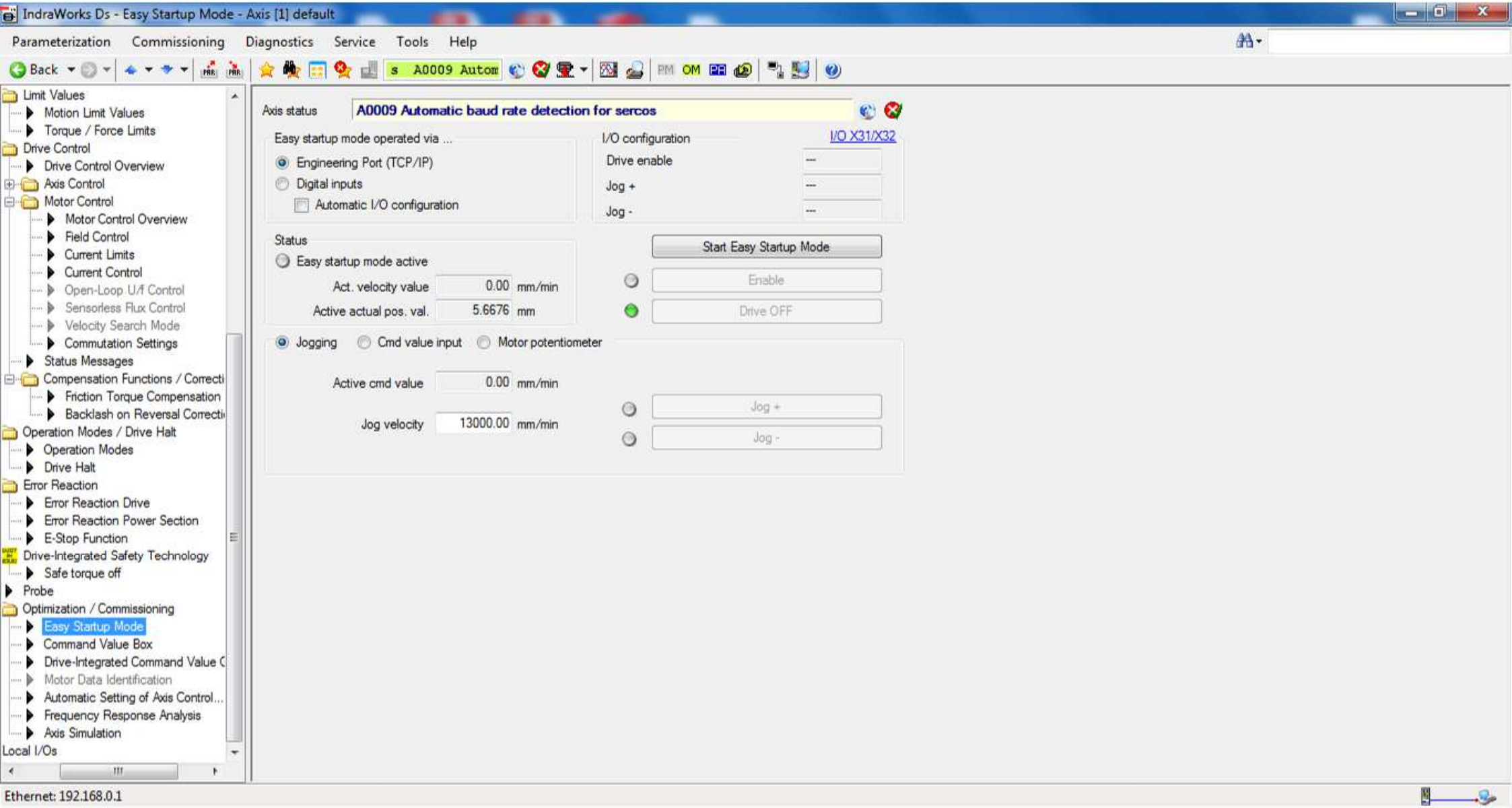
IndraWorks Ds - Easy Startup Mode - Axis [1] default
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s A0009 Autom
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A0009 Automatic baud rate detection for sercos
Easy startup mode operated via ...
Engineering Port (TCP/IP)
Digital inputs
Automatic I/O configuration
I/O configuration
I/O X31/X32
Drive enable
Jog +
Jog -
Status
Easy startup mode active
Act. velocity value
0.00
mm/min
Active actual pos. val.
5.6676
mm
Start Easy Startup Mode
Enable
Drive OFF
Jogging
Cmd value input
Motor potentiometer
Active cmd value
0.00
mm/min
Jog velocity
13000.00
mm/min
Jog +
Jog -
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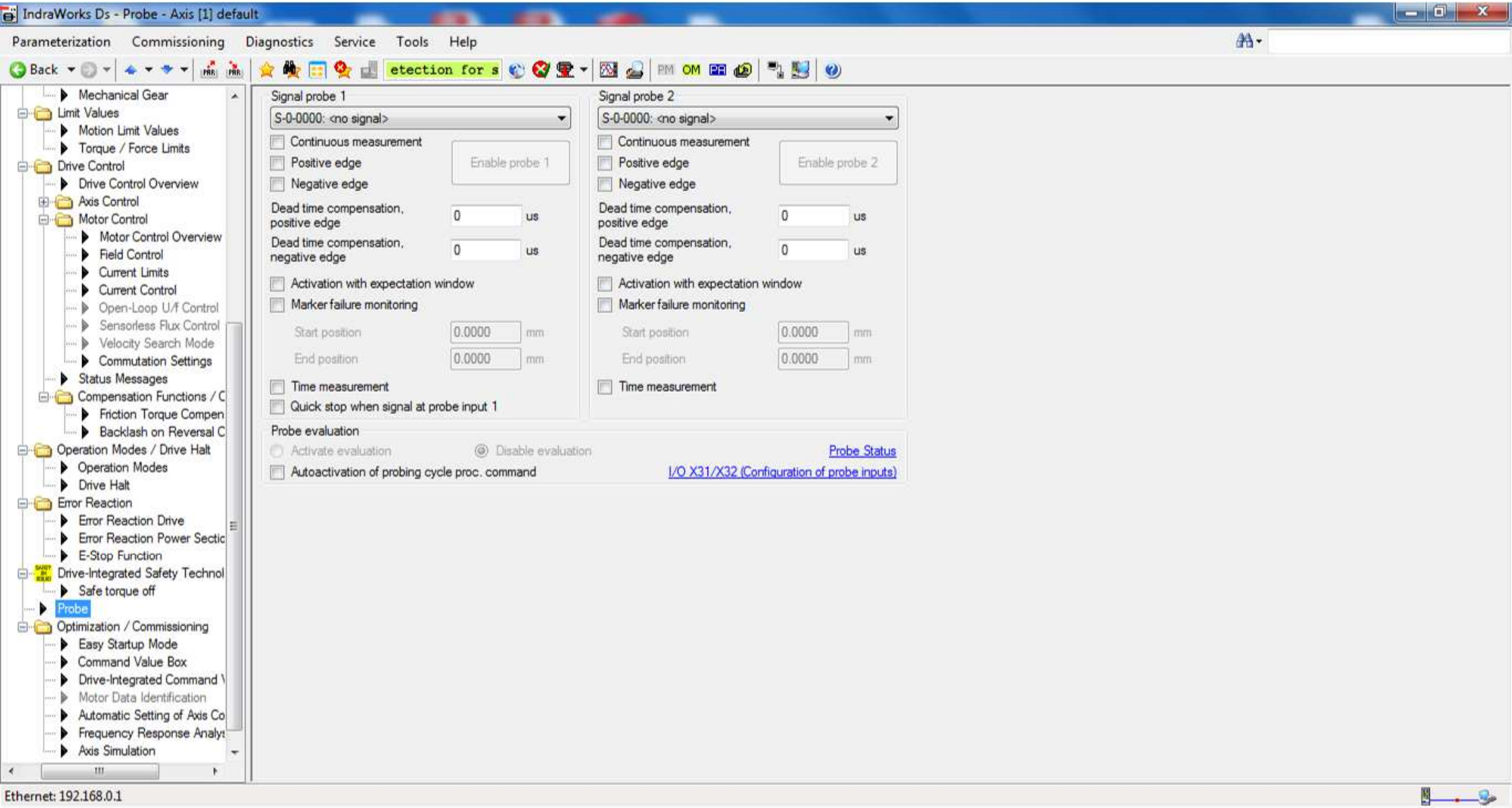
IndraWorks Ds - Probe - Axis [1] default
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Command Value Box
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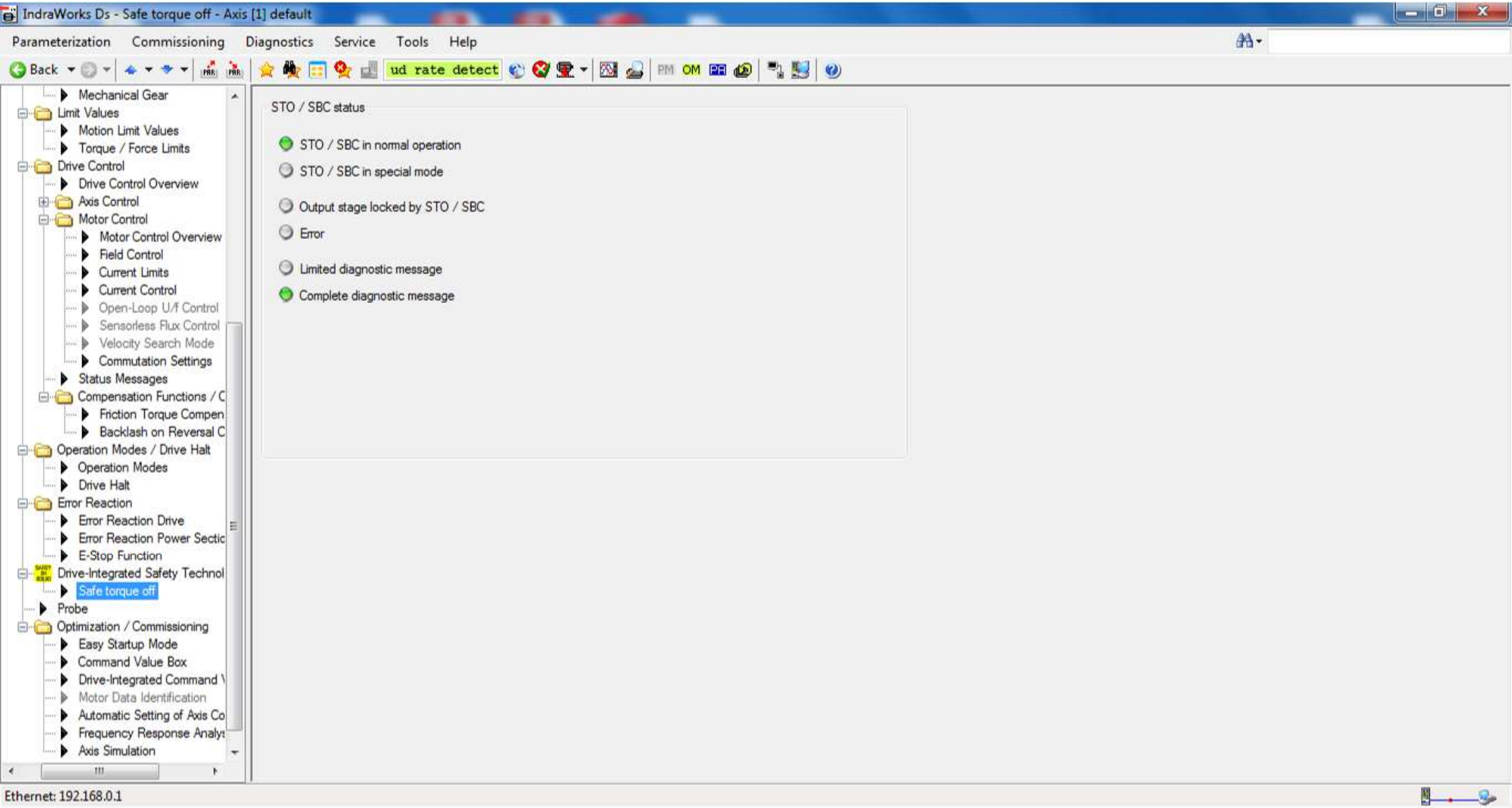
Motor Data Identification
Automatic Setting of Axis Co
Frequency Response Analys
Axis Simulation
Signal probe 1
S-0-0000: <no signal>
Continuous measurement
Positive edge
Negative edge
Enable probe 1
Dead time compensation, positive edge
0
us
Dead time compensation, negative edge
0
us
Activation with expectation window
Marker failure monitoring
Start position
0.0000
mm
End position
0.0000
mm
Time measurement
Quick stop when signal at probe input 1
Signal probe 2
S-0-0000: <no signal>
Continuous measurement
Positive edge
Negative edge
Enable probe 2
Dead time compensation, positive edge
0
us
Dead time compensation, negative edge
0
us
Activation with expectation window
Marker failure monitoring
Start position
0.0000
mm
End position
0.0000
mm
Time measurement
Probe evaluation
Activate evaluation
Disable evaluation
Probe Status
Autoactivation of probing cycle proc. command
I/O X31/X32 (Configuration of probe inputs)
Ethernet: 192.168.0.1


IndraWorks Ds - Safe torque off - Axis [1] default
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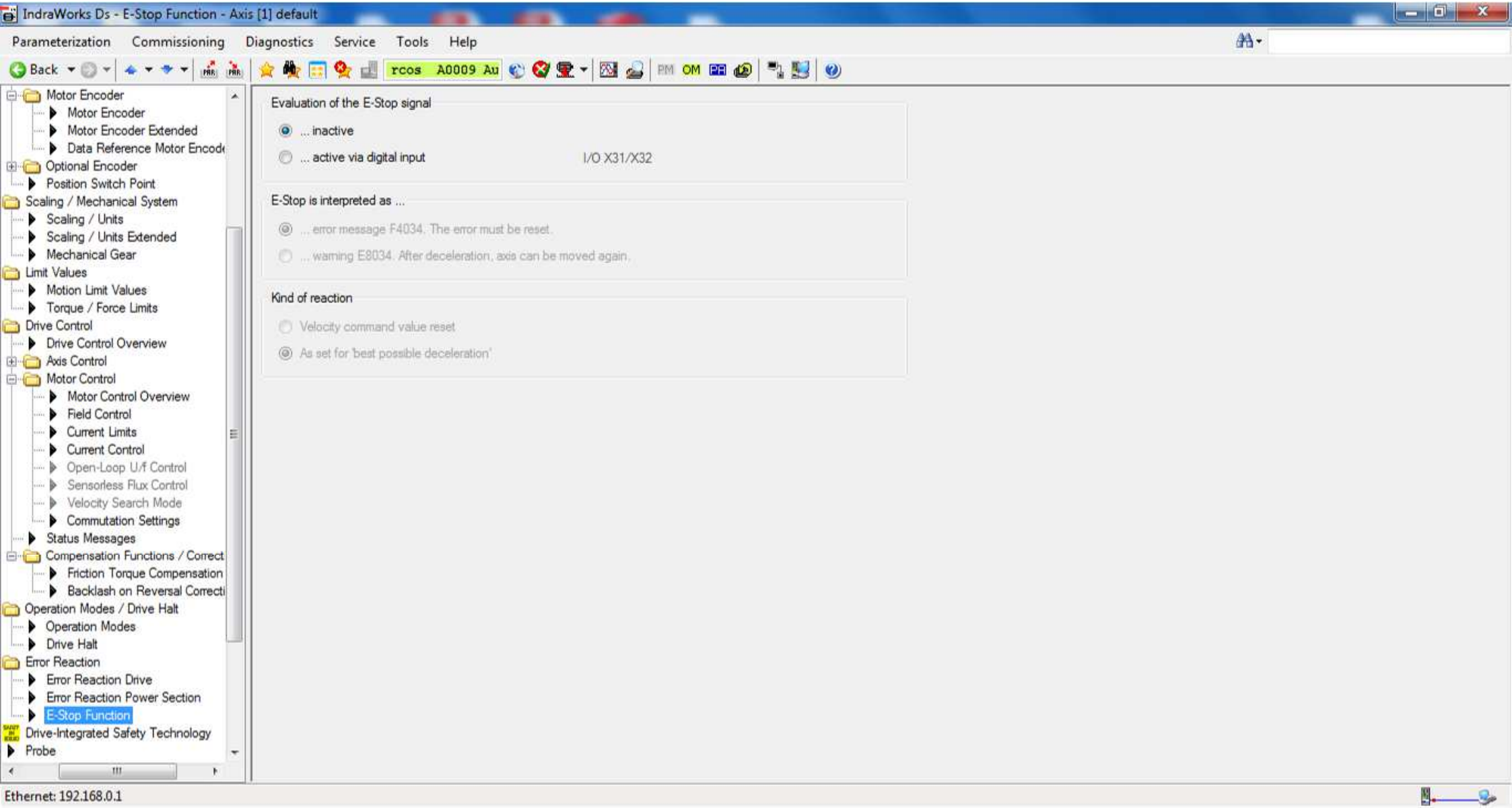
STO / SBC in normal operation
STO / SBC in special mode
Output stage locked by STO / SBC
Error
Limited diagnostic message
Complete diagnostic message
Ethernet: 192.168.0.1


