

parkemPRESS

Example Interface of basic function

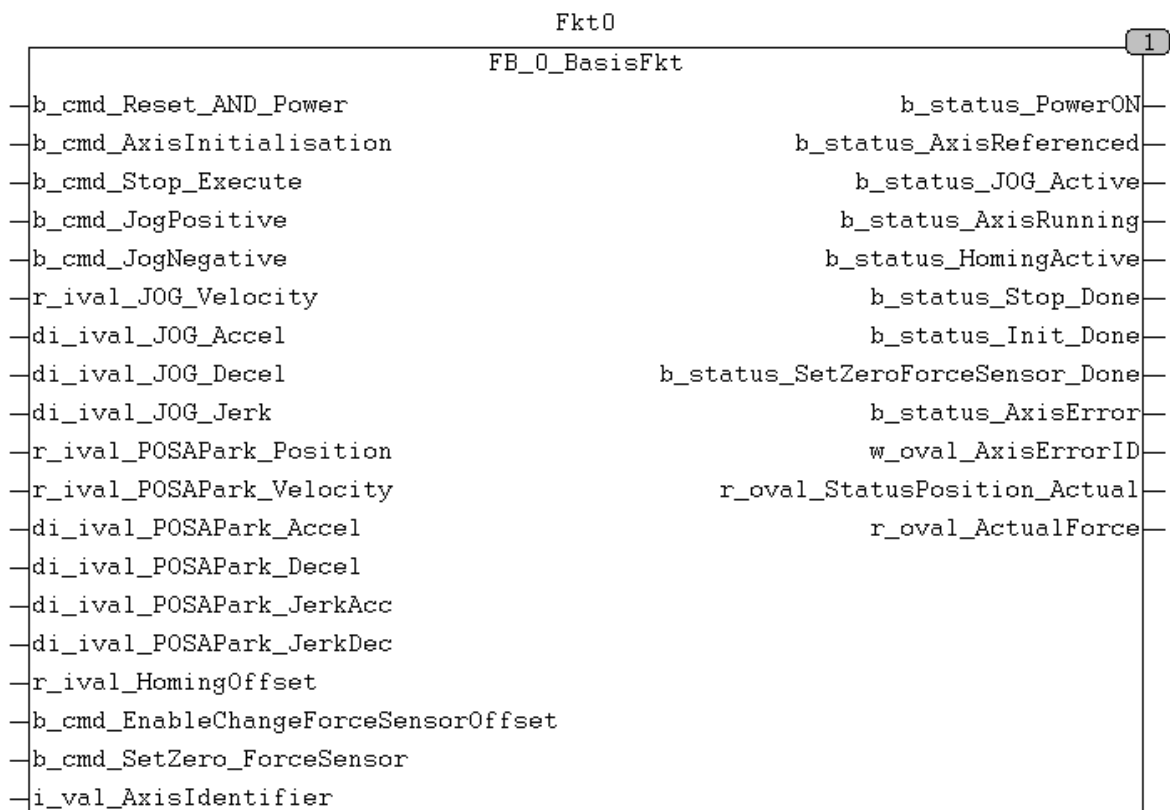


Basic functions

Function

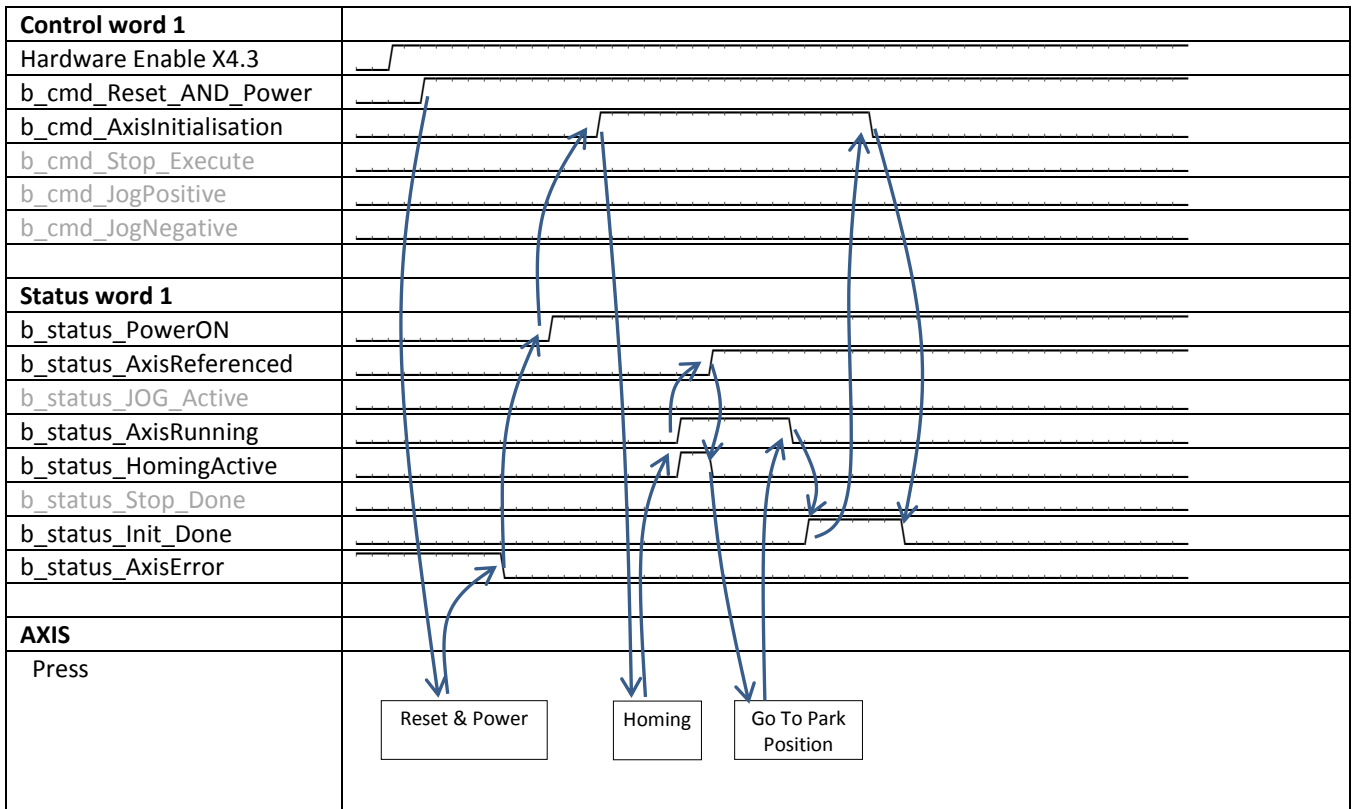
- Error-Reset and Power Motor
- Initialisation (Homing and Move to Park position)
- Jog positive / negative
- Set actual force to zero

