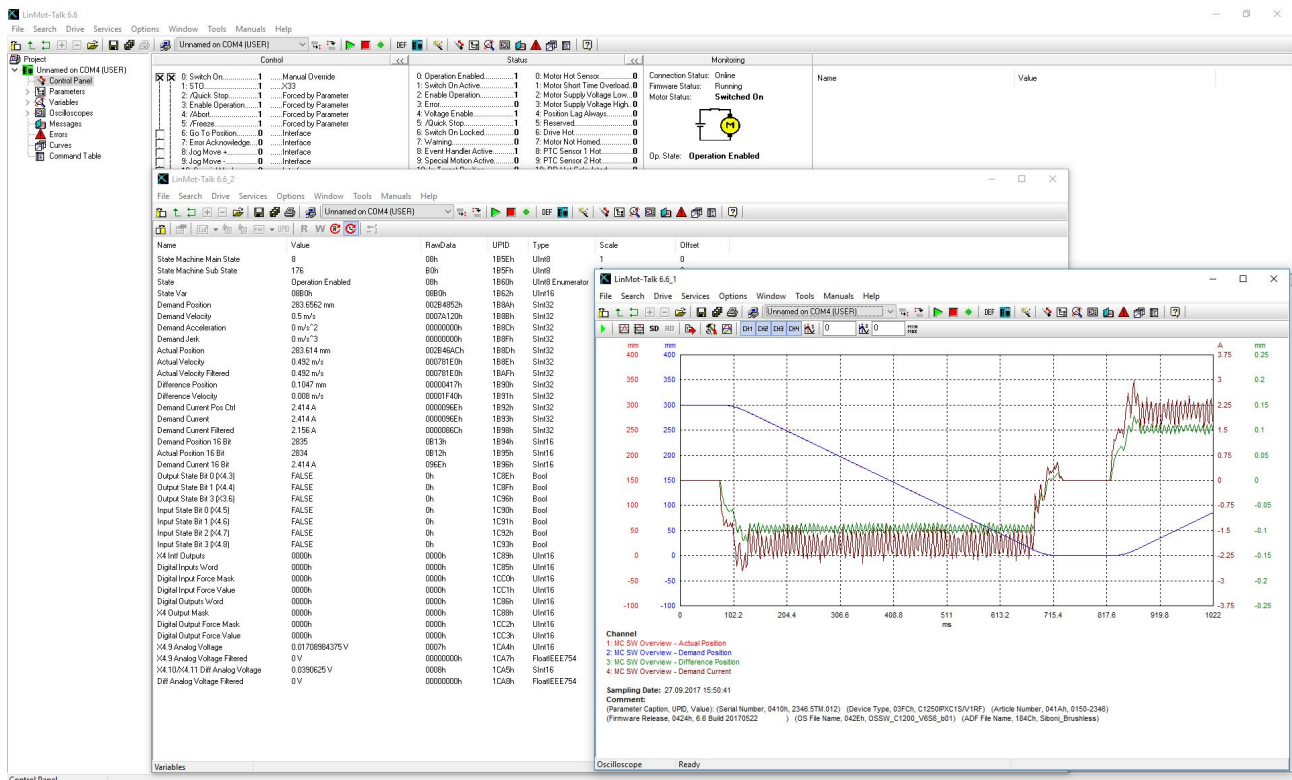


# LinMot-Talk 6 Configuration Software

## Manual



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#### Note

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# 1 Introduction

The LinMot-Talk 6 software is a PC based tool, which helps the user in a comfortable way [installing firmware](#) on the drive, setting up the drive's configuration, defining and programming motion profiles, emulating the PLC, watching variables and reading messages and errors. The LinMot-Talk 6 works with the drive series A1100, B1100, C1100, E1100, C1200, E1200, E1400 and B8050. It replaces the LinMot-Talk1100 software. For the rest of this document and all other documents, the more general term "LinMot-Talk" will be used for the Linmot- PC configuration software.

## 1.1 System Generation (SG)

The LinMot drive families are based on different hardware platforms, which are called system generations. The abbreviation is "SG". Whereas differences of hardware of software functionality exist between the system generations, the documentation is marked with the "SG" term. The following table gives an overview of which drive family belongs to which SG:

SG	Drives
SG1	Families E400, E4000 V1 (not supported by LinMot-Talk 6)
SG2	Families E400, E4000 V2 (not supported by LinMot-Talk 6)
SG3	Family E1100 (GP, CO, DN, DP) (LC/HC/XC)
SG4	Family B1100 (VF, PP, GP, ML) (LC/HC/XC)
SG5	Family E1200 (GP, DP, DS, EC, IP, PD, PL, PN, SC, SE) Family E1400 (GP, DP, DS, EC, IP, PD, PL, PN, SC, SE) (0S/1S) Family B8000-ML (GP, EC, IP, PL, SC)
SG6	Family C1250 (DS, EC, IP, PD, PL, PN, SC, SE) (0S/1S) Family E1400V2 (GP, DP, DS, EC, IP, PD, PL, PN, SC, SE) (0S/1S)
SG7	Family A1100 Family C1100 (GP, DS, EC, PD, PN, SE) (0S/1S)

## 1.2 UPID (Unique Parameter ID)

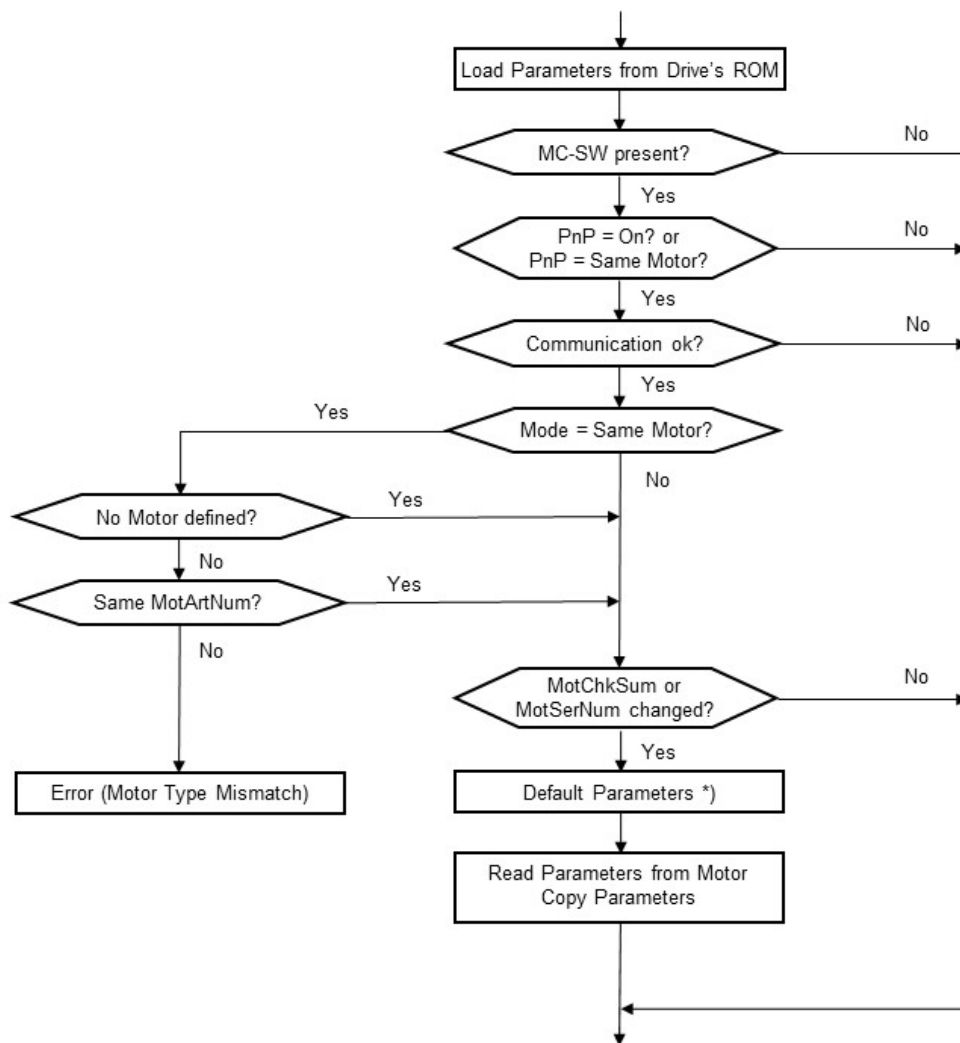
All parameters have an assigned identification number, which is called a UPID (Unique Parameter ID). All parameters are accessed on the drive over this identification.

## 1.3 PnP (Plug and Play)

The drive families A1100, C1100, C1200, E1200 and E1400 support the so called „Plug and Play“ functionality. When a motor is connected to the drive, the motor will be automatically detected and the parameters will be set accordingly. The drive then can control the motor without any further configuration procedure. When starting the motor wizard, the connected motor is already selected and all the further configuration, such as exact slider, moving mass, friction etc can be set up.

All components (drives and motors) which support the plug and play functionality are marked on the type label with "PnP".

The drive startup sequence is the following:

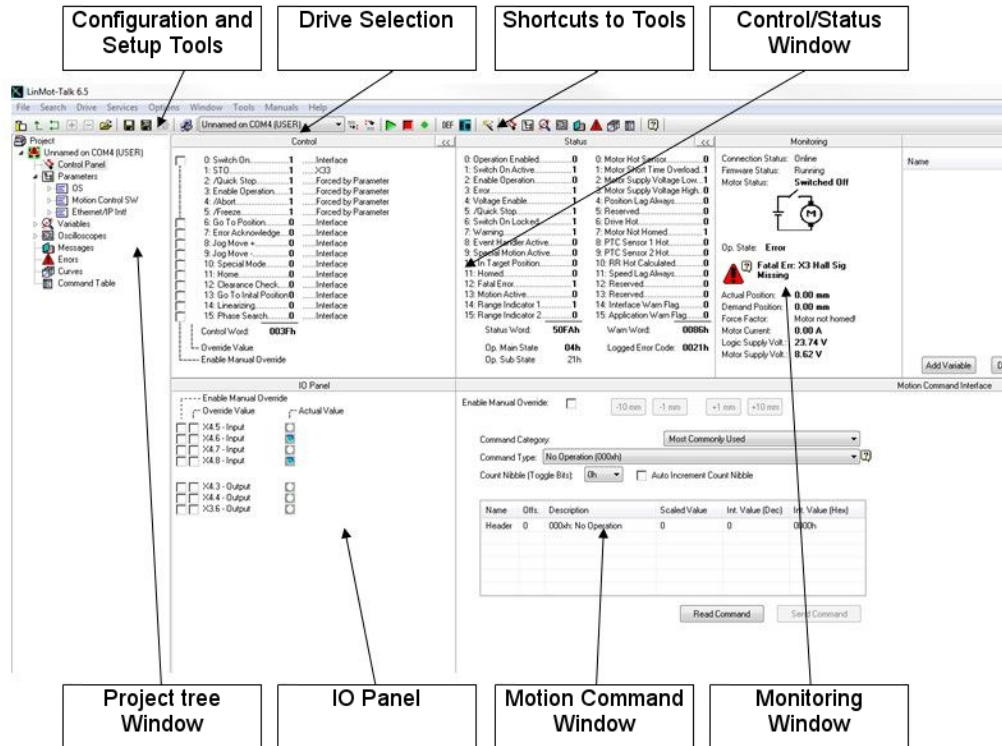


\*) All parameters, which are set by the previous PnP motor and do not exist in the new motor will be set to default values prior to load the new parameters.

## 2 Overview

The most used functions after a start of the LinMot-Talk software is [Install firmware](#) or [Login to a drive](#).

The following screenshot gives an overview of the different functions integrated in the LinMot-Talk software. The Configuration and Setup Tools the Drive Selection and the Shortcuts to Tools are in the [tool button bar](#). In the [control panel](#) are the Control/Status Window, the IO Panel, the Motion Command Window and the Monitoring Window.


















### 2.1 Tool button bar



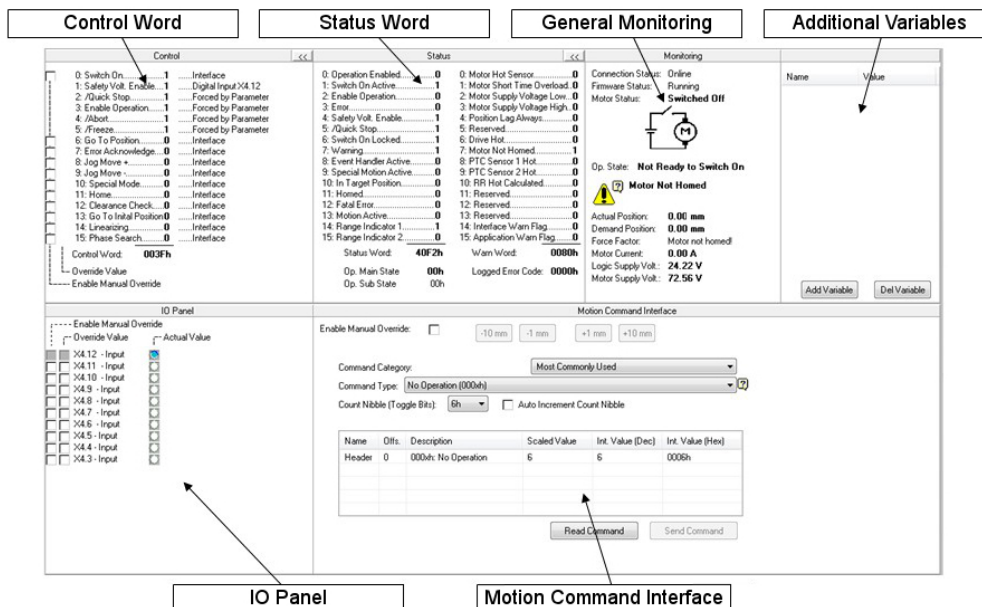
The tool button bar is always present and consists of the following buttons (from left):

- Show/Hide Tree shows or hides the project tree window.
- Up sets the focus in the project tree to the parent of the selection.
- Toggle toggles between the last two displayed tree branches.
- [Import Configuration](#) imports configurations to the drives.
- [Export Configuration](#) exports configurations. Different drives and parts, such as parameters, variables, oscilloscope or curves, can be selected to be exported.
- Print prints items like curves, parameter configurations etc.
- [Install Firmware](#) Start the drive's firmware installation.
- Open Login, login to all drives in the selected workspace.
- Save Login, save the actual workspace
- Reboot restarts the firmware on the drive.
- Stop stops the firmware on the drive, used for downloading and software configuration.
- Blink sends a blink LED command to the drive, which is selected.

-  **Default:** Parameters can be defaulted by instances. With this button, the default parameter procedure is started. A window will be shown where the instances (OS, MC, INTF and APPL software) can be selected. All parameters of the selected instances will be set to their default value.
-  **Go Offline** logs out from actual drive.
-  [Start Motor Wizard](#) starts the motor configuration setup wizard.
-  [Show Control Panel](#) switches to the control panel.
-  [Show Parameters](#) switches to the variables.
-  [Show Variables](#) switches to the variables.
-  [Show Oscilloscope](#) switches to the oscilloscope.
-  [Show Messages](#) switch to the message viewer.
-  [Show Errors](#) switches to error viewer.
-  [Show Curves](#) switches to the curve tool.
-  [Show Command Table](#) switches to the command table editor.
-  **Show Object Inspector** displays a window in which shows help information to each selected object.
-  Shows one decimal place more, for numbers like variable values. This button is only activated when the option "Round the decimal places" is activated.
-  Shows one decimal place less, for numbers like variable values. This button is only activated when the option "Round the decimal places" is activated.
-  Activates the [Information Window](#). This window will be showed on the bottom of the LinMot-Talk when there is a message inside and it is activated.

## 2.2 Control Panel

The Control Panel helps the user to access directly to the control and status word of the MC Software. The drive can be commanded from the PC, thus no PLC is necessary to be used for the first commissioning.



The screenshot displays the LinMot Control Panel interface, divided into four main sections:

- Control Word:** Lists 15 control words (0-15) with their current values and descriptions. For example, '0: Switch On' is set to 1, and '15: Phase Search' is set to 0.
- Status Word:** Lists 15 status words (0-15) with their current values. For example, '0: Operation Enabled' is 0, and '15: Application Warn Flag' is 0.
- General Monitoring:** Shows connection status (Online), firmware status (Running), and motor status (Switched Off). It also displays 'Op. State: Not Ready to Switch On' and 'Motor Not Homed' warnings.
- Additional Variables:** A table for monitoring variables with columns for Name, Offs, Description, Scaled Value, Int. Value (Dec), and Int. Value (Hex).

At the bottom, there are two main control areas:

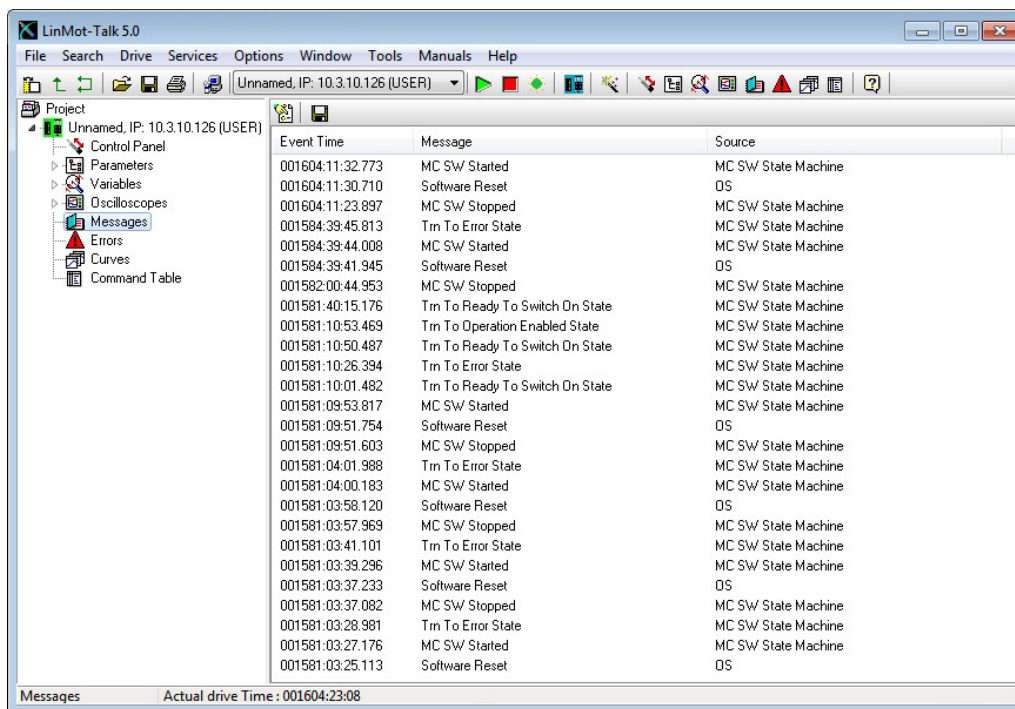
- IO Panel:** A list of digital inputs (X4.12 to X4.3) with checkboxes for their states.
- Motion Command Interface:** Includes an 'Enable Manual Override' checkbox, a 'Command Category' dropdown (set to 'Most Commonly Used'), a 'Command Type' dropdown (set to 'No Operation (000h)'), and a 'Count Nibble (Toggle Bits)' dropdown (set to 'R4'). It also features 'Read Command' and 'Send Command' buttons.

- **Control Word** The MC software's control word can be directly written from the PC. For taking over the PC control the left check box (Enable Manual Override) must be selected. The state of each flag can be set with the right check box (Override Value). If other flags have to be altered, the override mask must be configured in the parameter tree under \Parameters\Motion Control SW\State Machine Setup\Control Word\Ctrl, Word Parameter Force Mask.

- **Status Word** The status word shows the actual state of the drive's MC software status word. It is updated automatically.
- **General Monitoring** This window displays actual motor and drive information
- **Additional Variables** In this window variables could be chosen, then they are shown in the list and would updated automatically.
- **IO Panel** For commissioning. The user can take control of the X4 IOs on E1100 or X14 IOs on B1100 drives.
- **Motion Command Interface** The MC software's motion command Interface can be directly accessed over this window. When enabled (Enable Manual Override switch must be set), MC commands can be selected, parametrized and sent to the drive. Because the motion command interface is, independent of the interface running on the drive, the same, the commands can be exactly tested before programming them in the PLC.

## 2.3 Messages

This panel reads out and shows all messages, which are logged on the drive, and displays them in chronological order. If logged in a B1100 series drive, this window does not appear, because those drives do not support message logging. To get some informations about a message, select the message and press F1, the object inspector will show some information about the selected message.