IndraWorks Ds - E-Stop Function - Axis [1] default
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rcos A0009 Au
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Motor Encoder
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Operation Modes
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Error Reaction Power Section
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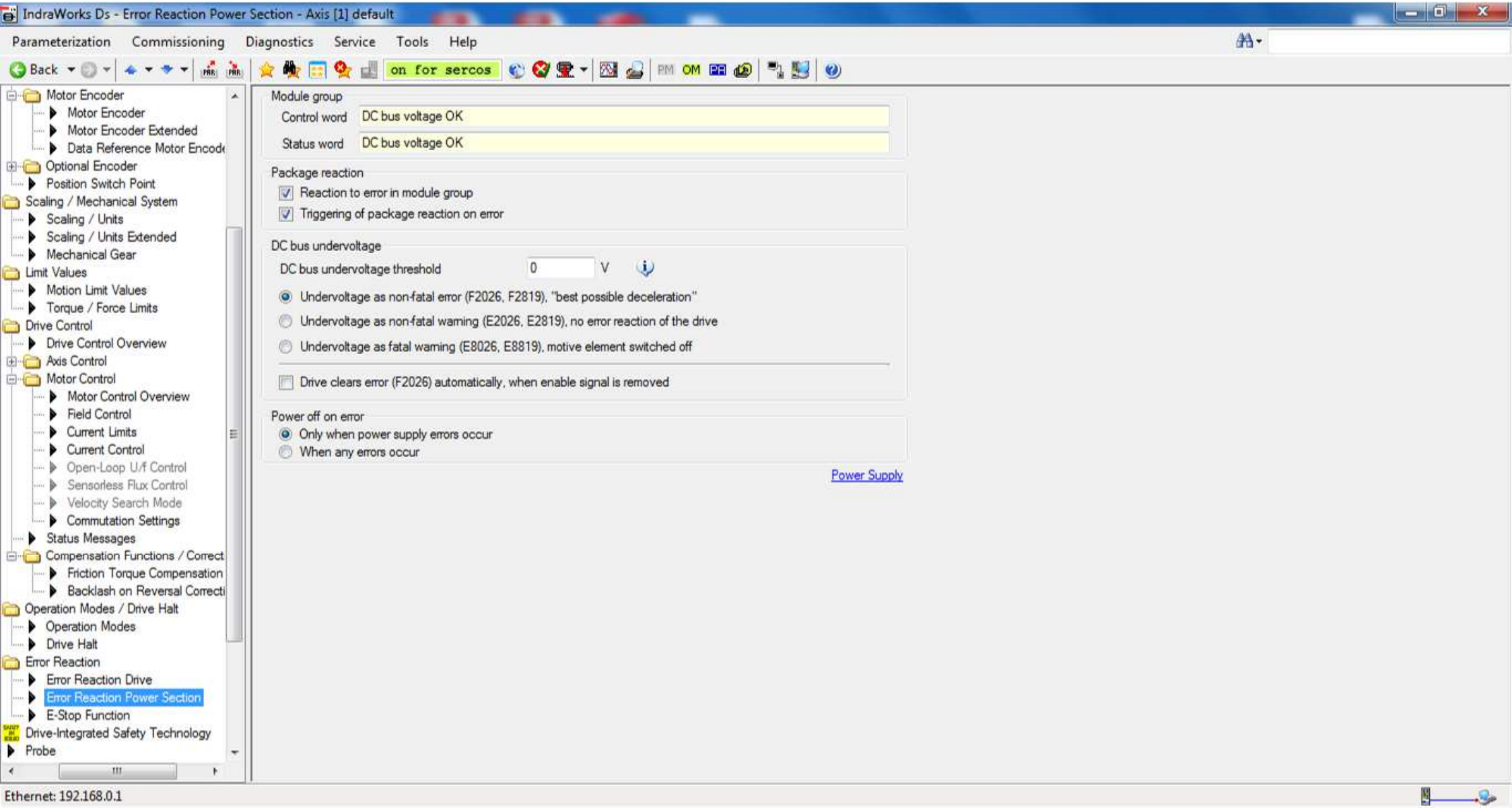
Probe
Evaluation of the E-Stop signal
... inactive
... active via digital input
I/O X31/X32
E-Stop is interpreted as ...
... error message F4034. The error must be reset.
... warning E8034. After deceleration, axis can be moved again.
Kind of reaction
Velocity command value reset
As set for 'best possible deceleration'
Ethernet: 192.168.0.1


IndraWorks Ds - Error Reaction Power Section - Axis [1] default
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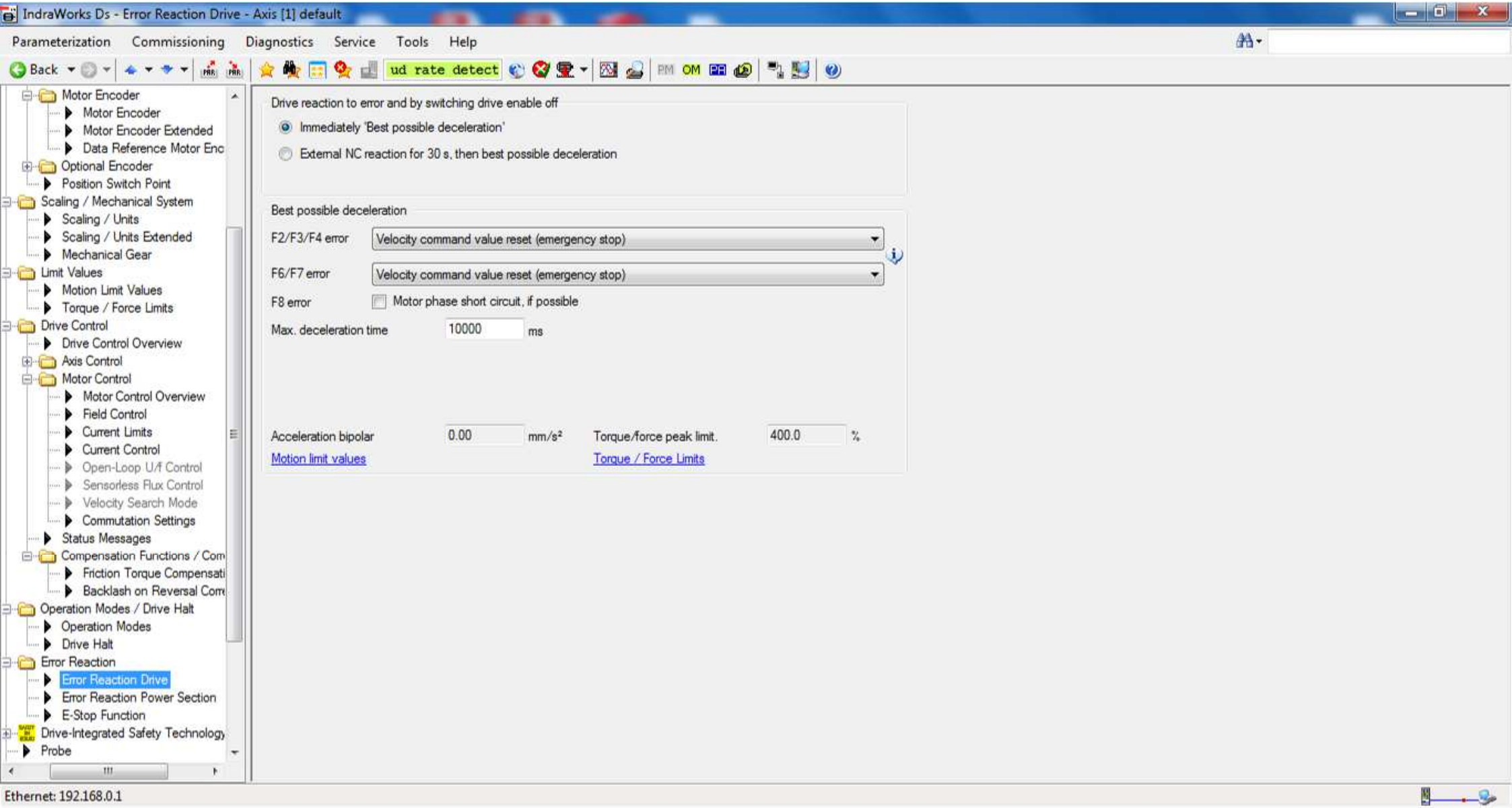
Module group
Control word
DC bus voltage OK
Status word
DC bus voltage OK
Package reaction
Reaction to error in module group
Triggering of package reaction on error
DC bus undervoltage
DC bus undervoltage threshold
0
V
Undervoltage as non-fatal error (F2026, F2819), "best possible deceleration"
Undervoltage as non-fatal warning (E2026, E2819), no error reaction of the drive
Undervoltage as fatal warning (E8026, E8819), motive element switched off
Drive clears error (F2026) automatically, when enable signal is removed
Power off on error
Only when power supply errors occur
When any errors occur
Power Supply
Ethernet: 192.168.0.1


IndraWorks Ds - Error Reaction Drive - Axis [1] default
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Drive reaction to error and by switching drive enable off
Immediately 'Best possible deceleration'
External NC reaction for 30 s, then best possible deceleration
Best possible deceleration
F2/F3/F4 error
Velocity command value reset (emergency stop)
F6/F7 error
Velocity command value reset (emergency stop)
F8 error
Motor phase short circuit, if possible
Max. deceleration time
10000
ms
Acceleration bipolar
0.00
mm/s²
Torque/force peak limit.
400.0
%
Motion limit values
Torque / Force Limits
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IndraWorks Ds - Drive Halt - Axis [1] default

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  - Drive Halt
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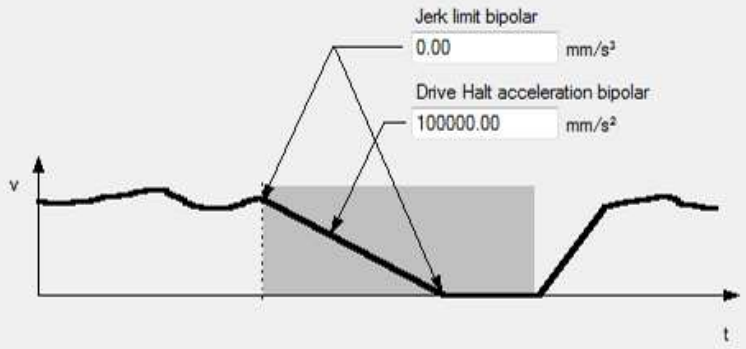


Drive Halt acknowledge

Standstill window

2000.00 mm/min

Status Messages

Drive Halt configuration

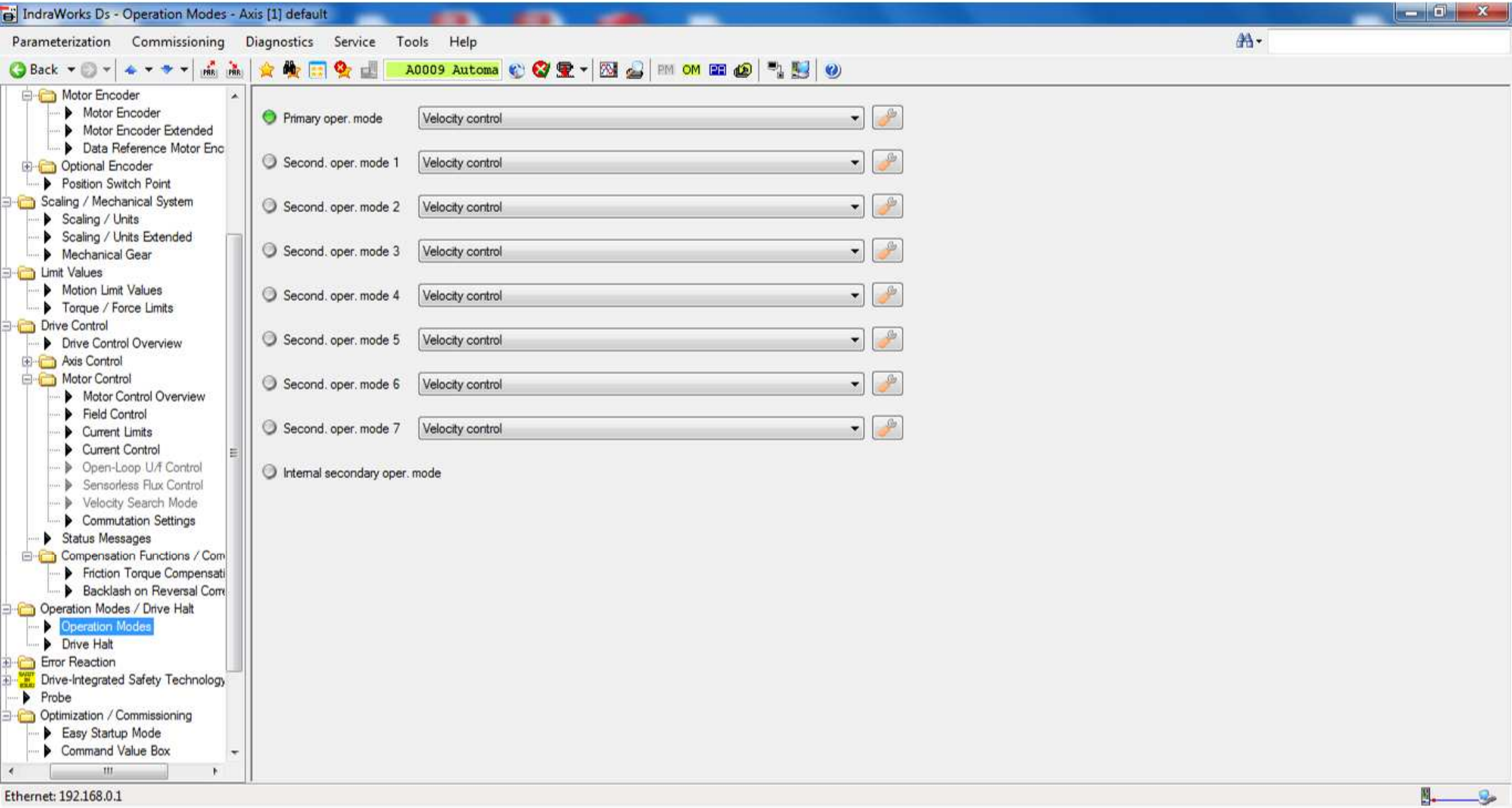
Best possible deceleration in active operation mode:

- Operational stop

Best possible deceleration in internal operation mode Drive Halt:

- Quick stop (position-controlled)
- Quick stop (velocity-controlled)
- Quick stop (defined by operation modes)

Ethernet: 192.168.0.1


IndraWorks Ds - Operation Modes - Axis [1] default
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Velocity control
Second. oper. mode 1
Velocity control
Second. oper. mode 2
Velocity control
Second. oper. mode 3
Velocity control
Second. oper. mode 4
Velocity control
Second. oper. mode 5
Velocity control
Second. oper. mode 6
Velocity control
Second. oper. mode 7
Velocity control
Internal secondary oper. mode
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IndraWorks Ds - Backlash on Reversal Correction - Axis [1] default