Overview FB

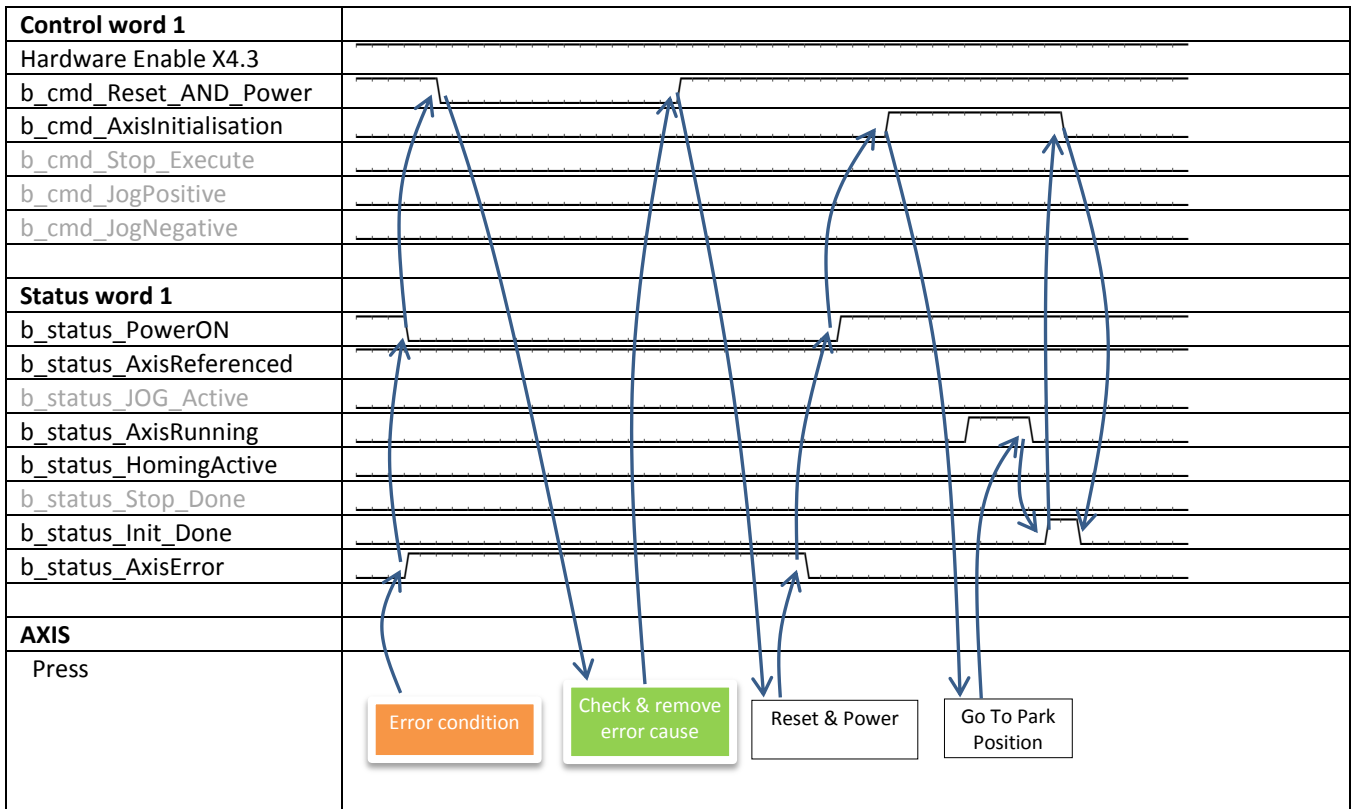


Control example with PLC

Example after power on



Example after axis error



Commands, Status and Parameter



Input Variable	Typ	Values	Unit	Description	Variable Array	Ethercat object nr	cyclic
Control word 1	WORD				Col04_Row01	Index: 0x2304 Sub 0x1	y
<i>b_cmd_Reset_AND_Power</i>	BOOL	0/1	-	Fault reset & Power on Motor if no Error	Control word 1 Bit 0		
<i>b_cmd_AxisInitialisation</i>	BOOL	0/1	-	Start Initialisation (Homing & Move to Park Position)	Control word 1 Bit 1		
<i>b_cmd_Stop_Execute</i>	BOOL	0/1	-	Stop Motion	Control word 1 Bit 2		
<i>b_cmd_JogPositive</i>	BOOL	0/1	-	Jog in positive direction as long as Input is HI	Control word 1 Bit 3		
<i>b_cmd_JogNegative</i>	BOOL	0/1	-	Jog in negative direction as long as Input is HI	Control word 1 Bit 4		
-	-	-	-	-	Control word 1 Bit 5		
-	-	-	-	-	Control word 1 Bit 6		
-	-	-	-	-	Control word 1 Bit 7		
-	-	-	-	-	Control word 1 Bit 8		
-	-	-	-	-	Control word 1 Bit 9		
<i>b_cmd_EnableChangeForceSensorOffset</i>	BOOL	0/1	-	If = HI then Force Sensor can be reseted	Control word 1 Bit 10		
<i>b_cmd_SetZero_ForceSensor</i>	BOOL	0/1	-	IF = HI and Enable = 1 Force Sensor value will be reseted	Control word 1 Bit 11		
-	-	-	-	-	Control word 1 Bit 12		
-	-	-	-	-	Control word 1 Bit 13		
-	-	-	-	-	Control word 1 Bit 14		
-	-	-	-	-	Control word 1 Bit 15		
<i>r_ival_JOG_Velocity</i>	REAL	0 ... +32678.000	mm/s	JOG Move Parameter: Velocity	Col02_Row01	Index: 0x2302 Sub 0x1	n
