BALDOR®
MOTORS AND DRIVES

AC SERVO DRIVE

DBSC Series 2000/3000
Servo Control
for Brushless AC Motors

Installation & Operating Manual

5/01 **MN1220**

Table of Contents

Section 1
General Information

Baldor makes no representations or warranties with respect to the contents hereof and specifically disclaims any implied warranties of fitness for any particular purpose. The information in this document is subject to change without notice. Baldor assumes no responsibility for any errors that may appear in this document.

CE Compliance

A custom unit may be required, contact Baldor. Compliance to Directive 89/336/EEC is the responsibility of the system integrator. A control, motor and all system components must have proper shielding, grounding, and filtering as described in MN1383. Please refer to MN1383 for installation techniques for CE compliance. For additional information, refer to Sections 3 and 8 of this manual.

Limited Warranty

For a period of two (2) years from the date of original purchase, BALDOR will repair or replace without charge controls and accessories which our examination proves to be defective in material or workmanship. This warranty is valid if the unit has not been tampered with by unauthorized persons, misused, abused, or improperly installed and has been used in accordance with the instructions and/or ratings supplied. This warranty is in lieu of any other warranty or guarantee expressed or implied. BALDOR shall not be held responsible for any expense (including installation and removal), inconvenience, or consequential damage, including injury to any person or property caused by items of our manufacture or sale. (Some states do not allow exclusion or limitation of incidental or consequential damages, so the above exclusion may not apply.) In any event, BALDOR's total liability, under all circumstances, shall not exceed the full purchase price of the control. Claims for purchase price refunds, repairs, or replacements must be referred to BALDOR with all pertinent data as to the defect, the date purchased, the task performed by the control, and the problem encountered. No liability is assumed for expendable items such as fuses.

Goods may be returned only with written notification including a BALDOR Return Authorization Number and any return shipments must be prepaid.

Product Notice

Intended use:

These drives are intended for use in stationary ground based applications in industrial power installations according to the standards EN60204 and VDE0160. They are designed for machine applications that require variable speed controlled three phase brushless AC motors.

These drives are not intended for use in applications such as:

- Home appliances
- Medical instrumentation
- Mobile vehicles
- Ships
- Airplanes

Unless otherwise specified, this drive is intended for installation in a suitable enclosure. The enclosure must protect the control from exposure to excessive or corrosive moisture, dust and dirt or abnormal ambient temperatures. The exact operating specifications are found in Section 7 of this manual.

The installation, connection and control of drives is a skilled operation, disassembly or repair must not be attempted.

In the event that a control fails to operate correctly, contact the place of purchase for return instructions.

Safety Notice:

This equipment contains high voltages. Electrical shock can cause serious or fatal injury. Only qualified personnel should attempt the start–up procedure or troubleshoot this equipment.

This equipment may be connected to other machines that have rotating parts or parts that are driven by this equipment. Improper use can cause serious or fatal injury. Only qualified personnel should attempt the start–up procedure or troubleshoot this equipment.

- System documentation must be available at all times.
- Keep non-qualified personnel at a safe distance from this equipment.
- Only qualified personnel familiar with the safe installation, operation and maintenance of this device should attempt start-up or operating procedures.
- Always remove power before making or removing any connections to this control.

PRECAUTIONS: Classifications of cautionary statements.

⚠ **WARNING:** **Indicates a potentially hazardous situation which, if not avoided, could result in injury or death.**

⚠ **Caution:** **Indicates a potentially hazardous situation which, if not avoided, could result in damage to property.**

Continued on next page.

⚠ **WARNING:** **Do not touch any circuit board, power device or electrical connection before you first ensure that power has been disconnected and there is no high voltage present from this equipment or other equipment to which it is connected. Electrical shock can cause serious or fatal injury.**

⚠ **WARNING:** **Be sure that you are completely familiar with the safe operation of this equipment. This equipment may be connected to other machines that have rotating parts or parts that are controlled by this equipment. Improper use can cause serious or fatal injury.**

⚠ **WARNING:** **Be sure all wiring complies with the National Electrical Code and all regional and local codes or CE Compliance. Improper wiring may cause a hazardous condition.**

⚠ **WARNING:** **Be sure the system is properly grounded before applying power. Do not apply AC power before you ensure that grounds are connected. Electrical shock can cause serious or fatal injury.**

⚠ **WARNING:** **Do not remove cover for at least five (5) minutes after AC power is disconnected to allow capacitors to discharge. Electrical shock can cause serious or fatal injury.**

⚠ **WARNING:** **Improper operation of control may cause violent motion of the motor shaft and driven equipment. Be certain that unexpected motor shaft movement will not cause injury to personnel or damage to equipment. Peak torque of several times the rated motor torque can occur during control failure.**

⚠ **WARNING:** **Motor circuit may have high voltage present whenever AC power is applied, even when motor is not rotating. Electrical shock can cause serious or fatal injury.**

⚠ **WARNING:** **If a motor is driven mechanically, it may generate hazardous voltages that are conducted to its power input terminals. The enclosure must be grounded to prevent a possible shock hazard.**

⚠ **WARNING:** **When operating a motor with no load coupled to its shaft, remove the shaft key to prevent injury if it were to fly out when the shaft rotates.**

⚠ **WARNING:** **The motor shaft will rotate during the autotune procedure. Be certain that unexpected motor shaft movement will not cause injury to personnel or damage to equipment.**

⚠ **WARNING:** **A DB Resistor may generate enough heat to ignite combustible materials. To avoid fire hazard, keep all combustible materials and flammable vapors away from brake resistors.**

⚠ **WARNING:** **The user must provide an external hard-wired emergency stop circuit to disable the control in the event of an emergency.**

⚠ **Caution:** **Suitable for use on a circuit capable of delivering not more than the RMS symmetrical short circuit amperes listed here at rated voltage.**

Horsepower	**RMS Symmetrical Amperes**
1–50	**5,000**

⚠ **Caution:** **To prevent equipment damage, be certain that the input power has correctly sized protective devices installed as well as a power disconnect.**

Continued on next page.

⚠ **Caution:**	**Avoid locating control immediately above or beside heat generating equipment, or directly below water or steam pipes.**
⚠ **Caution:**	**Avoid locating control in the vicinity of corrosive substances or vapors, metal particles and dust.**
⚠ **Caution:**	**For UL installations, do not connect any resolver cable shields to the motor frame. At a minimum, resolver signal integrity will be compromised and damage to the control may result.** **For CE installations, refer to CE guidelines stated in Sections 3 and 8 of this manual.**
⚠ **Caution:**	**Do not connect AC power to the control terminals U, V and W. Connecting AC power to these terminals may result in damage to the control.**
⚠ **Caution:**	**Baldor recommends not using "Grounded Leg Delta" transformer power leads that may create ground loops and degrade system performance. Instead, we recommend using a four wire Wye.**
⚠ **Caution:**	**Logic signals are interruptible signals; these signals are removed when power is removed from the drive.**
⚠ **Caution:**	**Controls are intended to be connected to a permanent main power source, not a portable power source. Suitable fusing and circuit protection devices are required.**
⚠ **Caution:**	**The safe integration of the drive into a machine system is the responsibility of the machine designer. Be sure to comply with the local safety requirements at the place where the machine is to be used. In Europe this is the Machinery Directive, the ElectroMagnetic Compatibility Directive and the Low Voltage Directive. In the United States this is the National Electrical code and local codes.**
⚠ **Caution:**	**Controls must be installed inside an electrical cabinet that provides environmental control and protection. Installation information for the drive is provided in this manual. Motors and controlling devices that connect to the drive should have specifications compatible to the drive.**
⚠ **Caution:**	**Violent jamming (stopping) of the motor shaft during operation may damage the motor and control.**
⚠ **Caution:**	**Do not tin (solder) exposed wires. Solder contracts over time and may cause loose connections.**
⚠ **Caution:**	**Electrical components can be damaged by static electricity. Use ESD (electro-static discharge) procedures when handling this control.**
⚠ **Caution:**	**Ensure that resolver or encoder wires are properly connected. Incorrect installation may result in improper rotation or incorrect commutation.**
⚠ **Caution:**	**The holes in the top and bottom of the enclosure are for cable clamps. Be sure to use an M4 bolt 12mm in length. Longer bolts may short circuit the electrical components inside the control.**

Section 2
Product Overview

Overview

The DBSC product is designed to serve the needs of machine designers and manufacturers. Baldor products have both UL and CE approvals. The DBSC is a “flexible” versatile compact control for brushless servo motors. This digital servo control can be tailored to suit many applications. It can accept 0–10VDC input, standard ±10VDC input, current loop input, pulse and direction input or electronic handwheel input.

Some flexible options are CAN bus interface (for resolver feedback only), internal or external regen, or with customer provided 24VDC to maintain logic power.

The DBSC can be integrated with Baldors’ motion controllers or to any industry standard motion controller.

Motors

Baldor servo controls are compatible with many motors from Baldor and other manufacturers. Motor parameters are provided with the PC software making the setup easy. Baldor compatible motors include:

- BSM–A–Series motors
- BSM–B–Series motors
- BSM–F–Series motors
- BSM–N–Series motors

Refer to the Speed/Torque curves in the BR1202 catalog or contact your local Baldor distributor or sales representative for assistance with motor sizing and compatibility. Custom motors or motors not manufactured by Baldor may be used. Please contact your local Baldor distributor or sales representative for assistance.

Command Source

In the analog mode (current or velocity), the control requires a variable 0-10VDC or ±10VDC external analog signal. Suitable sources can be a PLC or motion controller.

Pulse and Direction

In the pulse and direction mode, two opto isolated inputs are provided for pulse input and direction input.

The software identifies the command source: A leads B or Pulse Follower.

Serial Communications Interface

A serial port allows external communication. This means that the DBSC can interface to a PC (for configuration and control) or to other user–supplied equipment such as:

- Host computers
- PLC’s
- PC’s
- Motion controllers

The serial communication interface supports:

- RS232 and the four wire RS–485 communication standards
- Baud rate: 9600

Control Inputs Opto isolated inputs are single ended, user selectable and active high or low:

Enable	CW Enable
Hold	CCW Enable
Fault Reset	Machine Input 1
Pulse	Machine Input 2
Direction	

Control Outputs

One normally closed relay contact provides a dedicated “Drive Ready” output.

Two opto isolated outputs are single ended, active low and are current sinking. Either output can be assigned to one of the following:

In Position	Machine Input 1
CW Warning	Machine Input 2
CCW Warning	I^2t Warning
Following Error Flag	Drive Over Temperature
Following Error Warning	

Simulated Encoder Output

Resolver Feedback

The resolver feedback signal is converted to PPR (pulses per revolution) by a Resolver to Digital Converter. A position controller uses position feedback

The resolution of the simulated encoder output is software controlled with the following available resolutions:

512 PPR, 1024 PPR, 2048 PPR or 4096 PPR

Note: For speeds above 6000 RPM, resolution is limited to 1024PPR maximum.

Encoder Feedback

When encoder feedback is used, the encoder input signal is buffered and provided at the simulated encoder output.

Section 3
Installation

Receiving & Inspection

Baldor Controls are thoroughly tested at the factory and carefully packaged for shipment. When you receive your control, there are several things you should do immediately.

1. Observe the condition of the shipping container and report any damage immediately to the commercial carrier that delivered your control.
2. Remove the control from the shipping container and remove all packing materials. The container and packing materials may be retained for future shipment.
3. Verify that the part number of the control you received is the same as the part number listed on your purchase order.
4. Inspect the control for external physical damage that may have been sustained during shipment and report any damage immediately to the commercial carrier that delivered your control.
5. If the control is to be stored for several weeks before use, be sure that it is stored in a location that conforms to published storage humidity and temperature specifications stated in this manual.

Location Considerations

The location of the control is important. Installation should be in an area that is protected from direct sunlight, corrosives, harmful gases or liquids, dust, metallic particles, and vibration. Exposure to these can reduce the operating life and degrade performance of the control.

Several other factors should be carefully evaluated when selecting a location for installation:

1. For effective cooling and maintenance, the control should be mounted on a smooth, non-flammable vertical surface.
2. At least 0.6 inches (15mm) top and bottom clearance must be provided for air flow. Refer to Section 7 for mounting dimensions.
3. **Altitude derating**. Up to 3300 feet (1000 meters) no derating required. Derate the continuous and peak output current by 1.1% for each 330 feet (100 meters) above 3300 feet.
4. **Temperature derating**. From 5°C to 40°C ambient no derating required. Above 40°C, derate the continuous and peak output current by 2.5% per °C above 40°C. Maximum ambient is 50°C.

Mechanical Installation

Mount the control to the mounting surface. The control must be securely fastened to the mounting surface by the control mounting holes. The location of the mounting holes is shown in Section 7 of this manual.

Electrical Installation

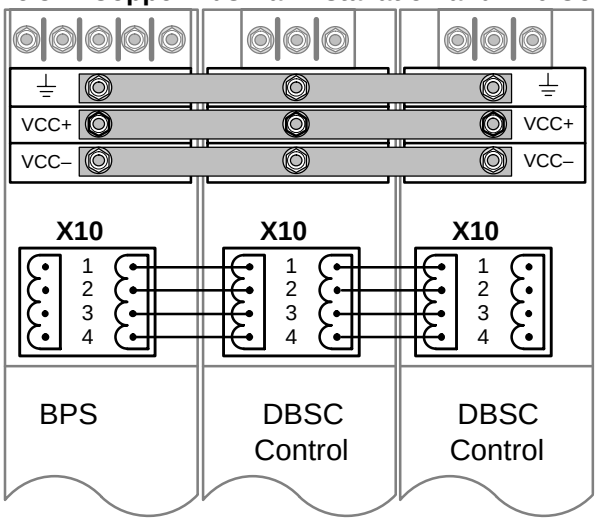
All interconnection wires between the control, AC power source, motor, host control and any operator interface stations should be in metal conduits. Use listed closed loop connectors that are of appropriate size for wire gauge being used. Connectors are to be installed using crimp tool specified by the manufacturer of the connector. Only class 1 wiring should be used.

Refer to MN1221 to connect AC power to the BPS (Baldor Power Supply). There are no AC power connections for the DBSC control.

VCC and X10 Connections

DC power connections are shown in Figure 3-1. Copper bus bars connect VCC+, VCC– and GND between each module from the BPS to the last control. X10 connections are daisy chained from the BPS to each control as shown in Figure 3-1.

Figure 3-1 Copper Bus Bar Installation and X10 Connections

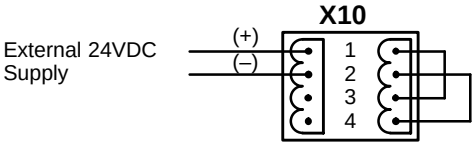


See Section 7 for correct bus bar length information.

See Terminal Tightening Torques in Section 7 of this manual.

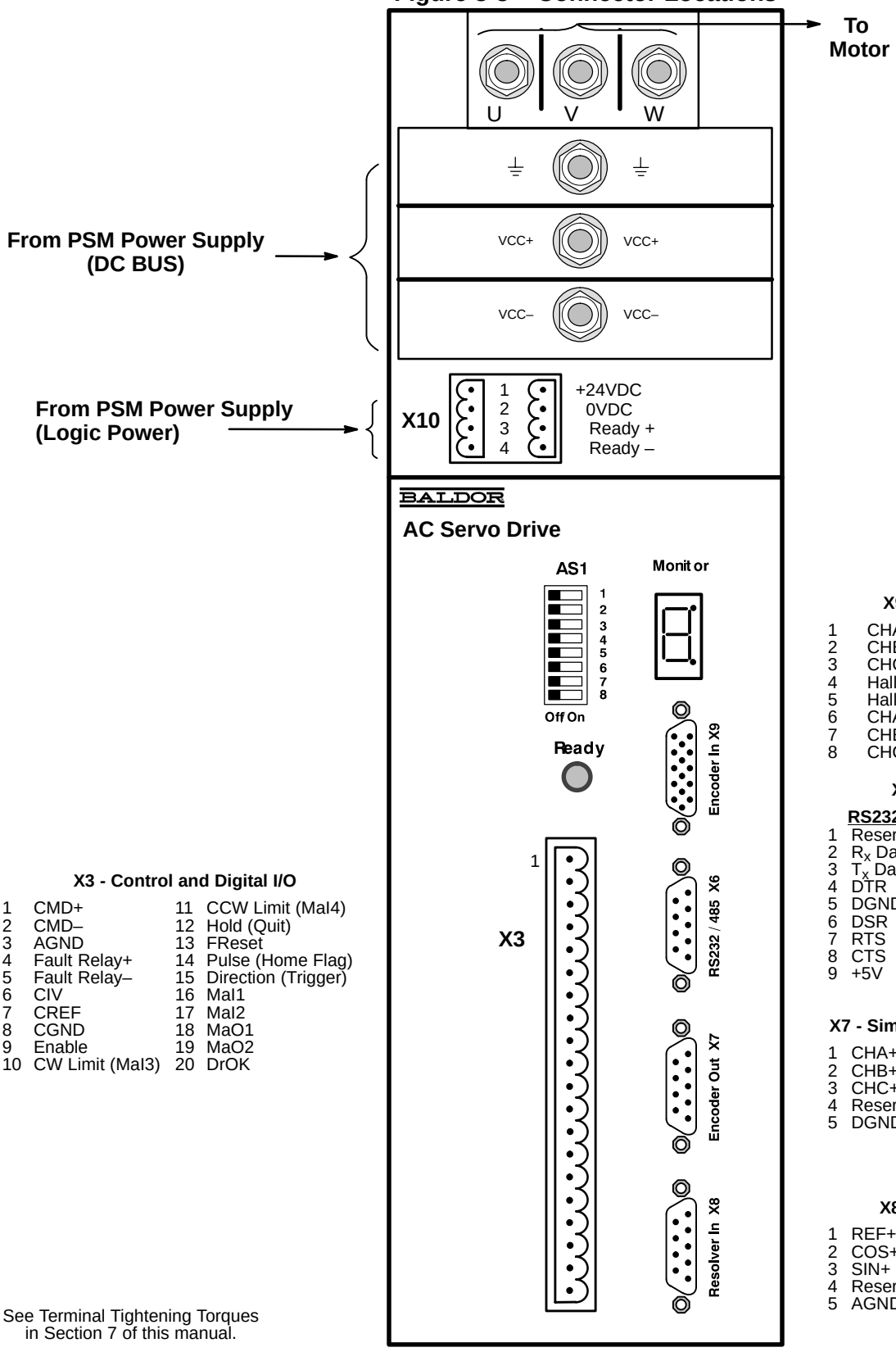
If an optional 24VDC power supply or battery backup is used, the connections to X10 must be made as shown in Figure 3-2. This allows position information and other memory related information to be stored when AC power is removed from the BPS.

Figure 3-2 External 24VDC connections



Jumpers must be installed to prevent a fault condition.

Figure 3-3 Connector Locations



X3 - Control and Digital I/O

1	CMD+	11	CCW Limit (MaI4)
2	CMD–	12	Hold (Quit)
3	AGND	13	FReset
4	Fault Relay+	14	Pulse (Home Flag)
5	Fault Relay–	15	Direction (Trigger)
6	CIV	16	MaI1
7	CREF	17	MaI2
8	CGND	18	MaO1
9	Enable	19	MaO2
10	CW Limit (MaI3)	20	DrOK

See Terminal Tightening Torques in Section 7 of this manual.

X9 - Encoder Input

1	CHA+	9	Hall 3+
2	CHB+	10	Hall 2+
3	CHC+	11	+5VDC
4	Hall 1+	12	N.C.
5	Hall 1–	13	DGND
6	CHA-	14	Hall 3–
7	CHB-	15	Hall 2–
8	CHC-		

X6 - RS232 / 485

	RS232		RS485
1	Reserved	1	TX-
2	R_X Data	2	TX+
3	T_X Data	3	RX+
4	DTR	4	RX-
5	DGND	5	DGND
6	DSR	6	RTS-
7	RTS	7	RTS+
8	CTS	8	CTS+
9	+5V	9	CTS-

X7 - Simulated Encoder Output

1	CHA+	6	CHA–
2	CHB+	7	CHB–
3	CHC+	8	CHC–
4	Reserved	9	Reserved
5	DGND		

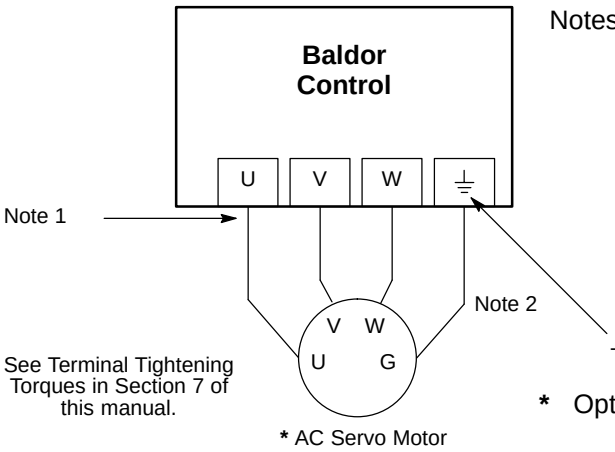
X8 - Resolver Input

1	REF+	6	REF–
2	COS+	7	COS–
3	SIN+	8	SIN–
4	Reserved	9	Reserved
5	AGND		

Motor Connections

Motor connections are shown in Figure 3-4. (Connections U, V and W are shown in Figure 3-3). If connected wrong, erratic operation including moves at peak force may occur until the overcurrent limit trips. This will result in a display of “7” and a “6” on the monitor. If erratic movement of the motor occurs, turn off power immediately and check the connections of the motor, hall sensors and encoder.

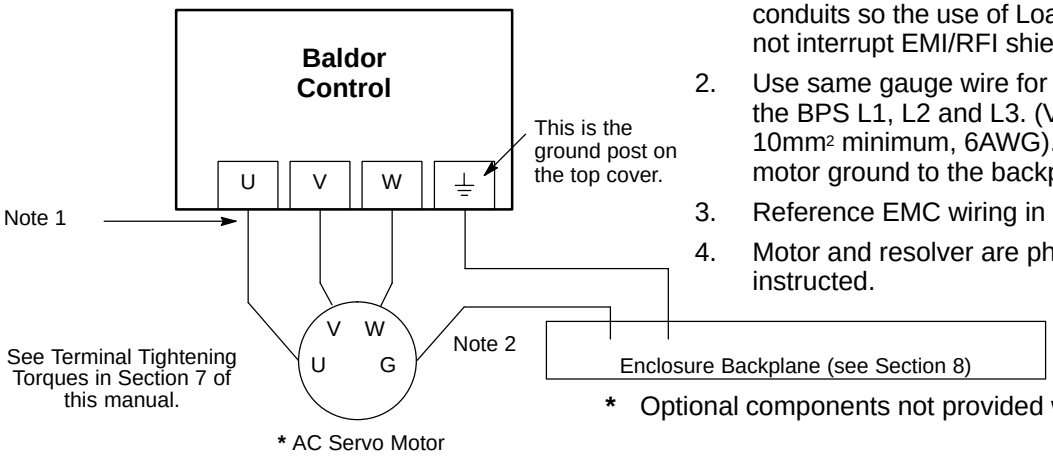
Figure 3-4 Motor Connections for U.L.



Notes:
1. Metal conduit or shielded cable should be used. Connect conduits so the use of Load Reactor* or RC Device* does not interrupt EMI/RFI shielding.
2. Use same gauge wire for Earth ground as is used for the BPS L1, L2 and L3. (VDE (Germany) requires 10mm^2 minimum, 6AWG). For CE compliance, connect motor ground to the backplane of the enclosure.
3. Reference EMC wiring in Section 8.
4. Motor and resolver are phase sensitive. Connect only as instructed.

* Optional components not provided with control.

Figure 3-5 Motor Connections for CE



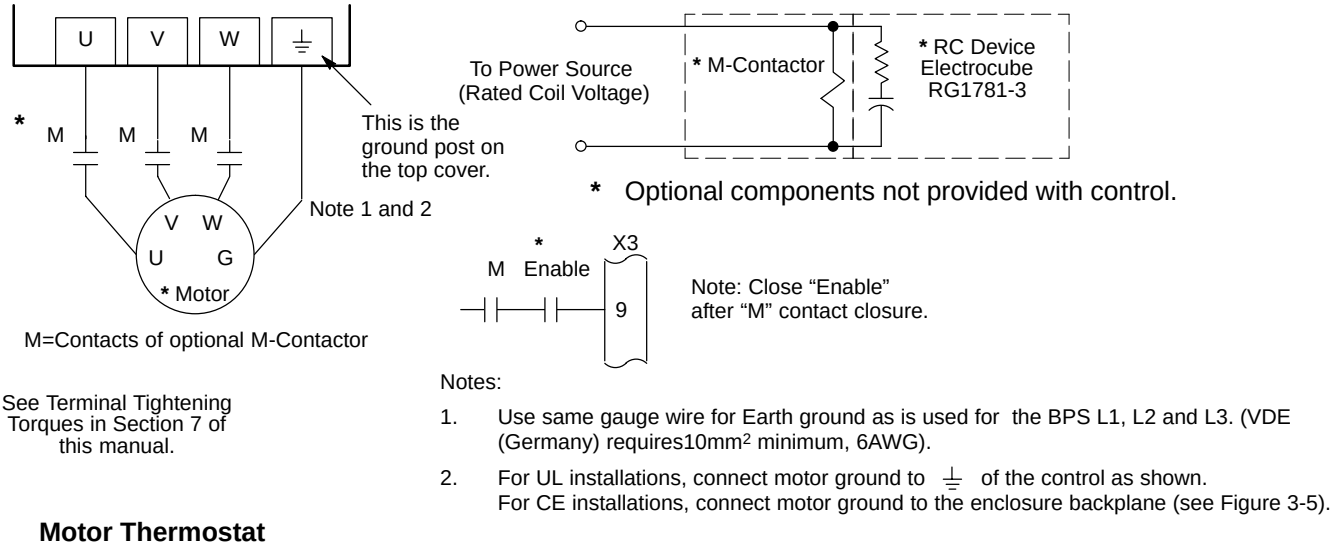
Notes:
1. Metal conduit or shielded cable should be used. Connect conduits so the use of Load Reactor* or RC Device* does not interrupt EMI/RFI shielding.
2. Use same gauge wire for Earth ground as is used for the BPS L1, L2 and L3. (VDE (Germany) requires 10mm^2 minimum, 6AWG). For CE compliance, connect motor ground to the backplane of the enclosure.
3. Reference EMC wiring in Section 8.
4. Motor and resolver are phase sensitive. Connect only as instructed.

* Optional components not provided with control.

Note: For CE compliant installations, connect unused leads within the motor cable to “PE” on both ends of the cable.

M-Contactor If required by local codes or for safety reasons, an M-Contactor (motor circuit contactor) may be installed. However, incorrect installation or failure of the M-contactor or wiring may damage the control. If an M-Contactor is installed, the control must be disabled for at least 20msec before the M-Contactor is opened or the control may be damaged. M-Contactor connections are shown in Figure 3-6.

Figure 3-6 Optional M-Contactor Connections



See Terminal Tightening Torques in Section 7 of this manual.

Notes:

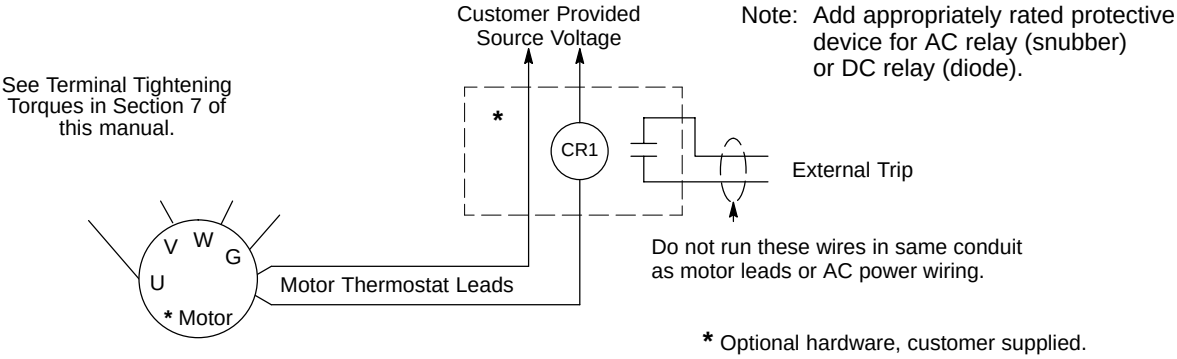
1. Use same gauge wire for Earth ground as is used for the BPS L1, L2 and L3. (VDE (Germany) requires10mm^2 minimum, 6AWG).
2. For UL installations, connect motor ground to ⏚ of the control as shown. For CE installations, connect motor ground to the enclosure backplane (see Figure 3-5).

Motor Thermostat

A relay contact can be used to isolate the motor thermostat leads for use with other devices, shown in Figure 3-7. The thermostat or overload relay should be a dry contact type with no power available from the contact. The optional relay (CR1) shown provides the isolation required and the N.O. contact is open when power is applied to the relay and the motor is cold. If the motor thermostat is tripped, CR1 is de-energized and the N.O. contact closes.

Connect the External Trip Input wires (N.O. relay contact) to a PLC or other device. Note that a machine input may be used and the PLC software of the DBSC control can define the thermal protection. Do not place these wires in the same conduit as the motor power leads.

Figure 3-7 Motor Temperature Relay



See Terminal Tightening Torques in Section 7 of this manual.