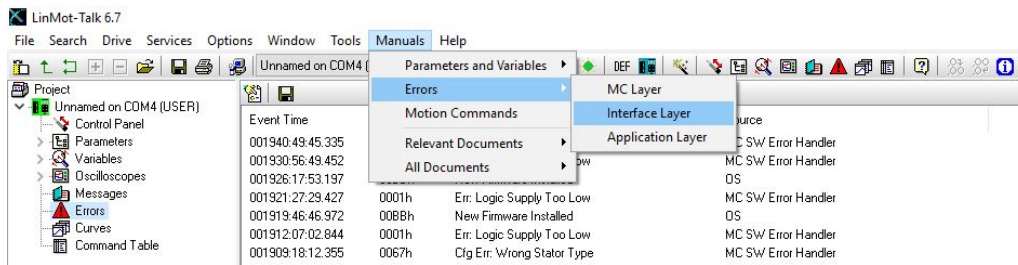
Event Time	Message	Source
001604:11:32.773	MC SW Started	MC SW State Machine
001604:11:30.710	Software Reset	OS
001604:11:23.897	MC SW Stopped	MC SW State Machine
001584:39:45.813	Tm To Error State	MC SW State Machine
001584:39:44.008	MC SW Started	MC SW State Machine
001584:39:41.945	Software Reset	OS
001582:00:44.953	MC SW Stopped	MC SW State Machine
001581:40:15.176	Tm To Ready To Switch On State	MC SW State Machine
001581:10:53.469	Tm To Operation Enabled State	MC SW State Machine
001581:10:50.487	Tm To Ready To Switch On State	MC SW State Machine
001581:10:26.394	Tm To Error State	MC SW State Machine
001581:10:01.482	Tm To Ready To Switch On State	MC SW State Machine
001581:09:53.817	MC SW Started	MC SW State Machine
001581:09:51.754	Software Reset	OS
001581:09:51.603	MC SW Stopped	MC SW State Machine
001581:04:01.988	Tm To Error State	MC SW State Machine
001581:04:00.183	MC SW Started	MC SW State Machine
001581:03:58.120	Software Reset	OS
001581:03:57.969	MC SW Stopped	MC SW State Machine
001581:03:41.101	Tm To Error State	MC SW State Machine
001581:03:39.296	MC SW Started	MC SW State Machine
001581:03:37.233	Software Reset	OS
001581:03:37.082	MC SW Stopped	MC SW State Machine
001581:03:28.981	Tm To Error State	MC SW State Machine
001581:03:27.176	MC SW Started	MC SW State Machine
001581:03:25.113	Software Reset	OS

Messages Actual drive Time : 001604:23:08

## 2.4 Errors

This panel reads out and shows all errors, which are logged on the drive and displays them in chronological order. Install new firmware will be logged because it is interesting if the error was before or after installing a new firmware.

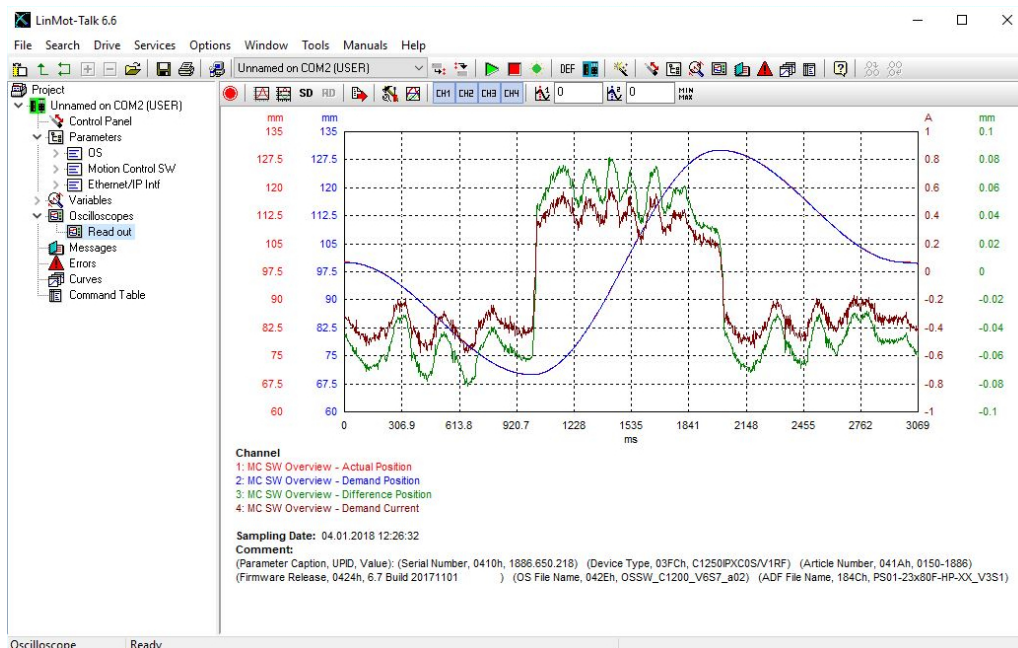
To receive more information about an error, select the error and press F1, the object inspector will show some information about the selected error. It is possible to get the information about all errors by generate an error list under Manuals -> Errors. The error list is a HTML Document and will open in a browser. There are error lists for every software layer. Therefore it is important to have a look on the source of an error. The source symbolises the layer where the error is explained.



## 2.5 Oscilloscope

The drive's built in oscilloscope, which can record up to eight channels in real time, is controlled with the oscilloscope tool.

During login the oscilloscope reads out the settings and data from the drive. If an oscilloscope shot is running or ready to read out data, an item called "Read out" will be displayed. Otherwise a default item will be generated.



The oscilloscope is controlled with the buttons



The functions are (from left):

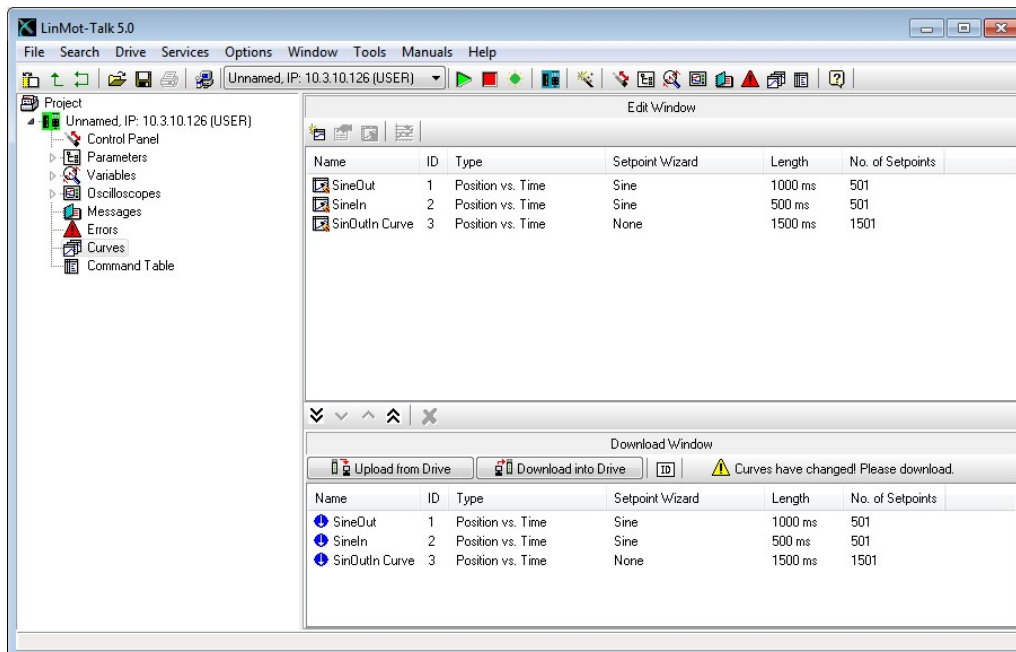
- **Start/Abort** Start or abort an oscilloscope shot. The button changes the symbol Abort the actual record. Abort the continuous mode and stop after the next record.
- **Fit View** Displays the recorded channels such as they fit best in the scope window.
- **Fit View (same unit same fit)** Displays the recorded channels such as the channels with the same unit have the same scaling and offset.
- **SD Save Display** stores the settings for zoom, scaling and offset.
- **RD Recall Display** restores the settings for zoom, scaling and offset, which are previously stored with Save Display.
- **Export Data:** Export data and setups of the last recorded oscilloscope shot in a csv file.
- **Oscilloscope Settings** Switch to setup mask for channels, triggers, times and modes.
- **Display Settings** is used to set scale, offset and color for the oscilloscope channels.



- **Show/Hide:** Show and hide the oscilloscope channels.
- **Show/Hide Cursor:** Two time cursors can be displayed for measuring the signals.
- **Statistics Value:** This button opens a window that shows some statistics value for each channel. The calculation is between the two cursors. When both cursor are disabled then the calculations are over the whole oscilloscope shot.

## 2.6 Curves

With the curve tool, motor motion profiles can be easily created, joined, uploaded, downloaded and saved. NOTE: On B1100 the curve feature must be enabled with an access key.



The curve tool is divided into the edit and the download window. The edit window is used to generate, merge and modify curves with the following buttons:



- **New Curve** Starts the curve wizard, which guides through the curve generation.
- **Edit Properties** The properties of a selected curve, like name, time or stroke, can be modified.
- **Edit Curve Values** The curve points can be manually edited.
- **Join Curves** All selected curves are joined. A wizard will be started for defining the curve properties of the joined curve.

The download window is used to manage the curves, which are stored on the drive or have to be downloaded. Modifications in this window will show up the message "Curves have changed! Please download." After pressing the download into Drive button the window and the drive will be synchronized.



- **Upload Curves from Drive** All curves stored on the drive will be uploaded and displayed.
- **Download Curves to Drive** The drive's curve sector will be synchronized with the download window.

- Auto Numerate Curves** The curve ID, which must be unique, will be set automatically.

The maximum number of curves and number of sample points is defined as follows:

Series B1100:

Max. 16 Curves

#Curves \* 70 Bytes + #SamplePoints1 \* 4 Bytes <= 2016 Bytes

Series A110/C1100:

Max. 50 Curves

#Curves \* 70 Bytes + #SamplePoints1 \* 4 Bytes <= 32512 Bytes

All other Series:

Max. 100 Curves

#Curves \* 70 Bytes + #SamplePoints1 \* 4 Bytes <= 65280 Bytes

1 #SamplePoint: total of sample points in all curves

## 2.7 Parameters

The drive's parameters are displayed in a tree view.

Name	Value	Raw Data	Value (RAM)	UPID	Type	Scale	Offset	Min	Max	Def...	Attr.
FF Constant Force	0 A	0000000h	0 A	139Ch	Stnt32	0.001 A	0 A	-15 A	15 A	0 A	R/W
FF Friction	0 A	0000000h	0 A	139Dh	Stnt32	0.001 A	0 A	0 A	15 A	0 A	R/W
FF Spring Compensation	0 A/m	0000h	0 A/m	139Eh	Stnt16	1 A/m	0 A/m	-25000 A/m	25000 A/m	0 A...	R/W
FF Damping	0 A/(m/s)	0000h	0 A/(m/s)	139Fh	Stnt16	0.01 A/(m/s)	0 A/(m/s)	-250 A/(m/s)	250 A/(m/s)	0 A...	R/W
FF Acceleration	0 A/(m/s <sup>2</sup> )	0000h	0 A/(m/s <sup>2</sup> )	13A0h	Ulnr16	0.001 A/(m/s <sup>2</sup> )	0 A/(m/s <sup>2</sup> )	85.535 A/(m/s <sup>2</sup> )	85.535 A/(m/s <sup>2</sup> )	0 A...	R/W
Spring Zero Position	0 mm	00000000h	0 mm	13A1h	Stnt32	0.0001 mm	0 mm	-214748.364...	214748.364...	0 mm	R/W
P Gain	1.5 A/mm	000Fh	1.5 A/mm	13A2h	Ulnr16	0.1 A/mm	0 A/mm	0 A/mm	6553.5 A/mm	1.5...	R/W
D Gain	3 A/(m/s)	001Eh	3 A/(m/s)	13A3h	Ulnr16	0.1 A/(m/s)	0 A/(m/s)	0 A/(m/s)	6553.5 A/(m/s)	3 A...	R/W
D Filter Time	0 us	0000h	0 us	13A8h	Ulnr16	1 us	0 us	0 us	50000 us	0 us	R/W
I Gain	0 A/(mm/s)	0000h	0 A/(mm/s)	13A4h	Ulnr16	0.1 A/(mm/s)	0 A/(mm/s)	6553.5 A/(mm/s)	6553.5 A/(mm/s)	0 A...	R/W
Integrator Limit	17 A	00004268h	17 A	13A5h	Stnt32	0.001 A	0 A	0 A	25 A	25 A	R/W
Maximal Current	17 A	00004268h	17 A	13A6h	Stnt32	0.001 A	0 A	0 A	25 A	25 A	R/W
Maximal Current Positive	25 A	000061A8h	25 A	13FDh	Stnt32	0.001 A	0 A	0 A	25 A	25 A	R/W
Maximal Current Negative	25 A	000061A8h	25 A	13FDh	Stnt32	0.001 A	0 A	0 A	25 A	25 A	R/W
Noise Deadband Width	0 mm	0000h	0 mm	13A7h	Ulnr16	0.0001 mm	0 mm	0 mm	0.2 mm	0 mm	R/W

The parameter service is controlled with the following buttons:



- Show/Hide Details:** Additional information for each parameter, such as unique parameter ID (UPID), scaling, min/max value, can be displayed on demand.
- Show UPID Browser:** When parameters are edited, which represent a UPID, this button will be visible. With this button, the UPID browser will be opened for an easy selection of a parameter.
- OK:** The input value is confirmed with this button. Pressing the enter key has the same effect.
- Cancel:** This button cancels the value typed in.
- Read:** All parameters will be read and refreshed from the drive.

When a parameter is marked with a little red L (L), in front of the name, the parameter is a live parameter. A live parameter could be changed without stopping the firmware, all other parameter can only be changed when the firmware is stopped.

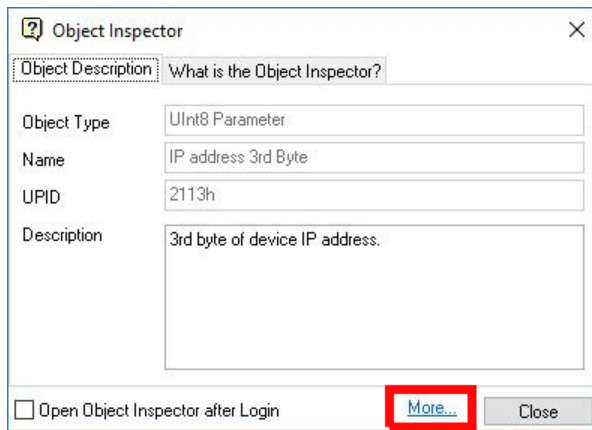
In the table below the columns of the parameter view are explained.

- Name:** This is the Name of the Parameter
- Value:** Value is the ROM Value, after a restart the ROM value is written in to the RAM value. This value is editable in the LinMot-Talk
- Raw Data:** is the Data like it is in the ROM without scaling and without the offset, in hexadecimal
- Value (RAM):** stands in the RAM, this is the active value at the moment. This value is not editable in the LinMot-Talk. When the parameter is a live parameter then the RAM value will change when the user changes the ROM value in the LinMot-Talk



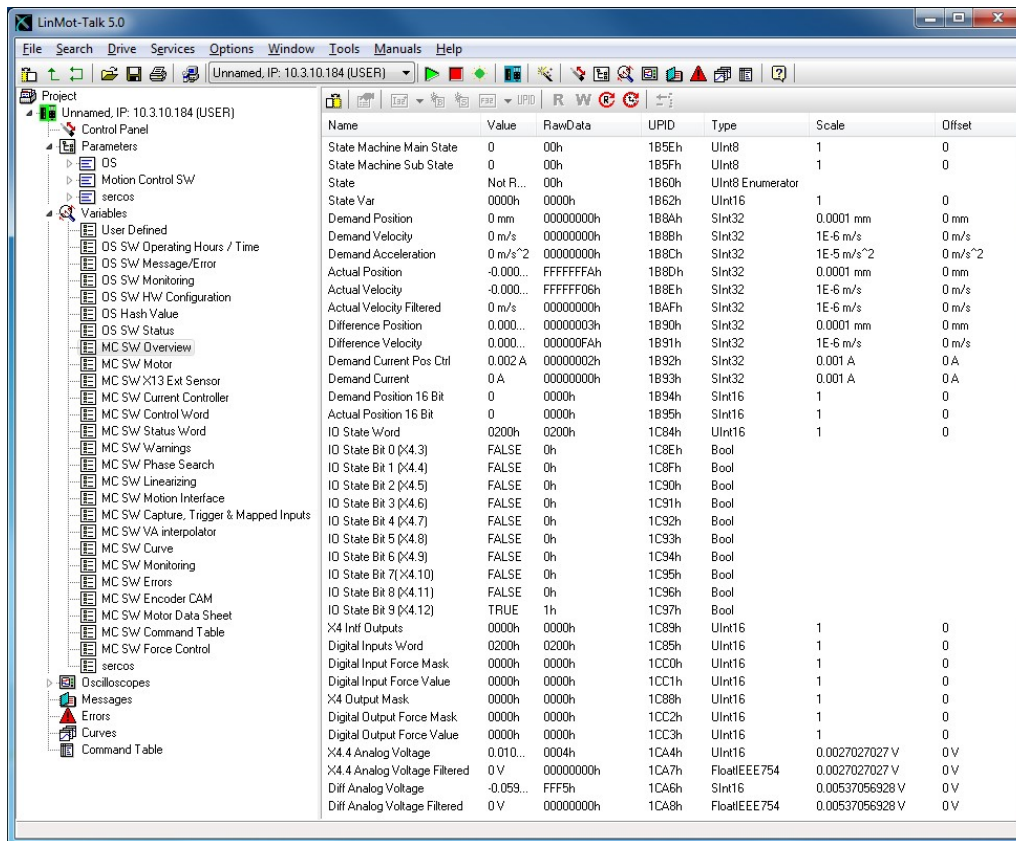
**UPID:** [Unique Parameter IDentification](#)  
**Type:** is the type of the parameter, for example SInt32, UInt32, String ...  
**Scale:** is the scale factor from the Raw Data to the Value.  
**Offset:** is the offset that must be added to the Raw Data to receive the Value  
**Min:** is the minimal value that the parameter value could have  
**Max:** is the maximal value that the parameter value could have  
**Default:** is the value that the parameter has after defaulting the drive  
**Attr.:** The Attribut defines what are the rights of the user with this parameter. R means read, W means write, with RW is both possible

When a parameter is selected and then the F1 button would be pressed, the Object Inspector starts up. In the Object Inspector are some informations about the parameter. If there is a blue more in the window it is a link to the documentation where it has more information about this parameter and his functionality.



## 2.8 Variables

The drive's variables, which can be watched, are arranged in different functional groups. The MC SW overview group contains the most used variables.



The variable service is controlled with the following buttons:



- **Show/Hide Details** Additional information for each parameter, such as unique parameter ID (UPID), scaling, min/max value, can be displayed on demand.
- **R Read Variable:** Reads the selected variable from the drive once.
- **W Write Variable:** Writes the selected variable to the drive.
- **Read All Variables:** Reads from the drive all variables of the section once.
- **Read All Variables Cyclically:** Reads from the drive all variables of the section cyclically.
- **Remove (Del):** Removes the selected variable from the list.

The following buttons are only used in special cases.

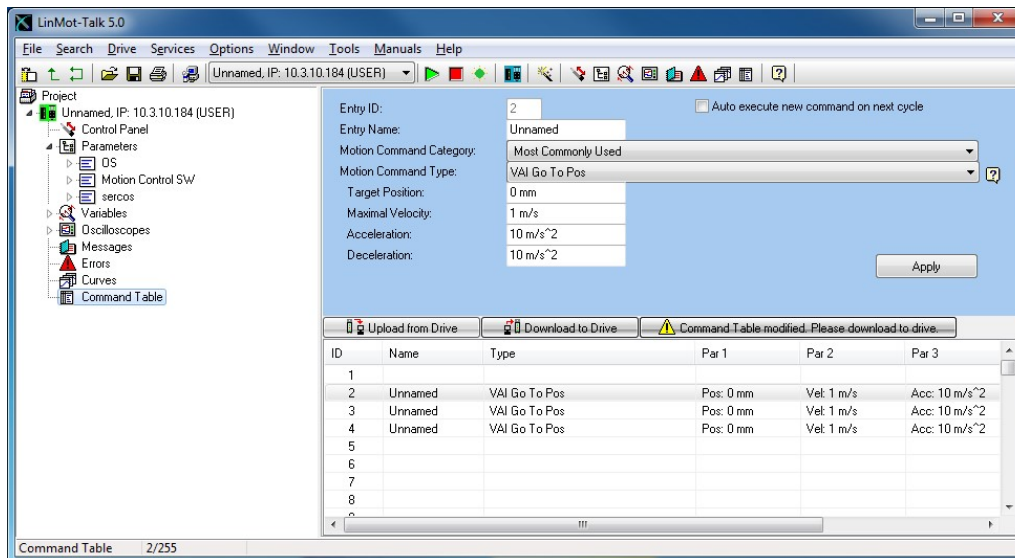
- **Edit Properties** The parameter properties can be displayed and changed.
- **New ... Variable** In a new generated variable section a new variable can be defined. This is a drop down menu, which supports different variable types.
- **New Bit Variable** In a new generated variable section a variable of the type bit can be defined.
- **New String Variable** In a new generated variable section a variable of the type string can be defined.
- **New Float32** In a new generated variable section a variable of the type float32 can be defined.
- **New With UPID** In a new generated variable section a variable can be added by using the UPID from the appropriate parameter.

