMBER | · | | | - | |
| TE | I/O End Register | | | | | |
| | Disable Input | - | | - | • | - |
| | Disable Output | - | • | | | - |
| | Motion Start Register | | | | | _ |
| H | Motion End Register | | | | | _ |
| I H | Details Status | | | - | | |
| E | oratus | | | | | = |
| P | a Min-uz-c. The module rids | CO-Ellik Siave Func | aon. | | | |
| | | | | | | |
| | | | | | | |
| E M | todule Details AFMP-02-C 9 | LOT#01 | | | | |
| Т | Slot Number | 1 | | | | |
| | Module Type | CC-Link - | - | | | |
| I L | Controller Number | | | | | |
| | Circuit Number | | - | | | |
| | 1/U Start Register | 0402 | - | | | |
| T | Disable Input | Enable | | | | |
| | Disable Output | Enable | - | | | |
| | Motion Start Register | | | | | |
| | Motion End Register | | | | | |
| | Details | | | | | |
| | Status | | | | | |
| jc | CC·Link : CC·Link Slave com | munications function. | L | | | _ |
| | | | | | | |
| | | | | | | |

No. 4 218IF-02 module addition

218IFB that 217IF that was the serial communications function and was the high-speed Ethernet function was added and 218IF-02 module that had line was added respectively once.

| Module Configuration | GROUP\ORDER | PLC MP2300 | Offline Local | | | | |
|-----------------------------|-----------------------|------------|---------------|-------------|-----|--|-----------------------------|
| PT#:- CPU#:- | | | | | | | |
| Controller | | | | | 1 | | |
| Slot Number | 00 | 01 | 02 | 03 | | | |
| Module Type | MP2300 - | 218IF-02 | UNDEFINED - | UNDEFINED 👻 | | | |
| Controller Number | | ŀ | | • | | | |
| Circuit Number | • | | • | • | | | |
| I/O Start Register | | | | | | | |
| I/U End Register | | | | | | 218IFB GROUP\ORDER PLC MP2300 Offline Local | |
| Disable Input | - | | | | | | PACK#01 Slot #01 CIP#01 |
| Uisable Uutput | - | | • | - | | | |
| Motion Start Hegister | | | | | | Transmission Parameters Status | |
| Dotale | | | | | | Transmission Parameters | |
| Statue | | | | | | Moo | dule Name Definition |
| Jidius | | 1 | | | | IP Address : 192 🕂 · 168 🕂 · 1 🛨 · 1 🕂 (0-255) Equ | ipment Name CONTROLLER NAME |
| 218IF-02 : The Module has E | themet, RS232 in fund | ctions. | | | | Subnet Mask · 255 · 255 · 255 · 0 · (0.255) | |
| | | | | | - | | -LID-Follow |
| | | | | | | Gateway IP Address: 이 숙 이 숙 이 숙 이 숙 (0-255) | etail Definition |
| | | | | | | | |
| Module Details 218IF-02 SL | OT#01 | | | | | Connection Parameter | |
| Slot Number | 1 | 2 | | | | Level Niete Courses Deste | |
| Module Type | 217IF 🗸 | 218IFB | • | | | CNO Pott Node IP Address Node Connect Proto | e Code |
| Controller Number | 01 | 01 | | | | 01 | · · |
| Circuit Number | 01 | 01 | | | | 02 | • • |
| I/O Start Register | | | | | | 03 | • • |
| I/O End Register | | | | | | 04 | <u> </u> |
| Motion Start Register | | | | | | 05 | • • |
| Motion End Register | | | | | | 06 | <u> </u> |
| Details | | | | | | | <u> </u> |
| Status | | | | | | | |
| | | | | | | 10 | T |
| | | | | | | 11 | - |
| 217IE: BS232 | | | | | | 12 🗸 | • • |
| 10202 | | | | | | 13 | • |
| | | | | | | | |
| | | | | J J | 111 | | |

No.5 Automatic logical port setting to communication process

To connect MPE720 with the controller, the physical communication port is set to the communication process and a logical port is made. It is a function that can be easily connected with the controller by setting this setting to the communication process on the MPE720Ver6 side automatically. (The communication process need not be considered.)