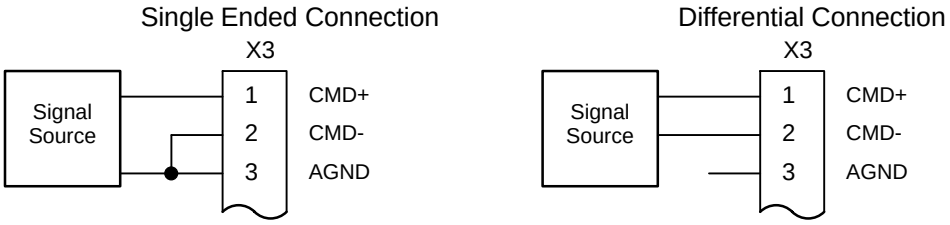
X1 Dynamic Brake Resistor An external DB (dynamic brake or regen resistor) resistor may be required to dissipate excess power from the DC bus during motor deceleration operations. For selection and installation of the DB resistor, refer to the specifications located in the BPS manual, MN1221.

Standard Control A control with standard Pulse & Direction feature (xxxW) – Level 1 in setup software

X3 Control Inputs & Digital I/O Connections

Control Inputs X3 pins 1 and 2 allows connection of an external analog command input. This input can accept a 0-10VDC or ±10VDC signal and can be wired as a single ended or differential input, shown in Figure 3-8.

Figure 3-8 Control Input Wiring



X3 Digital Inputs - Opto Isolated Inputs (**uses CREF, X3-7**)

Active High (Sourcing) - If pin X3-7 is grounded, an input is active when it is at +24VDC (+12VDC to +30VDC).

Active Low (Sinking) - If pin X3-7 is at +24VDC (+12VDC to +30VDC), an input is active when it is grounded.

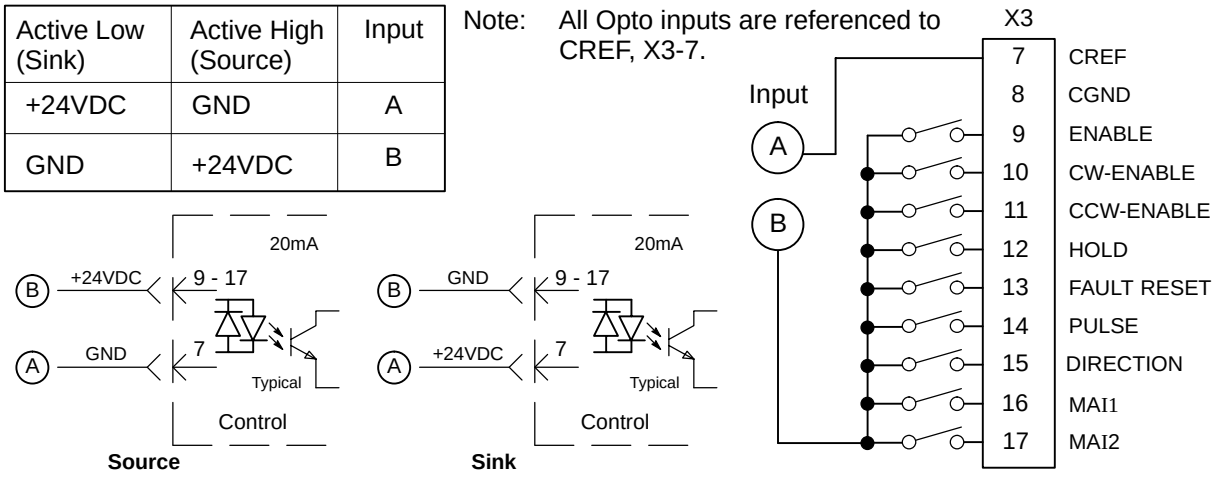
Logic input connections are made at terminal strip X3. Input connections can be wired as active High or active Low as shown in Figure 3-9. X3 pin 7 is the Control Reference point (CREF) for the Opto Isolated Input signals.

Note: An internal 24VDC power supply connection is not available from the control to power the Opto Input circuits. A customer provided external power source must be used as indicated in Figure 3-9.

Figure 3-9 Active HIGH /LOW Relationship

Active Low (Sink)	Active High (Source)	Input
+24VDC	GND	A
GND	+24VDC	B

Note: All Opto inputs are referenced to CREF, X3-7.



X3 Digital Inputs Continued

Table 3-1 Opto Input Signal Conditions

Pin Number	Signal Name	Switch = Closed (active)	Switch = Open (not active)
X3-9	Enable	Drive enabled.	Drive disabled.
X3-10	CW-Enable	Clockwise rotation enabled.	Clockwise rotation disabled.
X3-11	CCW-Enable	Counter-clockwise rotation enabled.	Counter-clockwise rotation disabled.
X3-12	Hold	HOLD function is active.	HOLD function is not active.
X3-13	Fault Reset	Fault Reset is active (reset control).	Fault Reset is not active.
X3-14	Pulse	See Pulse & Direction Definition.	See Pulse & Direction Definition.
X3-15	Direction	See Pulse & Direction Definition.	See Pulse & Direction Definition.
X3-16	MaI1	Machine Input 1 = Logical 1	Machine Input 1 = Logical 0
X3-17	MaI2	Machine Input 2 = Logical 1	Machine Input 2 = Logical 0

Signal Name **Opto Input Signal Definition**

Enable CLOSED allows normal operation.
OPEN disables the control and motor coasts to a stop.

CW-Enable CLOSED allows normal operation in the CW direction.
OPEN to disable CW rotation. The motor decels to a stop.

CCW-Enable CLOSED allows normal operation in the CCW direction.
OPEN to disable CCW rotation. The motor decels to a stop.

Hold CLOSED causes the motor to decelerate (at maximum deceleration rate) to rest and maintain a constant position (to prevent drift in velocity mode only).
OPEN allows normal operation.

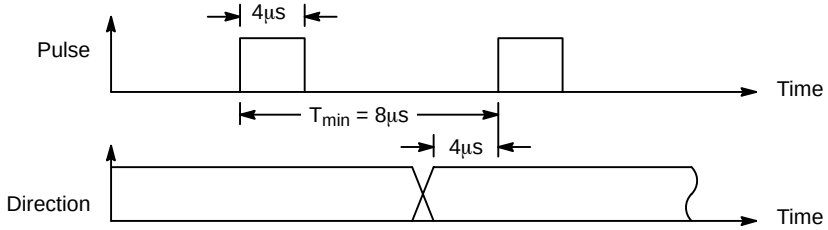
Fault Reset CLOSED allows the control to be cleared or “Reset” for any of the following four fault conditions (provided that the cause of the fault has been removed):

- Overvoltage
- Undervoltage
- Electronic Fusing
- Resolver Fault

OPEN allows normal operation.

Pulse & Direction The pulse and direction inputs allow the control to change speed and direction based on these signals. The frequency of the signal at the pulse input determines the motor velocity. The logic state of the signal applied at the direction input determines the direction of rotation (CW = 1; CCW = 0). The input voltage for both pulse and direction is 12 - 29VDC at 20mA.

Figure 3-10 Pulse & Direction Timing Diagram



MaI1 & 2 Two machine inputs are provided. These inputs can be used with the internal PLC software program. The internal PLC software can select up to three point–to–point moves based on the presence of MaI1 an MaI2.

4 Machine Input Version A control with 15 preset positions (xxxC) – Level 2 in setup software

X3 Digital Inputs - Opto Isolated Inputs (**uses CREF, X3-7**)

Active High (Sourcing) - If pin X3-7 is grounded, an input is active when it is at +24VDC (+12VDC to +30VDC).

Active Low (Sinking) - If pin X3-7 is at +24VDC (+12VDC to +30VDC), an input is active when it is grounded.

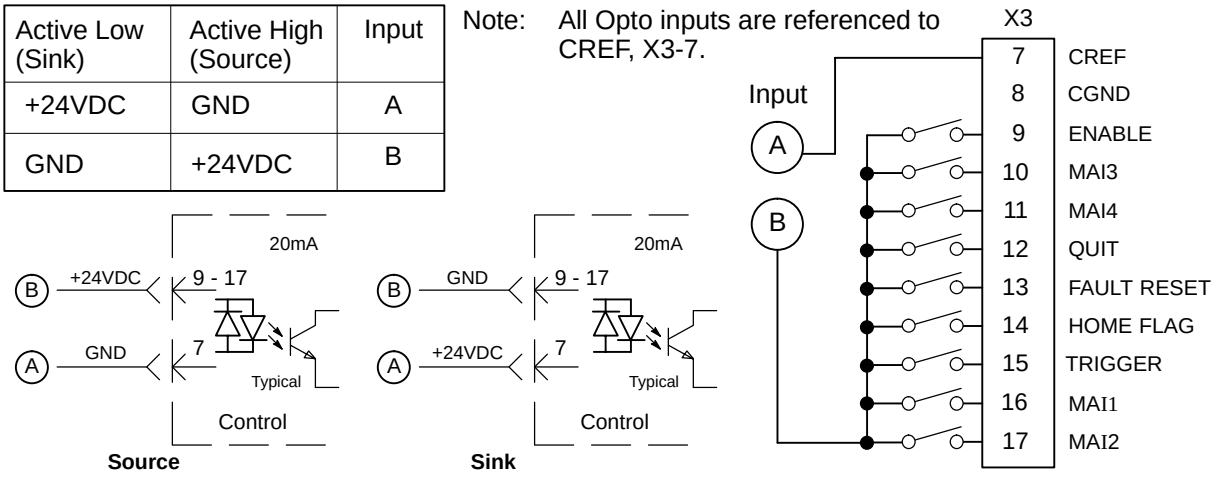
Logic input connections are made at terminal strip X3. Input connections can be wired as active High or active Low as shown in Figure 3-11. X3 pin 7 is the Control Reference point (CREF) for the Opto Isolated Input signals.

Note: An internal 24VDC power supply connection is not available from the control to power the Opto Input circuits. A customer provided external power source must be used as indicated in Figure 3-11.

Figure 3-11 Active HIGH /LOW Relationship

Active Low (Sink)	Active High (Source)	Input
+24VDC	GND	A
GND	+24VDC	B

Note: All Opto inputs are referenced to CREF, X3-7.



X3 Digital Inputs Continued

Table 3-2 Opto Input Signal Conditions

Pin Number	Signal Name	Switch = Closed (active)	Switch = Open (not active)
X3-9	Enable	Drive enabled.	Drive disabled.
X3-10	MaI3	Machine Input 3 = Logical 1	Machine Input 3 = Logical 0
X3-11	MaI4	Machine Input 4 = Logical 1	Machine Input 4 = Logical 0
X3-12	Quit	Stop positioning mode operation	Positioning mode is operating
X3-13	Fault Reset	Fault Reset is active (reset control).	Fault Reset is not active.
X3-14	Home Flag	Home flag = closing (rising) edge	Home flag = opening (falling) edge
X3-15	Trigger	Trigger = closing (rising) edge	Trigger = opening (trailing) edge
X3-16	MaI1	Machine Input 1 = Logical 1	Machine Input 1 = Logical 0
X3-17	MaI2	Machine Input 2 = Logical 1	Machine Input 2 = Logical 0

Signal Name **Opto Input Signal Definition**

Enable CLOSED allows normal operation.
OPEN disables the control and motor coasts to a stop.

Quit CLOSED cancels any move in progress and the motor will decelerate (at parameter MOT.ACC) to rest. This input is edge triggered.
OPEN allows position mode operation.

Fault Reset CLOSED allows the control to be cleared or “Reset” for any of the following four fault conditions (provided that the cause of the fault has been removed):

- Overvoltage
- Undervoltage
- Electronic Fusing
- Resolver Fault

OPEN allows normal operation.

Home Flag Edge triggered input that is used to sense the “Home Position”.

Trigger Rising edge triggered input that initiates a “point-to-point move”. The move is defined by the machine inputs MaI1 - 4.

MaI1,2,3,& 4 Four machine inputs are provided. These may be used with the internal PLC software program. The internal PLC software can cause an event to occur based on the presence of these inputs.

However, more often these inputs are used to define up to 15 preset positions or point to point moves. The 16th move is always home. With this method, it is not possible to use hardware limits (CW and CCW). Therefore, software limits must be used. Software limits are only active after a homing routine has completed.

Note: Hardware limit switches may be wired in series with the “Enable” input X3–9. Then if a limit is reached, the control will be disabled.

Figure 3-12 Positioning Mode Timing Diagram

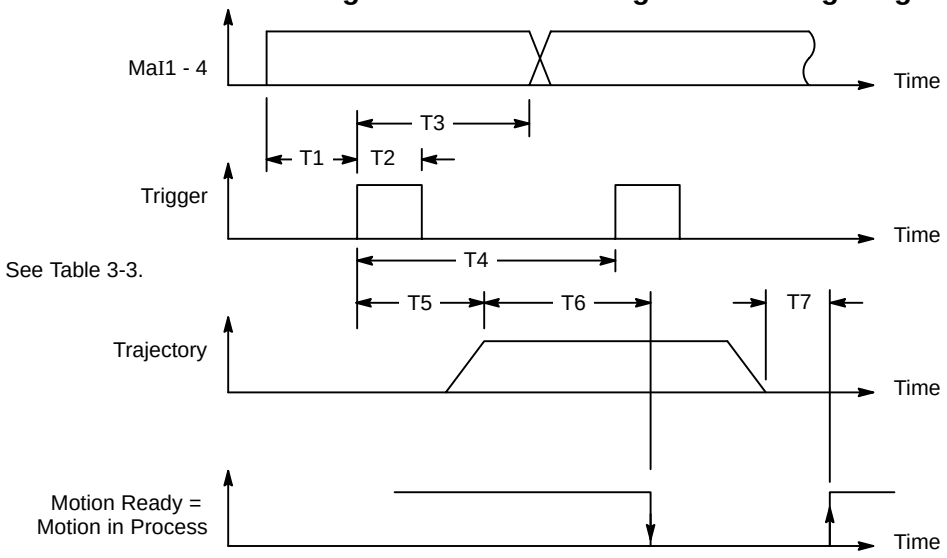
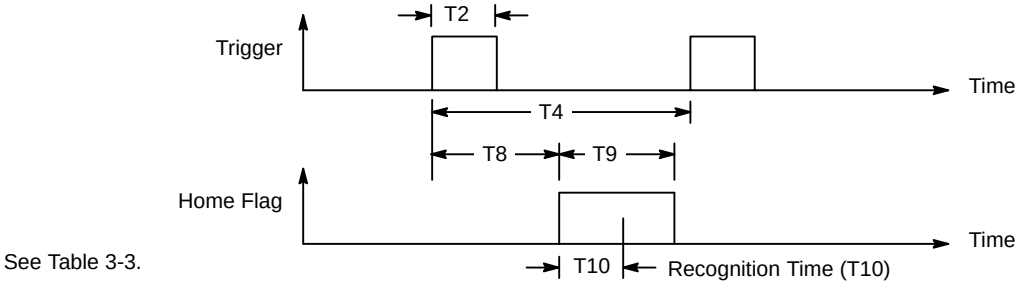


Table 3-3 Process Duration for Resolver and Encoder Feedback

Time	Resolver	Encoder
T1	≤1ms	≥2ms
T2	≥1.2µs	≥1ms
T3	≥28ms	≥14ms
T4	≥28ms	≥14ms
T5	≤10ms	≤14ms
T6	≤10ms	≤14ms
T7	≤10ms	≤14ms
T8	≥28ms	≥100ms
T9	≥1.2µs	≥2ms
T10	≥1.2µs	≥2ms

Figure 3-13 Homing Process Timing Diagram



X3 Digital Outputs - Opto Isolated Outputs

The control outputs are located on the X3 connector. A customer provided, external power supply must be used if digital outputs are to be used. The opto outputs provide status information and are not required for operation, Table 3-4.

Figure 3-14 Fault Relay Connections

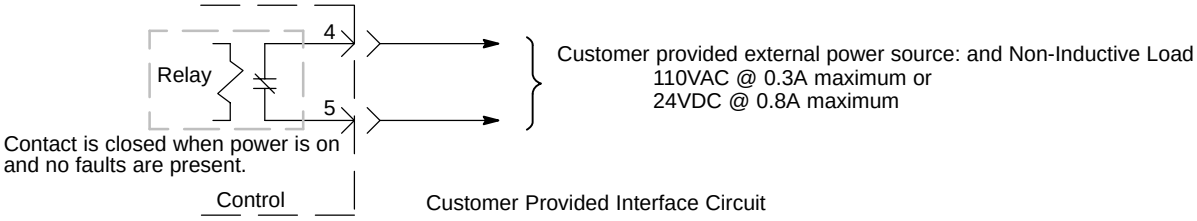


Figure 3-15 Opto Output Connections

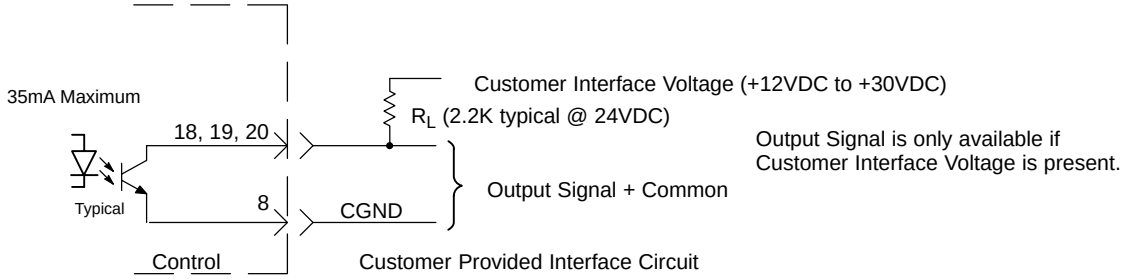


Table 3-4 Opto Output Signal Conditions

Pin Number	Signal Name	Switch = Closed (active)	Switch = Open (not active)
X3-4	Fault +	Drive OK - no faults detected	Fault is detected
X3-5	Fault -	Drive OK - no faults detected	Fault is detected
X3-18	MAO1	Machine Output 1 = Logical 1	Machine Output 1 = Logical 0
X3-19	MAO2	Machine Output 2 = Logical 1	Machine Output 2 = Logical 0
X3-20	DrOK	Drive OK - no faults detected	Fault is detected

Fault Relay A normally closed relay contact that opens if a fault occurs. The contact is rated: 24VDC @ 0.8A maximum or 110VAC @ 0.3A maximum.

MaO1 & 2 Two machine outputs are provided. Either output can be set to one of the following conditions: CW Warning, CCW Warning, In Position, Error Flag, Following Error Warning, MAI1-2, Drive Overtemperature or I^2T Warning.
Each output is rated 30VDC @ 35mA maximum.

DrOK This output is active when the control is ready for operation.
This output is rated 30VDC @ 35mA maximum.

RS232

A null modem cable (also called a modem eliminator cable) must be used to connect the control and the computer COM port. This will ensure that the transmit and receive lines are properly connected. Either a 9 pin or a 25 pin connector can be used at the computer, Figure 3-16. Maximum recommended length for RS232 cable is 3 ft. (1 meter).

Figure 3-16 9 & 25 Pin RS-232 Cable Connections for UL Installations

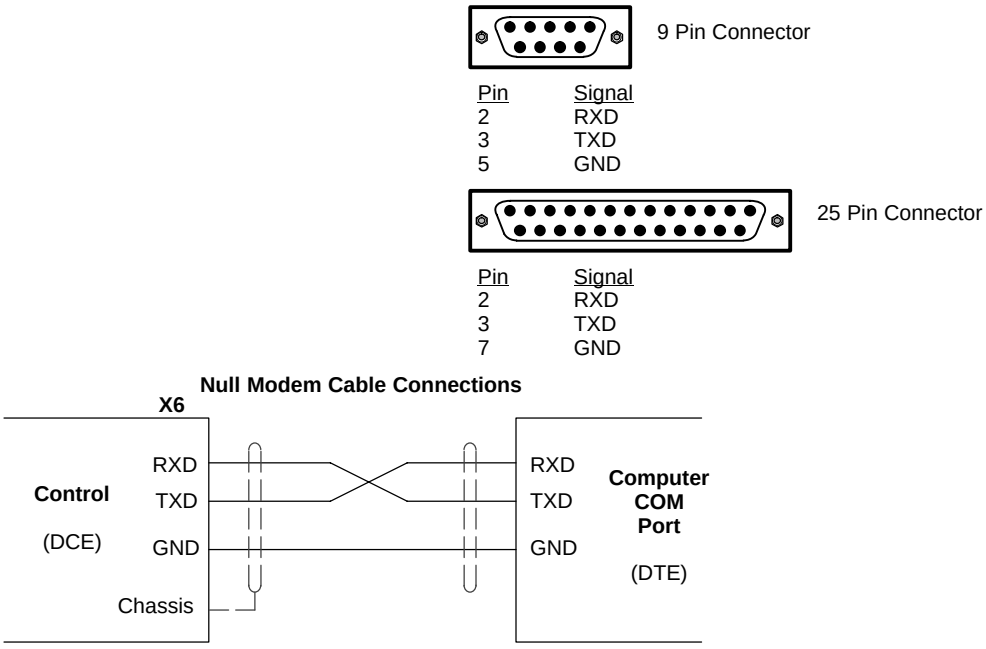
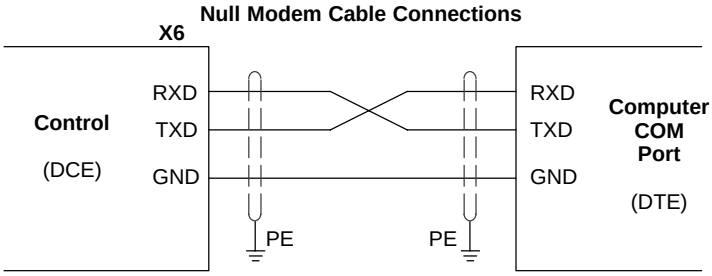


Figure 3-17 9 & 25 Pin RS-232 Cable Connections for CE Installations

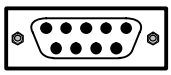


Note: For CE installations, connect the overall shield at each end of the cable to PE. The voltage potential between the PE points at each end of the cable must be Zero Volts.

RS485

Standard RS485 connections are shown in Figure 3-19. Maximum cable length is 3280 ft (1000M).

Figure 3-18 9 Pin RS-485 Cable Connections For UL Installations



9 Pin Connector

Pin	Signal
1	TX-
2	TX+
3	RX+
4	RX-
5	DGND

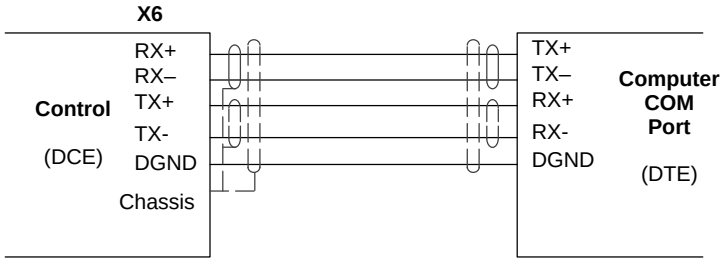
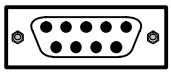
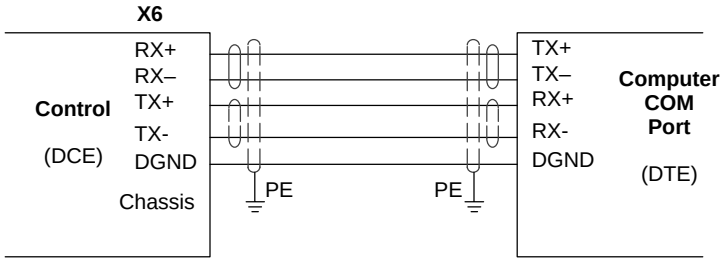


Figure 3-19 9 Pin RS-485 Cable Connections For CE Installations



9 Pin Connector

Pin	Signal
1	TX-
2	TX+
3	RX+
4	RX-
5	DGND



Note: For CE installations, connect the overall shield at each end of the cable to PE. The voltage potential between the PE points at each end of the cable must be Zero Volts.

RS485 Multi-Drop Connections

What does termination or a termination resistor do?

Termination resistance is used to match the impedance of the load to the impedance of the transmission line (cable) being used. Unmatched impedance causes the transmitted signal to not be fully absorbed by the load. This causes a portion of the signal to be reflected back into the transmission line (noise). If the *Source* impedance, *Transmission Line* impedance, and *Load* impedance are all equal, these reflections (noise) are eliminated.

Termination does increase load current and sometimes changes the bias requirements and increases the complexity of the system.

What is a termination resistor?

A resistor is added in parallel with the receiver input to match the impedance of the cable being used. Typically, the resistor value that is used is 100 ohm or 120 ohm. Resistors with 90 ohms or less should never be used.

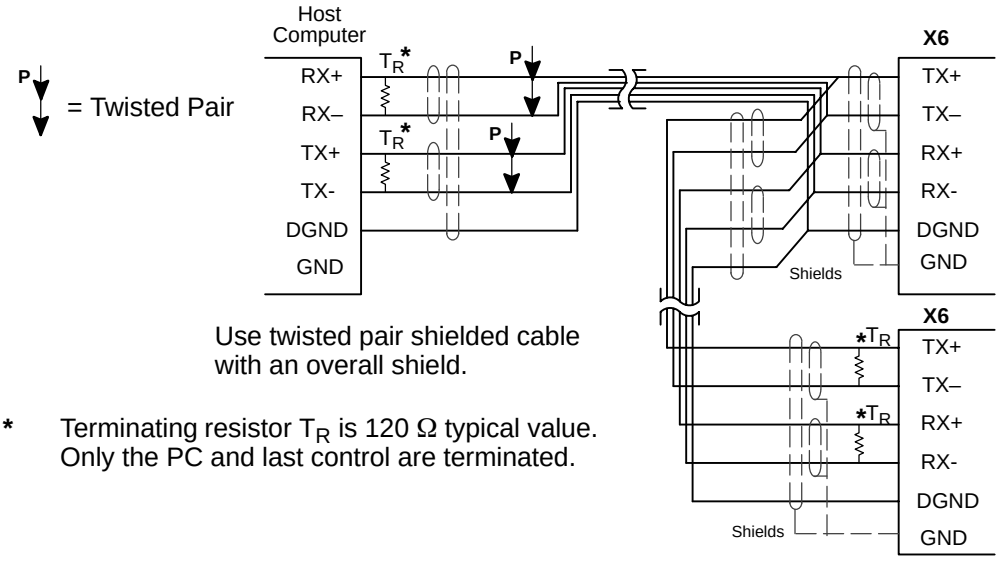
Where are these resistors placed?

Terminators or Termination resistors are placed in parallel with the receiver at both ends of a transmission line. This means that you should **never** have more than two terminators in the system (unless repeaters are being used).

How many resistors should my system have?

Terminators or Termination resistors are placed in parallel with the receiver at both ends of a transmission line. This means that you should **never** have more than two terminators in the system (unless repeaters are being used).

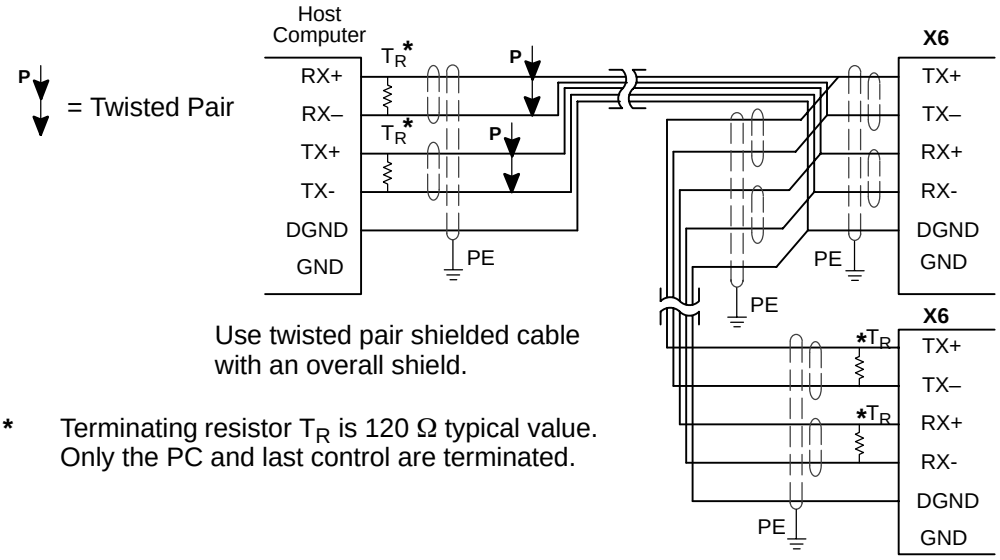
Figure 3-20 RS485 4 Wire Multi-Drop for UL Installations



Use twisted pair shielded cable with an overall shield.

* Terminating resistor T_R is 120 Ω typical value. Only the PC and last control are terminated.

Figure 3-21 RS485 4 Wire Multi-Drop for CE Installations



Use twisted pair shielded cable with an overall shield.

* Terminating resistor T_R is 120 Ω typical value. Only the PC and last control are terminated.

Note: For CE installations, connect the overall shield at each end of the cable to PE. The voltage potential between the PE points at each end of the cable must be Zero Volts.

See Section 4 of this manual for the description of switch “AS1-1 to AS1-4” for address settings for multi-drop applications.

X7 Simulated Encoder Output

The control provides a simulated encoder output at connector X7. This output may be used by external hardware to monitor the encoder signals. It is recommended that this output only drive one circuit load (RS422 interface – 28LS31 device). Refer to Table 3-5. The simulated Encoder Output is set to 512, 1024, 2048 or 4096ppr (pulses per revolution).

Table 3-5 Simulated Encoder Output at X7 Connector

X7 Pin	Signal Name
1	A+
2	B+
3	C+
4	Reserved
5	DGND
6	A–
7	B–
8	C–
9	Reserved
Shell	***** Chassis (Cable Shield)

***** For UL Installations ONLY. For CE Installations, connect the outer shield on each end of the cable to the enclosure backplane “PE”.