Under "User Defined" any variables or parameters can be arranged together. Typically the variables are selected via UPID. It is also possible to drag and drop them from the parameter or variable section.

## 2.9 Command Table

The drive supports the command table (CT) functionality, which means a set of up to 255 motion commands (31 commands for B1100GP and B1100VF series drives, on B1100PP CT is not supported) can be stored in this table.

An example of is shown in the following picture:



A big variety of commands can be set in this tables, such as motion commands, conditions, sequence directives, parameter access, ...

This makes the CT to very powerful functional unit. The CT entries can be accessed (executed) via digital inputs (on X6) or via interface software.

The CT tool has the following editing elements:

- **Entry ID** indicates the CT entry, which is being edited.
- **Entry Name** is a descriptive string of max. 16 characters
- **Motion Command Category** the available commands are fitted into groups for keeping a better overview
- **Motion Command Type** specifies the command to be executed in this entry.
- **Auto execute new command on next cycle** when selected, on the next cycle the entry specified under "ID of Sequenced Entry" will be executed. This gives the possibility of defining cycles, simple logical sequences.
- **ID of Sequenced Entry** defines the CT entry executed on the next cycle when "Auto execute new command on next cycle" is activated.
- **Apply** writes the edited values into the entry.
- **Upload from Drive** reads and displays the entire command table from the drive.
- **Download to Drive** writes the edited table (from the PC) to the drive.

An application example of the CT can be found in the motion control software user manual (Usermanual\_MotionCtrlSW\_E1100.pdf).

## 2.10 Access Codes

On the drive, special features or customer specific applications can be protected by a software key. This means, a key must be activated by an access code, which is drive specific (pinned to the serial number). Under Drive\Set Access Code\ the following window will open:

A maximum of four keys can be set on the drive. Under Active Keys all valid installed keys are listed (key value and access code).

A new key can be set by selecting the key name and defining the value and access code. With the write button, the key and access code are written to the drive. As soon

as the drive has rebooted (click the Activate button) the new key will be active, if the access code fits.

Please note: Access codes are drive specific. They cannot be copied from one drive to another.

The following table shows on which drives the different functions are available:

Legend:


S: Standard Function

TF: Technology Function, can be enabled with key

NA: Function not available

Technology Functions	Curve	Force Control
E1100	S	TF
B1100	TF	TF
B1150ML	TF	TF
E1200	S	TF
E1400V2	S	TF
A1100	S	TF
C1100	S	TF
C1200	S	TF
C1400	S	TF
D1400	S	NA

## 2.11 Information Window

The Information Window is only visible when it has a message inside and it is activated. It could activated with the Information Window button  in the Tool button bar. The window can show the messages from the list below.

Motor Wizard:	The MotorWizard was not used, the Motor is only defined by PnP.	The Motorwizard defines more Parameter then the PnP, this Parameters are not set now. This message will be cleared when the user finishes the Motor Wizard
Oscilloscope:	An Oscilloscope has new data.	This message shows that an oscilloscope has finished, it will be cleared when the user goes to an oscilloscope

## 3 Quick Start Guide

This chapter helps step by step to set up a system using servo drive and the LinMot-Talk configuration software.

Cabling drive is described in the following chapters:

[Cabling E1100](#)

[Cabling E1200](#)

[Cabling E1400](#)

[Cabling B1100](#)

[Cabling B8050-ML](#)

[Cabling A1100](#)

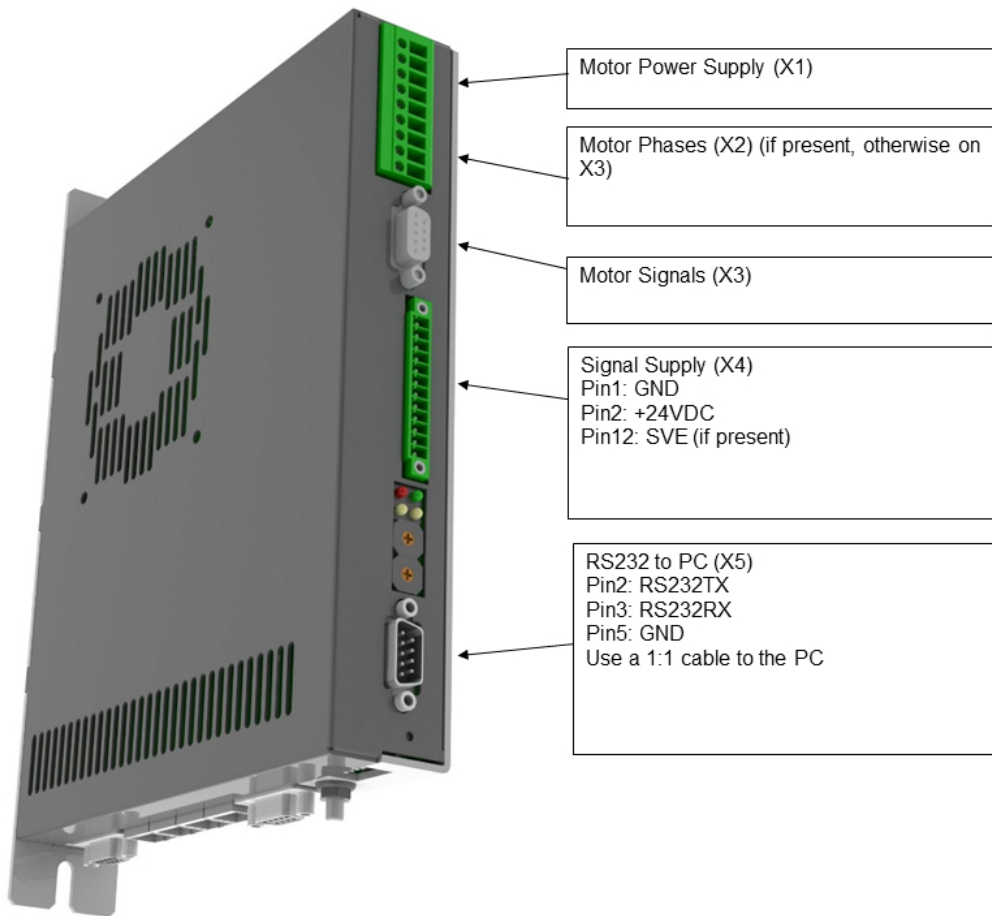
[Cabling C1100](#)

[Cabling C1200](#)

[Cabling M8000](#)

### 3.1 Cabling E1100

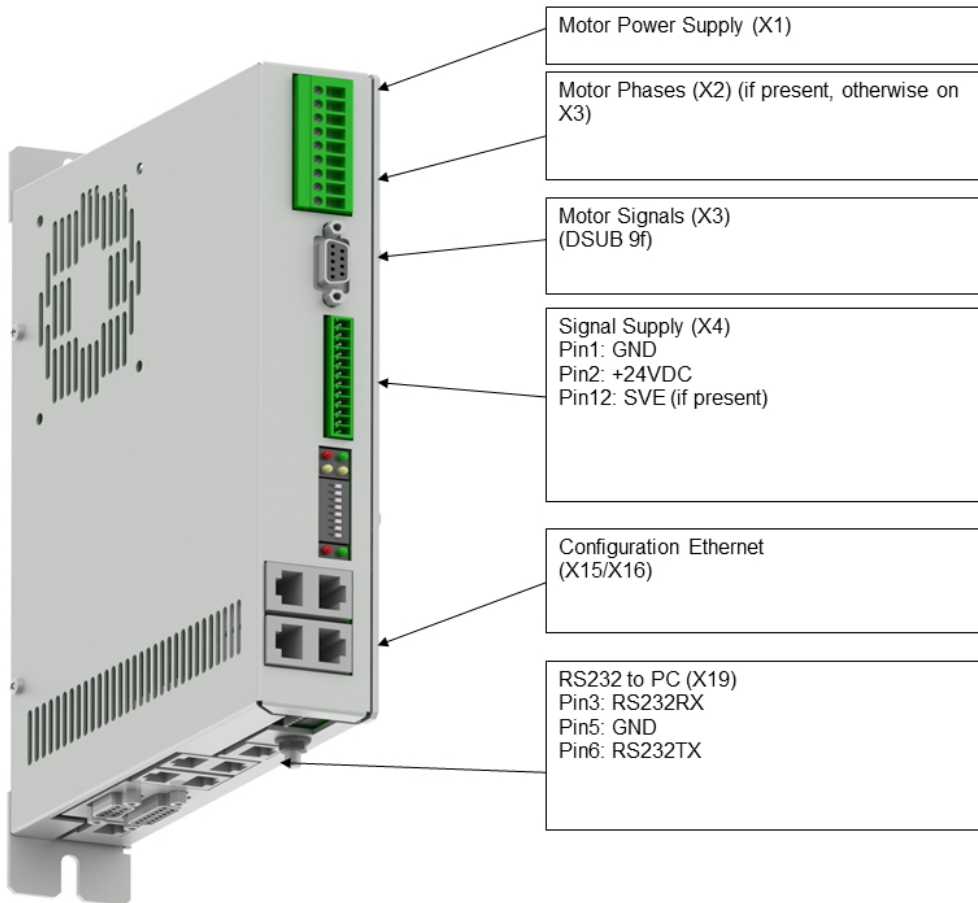
The following picture shows the connectors on the drive used for a first commissioning (with PC only).



- **X1** Motor Supply, use 48..72 VDC (between PWR+ and PGND).
- **X2** Motor Phases: if this connector is not present, connect the motor on X3 only.
- **X3** Motor signals: if motor has a DSUB-9 connector, connect it directly, otherwise use an adapter to DSUB-9 or wire the phase lines to X2.
- **X4** For a commissioning with the PC it is necessary to wire only the Pin1 (GND), Pin2 (+24VDC) and, if present, Pin12 save voltage enable (SVE, +24VDC).
- **X5** RS232: The cable between the LinMot drive and PC must be DSUB-9 F/F, 1:1 (X modem). If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).

### 3.2 Cabling E1200

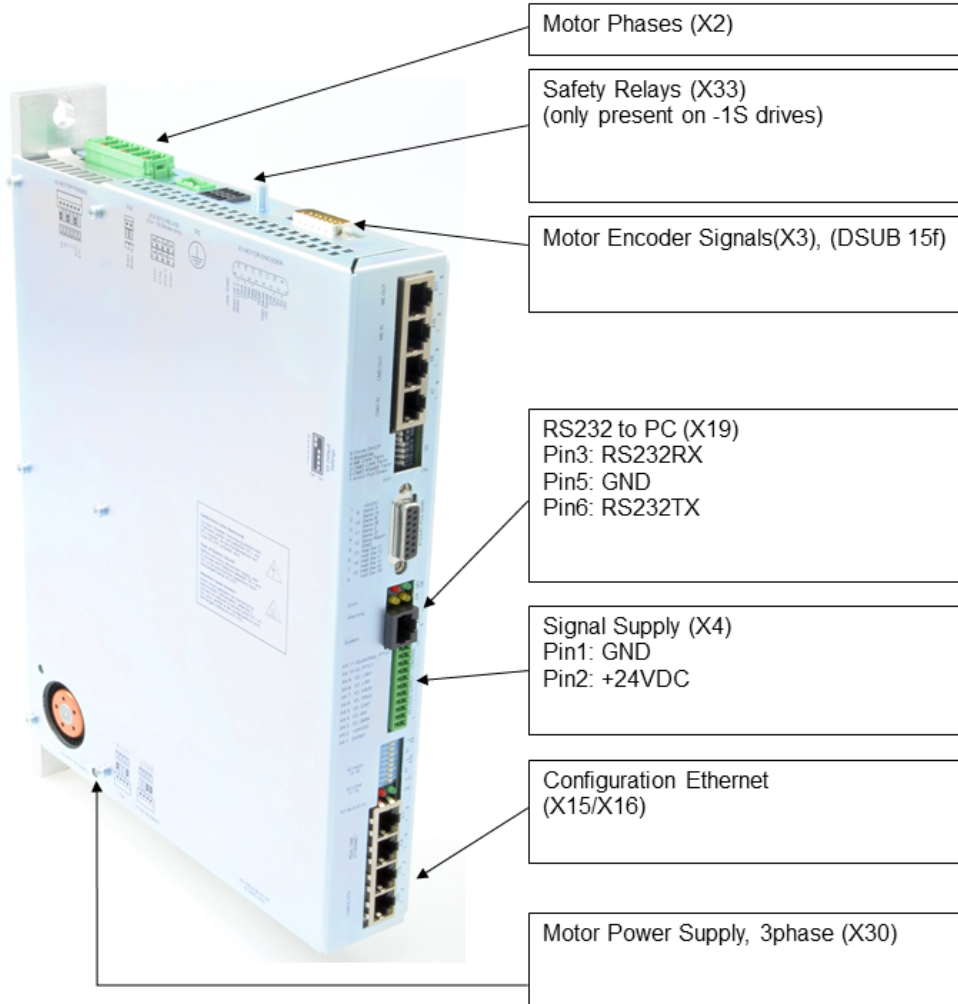
The following picture shows the connectors on the drive used for a first commissioning (with PC only).



- **X1** Motor Supply, use 48..72 VDC (between PWR+ and PGND).
- **X2** Motor Phases.
- **X3** Motor Signals. (Note: the motor phases are not present on this connector. Thus wire the motor phases in any case to X2).
- **X4** For a commissioning with the PC it is necessary to wire only the Pin1 (GND), Pin2 (+24VDC) and, if present, Pin12 save voltage enable (SVE, +24VDC).
- **X15/X16** Ethernet: Use a standard RJ45 patch cable to wire to the LAN.
- **X19** RS232: Use the RS232 PC configuration cable (LinMot article number 0150-2143) to connect your PC via RS232. If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).

## 3.3 Cabling E1400

The following picture shows the connectors on the drive used for a first commissioning (with PC only).

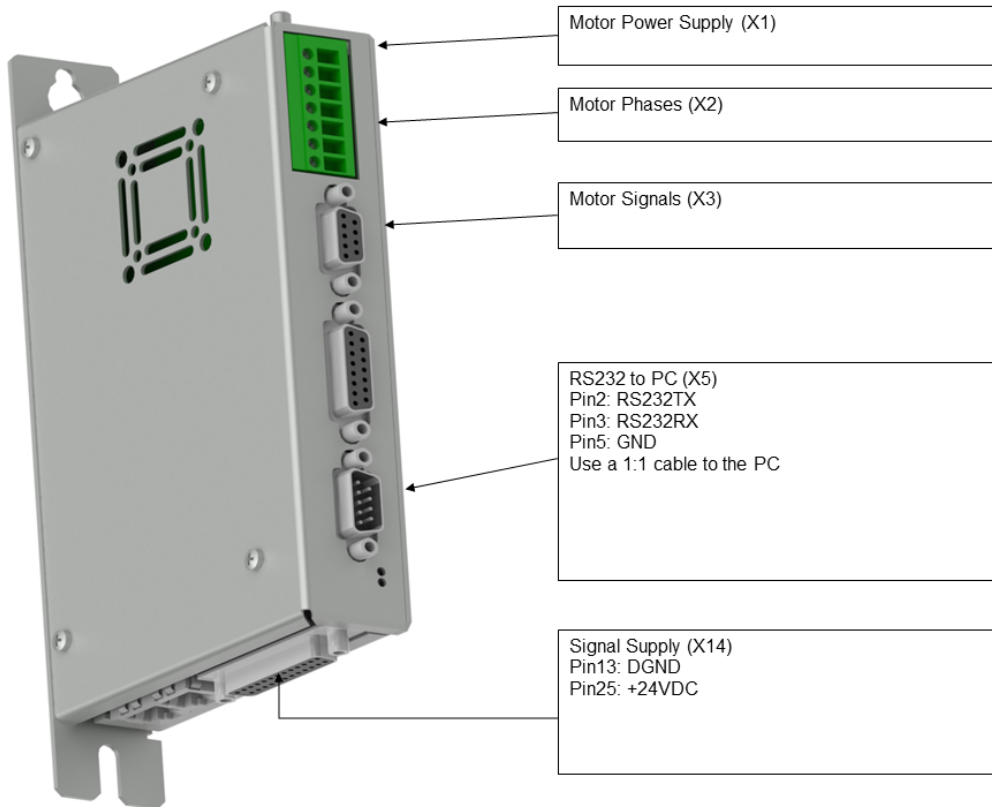


- **X2** Motor Phases.
- **X3** Motor Encoder Signals.
- **X4** For a commissioning with the PC it is necessary to wire only the Pin1 (GND) and Pin2 (+24VDC).
- **X15/X16** Ethernet: Use a standard RJ45 patch cable to wire to the LAN.
- **X19** RS232: Use the RS232 PC configuration cable (LinMot article number 0150-2143) to connect your PC via RS232. If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X30** Motor Supply, use 3x400 / 3x480VAC 50/60 Hz
- **X33** Safety Relays: For the safety relays use a separate +24VDC supply. For a commissioning it is necessary to wire both Ksr+ (X33.4 and X33.8) to +24 VDC and both Ksr- (X33.3 and X33.7) to GND.



### 3.4 Cabling B1100

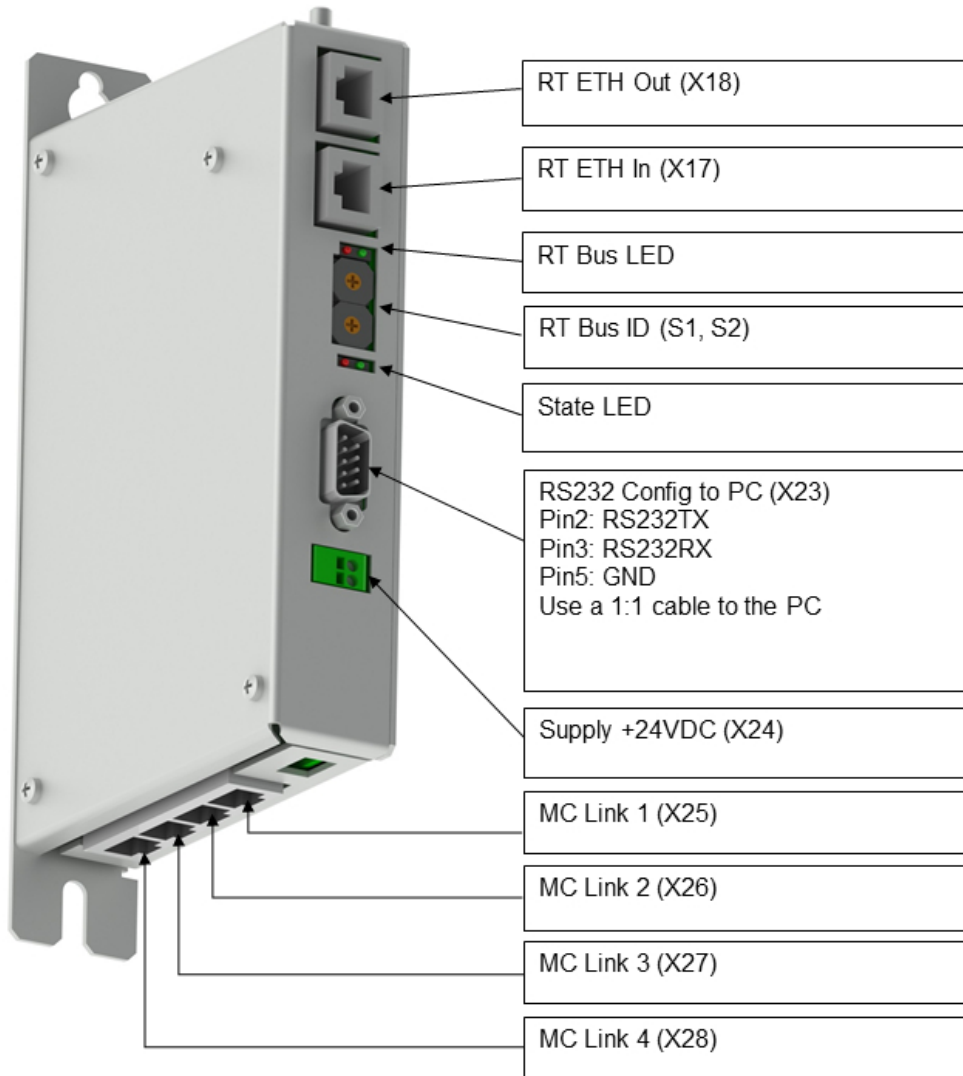
The following picture shows the connectors on the drive used for a first commissioning (with PC only).