A physical port of the unsetting is selected from the list of the communication port in the communication process. It is set to empty logical port in the communication process that it clicks on a "Connection" button or "Setting" button by the automatic operation.

| Physical port | Set item | Set value | | | | | |
|---------------|---------------------------------|--|--|--|--|--|--|
| Ethernet (LP) | Port type | 100Base-TX | | | | | |
| | Time out | 10000ms | | | | | |
| | IP Address | It is an automatic reading of IP set with the personal | | | | | |
| | | computer. | | | | | |
| | Engineering port | 9999 | | | | | |
| | Message reception specification | No | | | | | |
| Ethernet | Port type | CP218 | | | | | |
| | Time out | 10000ms | | | | | |
| | IP Address | It is an automatic reading of IP set with the personal | | | | | |
| | | computer. | | | | | |
| | Engineering port | 10000 | | | | | |
| | Message reception specification | No | | | | | |
| Serial | Port type | Serial | | | | | |

| ^p arameter | ist | set | to | communication | process | automatically |
|-----------------------|-----|-----|----|---------------|---------|---------------|
|-----------------------|-----|-----|----|---------------|---------|---------------|

| | Time out | 10000ms | | | | | |
|--------|---------------|---|--|--|--|--|--|
| | Physical port | It is an automatic reading of the port number from the | | | | | |
| | | personal computer. | | | | | |
| | Unit No. | 1 | | | | | |
| | Baud rate | 19. 2K | | | | | |
| | Data length | 8 | | | | | |
| | Parity | Even | | | | | |
| | Stop bit | 1 | | | | | |
| USB | Port type | USB | | | | | |
| | Time out | 10000ms | | | | | |
| MP2100 | Port type | MP2100/2500 | | | | | |
| | Time out | 10000ms | | | | | |
| | Destination | Device | | | | | |
| | CP | It is an automatic reading of the CP number from the personal | | | | | |
| | | computer. | | | | | |

No. 6 Controller retrieval by 218IF-02

The controller connected with the Ethernet cable will be searched by retrieving on the network of Ethernet. It is a function that can be easily connected from this retrieval result by selecting the controller.

When Ethernet (LP) is selected in the communication port, the controller retrieval screen is displayed. The controller retrieval screen retrieves the MP controller on the network connected with Ethernet. And, it displays it as a tree list.

When "Controller retrieval list" at the head of the tree is developed, the retrieval is executed. The execution result is displayed in subordinate's tree. And, IP of the controller who selects it is set to the Internet Protocol address setting item by the automatic operation.

| 🚆 Communications Setting | |
|--|-------------------|
| Set the communication setting Communication port 3 : Ethernet(LP) (IP:192.168.1.2) | Connection |
| IP address 192 . 168 . 1 . 1 | Cancel |
| Search Controller Search | << <u>D</u> etail |
| Controller IP address/port Module name | |
| MP2300 192.168.1.1/9999 CONTROLLER NAME | |
| Use the router | |

No. 7 New motion instruction addition(ASCII/ SSEE/ FUNC/ C-TSK/ C-FUNC)

end;

The ASCII/ SSEE/ FUNC/ C-TSK/ C-FUNC instruction was newly added as a motion instruction.

< Instruction explanation > ASCII: ASCII character string is set to a specified register. SSEE: The sequence subprogram is called. FUNC: Function drawing call from sequence program C-TSK: Call of C language task C-FUNC: Call of C language function PT#:-- CPU#:--🗅 😂 🖬 🥵 🗡 ; 🛤 📟 🕴 🖡 🗊 🖬 🥾 부 🔛 🔳 🔯 🏻 • 00001 ASCII 'ABCDEFG' MW10; 00002 SSEE SPS020; FUNC FUNC001 MB000000 IW0010 MB000020, MA00100, 00003 MB000001 MW00201 ML00202; CTSK DB01 DW12, DA10, DB02 DB03 DL04; 00004 00005 CFUNC MBOD 0 0, MAO2 MA10 MA20, MB03 MB04 ML24; 00006

No. 8 For sequence program

00007

00008 Line

Sequence program (SPMxxx/ SPSxxx) executed at each scanning was able to be made. * It is possible to use it only by general that has M-EXECUTOR controller

| Motion | × |
|------------------------|---|
| | |
| Program | |
| 🖃 📊 test [MP2310] | |
| - 🕀 🖾 Motion program | |
| 🗖 🗖 👼 Sequence program | |
| 🖙 🚍 ि Main program | |
| SPM001 | |
| Sub program | |
| [] SPS002 | |
| | |
| | |
| | |

No. 9 Motion program instruction input support

The motion program instruction input support is a function to support the description of the motion program when the motion program is made.