X8 Resolver Feedback The resolver connections are made at the X8 connector as shown in Figure 3-22. The resolver cable must be shielded twisted pair #22 AWG (0.34mm^2) wire minimum. The cable must also have an overall shield. Maximum wire-to-wire or wire-to-shield capacitance is 50pf per foot.

Resolver wiring must be separated from power wiring. Separate parallel runs of resolver and power cables by at least 3″. Cross power wires at right angles only. Insulate or tape ungrounded end of shields to prevent contact with other conductors or ground.

Note: Motor and resolver are phase sensitive. Connect only as instructed.

Figure 3-22 Resolver Cable Connections for UL Installations

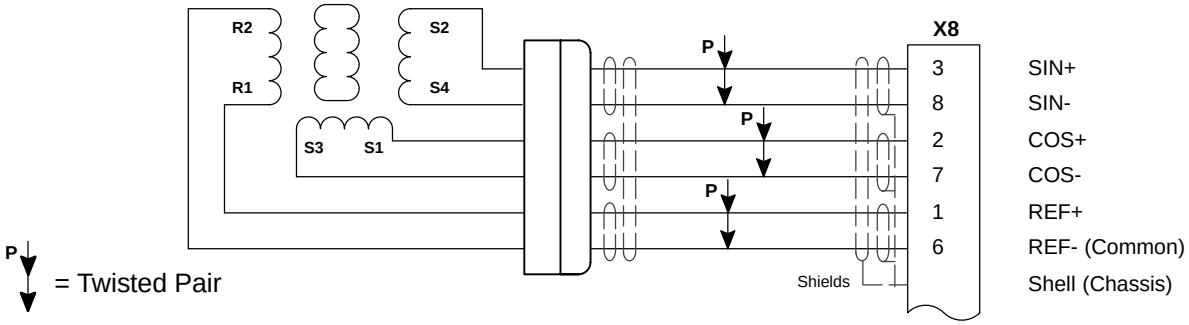
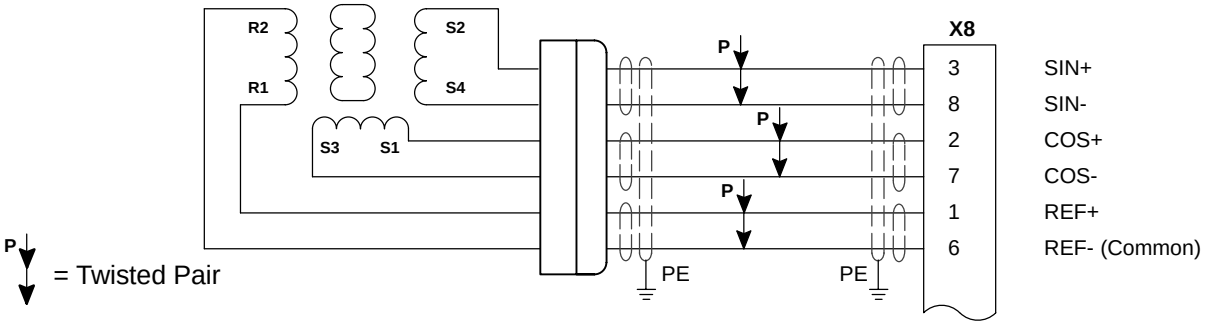


Figure 3-23 Resolver Cable Connections for CE Installations



X9 Handwheel (Encoder) Installation

Handwheel Mode (xAxx Models)

Twisted pair shielded wire with an overall shield should be used. Figure 3-24 shows the electrical connections between the encoder and the encoder connector.

Note: If the control was ordered with option Encoder/Hall feedback (catalog xBxx), it is not possible to connect the handwheel.

Figure 3-24 Differential Encoder Connections for UL Installations

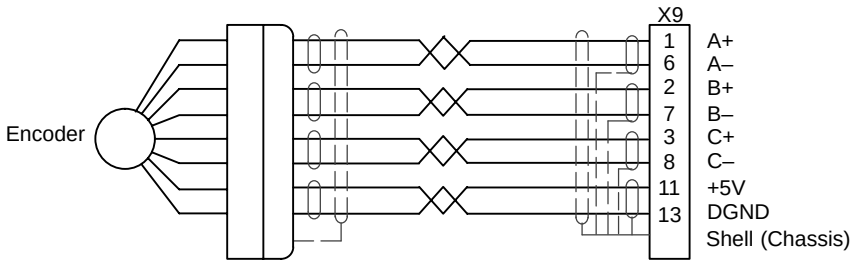
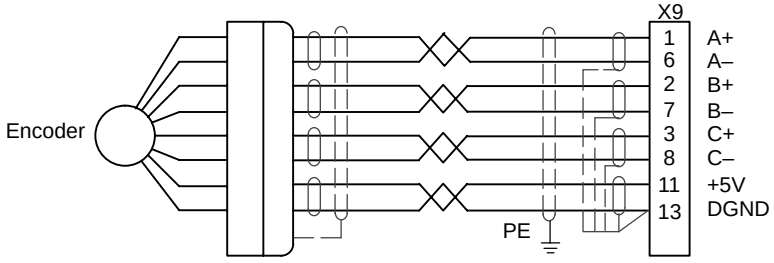


Figure 3-25 Differential Encoder Connections for CE Installations



Connection of shields to digital ground is optional.

X9 Encoder w/Hall Tracks Optional (**(xBxx Models)**)

Twisted pair shielded wire with an overall shield should be used. Figure 3-26 shows the electrical connections between the encoder and the encoder connector.

Note: If the control was ordered with option Encoder/Hall feedback (catalog xBxx), it is not possible to connect the handwheel.

Figure 3-26 Encoder with Hall Tracks Connections for UL Installations

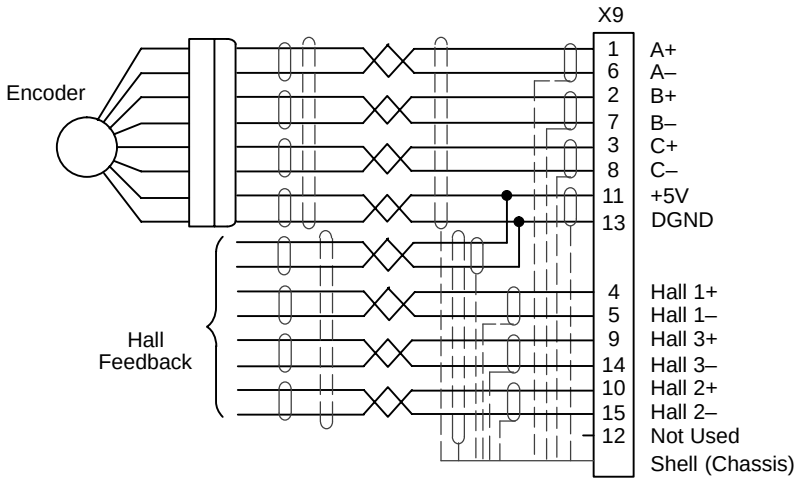
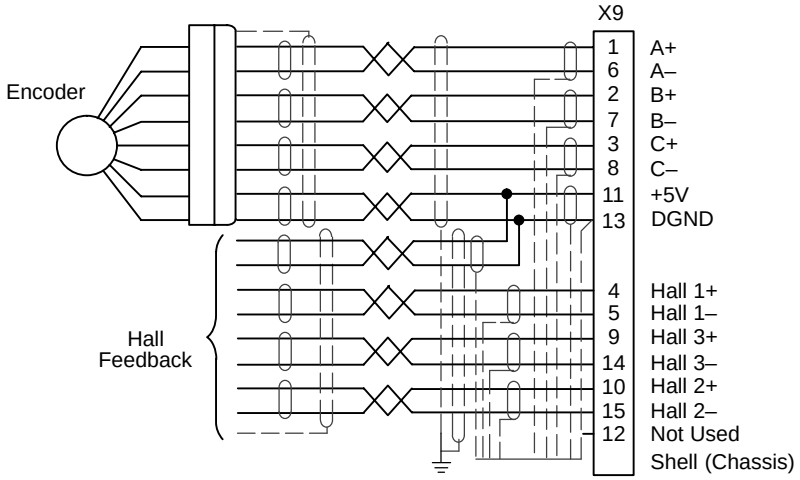
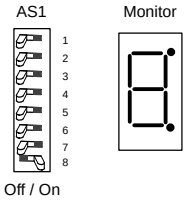


Figure 3-27 Encoder with Hall Tracks Connections for CE Installations



Section 4
Switch Setting and Start-Up

Switch AS1 Settings



AS1 switches are located on the front panel.

Note: AS1–8 is shown in the “ON” position (Drive Enabled). All other switches are shown in the “OFF” position.

Address Setting, AS1-1 to AS1-4 (for Multi-Drop Applications)

Each control address can be set using switches AS1-1 to AS1-4 of each control. Each control must have a unique address. Refer to Table 4-1.

Table 4-1 Control Address Setting

AS1-1	AS1-2	AS1-3	AS1-4	Control Address (Hexadecimal)
OFF	OFF	OFF	OFF	0 (Factory Setting)
ON	OFF	OFF	OFF	1
OFF	ON	OFF	OFF	2
ON	ON	OFF	OFF	3
OFF	OFF	ON	OFF	4
ON	OFF	ON	OFF	5
OFF	ON	ON	OFF	6
ON	ON	ON	OFF	7
OFF	OFF	OFF	ON	8
ON	OFF	OFF	ON	9
OFF	ON	OFF	ON	A
ON	ON	OFF	ON	B
OFF	OFF	ON	ON	C
ON	OFF	ON	ON	D
OFF	ON	ON	ON	E
ON	ON	ON	ON	F

Setting of switches AS1-5 to AS1-8

The function of switches AS1-5 to AS1-8 are described in Table 4-2.

Table 4-2 AS1-5 to AS1-8 Description

Switch	Function	ON	OFF
AS1-5	Not Used		
AS1-6	Hold-Position	Hold-Position is active.	Hold-Position is not active
AS1-7	Offset Tuning	Automatic Offset Tuning is active.	Automatic Offset Tuning is not active.
AS1-8	Enable	Control is enabled (Enable is active)	Control is disabled (Enable is not active)

Hold-Position

OFF allows normal operation.
ON causes the motor to quickly decelerate to rest and maintain a constant position (in current or velocity modes). (Deceleration time = 0 with the Hold function.) The Hold position mode can be activated by X3–12 input or by software.

Offset Tuning

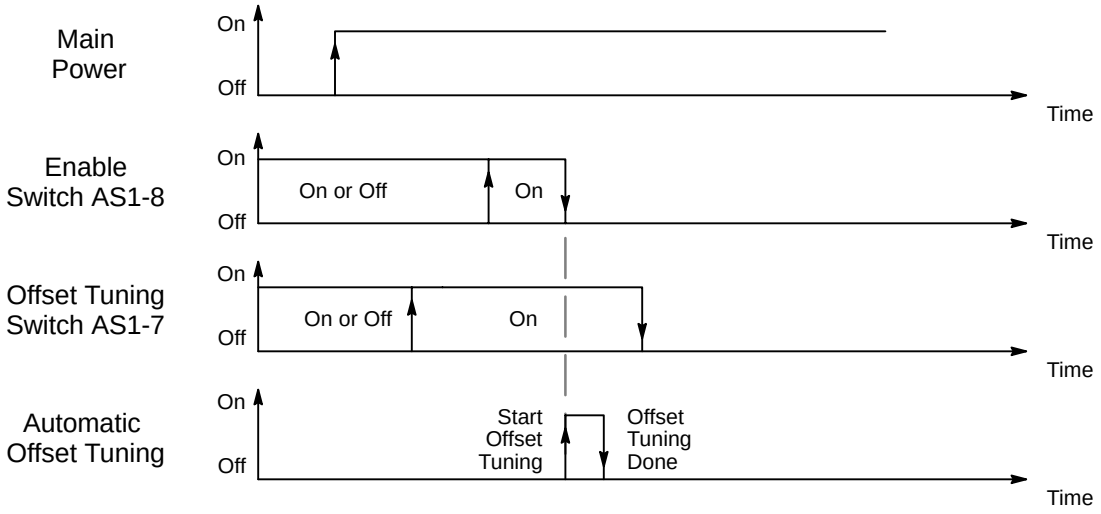
OFF allows normal operation.
ON causes Offset Tuning to automatically start the next time Enable is changed from ON to OFF. The purpose of Offset Tuning is to remove DC offset voltages (on the command input X3-1 and X3-2) and achieve a stationary motor shaft with 0VDC at the command input. Leave this switch OFF when not in use. See Figure 4-1 for additional information.

Enable

OFF disables the control and the motor coasts to a stop.
ON allows normal control operation if X3–9 enable input is closed.

Note: AS1-8 and X3-9 must both be enabled to allow control operation.

Figure 4-1 Automatic Offset Tuning Timing Diagram



Note: It is important that you set the analog command to 0VDC before the Automatic Offset Tuning is started.

Start-Up Procedure

Power Off Checks

Before you apply power, it is very important to verify the following:

1. Disconnect the load from the motor shaft until instructed to apply a load. If this cannot be done, disconnect the motor wires at X1-U, V and W.
2. Verify that switches AS1-5 to AS1-8 are set to OFF.
3. Verify the AC line voltage at the source matches the control rated voltage.
4. Inspect all power connections for accuracy, workmanship and tightness.
5. Verify that all wiring conforms to applicable codes.
6. Verify that the control and motor are properly grounded to earth ground.
7. Check all signal wiring for accuracy.

Power On Checks

When power is first applied, the “Monitor” LED display will show four indications if there is no failure found.

8. All segments and decimal point are on.

0 Display test.

1 Option number of test (1, 2 etc.).

d Final display with no decimal point (control disabled because AS1-8 = OFF).

Procedure:

1. Apply AC power.
2. Apply logic power (only if your control is equipped with this option).
3. The BPS “Ready” LED should be green.
4. The BPS “DB ON” LED should be OFF.
5. The control “Ready” LED should be green.
6. Verify the Monitor LED power on sequence. If “d” is displayed, continue otherwise disconnect AC power and refer to the Troubleshooting procedure.
7. Disconnect AC and logic power.
8. Connect the load to the motor shaft (or connect the motor wires at X1).
9. Apply AC and Logic Power (24VDC) if option is present.
10. Set switches AS1-7 and AS1-8 to ON.
11. Set switch AS1-8 to OFF (initiate offset tuning).
12. Set switch AS1-7 to OFF.
13. Configure the control using the Setup Software provided. Refer to Section 5 of this manual.
14. Set switch AS1-8 to ON and close X3–9, the decimal point should be ON.

Note: If control monitor displays “L”, check the limit switches (X3–10 and 11). If control monitor displays “d”, check the enable inputs at X3–9 and AS1–8.

15. Perform System Tuning.

The drive is now ready for use.

Note: To protect the internal fuse, allow at least 1 minute after power down before turning power on (power Off/On cycle).

Section 5
Operation

Installing Software on your PC

The setup software is Windows–based. The servo control connects to a serial port on your PC. The setup wizard will guide you through the necessary steps to set–up your servo control. Online–help to each topic is available.

Minimum system requirements

Hardware requirements (minimum):

Processor: Intel 80486 / 33 MHz

RAM: 8 MB

Hard Disk Space: 50 MB

Screen: 600 x 480 (minimum)

Recommended: Intel Pentium, 16 MB RAM, 133 MHz, 100 MB Free Space

Software requirements:

Operating system: Windows 3.1x (minimum)

Recommended: Win95 or Windows NT

Installation

The following procedure will install the setup software on your computer's hard disk:

1. Start Windows. Make sure that no other programs are running during this installation.
2. Place installation **Disk #1** in your computer's floppy drive.
3. Run A:\Setup.exe (if A:\ is your floppy drive) or double click the file **Setup.exe** from My computer, 3.5 inch Floppy (A:).
4. Follow the instructions and insert the other installation disks as required.

After the installation process is finished, a program manager group and a progman icon are created. Double clicking this icon will start the setup program.

A file "Readme.txt" is included in the master directory of the software. This file contains installation instructions, change notices from previous revisions and information that became available after this manual was printed.

Host Communications Setup

Be sure the communications port of the PC is correctly set for communications with the Drive software. The following examples assume COM1 of the PC is used. If you are using COM2 – 4, substitute the correct COM port number in the example.

Windows 3.1 Terminal Emulation

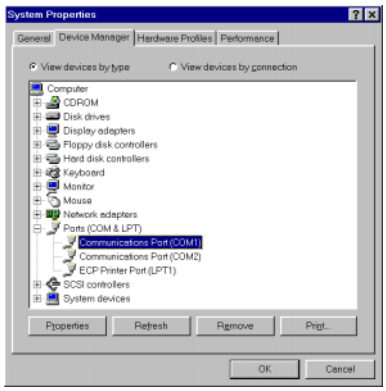
1. Power up the Host and start Windows software.
2. In the "Windows Accessories Group" select "Terminal" ICON.
3. Select "Communications" from the Settings pull down menu within Terminal program.
4. Set the communications settings for:
   9600 Baud rate
   8 Data Bits
   1 Stop Bit
   No Parity
   Xon/Xoff Flow Control
   COM1

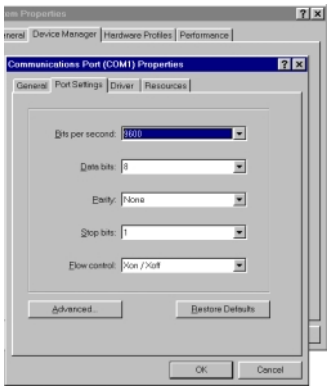
5. Select “Binary Transfers” from the Settings pull down menu within Terminal program.
6. Set the Binary Transfer protocol to XModem/CRC.
7. Close menu and save the settings.
8. Terminal Communications settings are now complete.

Windows 95

1. Power up the Host and start Windows software.
2. In “Control Panel” select and open “System”.
3. Open “Ports”, select the COM port you are using then click “properties”.

Figure 5-2



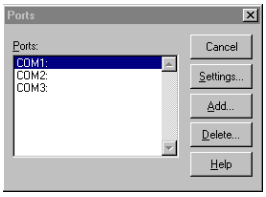


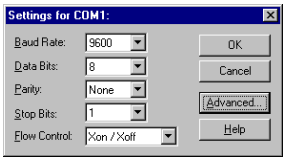
4. Be sure the port settings are as: Bits per second=9600, Data bits=8, Parity=none, Stop bits=1 and Flow control=Xon/Xoff.

Windows NT

1. Power up the Host and start Windows software.
2. In “Control Panel”, select and open “Ports” then click “Settings”.

Figure 5-3





3. Be sure the port settings are as: Bits per second=9600, Data bits=8, Parity=none, Stop bits=1 and Flow control=Xon/Xoff.

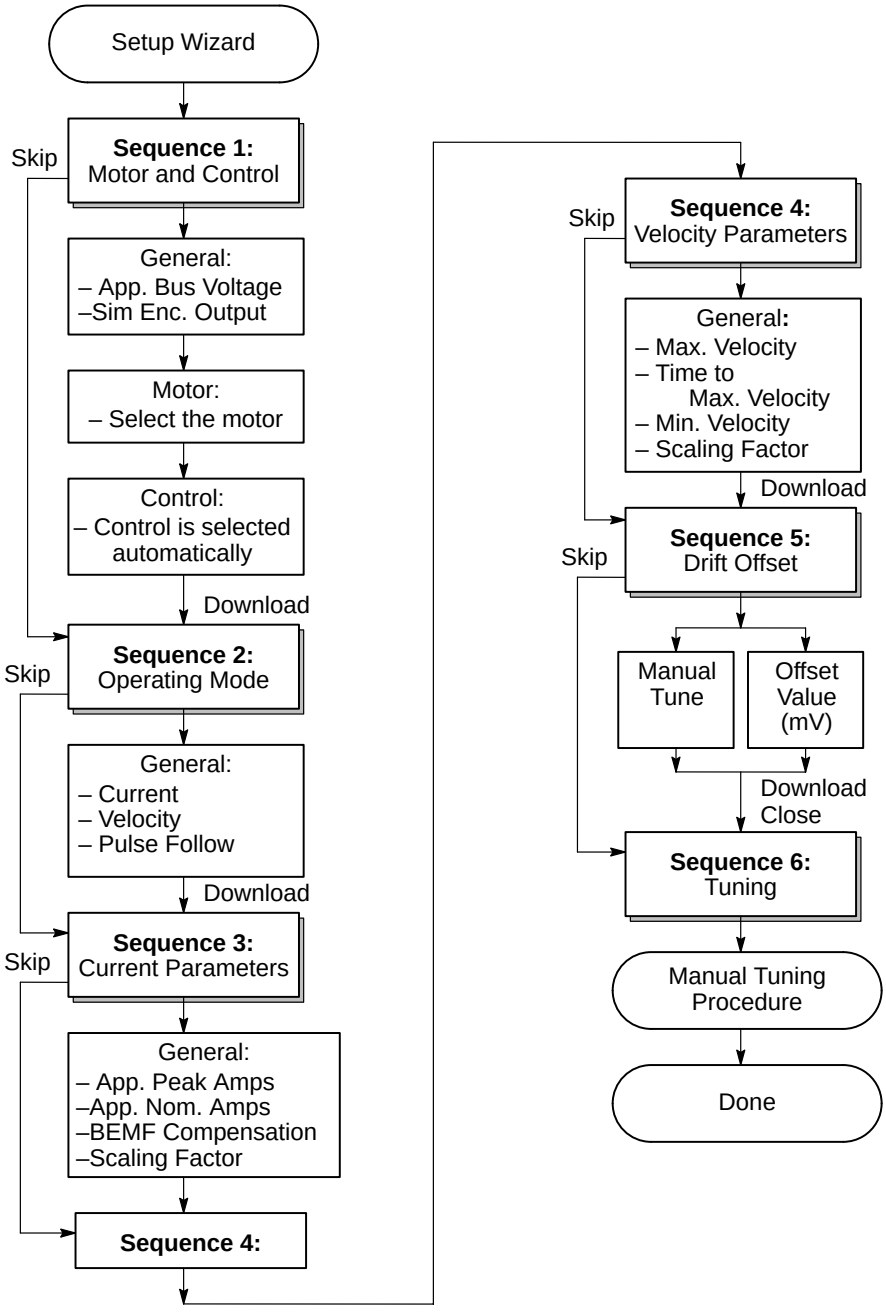
Using The Setup Wizard

The setup software wizard guides you through each step to set the basic parameters. This wizard is activated automatically after each start-up of the software. This automatic start of the Wizard can be turned off. It can be activated (and reset to automatic start) by Help → Wizard.

Figure 5-1 shows the flowchart of the Setup Wizard.

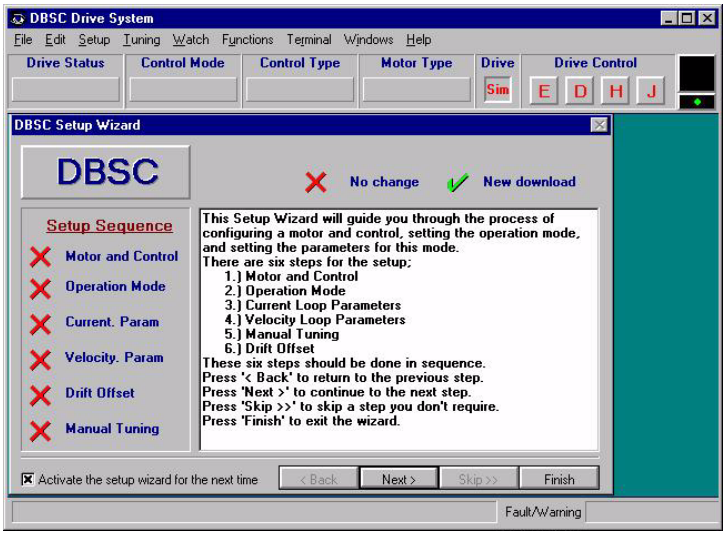
All selected parameters can be stored in a file. To save the configuration, select **Setup → Save Configuration**. To restore these parameter values or to configure a several controls with the same parameter sets, select the **Setup → Restore Configuration**.

Figure 5-1 Flowchart of the Setup Wizard

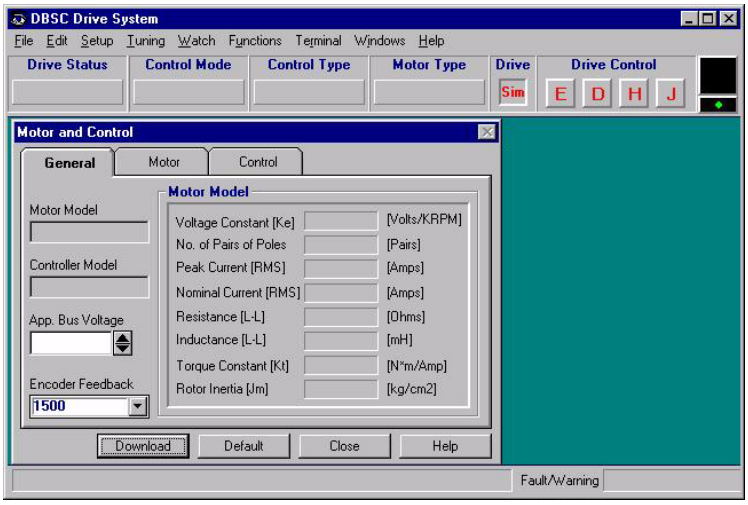


Set up Software

Opening menu. Click NEXT to go to the Set up Software. If you have already set up the parameters and saved them to a file, click FINISH then load the parameter file using the File → Open selection.



Start by selecting the Motor and Control and these parameters will be entered automatically for you by the software for a stock motor. For a custom motor, the motor parameters must be entered on the general menu. First, click on “Motor” and then select “User Models” in the Library menu. Then, click “General” to return to this menu and enter all parameters.

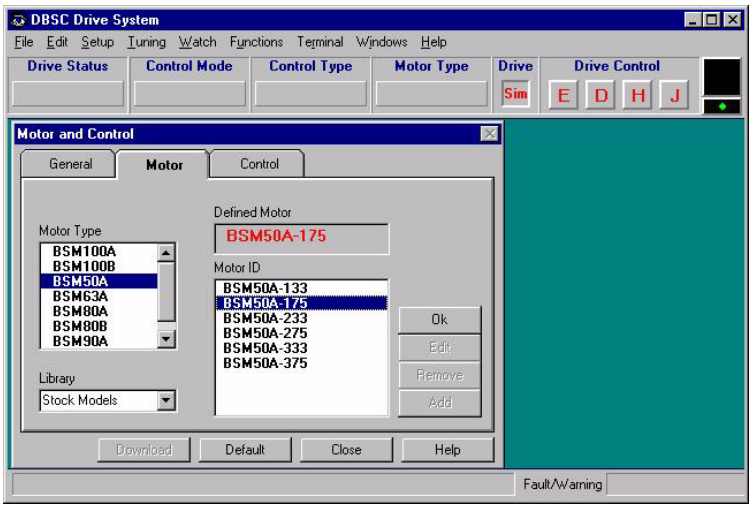


There are 7 parts to the setup procedure:

Motor

Select your motor from the list. First, select the general "Motor Type". Then select your specific "Motor ID". All of the parameters will be entered if your motor is on the list. If your motor is not on the list, you must define a motor and all of its parameters. If your motor is not listed, select "User Models" in the Library menu and enter the motor parameters. Click "Download" when finished.

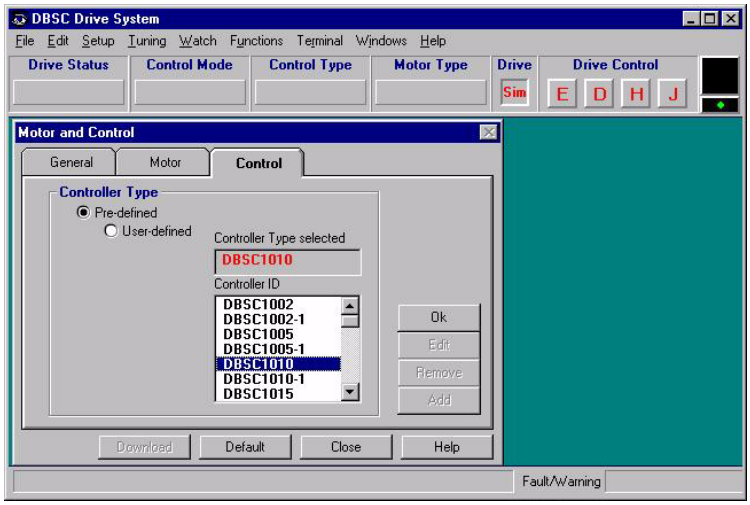
Figure 5-2 Motor Selection Screen



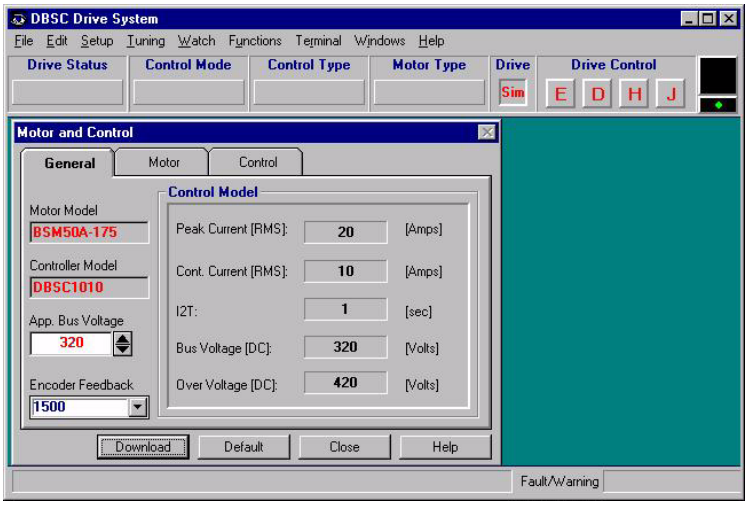
Control

The "Control ID" is automatically selected. All of the parameters will be entered if your control is on the list. Click "Download" when finished.