- **X1** Motor Supply, use 48..72 VDC between (PWR+ and PGND).
- **X2** Motor Phases
- **X3** Motor signals: if motor has a DSUB-9 connector, connect it directly, otherwise use an adapter to DSUB-9 or wire the phase lines to X2.
- **X5** RS232: The cable between the LinMot drive and PC must be DSUB-9 F/F, 1:1 (X modem). If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X14** For a commissioning with the PC it is necessary to wire only the Pin13 (DGND) and Pin25 (+24VDC).

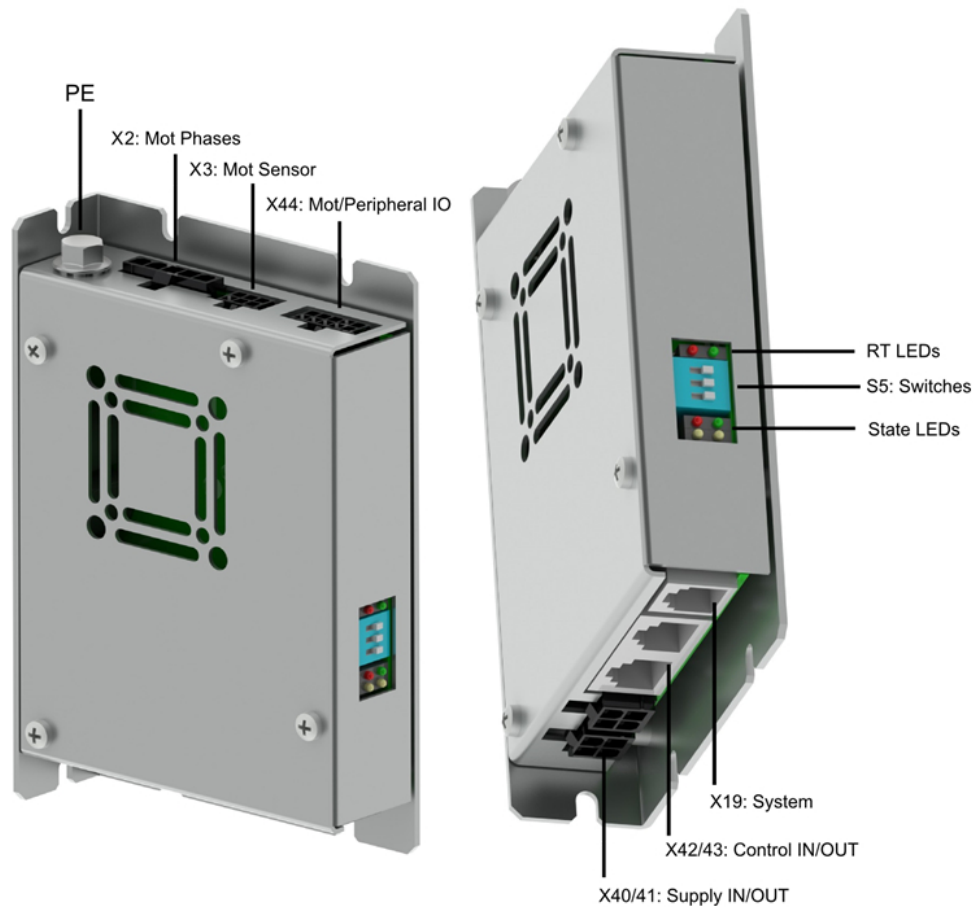
### 3.5 Cabling B8050-ML

The following picture shows the connectors on the drive used for a first commissioning (with PC only).



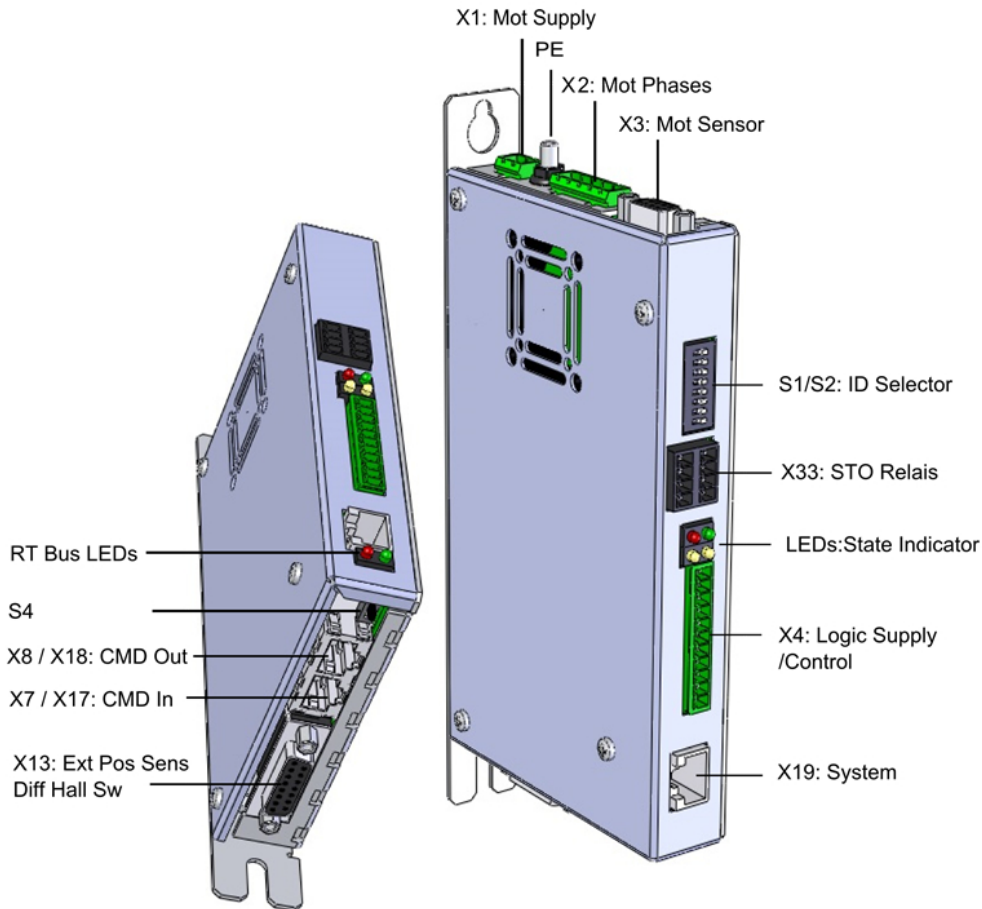
- **X23** RS232: The cable between the LinMot drive and PC must be DSUB-9 F/F, 1:1 (X modem). If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X24** Use a 24V switched power supply.

### 3.6 Cabling A1100



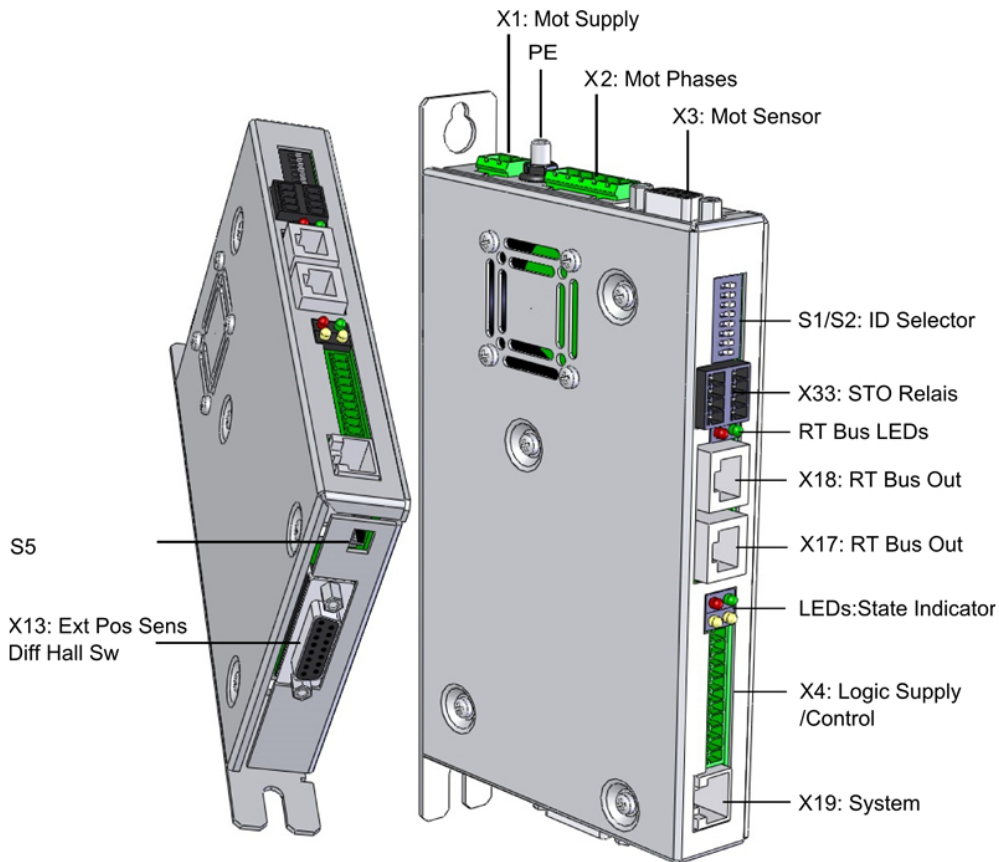
- **X2** Motor Phases.
- **X3** Motor Signals.
- **X19** RS232: Use the RS232 PC configuration cable (LinMot article number 0150-3544) to connect your PC via RS232. If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X40** Wire Pin1 (GND) and Pin2 (+24VDC) for signal supply, and for motor supply, use 48..72 VDC for PWR+ on Pin4 and PGND is on Pin3. (Linmot provides a connector with the crimped 1.5m long wires as a product under the article number 0150-3545.)

## 3.7 Cabling C1100



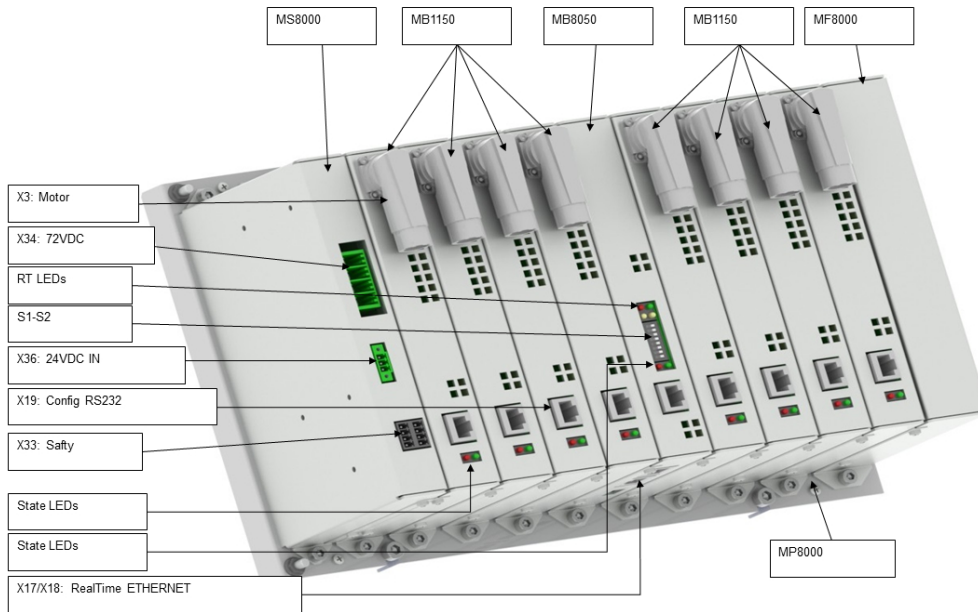
- **X1** Motor Supply, use 48..72 VDC (between PWR+ and PGND).
- **X2** Motor Phases.
- **X3** Motor Signals. (Note: the motor phases are not present on this connector. Thus wire the motor phases in any case to X2).
- **X4** For a commissioning with the PC it is necessary to wire only the Pin1 (GND) and Pin2 (+24VDC).
- **X19** RS232: Use the RS232 PC configuration cable (LinMot article number 0150-2143) to connect your PC via RS232. If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X33** Safety Relays: The connector X33 is only present for 1S safety functionality. For the safety relays use a separate +24VDC supply. For a commissioning it is necessary to wire both Ksr+ (X33.4 and X33.8) to +24 VDC and both Ksr- (X33.3 and X33.7) to GND.

### 3.8 Cabling C1200



- **X1** Motor Supply, use 48..72 VDC (between PWR+ and PGND).
- **X2** Motor Phases.
- **X3** Motor Signals. (Note: the motor phases are not present on this connector. Thus wire the motor phases in any case to X2).
- **X4** For a commissioning with the PC it is necessary to wire only the Pin1 (GND) and Pin2 (+24VDC).
- **X19** RS232: Use the RS232 PC configuration cable (LinMot article number 0150-2143) to connect your PC via RS232. If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X33** Safety Relays: The connector X33 is only present for 1S safety functionality. For the safety relays use a separate +24VDC supply. For a commissioning it is necessary to wire both Ksr+ (X33.4 and X33.8) to +24 VDC and both Ksr- (X33.3 and X33.7) to GND.

## 3.9 Cabling M8000



- **X3 Motor:** This is the only connector to the motor, it includes the phases and signals.
- **X19 RS232:** Use the RS232 PC configuration cable (LinMot article number 0150-2143) to connect your PC via RS232. If the PC has no COM port available, use the USB to RS232 converter (LinMot article number 0150-3110).
- **X33 Safety Relays:** The connector X33 is only present for 1S safety functionality. For the safety relays use a separate +24VDC supply. For a commissioning it is necessary to wire both Ksr+ (X33.4 and X33.8) to +24 VDC and both Ksr- (X33.3 and X33.7) to GND.
- **X34 Motor Supply,** use 48..72 VDC (between PWR+ and PGND). The Axis 1-4 and 5-8 are supplied separately.
- **X36:** For a commissioning with the PC it is necessary to wire only the Pin1 (GND) and Pin2 (+24VDC).

### 3.10 Firmware Download

As the [cabling](#) is done correctly now, turn on the drive's power and start up the LinMot-Talk software. Before using the drive the first time, the firmware has to be downloaded.

Therefore press install firmware button to start the wizard. Choose the file "Firmware\_Build20101126.sct" (or similar) and press "Open". Then the wizard will start and guide through the installation.

In case of installing the firmware over ETHERNET, the service password is required. This is for safety reasons. Especially if there are a lot of drives accessible in the network, it can easily happen to confound them. Thus it is strongly recommended to set a password. By default no password is set. If the password is unknown, the parameters can be set to default by hex switches, see [4.1](#). Installing the firmware over ETHERNET is only possible on drives with a separate Config Ethernet (E1200 and E1400). Installation over RT Ethernet is not possible.

According to the drive type, different interfaces and application software can be selected.

The following tables show the compatibility of drive type, interfaces and applications.

Legend:

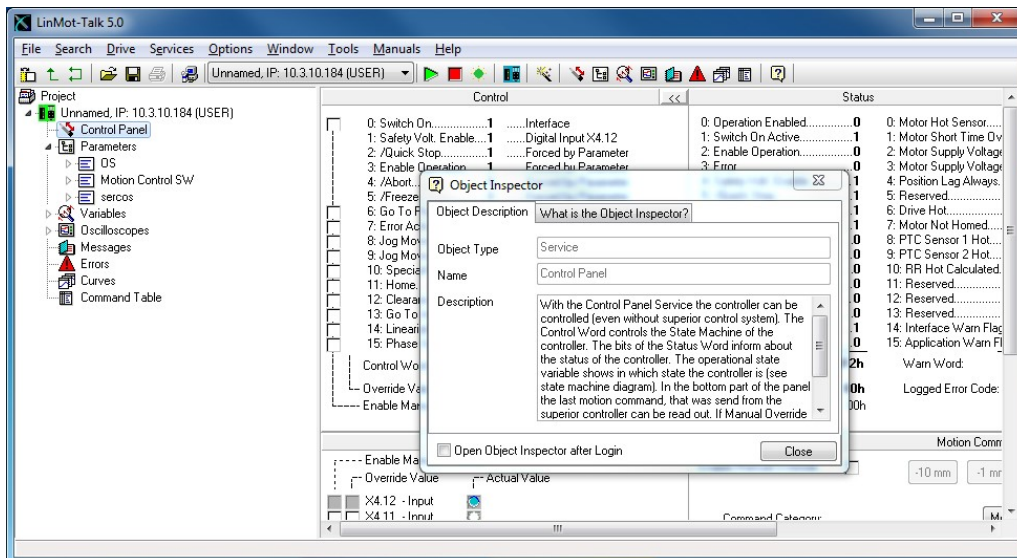
- D: Programmed as default
- X: Can be selected
- P: Planned
- GW: Gateway Software
- 6.3: Until Software Build 6.3
- ML: Motion Link Version

Drivetypes/ Interfaces/ Applications	None	MC Link	CT Interface	LinRS	CO	DN	DP	EtherCAT	SoE	CIA402	PN	PD	PL	SC	IP	LinUDP V1	LinUDP V2	None	EasySteps	EasyStepsX6	MasterSlave	AutoStart	SnrIde
A1100-GP	X				D													D				X	X
C1100-GP	X			X	D													D	X			X	
C1150-DS										D								D	X			X	
C1150-EC								D										D	X			X	
C1150-PD												D						D	X			X	
C1150-PN											D							D	X			X	
C1150-SE									D									D	X			X	
C1250-DS										D								D	X				
C1250-EC								D										D	X				
C1250-IP															D	6.3		D	X				
C1250-LU																	D	D	X				
C1250-PD												D						D	X				
C1250-PL													D					D	X				
C1250-PN											D							D	X				
C1250-SC														D				D	X				
C1250-SE									D									D	X				
E1200-GP	X			X	D													D	X		X		
E1230-DP							D											D	X		X		
E1250-DS										D								D	X		X		
E1250-EC								D										D	X		X		
E1250-IP															D	6.3		D	X		X		
E1250-LU																	D	D	X		X		
E1250-PD												D						D	X		X		
E1250-PL													D					D	X		X		
E1250-PN											D							D	X		X		
E1250-SC														D				D	X		X		
E1250-SE									D									D	X		X		
E1400GP V2	X			X	D													D	X		X		
E1430-DP V2							D											D	X		X		
E1450-DS V2										D								D	X		X		
E1450-EC V2								D										D	X		X		
E1450-IP V2															D			D	X		X		
E1450-LU V2																	D	D	X		X		
E1450-PD V2												D						D	X		X		
E1450-PL V2													D					D	X		X		
E1450-PN V2											D							D	X		X		
E1450-SC V2														D				D	X		X		
E1450-SE V2									D									D	X		X		
E1400-GP V1	X			X	D													D	X		X		
E1430-DP V1	X			X	X		D											D	X		X		
E1450-EC V1	X			X	X			D	X									D	X		X		
E1450-IP V1	X			X	X										D	X		D	X		X		
E1450-PL V1	X			X	X								D					D	X		X		
E1450-PN V1	X			X	X						D							D	X		X		
E1450-SC V1	X			X	X									D				D	X		X		
E1450-SE V1	X			X	X			X	D									D	X		X		

E1100-GP	X		D	X	X	X														D	X	X	X	X	X	
E1100-CO	X			X	D																D	X		X	X	X
E1100-DN	X			X	X		D														D	X		X	X	X
E1100-RS	X				D																D	X		X	X	X
E1130-DP	X		X	X	X		D														D	X		X	X	X
B1100-GP	X			X	D	X															D	X				X
B1100-VF	D																				D	X				
B1100-PP	D																				D					
B1100-ML		D																			D	X				X
MB1100-ML		D																			D	X				X
B8000-ML-GP							GW														D					
(M)B8050-ML-PL																	ML				D					
(M)B8050-ML-SC																		ML			D					
(M)B8050-ML-EC									EC												D					
(M)B8050-ML-IP																			ML		D					
(M)B8050-ML-PN																	ML				D					

### 3.11 Login

When successfully finished downloading the firmware, login with \File\Login... or with a double click on Project in the project tree window, then select the appropriate port and press ok. A login info window will appear showing the login progress. When logged in you will find the following window:

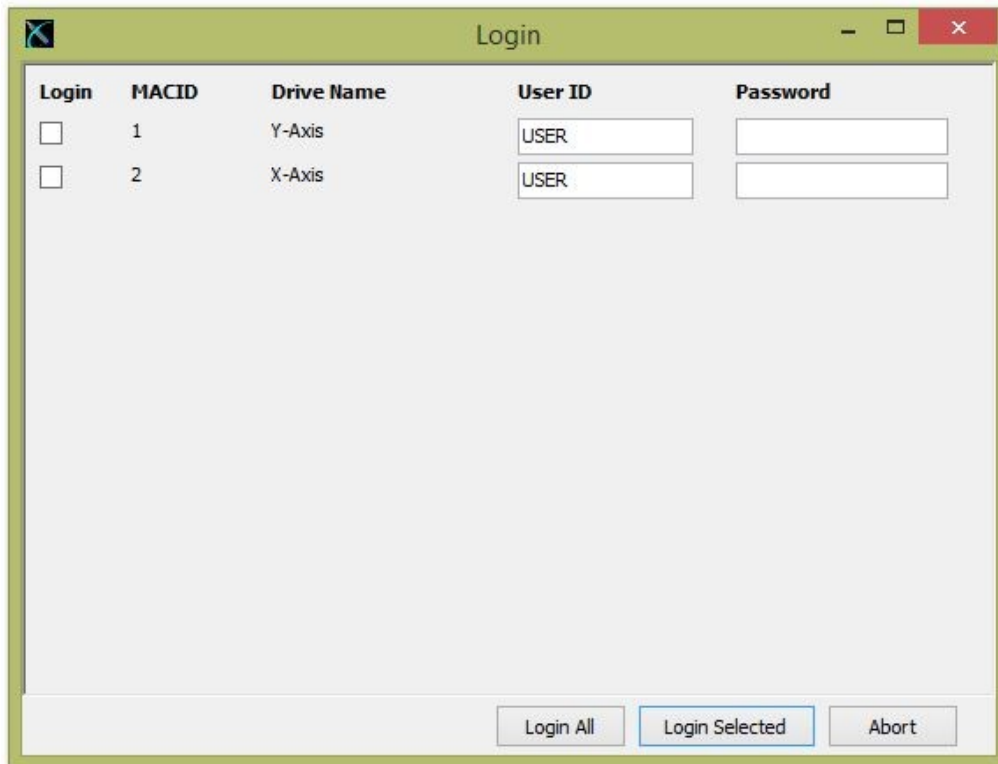


The Object Inspector window can be dragged away or closed. It can be reopened with F1.