The pop-up menu is displayed in the cursor point that describes the motion program. When a motion instruction "MOV: Position" etc. is arbitrarily selected from the menu, the instruction assistance input screen is displayed. The parameter of the instruction is displayed on this screen. The instruction can be inserted in the program by setting the parameter without referring to the manual on this screen.

The instruction supported by the sequence program and each motion program is different. Motion command assist Instruction insert

| Sea Motion command assist | | | | | "POSITIONING" MOV (A11100000 (B11300000) |
|----------------------------------|------|-----------------|--------|----------|---|
| Select Command MOV : POSITIONING | | | | • | MOT [A1]100000 [D1]300000; |
| MOV [Axis1]- [Axis2]; | | | | | Format |
| Axis number : 2 | | | | Update | Axis |
| Argument | Axis | Setting value I | Jnit | <u>~</u> | |
| [Axis1] Position | A1 | 100000 [| pulse] | <u> </u> | |
| [Axis2] Position | B1 | 300000 _ [| pulse] | | |
| Comment | | | | <u> </u> | Parameter |
| POSITIONING | | | | | Comment |
| | | Insert Clos | e | Help | |

| Classification | ltem | Motion | Sequence |
|----------------|--|--------------|--------------|
| Auto Marca | | Program | Program |
| AXIS MOVE | | × | |
| Commands | | ✓ | |
| | MCW : CIRCULAR INTERPULATION (CIOCKWISE) | ✓ | |
| | MCG - GIRCULAR INTERPULATION (COUNTERCIOCKWISE) | · · | |
| | MCW · GIRCULAR INTERPULATION radius (Glockwise) | · · | |
| | MUG - CIRCULAR INTERPOLATION radius (Counterclockwise) | · · | |
| | | · · | |
| | MCG : HELICAL INTERPOLATION (Counterclockwise) | · · | |
| | MCW HELICAL INTERPULATION radius (CIOCKWISE) | · · | |
| | MCG : HELICAL INTERPULATION radius (Counterclockwise) | · · | |
| | ZRN - ZERU PUTNI RETURN | · · | |
| | | ✓ | |
| | | · · | |
| | EXM : EXTERNAL PUSTITUNING | · · | |
| Control | ABS : ABSULUTE MUDE | ✓ | |
| commands | INC : INCREMENTAL MODE | ✓ | |
| | | ✓ | |
| | PLN : COURDINATE PLANE SETTING | ✓ | |
| | MVM : MOVE ON MACHINE COORDINATES | ✓ | |
| | PLD : PROGRAM CURRENT POSITION UPDATE | ✓ | |
| | | ✓ | |
| | END : PROGRAM END | ✓ | ~ |
| Speed And | ACC : ACCELERATION TIME CHANGE | ✓ | |
| Acceleration/ | DCC : DECELERATION TIME CHANGE | | |
| Deceleration | SCC : S-CURVE TIME CONSTANT CHANGE | | |
| Commands | VEL : SEI SPEED | | |
| | IFP : INTERPOLATION FEED SPEED RATIO SETTING | ✓ | |
| | FMX : MAXIMUM INTERPOLATION FEED SPEED | ✓ | |
| | IAC : INTERPOLATION ACCELERATION TIME CHANGE | ✓ | |
| | IDC : INTERPOLATION DECELERATION TIME CHANGE | ✓ | |
| High-Level | PFN : SECOND IN-POSITION CHECK | ✓ | |
| Control | INP : SET SECOND IN-POSITION RANGE | ✓ | |
| Commands | SNGD SNGE : SINGLE-BLOCK SIGNAL DISABLED/ENABLED | ✓ | |
| | IOW : I/O VARIABLE WAIT | ✓ | |
| | MSEE : SUBROUTINE CALL | \checkmark | |
| | SSEE : SEQUENCE SUBROUTINE CALL | | \checkmark |
| | RET : SUBROUTINE RETURN | \checkmark | \checkmark |
| | EOX : ONE SCAN WAIT | \checkmark | |
| | IF ELSE IEND : Branching Commands | \checkmark | \checkmark |
| | WHILE WEND : Repeat Commands | \checkmark | \checkmark |
| | PFORK JOINTO PJOINT : Parallel Execution Commands | \checkmark | |
| | SFORK JOINTO SJOINT : Selective Execution Commands | \checkmark | |