Figure 5-3 Control Selection Screen



After the motor and control are selected, click the General menu and note that the values are filed in.



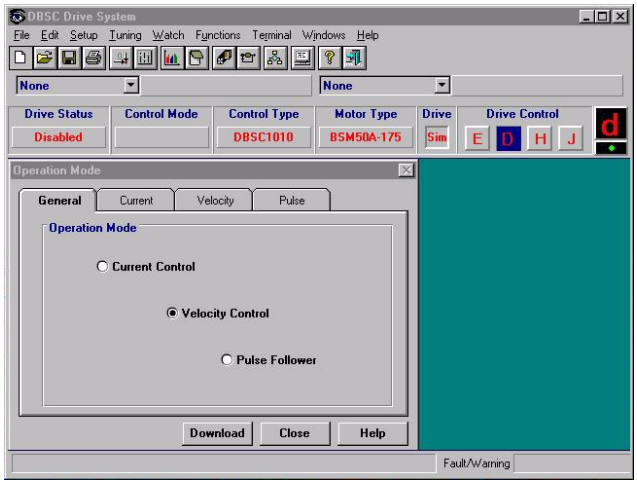
Operating Mode

Select the operating mode of the control. Choices are:

1. Current Mode.
2. Velocity Mode.
3. **Pulse** – Pulse Follower Mode (Pulse & direction or Electronic Handwheel) for Level 1 control option (xxxW).
   Positioning – Up to 15 preset positions (preset moves to target position) for Level 2 control option (xxxC).
4. Click “Download” when finished.

Note: If an encoder (feedback) is plugged into X9, the handwheel cannot be used. The handwheel feature can only be used with resolver feedback.

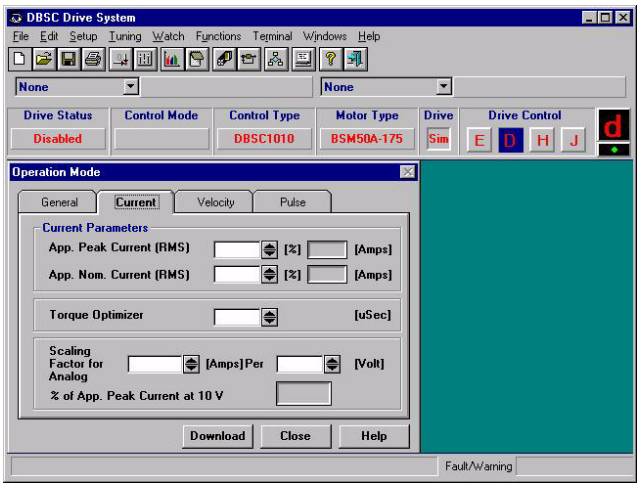
Figure 5-4 Operating Mode Selection Screen



Current Parameter

Nominal and peak current values are automatically entered for the motor type. For manual tuning only, set the control current limit value to a percentage of the continuous current rating. For example, if your control is rated for 5A continuous current and you desire to limit the output current to 4A, enter 80%. If you wish to use the full output power of the control, enter 100%. Click “Download” when finished.

Figure 5-5 Current Parameter Screen



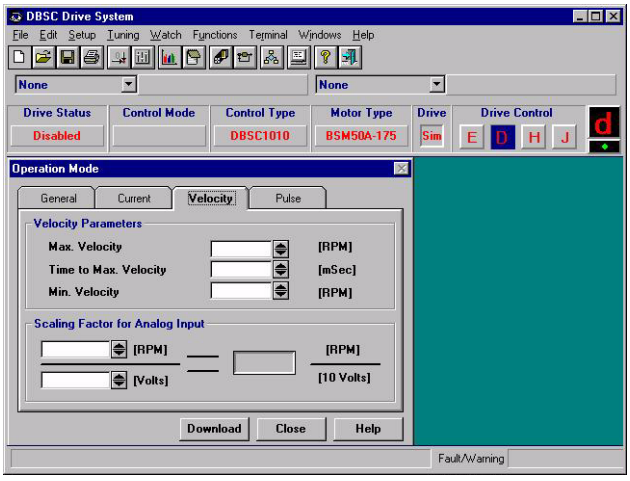
Velocity Parameter

Set the velocity parameters of the control:

1. Scale factor - ratio of the input voltage to output RPM.
2. Minimum velocity
3. Time to maximum velocity

   Click “Download” when finished.

Figure 5-6 Velocity Parameter Screen

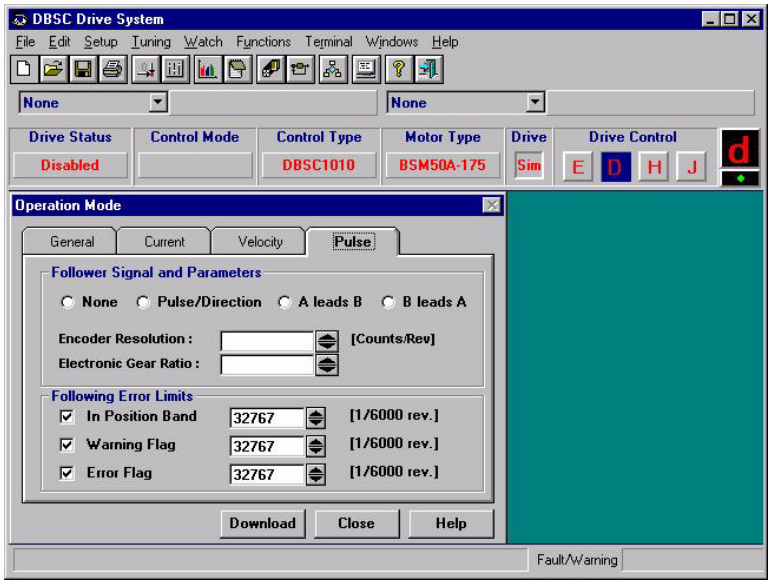


Pulse

Enter the parameter values for the Pulse Follower (hand wheel) mode. (Option xxxW).

1. Select the type of follower signal used.
2. Enter a value for Encoder Resolution (master encoder resolution in Counts/Rev).
3. Enter the desired electronic gear ratio. The sign (+ or –) is the tracking direction.
4. Enter the “Following Error Limits”.
5. Click “Download” when finished.

Figure 5-7 Pulse Parameter Screen

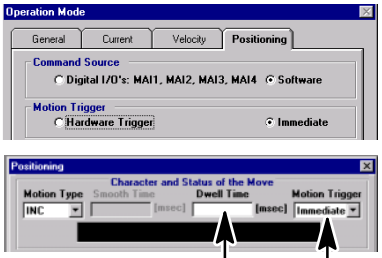


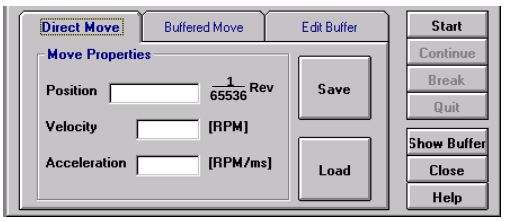
Positioning

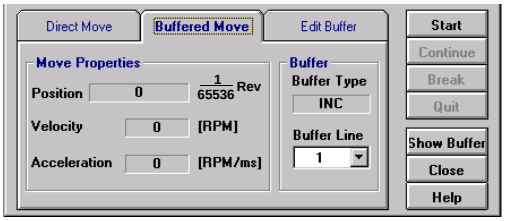
There are two ways to start a move: Software triggered or Hardware triggered. (Option xxxC).

Software Triggered

1. From the Main menu select “Setup ⇒ Operation Mode”.
2. Click on “Positioning Tab” and set Command Source to “Software”.
3. Set Motion Trigger to “Immediate” then click “Download” and “Close”.
4. From the Main menu select “Motion ⇒ Positioning”.
5. Set Motion Type to “INC” = Incremental or “ABS” = Absolute.
6. Set “Dwell Time” as desired (the wait time before the next move starts).
7. Set Motion Trigger to “Immediate”.
   Note: The Motion Trigger must be set to identical values in both of these positioning menus. Otherwise, problems will occur.
8. For Direct move, enter the position, velocity and acceleration parameters.
9. For Buffered move, select “Buffered Move” then select the buffer line number 1–15.
10. Click the Start button to begin (Quit button to stop).

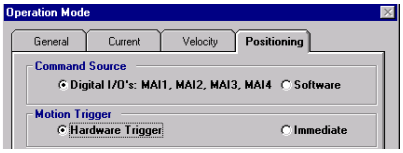






Hardware Triggered

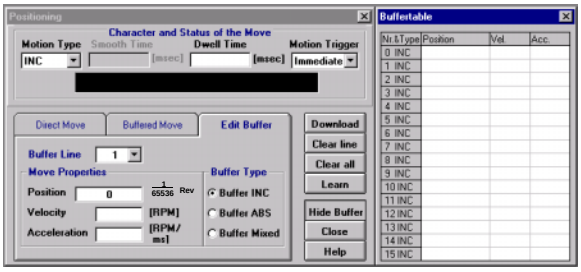
1. From the Main menu select “Setup ⇒ Operation Mode”.
2. Click on “Positioning Tab” and set Command Source to “Digital I/O’s”.
3. Set Motion Trigger to “HW Trig.” then click “Download” and “Close”.
4. From the Main menu select “Motion ⇒ Positioning”.
5. Set Motion Type to “INC” = Incremental or “ABS” = Absolute.
6. Set “Dwell Time” as desired (the wait time before the next move starts).
7. Set Motion Trigger to “HW Trig.”.
   Note: The Motion Trigger must be set to identical values in both of these positioning menus. Otherwise, problems will occur.
8. For a Direct move, enter position, velocity and acceleration parameters.
9. To start a direct move, the external trigger must be present at input X3 pin 15.
10. For a buffered move, the buffer line must be selected by MAI1–4.
11. After the buffer line is selected, the external trigger must be present at input X3 pin 15 to start the move.



Buffer	MAI4	MAI3	MAI2	MAI1
0	Open	Open	Open	Open
1	Open	Open	Open	Closed
2	Open	Open	Closed	Open
etc.				

Initialize Buffers

1. From the Main menu select “Motion ⇒ Positioning”.
2. Select “Edit Buffer”.
3. Set Motion Type, Dwell and Motion Trigger. (Software or Hardware Triggered).
4. If you want to see the buffer contents, click on “Show Buffer”.
5. Define up to 15 moves by selecting the Buffer Line number, then enter the position, velocity and acceleration for that move.
6. If you want the present absolute position to be stored in a buffer, select the buffer line number, then click “Learn”.
7. In the box “Edit Buffer” select the “Buffer Type” (INC = incremental, ABS = absolute or Mixed = absolute + incremental). Mixed is a combination of absolute and incremental. The position value in line 0 is an absolute position and is the reference position for the other buffer lines.



Example:

The position values in the buffer lines 2 .. 15 are incremental values.
e.g. Position value in Buffer line 1=1000, Buffer line 2=10.
If you start a move with buffer line one, the control stops the move when the position 1000 is reached.
If you start a move with buffer line two the control stops the move if the position 10 reached.
If you start an incremental move with buffer line 1, then buffer line 2 the control stops the move at position 1010.

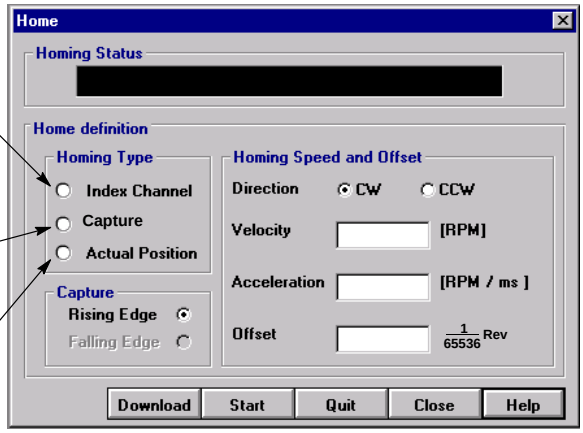
Home

Starts a search for the machines absolute zero position. When home is found, the control will hold the position at absolute zero. There are three Homing types: Index channel, Capture and Actual Position.

Index Channel causes the motor shaft to rotate to a predefined home position. The motor may rotate CW or CCW as specified by the user. Home is located when a machine mounted switch is activated, then the motor direction is reversed and continues until the “0” position of the resolver is detected (or the “C” channel of an encoder). The actual position of “Zero” relative to this point can be set by the user by changing the offset value.
If home flag is active, clear absolute revolution counter at position C. Set C (+ HOME.OFFSET) = Zero Position.
Brake with HOME.ACC to zero velocity. Move to Zero.

Capture is a more accurate way to define home position.
The home flag captures the closure of the machine mounted switch. This captured position (+ HOME.OFFSET) = Zero Position.
Brake with HOME.ACC to zero velocity. Move back to Zero.

Actual position sets the Zero position to the current position.
No movement required.



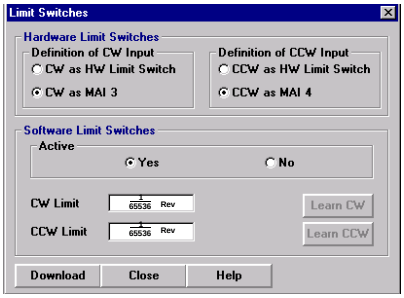
Procedure to define home position.

1. Be sure the machine mounted switch (Home position) is connected to X3 pin 14.
2. Select “Homing” from the Motion menu.
3. Choose the desired homing type.
4. Choose the desired capture edge (rising or falling).
5. Choose the desired home direction, CW or CCW.
6. Choose the desired home velocity, acceleration and offset parameters.
7. Click Download.
8. Click the Start button to begin the homing definition (Quit button to stop).
9. To start homing by hardware, buffer line 0 must be selected by MAI1–4.
10. To begin the home move, the external trigger must be present at input X3 pin 15.

Limit Switches

After Homing is set, the limit switches can be activated and set as desired. If the inputs at X3–10 and X3–11 are used for machine inputs, software limits can be used to sense when a position limit has been reached.

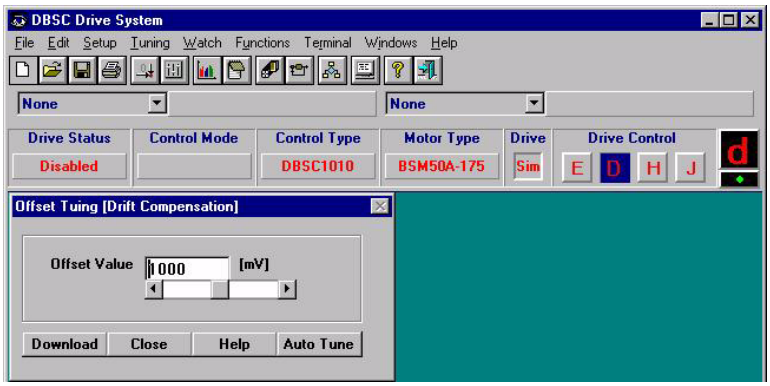
1. From the Main menu select “Setup ⇒ Limit Switches”.
2. Set “Hardware Limit Switches” as limits switches or as machine inputs.
3. Set the Software Limit Switches, “Active” to Yes or No. Yes activates a software switch when the position exceeds a predefined limit. No deactivates the software limit switch feature.
4. If software limit switches are set to Active = Yes, enter a position for the CW limit and a position for the CW limit.
   If you want to take the current absolute position as CW limit or CCW limit, click on “Learn CW” or “Learn CCW”. The ”Learn” function only works after a successful homing sequence.
5. Click ”Download” to send the parameters to the control.
   Note: The value for the CW limit must be greater than the CCW limit value.



Drift

If you know the input offset value of the control, you may enter the value manually. Otherwise, you may initiate automatic offset tuning and let the control measure and set this value. Click “Download” when finished.

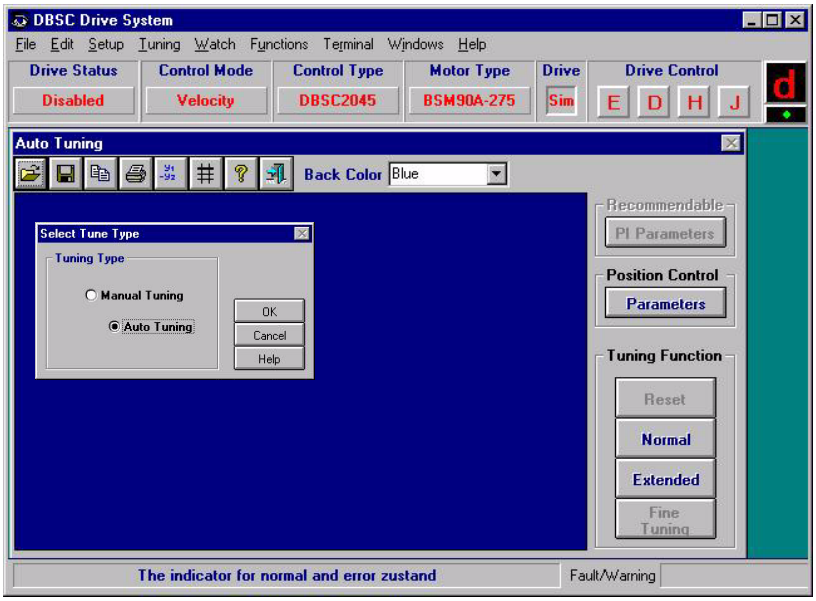
Figure 5-8 Drift Parameter Screen



Autotune

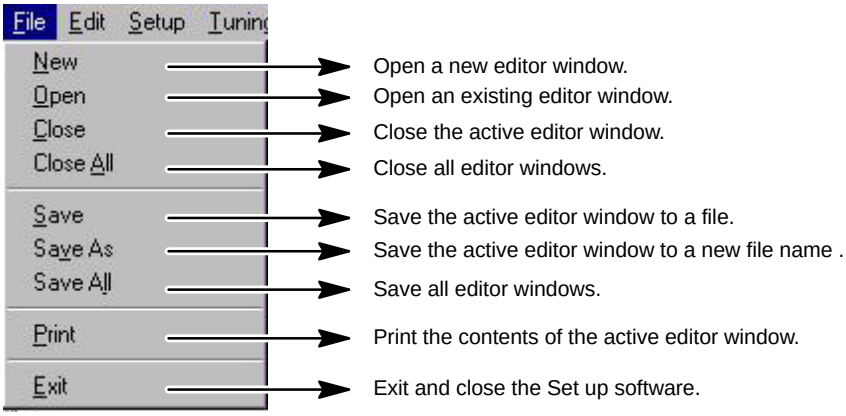
You may select autotune or manual tuning (described in Appendix A).

Figure 5-9 Autotune Screen



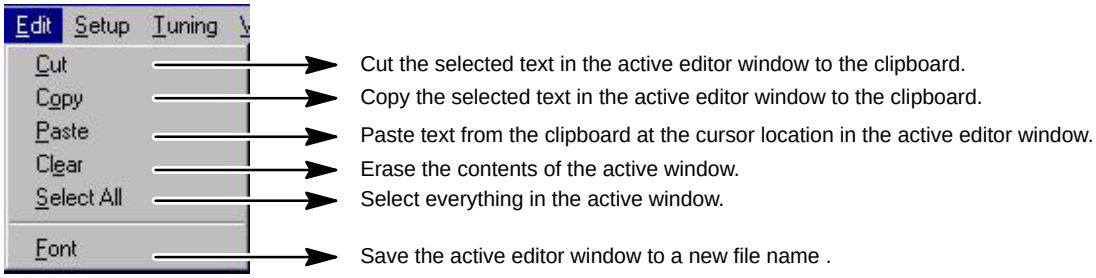
Main Menu Choice Descriptions

File



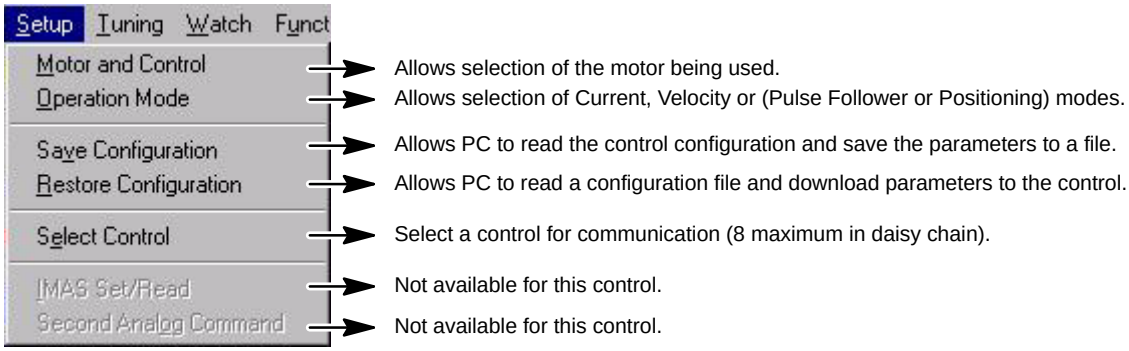
- New — Open a new editor window.
- Open — Open an existing editor window.
- Close — Close the active editor window.
- Close All — Close all editor windows.
- Save — Save the active editor window to a file.
- Save As — Save the active editor window to a new file name .
- Save All — Save all editor windows.
- Print — Print the contents of the active editor window.
- Exit — Exit and close the Set up software.

Edit



- Cut — Cut the selected text in the active editor window to the clipboard.
- Copy — Copy the selected text in the active editor window to the clipboard.
- Paste — Paste text from the clipboard at the cursor location in the active editor window.
- Clear — Erase the contents of the active window.
- Select All — Select everything in the active window.
- Font — Save the active editor window to a new file name .

Setup



- Motor and Control — Allows selection of the motor being used.
- Operation Mode — Allows selection of Current, Velocity or (Pulse Follower or Positioning) modes.
- Save Configuration — Allows PC to read the control configuration and save the parameters to a file.
- Restore Configuration — Allows PC to read a configuration file and download parameters to the control.
- Select Control — Select a control for communication (8 maximum in daisy chain).
- IMAS Set/Read — Not available for this control.
- Second Analog Command — Not available for this control.

Tuning

Allows manual or automatic tuning to remove offset drift.

Allows manual or automatic tuning of velocity control parameters.

Watch

Show or hide the “symbols list bar”.

Show or hide the “system parameters bar”.

Show or hide the “system status bar”.

Gather and plot motor data for two variables.

View the error log.

View the available options for the selected control.

Functions

Enable the control.

Disable the control – Active: Motor decels to stop then control disables.
Passive: Motor coasts to stop.

Cause motor to stop and maintain position.

Allow you to Jog the position of the motor.

Define up to 12 PLC statements (logical association of input / output conditions).

Terminal

Allows communication with selected control using command set (see Appendix B).

Configure PC COM port 1, 2, 3 or 4 to communicate with the selected control.

Windows

Cascade display of all open software windows.

Tile display of all open software windows.

Help

Alphabetic glossary listing of keywords.

Search for help based on a keyword.

Get help for a specific topic.

Starts the setup wizard to configure a motor and control.

Software version and release information.

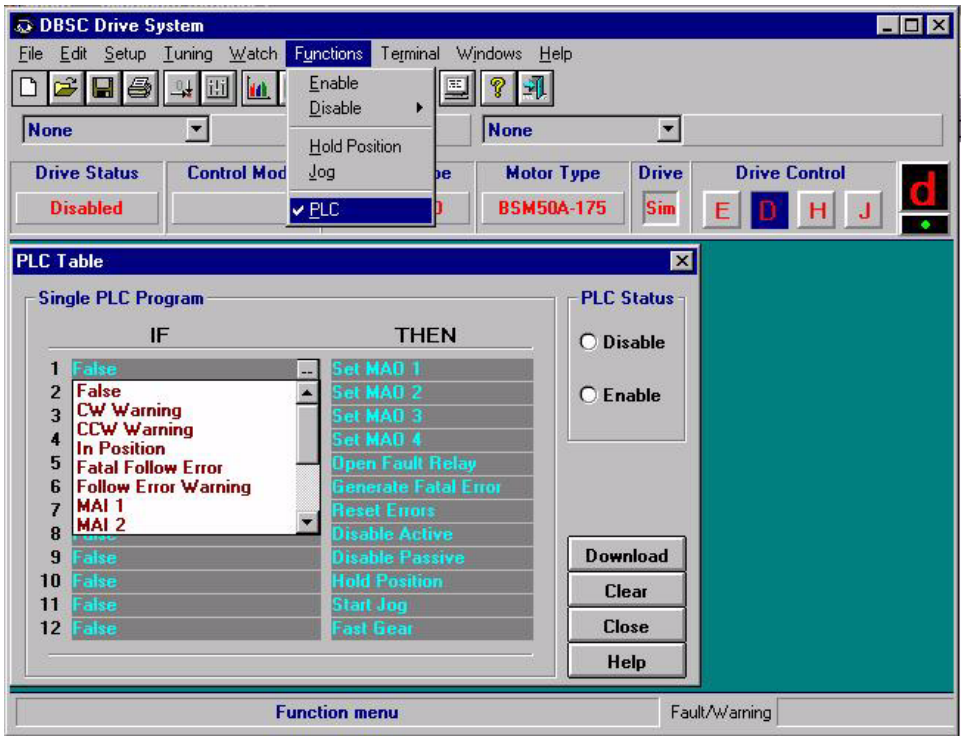
PLC Program

At the main menu, select “Functions” then “PLC”. See Figure 5-10.

1. Determine which event (listed under the THEN column) you wish to use.
2. Next, click in the IF column on the same ROW as the desired event. For example, If you are to use the MAO1 output, click in row 1 in the IF column as shown.
3. Choose the condition for the desired event.
4. Set other event conditions as desired.
5. Activate the PLC by selecting “Enable” on PLC Status.
6. Select “Download” to update the parameter values in the control.
7. Select “Close” when finished.

Note: To reset all IF conditions to False, select “Clear” located just below the Download selection. This will clear all condition choices.

Figure 5-10 PLC Program Menu



Section 6
Troubleshooting

Overview

The DBSC Control requires very little maintenance and should provide years of trouble free operation when installed and applied correctly. Occasional visual inspection and cleaning should be considered to ensure tight wiring connections and to remove dust, dirt, or foreign debris which can reduce heat dissipation.

Operational failures called “Faults” will be displayed as they occur. A comprehensive list of these faults, their meaning and related information is provided in this section.

Before attempting to service this equipment, all input power should be removed to avoid the possibility of electrical shock. The servicing of this equipment should be handled by a qualified electrical service technician experienced in the area of high power electronics.

It is important to familiarize yourself with the following information before attempting any troubleshooting or service of the control. Most troubleshooting can be performed using only a digital voltmeter having an input impedance exceeding 1 megohm. In some cases, an oscilloscope with 5 MHZ minimum bandwidth may be useful. Before consulting the factory, check that all power and control wiring is correct and installed per the recommendations given in this manual.

BPS Troubleshooting Procedure

BPS LEDs’

The system troubleshooting procedures involves observing the status of the “Ready” LED, the “DB On” LED and the “Monitor” 7 segment display. Table 6-1 provides information related to the indications provided by these devices.

The DB LED is on whenever Dynamic Brake power is dissipated into the optional DB (Dynamic Brake) resistor.

Display Identification

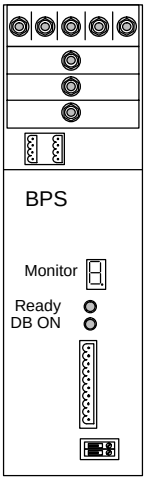


Table 6-1 Operating Mode Indications

Ready	Monitor	Status
OFF	OFF	BPS is powered off
Green	Decimal Point	Normal operation, no faults
OFF	0	Logic supply power loss
OFF	1	Logic supply undervoltage
OFF	2	Bus undervoltage
OFF	3	Loss of one or more AC power phases (L1, L2, L3)
OFF	4	Overtemperature
OFF	5	Dynamic brake fault
OFF	6	Reduced voltage starting feature is active and input AC power (L1, L2, L3) (or Bus voltage) is too high
Green	L	Reduced voltage starting feature is active

BPS Ready LED

The “Ready” LED is located on the panel. If a BPS fault occurs, the Ready LED will be OFF. All controls connected to that BPS are disabled.

BPS “DB ON” LED

The DB LED is located on the panel. The DB LED is on (green) whenever Dynamic Brake power is dissipated into the DB (Dynamic Brake) resistor. The DB resistor is also called a Regen resistor.

Control Troubleshooting Procedure

Table 6-2 Status Indications

Ready	Monitor	Status	Cause
OFF	OFF	BPS is powered off	No fault
Green	OFF	Control is disabled	No fault
Green	Decimal Point	Normal operation, control is enabled	No fault
Red	1	Bus over voltage	Damaged or missing regen resistor
Red	2	BPS Ready signal missing	Problem in BPS or X10 wiring
Red	3	Overcurrent (exceeded 2X Peak Current value)	Power stage fault or shorted motor leads
Red	4	Internal 15VDC supply fault	Under or over voltage condition of internal supply
Red	5	Resolver fault	Check Resolver or cable (X8) connections
Red	6	Electronic fusing (also see fault 7)	Control current over-load detected by software.
Red	7	I^2t limit reached. After a fault is detected, control will run at nominal output current for 2.4 seconds then stop. The control is disabled and the Monitor will first display “7” fault then the “6” fault. Control Over-Temperature	Cycle time between Acceleration and Deceleration is too short. Control should be relocated to cooler area. Add fans or air conditioning to control cabinet.
Red	8	Reserved	No fault
Red	9	RAM or EPROM error Fault Relay Activated (optional)	Internal control card fault. Reset control (turn off AC power, wait 1 minute then turn power on). Close X3–13 (fault reset) or reset control (turn off AC power, wait 1 minute then turn power on).
Red	0	Processor “Watchdog” timeout	Reset control (turn off AC power, wait 1 minute then turn power on).