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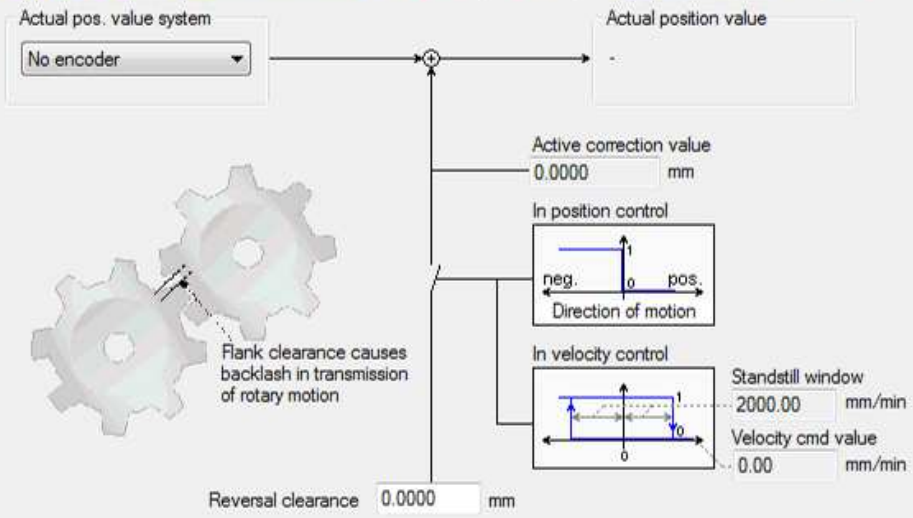
- eration Modes / Drive Halt
- or Reaction
- ve-Integrated Safety Technology
- be
- timization / Commissioning
- Easy Startup Mode
- Command Value Box
- Drive-Integrated Command Value Generat
- Motor Data Identification



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IndraWorks Ds - Friction Torque Compensation - Axis [1] default

Parameterization Commissioning Diagnostics Service Tools Help

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- Motor Encoder
  - Motor Encoder
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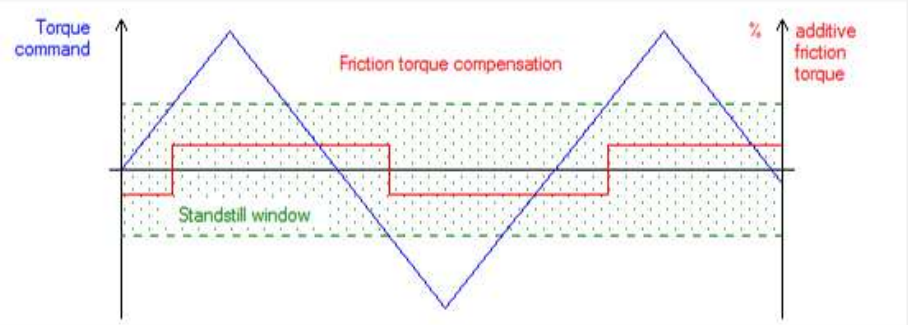
- Command Value Box
- Drive-Integrated Command Value Gen
- Motor Data Identification

Friction torque compensation

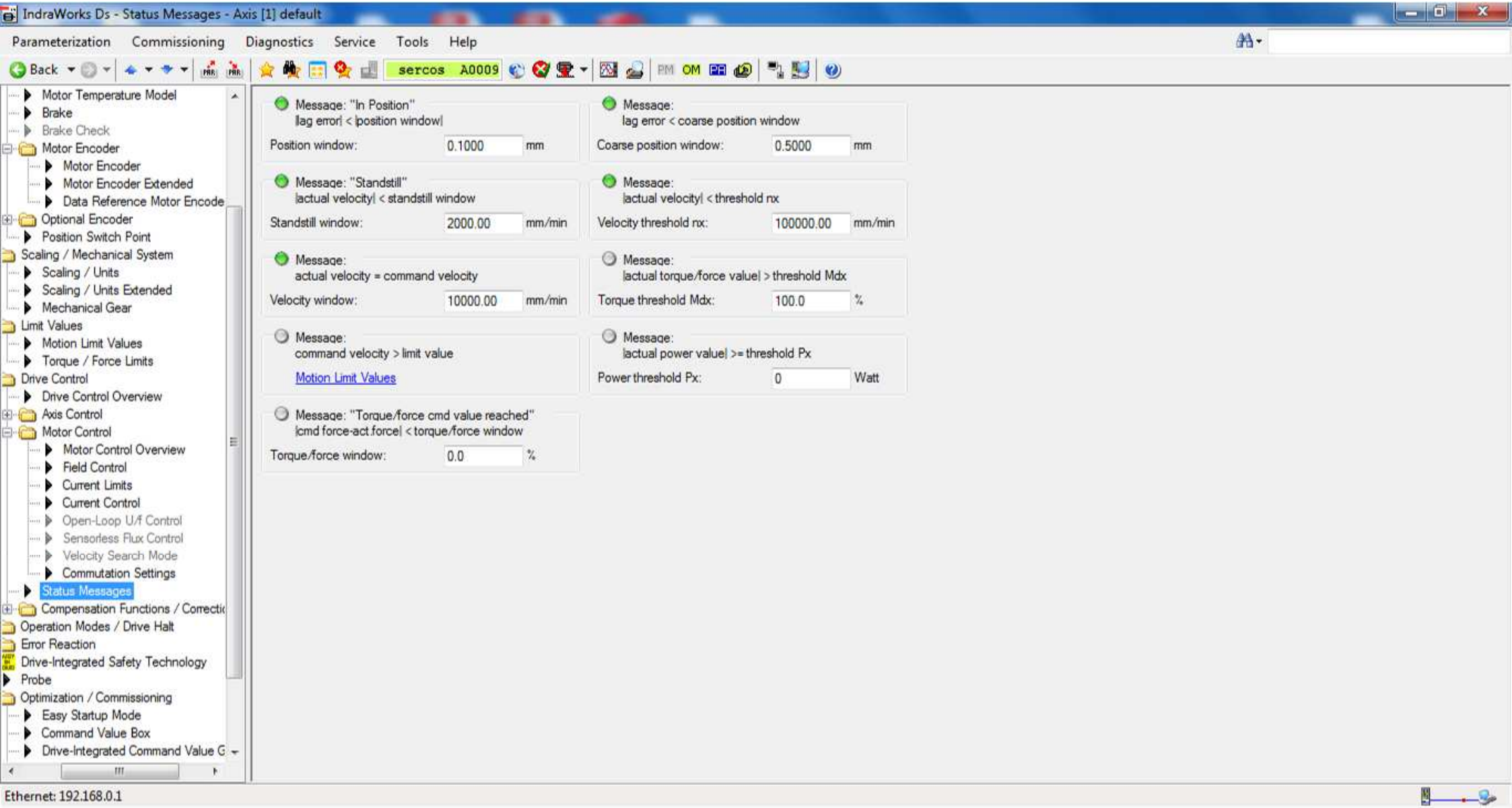
0.0 % = $\frac{\text{| Friction value, positive | + | Friction value, negative |}}{2}$



with

Standstill window 2000.00 mm/min

Ethernet: 192.168.0.1


IndraWorks Ds - Status Messages - Axis [1] default
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sercos A0009
Motor Temperature Model
Brake
Brake Check
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Operation Modes / Drive Halt
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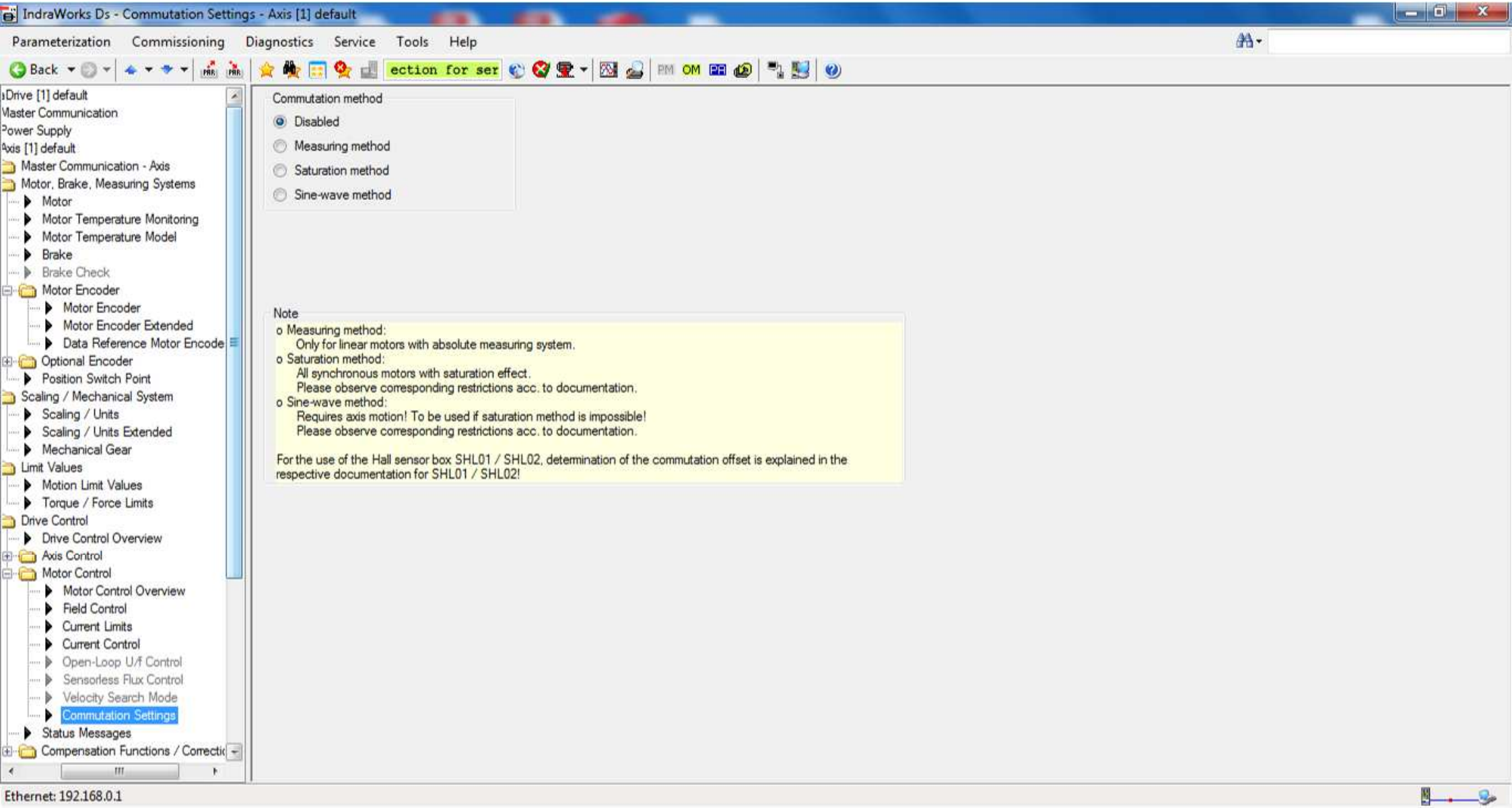
Command Value Box
Drive-Integrated Command Value G
Message: "In Position"
|lag error| < |position window|
Position window: 0.1000 mm
Message:
lag error < coarse position window
Coarse position window: 0.5000 mm
Message: "Standstill"
|actual velocity| < standstill window
Standstill window: 2000.00 mm/min
Message:
|actual velocity| < threshold rx
Velocity threshold rx: 100000.00 mm/min
Message:
actual velocity = command velocity
Velocity window: 10000.00 mm/min
Message:
|actual torque/force value| > threshold Mdx
Torque threshold Mdx: 100.0 %
Message:
command velocity > limit value
Motion Limit Values
Message:
|actual power value| >= threshold Px
Power threshold Px: 0 Watt
Message: "Torque/force cmd value reached"
|cmd force-act.force| < torque/force window
Torque/force window: 0.0 %
Ethernet: 192.168.0.1


IndraWorks Ds - Commutation Settings - Axis [1] default
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Drive [1] default
Master Communication
Power Supply
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Commutation method
Disabled
Measuring method
Saturation method
Sine-wave method
Note
o Measuring method:
Only for linear motors with absolute measuring system.
o Saturation method:
All synchronous motors with saturation effect.
Please observe corresponding restrictions acc. to documentation.
o Sine-wave method:
Requires axis motion! To be used if saturation method is impossible!
Please observe corresponding restrictions acc. to documentation.
For the use of the Hall sensor box SHL01 / SHL02, determination of the commutation offset is explained in the respective documentation for SHL01 / SHL02!
Ethernet: 192.168.0.1

IndraWorks Ds - Current Control - Axis [1] default

Parameterization Commissioning Diagnostics Service Tools Help

Back rate detection

- Drive [1] default
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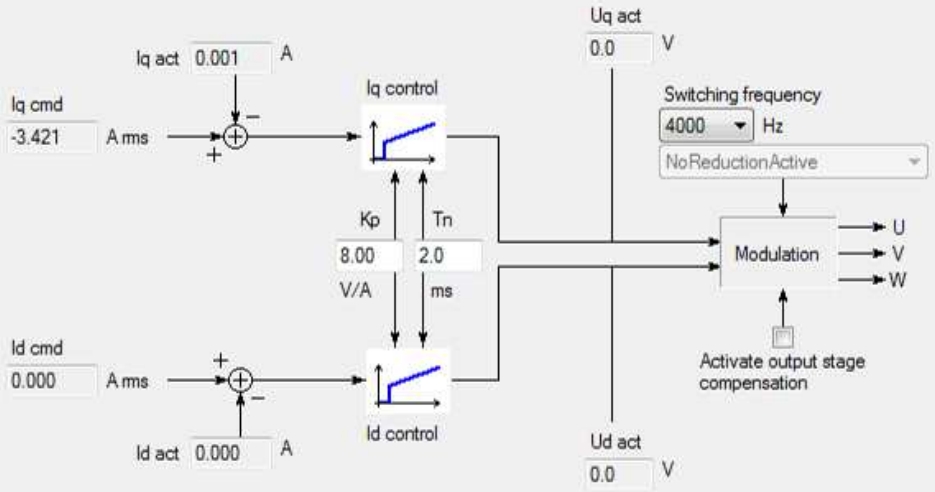
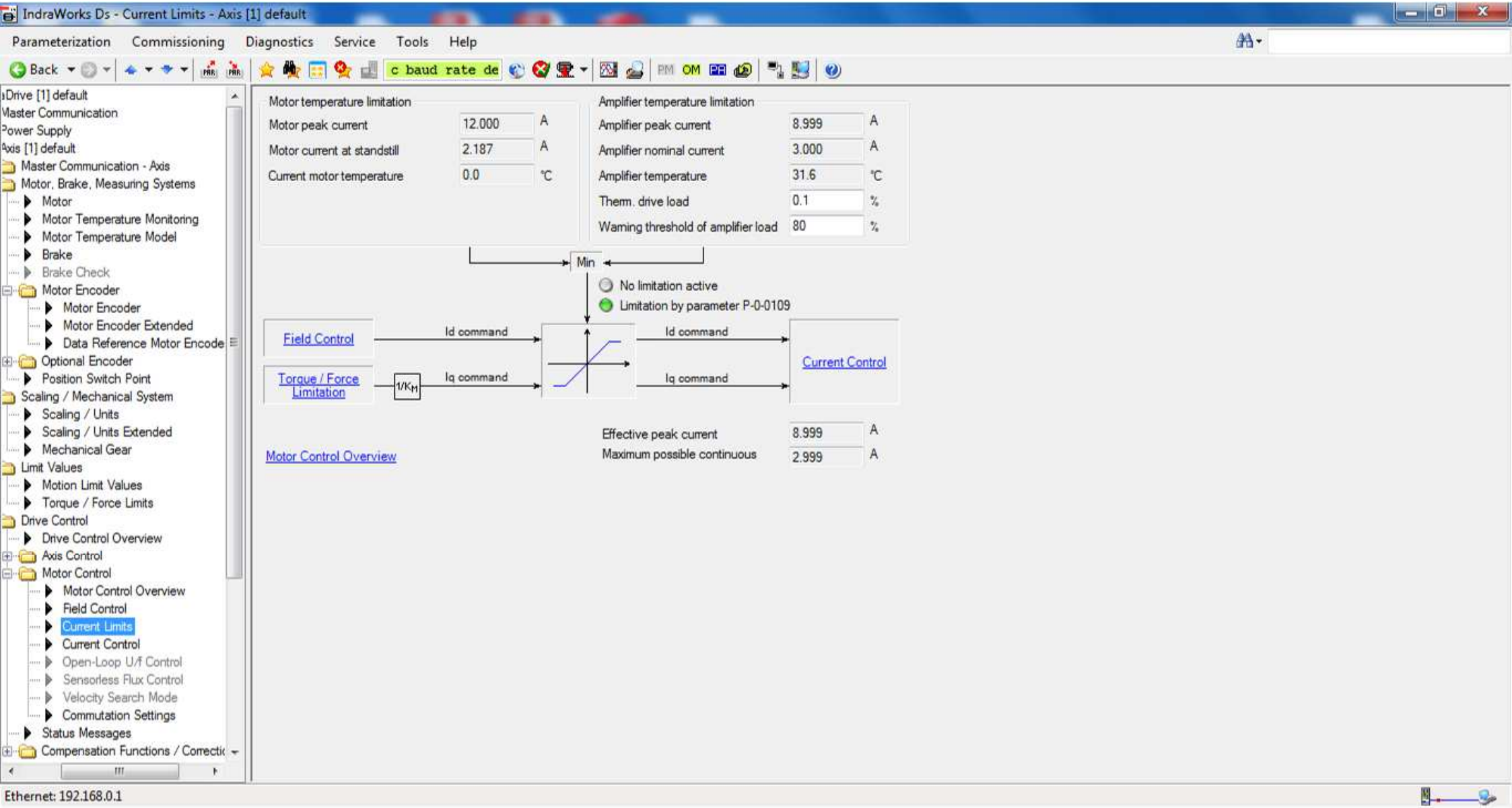
    - Compensation Functions / Correcti