Instruction input support support list

| Overview of | SFR : BIT RIGHT SHIFT | \checkmark | \checkmark |
|-----------------|-------------------------------|--------------|--------------|
| Sequence | SFL : BIT LEFT SHIFT | \checkmark | \checkmark |
| Commands | BLK : BLOCK MOVE | \checkmark | \checkmark |
| | CLR : CLEAR | \checkmark | \checkmark |
| | SIN : SINE | \checkmark | \checkmark |
| | COS : COSINE | \checkmark | \checkmark |
| | TAN : TANGENT | \checkmark | \checkmark |
| | ASN : ARC SINE | \checkmark | \checkmark |
| | ACS : ARC COSINE | \checkmark | \checkmark |
| | ATN : ARC TANGENT | \checkmark | \checkmark |
| | SQT : SQUARE ROOT | \checkmark | \checkmark |
| | BIN : BCD-TO-BINARY | \checkmark | \checkmark |
| | BCD : BINARY-TO-BCD | \checkmark | \checkmark |
| | S{} : SET BIT | \checkmark | \checkmark |
| | R{} : RESET BIT | \checkmark | \checkmark |
| | ASCII : SET ASCII | \checkmark | \checkmark |
| | PON : RISING PULSE | | \checkmark |
| | NON : FALLING PULSE | | \checkmark |
| | TON : ON-DELAY TIMER | | \checkmark |
| | TOF : OFF-DELAY TIMER | | \checkmark |
| Math Commands | = : SUBSTITUTE | \checkmark | \checkmark |
| | + : ADD | \checkmark | \checkmark |
| | - : SUBTRACT | \checkmark | \checkmark |
| | * : MULTIPLY | \checkmark | \checkmark |
| | / : DIVIDE | \checkmark | \checkmark |
| | MOD : REMAINDER | \checkmark | \checkmark |
| | : OR | \checkmark | \checkmark |
| | & : AND | \checkmark | \checkmark |
| | Λ : XOR | \checkmark | \checkmark |
| | ! : NOT | \checkmark | \checkmark |
| | = : MATCH | \checkmark | \checkmark |
| | ♦ : MISMATCH | \checkmark | \checkmark |
| | > : GREATER THAN | \checkmark | \checkmark |
| | < : LESS THAN | \checkmark | \checkmark |
| | >= : Greater than or equal to | \checkmark | \checkmark |
| | <= : LESS THAN OR EQUAL TO | \checkmark | \checkmark |
| Command Setting | Jog | \checkmark | \checkmark |
| | Servo Enable | \checkmark | \checkmark |
| | Servo Disable | \checkmark | \checkmark |
| | Inverter Enable | \checkmark | \checkmark |
| | Alarm Clear | \checkmark | \checkmark |
| | Inverter Drive Control | \checkmark | \checkmark |
| | Inverter Input Command | \checkmark | \checkmark |

No. 10 Motion program instruction input support (Servo On / Servo Off)

A specified axis is selected, and the program code in which a Servo On register is turned ON/OFF is made automatically. As a result, the motion register address is not considered and the program can be made.

| O ∶ Servo Off 1:Servo On |
|-----------------------------|
| 🐱 Select Axis 🛛 🔀 |
| Axis A1 |
| Insert Close |

"[A1] Servo Disable" OB80000 = 0;

No. 11 Motion program instruction input support (Alarm Clear)

The program code in which a clear alarm is turned ON is generated automatically.