### 3.12 Scanning CAN Bus

When one or several drives are linked with CAN bus for configuring, it can be very helpful to scan the CAN bus for linked drives automatically. Thus, it is not necessary to know all node IDs. Under \File\Scanning (with CANusb) a list of the present drives will be displayed:

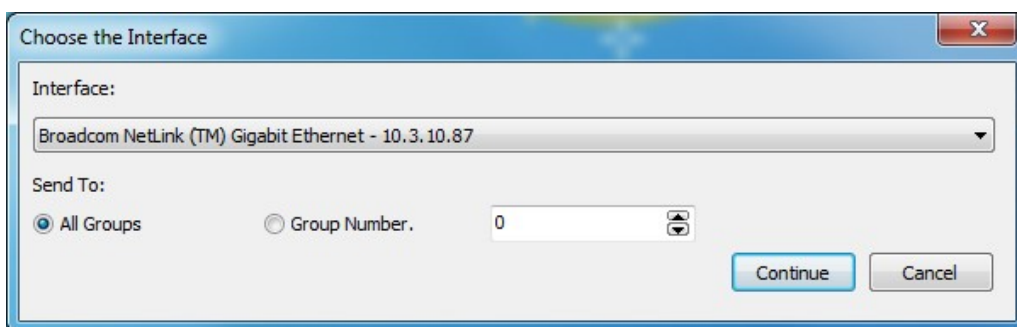







With just one click the LinMot-Talk software will log in to all drives.

### 3.13 Scanning Ethernet

When one or several drives are linked with Ethernet for configuring, it is helpful to scan automatically for linked drives. Thus, it is not necessary to know all node IP addresses. Under \File\Scanning (via Ethernet) first the interface has to be selected (network link) With the radio button Group Number could be activated a scan for a special drive group. The list will only display the drives with the group number, like the number in the text field. In the drives this number is saved in the parameter with the name Net Group and the UPID 0078h.



A list of the present drives will be displayed like in the picture below. With just one click the LinMot-Talk software will log in to all drives. The colored markings have the following meaning:

-  Green: The drive is ready to log in.
-  Grey: You are already logged into this drive.
-  Red: Another instance is logged into this drive (other user or other interface).

The default mode for acquiring an IP address is via DHCP. If no servers on the connected network respond, the drive switches to the Ipv4 Link-Local addressing scheme (also known as APIPA on Windows systems). This way the drive automatically

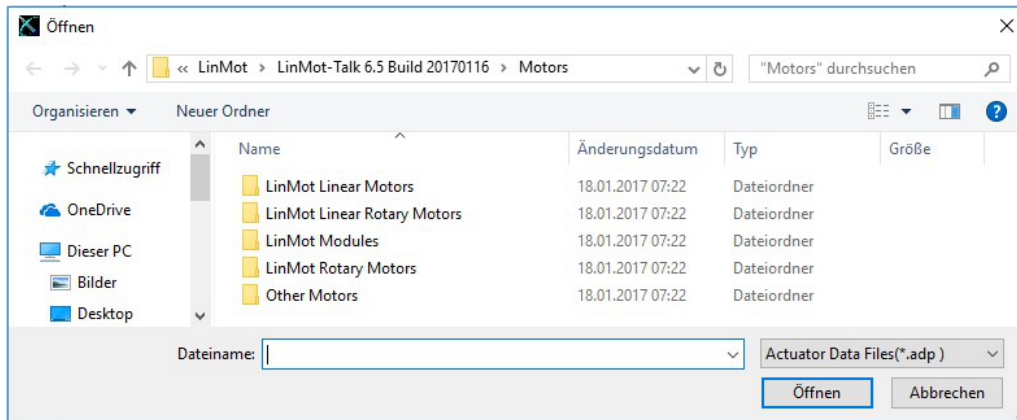
assigns itself an address within the range of 169.254.0.1 through 169.254.255.254 (Subnet Mask 255.255.0.0).

Please note that this process can take up to a minute until a valid address is assigned to the drive this way.

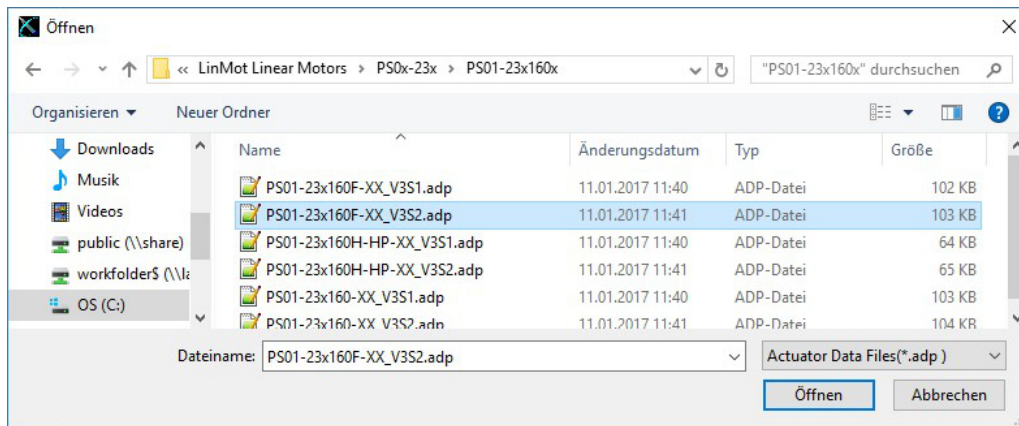


### 3.14 Motor Wizard

As no motor is defined, the next step is to start the motor setup wizard. Press the button and the following window will appear:



As we want to configure a LinMot Motor we choose "LinMot Linear Motors" and press Open. Then we choose the statorfamily like "PS0x-23x" and then the statorsubfamily like "PS01-23x160x". Select the actuator type you have connected to the drive, then press Open.



### 3.14.1 Actuator Selection

The following steps will show forms including drawings and descriptive texts. The first step is to define the stator and slider.

**Motor Wizard** [Close] [Maximize] [Refresh]

**Step 1/9: Actuator Selection**

**Actuator Data File:** PS01-37x120-XX\_V3S3.adp Change Actuator ...

**Stator:** PS01-37x120-C

**Slider:** PL01-20x600/540-LC (L: 600mm; D: 20mm; ArtNo: 0150-2564)

The slider can be identified by its length and the number of notches on the front end (1 Notch = Standard, 2 Notches = HP, 3 Notches = LC).

Standard    -HP    -LC

**Slider Mounting Direction:** Regular

The sliders are not symmetric. The value of ZP (Zero Position) depends on the mounting direction relative to the stator. Therefore the available stroke range changes with the mounting direction.

**Positive Moving Direction:** Regular

➔ Symbol for positive moving direction

Derived Settings	Value	Comment
STATOR	PS01-37x120-C	
Article Number	0150-1223	
Stator Length	216 mm	
Stator Mass	740 g	

Help    < Back    Next >    Finish    Cancel

The derived settings show information about the complete motor type, article numbers and the most important technical data. The change of the positive moving direction is supported since release 6R7 and only for motors with PnP version V3S2 and higher. Motor with PnP version V3S1 do not work with changed positive moving direction. Be also aware in case of exchange!

### 3.14.2 Drive Settings

The next step is to choose a drive name and if it is possible a regeneration resistor.

The screenshot shows a window titled "Motor Wizard" with a sub-header "Step 2/9: Drive Settings". The main area contains a "Drive Name:" label followed by a text input field containing "Unnamed". Below this is a "Regeneration Resistor:" section with a "Type:" label and a dropdown menu currently set to "None". At the bottom of the main area is a table with three columns: "Derived Settings", "Value", and "Comment". The table is currently empty. At the very bottom of the window is a row of five buttons: "Help", "< Back", "Next >" (which is highlighted with a blue border), "Finish", and "Cancel".

Derived Settings	Value	Comment

### 3.14.3 Extantion Cable Setup

Longer extension cables will have an effect to the motor's phase resistance. In step 3 can be defined two cable segments.

**Step 3/9: Extension Cable Setup**

**First Extension Cable Segment**  
 Type:  ▼  
 Length:  m

**Second Extension Cable Segment**  
 Type:  ▼

The ohmic resistance of extension cables can be quite high in relation to the motor's phase resistance. If the firmware knows the total ohmic resistance it can optimize the current control loop to the load. If there are extension cables used in the application, then that/these segment(s) should be defined here. The cable piece that comes directly out of the motor is negligible.

Derived Settings	Value	Comment
Motor Phase Resistance	4.8 Ohm	
Cable Resistance	0.14 Ohm	
Total Resistance	4.94 Ohm	

Help

### 3.14.4 External Position Sensor System

The next hardware setup step is to define an external position sensor system (if present). For E1100 drives can be chosen between none, incremental AB(Z) and analog sine/cosine 1Vpp. For B1100 drives can be chosen between none, incremental AB(Z) and AB encoder simulation.

Motor Wizard
— □ ×

**Step 4/9: External Position Sensor System**

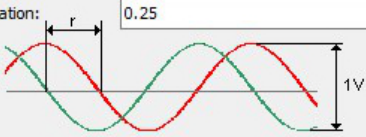
**External Position Sensor**

Type: Analog Sine/Cosine (1Vpp)

Positive

250

Minimal Edge Separation: 0.25 us



With an additional external position measuring system the positioning accuracy and the linearity can be improved. The optional position sensor has to be connected to Ext Pos Sens connector on the drive. In case of a absolute position sensor the position recovery mode will be set accordingly.

Mode: None

Derived Settings	Value	Comment

Help
< Back
Next >
Finish
Cancel

### 3.14.5 Feed Forward Parameters

With step 5 the feed forward parameters are set up. Depending on the moving mass, additional load mass, friction and orientation. Under the derived settings the influence can be watched.

**Motor Wizard** - Step 5/9: Feed Forward Parameters

**Mechanical Layout**  
 Moving Part of Motor:   
 Orientation Angle (-90°..+90°):  °

**Moving Mass**  
 Slider:  g  
 Additional Load Mass:  g

**Friction Forces**  
 Dry Friction:  N  
 Viscous Friction:  N/(m/s)

**MagSpring (or other constant force)**  
 External Constant Force:  N  
 Force Direction:

Diagram: A horizontal slider mechanism with a plus sign (+) at the right end. Below it are three angle selection buttons: -90° (down arrow), 0° (right arrow), and +90° (up arrow).

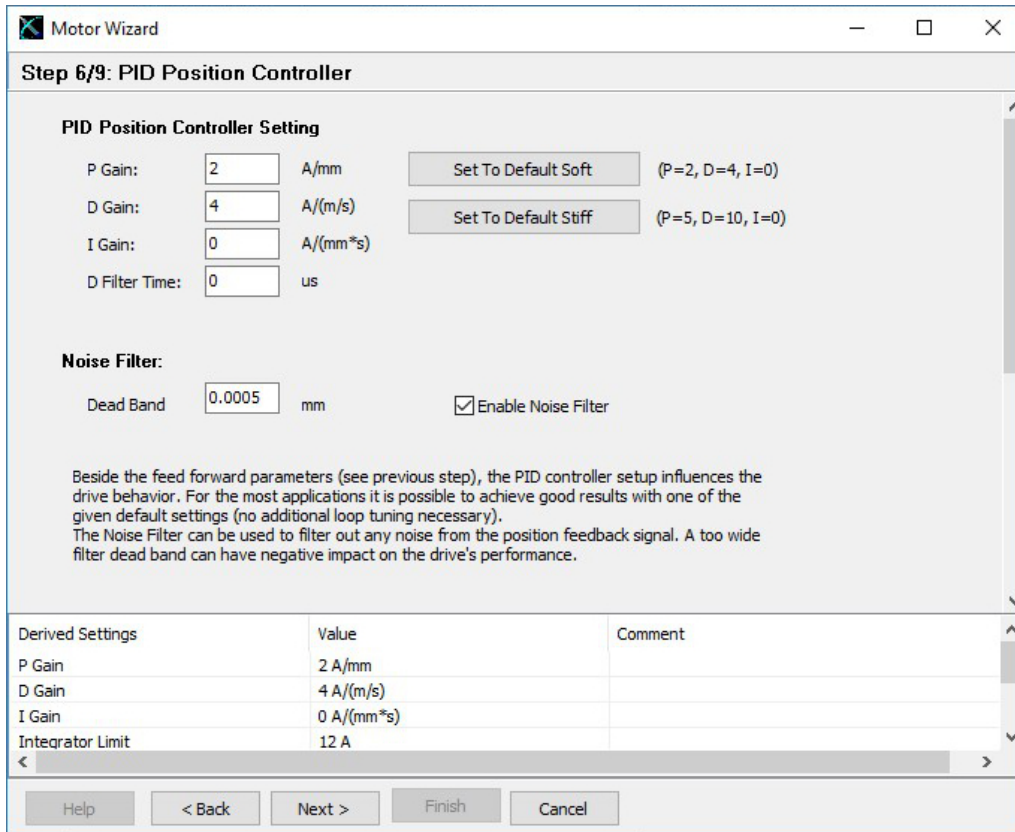
Derived Settings	Value	Comment
Total Moving Mass	1564 g	
Gravitation force in motor direction	0 N	
External Constant Force	0 N	
Sum of Constant Effective Forces	0 N	

Navigation: Help | < Back | Next > | Finish | Cancel



### 3.14.6 PID Position Controller

With the next and last step the position drive's parameters will be set up:



It is recommendable to start with the default soft settings, because the parameters can be changed any time later on (by restarting the motor wizard or by setting in the parameter tree directly).

With the soft parameter setting, PID values will be quite low such as the motor is low noise and the position is not controlled very stiffly.

The stiff parameter set tends to more noise and more power consumption of the motor, but the position will be controlled harder.

In both settings, the I Gain is set to zero, which means a steady-state deviation from the desired position can occur. When using the I Gain, the position controller may tend to swing.

The Noise Filter option is to reduce the noise from the position feedback sensor at standstill.

For finding the best set of PID parameters, the system has to be optimized iteratively. There is no general way of how to optimize the settings, because different goals can be achieved such as position accuracy, power minimization, noise reduction, ...

### 3.14.7 Homing 1

The next step is to define the homing procedure.

**Motor Wizard**

**Step 7/9: Homing I**

**Home Position Search Move**

Speed: 0.01 m/s

Mode: Mechanical Stop Negative Search

The motor moves in negative direction until a mechanical stop is reached. This position is assumed to be the Home Position.

Before motion commands can be executed, the motor must be homed. Depending on the selected mode, the motor searches a mechanical stop and/or an electrical switch.

Derived Settings	Value	Comment

Help < Back **Next >** Finish Cancel

The most frequently used homing mode is “Mechanical Stop Negative Search”. In this case the slider will move with the notch towards the stator’s front end (where no cable is).

Other modes support homing on home switches, limit switches, indexer inputs or some combinations of those.

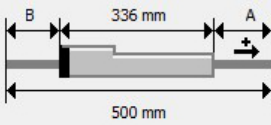
### 3.14.8 Homing 2

Step 8 is to define the slider home position. This is for the motor and drive the most important value. It defines at the home position, where the slider is positioned relative to the stator. This defines how far the motor can move in each direction.

Motor Wizard
- □ ×

**Step 8/9: Homing II**

**Distance from Stator End to Slider End at the Home Position**



Distance A  mm

Distance B  mm

The drive needs to know the physical position of the slider relative to the stator. Please determine either distance A or distance B when the motor stands at the Home Position (mechanical stop or switch). Then enter the corresponding value. The other value is calculated by the software. If the slider end is inside the stator tube, then you have to give your entry a negative sign.

Derived Settings	Value	Comment
Slider Home Position	10 mm	Corresponds to distance A

Help < Back Next > Finish Cancel

### 3.14.9 Homing 3

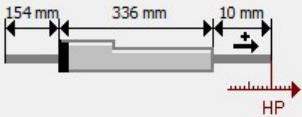
With the last wizard step the user's coordinate system can be defined.

**Motor Wizard** — □ ×

**Step 9/9: Homing III**

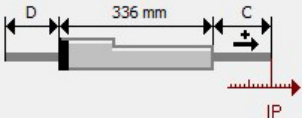
**Definition of the Application Reference System**

Home Position (HP):  mm



**Move to the Initial Position at the End of the Homing Procedure**

Initial Position (IP):  mm



You can define your application specific reference system by assigning any position value to the Home Position. All further position values are based on this system.  
At the end of the homing procedure the motor moves to the Initial Position. Then it is ready to execute the motion commands. If the motor has to be homed on a mechanical stop, then the Initial Position value should differ from the Home Position.

Minimal Position Error Enabled    Minimal Position:  mm    (-70mm <= Position <= 290mm)

Maximal Position Error Enabled    Maximal Position:  mm

Derived Settings	Value	Comment
Minimal Position (stroke range limit)	-70 mm	
Maximal Position (stroke range limit)	290 mm	
Distance C	20 mm	
Distance D	144 mm	

At the end, press finish. If the firmware on the drive is still running, an appropriate message will be shown. All parameters will now be written to the drive. The motor wizard can be run several times, e.g. to setup an external sensor, to change the load setup or to change the motor type. When rerunning it, at the end will be shown a list of parameters, which will be changed.