<i>di_ival_JOG_Accel</i>	DINT	0 ... 2'147'483'648	mm/s ²	JOG Move Parameter: Acceleration	Col06_Row01	Index: 0x2306 Sub 0x1	n
<i>di_ival_JOG_Decel</i>	DINT	0 ... 2'147'483'648	mm/s ²	JOG Move Parameter: Deceleration	Col07_Row01	Index: 0x2307 Sub 0x1	n
<i>di_ival_JOG_Jerk</i>	DINT	0 ... 2'147'483'648	mm/s ³	JOG Move Parameter: Jerk	Col08_Row01	Index: 0x2308 Sub 0x1	n
<i>r_ival_POSAPark_Position</i>	REAL	-32677.000 ... +32678.000	mm	ParkPosition Move Parameter: Position	Col01_Row03	Index: 0x2301 Sub 0x3	n
<i>r_ival_POSAPark_Velocity</i>	REAL	0 ... +32678.000	mm/s	ParkPosition Move Parameter: Velocity	Col02_Row03	Index: 0x2302 Sub 0x3	n
<i>di_ival_POSAPark_Accel</i>	DINT	0 ... 2'147'483'648	mm/s ²	ParkPosition Move Parameter: Acceleration	Col06_Row03	Index: 0x2306 Sub 0x3	n
<i>di_ival_POSAPark_Decel</i>	DINT	0 ... 2'147'483'648	mm/s ²	ParkPosition Move Parameter: Deceleration	Col07_Row03	Index: 0x2307 Sub 0x3	n
<i>di_ival_POSAPark_JerkAcc</i>	DINT	0 ... 2'147'483'648	mm/s ³	ParkPosition Move Parameter: Jerk Acceleration	Col08_Row03	Index: 0x2308 Sub 0x3	n
<i>di_ival_POSAPark_JerkDec</i>	DINT	0 ... 2'147'483'648	mm/s ³	ParkPosition Move Parameter: Jerk Deceleration	Col09_Row03	Index: 0x2309 Sub 0x3	n
<i>r_ival_HomingOffset</i>	REAL	-32677.000 ... +32678.000	mm	Homing Offset, base is real homing position	Col01_Row02	Index: 0x2301 Sub 0x2	n
<i>i_val_AxisIdentifier</i>	INT	AXIS_REF_LocalAxis	-	Compax3 internal Axis Identifier	internal		