Table 6-3 Operation Mode Indications

Ready	Monitor	Indication	Corrective Action
Green	–	Burn–in (– moving from top to bottom)	Control is in Burn–in mode which can only be set by software.
Green	⌊ ⌉	Move Command not accepted.	More than two move commands have been sent to the control. To return to normal status, send a “Quit” or a new move command to the control. A non-initialized buffer line has been called by the Machine inputs. To return to normal status, call an initialized buffer line by MA1-4 or send a “Quit” to the control. During the dwell time this symbol may appear if positioning is triggered by the hardware.
Green	–l	CW limit switch active	If limit switch is not activated, check wiring or switch. No fault.
Green	l–	CCW limit switch active	If limit switch is not activated, check wiring or switch. No fault.
Red	A	EEPROM checksum error.	The personality must be downloaded to EEPROM and reset the control. If problem remains, contact Baldor.
Red	c	Velocity data in the EEPROM failed.	The velocity data must be downloaded to EEPROM and reset the control. If problem remains, contact Baldor.
Green	C	CAN bus problem detected.	(“C” blinking) A communication error on the CAN bus exists. The control is still connected to the CAN bus.
Red	C	CAN bus problem detected.	(“C” blinking) A communication error on the CAN bus exists. The control will attempt resynchronization to establish the CAN bus.
Green	d	Control disabled.	Disable mode activated by hardware or software. No fault.
Green	E	Following Error.	The following error exceeded the user defined value of the Following Error Band. This error is not stored and goes away when the following error is reduced to within limits.
Green	F	Fatal Following Error.	The following error exceeded the user defined value defined in “Operation Mode→Pulse Follower” or “Operation Mode→Tracking” or “Operation Mode→Positioning” This error is stored and must be cleared by the operator, but operation continues as long as the error is less than $\pm 2^{15}$ ($\pm$32768).

Table 6-3 Operation Mode Indications Continued

Ready	Monitor	Indication	Corrective Action
Green	H	Hold-Position mode.	Hold mode activated by hardware (X3–12) or software. No fault.
Green	J	Jog mode.	Jog mode activated by hardware or software. No fault.
Red	L	Both limit switches active.	Defective or missing limit switch or wiring.
Green	P	In Position.	The following error is less than the user defined preset value. No fault.
Red	U	EPROM version fault.	The personality must be downloaded to EEPROM and reset the control.
Red	u	EEPROM version fault.	The personality must be downloaded to EEPROM and reset the control.

It is important to connect the motor leads U, V and W correctly at the X1 connector of the control. Incorrect wiring can cause erratic operation including moves at peak force until the overcurrent limit trips. This will result in a display of “7” and a “6” on the monitor. If erratic movement of the motor occurs, turn off power immediately and check the connections of the motor, hall sensors and encoder.

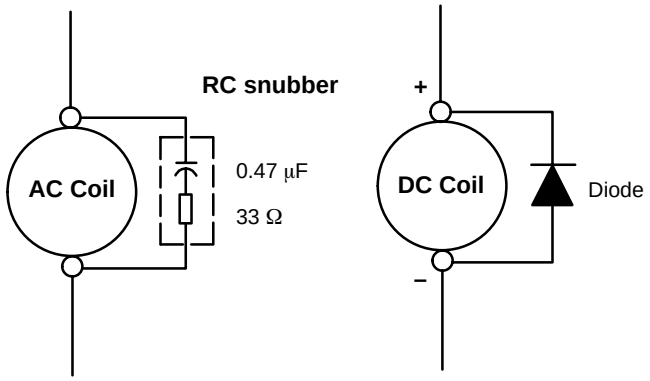
Electrical Noise Considerations All electronic devices are vulnerable to significant electronic interference signals (commonly called “Electrical Noise”). At the lowest level, noise can cause intermittent operating errors or faults. From a circuit standpoint, 5 or 10 millivolts of noise may cause detrimental operation. For example, analog speed and torque inputs are often scaled at 5 to 10 VDC maximum with a typical resolution of one part in 1,000. Thus, noise of only 5 mV represents a substantial error.

At the extreme level, significant noise can cause damage to the drive. Therefore, it is advisable to prevent noise generation and to follow wiring practices that prevent noise generated by other devices from reaching sensitive circuits. In a control, such circuits include inputs for speed, torque, control logic, and speed and position feedback, plus outputs to some indicators and computers.

Relay and Contactor Coils Among the most common sources of noise is the coil of a contactor or a relay. When these highly inductive coil circuits are opened, transient conditions often generate spikes of several hundred volts in the control circuit. These spikes can induce several volts of noise in an adjacent wire that runs parallel to a control–circuit wire.

Figure 6-1 illustrates noise suppression for AC and DC operated coils.

Figure 6-1 AC & DC Coil Noise Suppression



Electrical Noise Considerations Continued

Wires between Controls and Motors

Output leads from a typical 460 VAC drive controller contain rapid voltage rises created by power semiconductors switching 650V in less than a microsecond, 1,000 to 10,000 times a second. These noise signals can couple into sensitive drive circuits. If shielded pair cable is used, the coupling is reduced by nearly 90% compared to unshielded cable.

Even input AC power lines contain noise and can induce noise in adjacent wires. In some cases, line reactors may be required.

To prevent induced transient noise in signal wires, all motor leads and AC power lines should be contained in rigid metal conduit, or flexible conduit. Do not place line conductors and load conductors in same conduit. Use one conduit for 3 phase input wires and another conduit for the motor leads. The conduits should be grounded to form a shield to contain the electrical noise within the conduit path. Signal wires - even ones in shielded cable should never be placed in the conduit with motor power wires.

Special Drive Situations

For severe noise situations, it may be necessary to reduce transient voltages in the wires to the motor by adding load reactors. Load reactors are installed between the control and motor.

Reactors are typically 3% reactance and are designed for the frequencies encountered in PWM drives. For maximum benefit, the reactors should be mounted in the drive enclosure with short leads between the control and the reactors.

Control Enclosures

Motor controls mounted in a grounded enclosure should also be connected to earth ground with a separate conductor to ensure best ground connection. Often grounding the control to the grounded metallic enclosure is not sufficient. Usually painted surfaces and seals prevent solid metallic contact between the control and the panel enclosure. Likewise, conduit should never be used as a ground conductor for motor power wires or signal conductors.

Special Motor Considerations

Motor frames must also be grounded. As with control enclosures, motors must be grounded directly to the control and plant ground with as short a ground wire as possible. Capacitive coupling within the motor windings produces transient voltages between the motor frame and ground. The severity of these voltages increases with the length of the ground wire. Installations with the motor and control mounted on a common frame, and with heavy ground wires less than 10 ft. long, rarely have a problem caused by these motor–generated transient voltages.

Analog Signal Wires

Analog signals generally originate from speed and torque controls, plus DC tachometers and process controllers. Reliability is often improved by the following noise reduction techniques:

- Use twisted-pair shielded wires with the shield grounded at the drive end only.
- Route analog signal wires away from power or control wires (all other wiring types).
- Cross power and control wires at right angles (90°) to minimize inductive noise coupling.

Section 7
Specifications and Product Data

Identification

Servo Control **DBSC X 0 X X X1 X2 X3 X4**

Digital Brushless
Servo Control
2=230V Control
3=460V Control

DC Input Voltage

Control Current Rating
07= 7A (DBSC3000 only)
15= 15A
25= 25A
35= 35A
45= 45A

Option – Letter	Option Description	A	B	C	G	H	W
X1 – Input Option	RS232 RS485 Binary Encoder Simulation Address DIP Switch Handwheel Input * Opto Isolated Pulse Follower				x – x x x x	– x x x x x	
X2 – Feedback Option	A=Resolver B=Encoder	x –	– x				
X3 – Field Bus Option	A=None B=CAN	x –	– x				
X4 – Software Option	Standard (Level 1) Point–to–point (Level2) Positioning (Level 3)		– – x	– x –			x – –

* Available only for resolver commutation.

Option not available.

CAN Bus is only available for controls with resolver feedback. Controls with encoder feedback can not have CAN Bus.

DBSC Servo Control Specifications: (230VAC)

Description	Unit	DBSC2015	DBSC2025	DBSC2035	DBSC2045
Input voltage (Logic & Fan)	VDC	24 (+20%, –15%)			
	ADC	1.6 (2.5 surge @ power on)			
Nominal Output Bus Voltage (Range)	VDC	300 (0-350)			
Nominal Output Bus Current	A_{RMS}	15	25	35	45
Peak Output Bus Current (±10%); 2.5s ±.5s	A_{RMS}	30	50	60	90
Nominal Output Power	kVA	6.5	10.8	15.1	19.5
Enclosure Size		B	B	B	C
Simulated Encoder Output	ppr	512/1024/2048/4096			
Efficiency	%	>95			
Minimum Load Inductance	μH	200			
Analog Command Input	VDC	±10			
Signal Resolution	Bits	12			
Velocity Feedback Resolution	Bits	14 ≤ 6100RPM 12 < 6100RPM			
Nominal Switching Frequency	kHz	8.5			
Output Frequency	Hz	0 – 500			
Mounting	–	Panel			
Weight	lb (kg)	18.7 (8.5)			21 (9.5)
Operating Altitude	ft(M)	To 3300ft (1000M). Above 3300 ft, derate 11% per 3300ft (1000M).			
Operating Shock	G	1G			
Operating Vibration	G	1.0G (10-60Hz)			
Operating Temperature Range	°C	5 to 40 °C			
Maximum Operating Temperature	°C	40°C Maximum			
Humidity	%	10–90 Non–Condensing			
Storage Temperature Range	°C	–25 to +70°C			
Speed Command Potentiometer		5kΩ or 10kΩ, 0.5watt			

All values at ambient temperature of 25°C unless otherwise stated.

DBSC Servo Control Specifications: (460VAC)

Description	Unit	DBSC3007	DBSC3015	DBSC3025	DBSC3035
Input voltage (Logic & Fan)	VDC	24 (+20%, –15%)			
	ADC	1.6			
Nominal Output Bus Voltage (Range)	VDC	565(50Hz) or 650(60Hz) (0-740)			
Nominal Output Bus Current	A_{RMS}	7	15	25	35
Peak Output Bus Current (±10%); 2.5s ±.5s	A_{RMS}	14	30	50	70
Nominal Output Power	kVA	7.0	13.0	21.6	30.3
Enclosure Size		B	B	B	C
Simulated Encoder Output	ppr	512/1024/2048/4096			
Efficiency	%	>95			
Minimum Load Inductance	μH	200			
Analog Command Input	VDC	±10			
Signal Resolution	Bits	12			
Velocity Feedback Resolution	Bits	14 ≤ 6100RPM 12 < 6100RPM			
Nominal Switching Frequency	kHz	8.5			
Output Frequency	Hz	0 – 500			
Mounting	–	Panel			
Weight	lb (kg)	18.7 (8.5)			21 (9.5)
Operating Altitude	ft(M)	To 3300ft (1000M). Above 3300 ft, derate 11% per 3300ft (1000M).			
Operating Shock	G	1G			
Operating Vibration	G	1.0G (10-60Hz)			
Operating Temperature Range	°C	5 to 40 °C			
Maximum Operating Temperature	°C	40°C Maximum			
Humidity	%	10–90 Non–Condensing			
Storage Temperature Range	°C	–25 to +70°C			
Speed Command Potentiometer		5kΩ or 10kΩ, 0.5watt			

All values at ambient temperature of 25°C unless otherwise stated.

Control Signal Levels:

Description	Unit	DBSC 2000 and DBSC 3000
Command Input	VDC	0-10, ±5, ±10VDC
Command Signal Resolution	bits	12
Feedback System	–	Resolver
Feedback Resolution	bits	16 (velocity < 1500 RPM) 14 (velocity < 6100 RPM) 12 (velocity ≥ 6100 RPM)
Resolver Pole Pairs	–	1
Resolver Winding Ratio	–	0.5
Simulated Encoder Output	–	RS422 (5V @ 500kHz maximum, Differential line Driver)
Encoder Simulation Resolution	ppr	512/1024/2048/4096
Opto Isolated Inputs (Pulse & Direction)	VDC	24 (20 – 29)

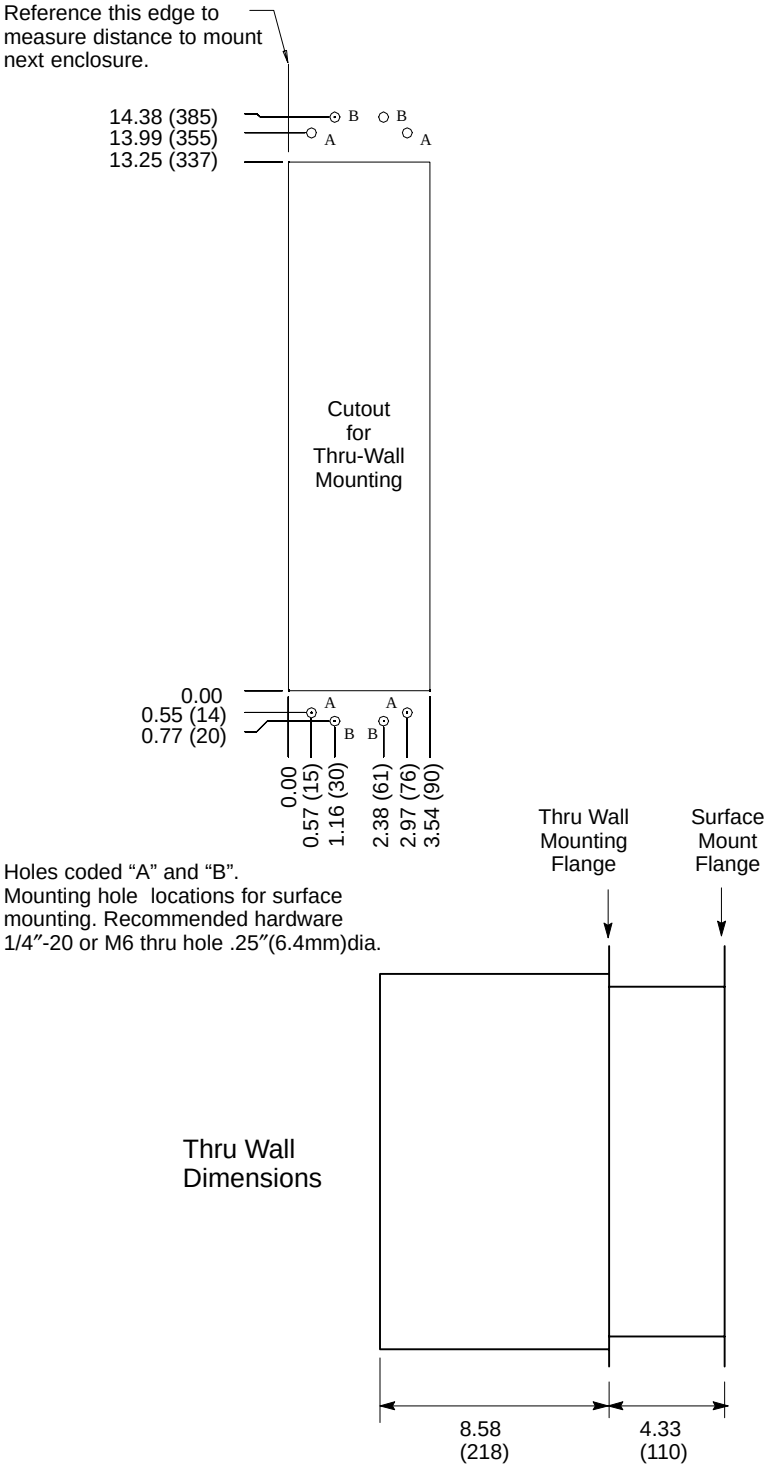
Terminal Tightening Torque Specifications

Table 7-1 Tightening Torque Specifications – DBSC

Tightening Torque					
U, V and W		GND		+VCC, –VCC, GND	
Lb-in	Nm	Lb-in	Nm	Lb-in	Nm
20-27	2.3-3.0	35-46	4.0-5.0	35-46	4.0-5.0

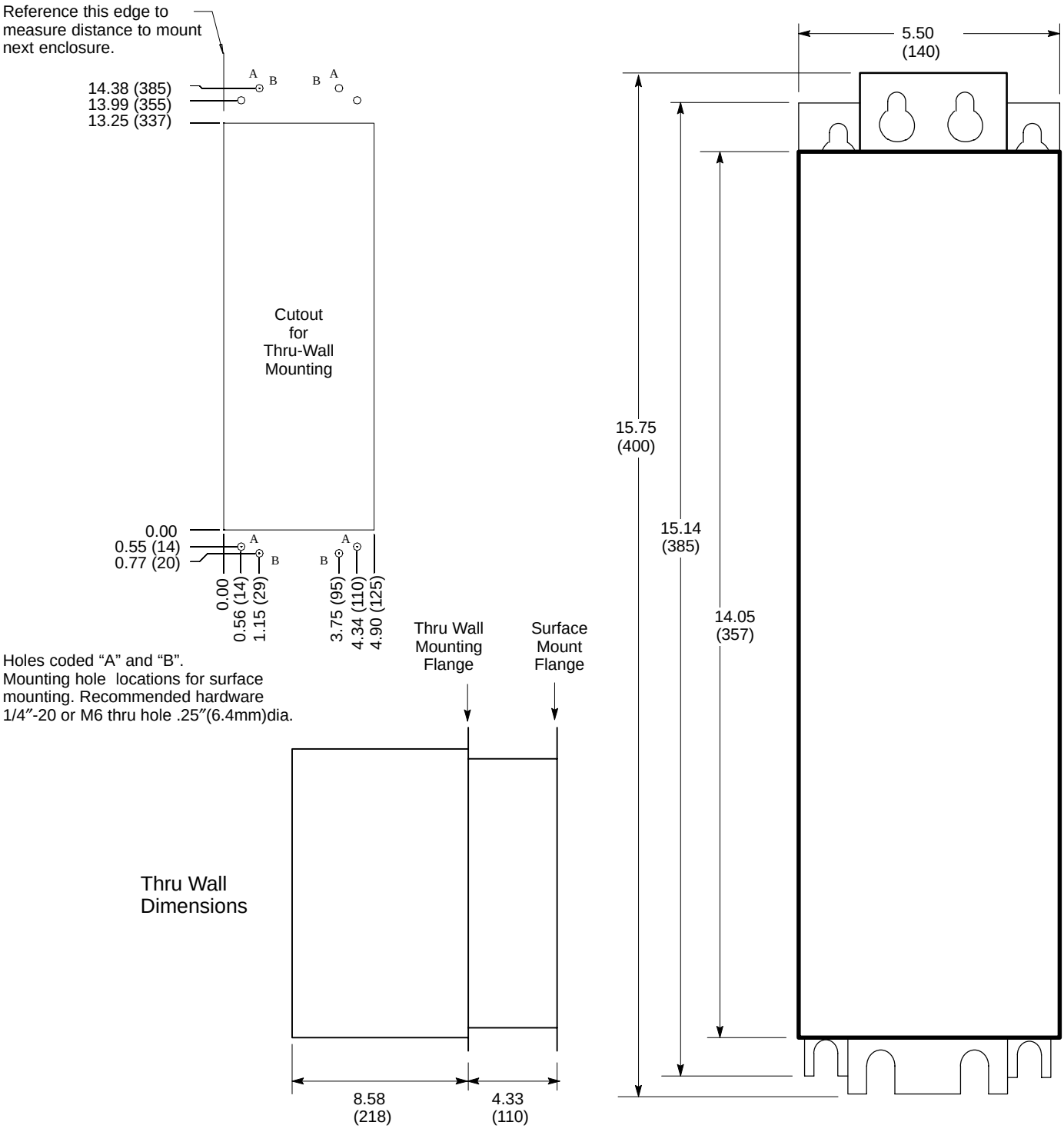
DBSC Dimensions

Size B Dimensions & Mounting



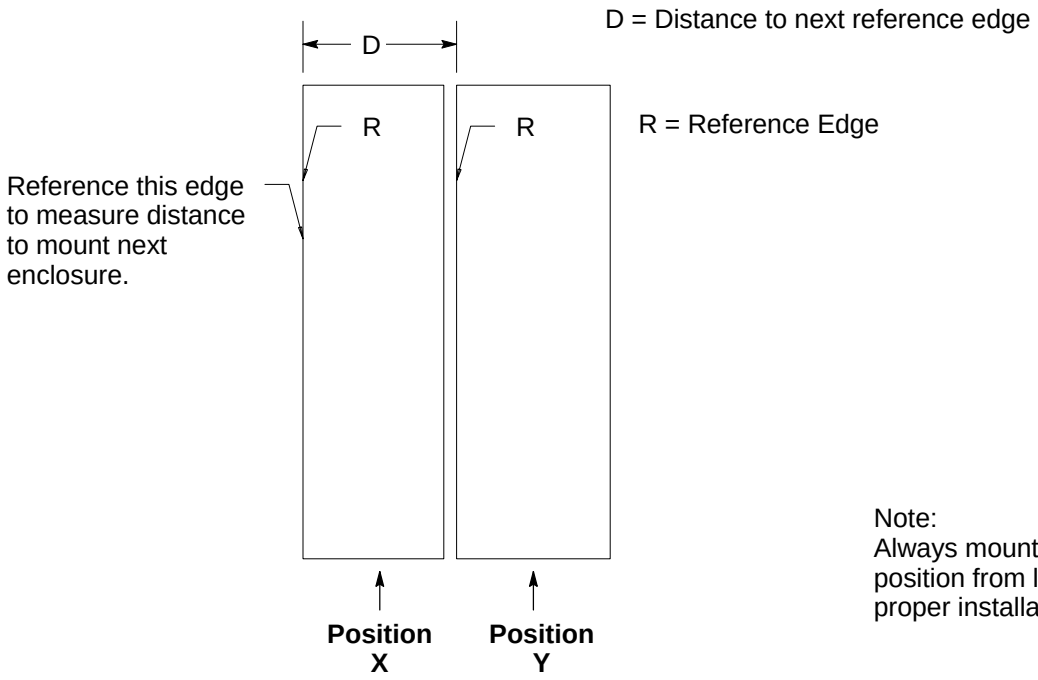
26M-PO/PSM-PR Dimensions Continued

Size C Dimensions & Mounting



26M-PO/PSM-PR Dimensions Continued

Mounting Considerations



Note:
Always mount the PSM in the first position from left to right. This allows proper installation of the power bus bars.

Mounting and Bus Bar Information

Position X Size	Position Y Size	Distance to next reference edge "D"	Power Bus Bar		
			Part Number	Length	Hole Spacing
D	D	10.6 (270)	V1093641	11.74(298)	10.64(270)
D	C	10.5 (267)	V1093651	4.93(125)	3.78(96)
D	B	10.5 (267)	V1093651	4.93(125)	3.78(96)
C	C	5.5 (140)	V1093661	6.82(173)	5.52(140)
C	B	5.5 (140)	V1093661	6.82(173)	5.52(140)
B	D	4.3 (109)	V1093681	12.10(307)	11.03(280)
B	B	4.2 (106)	V1093671	5.24(133)	4.18(106)
B	C	4.2 (106)	V1093671	5.24(133)	4.18(106)

Section 8
CE Guidelines

CE Declaration of Conformity

Baldor indicates that the products are only components and not ready for immediate or instant use within the meaning of “Safety law of appliance”, “EMC Law” or “Machine directive”.

The final mode of operation is defined only after installation into the user’s equipment. It is the responsibility of the user to verify compliance.

The product conforms with the following standards:

DIN VDE 0160 / 05.88	Electronic equipment for use in electrical power installations
DIN VDE 0100	Erection of power installations with nominal voltages up to 1000V
DIN IEC 326 Teil 1 / 10.90	Design and use of printed boards
DIN VDE 0110Teil 1-2 / 01.89	Dimensioning of clearance and creepage
DIN VDE 0110Teil 20 / 08.90	distances
EN 60529 / 10.91	Degrees of protection provided by enclosures

EMC – Conformity and CE – Marking

The information contained herein is for your guidance only and does not guarantee that the installation will meet the requirements of the council directive 89/336/EEC.

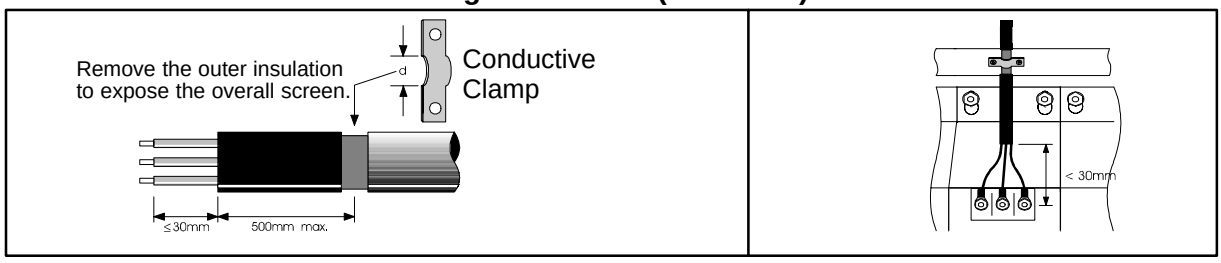
The purpose of the EEC directives is to state a minimum technical requirement common to all the member states within the European Union. In turn, these minimum technical requirements are intended to enhance the levels of safety both directly and indirectly.

Council directive 89/336/EEC relating to Electro Magnetic Compliance (EMC) indicates that it is the responsibility of the system integrator to ensure that the entire system complies with all relative directives at the time of installing into service.

Motors and controls are used as components of a system, per the EMC directive. Hence all components, installation of the components, interconnection between components, and shielding and grounding of the system as a whole determines EMC compliance.

The CE mark does not inform the purchaser which directive the product complies with. It rests upon the manufacturer or his authorized representative to ensure the item in question complies fully with all the relative directives in force at the time of installing into service, in the same way as the system integrator previously mentioned. Remember, it is the instructions of installation and use, coupled with the product, that comply with the directive.

Wiring of Shielded (Screened) Cables

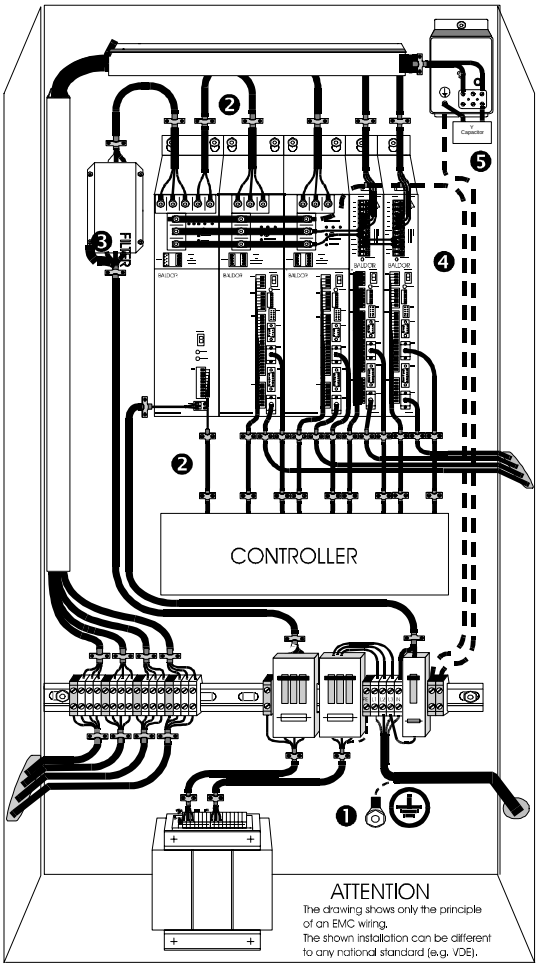


Using CE approved components will not guarantee a CE compliant system!

1. The components used in the drive, installation methods used, materials selected for interconnection of components are important.
2. The installation methods, interconnection materials, shielding, filtering and grounding of the system as a whole will determine CE compliance.
3. The responsibility of CE mark compliance rests entirely with the party who offers the end system for sale (such as an OEM or system integrator).

Baldor products which meet the EMC directive requirements are indicated with a “CE” mark. A duly signed CE declaration of conformity is available from Baldor.

EMC Wiring Technique



1 **CABINET**
The drawing shows an electroplated zinc coated enclosure, which is connected to ground.
This enclosure has the following advantages:
– All parts mounted on the back plane are connected to ground.
– All shield (screen) connections are connected to ground.
Within the cabinet there should be a spatial separation between power wiring (motor and AC power cables) and control wiring.

2 **SCREEN CONNECTIONS**
All connections between components must use shielded cables. The cable shields must be connected to the enclosure. Use conductive clamps to ensure good ground connection. With this technique, a good ground shield can be achieved.

3 **EMC – FILTER**
The EMI or main filter should be mounted next to the power supply (here BPS). For the connection to and from the main filter screened cables should be used. The cable screens should be connected to screen clamps on both sides. (Exception: Analog Command Signal).

4 **Grounding (Earth)**
For safety reasons (VDE0160), all BALDOR components must be connected to ground with a separate wire. The diameter of the wire must be at minimum AWG#6 (10mm^2). Ground connections (dashed lines) must be made from the central ground to the regen resistor enclosure and from the central ground to the Shared Power Supply.