No. 12 Driving control panel

In MP2300S/ MP2310/ MP2400, the driving control panel to be able to drive the made motion program easily was added.

| rive control panel | 2400 1 🔀 |
|---------------------------|-----------|
| Program exec registry No. | No01 |
| Program number | MPM 001 📆 |
| START | START |
| PAUSE | PAUSE |
| Stopped | STOP |
| ALMRST | ALMRST |
| RUNNING | |
| PAUSING | PAUSING 🔘 |
| STOPPED | STOPPED 🔘 |
| ALARM | |
| PRGNUERR | PRGNUERHO |
| Display | Display |

No. 13 Addition of program execution registration screen

In MP2300S/ MP2310/ MP2400, the function that the executed motion program/sequence program was able to be registered to the system easily was added.

| Program execution registry screen | |
|---|----------------------------|
| M-EXECUTOR (individual) | |
| Program execution registry number | Program number MPM001 🗨 |
| Execution type Motion program | Specification |
| Allocation register Allocation DISAB Program number Status ? | |
| Control signal ? 🔽 Override(1=0.01%) | |
| List Delete OK | Cancel |

No. 14 Set parameter addition

The following items were added to SVB setup parameter No2.

- *"Stop mode"
- *"Decelerate to a stop according to the linear deceleration time constant" *"Stop immediately"

*"Decelerate to a stop according to the deceleration parameter"

| Detail | | |
|-------------------|-------------------|---|
| Mode s | etting 2 | |
| bit 0 | Monitor 2 enabled | C Enabled 🕞 Disabled |
| bit 8-F Stop mode | | Decelerate to a stop according to the linea |
| | | OK Cancel |

No. 15 The motion alarm analysis screen is added

When some errors occurred by the motion program, the screen where the error generation part, the cause of the error, and the measures were displayed was added.

As a result, it comes to be able to jump to the error part of the correspondence when the error part displayed on this screen is double-clicked.



| E | Error information screen | | | | | |
|-------------------|---|-------------------------|---------------------------------|-----------------------------|-----------------|--|
| Γ | Execution program information | | | | | |
| | Registry nu | umber: 01 | × D | ouble-click the line to jum | p to the | |
| | Registry pr | ogram: MPM001 | CO | rresponding program whic | h alarm occurs. | |
| | Parallel | Alarm code | Alarm name | Program number | Block numb | |
| | 1 | 0085H | Motion Command Response Error | MPM001 | 0 | |
| | 2 | | | | | |
| | 3 | | | | | |
| | 4 | | | | | |
| | • | | I | | Þ | |
| 7 | Alarm Conte | ents | | | | |
| | The motion | n command response doe: | s not match the motion command. | | | |
| Corrective Action | | | | | | |
| | Axis may be in an alarm state. Clear alarm. Enable servo if it is disabled. Check if multiple programs execute a motion instruction on the same axis. | | | | | |
| | ОК | | | | | |

No. 16 System window addition

"Module composition definition", "Test run", "Axis monitor", "Alarm monitor" and "Motion parameter screen" can be opened from System window by the one click in cooperation with Ver6 main screen.

The System window is a style of the docking System window similar to the tree System window of the motion program. Information on the system is displayed with the tree.

- * The module composition definition screen can be opened directly by clicking "Module composition definition".
- * When the tree of "Axis composition" is opened, "Test run", "Axis monitor" and "Alarm monitor" is displayed. The test run screen, the Axis monitor screen, and the Alarm monitor screen can be opened by clicking of each.
- * The motion parameter screen can be opened directly by clicking the tree of the axis.



No. 17 Test run (Servo On (Off) /JOG /STEP /Alarm)

The test run is a function to confirm whether the axis operates according to a high-ranking instruction from the MP controller. It can be confirmed that the axis drives in the MP controller's instruction in front of the application development process after it wires for the equipment.

- A Servo On/Servo Off and the Jog driving, the step driving, and the alarm are provided as a function. *Servo On / Servo Off: It instructs by turning OB80000 that is the configuration parameter on and off.
 - *JOG: It instructs in the fixed velocity sending by the motion command.
 - *STEP: Relative Position Mode is specified.