Motor Control Overview

Ethernet: 192.168.0.1


IndraWorks Ds - Current Limits - Axis [1] default
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c baud rate de
Drive [1] default
Master Communication
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Motor temperature limitation
Motor peak current
12.000
A
Motor current at standstill
2.187
A
Current motor temperature
0.0
°C
Amplifier temperature limitation
Amplifier peak current
8.999
A
Amplifier nominal current
3.000
A
Amplifier temperature
31.6
°C
Therm. drive load
0.1
%
Warning threshold of amplifier load
80
%
Min
No limitation active
Limitation by parameter P-0-0109
Field Control
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Id command
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Iq command
Iq command
Effective peak current
8.999
A
Maximum possible continuous
2.999
A
Motor Control Overview
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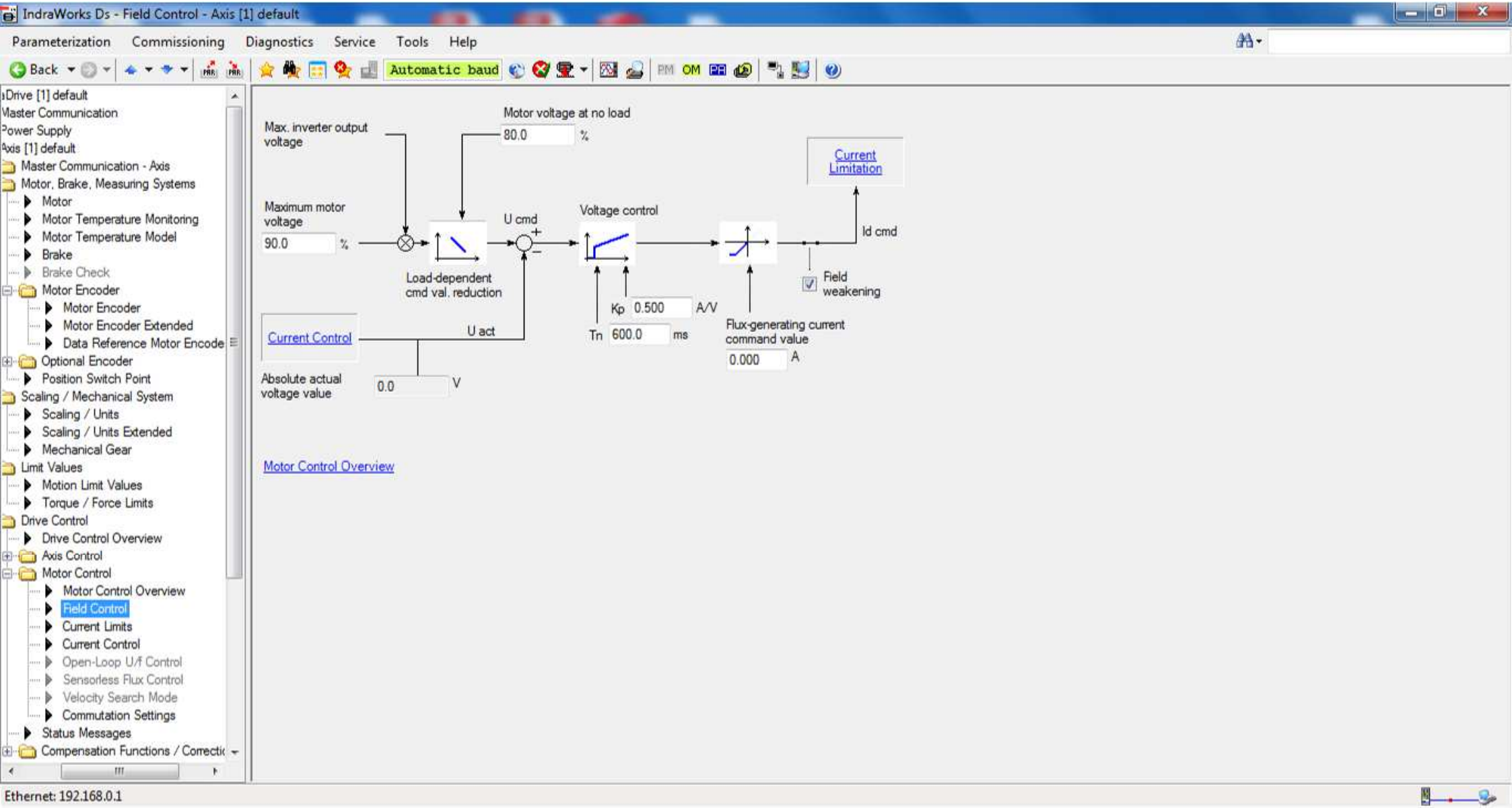
IndraWorks Ds - Field Control - Axis [1] default
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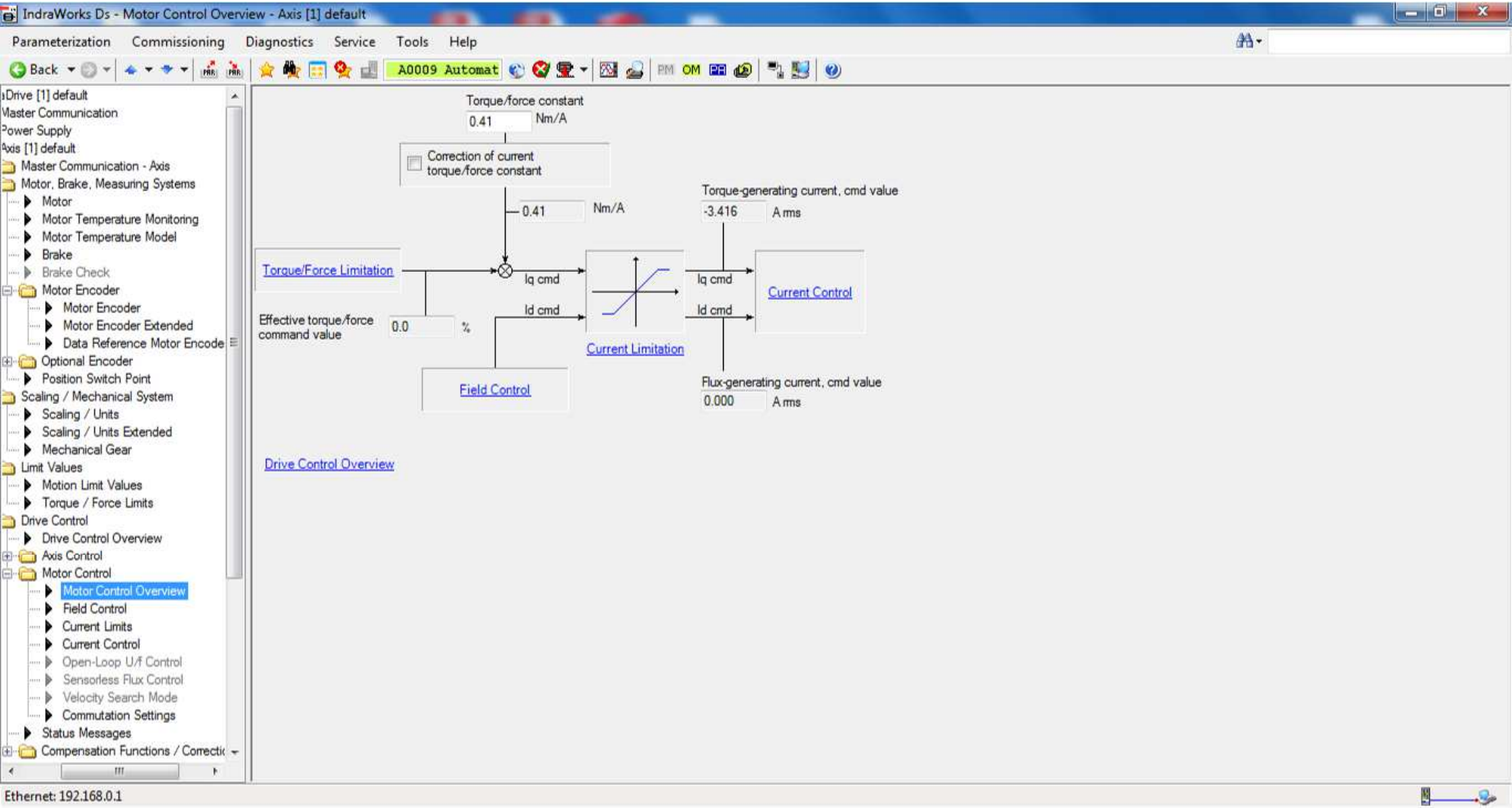
Sensorless Flux Control
Velocity Search Mode
Commutation Settings
Status Messages
Compensation Functions / Correcti
Motor voltage at no load
Max. inverter output voltage
80.0
%
Current Limitation
Maximum motor voltage
90.0
%
U cmd
Voltage control
Id cmd
Load-dependent cmd val. reduction
Field weakening
Kp 0.500 A/V
Tn 600.0 ms
Current Control
U act
Flux-generating current command value
0.000
A
Absolute actual voltage value
0.0
V
Motor Control Overview
Ethernet: 192.168.0.1


IndraWorks Ds - Motor Control Overview - Axis [1] default
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Torque/force constant
0.41
Nm/A
Correction of current torque/force constant
0.41
Nm/A
Torque-generating current, cmd value
-3.416
A rms
Torque/Force Limitation
Iq cmd
Id cmd
Effective torque/force command value
0.0
%
Current Limitation
Iq cmd
Id cmd
Current Control
Field Control
Flux-generating current, cmd value
0.000
A rms
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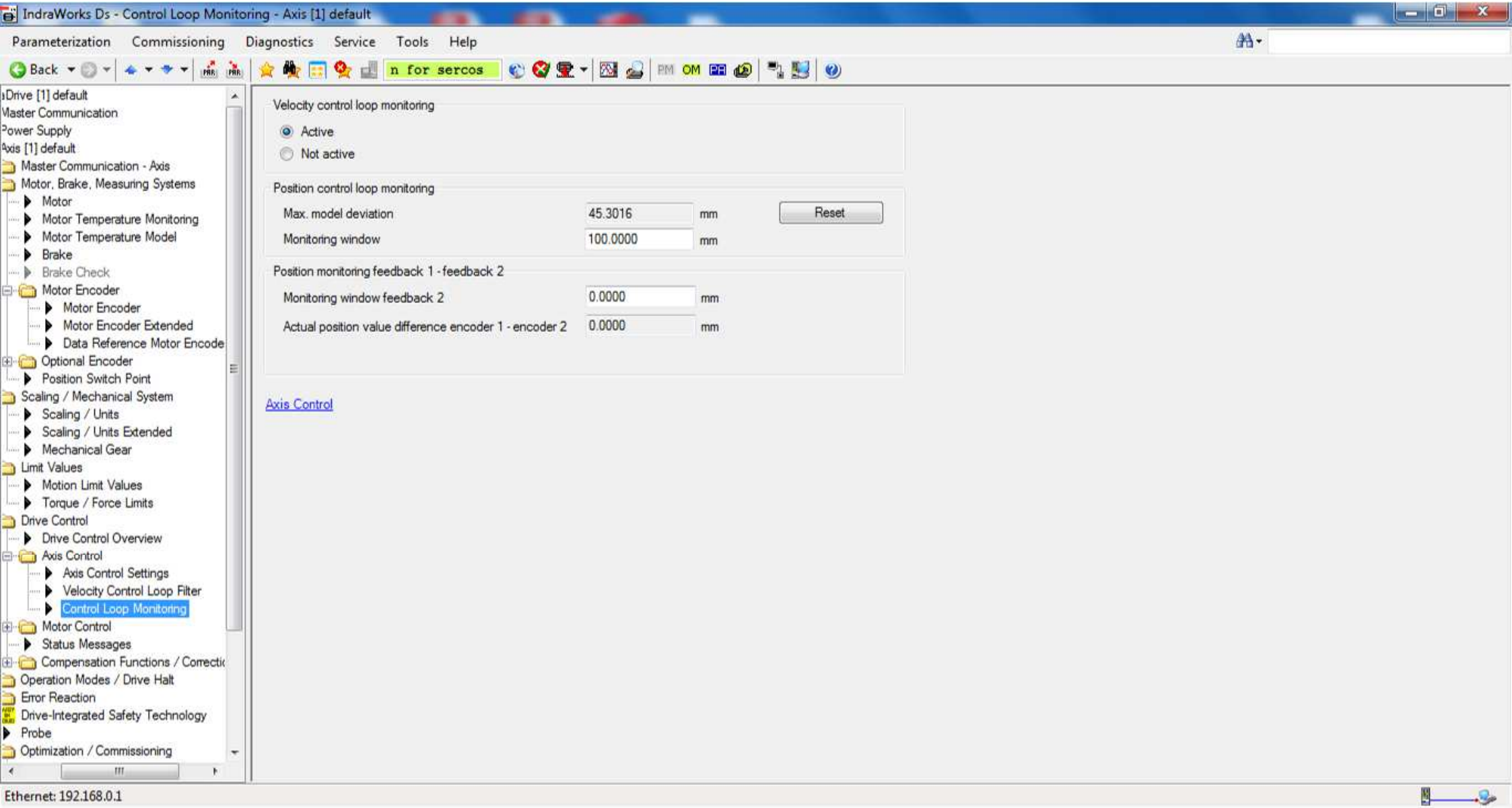
IndraWorks Ds - Control Loop Monitoring - Axis [1] default
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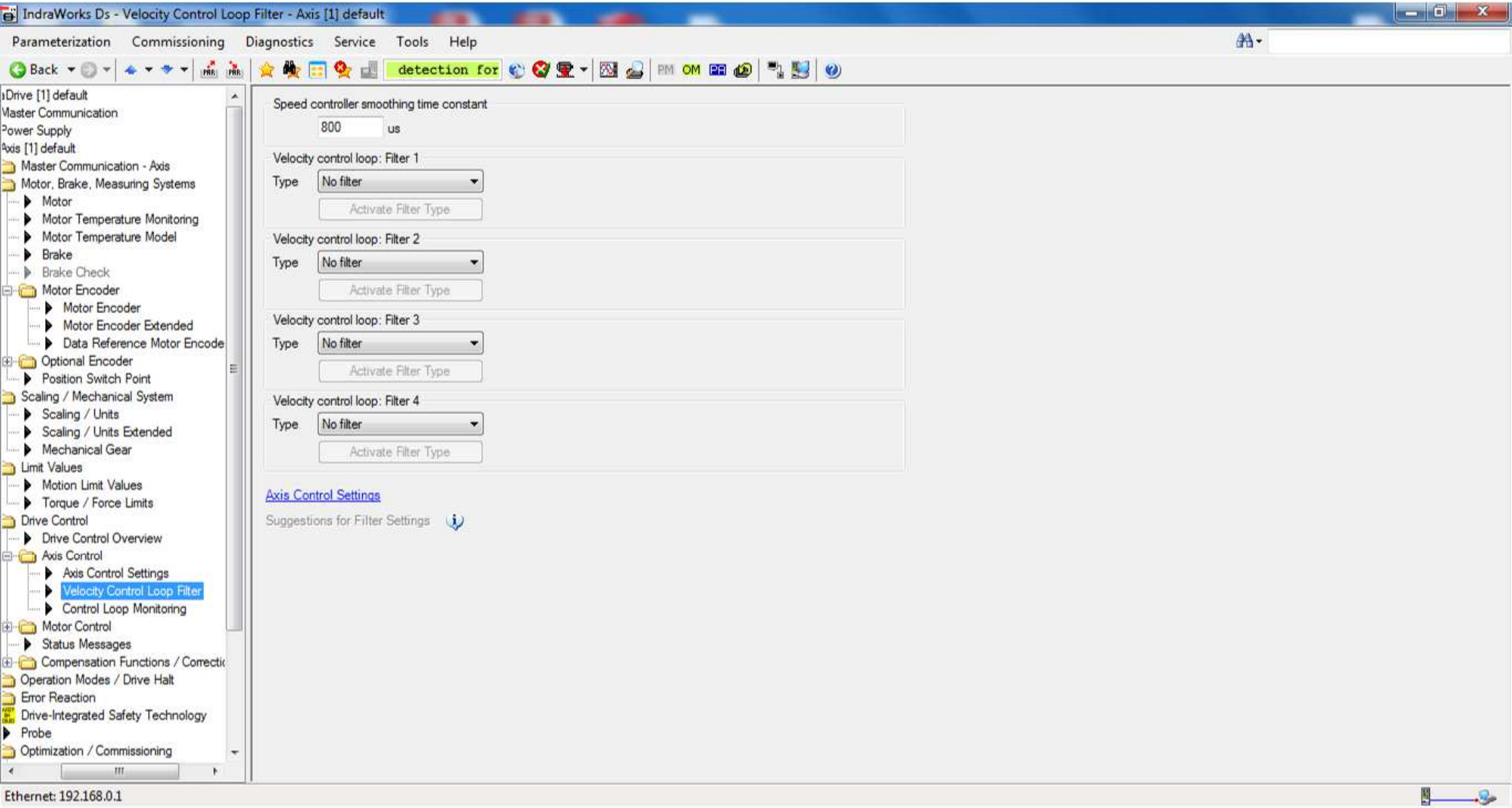
Velocity control loop monitoring
Active
Not active
Position control loop monitoring
Max. model deviation
45.3016
mm
Reset
Monitoring window
100.0000
mm
Position monitoring feedback 1 - feedback 2
Monitoring window feedback 2
0.0000
mm
Actual position value difference encoder 1 - encoder 2
0.0000
mm
Axis Control
Ethernet: 192.168.0.1