5 **Y–CAPACITOR**
The connection of the regeneration resistor can cause RFI (radio frequency interference) to be very high. To minimize RFI, a Y–capacitor is used. The capacitor should only be connected between the dynamic brake resistor housing and terminal pin R1 (lead).
Recommendation: 0,1µF / 250VAC Type: PME265
BALDOR–Ordering–No.: ASR27104

EMC Installation Instructions

To ensure electromagnetic compatibility (EMC), the following installation instructions should be completed. These steps help to reduce interference. Consider the following:

- Grounding of all system elements to a central ground point
- Shielding of all cables and signal wires
- Filtering of power lines

A proper enclosure should have the following characteristics:

A) All metal conducting parts of the enclosure must be electrically connected to the back plane. These connections should be made with a grounding strap from each element to a central grounding point . [1]

B) Keep the power wiring (motor and power cable) and control wiring separated. If these wires must cross, be sure they cross at 90 degrees to minimize noise due to induction.

C) The shield connections of the signal and power cables should be connected to the screen rails or clamps. The screen rails or clamps should be conductive clamps fastened to the cabinet. [2]

D) The cable to the regeneration resistor must be shielded. The shield must be connected to ground at both ends.

E) The location of the AC mains filter has to be situated close to the drive so the AC power wires are as short as possible.

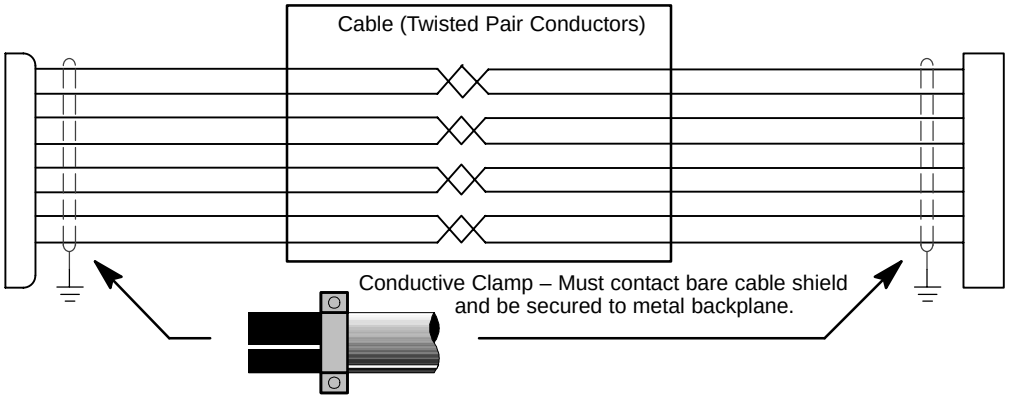
F) Wires inside the enclosure should be placed as close as possible to conducting metal, cabinet walls and plates. It is advised to terminate unused wires to chassis ground. [1]

G) To reduce ground current, use at least a 10mm^2 (6 AWG) solid wire for ground connections.

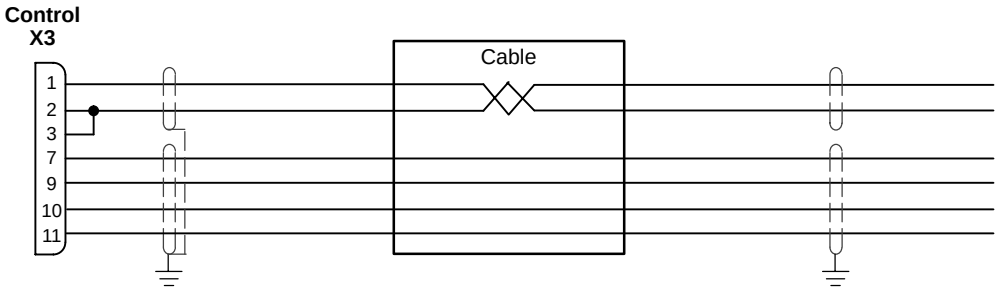
[1] Grounding in general describes all metal parts which can be connected to a protective conductor, e.g. housing of cabinet, motor housing, etc. to a central ground point. This central ground point is then connected to the main plant (or building) ground.

[2] Or run as twisted pair at minimum.

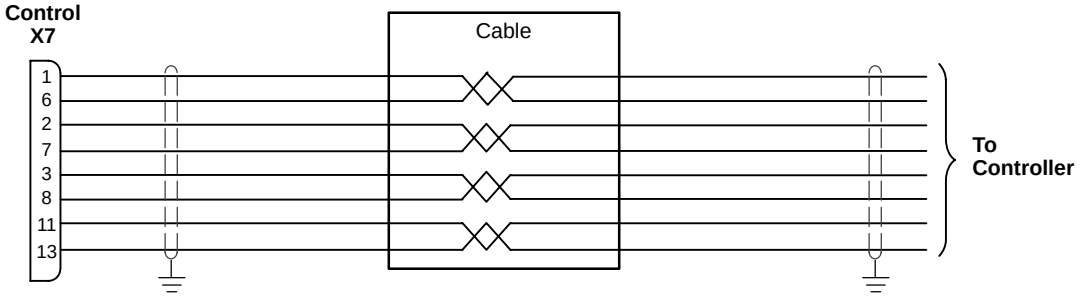
Cable Screens Grounding



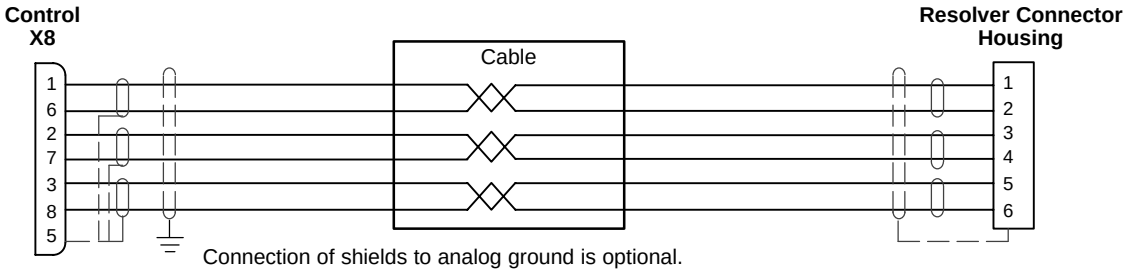
Input Signal Cable Grounding



Simulated Encoder Output Cable Grounding

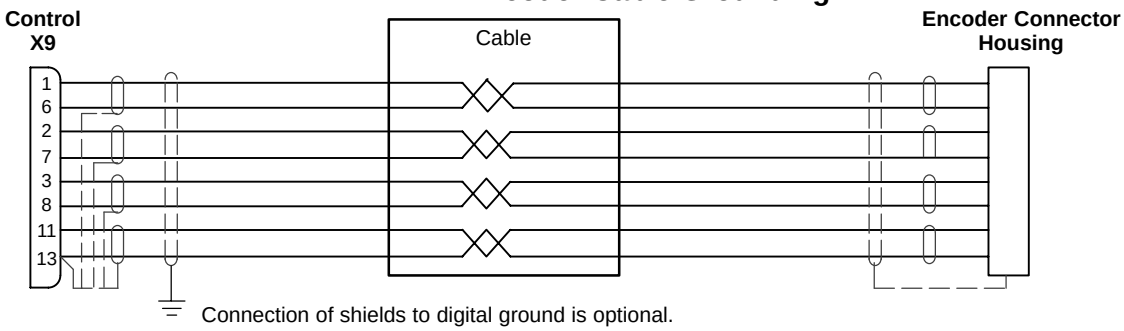


Resolver Cable Grounding



Connection of shields to analog ground is optional.

Encoder Cable Grounding



Connection of shields to digital ground is optional.

Section 9
Accessories and Options

Cables

Shielded (Screened) cable provides EMI / RFI shielding and are required for compliance to CE regulations. All connectors and other components used must be compatible with this shielded cable.

Connectors

Mating Connector by connector number (for spare parts)

X3 – #ASR16000 (20 pin, Female)
X6 – #ASR16215 (9 pin, Male)
X7 – #ASR16215 (9 pin, Male)
X8 – #ASR23345 (9 pin, Female)
X9 – #ASR25828A (15 pin, Male)
X10 – #ASR22938 (for right side)
#ASR22939 (for left side)

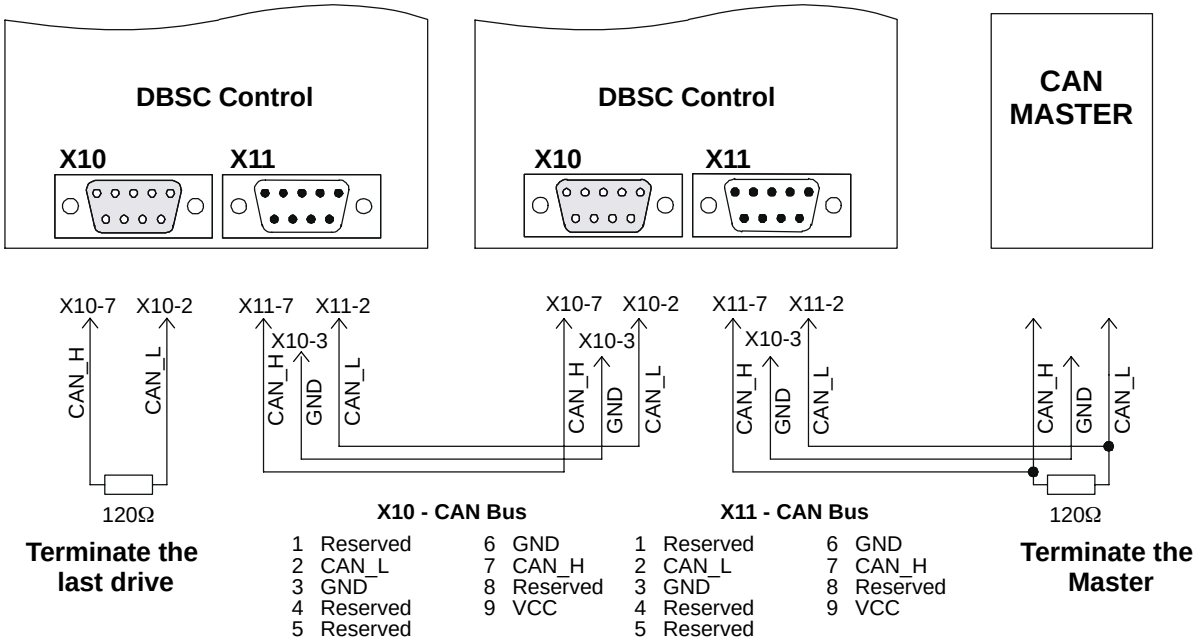
Resolver Feedback Cable

Motor Type	Cable Assembly Description	Baldor Catalog Number	Length	
			Feet	Meters
BSM 50/63/80/90/100	Resolver Feedback Cable Assembly Threaded connector (Standard-Metric Style)	CBL015SF–ALM	5	1.5
		CBL030SF–ALM	10	3.0
		CBL046SF–ALM	15	4.6
		CBL061SF–ALM	20	6.1
		CBL076SF–ALM	25	7.6
		CBL152SF–ALM	50	15.2
	Resolver Feedback Cable Assembly Quick Connect Style	CBL015SF–ALQ	5	1.5
		CBL030SF–ALQ	10	3.0
		CBL046SF–ALQ	15	4.6
		CBL061SF–ALQ	20	6.1
		CBL076SF–ALQ	25	7.6
		CBL152SF–ALQ	50	15.2
	Resolver Feedback Cable Assembly CE Style Threaded Connector	CBL030SF–ALCE	10	3.0
		CBL061SF–ALCE	20	6.1
		CBL091SF–ALCE	30	9.1
		CBL152SF–ALCE	50	15.2
BSM 50/63/80/90/100	Resolver Feedback Cable No Connector	CBL030SF–A	10	3.0
		CBL061SF–A	20	6.1
		CBL091SF–A	30	9.1
		CBL152SF–A	50	15.2

CAN Bus (Optional – Not available for controls with encoder feedback.)

Controls that are supplied with the CAN bus option have two additional connectors, X10 and X11 (conform to DS102, version 2.0). These are shown in Figure 9-1. CAN is a factory installed option.

Figure 9-1 CAN Bus Connectors



CAN Bus Protocol

Baldor uses CAN_OPEN, DS 301 protocol.

Baud rate is preset to 125kbit/second may be changed by AS1 switch settings or serial command (e.g. command: CAN.BD = 1000 for 1Mbit/sec). Available baud rates are: 10, 20, 50, 100, 125, 250, 500, 800, and 1000kbit/sec.

NODE_ID may be changed by switch settings or serial command (e.g. command: CAN.ID = 50). Available addresses are 1 to 127.

CAN Bus Features

The following features are available with the Baldor CAN_OPEN structure:

- One SDO
- Two PDO's; each for transmit and receive (synchronous or asynchronous)
- SYNC message
- EMERGENCY object
- Default and variable PDO mapping
- All ID's can be set with SDO
- Node guarding
- Simple boot-up

Index Range The index range from 0x1000 to 0x100D is valid.
The following index ranges are important:

0x1400	1st PDO receive (communication)
0x1402	2nd PDO receive (communication)
0x1600	1st PDO receive (mapping)
0x1602	2nd PDO receive (mapping)
0x1800	1st PDO transmit (communication)
0x1802	2nd PDO transmit (communication)
0x1A00	1st PDO transmit (mapping)
0x1A02	2nd PDO transmit (mapping)

Object Entries The following object entries are available with PDO:

– Read position (absolute and resolver position)
– Read and write velocity
– Read status
– Write torque

The following object entries are available with SDO:

– Variables and commands

Getting Started with CAN_OPEN

The CAN message transmission consists of an address (=Identifier = ID) followed by 0 to 8 Data bytes. CAN drives use the following addresses (according to CAN_OPEN, DS301):

PDO1 (Receive, Master to Drive): 0x200 + Node_ID

PDO2 (Receive, Master to Drive): 0x300 + Node_ID

PDO1 (Transmit, Drive to Master): 0x180 + Node_ID

PDO2 (Transmit, Drive to Master): 0x280 + Node_ID

NMT: 0x000

SYNC: 0x80

EMERGENCY: 0x80 + Node_ID

SDO (Master to Drive): 0x600 + Node_ID

SDO (Drive to Master): 0x580 + Node_ID

PDO = Process data transfer, fast communication ex: velocity command.

SDO = Service data transfer, slow communication to access all parameters inside the drive.

NMT = Network management task, to switch the PDOs free and to reset the drive.

SYNC = Specific CAN_OPEN message to do some synchronization.

EMERGENCY: The drive will send this message automatically if a fatal drive error occurs

Node_ID: Special setting (= drive number) for each drive. Range : 1 to 127

The default Baud rate is set to 125 kbit/second and the Node_ID is the drive address+1 (AS1 switches 1 to 4).

Note: Every drive, connected to one CAN Bus system must have a different Node_ID.

After power up you will receive an EMERGENCY message with two data bytes (0x00 and 0x00) to inform you that the CAN_DRIVE is now active.

Now you will have access to all commands via SDO. If you want to give a command or set a parameter, you have to put the following message on the CAN_BUS:

To send a command or set a parameter in the drive:

PC Master → Drive

D0	D1	D2	D3	D4	D5	D6	D7
0x20	Ind_lo	Ind_hi	Sub	XXX	XXX	XXX	XXX

ID = 0x600 + NODE_ID <----------

0x20	Ind_lo	Ind_hi	Sub	XXX	XXX	XXX	XXX

ID = 0x580 + NODE_ID <----------

Where:

X	Data bytes (to write a parameter)
ID	Identifier
0x	Hexadecimal data format
D0 - D7	Data byte 0 to 7 of CAN message
Ind_lo	Low byte of Index of Object dictionary
Ind_hi	High byte of Index of Object dictionary
Sub	Subindex of Object dictionary. If Object has only one entry, Subindex must always be 0

Note: If the first data byte in the returned message from the drive = 0x80, the commanded action failed.

To read a parameter from the drive:

PC Master → Drive

	D0	D1	D2	D3	D4	D5	D6	D7
	0x40	Ind_lo	Ind_hi	Sub	XXX	XXX	XXX	XXX
ID = 0x600 + NODE_ID <----------								
	0x60	Ind_lo	Ind_hi	Sub	0x00	0x00	0x00	0x00
ID = 0x580 + NODE_ID <----------								

Where:

X	Don't care
ID	Identifier
0x	Hexadecimal data format
D0 - D7	Data byte 0 to 7 of CAN message
Ind_lo	Low byte of Index of Object dictionary
Ind_hi	High byte of Index of Object dictionary
Sub	Subindex of Object dictionary. If Object has only one entry, Subindex must always be 0
P_lsb	Low byte of requested parameter
P_msb	High byte of requested parameter

Note: If the first data byte in the returned message from the drive = 0x80, the commanded action failed.

To send a velocity command to the drive:

1. Verify that the correct motor and drive parameters and operating mode are set. This is done by CAN or RS232 communications.
2. Send the following CAN messages to the drive.

ID	D0	D1	D2	D3	D4	D5	D6	D7	Description
0x601	0x20	0x8F	0x21	0x00	0x08	XXX	XXX	XXX	Select CAN card for velocity command.
0x581	0x60	0x8F	0x21	0x00	0x00	0x00	0x00	0x00	Drive response with "OK".
0x601	0x20	0x83	0x21	0x00	XXX	XXX	XXX	XXX	Enable drive.
0x581	0x60	0x8F	0x21	0x00	0x00	0x00	0x00	0x00	Drive response with "OK".
0x601	0x20	0x90	0x20	0x00	Vl	Vm	XXX	XXX	Velocity command (Vl=lsb; Vm=msb. Scaling=bits/msec)
0x581	0x60	0x8F	0x21	0x00	0x00	0x00	0x00	0x00	Drive response with "OK".

Note: Every command is answered by the drive. Allow time for the response.

Summary:

With a CAN_OPEN master you don't need to know each data byte. Therefore you only should be informed about the object dictionary, which you will find in the Appendix.

Appendix: Object dictionary
ASCII command set description

Identifiers and object list

The distribution of the identifiers of the supported objects conforms to Can Open (DS301, V 3.0, S. 8–12).

Message / Object	Function Code	COB - Identifier	Services
NMT Services	0	0 (broadcast)	Start_Remote_Node Stop_Remote_Node Pre-Operational-State NMT_Reset_Node NMT_Reset_Com
Sync. Emergency	1 1	128 (broadcast) 128 + Node_ID	Synchronization Emergency (fault)
PDO1 (tx)		384 + Node_ID	Transmit PDO (asynchronous)
PDO1 (rx)		512 + Node_ID	Receive PDO (asynchronous)
PDO2 (tx)		640 + Node_ID	Transmit PDO (synchronous)
PDO2 (rx)		768 + Node_ID	Receive PDO (synchronous)
SDO (tx)		1408 + Node_ID	Transmit SDO
SDO (rx)		1536 + Node_ID	Receive SDO
Node guarding		1760	NMT node guarding

Node_ID is the node identifier, which is the card–address (set by switch AS1–4).

SDO Protocols (CMS Multiplexed Domain Protocols)

In CiA/DS202–2 CMS protocol specification, the following specifications of the SDO COB identifier. This protocol specifies the meaning of the content of the 8 data bytes transferred within a CAN Message for the different domain protocols.

Byte 1	Byte 2	Byte 3	Byte 4	Byte5 to Byte 8
Protocol	Multiplexer or Data Bytes			up to 4 Data Bytes
Control Bits	index, lsb	index, msb	sub-index	Data (byte 5 is lsb; byte 8 is msb)

Multiplexed: Same identifier, message indication by Index + Subindex

Expedited: Used, if data to be transported is less or equal 4 byte (long int, 32 Bit)

The following tables list the meaning / setting of the control bits of first byte (x = not used, always 0) to select the protocol and the correspondent meaning of the further 7 data bytes of the CAN frame.

Expedited domain download and initiate domain download

Domain Protocols	7..5:	4:	3..2:n	1:e	0:s	= 1.byte	m	up to 4 data bytes
Expedited Domain Download Request Confirm	ccs 001 scs 011	x x	(0 or n) x	1 x	s x	=22, 2x1 =60	multiplexor	data to be downloaded
Initiate Domain Download Request Confirm	ccs 001 scs 011	x x	x x	0 x	s x	=20, 2x2 =60	multiplexor	if s=1: number of data reserved

n: If e=1 & s=1, n indicates the number of bytes, which do not contain data (therefore only valid for expedited protocol)

s: Data set size is not indicated / indicated: 0 / 1

[1] If s=1, the 1.byte contains: 23 or (n shifted 2 left)

[2] If s=1, the 4 data bytes contain the number of data bytes to be transferred in the segmented domain.

Segmented domain download

Domain Protocols	7..5:	4: t	3..1:n		0:c	= 1.byte	up to 3+	up to 4 data bytes
Download Domain Segment Request Confirm	ccs 000 scs 001	0 / 1 0 / 1	n x		0 x	=00 / 10 =20 / 30	7 data bytes to be downloaded Reserved	
End of Download Domain Segment Request Confirm	ccs 000 scs 001	0 / 1 0 / 1	n x		1 x	=0X / 1X[3] =20 / 30	≤7 data bytes to be downloaded Reserved	

t: Toggle bit of segmented domain, with first download domain segment t=0

n: n indicates the number of bytes, which do not contain data

c: 1 if last segment to be downloaded, else 0

3 The 1. byte contains: 01 or (n shifted 1 left)

Expedited domain upload and initiate domain upload

Domain Protocols	7..5:	4: t	3..1:n	1:e	0:c	= 1.byte	m	up to 4 data bytes
Expedited Domain Upload Request Confirm	ccs 001 scs 010	x x	x (0 or n)	X 1	x s	=40 =42,4X[4]	multiplexor	reserved data to be downloaded
Initiate Domain Upload Request Confirm	ccs 001 scs 010	x x	x 0	x 0	x s	=40 =40, 41	multiplexor	reserved if s=1: number of data

n: If e=1 & s=1, n indicates the number of bytes, which do not contain data

s: Data set size is not indicated / indicated: 0 / 1, in the case of expedited protocol s indicates that n gives the number of non–data bytes, in the case of initiate protocol s indicates that the four data bytes 5. data byte 5 .. 8. data byte contain the total number of bytes to be uploaded.

4 If s=1, the 1.byte contains: 43 or (n shifted 2 left)

Segmented domain upload

Domain Protocols	7..5:	4: t	3..1:n		0:c	= 1.byte	up to 3+	up to 4 data bytes
Upload Domain Segment Request Confirm	ccs 001 scs 000	0 / 1 0 / 1	x n		x 0	=60 / 70 =0E / 1E	Reserved 7 data bytes to be downloaded	
End of Upload Domain Segment Request Confirm	ccs 011 scs 000	0 / 1 0 / 1	x n		x 1	=60 / 70 =0X / 1X[5]	Reserved ≤7 data bytes to be downloaded	

t: Toggle bit of segmented domain, with first upload domain segment t=0

n: n indicates the number of bytes, which do not contain data

c: 1 if last segment to be uploaded, else 0

5 The 1. byte contains: 01 or (n shifted 1 left)

Abort Domain Transfer (Unconfirmed)

Domain Protocols	7..5:	4.0				1.byte	m	up to 4 data bytes
Expedited Domain Upload Request	c100	x				[80]	multiplexor	reason for the abort

Object Dictionary (CAN - Version: 23310D)

Index (hex)	Object	Used	
0000	not used		
0001 – 001F	Static Data Types	OBJECT_UNSIGNED8	0005
0020 – 003F	Complex Data Types		
0040 – 005F	Manufacturer Specific Data Types		
0060 – 007F	“Device Profile Specific Static Data Types”		
00A0 – 0FFF	”Reserved for future use ”		
1000 – 1FFF	Communication Profile Area	DEVICE_TYPE ERROR_REGISTER MANUFACT_STATUS_REGISTER PREDEFINED_ERROR_FIELD NUMBER_OF_PDOS COB_ID_SYNC_MSG COMMUNI_CYCLE_PERIODE SYNCHRON_WINDOW_LENGTH MANUFACT_DEVICE_NAME MANUFACT_HW_VERSION MANUFACT_SW_VERSION NODE_ID GUARD_TIME LIFE_TIME_FACTOR RECEIVE_PDO_2_COMMUNI_PARAM RECEIVE_PDO_1_COMMUNI_PARAM RECEIVE_PDO_2_MAPPING_PARAM RECEIVE_PDO_1_MAPPING_PARAM TRANSMIT_PDO_2_COMMUNI_PARAM TRANSMIT_PDO_1_COMMUNI_PARAM TRANSMIT_PDO_2_MAPPING_PARAM TRANSMIT_PDO_1_MAPPING_PARAM	1000 1001 1002 1003 1004 1005 1006 1007 1008 1009 100A 100B 100C 100D 1400 1402 1600 1602 1800 1802 1A00 1A02
2000 – 5FFF	Manufacturer Specific Profile Area	MANUFACT_NODI_ID MANUFACT_BAUD_RATE **Objects with Subindexes (2010 – 2020):** MANUFACT_CUR_CONTROLLER MANUFACT_VEL_CONTROLLER MANUFACT_HANDWHEEL_PARAM MANUFACT_POS_CONTROLLER MANUFACT_MOTOR_PARAM MANUFACT_DRIVE_PARAM MANUFACT_SYS_PARAM MANUFACT_JOG_PARAM MANUFACT_MOT_PARAM MANUFACT_HOM_PARAM MANUFACT_LIM_PARAM MANUFACT_COM_JOG MANUFACT_COM_MOV MANUFACT_COM_GO MANUFACT_COM_LRN **PDO mappable parameters (2080 – 2093):** MANUFACT_POS MANUFACT_ABS_POS MANUFACT_VEL MANUFACT_VEL_COMMAND MANUFACT_CONTROL_COMMAND MANUFACT_TORQUE_COMMAND MANUFACT_POS_COMMAND	2000 2001 2010 2011 2012 2013 2014 2015 2016 2017 2018 2019 2020 2050 2051 2052 2053 2080 2082 2081 2090 2091 2092 2093

Index (hex)	Object	Used	
2000 – 5FFF	Manufacturer Specific Profile Area –Continuied	**Read only:** MANUFACT_COM_ACTU MANUFACT_COM_ACTV MANUFACT_COM_ANAIN MANUFACT_COM_CUR MANUFACT_COM_FLT MANUFACT_COM_FEST MANUFACT_COM_LOG MANUFACT_COM_MODE MANUFACT_COM_MPFE MANUFACT_COM_MVFE MANUFACT_COM_PFE MANUFACT_COM_VFE MANUFACT_COM_POS MANUFACT_COM_PREF MANUFACT_COM_RFOFS MANUFACT_COM_VEL MANUFACT_COM_VREF MANUFACT_COM_WRN MANUFACT_COM_ABSPOS **Write only:** MANUFACT_COM_CLEAR 2180 MANUFACT_COM_DIS MANUFACT_COM_ENA MANUFACT_COM_DISA MANUFACT_COM_FRST MANUFACT_COM_GRST MANUFACT_COM_HOLD MANUFACT_COM_IADJ MANUFACT_COM_ICLC MANUFACT_COM_JS MANUFACT_COM_LOGRST MANUFACT_COM_PRST MANUFACT_COM_ABS MANUFACT_COM_HOME MANUFACT_COM_INC MANUFACT_COM_CALC MANUFACT_COM_QUIT MANUFACT_COM_CONT MANUFACT_COM_STOP MANUFACT_COM_PLOAD MANUFACT_COM_PSAVE	 2100 2101 2102 2103 2104 2105 2106 2107 2108 2109 210A 210B 210C 210D 210E 210F 2110 2111 2112 2180 2181 2182 2183 2184 2185 2186 2187 2188 2189 218A 218B 218C 218D 218E 2190 2191 2192 2193 2194 2195
6000 – 9FFF	Standardized Device Profile Area		
A000– FFFF	Reserved		

Subindexes to Index 2010 (CUR. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
CUR.ACTV	0x01	RO
CUR.ACTU	0x02	RO
Reserved	0x03	
CUR.IPEAK	0x04	RW
CUR.INOM	0x05	RW
Reserved	0x06	
Reserved	0x07	
Reserved	0x08	
CUR.TOFR	0x09	RW
CUR.TOSH	0x0A	RW
CUR.BEMF	0x0B	RW
CUR.SCAL	0x0C	RW
CUR.VOLT	0x0D	RW

Subindexes to Index 2011 (VEL. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
VEL.ACC	0x01	RW
VEL.ADZON	0x02	RW
VEL.BW	0x03	RW
Reserved	0x04	
VEL.MXRPM	0x05	RO
VEL.VEL	0x06	RO
Reserved	0x07	
VEL.VREF	0x08	RO
VEL.CTRL	0x09	RW
VEL.TRKFCT	0x0A	RW
VEL.GV	0x0B	RW
VEL.GVI	0x0C	RW
Reserved	0x0D	
Reserved	0x0E	
Reserved	0x0F	
VEL.INRT	0x10	RW
VEL.SCAL	0x11	RW
VEL.VOLT	0x12	RW

Subindexes to Index 2012 (HW. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
HW.GRFX	0x01	RW
HW.GRSH	0x02	RW
HW.PLCGEAR	0x03	RW
HW.RES	0x04	RW
HW.TYPE	0x05	RW

Subindexes to Index 2013 (POS. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
POS.FEWRN	0x01	RW
POS.FEFAT	0x02	RW
POS.FEST	0x03	RO
POS.FFA	0x04	RW
POS.FFTYPE	0x05	RW
POS.FFV	0x06	RW
POS.IPOS	0x07	RW
POS.KP	0x08	RW
POS.MPFE	0x09	RO
POS.REF	0x0A	RO
POS.PFE	0x0B	RO
POS.POS	0x0C	RO

Subindexes to Index 2014 (MTR. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
MTR.IDX	0x01	RW
MTR.IND	0x02	RW
MTR.INOM	0x03	RW
MTR.IPEAK	0x04	RW
MTR.JM	0x05	RW
MTR.MPLS	0x06	RW
MTR.RPLS	0x07	RW
MTR.RES	0x08	RW
MTR.KT	0x09	RW
MTR.KV	0x0A	RW
MTR.NAME	0x0B	RW

Subindexes to Index 2015 (DRV. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
DRV.BUSAPP	0x01	RW
DRV.BUSOV	0x02	RW
DRV.BUSV	0x03	RW
DRV.I2T	0x04	RW
DRV.ID	0x05	RW
DRV.IDX	0x06	RW
DRV.INOM	0x07	RW
DRV.IPEAK	0x08	RW
DRV.LIFE	0x09	RO

Subindexes to Index 2016 (SYS. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
SYS.ANAIN	0x01	RO
SYS.ANA2	0x02	RO
SYS.ENC	0x03	RW
SYS.ENCRES	0x04	RW (encoder system only)
SYS.FAULT	0x05	RO
SYS.FBACK	0x06	RW
SYS.INFO	0x07	RO
SYS.MOD	0x08	RW
SYS.OPT	0x09	RO
SYS.POWER	0x0A	RO
SYS.RFOFS	0x0B	RW
SYS.POS	0x0C	RO
SYS.STTS	0x0D	RO
SYS.VER	0x0E	RO
SYS.WRN	0x0F	RO
Reserved	0x10	
SYS.ENCINDX	0x11	RW
SYS.LEVEL	0x12	RO

Subindexes to Index 2017 (JOG. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
JOG.TIME	0x01	RW
JOG.TYPE	0x02	RW
JOG.VEL	0x03	RW

Subindexes to Index 2018 (MOT. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
MOT.ABSPOS	0x01	RO
MOT.ACC	0x02	RW
MOT.VEL	0x03	RW
Reserved	0x04	
MOT.TYPE	0x05	RW
MOT.DWELL	0x06	RW
MOT.INCCW	0x07	RW
MOT.INCW	0x08	RW
MOT.SRC	0x09	RW
MOT.STATUS	0x0A	RO
MOT.TRIG	0x0B	RW
MOT.BUFTYPE	0x0C	RW
MOT.GENPOS	0x0D	RO

Subindexes to Index 2019 (HOM. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
HOM.ACC	0x01	RW
Reserved	0x02	
HOM.VEL	0x03	RW
HOM.TYPE	0x04	RW
HOM.OFFSET	0x05	RW
HOM.POLR	0x06	RW
HOM.STATUS	0x07	RO

Subindexes to Index 2020 (LIM. Commands)

ASCII Command	Subindex	Read/Write (RW), Read only (RO), Write only (WO)
(Entries)	0x00	RO
LIM.CW	0x01	RW
LIM.CCW	0x02	RW
LIM.ON	0x03	RW
LIM.LRN	0x04	RW

Appendix A
Manual Tuning

TUNING

This appendix presents guidelines for manual tuning the Control. Tuning is necessary, since a various loads (friction and inertia) will effect the drive response. Response may be defined as the time required for the drive to reach speed.

