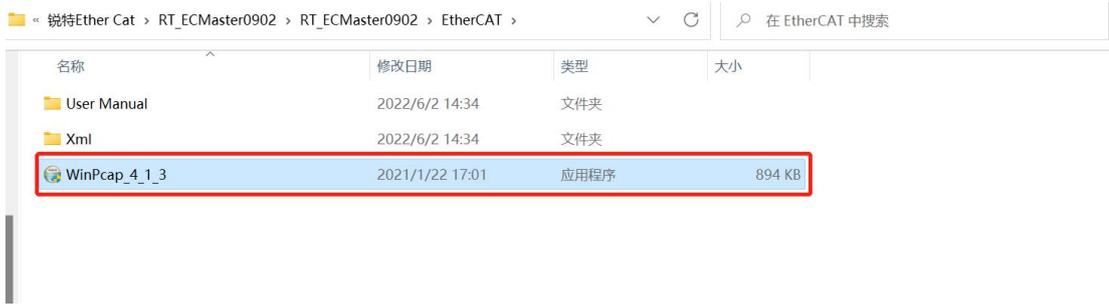


一、安装 Ether cat 运行环境

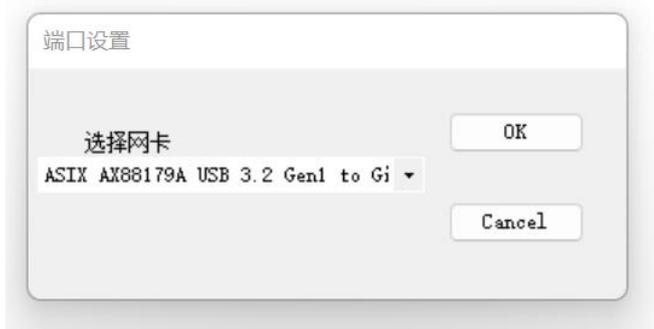


二、打开软件连接驱动器

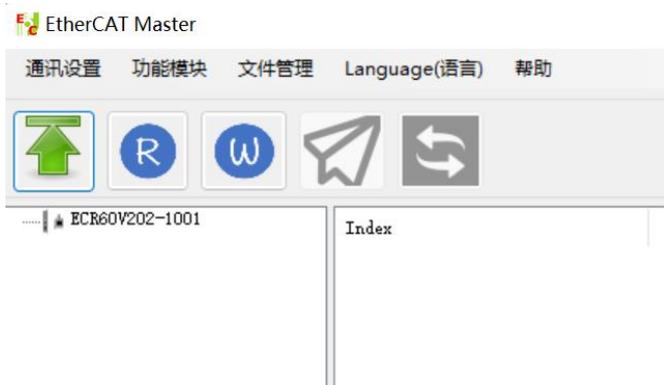
1、双击图标打开软件



2、选择网卡



3、连接成功后左边选型号，双击打开参数



三、修改参数

1、修改正负限位的常闭

在对象字典 0x 2008 写入十进制 51

对象字典 0x 2008 的 BIT0~BIT5 对应驱动器的 IN1~IN6，把对应的 BIT 位改成 0。

Index	Name	Flags	Value
2003	Idle Current Percentage	RW P	0x0032 (50)
2005	Outputs function	RO	0x02 (2)
2006	Output Polarity	RW P	0x0003 (3)
2007	Inputs function	RO	0x06 (6)
2008	Inputs Polarity	RW P	0x003f (63)
2009	Filter Time	RW P	0x6400 (25600)
200A	Soft lock Time	RW P	
200B	Current loop parameters	RO	
200C	Motor parameters	RO	
200D	Invert motor direction	RW P	
200E	Alarm Code	RO P	
200F	Status Code	RO P	
2010	Zero Position	RW P	
2011	Control mode	RW P	
2020	Encoder Resolution	RW	
2021	Encoder Counter in one rev	RO P	
2022	Position trace error Limit	RW P	
2023	Position loop parameters	RO	
2024	InPosition parameters	RO	
2025	Servo filters	RO	
2026	Servo mode2 parameters	RO	
2043	Speed Reference	RO P	
2044	Speed Feedback	RO P	
2048	BusVoltage	RO P	
2049	Input Level	RO P	
204A	Output Level	RO P	
2056	Error Detect enable	RW P	