IndraWorks Ds - Velocity Control Loop Filter - Axis [1] default
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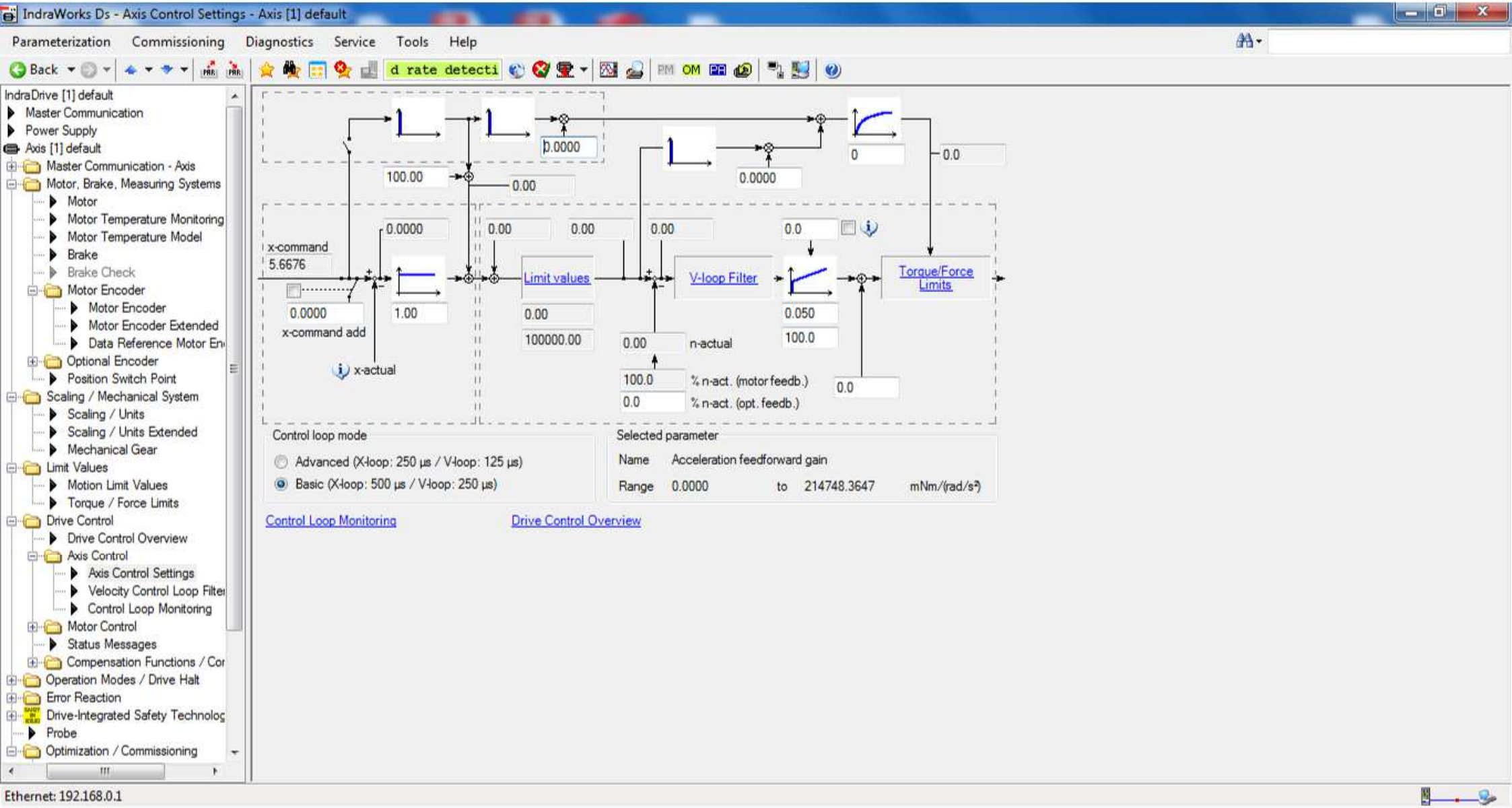
Speed controller smoothing time constant
800
us
Velocity control loop: Filter 1
Type
No filter
Activate Filter Type
Velocity control loop: Filter 2
Type
No filter
Activate Filter Type
Velocity control loop: Filter 3
Type
No filter
Activate Filter Type
Velocity control loop: Filter 4
Type
No filter
Activate Filter Type
Axis Control Settings
Suggestions for Filter Settings
Ethernet: 192.168.0.1


IndraWorks Ds - Axis Control Settings - Axis [1] default
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x-command
5.6676
0.0000
x-command add
x-actual
1.00
100.00
0.00
0.0000
0.00
0.00
0.00
Limit values
0.00
100000.00
V-loop Filter
0.0
0.050
100.0
Torque/Force Limits
0
0.0
0.0000
0.0
0.00
n-actual
100.0
% n-act. (motor feedb.)
0.0
% n-act. (opt. feedb.)
0.0
Control loop mode
Advanced (X-loop: 250 µs / V-loop: 125 µs)
Basic (X-loop: 500 µs / V-loop: 250 µs)
Selected parameter
Name
Acceleration feedforward gain
Range
0.0000
to
214748.3647
mNm/(rad/s²)
Control Loop Monitoring
Drive Control Overview
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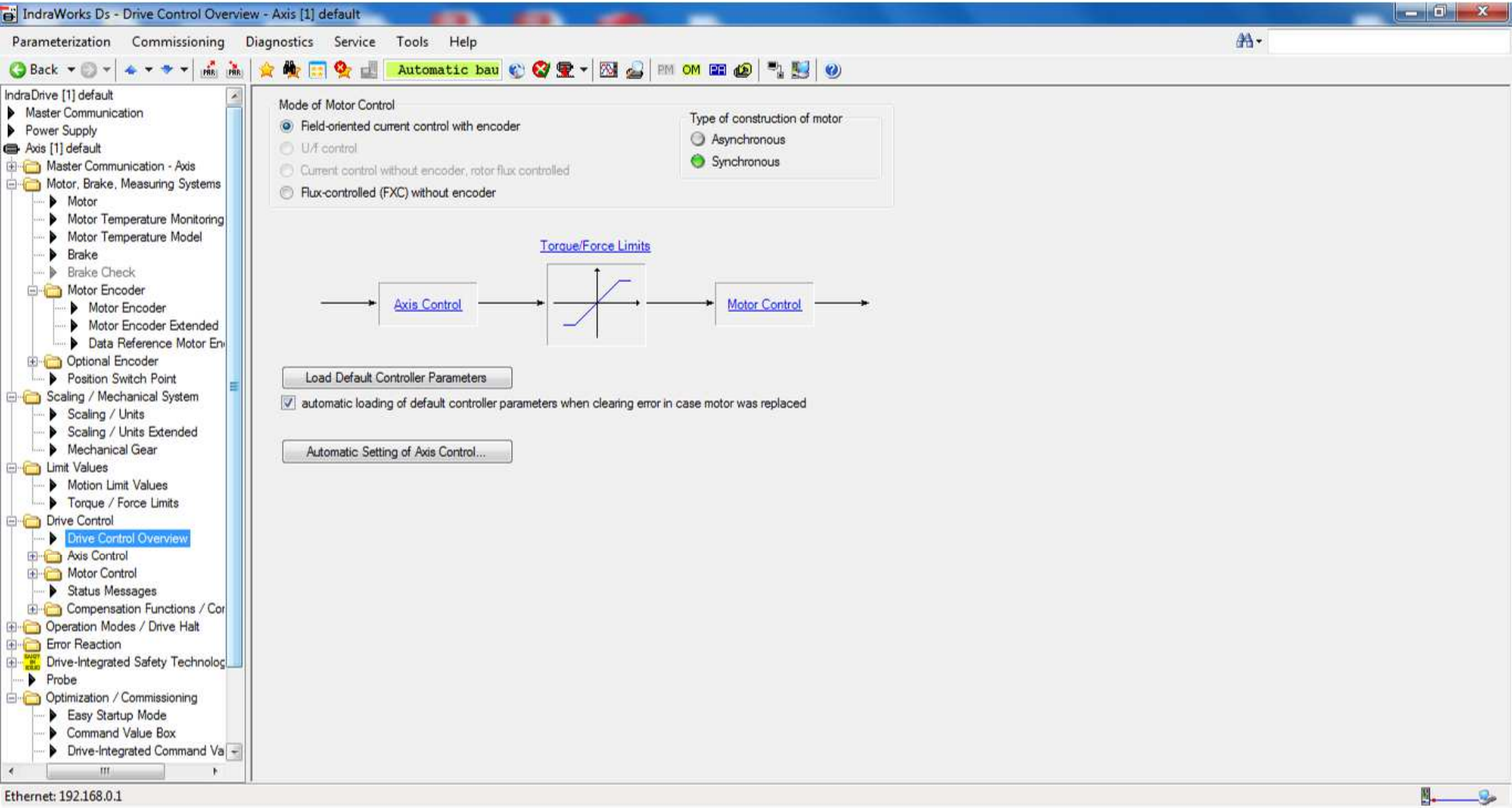
IndraWorks Ds - Drive Control Overview - Axis [1] default
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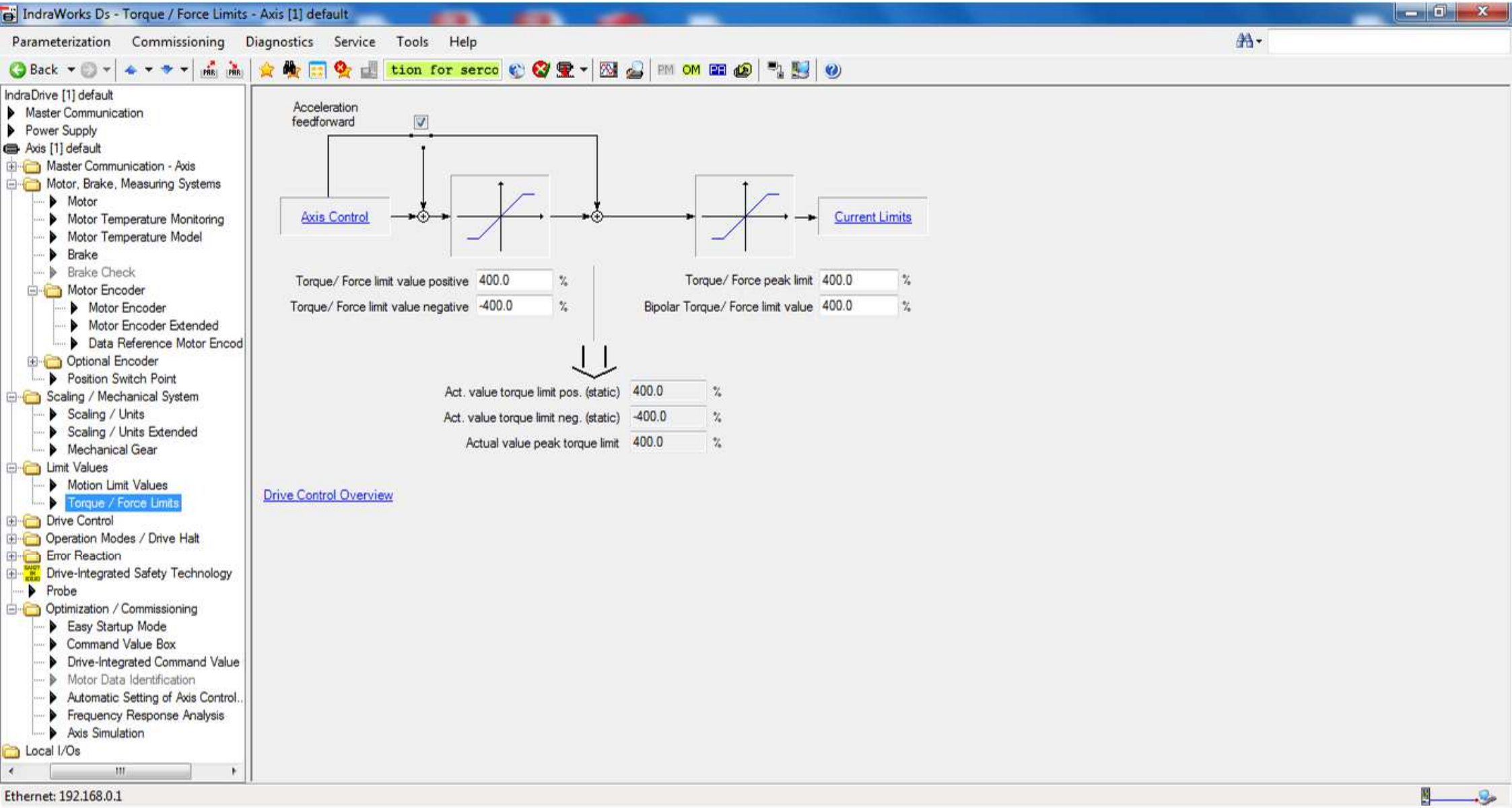
Mode of Motor Control
Field-oriented current control with encoder
U/f control
Current control without encoder, rotor flux controlled
Flux-controlled (FXC) without encoder
Type of construction of motor
Asynchronous
Synchronous
Torque/Force Limits
Axis Control
Motor Control
Load Default Controller Parameters
automatic loading of default controller parameters when clearing error in case motor was replaced
Automatic Setting of Axis Control...
Ethernet: 192.168.0.1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Acceleration feedforward
Axis Control
Current Limits
Torque/ Force limit value positive 400.0 %
Torque/ Force limit value negative -400.0 %
Torque/ Force peak limit 400.0 %
Bipolar Torque/ Force limit value 400.0 %
Act. value torque limit pos. (static) 400.0 %
Act. value torque limit neg. (static) -400.0 %
Actual value peak torque limit 400.0 %
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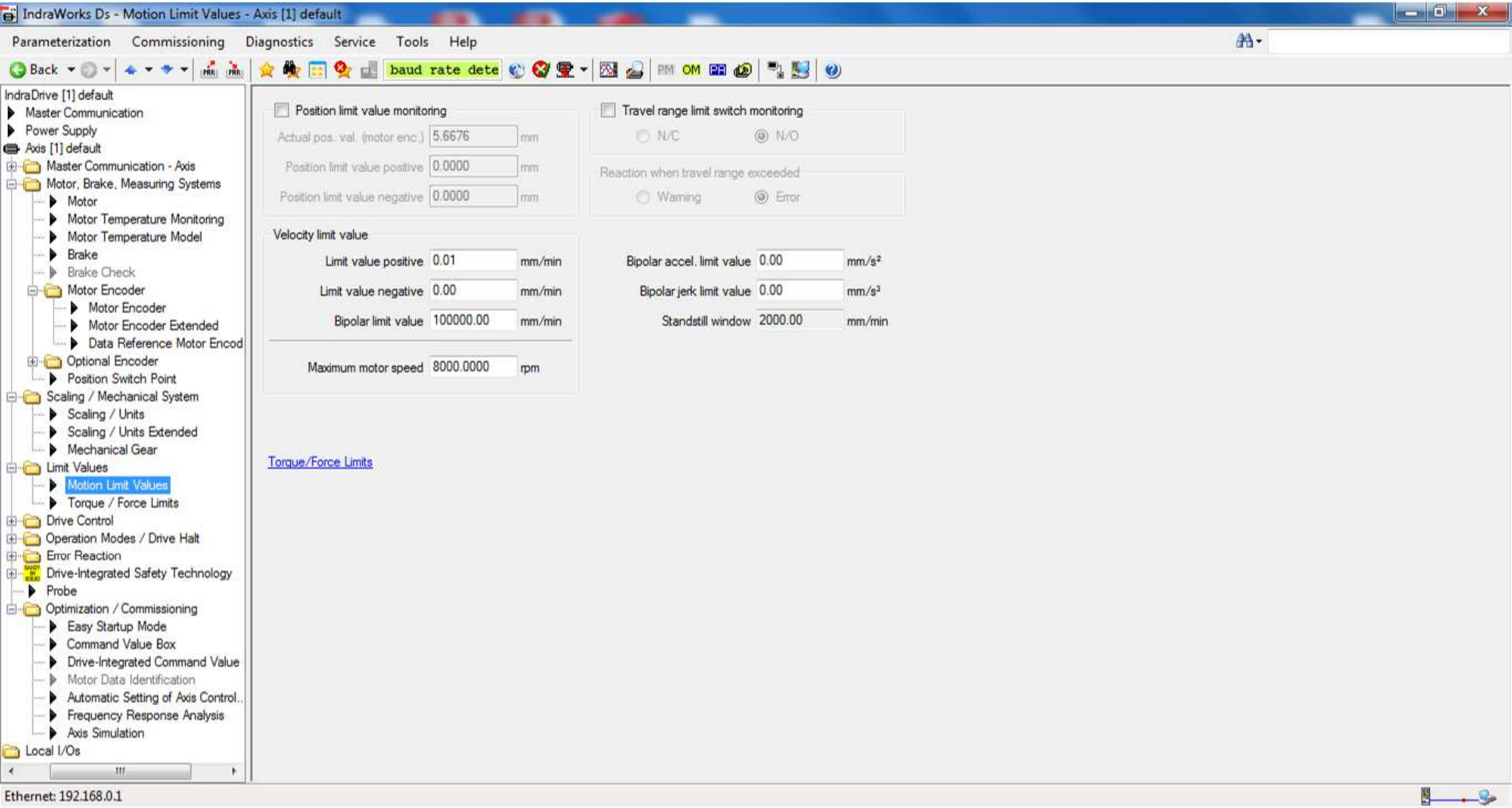
Ethernet: 192.168.0.1