Various software “tools” are available to make tuning easier, such as:
Internal libraries (easy definition of parameters),
pole placement (the software calculates a “no–overshoot” response),
plotting routine (the drive response is displayed on a screen).
This information is as a guide only and the exact response is entirely up to the individual performing the tuning.

TUNING GUIDELINES

The control is easily tuned using a laptop computer and software. The autotuning procedure provides a stable and responsive drive, by adjusting the parameter values for velocity loop tuning. The autotuning procedure will work for most applications. Manual tuning however may be desirable when very tight response is required. These guidelines provide a basic reference starting point for any additional adjustments.

General Tuning Rules

Tune the velocity loop first, and then tune the position loop (when using pulse/direction, or position follower mode). The velocity loop should always be tuned before the position loop, as velocity loop tuning affects the position loop response. To reduce mechanical resonance, use a stiffer mechanical coupling or decrease the low–pass filter value.

Manual Tuning

Manual tuning may be used to adjust the response of the control. Two types of manual tuning are possible: velocity tuning and position tuning (for a system which has been set up to operate in either the pulse/direction, or position follower mode).

Initial Settings Required

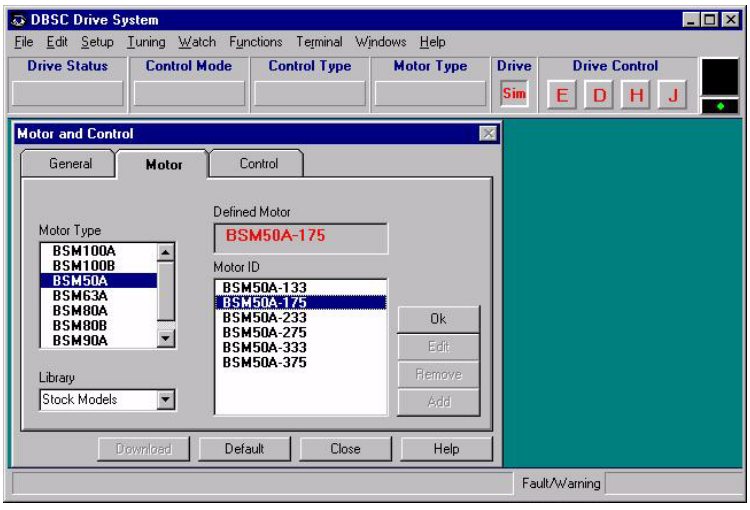
Before manual tuning can begin, the motor, control, and operating mode must be set. Make sure that these parameters have been selected and downloaded.

There are 7 parts to the setup procedure:

Motor

Select your motor from the library. First, select the general motor type. Then select your specific motor. All of the parameters will be entered if your motor is on the list. If your motor is not on the list, you may define a motor and all of its parameters. Click “Download” when finished.

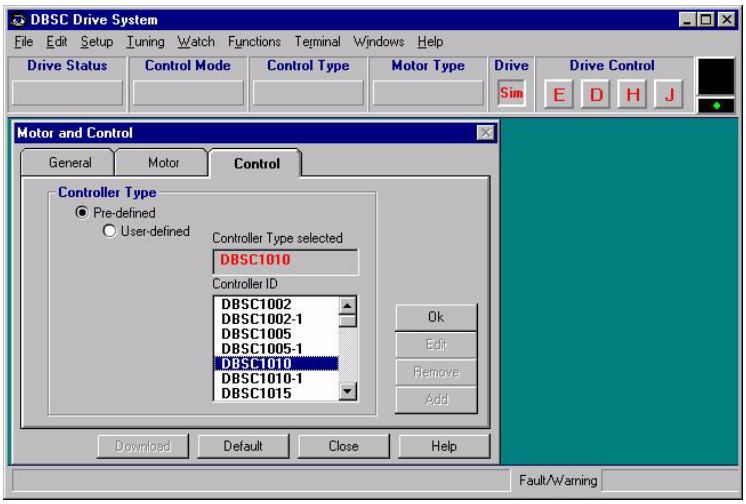
Figure 4-2 Motor Selection Screen



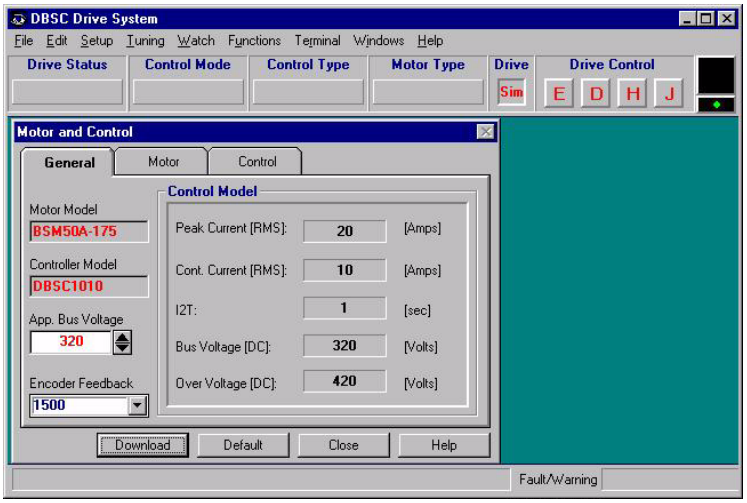
Control

The “Control ID” is automatically selected. All of the parameters will be entered if your control is on the list. Click “Download” when finished.

Figure 4-3 Control Selection Screen



After the motor and control are selected, click the General menu and note that the values are filed in.

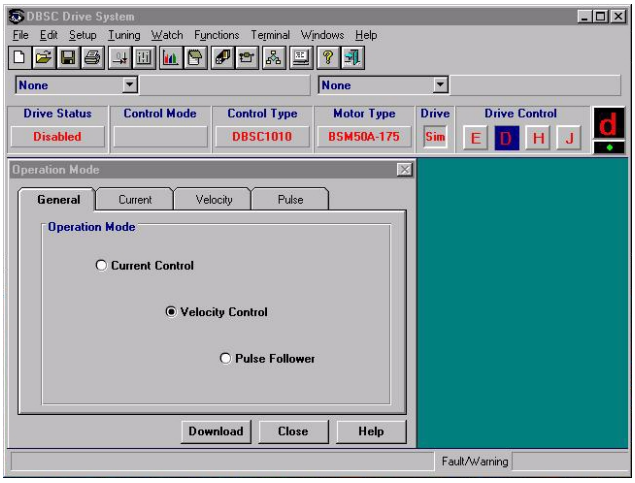


Operating Mode

Select the operating mode of the control. Choices are:

1. Current Mode
2. Velocity Mode
3. Pulse Follower Mode (Pulse & direction or Electronic Handwheel)
   Click “Download” when finished.

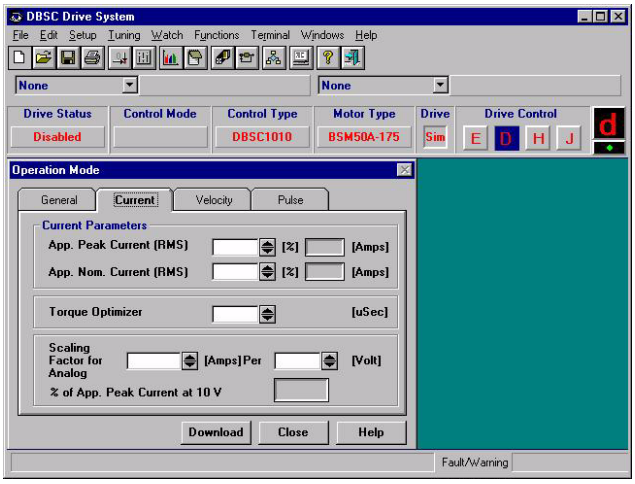
Figure 4-4 Operating Mode Selection Screen



Current Parameter

Nominal and peak current values are automatically entered for the motor type. For manual tuning only, set the control current limit value to a percentage of the continuous current rating. For example, if your control is rated for 5A continuous current and you desire to limit the output current to 4A, enter 80%. If you wish to use the full output power of the control, enter 100%. Click “Download” when finished.

Figure 4-5 Current Parameter Screen

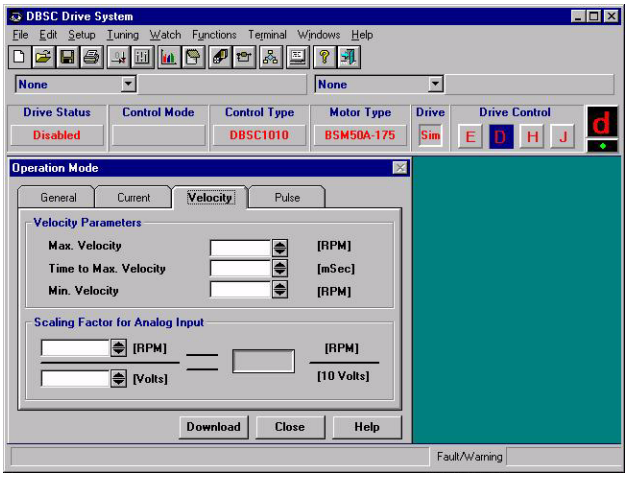


Velocity Parameter

Set the velocity parameters of the control:

1. Scale factor - ratio of the input voltage to output RPM.
2. Minimum velocity.
3. Time to maximum velocity
   Click “Download” when finished.

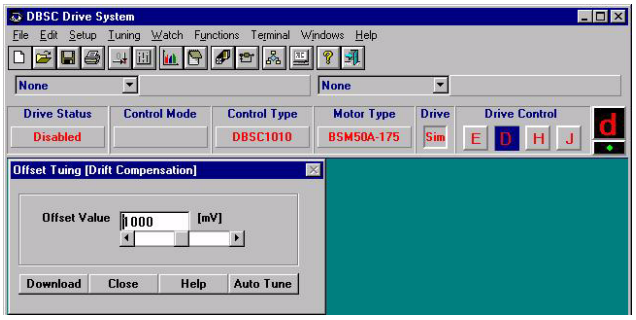
Figure 4-6 Velocity Parameter Screen



Drift

If you know the input offset value of the control, you may enter the value manually. Otherwise, you may initiate automatic offset tuning and let the control measure and set this value. Click “Download” when finished.

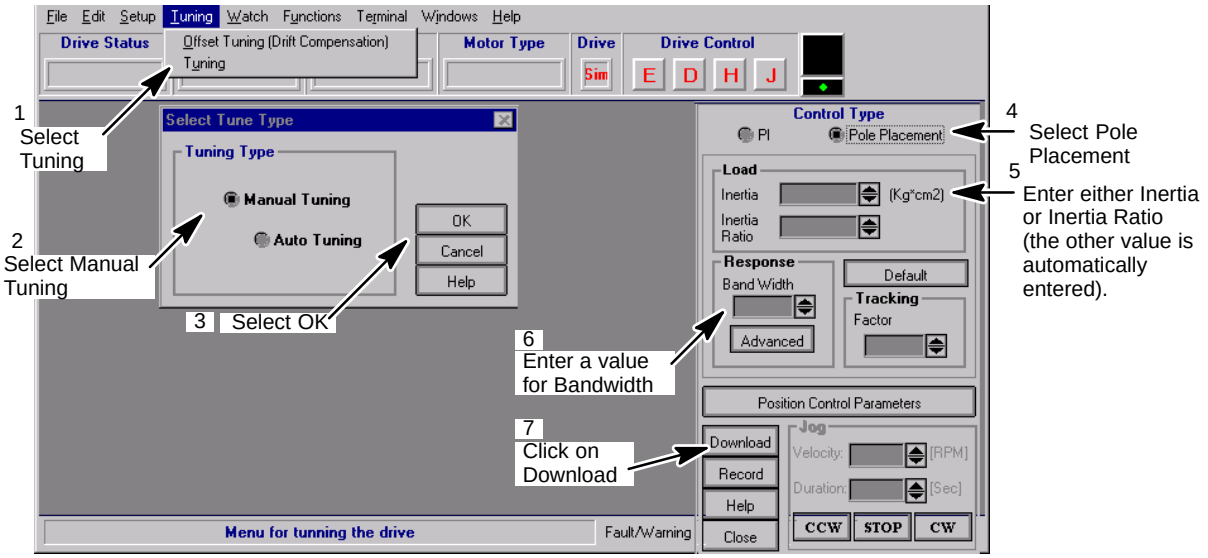
Figure 4-7 Drift Parameter Screen



Manual Tuning

The first six steps of the manual tuning process is shown in Figure 4-8.

Figure 4-8 Select Manual Tuning



If “Pole Placement” method of adjustment is selected, you would enter values for “inertia” or “inertia ratio”. Enter either one, and the other value will automatically be entered. This is the easiest and recommended method of adjustment.

If “PI” method of adjustment is selected, you would enter values for GV–gain and GVI–gain. This is an advanced method of adjustment, and is more difficult.

Both methods of adjustment provide identical results. PI method is described later in this section.

POLE PLACEMENT

Pole placement provides a “no–overshoot response” when tuned for the correct inertia. This is the easiest and recommended method of adjustment.

Inertia

Click in the “Load” block and enter the value in Kg–cm^2. The range is from 0 to 133 Kg–cm^2.

If the inertia is under–estimated, the system will be stable. If the inertia is over–estimated, the system will vibrate or oscillate due to too much system gain. If the load inertia is unknown, estimate low. It is recommended to start with “load inertia = 0.2”, which represents a stable condition.

If you entered the “inertia ratio”, you should enter a value representing the ratio of reflected load inertia to motor inertia. The range is from 0 to 100.

Response

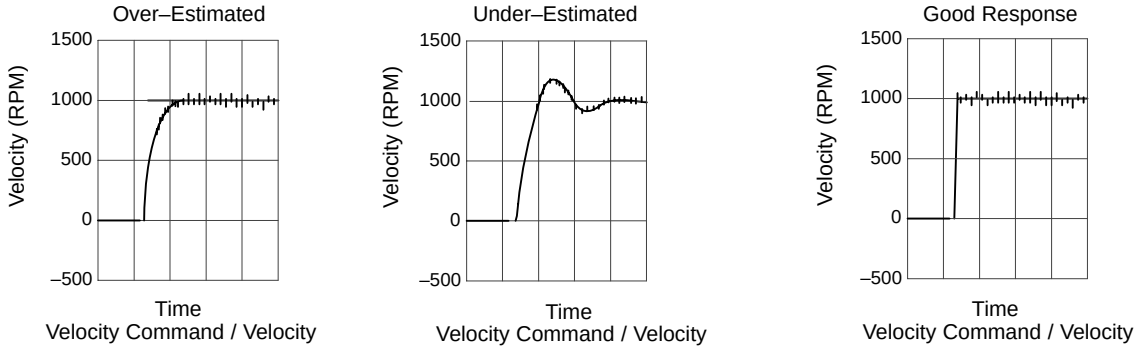
Move to the “Response” block and place the cursor in the “bandwidth” window, and click on it.

The “bandwidth” is a measure of the range over which the system can respond. It is expressed in frequency or Hertz. This parameter controls the “rise time” of the system. It does not effect overshoot.

It is recommended that bandwidth is increased only if higher dynamic response is required. Increase the bandwidth and observe (go to plotting of move) the “velocity” and “command current”, until current reaches maximum value, then back off to 80%. The range is from 10–200.

The next step, would be to verify that the value you entered, provides for adequate system response. You can check this out, by having the software move the equipment and plot the response. Proceed to “Plotting of Move”.

Figure 4-9 Inertia and Load Response Examples



Tracking factor

The tracking factor parameter controls the amount of tracking versus overshoot. The range is 0 to 200. A “tracking factor” of “0” generates no overshoot. A “tracking factor” of 200 results in a PI equivalent control (i.e. with overshoot).

The next step, would be to verify that the values you entered, provides for adequate system response. You can check this out, by having the software move the equipment and plot the response. Proceed to “Plotting of Move”.

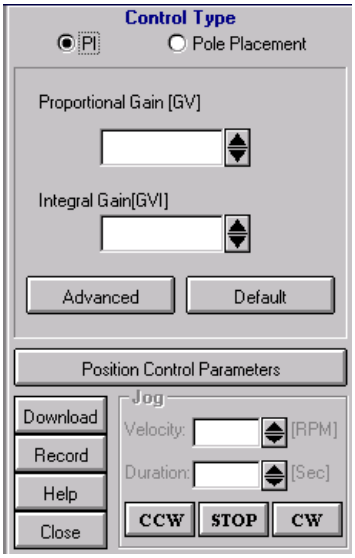
Click in the “Tracking” block and enter the desired adjustment value. This adjustment is used for applications that require improved tracking (or following) capability, to improve (or reduce) following error.

PI COMPENSATION

PI method of adjustment allows adjustment of the acceleration ramp time and overshoot values. If “PI” Compensation is selected, you would enter values for GV–gain and GVI–gain. Select PI Compensation instead of Pole Placement on the menu shown in Figure 4-8.

This is an advanced method of adjustment for use by servo engineers. The “pole placement” method is easier to use for most applications and is recommended.

Figure 4-10 PI Compensation Menu



GVI–Gain

The “Integral Gain (GVI)” is the “integral gain” of the velocity loop. It controls 1) the stiffness (the ability to reject load disturbances), and 2) the amount of offset, or following error, during steady state conditions (velocity command or load does not change). The adjustable range is from 0 to 32767.

1. Click on the “Integral Gain (GVI)” box and enter a value. You may want to begin with the default values – click on the “default” button and answer “yes. To increase stiffness, increase the GVI–gain setting. It rejects load disturbance and compensates for system friction.

   To reduce following error, or offset, during steady state running conditions, increase the GVI–gain setting. To reduce the overshoot, reduce the GVI–gain setting.

Note: As you increase the value for GVI, the system will become unstable, i.e. oscillate. You may hear an audible noise. Decrease the GVI value immediately. Continue to decrease the value until the noise is no longer heard, then decrease it another 10%.

2. Next, verify that the value you entered provides adequate system response. To verify, have the software move the equipment and plot the response. Proceed to “Plotting of Move”.

GV–Gain

This is the “proportional gain” of the velocity loop. It controls the gain of the velocity loop by adjusting the controls response to the error. The error is the difference between the commanded and actual velocity. The higher the gain, the smaller the difference (or error). The adjustable range is from 0 to 32767.

1. Click in the “Proportional Gain (GV)” box. Enter a value for GV. You may want to begin with the default values – click on the “default” button and answer “yes”.

Note: The default values may not be best for all applications, it may be too high. If the system is noisy (displays an audible noise) decrease this value immediately.

To obtain a faster rise time, increase the GV–gain setting. The ramp up time (to operating speed) will be faster. As you increase the value for GV, the system may have very large overshoots and become unstable. Decrease the GV value immediately. Then decrease it another 10%.

2. Next, verify that the value you entered provides adequate system response. You can check this out, by having the software move the equipment and plot the response. Proceed to “Plotting of Move”.

Plotting of Move

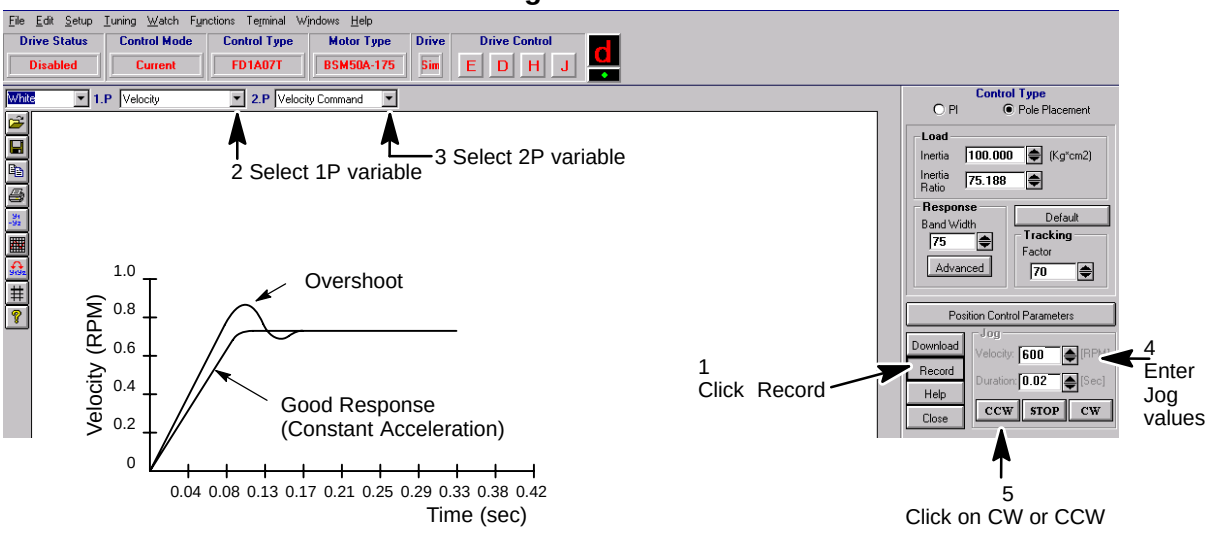
At any time after the setup parameters are downloaded to the control, you may proceed to the plotting routine. Plot allows you to verify that the parameter values you entered provide adequate system response.

In this section, you will inform the software what move to perform. You will enter time (for the move), direction (CW or CCW) and speed. It is recommended that you start with low speeds (i.e. 100 RPM) and short time periods (i.e. 0.5 sec) until you get a feel for your system.

Control Window

Enter the parameter values using the Pole Placement menu and click the "Download" button. Refer to Figure 4-8 for details.

Figure 4-11 Record & Plot Menu



Graphic Screen

Click on the "Record" button to activate a graphic screen.

Move the cursor to the "plot variable" window (1P and 2P windows = 1st and 2nd Plot windows) and choose one or two variables which will be drawn on the plot (such as velocity, velocity command, etc.).

Jog Block

Click on "velocity" in the Jog window. Enter a value to run the motor. A low speed (i.e. 100 RPM) is recommended.

Click on "duration" in the Jog window. Choose a duration time. Recommend that you use a short time period (i.e. 0.5 sec).

Initiate Move

Click on either the "CW" or "CCW" button. This selects the direction of movement and the software will plot the variables you selected. Observe the performance plot. If it meets your expectations, you are done. If you wish to alter parameters and view another plot, repeat the above procedure.

Pulse Follower Applications (Only used in “pulse follower” applications).

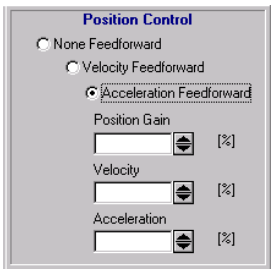
Choose Tuning

Select the “Manual tune” method as shown in Figure shown in Figure 4-8.

Position Parameters

Click on the “Position Parameters” button. You will see parameters as shown in Figure 4-12. Selecting “None Feedforward” allows you to enter Position Gain.

Figure 4-12 Position Control Menu



Select Velocity feedforward allows you to enter Position Gain and Velocity, a parameter that is proportional to the desired velocity. Increasing this gain, compensates for damping (brings actual velocity closer to desired velocity). It is not within the servo loop, so it does not effect stability. The adjustable range is from 25 to 100%.

Select Acceleration feedforward allows you to enter Position Gain and Velocity and Acceleration. Acceleration is a parameter that is proportional to the desired acceleration. Increasing this gain, compensates for inertia (brings desired acceleration closer to actual acceleration). It is not within the servo loop, so it does not effect stability. Inertia resists acceleration. The adjustable range is from 25 to 100%.

Initiate Move

To verify that the parameter values are correct, you must cause the system to move. This would be accomplished by having the “host controller”, or “indexer”, or “computer” output a string of pulses.

During movement, observe the “Monitor” (7–segment display) on the front panel.

If a “P” is observed on the Monitor display, the drive is within the “in–position” band which has been set. If a “P” is not observed, then the drive is outside the band, or window. This would occur, for example, with a high friction system.

Either the gain or feedforward term must be adjusted, or the “in–position” band must be opened (until a “P” is observed).

Note: To change the “in–position” band or window, you have to choose Setup (from the “toolbar” at top of the screen). In the box, choose “Operation Mode”. You will see choices of “general”, “current”, “velocity”, and “pulse”. Select “pulse” tab. This will open the window showing the “following error limits”. You may enter and modify (open) the in–position bands.

Appendix B
Command Set

ASCII Command Set

General

DBSC controls use the RS232 communication port (optional RS485) as the Interface. This document describes existing ASCII terminal commands for setup and control of the servo drive.

There are three types of ASCII commands:

1. Parameters. Without parameters, these commands are handled as queries. To modify the value of a parameter, the value to be set is added to the command. Some parameters may only be modified under special drive conditions. Query is not restricted to special drive conditions.
2. Variables or system constants. System variables are internally updated in the control, and can not be changed by the user. System constants are fixed (e.g. by hardware) system properties. Query of variables or constants is not restricted to special drive conditions.
3. Methods support control of the system. Methods may or may not require a parameter. Commanding a method to be executed is in some cases also restricted to special drive conditions. Each command is defined as a special mnemonic, which is used for query of parameters, variables and constants as well as for parameter less methods. Modifying a parameter respectively commanding a parameterized method is done by simply adding the parameter value to the mnemonic.

Syntax

General structure of the ASCII command

Each ASCII command is structured in principle according to “Mnemonic” “Delimiter” “Parameter List”. Syntax allows multiple commands in the same string separated by blank space delimiter. Each command string is terminated by a carriage return. i.e. generally, a command string looks like:

“Mnemonic1” “Delimiter” “Parameter List1”... “MnemonicN” “Delimiter” “Parameter ListN” [CR]

Up to 80 characters are allowed at the command prompt.

For each correct command the control returns a “>” sign (ASCII 3E hex) as an acknowledge. If a command is not accepted, the reason for the command revision is sent instead of the acknowledge.

Mnemonics

The mnemonics are not case sensitive. Most of the ASCII commands are grouped into functional groups. The Mnemonics of the commands of parameters, variables and methods of these function groups have a prefix, which indicate the function and, separated by the dot, the command identifier. The general structure of Function Group Commands is as follows:

“Functional Group”.“Command Identifier” “Delimiter”“Parameter list” [CR].

e.g. SYS.MOD 1

All prefixed commands are drive parameters. The delimiter between mnemonic and parameter of these commands is either blank space or equal sign (one of both is mandatory). To query all parameters and variables of a function group, the function group prefix followed by dot and asterisk can be used:

“Functional Group”.*

e.g. SYS.*

Upon receiving a command, the controller answers by sending the function parameter and variable list. General purpose commands are not prefixed. These commands only consist of the command identifier and therefore need the general structure

“Command Identifier” [“Delimiter”]“Parameter list” [CR]

With the non–prefixed commands, no delimiter is mandatory, but the blank space can be inserted optional.

Parameters and Units

The parameters used within the ASCII commands are integers of different sizes:

INTEGER: 16 bit value ranged 8000.. 7FFF hex (-2^{15}.. $+2^{15}-1$ dec.)

UNSIGNED INT: 16 bit value ranged 0.. FFFF hex (0..$2^{16}-1$ dec.)