*Alarm: The state of generated alarm/Warning is displayed. Moreover, alarm/Warning information screen is displayed.



| Test driving function list (Servo) | | |
|------------------------------------|------------------------|--|
| Function | Function | |
| | explanation | |
| Servo On | Servo On / Servo Off | |
| Servo Off | specified axis | |
| Alarm Clear | The state of the alarm | |
| | or Warning is | |
| | monitored, and the | |
| | Alarm clear is | |
| | executed. | |
| JOG | The axis is moved in a | |
| | specified direction | |
| | of the rotation at a | |
| | constant speed for a | |
| | specified axis. | |
| STEP | It positions it for a | |
| | specified axis for the | |
| | specified amount of | |
| | the movement. | |

| Test | driving | function | list | (Inverter) |
|------|---------|----------|------|------------|
|------|---------|----------|------|------------|

| Function | Function |
|-------------|------------------------|
| | explanation |
| Driving | Run permission |
| permission | specified axis. |
| Alarm Clear | The state of the alarm |
| | or Warning is |
| | monitored, and the |
| | Alarm clear is |
| | executed. |
| JOG | The axis is moved in a |
| | specified direction |
| | of the rotation at a |
| | constant speed for a |
| | specified axis. |
| STEP | No function |

[Attention]

When the motion command is not issued, the test run can be started. The test run ends when the motion command is issued when the test run is starting. And, the test run screen shuts.

(1) Servo On / Servo Off

A Servo On or a Servo Off can be done. OB80000 is set to turning on or turning off by the button click.

"Driving permission" can be done for the inverter. OB8000D is set to turning on or turning off by the button click.



| | | Operating procedure | The setting data |
|----|-----------|---|--|
| 1. | Servo On | The Servo On button ([Run permission] button) | OW8000 (bit0): A Servo On is set to turning |
| | | is pressed on the test run screen. Servo On | on. |
| | | a specified axis. | * OW8000 (bit D): Driving permission can be |
| | | | done for the inverter. |
| 2. | Servo Off | The Servo Off button ([Run permission] | OW8000(bit0):A Servo Off is set to turning |
| | | button) is pressed on the test run screen. | on. |
| | | Servo On a specified axis | *"OW8000 (bit D): Driving permission" can be |
| | | | done for the inverter. |

(2) JOG

In set "Speed instruction value", the normal rotation or the reversal can drive the axis. The axis rotates only while pressing the operation button. Driving stops when pressing is released.



Servo

| Operating procedure | | | The setting data | |
|---------------------|-----------------|---|---|--|
| 1. | Servo On | The Servo On button is pressed. | OW8000 (bit0): A Servo On is set to turning | |
| | | Servo On a specified axis. | on. | |
| 2. | Speed reference | The tab of Jog is selected. | The value is set to | |
| | | Speed reference is set pressing [Speed | OL8010: Speed reference. | |
| | | reference] button. | | |
| 3. | Jog start | [Forward] or [Reverse] button is pressed. | OW8009 (Bit2): Direction of the movement | |
| | | | is set. | |
| | | | OW8008: The Jog Mode (7) is set to the | |
| | | | motion command. | |

STEP

| | | Operating procedure | The setting data |
|----|-----------------|---|--|
| 1. | Servo On | [Run permission] button is pressed. | OW8010 (bit D): Driving permission can be |
| | | Servo On a specified axis. | done for the inverter. |
| 2. | Speed reference | The tab of the Jog run is selected. | The value is set to OW8011: Speed |
| | | Speed reference is set pressing [Speed | reference. |
| | | reference] button. | Attention) The unit of a set value becomes |
| | | | a unit specified by "Frequency Reference |
| | | | " of inverter constant. Please confirm, |
| | | | and operate it. |
| 3. | Jog start | [Forward] or [Reverse] button is pressed. | OW8010(bit0): Forward and OW8010(bit1): |
| | | | Reverse are turned on respectively. |
| | | | OW8008: Inverter Drive Control (1) is set |
| | | | to the command. |

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