IndraWorks Ds - Motion Limit Values - Axis [1] default
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baud rate dete
IndraDrive [1] default
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Position limit value monitoring
Actual pos. val. (motor enc.) 5.6676 mm
Position limit value positive 0.0000 mm
Position limit value negative 0.0000 mm
Travel range limit switch monitoring
N/C
N/O
Reaction when travel range exceeded
Warning
Error
Velocity limit value
Limit value positive 0.01 mm/min
Limit value negative 0.00 mm/min
Bipolar limit value 100000.00 mm/min
Maximum motor speed 8000.0000 rpm
Bipolar accel. limit value 0.00 mm/s²
Bipolar jerk limit value 0.00 mm/s³
Standstill window 2000.00 mm/min
Torque/Force Limits
Ethernet: 192.168.0.1

IndraWorks Ds - Mechanical Gear - Axis [1] default

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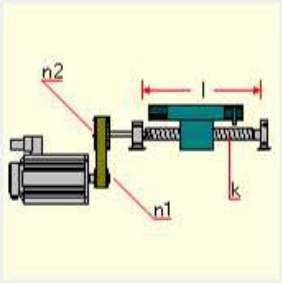

Position data in

- (•) absolute format
- ( ) modulo format

360.0000 mm

Mode

- (•) Shortest distance
- ( ) Positive direction
- ( ) Negative direction

Maximum travel range l	1000.0000	mm
Feed constant k	5.0000	mm/Rev
Input revolutions of load gear n1	1	
Output revolutions of load gear n2	1	
Load inertia, with reference to motor	0.5000000	kgm²

( ) Absolute encoder evaluation of motor enc. possible
Settings of Motor Encoder

( ) Absolute encoder evaluation of optional enc. possible
Settings of Optional Encoder

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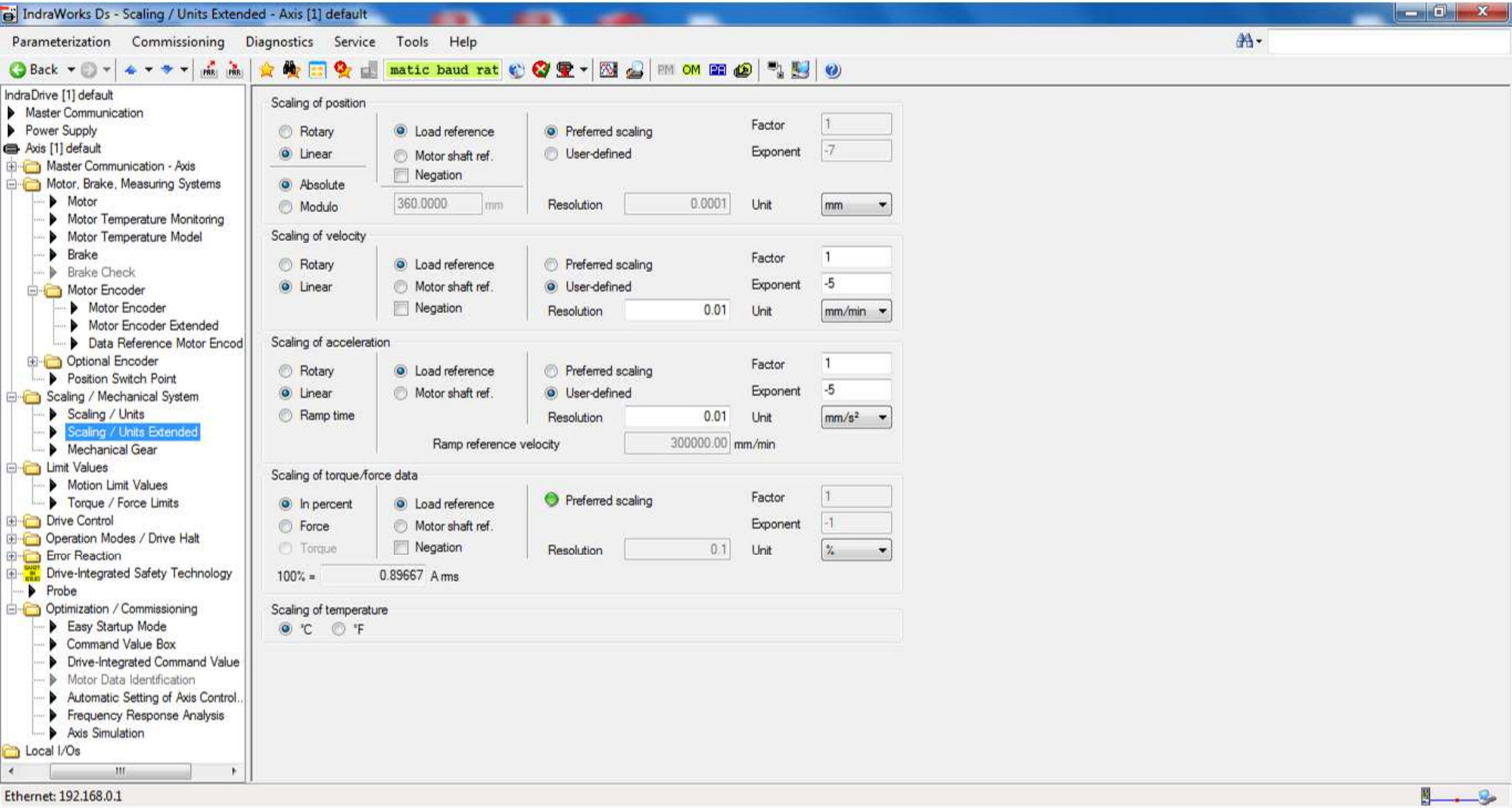
IndraWorks Ds - Scaling / Units Extended - Axis [1] default
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Scaling of position
Rotary
Linear
Absolute
Modulo
360.0000
mm
Load reference
Motor shaft ref.
Negation
Preferred scaling
User-defined
Resolution
0.0001
Factor
1
Exponent
-7
Unit
mm
Scaling of velocity
Rotary
Linear
Load reference
Motor shaft ref.
Negation
Preferred scaling
User-defined
Resolution
0.01
Factor
1
Exponent
-5
Unit
mm/min
Scaling of acceleration
Rotary
Linear
Ramp time
Load reference
Motor shaft ref.
Preferred scaling
User-defined
Resolution
0.01
Factor
1
Exponent
-5
Unit
mm/s²
Ramp reference velocity
300000.00
mm/min
Scaling of torque/force data
In percent
Force
Torque
Load reference
Motor shaft ref.
Negation
Preferred scaling
Resolution
0.1
Factor
1
Exponent
-1
Unit
%
100% =
0.89667
A rms
Scaling of temperature
°C
°F
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IndraWorks Ds - Scaling / Units - Axis [1] default

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      - Axis Simulation
  - Local I/Os

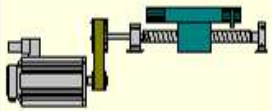
Scaling type

- (○) Rotary
- (●) Linear
- (○) Scaling not uniform

Position data format

- (●) Absolute
- (○) Modulo

360.0000 mm



Resolution ...

... of position data	0.0001	mm
... of velocity data	0.001	mm/min
... of acceleration data	0.001	mm/s²
... of torque/force data	0.1	%

Extended...

Negation of position, velocity and torque/force data

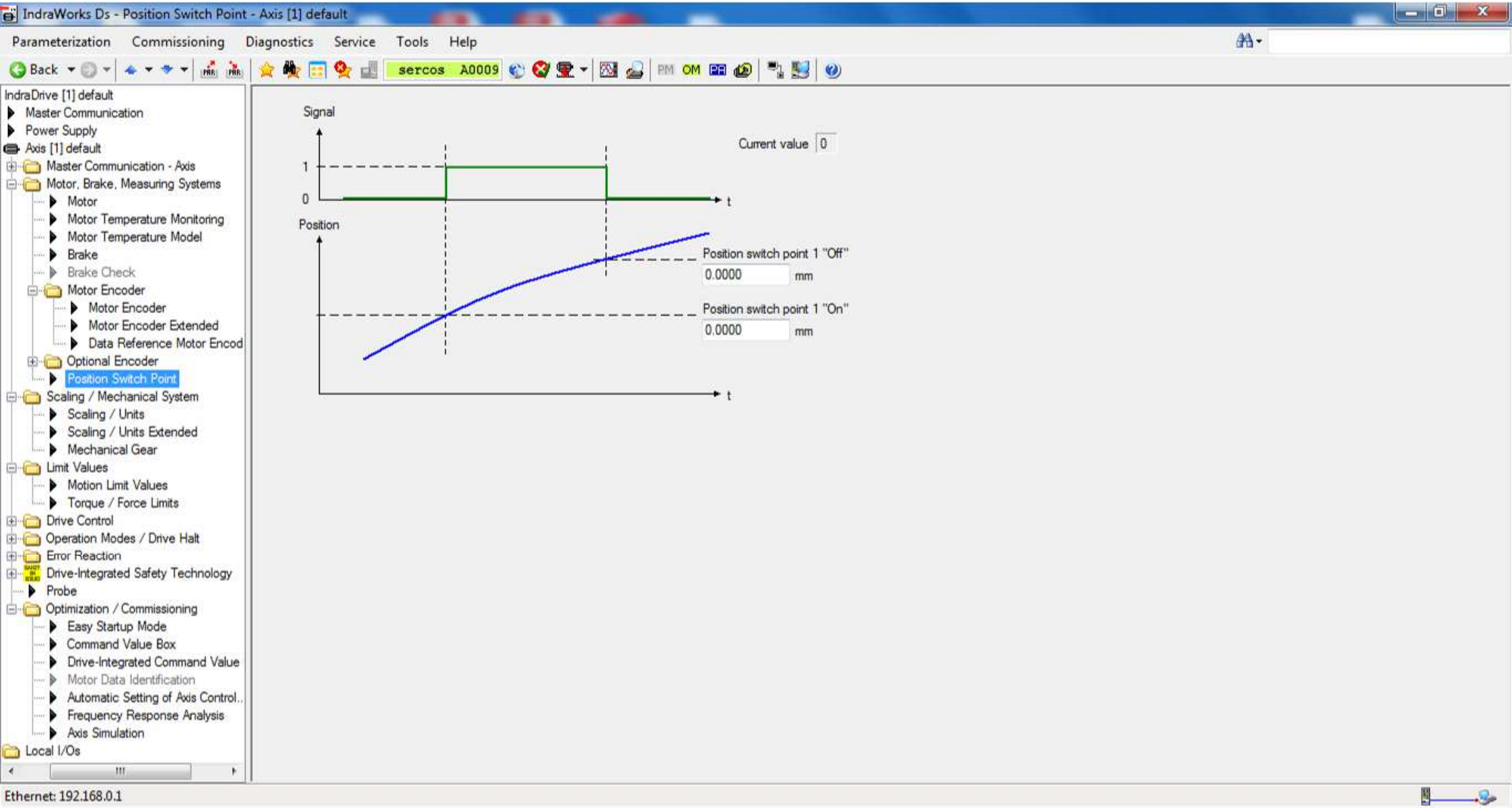
- (○) yes
- (●) no
- (○) Negation not uniform

Data with reference to ...

- (●) Load
- (○) Motor shaft
- (○) Data reference not uniform

Data refer automatically to load. Changes only via "Extended"

Ethernet: 192.168.0.1


IndraWorks Ds - Position Switch Point - Axis [1] default
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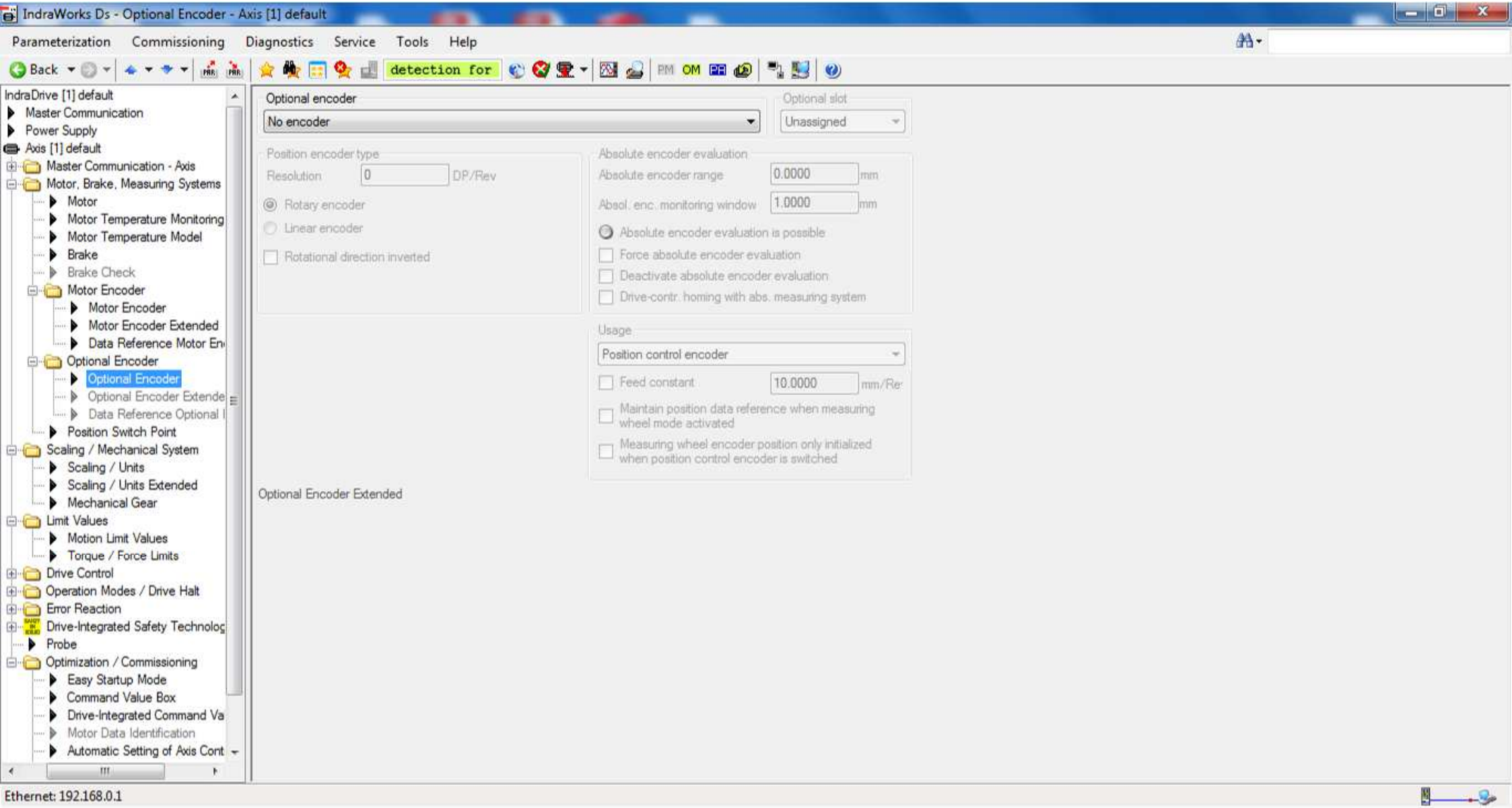
Signal
1
0
t
Current value
0
Position
Position switch point 1 "Off"
0.0000
mm
Position switch point 1 "On"
0.0000
mm
t
Ethernet: 192.168.0.1