Output Variable	Typ	Values	Unit	Description	Variable Array	Ethercat object nr	cyclic
Status word 1	WORD				Col05_Row01	Index: 0x2305 Sub 0x1	y
<i>b_status_PowerON</i>	BOOL	0/1	-	1 = Motor is powered	Status word 1 Bit 0		
<i>b_status_AxisReferenced</i>	BOOL	0/1	-	1 = Axis was referenced or Motor with Absolute Encoder	Status word 1 Bit 1		
<i>b_status_JOG_Active</i>	BOOL	0/1	-	1 = Jog Move is active	Status word 1 Bit 2		
<i>b_status_AxisRunning</i>	BOOL	0/1	-	1 = An axis movement is active	Status word 1 Bit 3		
<i>b_status_HomingActive</i>	BOOL	0/1	-	1 = Homing routine is active	Status word 1 Bit 4		
<i>b_status_Stop_Done</i>	BOOL	0/1	-	1 = Stop Done	Status word 1 Bit 5		
<i>b_status_Init_Done</i>	BOOL	0/1	-	1 = Init Done	Status word 1 Bit 6		
<i>b_status_SetZeroForceSensor_Done</i>	BOOL	0/1	-	1 = SetZeroForce of Sensor Done	Status word 1 Bit 7		
<i>b_status_AxisError</i>	BOOL	0/1	-	1 = Drive is in Error state	Status word 1 Bit 8		
-	-	-	-	-	Status word 1 Bit 9		
-	-	-	-	-	Status word 1 Bit 10		
-	-	-	-	-	Status word 1 Bit 11		
-	-	-	-	-	Status word 1 Bit 12		
-	-	-	-	-	Status word 1 Bit 13		
-	-	-	-	-	Status word 1 Bit 14		
-	-	-	-	-	Status word 1 Bit 15		
<i>w_oval_AxisErrorID</i>	WORD	0 ... FFFF	-	Drive Fault description number	Col05_Row02	Index: 0x2305 Sub 0x2	y
<i>r_oval_StatusPosition_Actual</i>	REAL	-32677.000 ... +32678.000	mm	Actual position value	Col01_Row04	Index: 0x2301 Sub 0x4	y
<i>r_oval_ActualForce</i>	REAL	-32677.000 ... +32678.000	N	Actual force value	Col02_Row04	Index: 0x2302 Sub 0x4	y