### 3.15 Unit System

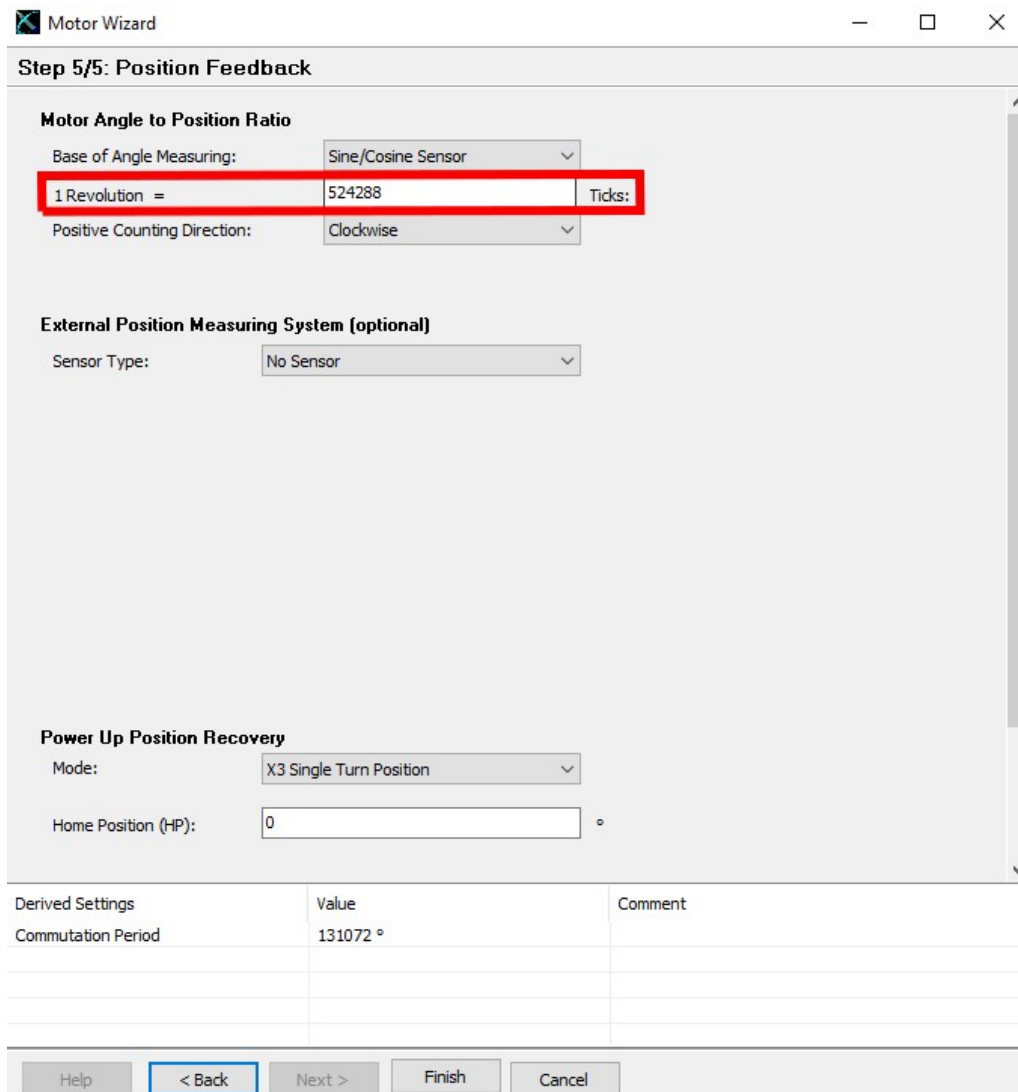
For LinMot rotary Motors and the rotary part of PR01 motors in the motor wizard it has a special page. This page is to choose the unit system. The unit system is only in the LinMot-Talk active and has no effect to the drive. There are two unit systems. One is a Linear system the position is displayed in 'mm', the other system is a rotary system especially for rotary motors. The position is in this case displayed in '°'.

In the Page Number 5 Position Feedback, there is one parameter called "1 Revolution". In the Linear unit system, this parameter says how many mm represent one revolution. In the rotary unit system, this parameter says how many ticks (one bit of the position in the motioncontrol software) are a revolution. In both cases, it has two recommended possibility. If the parameter has a multiple of 360 the numbers are well represented. Otherwise if the parameter has a value  $2^n$  or in linear case  $2^n \cdot 100nm$  the position of the motor is on 0 position the same also after an overflow of the position

**Attention:**

For LinMot rotary Motors (EC02) it is important, that the value in this parameter is divisible by 4. That means  $x \cdot 4$  or  $x \cdot 4 \cdot 100nm$  .

For the rotary part of the PR01 motors it is important, that the value in the parameter is divisible by 12. That means  $x \cdot 12$  or  $x \cdot 12 \cdot 100nm$  .

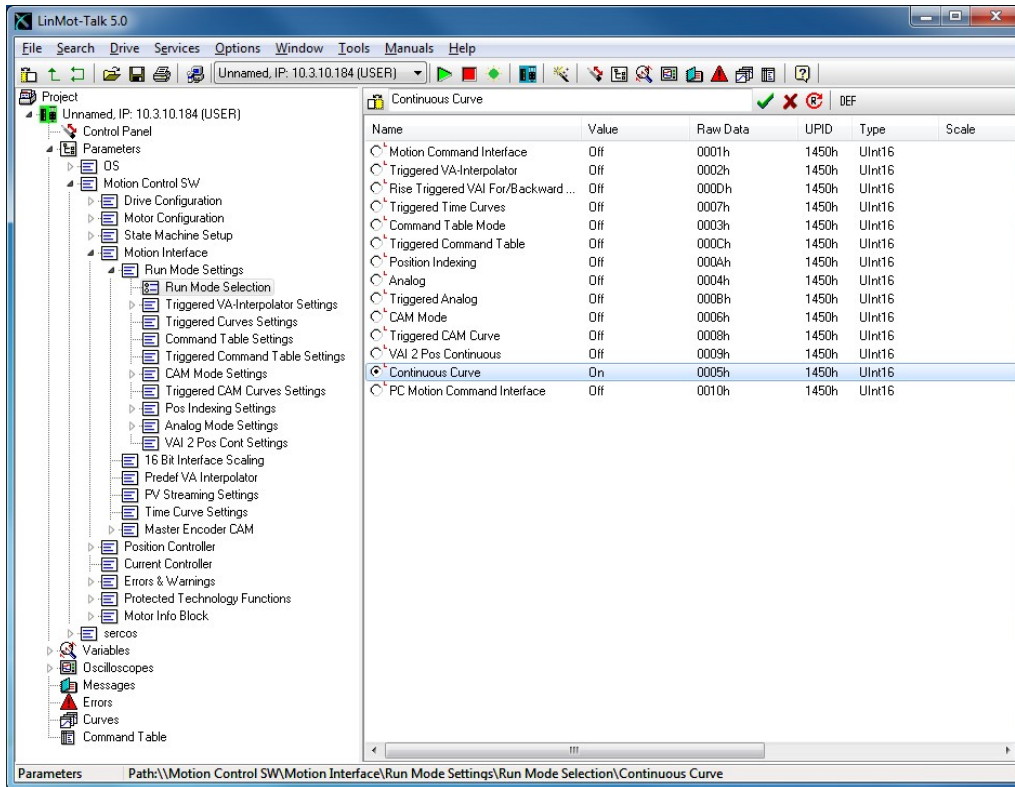


### 3.16 Continuous Curve Mode

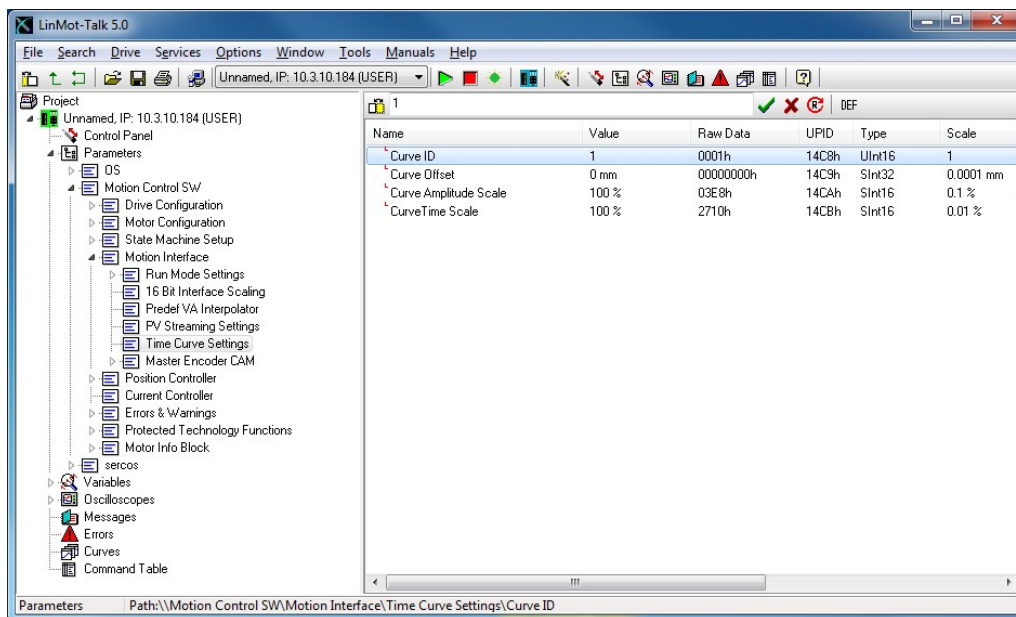
We want the motor to run a curve cyclically (The easiest, but not so informative way to run the motor would be the VAI 2 Pos Continuous mode).

The drive is set to continuous curve mode by selecting “Continuous Curve” under \Motion Control SW\Motion Interface\Run Mode Settings\Run Mode Selection\ in the parameter tree.

NOTE: For enabling the curve feature on B1100 drives, it is necessary to set an access key.





The second parameter to be set is to define which curve has to be run. Set the parameter “Curve ID” to 1 under \Motion Control SW\Motion Interface\Time Curve Settings.

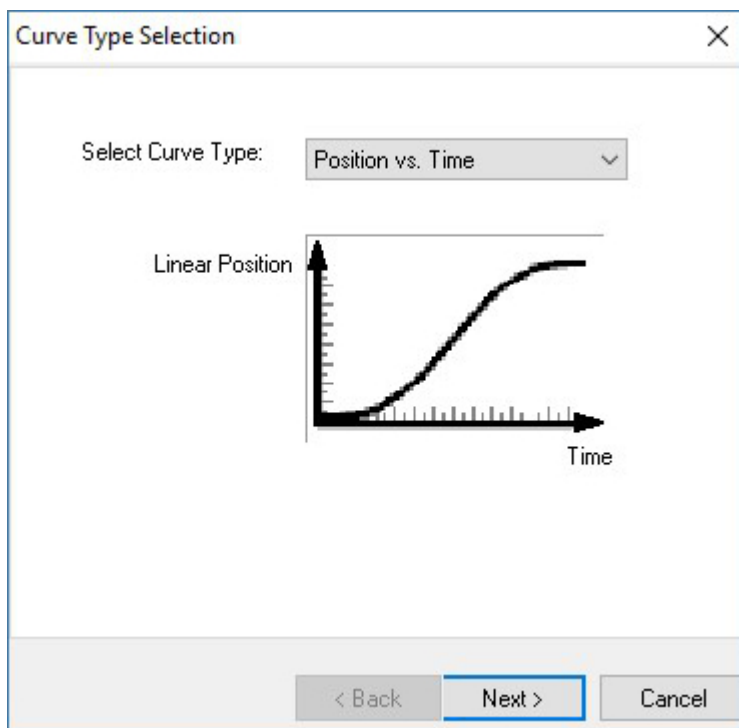


Before running the curve, it is advisable to define the curve we want to run.

### 3.17 Defining Curves

Curves can be easily defined with the curve wizard. For this example we will define two sine curve forms over a stroke of 50mm out and in with different speeds, which will be joined together.

Now, step by step: Open the curve tool by clicking the “Show Curves” button  in the tool button bar. Then press the “New Curve” button  to start the curve wizard.



As we want to define a curve in position vs. time mode we can keep the default selection and press the next button.

Curve Settings

Curve ID (1..100): 2

Curve Name: SineOut

Setpoint Calculation Wizard: Sine

Curve Length: 1000 ms

Start Point: 0 mm

End Point: 50 mm

< Back   Next >   Cancel

In this mask, we will set the curve ID to 2 (we will have the merged curve with ID 1 at the end) and as name we set e.g. "SineOut". The end point is placed at 50mm. With "Next" the wizard will show some curve data:

Calculated Curve Data

Based on the Curve Settings Data the wizard has calculated additional curve information:

Stroke: 50 mm

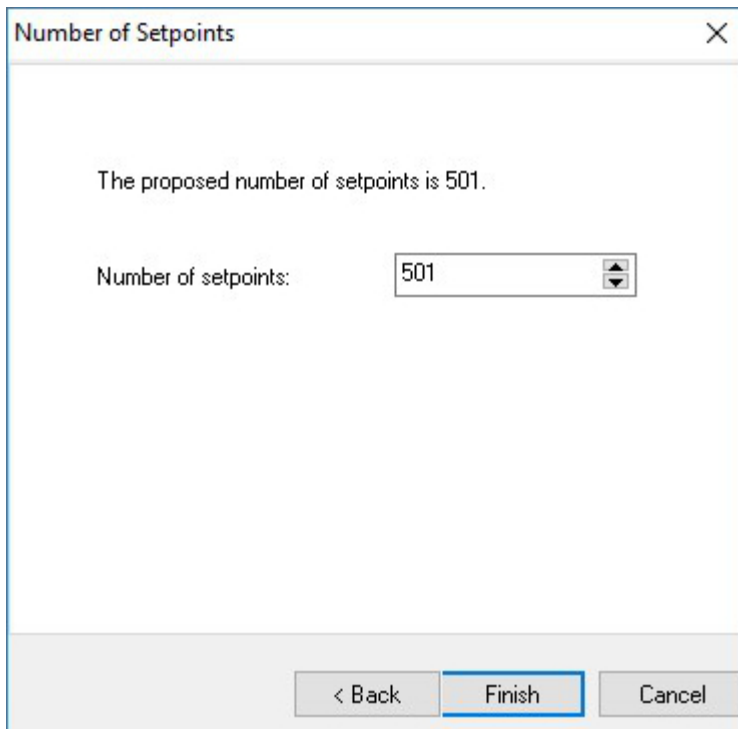
Peak Velocity: 0.07854 m/s

Peak Acceleration: 0.24674 m/s<sup>2</sup>

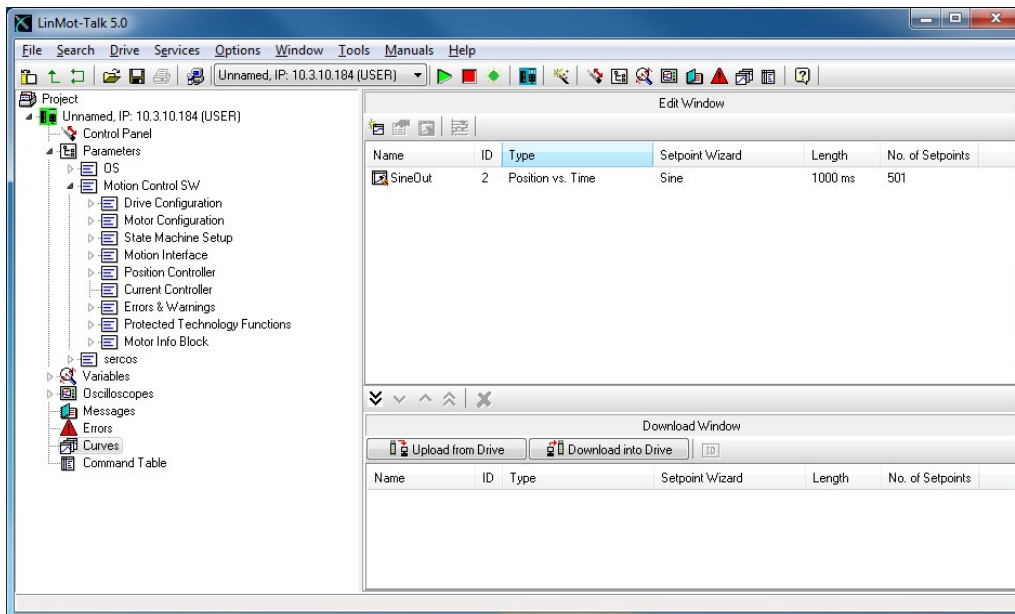
< Back   Next >   Cancel

The next and last mask proposes a number curve setpoints. It is advisable to accept this proposal.

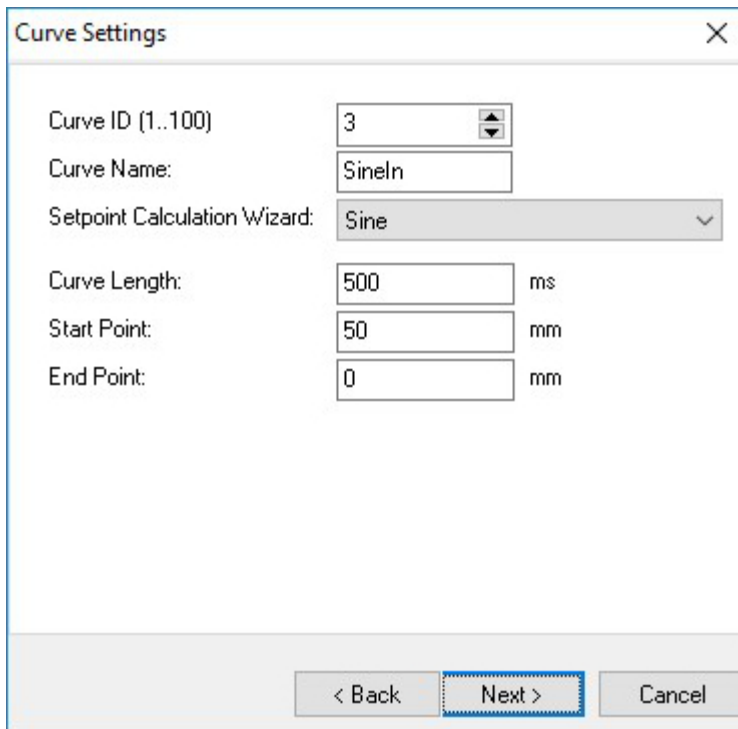




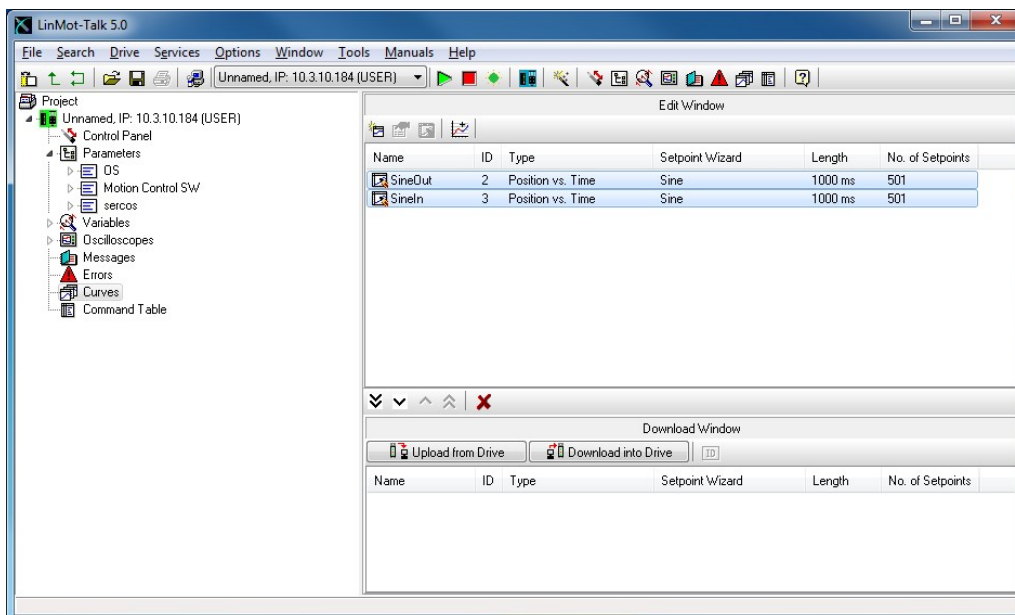
with “Finish” the first curve is defined. The curve will be displayed as follows:




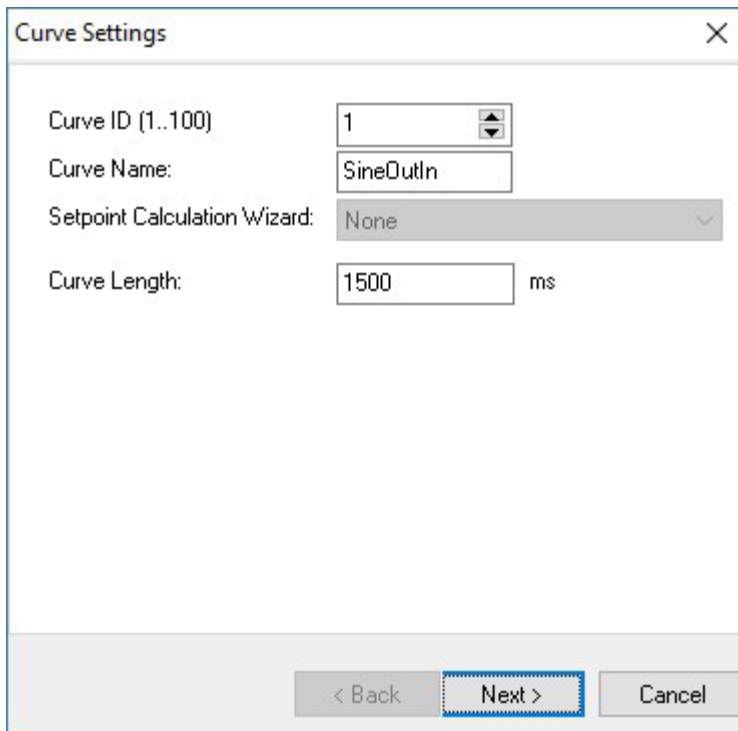
We will now define curve going back. So we start the curve wizard again and define under curve settings the following:



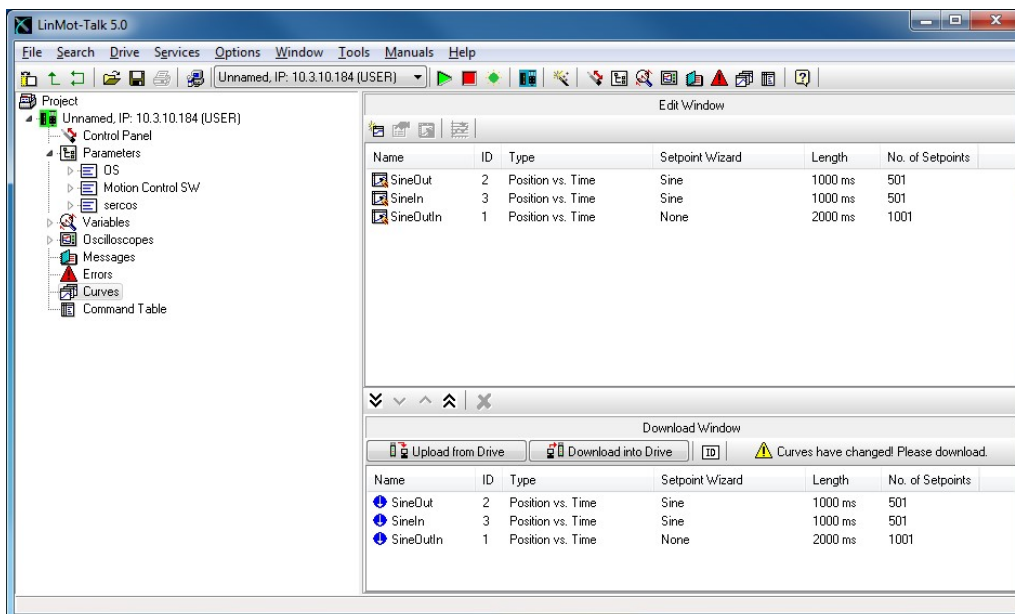
Set curve ID to 3, Curve Name to “SineIn”, Curve Length to 500ms, Start Point to 50mm and End Point to 0mm. Click twice “Next” and then “Finish”.  
 Now we have defined the two curve segments and will join them together. Select the two curves



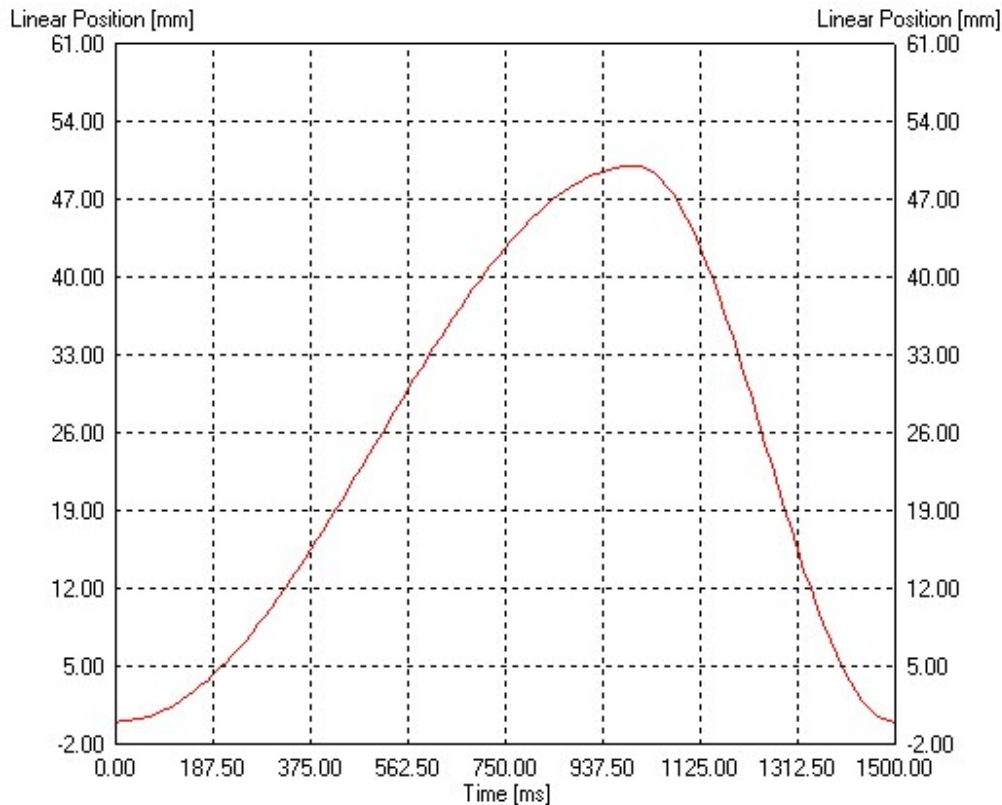
then press the “Join Curves” button  The curve settings mask for the joined curve appears:





We will set the curve name to “SineOutIn” and make sure the curve ID is 1. The curve length is proposed as the sum of the curve segment times. Please consider the maximal number of curves and curve points indicated in chapter [2.6](#). Press “Next” and “Finish”. The curve for the continuous curve mode is now defined and has, according to the parameter settings, the curve ID 1. As we want to download the curves to the drive we select all the curves in the edit window and move them to the download window.



When double click the “SineOutIn” Curve the joined curve is shown:





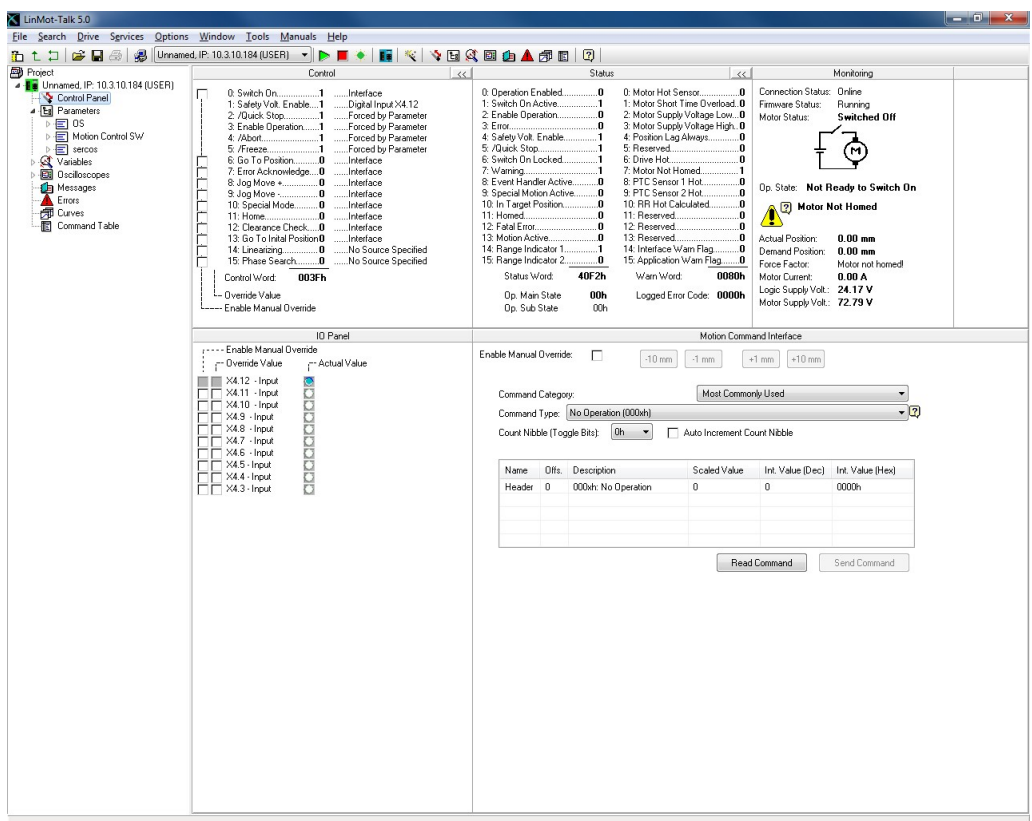
Now the curves must be downloaded to the drive. Therefore press the “Show Curves”

button  and then the “Download Curves into Drive” button  **Download into Controller**

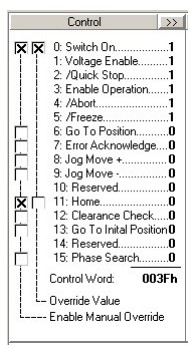
. Then a warning comes up which has to be confirmed and the progress window will display the actions taken to download the curves.

### 3.18 Control Status

As we have defined now all parameters and curves, we will let the motor running. For this time, we will take over the interface control from the PC. So we are interface-independent. Switch to the control panel with the button , then press the start button  (starting the drive's firmware) and wait until the control status panel is updated and looks the following:






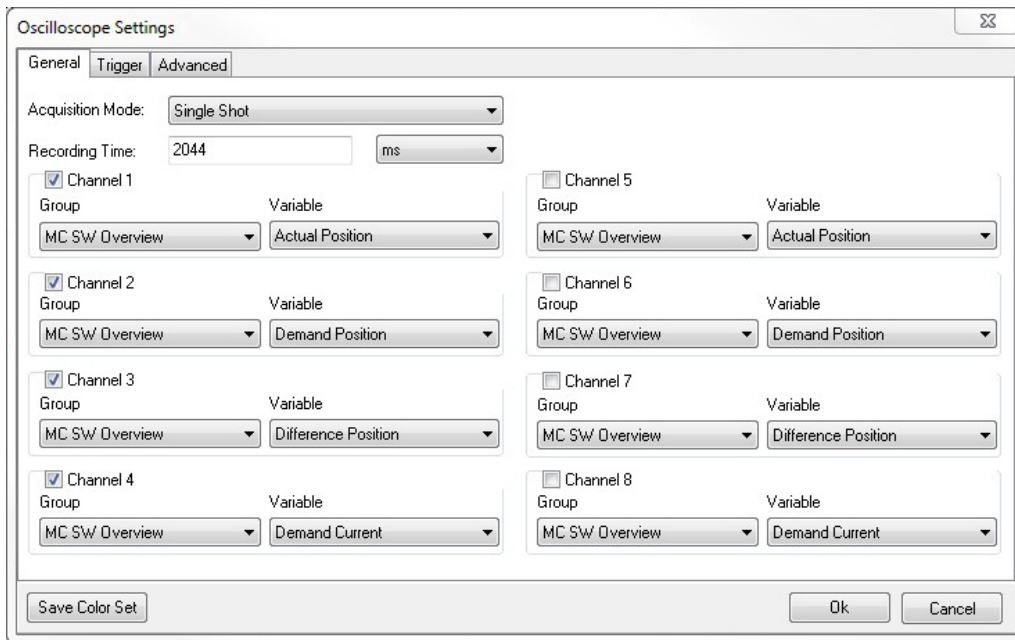
Now we will fetch the control over the “Switch On” and the “Home” flags.




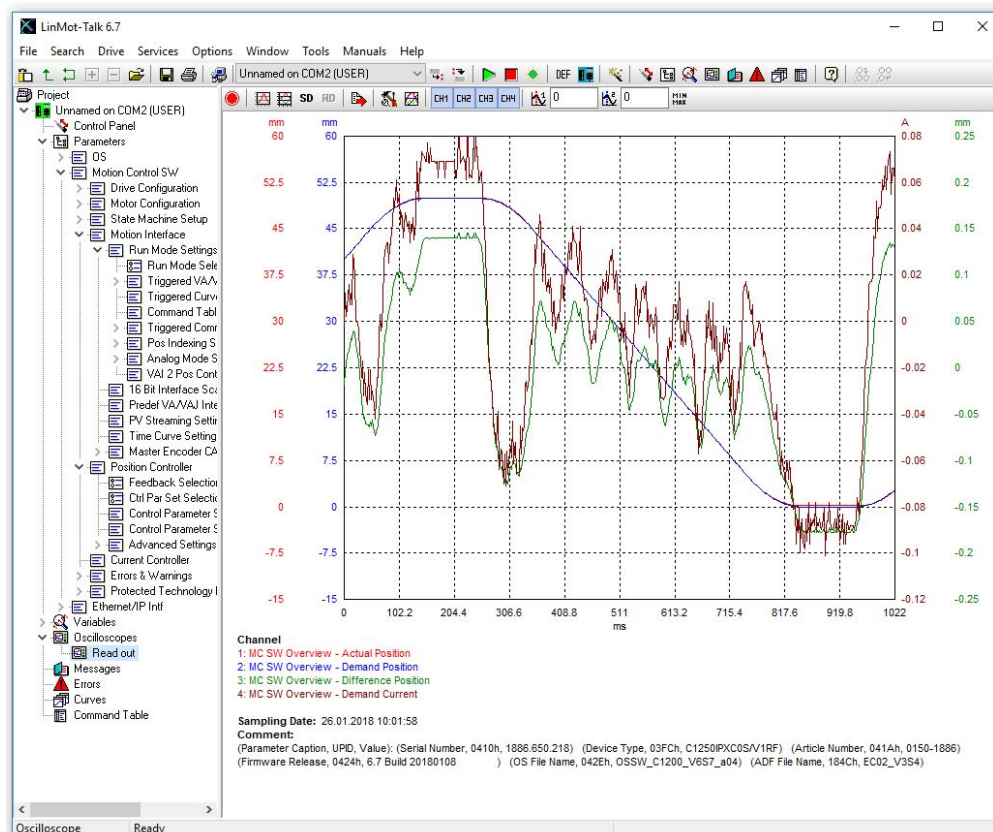
Now turn off and turn on again the “Switch On” flag, this is because of the auto start prevention. At this time, the motor will be powered and position controlled at the actual position. Set the “Home” flag and the motor will initialize against the inner hard stop. When the motor stands still, clear the “Home” flag and the motor will run the curve continuously. Detailed information about the MC software’s state diagram can be found in the MC software manual.


### 3.19 Oscilloscope

The oscilloscope is a very useful tool for tuning the motor. The LinMot-Talk software has defined a default oscilloscope, which samples the actual position, demand position, position difference and demand current. When clicking on the “Show Oscilloscope” button , the focus will be set to the default oscilloscope. We could start the oscilloscope now with the start button , but it is recommended to set the recording time about 2 seconds (one curve cycle is 1.5 s). We will switch to the oscilloscope settings with .






Then press Ok and start the oscilloscope with . The recorded data on will be read out from the drive and displayed, which will look somehow like the following.




Possibly it is necessary to press button  (fit view). Tuning the system would be started at this point. One possibility is by restarting the Motor Wizard and changing the load or control parameter, another one is to change the parameters directly in the parameter tree.


### 3.19.1 Display Settings


To Change the display settings in the oscilloscope there are several possibilities. One is with the Fit-Buttons  and . For both buttons it is possible to push the numbers on the Keyboard on the same time of clicking on the button. When some numbers are pushed, the functionality of the buttons has only influence on the channel with the same numbers. For example when somebody clicks on the Fit-Button and push on the same time number 2 and 3, only channel 2 and 3 will be fitted.



Fit view  looks that every channel is showed optimized in the window of the oscilloscope. Every point of a channel is in the window, but it uses the most part of the window.

Fit view (same unit same fit)  makes the same like fit view but the channels with the same units have the same scale. That means all points of all channels with the same unit are in the window and have the same scale.

An other possibility to scale the view is the mousewheel. With it the Keyboard has also influence. The number make the same like by the fit-view buttons and when the 'X' is pushed then it scales only in X-direction. The same is with the 'Y' then it scales only in the Y-direction. By scaling without all channels, it scales also only in Y-direction.

The third possibility is with the Display Settings window . In this window it is possible to change the scale, offset and colour of each channel. It is possible to change the

time scale. This button  changes how the curves are represented, only with a line,

only with the measure points  or with line and measure points .

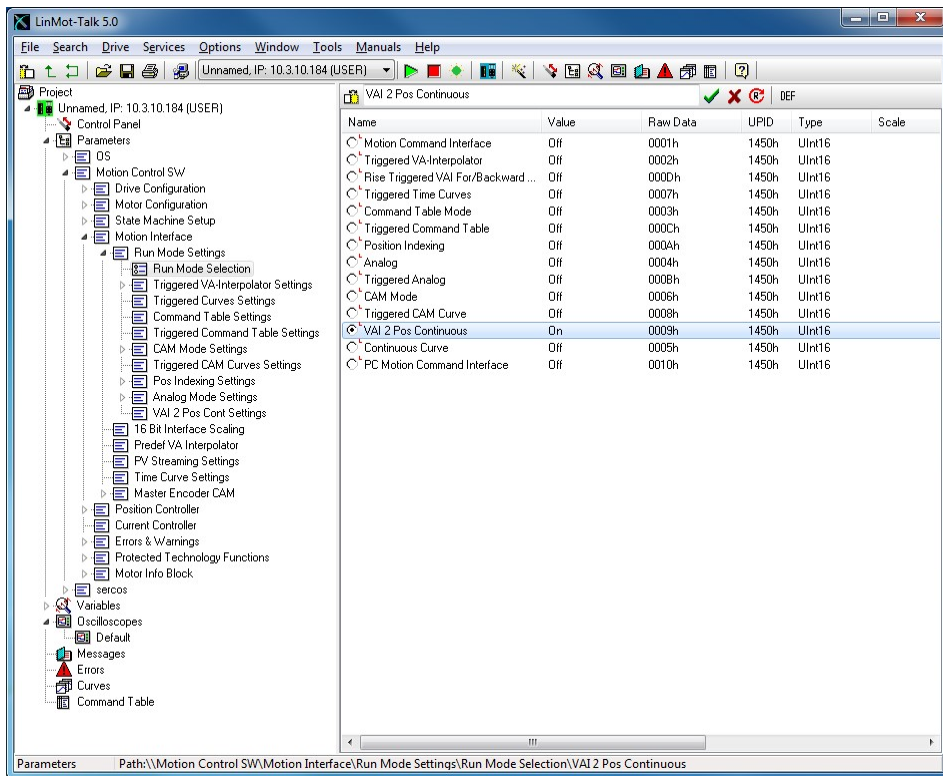
In the tab print it is possible to add some UPIDs. This UPIDs will be written with their values in the comment when the oscilloscope window will be printed. With this function it could given out some information, fore example some control parameters.

### 3.20 Continuous Two Point Mode

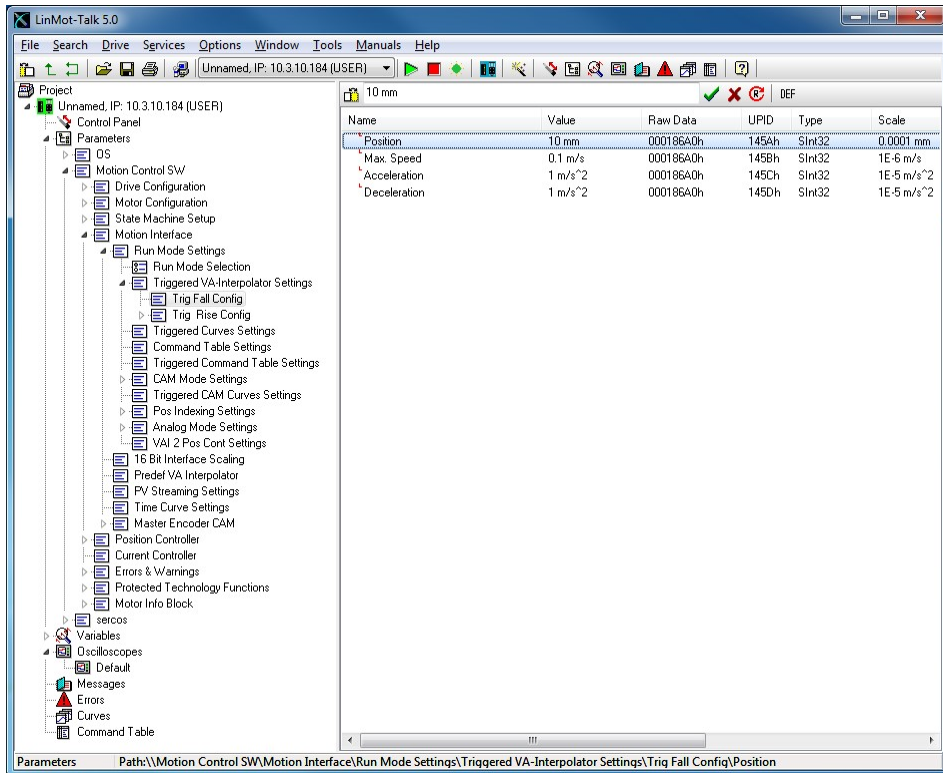
The easiest way to run the motor continuously is to set the VAI 2 Pos Continuous mode. In this mode the motor moves between the two positions Trig Fall and Trig Rise. The time the motor waits at the two positions is defined under "VAI 2 Pos Cont Settings".