IndraWorks Ds - Optional Encoder - Axis [1] default
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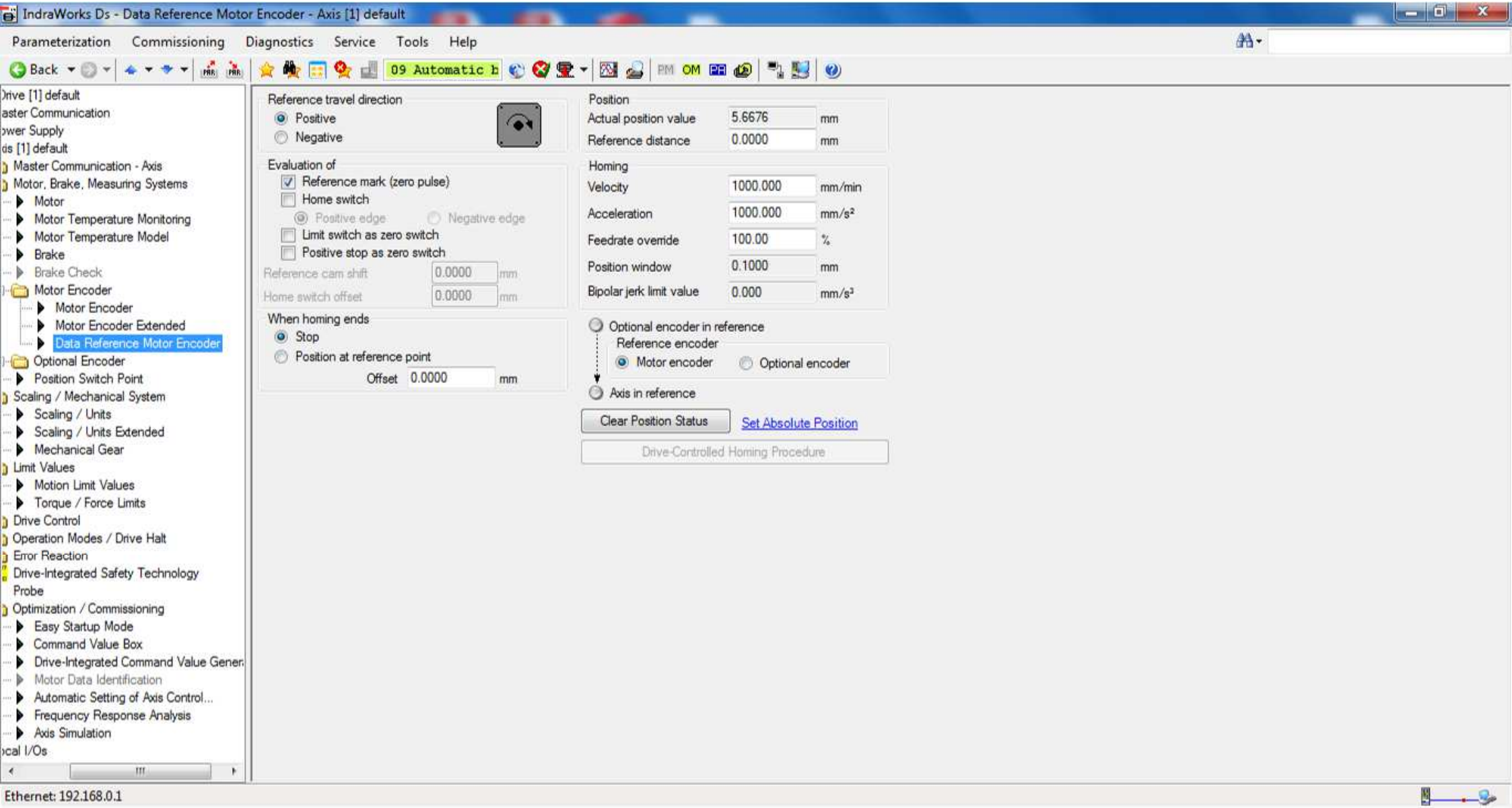
Optional encoder
No encoder
Optional slot
Unassigned
Position encoder type
Resolution
0
DP/Rev
Rotary encoder
Linear encoder
Rotational direction inverted
Absolute encoder evaluation
Absolute encoder range
0.0000
mm
Absol. enc. monitoring window
1.0000
mm
Absolute encoder evaluation is possible
Force absolute encoder evaluation
Deactivate absolute encoder evaluation
Drive-contr. homing with abs. measuring system
Usage
Position control encoder
Feed constant
10.0000
mm/Re
Maintain position data reference when measuring wheel mode activated
Measuring wheel encoder position only initialized when position control encoder is switched
Optional Encoder Extended
Ethernet: 192.168.0.1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cal I/Os
Reference travel direction
Positive
Negative
Evaluation of
Reference mark (zero pulse)
Home switch
Positive edge
Negative edge
Limit switch as zero switch
Positive stop as zero switch
Reference cam shift
0.0000
mm
Home switch offset
0.0000
mm
When homing ends
Stop
Position at reference point
Offset
0.0000
mm
Position
Actual position value
5.6676
mm
Reference distance
0.0000
mm
Homing
Velocity
1000.000
mm/min
Acceleration
1000.000
mm/s²
Feedrate override
100.00
%
Position window
0.1000
mm
Bipolar jerk limit value
0.000
mm/s³
Optional encoder in reference
Reference encoder
Motor encoder
Optional encoder
Axis in reference
Clear Position Status
Set Absolute Position
Drive-Controlled Homing Procedure
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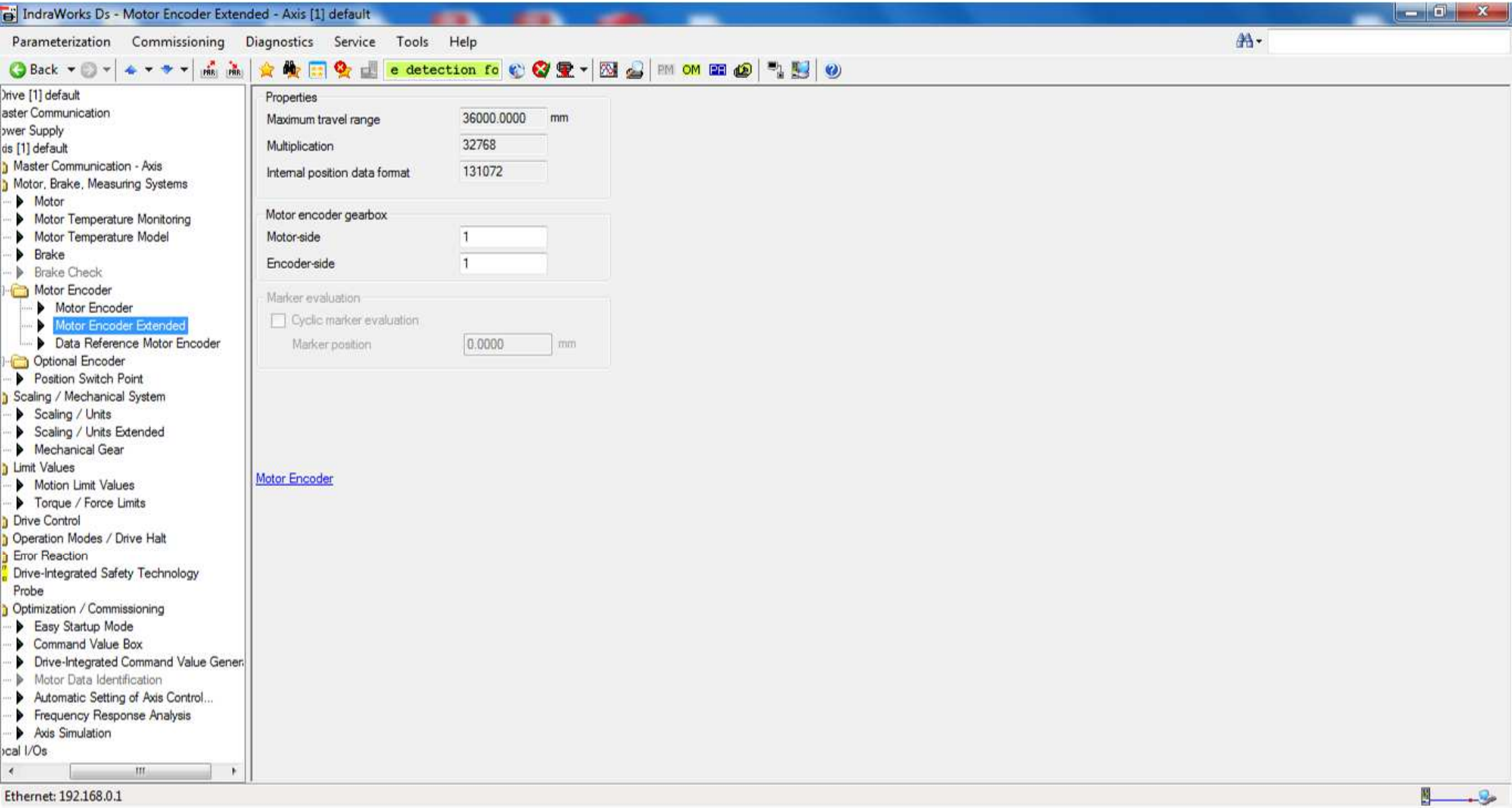
IndraWorks Ds - Motor Encoder Extended - Axis [1] default
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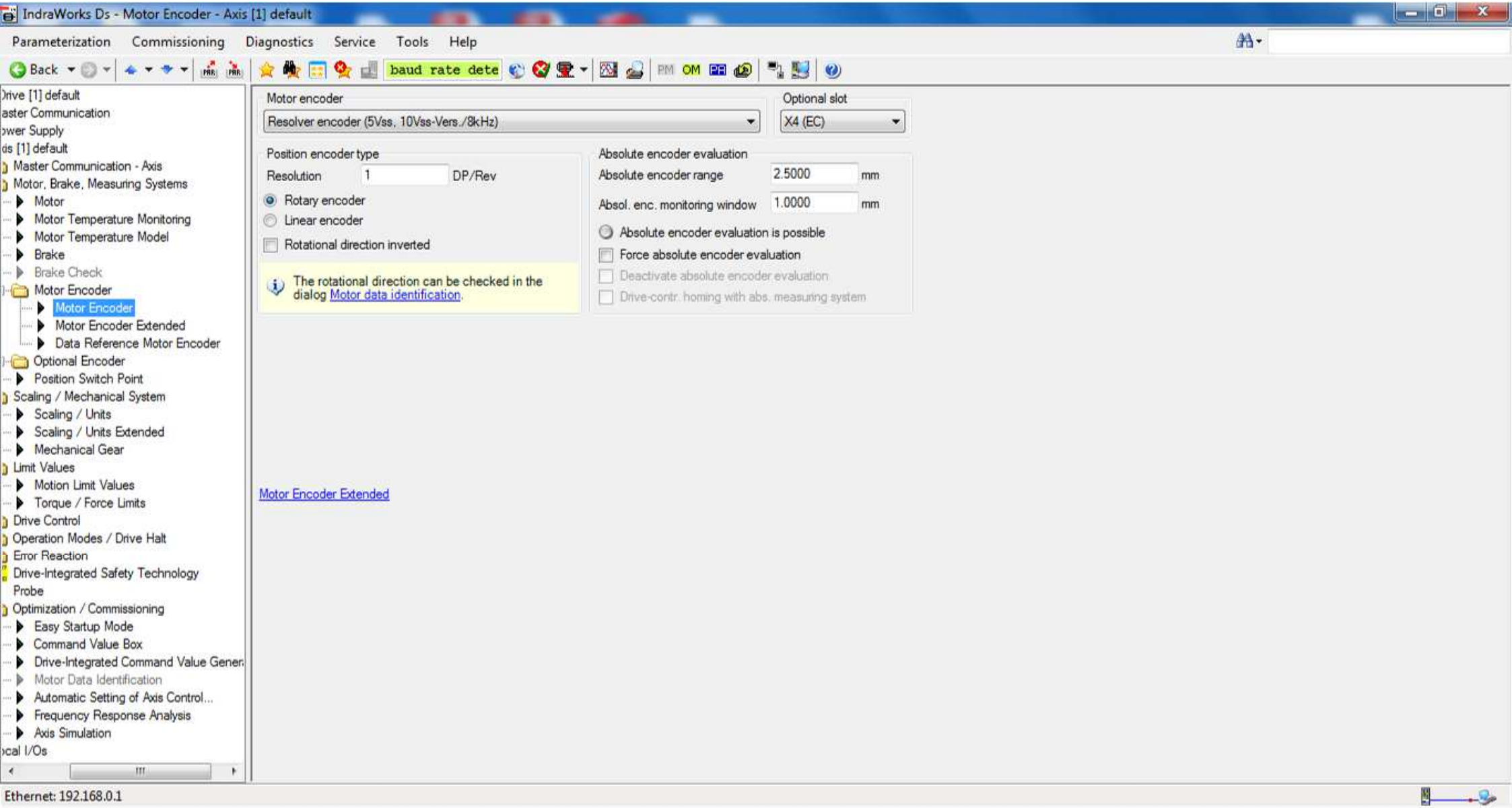
Properties
Maximum travel range
36000.0000
mm
Multiplication
32768
Internal position data format
131072
Motor encoder gearbox
Motor-side
1
Encoder-side
1
Marker evaluation
Cyclic marker evaluation
Marker position
0.0000
mm
Motor Encoder
Ethernet: 192.168.0.1