LONG: 32 bit value ranged 80000000.. 7FFFFFFF hex (-2^{31}.. $+2^{31}-1$ dec.)

UNSIGNED LONG: 32 bit value ranged 0.. FFFFFFFF hex (0.. $+2^{32}-1$ dec.)

STRINGS: Strings of ASCII characters (0 .. FF hex).

A string parameter is preceded and terminated with double quote character (″)!

Commands, which accept or require more than one parameter, use parameter lists which are composed of the sequence of parameters necessary, with the delimiters blank space or comma between.

The number of the parameter can be given as decimal value or as hexadecimal value. Hexadecimal values are preceded by one or more 0–character (30 hex), while decimal values are taken as default without indicator.

The ASCII command set description below, also shows the units of the parameters respectively indicate parameters with no units. For best resolution within the accepted range, the units of the parameters are not chosen according to SI, but most of the units used are SI units multiplied with potentials of 10.

In some cases, units are related to system properties and can therefore not be same for all applications. The following is an example of how to calculate Counts and Limits, used with positioning and homing:

Resolver

max.	RPM Resolution	Counts/rev.	Limits
< 1500	2^{16}	2^{16}	$\pm$ 229–1
< 6100	2^{14}	2^{16}	$\pm$ 229–1
< 6100	2^{12}	2^{16}	$\pm$ 229–1

Encoder

Pulses/rev.	Resolution	Counts/rev.	Limits
1000	4000	64000	225–1
1500	6000	48000	226–1
2000	8000	64000	226–1
2500	10000	40000	227–1
5000	20000	40000	228–1
6000	24000	48000	228–1

The resolution of all (Resolver or Encoder) is between $\pm\ 2^{13}$ and $\pm\ 2^{14}$.

Start–up with Terminal Communication and Command Examples

1. Select the correct COM port NR. and set the following at your PC:
   – Baud Rate: 9600
   – Protocol (Hardware, Xon/Xoff, None): OFF
   – Data Length: 8 Bit
   –Stop Bit: 1
   –Parity: NONE
2. Set the control address. The address is set by switch AS1-1 to AS1-4. To locate a control, type “A” then the control address, e.g. **A3** (searches for a control with address 3). If a drive with address “3” is running and connected to the PC COM, this drive answers with the prompt sign “>” to indicate that communication to the drive is established. Additional command may be sent to the A3 control.

   Entering an address command with another address number, will terminate communication with control A3. If more than one drive is connected to the PC COM port, typing the address of another drive connected, will change communication path to this one.
3. Communication is now established and the ASCII commands may be used.

Note: If more than one drive is connected to the PC port, correct communication can only be established if all drives have different addresses.

4. **Error messages** (from the control)

   If the syntax and the values of the ASCII command string are correct, the control accepts the command and answers by sending “<” as acknowledge. If any error within the transferred command was found, the control rejects the command by sending a correlated error string. There are following terminal–reported errors :

   – **SYNTAX ERROR:** invalid character;

   – **EXECUTION ERROR:** invalid command;

   – **RANGE ERROR:** invalid parameter value;

   – **INVALID EXE CONTEXT:** invalid command or operation mode;

   – **CONTROL DESIGN FAILURE:** invalid control model;

   – **INPUT BUFFER OVERFLOW:** command line exceeded 80 char.;

   – **TOO MANY PARAMETERS:** too many parameters;

   – **REQ. PARAMETER MISSED:** not enough parameters;

   In case of an error, the event protocol will return a NAK (negative acknowledge) to a user. The error check can only provide a syntax and range check for each command. Error checking will not check a wrong parameter value that may degrade system performance.

General Settings

System Constants

Command	Description	Range	Common	Lev I	LevII
SYS.POWER	Queries dip switch ID, (see DRV.ID)		X		
SYS.FBACK	Queries system feedback (encoder / resolver)as defined by ALTERA	0:1	X		
SYS.INFO (SYS.VER)	Queries firmware version with naming and version number as ASCII string	ASCII letters	X [1]		
SYS.LEVEL	Queries level version	1 : 2	X [2]		
SYS.OPT	Queries ALTERA option(s)X	0 : 7	X		
SYS.STTS (COM.ADDR)	Most Significant–Word of SYS.STTS gives control address of (LS–Words. below). Control Address is set per Dip Switch	(MS-Word of SYS.STTS)			

[1] Firmware versions RES–1.xx, ENC–1.xx SYS.VER is equal to SYS.INFO , downward versions: answer to SYS.VER is unsigned integer version number only

[2] Firmware versions RES–1.xx, ENC–1.xx only (no version)

Basic System Parameters

Motor Parameters (MTR. prefixed)

Command	Description	Units	Range	Default	E² / Par. set
MTR.IDX	DBSC Setup library defined Motor Index		Unsign Int.		E / P
MTR.IND	Motor inductance	0.01 H	1 : 65535		E / P
MTR.INOM	Motor nominal current	0.1 A	1 : 65535		E / P
MTR.IPEAK	Motor peak	0.1 A	1 : 65535		E / P
MTR.JM	Motor Inertia	0.01 Kg-cm^2	1 : 65535		E / P
MTR.MPLS	Motor number of poles		1 : 65535		E / P
MTR.RES	Motor resistance	0.01 Ohm	1 : 65535		E / P
MTR.KT	Motor torque constant (torque to RMS phase current)	0.001 Nm/A	1 : 65535		E / P
MTR.KV	Motor bemf constant	V/1000RPM	1 : 65535		E / P
MTR.NAME	Motor string name in ASCII characters		ASCII char		E / P

Drive Parameters (typical DRV. prefixed)

Command	Description	Units	Range	Default	E² / Par. set
DRV.BUSAPP	Application bus voltage	V	Unsign. Int.		E / P
DRV.BUSOV	Application bus over voltage	V	Unsign. Int.		E / P
DRV.BUSV	Drive Bus voltage	V	Unsign. Int.		E / P
DRV.I2T	I2t warning time	0.01 s	100 : 300		E / P
DRV.ID	Drive ID (EEPROM value) to be checked against power ID (dip switch) in case of Version Error (“U”)		Unsign. Int.		E / P
DRV.IDX	DBSC Setup library index		Unsign. Int.		E / P
DRV.INOM	Drive nominal current	0.1 A	Unsign. Int.		E / P
DRV.IPEAK	Drive peak current	0.1 A	Unsign. Int.		E / P

Additional System parameters (mostly SYS.* prefixed)

Velocity Feedback Parameters:

Command	Description	Units	Range	Default	E² / Par. set
MTR.RPLS	Resolver number of poles	–	1 : 65535		E / P
SYS.ENCRES	Queries / updates encoder feedback resolution for encoder motors (in pulses per revolution, i.e. before quadrature)	pulses/rev.	1 : 16384		E / P
SYS.ENCTBL	Queries encoder motor hall table type.	–	0 : 2		E / P

* Firmware versions RES–1.xx, ENC–1.xx only

Encoder Simulation Output Parameter:

Command	Description	Units	Range	Default	E² / Par. set
SYS.ENC	Encoder simulation resolution. Range depends on maximum velocity (VEL.MXRPM) Up to 1500 RPM: 512 :4096; above 1500 RPM: 512 only. Downward versions to 80112d1000, (incl.) also provide the decimal values.	Puls/Rev.	512 : 1024 (2048 : 4096) (500, 1000 1250, 1500)		E /

Software Limit Switches Parameters:

Command	Description	Units	Range	Default	E² / Par. set
LIM.CCW	Absolute Position of Software Limit Switch CCW (related to Home, activated after Homing only)	Counts	–Limit:Limit 1	0	E /
LIM.CW	Absolute Position of Software Limit Switch CW (related to Home, activated after Homing only)	Counts	–Limit:Limit 1	0	E /
LIM.ON	Deactivate / activate Software Limit Switches (independent from Hardware Limit Switches)	–	0 (off) 1 (on)	0	E /

Units depend on Resolver and Encoder resolution

Variables: NONE

Software Limit Switches Methods:

Command	Description	Parameter	Units	Range
LIM.LRN	Take actual position as software limit for CW and CCW respectively	0: CW 1: CCW	–	0 : 1

PLC Parameters:

Command	Description	Units	Range	Default	E² / Par. set
PLC.LINE	Defines PLC statement :IF [input]=TRUE, THEN [action] set/started, with syntax PLC.LINE [num] [action] [input] [num] [action] – PLC line number, and string parameter for PLC action, fixed to line number: 0 “ENABLE” (PLC enable) 1 “MAO1” (Digital Input MAO1) 2 “MAO2” (Digital Input MAO2) 3 “MAO3” (Digital Input MAO3, if available) 4 “MAO4” (Digital Input MAO4, if available) 5 “RELAY” 6 “USRERR” (Error “9”) 7 “FRST” (Fault Reset) 8 “DISA” Disable drive actively (brake to stop then disable) 9 “DISP” Disable drive passively (disable and coast to stop) 10 “HOLD” Stop drive and hold position 11 “JOG” (see JOG parameters at end of this section) 12 “GEAR” (see Position Controller at end of this section) [input] – string parameter with enumerated values: “FALSE”: Always false, i.e. switched off “CW”, “CCW”: Hardware or Software Limit Switches “MAI1”, “MAI2 ”: Digital Inputs “MAI3”, “MAI4”: Digital Inputs (if available) “DRVOT”,“MTROT”: Drive respectively motor overtemperature “I2tWRN”: I²T–warning (error “7”) “TRUE”: Always true, i.e. switched ON “INPOS”, “FEWRN”, “FEFAT”: Flags of Position Controller in position, following error warning, following error limit “BADMOV”: Not initialized motion buffer line commanded “MOTRDY”, “MOTNRDY”: Positioning finished respectively in process (see PTP Mode at end of this section)	num: 0 : 12 action: s. left lines: input: s. left lines:	PLC disabled, all lines: input = false		E / P

Note: Choice of Inputs and Outputs is not completely available in all configurations

Variables: NONE

PLC Methods:

Command	Description	Parameter	Units	Range
PLC	Enables (“on”) / disables (“off”) / clears and disables (“clr”) PLC. PLC on and off command is stored in PLC buffer line 0.	“on”, (“off”), “clr”		

OCI Interface Parameters:

Command	Description	Units	Range	Default Significant	E² / Par. set
CAN.BD	(The range check is: Invalid execute context.) It should be: “Range error”	Hz	10 : 1000	OK	
CAN.ID	(The range check is: Invalid execute context.)	–	1 : 127	OK	

Digital Interface Parameters:

Command	Description	Units	Range	Default	E² / Par. set
MOT.INCCW	Defines digital Input CCW/MAI4 as CCW (0) or as MAI4 (1) for positioning	–	0 : 1	0	E / P
MOT.INCW	Defines digital Input CW/MAI3 as CW (0) or as MAI3 for positioning	–	0 : 1	0	E / P

Analog Interface Parameters:

Command	Description	Units	Range	Default	E² / Par. set
SYS.RFOFS (RFOFS)	Query / updates system reference offset of the analog input, with analog input range ±10V (RFOFS only supports query)	mV	–100000 : 100000	0	E / –

Note: Scaling of the analog input command is offered with firmware versions RES–1.xx, ENC–1.xx. Because scaling parameters are different for current mode and velocity mode, these parameters are described under 0 (current command scaling) respectively 0 (velocity command scaling).

System Variables

General Variables:

Command	Description	Units	Range	Default	E² / Par. set
DRV.LIFE	Drive life time.	Hrs	Unsign.Word		E / –
SYS.STTS	Queries system status as a double word, where Word High word is drive address (set by Dip switches) Low word: bit array “OR”ed with system status: 0x0001: Disable SW 0x0002: Disable HW 0x0004: CW 0x0008: CCW 0x0010: Fault exists 0x0020: Warning exits 0x0040: Hold mode 0x0080: Burn in Status 0x0100: Jog Status 0x0200: Enable 0x0400: Jog Non Zero Velocity 0x0800: n/a 0x1000: HW source for Disable HW: 0x2000: PLC active	–	Long Word		– / –

Queries / modifications of Fault Listing Variables:

Command	Description	Units	Range	Default	E² / Par. set
FAULT	Gets system fault string list, response is multiple string X1	–	See X1 Possible Faults		– / –
FLT	Gets system fault string list, response is error numberX1	–			– / –
LOG, LG	Gets system fault log list X1	–			– / –
LG	Gets system fault log number list X1	–			– / –
WRN	Gets system warning list as multiple strings	–			– / –
SYS.FAULT	Queries system fault as ID of the most significant fault	–			– / –
SYS.WRN	Queries system warnings. The most important warning will be reported as ID	–			– / –

X1 Possible Faults

X1 Fault	Display	Description
1	"USER ERROR"	PLC user generated error. Displays '9'.
2	"OVERCURRENT"	Over current. Displays '3'.
3	"OVERVOLTAGE"	Bus over voltage. Displays '1'.
4	"FEEDBACK"	Resolver/encoder position feedback error. Displays '5'.
5	"POWER_FAIL"	Power fail. Displays '2'.
6	"BPS"	BPS fail. Displays '2'.
7	"OVER_15_VOLTAGE"	±15v over voltage. +15v line is more then 17v or –15v line is more than –17v. Displays '4'.
8	"UNDER_15_VOLTAGE"	±15v under voltage. +15v line is less then 12v or –15v line is less than –12v. Displays '4'.
9	"EEPROM_ERROR"	N.I
10	"EPROM_ERROR"	N.I
11	"RAM_ERROR"	RAM integrity error. Displays '9'.
12	"FAULT_RELAY"	when fault relay is closed. Displays '9'.
13	"EAF"	N.I
14	"MISSING INT"	N.I
15	"POWER_ID"	DRV.ID != SYS.POWER. Displays 'u'.
16	"CW_CCW"	Both limit switches are on. Displays 'L'.
17	"DESIGN_FAILURE"	Control design fail. Displays 'c'.
18	"EE_CLEARED"	EEPROM header stamp was not detected. Displays 'U'
19	"EE_INTEGRITY"	EEPROM footer stamp was not detected. Displays 'A'.
20	"EAF Drive Temp"	EAF drive over temperature error. Displays '6'.
21	"EAF Motor Temp"	EAF motor over temperature error. Displays '6'.
22	"EAF Drive I2T"	EAF drive I^2T error. Displays '6'.
23	"EAF Motor I2T"	EAF motor I^2T error. Displays '6'.

Methods:

Command	Description	Parameter	Units	Range
FRST	Resets system faults if allowed. Reset is not allowed, if error is still pending.	–	–	–
LOGRST	Resets system fault log.	–	–	–

Communication Settings

Parameter:

Command	Description	Units	Range	Default	E² / Par. set
ECHO	Disable / enable echoing for input characters	–	“ON/OFF	“ON”	– / –
PROMPT	Enables / disables terminal prompt	–	“ON/OFF	“ON”	– / –
TALK	Enables / Disables terminal error notification	–	“ON/OFF	“ON”	– / –

Variable:

Command	Description	Units	Range	Default	E² / Par. set
COM.STTS	Queries the most recent communication handler error	–	0:65535		– / –

Methods:

Command	Description	Parameter	Units	Range
B	Opens communication to the drive, called by its address (the addresses a constant, which can be queried by COM.ADDR or SYS.STTS)	Address	–	0 : 7

Queries of System Variables, Status, Faults

Single Values:

Command	Description	Units	Range	Default	E² / Par. set
ACTU CUR.ACTU	Query for actual current U	0.01 A			– / –
ACTV CUR.ACTV	Query for actual current V	0.01 A			– / –
ANAIN SYS.ANAIN	Query for analog input	mV			– / –
POS, RPOS,	Queries motor position				– / –
SYS.POS POS.POS	Resolver bits / encoder counts				– / –
VEL VEL.VEL	Query feedback velocity	RPM			

Data Record (REC. prefixed) Parameters:

Command	Description	Units	Range	Default	E² / Par. set
REC.GAP	Specify gap between recording samples in number of servo loops (0.5 ms)	–	0 : 65535	1	E / –
REC.TIME	Specify recording time	0.5 ms	1:65535	1000	– / –
REC.VAR1, REC.VAR2	Specify recording variable: “POS”: position, “REF”: velocity command, “VEL”: velocity, “CUR”: current command, “ACTU”: current U, “ACTV”: current V, “FE”: position following error.	–	s. left	“POS” “VEL”	– / –

Data Record (REC. prefixed) Variable:

Command	Description	Units	Range	Default	E² / Par. set
REC.VFREE1	Specify recording address for REC.VAR1	–	Unsign.Long		– / –
REC.VFREE1	Specify recording address for REC.VAR2	–	Unsign.Long		– / –

Methods:

Command	Description	Parameter	Units	Range
GETD	Gets data from recording buffer in decimal form.	–	–	–
GETX	Gets data from recording buffer in hex form, data buffer is cleared afterwards	–	–	–
REC	Starts(“on”) / stops (“off”) recording process	start / stop	–	“on”, “off”

Memory related methods (Queries / modifications):

RAM related:

Command	Description	Parameter	Range
BDUMP	Gets hexadecimal memory dump in bytes	Memory address	Unsign.Int.
BMEMH	Query / Update memory byte in hex	Memory address	Unsign.Int.
BMEMD	Query / Update memory byte in dec	Memory address	Unsign.Int.
WDUMP	Get hexadecimal memory dump in words	Memory address	Unsign.Int.
WMEMH	Query / update hexadecimal word memory location	Memory address	Unsign.Int.
WMEMD	Query / update decimal word memory	Memory address	Unsign.Int.

EEPROM related:

Command	Description	Parameter	Range
CLEAR	Clear EEPROM content and drive life time variable by filling it with 0xFFFF (except code for Level I/II; Baldor/HD)		
EEDUMP	Display all EEPROM data (256 words).		
UP	Uploads EEPROM data to terminal (ASCII file)		

Operation Mode Control

Normal Modes Parameters:

Command	Description	Units	Range	Default	E^2 / Par. set
SYS.MOD	Queries / updates system operating mode	–	0 : 3	1	E / P
MODE	Where 0 – current, 1 – velocity, 2 – position				

Normal Modes Variables:

Command	Description	Units	Range	Default	E^2 / Par. set
STATUS	Queries drive status: DIS_HW, DIS_SW, ENABLE, BURN_IN, FAULT	–			– / –

Normal Modes Methods:

Command	Description	Parameter	Units	Range
DISP	Disables drive passively, disable drive and coast to stop			
DISA	Disables drive actively, brake to stop then disable control			
ENA	Enables drive			
HOLD	Stops drive and maintains position after stop			
QUIT	Stops drive and maintains position after stop			
STOP	Stops drive and maintains position after stop (CONT will resume the interrupted move)			
CONT	Continues interrupted move (interrupted by STOP)			

Note: In velocity and current mode, braking is with acceleration=zero.
In positioning mode (SYS.MOD 3), braking is with acceleration=MOT.ACC.

Sys.mod 0:

Current mode Parameters:

Command	Description	Units	Range	Default	E^2 / Par. set
CUR.BEMF	Back EMF voltage compensation, in percentage of nominal motor value Ke.	%	80 : 120	100	E / P
CUR.IPEAK	Queries / updates application peak current in percentage of DRV.IPEAK	%	0 : 1000	100	E / P
CUR.INOM	Queries / updates application nominal current in percentage of DRV.IPEAK	%	0 : 500	50	E / P
CUR.TOFR	Queries / updates mantissa of Torque Optimizer: Phase Advance or BEMF Compensation		0x0f00 : 0x1100		E / P
CUR.TOSH	Queries / updates Torque Optimizer Shift coefficient		16		E / P
CUR.SCAL	Corresponding current value to analog input voltage CUR.VOLT for setting of analog input scaling	0.1 % of CUR.IP	100 : 10000	1000	E / P
CUR.VOLT	Corresponding analog input voltage to current value CUR.SCAL for setting of analog input scaling	0.1 VEAK	1 : 100	100	E / P

Current mode Variables:

Command	Description	Units	Range	Default	E^2 / Par. set
CUR.CUR	Query for actual current command		0 : 65535		E / –
CUR					

Current mode Methods:

Command	Description	Parameter	Units	Range
CALC	Calculate current control parameters from MTR.*, DRV.* and CUR.* parameters.	torque equivalent	mV	–10000 : 10000
T	Commanding digital current command (torque equivalent)			
TS	Stops current commanded motion (started by T“command”)			

Sys.mod 1

Velocity mode Parameters:

Command	Description	Units	Range	Default	E² / Par. set
VEL.ACC	Queries /updates velocity acceleration limits (time to max. velocity).	RPM/ms	0 : 7500		E / P
VEL.ADZON	Queries / updates min. velocity in RPM	RPM	0 : Max_RPM		E / P
VEL.BW	Queries / updates velocity control band width	Hz	10 : 200		E / P
VEL.CTRL	Queries / updates velocity control type		0, 2		E / P
VEL.GV	Queries / updates velocity control proportional gain		0 : 32767		E / P
VEL.GVI	Queries / updates velocity control integral gain		0 : 32767		E / P
VEL.INRT	Load inertial, set in % of motor inertia MTR.JM	%	0 : 10000		E / P
VEL.LPFA	Bandwidth of single velocity control filter.	Hz	20 : 800	500	E / P
VEL.LPFB	Second Bandwidth of double velocity control filter (First s. VEL.LPFA).	Hz	20 : 800	500	E / P
VEL.LPFMOD	Type of velocity control filter (0: no filter, 1: filter with bandwidth VEL.LPFA, 2: double filter with bandwidths VEL.LPFA and VEL.LPFB	–	0 : 20	0	E / P
VEL.TRKFCT	Queries / updates velocity control tracking factor		–32768 : 32767		E / P
VEL.MXRPM	Queries / updates velocity control MAX RPM value. The limit for this value is internally calculated by the Application Bus Voltage and the Motor Voltage Constant. Absolute limit for velocity is 7500 RPM.	RPM	1000 : (7500)		E / P
VEL.SCAL	Corresponding velocity value to analog input voltage VEL.VOLT for setting of analog input scaling.	RPM	100 : 32767		E / P
VEL.VOLT	Corresponding analog input voltage to velocity value VEL.SCAL for setting of analog input scaling	0.1 V	1 : 100		E / P

Velocity mode Variables:

Command	Description	Units	Range	Default	E² / Par. set
VEL.VREF	Queries velocity reference, commanded at analog input	RPM			– / –
VREF					– / –

Velocity mode Methods:

Command	Description	Parameter	Units	Range
VCRST	Velocity controller parameters reset to default values: Pole Placement controller: BW = 20 Hz, TRFCT = 0 , INRT = 0; PI controller: GV, GVI equivalent to Bandwidth 20 Hz			

Jog

Parameters:

Command	Description	Units	Range	Default	E² / Par. set
JOG.TIME	Jog time in milliseconds	ms	3432448		E / –
JOG.TYPE	0 – continuous, 1 – step, 2 – square wave	–	0 : 2		E / –
JOG.VEL	Jog velocity in RPM, limited to maximum velocity VEL.MXRPM.		VEL.MXRPM		E / –

Methods:

Command	Description	Parameter	Units	Range
JOG	Commanding a Jog according to JOG.* parameters, with	Direction	–	“+”, “–”
JS	Stops jog and returns to previous operation mode	–	–	–

Position Controller

Position Controller Parameters:

Command	Description	Units	Range	Default	E² / Par. set
POS.FFA	Queries/updates acceleration FF factor unsigned integer ranged 0..100	–	25 : 100		E / P
POS.FFTYPE	Queries / updates FF type with position controller redesign 0 – FF none, 1 – velocity FF, 2 – acceleration FF	–	0 : 2		E / P
POS.FFV	Queries / updates velocity FF factor unsigned integer ranged within 0..100	–	25 : 100		E / P
POS.KP	Queries / updates position gain unsigned integer ranged within 25.. 200	–	25 : 100		E / P
POS.FEWRN	Queries / updates FE warning limits resolver: 1/4096 of revolution, encoder: 1/(4*SYS.encres) of revolution integer, > 0 (< 0: disabled)	1/4096 (resolver) 1/(4*SYS.encres) encoder	–32768 : 32767		E / P
POS.FEFAT	Queries / updates FE fatal limits 1/4096 of revolution, integer,	1/4096 of revolution	–32768 : 32767		E / P
POS.IPOS	Queries / updates FE in position limits 1/4096 of revolution, integer, > 0 (< 0: disabled)	1/4096 of revolution	–32768 : 32767		E / P

Variables:

Command	Description	Units	Range	Default	E² / Par. set
POS.MPFE	Queries maximum position following error	1/4096 of rev.			– / –
MPFE					– / –
POS.PFE	Queries position following error	1/4096 of rev.			– / –
PFE					– / –
PREF	Queries for position reference	1/4096 of rev.			– / –
POS.REF	Queries position controller reference, 1/4096 of revolution	1/4096 of rev.			– / –
POS.FEST	Returns follow error status: 0 – normal, 1 – in position, 2 –warning, 3 – error	–	0 : 3		– / –
FEST					– / –

Methods:

Command	Description	Parameter	Units	Range
PRST	Resets position following error	–	–	–

Sys.mod 2: Pulse Follower (Handwheel respectively Pulse/Direction)

Parameters:

Command	Description	Units	Range	Default	E² / Par. set
HW.GRFX	Queries/updates mantissa HW gear parameter, negative value means negative gear.		–32767 : 32767		E / P
HW.GRSH	Queries/updates shift HW gear parameter		0 : 32767		E / P
HW.PLC	GEAR Queries/ updates PLC gear ratio		0 : 65535		E / P
HW.RES	Queries / updates HW resolution in pulses per revolution (only necessary for	pulses/rev.	–32768 : 32767		E / P
HW.TYPE	Queries / updates HW type: 0 – None, 1 – Pulse and Direction at connector X3, 2 – A leads B at connector X9, 3 – B leads A respectively, Pulse and Direction at connector X92, 4 – A leads B at connector X32		0 : 4 – resolver, 0 : 1 – encoder		E / P

Sys.mod 3: PTP mode

Parameters:

Command	Description	Units	Range	Default	E² / Par. set
MOT.ACC	MOTION acceleration and deceleration	RPM / 10msec	1 – 65535	23	E / P
MOT.BUF	With parameters [line] [position] [velocity] [acceleration], the motion buffer is initialized line by line. Query is done line by line by only adding the parameter [line]. Query of whole motion buffer can be done by BUFDUMP	line: – pos: vel: RPM acc:RPM/10msec	1–15 velocity: 0–7500 0–65535	line: – velocity: 0 0	E / P
MOT.BUFTYPE	Defines, whether buffered target positions are absolute or incremental: 0 – incremental; 1, 2 – absolute		0–2	1	E / P
MOT.DWELL	Queries / updates dwell time between the end of a running trajectory and the trajectory start of a stored move.	msec	0–65534	0	E / P
MOT.SRC	Defines source of motion command 0 – RS232 / CAN; 1 – digital input combination		0–1	0	E / P
MOT.TRIG	Defines trigger for motion start: 0 – immediate; 1 – rising edge at digital input TRIGGER		0–1	0	E / P
MOT.TYPE (ABS, INC)	Defines, whether motion to target position is absolute or incremental: 0 – incremental; I – absolute.		0–1	1	E / P
MOT.VEL	Queries / updates MOTION velocity, stored in MOT.INCW, MOT.INCCW	RPM	1–7499	1000	E / P

Variables:

Command	Description	Units	Range	Default	E² / Par. set
MOT.ABSPOS	Actual absolute position related to ZERO	count	±Limit		E / P
MOT.STATUS	Indicates the status of the motion process 0 – Ready to start move 1 – acceleration and constant velocity phase of trajectory 2 – deceleration phase of trajectory 3 – dwell state after finishing trajectory		0–5		E / P
MOT.GENPOS	Actual commanded position related to ZERO (following the trajectory in process)	count	±Limit		E / P

Methods:

Command	Description	Units	Range	Default	E² / Par. set
BUFDUMP	Reads out whole buffer lines				E / P
GO	Commands the buffered move (according to buffered target position, velocity, acceleration and buffer type), chosen by the parameter	line	1–15		E / P
LRN	Writes actual position, velocity MOT.VEL and acceleration MOT.ACC into the buffer line, chosen by the parameter	line	1–15		E / P
MOV	Executes motion according to previously defined motion type (ABS/INC), acceleration (PTP.ACC),cruise velocity (PTP.VEL	target position	±Limit		E / P
PLOAD	Load EEPROM values of MOT.ACC, MOT.VEL, MOT.TRIG, MOT.DWELL to actual ones (i.e. activate them)				E / P
PSAVE	Saves preset values of MOT.ACC, MOT.VEL, MOT.TRIG, MOT.DWELL into the EEPROM				E / P

Homing

Parameters:

Command	Description	Units	Range	Default	E^2 / Par. set
HOM.ACC	Queries / updates HOME acceleration	RPM/10msec	1–65535		E / P
HOM.VEL	Queries / updates homing velocity	RPM	±2500		E / P
HOM.TYPE	Queries / updates HOME type: 1 – ZERO is found by Home Flag (Resolver zero) 2 – ZERO position is captured at Home Flag edge 3 – Actual position is defined as ZERO		1–3		E / P
HOM.OFFSET	Queries / updates HOME offset	counts	±Limit		E / P
HOM.POLR	Queries / updates HOME switch polarity: 0 – active low, 1 – active high		0–1 (resolver) 0 (encoder)		E / P

Variables:

HOM.STATUS	0 – power up (i.e. homing not done yet) 2 – moving out of Home area (only, if HOME is commanded while the drive is standing in the Home area) 5 – moving in specified direction, waiting for Home Signal 10 – home motion finished (1, 3, 4, 6, 7, 8, 9 – in between status)		0–10		E / P

Methods:

HOME	Executes homing the drive according to previously defined parameters HOM.*, if motion command source is set to software (MOT.SRC=O)				E / P

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