The minimal settings for this mode are shown next. First the mode has to be set:





And then the positions have to be set under “Trig Fall Config\Position” and “Trig Rise Config\Position”:

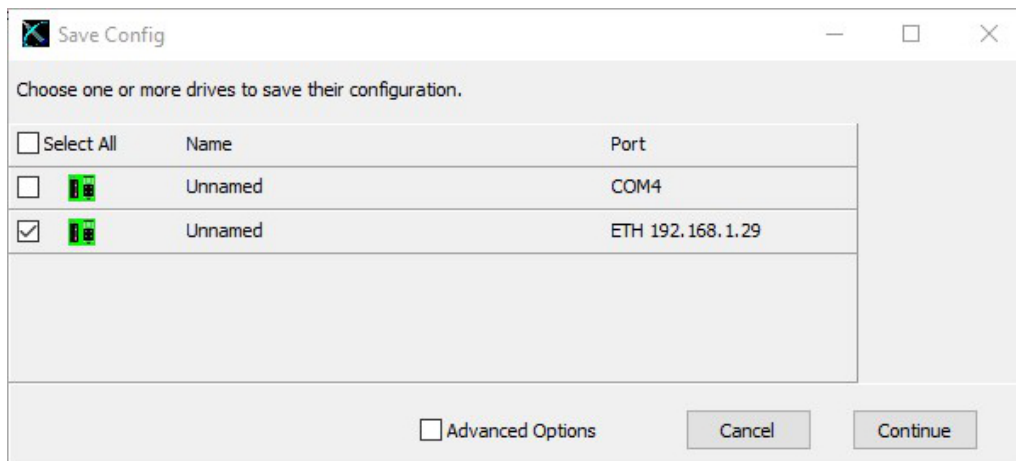


This is all we have to configure. The speed, acceleration and deceleration can also be defined at this place in the parameter tree. The motor can now be started the same way as described under [3.18](#) .

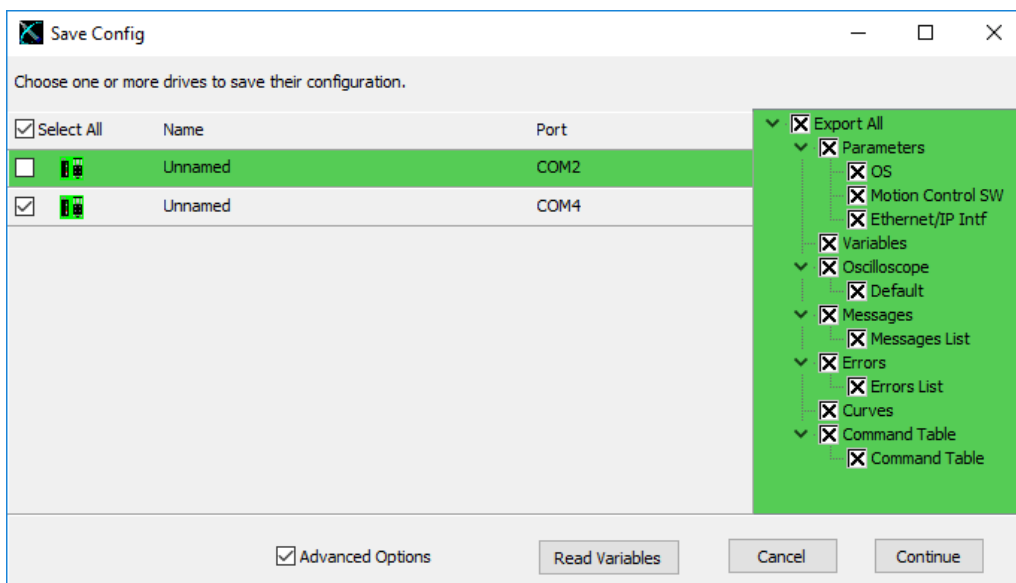


### 3.21 Export Configuration

When the drive settings are done, it is strongly recommended to save the complete configuration. This can be done under File à Export... or with by clicking on . First it will open the Save Config window. This window is to choose the drives, from them the config should be saved. There are the possibilities to select one drive or a group of drives. With out the Advanced Options the LinMot-Talk will read the empty (still not read) variables before it saves the configuration.



The selection Advanced Options opens the tree to select only parts of a drive. It can be selected for each drive different parts. The active drive is market green. To change the active drive only click on the new drive that should be active.




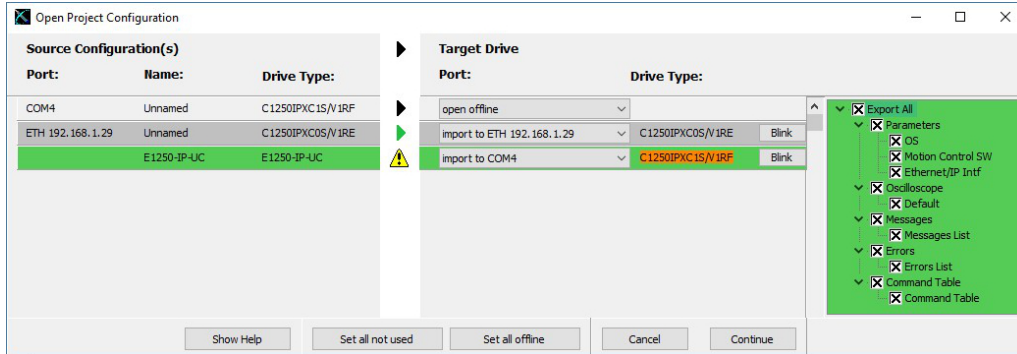
After that the file name dialog will open to choose the filename and the folder where the file should be saved.

It is recommended to export all parts of a drive. For a configuration recovery, it is necessary to select the parameters, curves and command table.


In case of a support request, it is recommended to save the configuration without the advanced options and all drives should be selected. Because then the supporters have all informations from the drive that they need.


### 3.22 Import Configuration


A configuration can be imported with File à Import... or with the button . First it opens a dialog window.




In this window, each configuration in the file has a line, in the combobox a drive could be selected. In this drive the configuration will be loaded. There are four possibilities of imports. They have the followed Symbols.

 not used

 open offline

 import to a drive with the same drivetype like the drivetype in the config

 import to a drive with another drivetype then the drivetype in the config. In this case, it can have some inconsistent parameter trees!

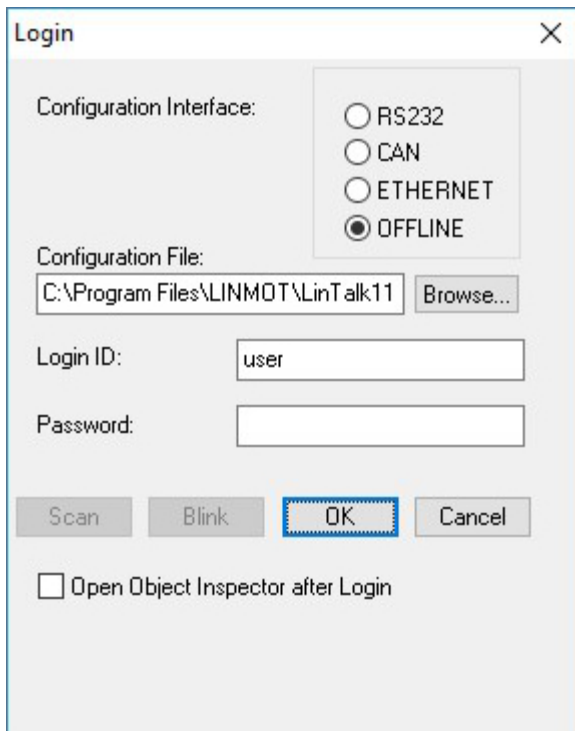
Two possibilities are always possible, not used and open offline. Not used means with this configuration nothing happens. Open offline means for this configuration an offline device will be created and the configuration will load in it. Each drive, on it the LinMot-Talk is logged in, could only selected in one line at the time.

In the green part on the right side of the window, it is possible to select the parts from the configuration, they will be imported to the drive. For each configuration, it has an only tree of parts. The shown tree is from the configuration that is green too. It is possible to import only some specific parts (e.g. curves or command table).

When opening a configuration to a drive, a compatibility list of the parameter trees will be shown. Then the selection of the importable parts will be shown.

### 3.23 Open Offline Configuration

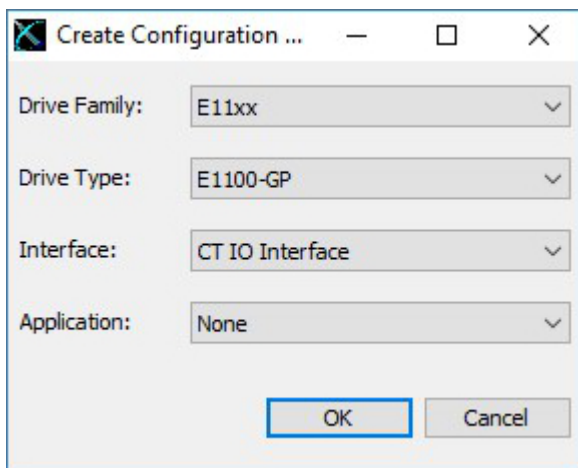
A configuration can also be opened when no drive is present. Under File à Login/Open offline...



This is a very helpful feature for supporting problems.

### 3.24 Create Offline Configuration

For any supported drive a configuration can be created offline. Choose the menu item File>Create Offline...



The above window will be shown. Select the drive family first, then select the drive type, then choose the interface and application software. The software parts, which can be selected, are the same as when installing firmware to the drive. When created the configuration, the parameters will have their default values. The configuration can then be altered and saved the normal way.

### 3.25 Compare Parameters

Under Drive → Compare Parameters, there is a function, which allows to compare the settings between different drives.

Nr.	UPID	Path	Name	Value1	Value2
1	03E8h	OS\Drive Name	Drive Name	E1400-GP-QN-1S Ver.2	E1450-EC-QN-0S Ver.2
2	2000h	CANopen Interface\Dis-/Enable	Dis-/Enable	Enable	UPID does not exist
3	2010h	CANopen Interface\Baud Rate\Baud ...	Baud Rate Source Select	By Hex Switch S1	UPID does not exist
4	2011h	CANopen Interface\Baud Rate\Baud ...	Baud Rate Parameter Definition	500 kBit/s [3]	UPID does not exist
5	2012h	CANopen Interface\Baud Rate\Advan...	BTR Value	22345	UPID does not exist
6	2013h	CANopen Interface\Node-ID\Node-ID...	Node-ID Source Select	By Hex Switch S2	UPID does not exist
7	2014h	CANopen Interface\Node-ID\Node-ID...	Node-ID Parameter Value	63	UPID does not exist
8	2100h	CANopen Interface\PDO Configuratio...	TxPDO 1 Enable	Enable	UPID does not exist
9	2101h	CANopen Interface\PDO Configuratio...	Transmission Type	1	UPID does not exist
10	2180h	CANopen Interface\PDO Configuratio...	No.of SYNC msgs between transmissions	1	UPID does not exist
11	2102h	CANopen Interface\PDO Configuratio...	Inhibit Time	10000us(Scale: 1.0000E+002, Offset...	UPID does not exist(Scale: 1.0000E+...
12	2103h	CANopen Interface\PDO Configuratio...	Event Time	100ms	UPID does not exist
13	2110h	CANopen Interface\PDO Configuratio...	TxPDO 2 Enable	Enable	UPID does not exist
14	2111h	CANopen Interface\PDO Configuratio...	Transmission Type	1	UPID does not exist
15	2181h	CANopen Interface\PDO Configuratio...	No.of SYNC msgs between transmissions	1	UPID does not exist
16	2112h	CANopen Interface\PDO Configuratio...	Inhibit Time	10000us(Scale: 1.0000E+002, Offset...	UPID does not exist(Scale: 1.0000E+...
17	2113h	CANopen Interface\PDO Configuratio...	Event Time	100ms	UPID does not exist
18	2120h	CANopen Interface\PDO Configuratio...	TxPDO 3 Enable	Enable	UPID does not exist
19	2121h	CANopen Interface\PDO Configuratio...	Transmission Type	1	UPID does not exist
20	2182h	CANopen Interface\PDO Configuratio...	No.of SYNC msgs between transmissions	1	UPID does not exist
21	2122h	CANopen Interface\PDO Configuratio...	Inhibit Time	10000us(Scale: 1.0000E+002, Offset...	UPID does not exist(Scale: 1.0000E+...
22	2123h	CANopen Interface\PDO Configuratio...	Event Time	100ms	UPID does not exist

This useful function works with online and offline configurations. There are different setups available, such as firmware instances (OS, MC, INTF and APPL) or parameter types (read only or writable). The parameter list can be saved as a \*.pvl file (comma separated text file).

## 4 Trouble shooting

### 4.1 Setting all Parameters to Default Values

#### **E1100, E1200, E1400, B8050, MB8050, C1100-GP and C1250**

All parameters of the SG3 and SG5 drives can be set to their default values without the use of the LinMot-Talk. This can be done according these steps:

1. Power off the drive.
2. Set the two ID switches to 0xFF.
3. Power on the drive, the Error and Warn LEDs will blink alternately at ~4Hz.
4. Set the two ID switches to 0x00.
5. Wait until the Warn and EN LEDs will flash together at ~2Hz.
6. Power off and on again.

#### **B1100**

On SG4 drives an image of the default parameters will be stored during the software installation. This image can be reloaded to the operating parameters. The procedure is the following:

1. Set the parameter with UPID 0x6085 to 0x0001.
2. Power off the drive.
3. Power on the drive.

The value of the parameter with UPID 0x6085 will be automatically cleared to 0x0000.

#### **A1100**

All parameters set to their default values without the use of the LinMot-Talk. This can be done according these steps:

1. Power of the drive.
2. Set the DIP switch S5.2 to on.
3. Power on the drive, the Error and Warn LEDs will blink alternately at ~4Hz.
4. Set the DIP switch S5.2 to off.
5. Wait until the Warn and EN LEDs will flash together at ~2Hz.
6. Power off and on again.

### 4.2 Interface does not run

If the interface software (DeviceNet, CANopen, Profibus, LinRS) does not communicate there may be several reasons:

- Specific Interface Software not installed
- Switch S3.4 "Interface" on drive's bottom side must be set to "On". (In case of LinRS, this switch must be set to off when configuring over RS232, and set to on when running the LinRS interface).
- Parameter with UPID 2008h set to disable.
- Baud Rate and Node ID selection not correctly set (Parameters and/or ID switches on drive's front)

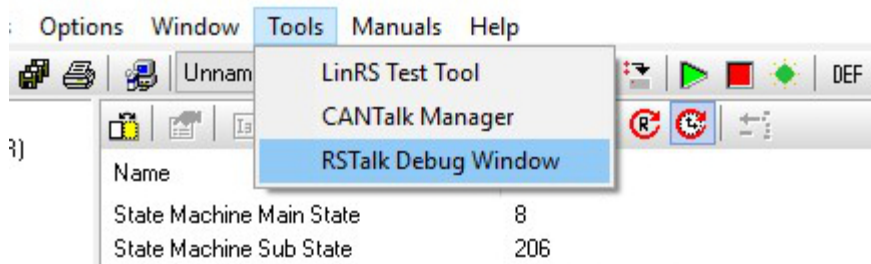
### 4.3 Stopping Firmware

When the same link is used for configuration purposes and from the interface (e.g. RS232 link and LinRS interface) it may not be possible to login with the LinMot-Talk software. In some cases, it should be possible to log in, e.g. to download new firmware.

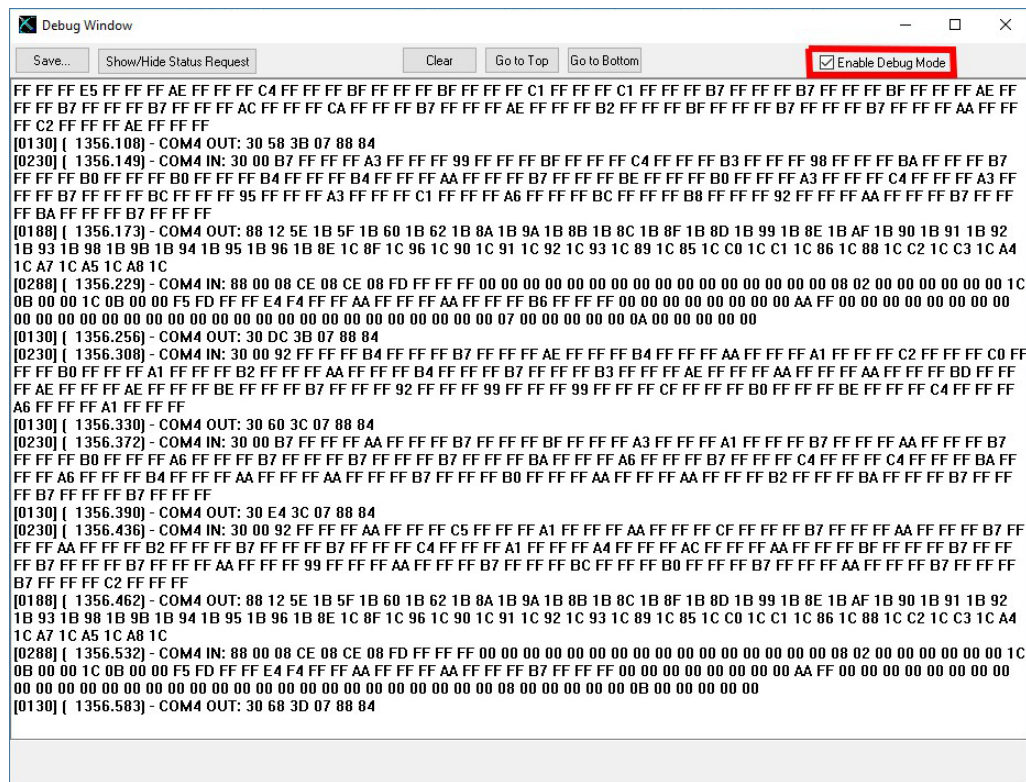
On E1100 drives, the interface switch S3.4 can be set to off and after a power up the interface software should be deactivated and the configuration link should be free. If this does not help, or you are working with a B1100 drive, there is a script under File -> Open -> StopFirmware.sct, which keeps trying to stop the drives firmware while it is powered on. After a power up, within the first 2 seconds the interface can be prevented from starting.

#### 4.4 Communication debug Window

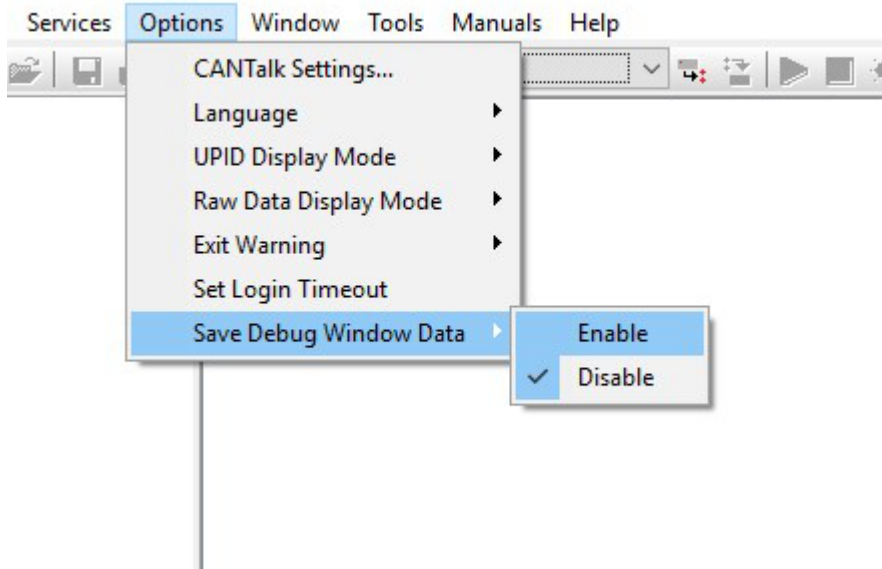
To see the communication between the LinMot-Talk and the Drives, there is a debug window. In the menu, Tools – RSTelk Debug Window, it opens the debug window.



The debug window looks like in the picture below. To see the communication, it is necessary to check the checkbox "Enable Debug Mode".



In the menu, Options – Save Debug Window Data, it is possible to enable the automatic save of the debug window.



If this is enabled, it is not necessary to have the debug window active. The data will be saved in files with the path: "C:\Users\username\AppData\Local\LinMot\LinMot-Talk6.6-BuildXXXXXXXX\Communication". The LinMot-Talk saves this data in 10 files. It saves the data cyclic and when it begins with a new file it overwrites the oldest one. Every time when the LinMot-Talk will be restarted this option is disabled.

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