IndraWorks Ds - Motor Encoder - Axis [1] default
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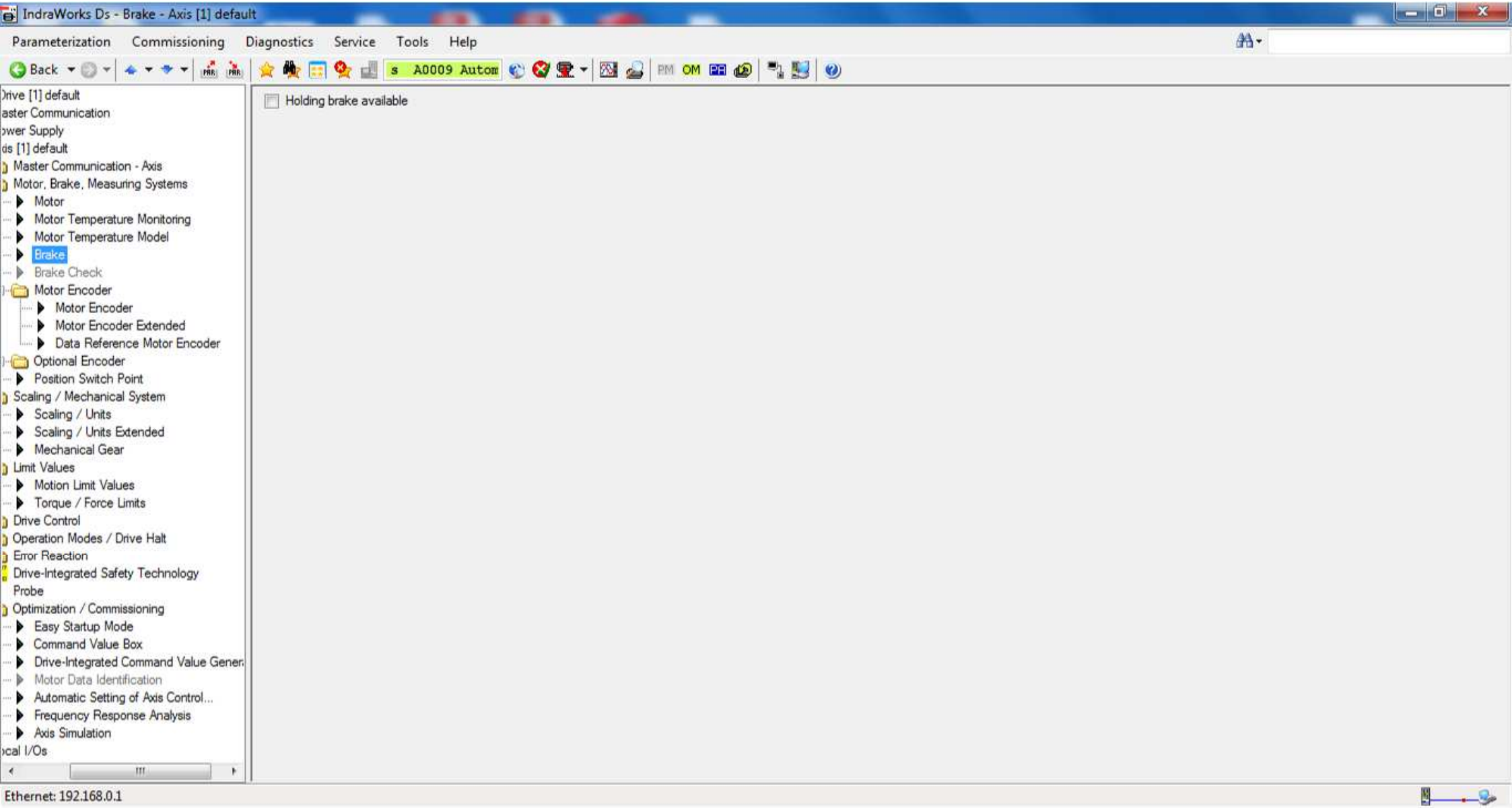
Motor encoder
Resolver encoder (5Vss, 10Vss-Vers./8kHz)
Optional slot
X4 (EC)
Position encoder type
Resolution
1
DP/Rev
Rotary encoder
Linear encoder
Rotational direction inverted
The rotational direction can be checked in the dialog Motor data identification.
Absolute encoder evaluation
Absolute encoder range
2.5000
mm
Absol. enc. monitoring window
1.0000
mm
Absolute encoder evaluation is possible
Force absolute encoder evaluation
Deactivate absolute encoder evaluation
Drive-contr. homing with abs. measuring system
Motor Encoder Extended
Ethernet: 192.168.0.1


IndraWorks Ds - Brake - Axis [1] default
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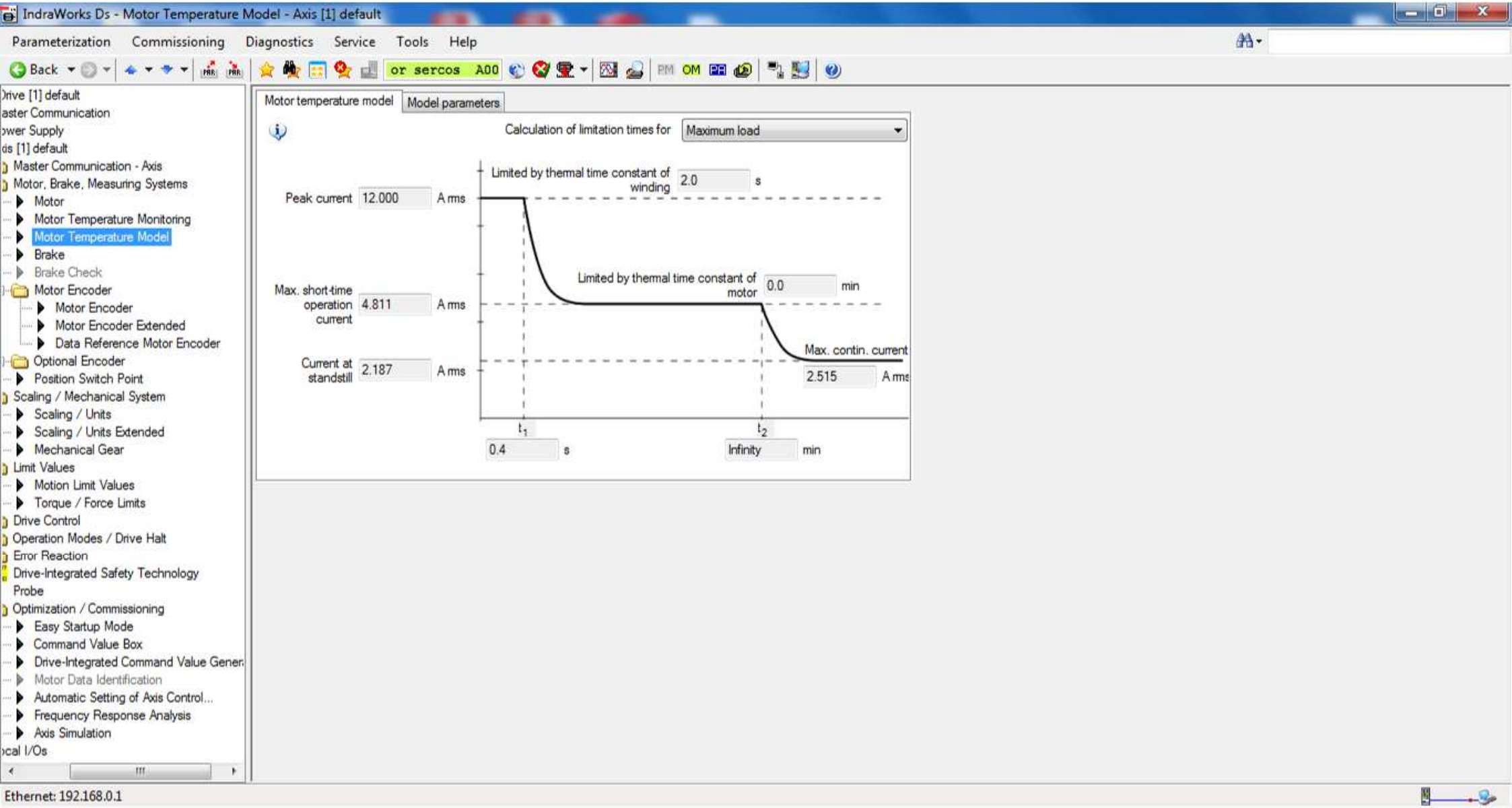
IndraWorks Ds - Motor Temperature Model - Axis [1] default
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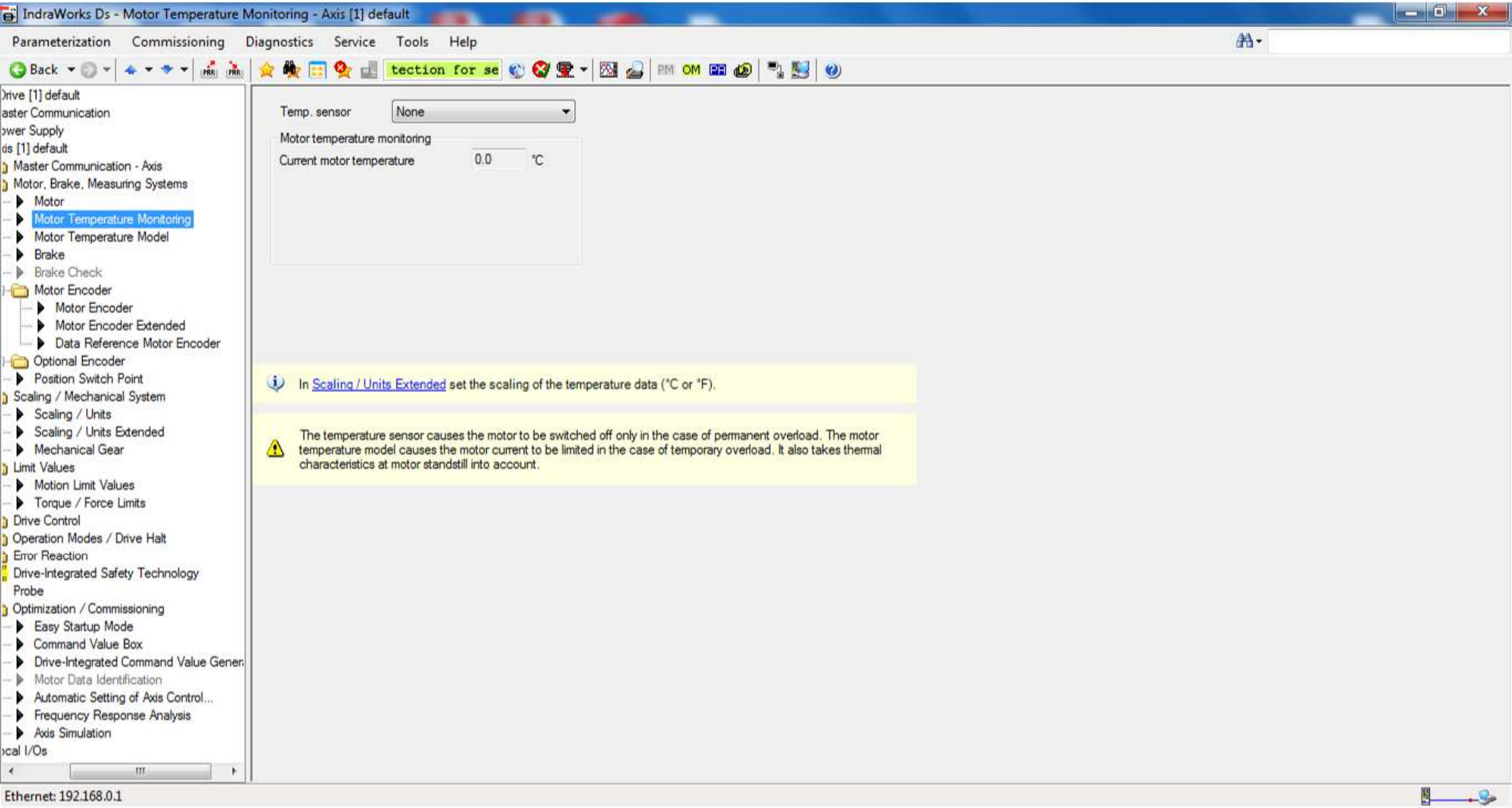
Automatic Setting of Axis Control...
Frequency Response Analysis
Axis Simulation
cal I/Os
Motor temperature model
Model parameters
Calculation of limitation times for
Maximum load
Limited by thermal time constant of winding
2.0
s
Peak current
12.000
A rms
Limited by thermal time constant of motor
0.0
min
Max. short-time operation current
4.811
A rms
Max. contin. current
2.515
A rms
Current at standstill
2.187
A rms
t1
t2
0.4
s
Infinity
min
Ethernet: 192.168.0.1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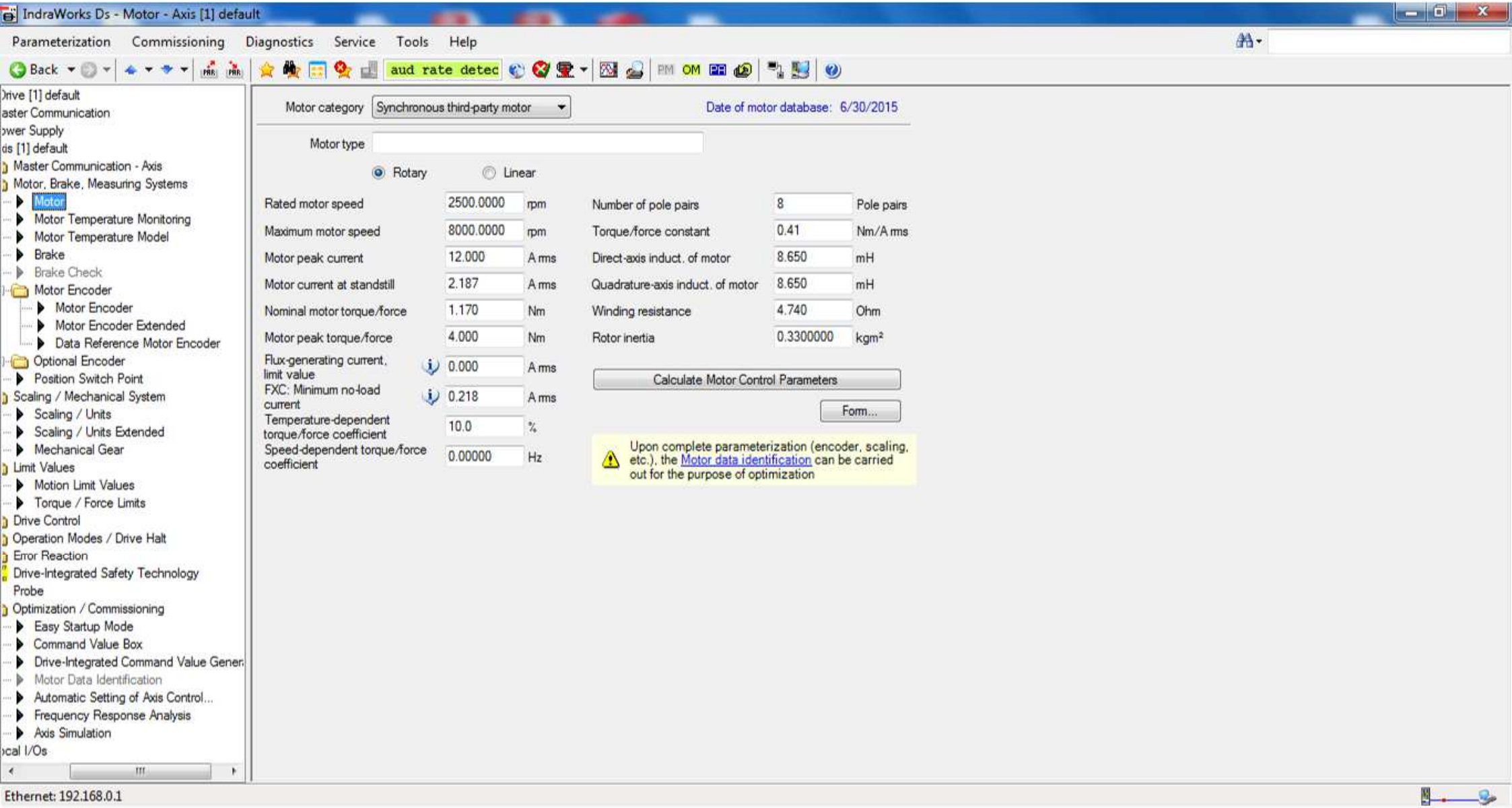
cal I/Os
Temp. sensor
None
Motor temperature monitoring
Current motor temperature
0.0
°C
In Scaling / Units Extended set the scaling of the temperature data (°C or °F).
The temperature sensor causes the motor to be switched off only in the case of permanent overload. The motor temperature model causes the motor current to be limited in the case of temporary overload. It also takes thermal characteristics at motor standstill into account.
Ethernet: 192.168.0.1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cal I/Os
Motor category
Synchronous third-party motor
Date of motor database: 6/30/2015
Motor type
Rotary
Linear
Rated motor speed
2500.0000
rpm
Maximum motor speed
8000.0000
rpm
Motor peak current
12.000
A rms
Motor current at standstill
2.187
A rms
Nominal motor torque/force
1.170
Nm
Motor peak torque/force
4.000
Nm
Flux-generating current, limit value
0.000
A rms
FXC: Minimum no-load current
0.218
A rms
Temperature-dependent torque/force coefficient
10.0
%
Speed-dependent torque/force coefficient
0.00000
Hz
Number of pole pairs
8
Pole pairs
Torque/force constant
0.41
Nm/A rms
Direct-axis induct. of motor
8.650
mH
Quadrature-axis induct. of motor
8.650
mH
Winding resistance
4.740
Ohm
Rotor inertia
0.3300000
kgm²
Calculate Motor Control Parameters
Form...
Upon complete parameterization (encoder, scaling, etc.), the Motor data identification can be carried out for the purpose of optimization
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