Set Value Dialog

Slave: 1 Quantity: 1

Index: 2008 SubIndex: 0

Dec: 51 OK

Hex: 33

Binary: 110011 Cancel

Bit Size: 1 8 16 32

16(H): 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0

16(L): 0 0 0 0 0 0 0 0 0 0 1 1 0 0 1 1

2、修改电流

在对象字典 0x 2000 写入电流值，电流值可参考电机的额定电流，单位 ma。

1A01		0x0c (12)
1A02		0x0c (12)
1C00		0x04 (4)
1C12		0x03 (3)
1C13		0x03 (3)
1C32		0x20 (32)
1C33		0x20 (32)
2000		0x03e8 (1000)
2001		0x2710 (10000)
2002		0x03e8 (1000)
2003		0x0032 (50)
2005		0x02 (2)
2006		0x0003 (3)
2007		0x06 (6)
2008		0x003f (63)
2009		0x6400 (25600)
200A		0x03e8 (1000)
200B		0x04 (4)
200C		0x06 (6)
200D		0x0000 (0)
200E		0x0000 (0)

Set Value Dialog

Slave: 1 Quantity: 1

Index: 2000 SubIndex: 0

Dec: 2500 OK

Hex: 9C4

Binary: 100111000100 Cancel

Bit Size: 1 8 16 32

16(H): 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0

16(L): 0 0 0 0 1 0 0 1 1 1 0 0 0 1 0 0

3、修改细分

5ECR 系列开环驱动器细分默认是对象字典 0x 2001 的值，直接修改保存生效。

开环细分：

The screenshot shows a parameter list on the left and a 'Set Value Dialog' window on the right. In the parameter list, row 2001 'Motor Resolution' is highlighted with a red box. In the dialog, the 'Index' is set to 2001 and the 'Dec' value is set to 5000, also highlighted with a red box. The dialog includes fields for Slave, Quantity, Hex, Binary, and Bit Size (16 is selected).

4、IO 输入端口功能设置

驱动器出厂默认 IN3 正限位、IN4 负限位、IN5 原点，也可以根据实际情况修改，在对象字典 0x2007 子索引写值。

The screenshot shows a parameter list on the left and a 'Set Value Dialog' window on the right. In the parameter list, rows 2007:3 'IN3 function' and 2007:4 'IN4 function' are highlighted with red boxes. In the dialog, the 'Index' is set to 2007 and the 'SubIndex' is set to 3. The 'Dec' value is set to 2, also highlighted with a red box. The dialog includes fields for Slave, Quantity, Hex, Binary, and Bit Size (16 is selected).

值对应的功能：

值	功能
0	通用输入口
1	CW 限位输入
2	CCW 限位输入
3	HOME 输入
4	清除故障
5	急停信号

6	电机脱机
7	探针 1
8	探针 2

5、修改运行方向

开环驱动器可以直接通过调换电机线 A+A- 来改变运行方向，闭环驱动器不可以调线，需要在对象字典 0x200D 写入 1。

The screenshot shows a parameter list on the left and a 'Set Value Dialog' window on the right. In the parameter list, row 200D 'Invert motor direction' is highlighted with a red box. In the dialog, the 'Dec' field is set to 1 and is also highlighted with a red box. The 'Index' is 200D and 'SubIndex' is 0. The 'Bit Size' is set to 16. The dialog also shows binary representations for 16(H) and 16(L) bits.

四、保存参数

请注意所有修改的参数都需要保存至驱动器，否则断电重启就恢复出厂设置的参数。

保存参数在对象字典 0x1010.1 写入 1。

The screenshot shows a parameter list on the left and a 'Set Value Dialog' window on the right. In the parameter list, row 1010.1 'Save all' is highlighted with a red box. In the dialog, the 'Dec' field is set to 1 and is highlighted with a red box. The 'Index' is 1010 and 'SubIndex' is 1. The 'Bit Size' is set to 16. The dialog also shows binary representations for 16(H) and 16(L) bits.