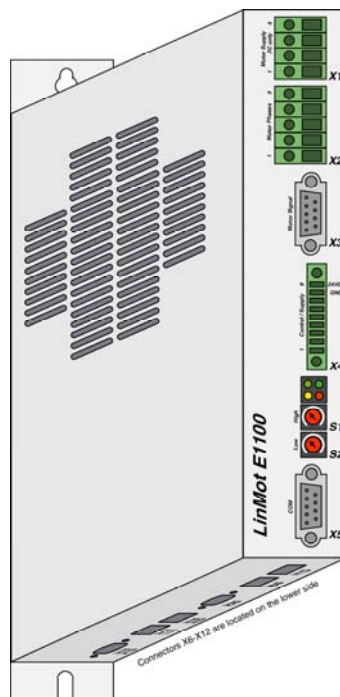




**Documentation of  
*LinMot-Talk 1100*  
Configuration Software**



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***LinMot-Talk 1100***  
User Manual

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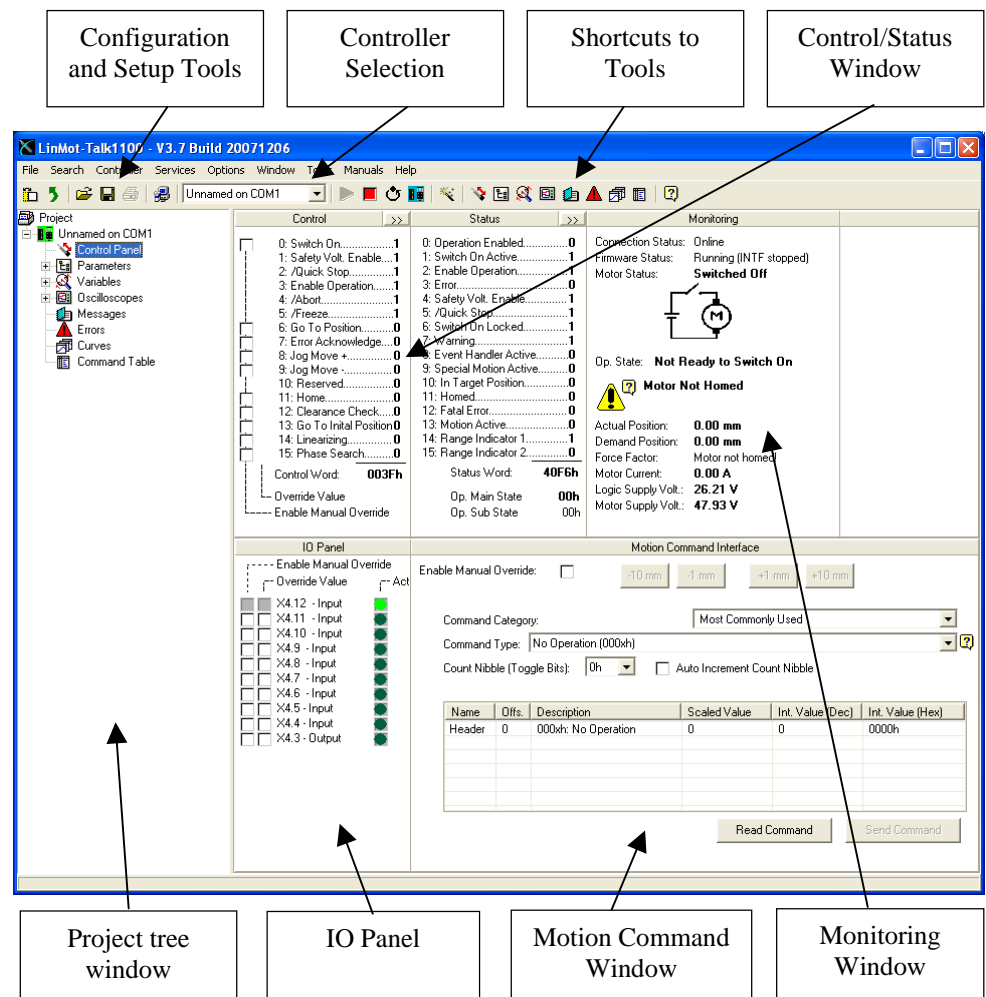
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## 1 Introduction

The LinMot-Talk1100 software is a PC based tool, which helps the user in a comfortable way installing firmware on the controller, setting up the controller's configuration, defining and programming motion profiles, emulating the PLC, watching variables and reading messages and errors. The LinMot-Talk 1100 works with the controller series E1100 and B1100.

## 2 Overview

The following screen shot gives an overview of the different functions integrated in the LinMot-Talk 1100 software.



## 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.
- **Import Configuration** imports a controller's configuration.
- **Export Configuration** exports a controller's configuration. Different 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 controller's firmware installation.
- **Start** starts the firmware on the controller.
- **Stop** stops the firmware on the controller, used for downloading software configuration.
- **Reset** resets controller's firmware.
- **Go Offline** logs out from actual controller.
- **Start Motor Wizard** starts the motor configuration setup wizard.
- **Show Control Panel** switches to the control panel.
- **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.

## 2.2 Control Panel

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

**Control Word**

Control

- 0: Switch On.....1
- 1: Safety Volt. Enable...1
- 2: /Quick Stop.....1
- 3: Enable Operation.....1
- 4: /Abort.....1
- 5: /Freeze.....1
- 6: Go To Position.....0
- 7: Error Acknowledge...0
- 8: Jog Move +.....0
- 9: Jog Move -.....0
- 10: Reserved.....0
- 11: Home.....0
- 12: Clearance Check...0
- 13: Go To Initial Position0
- 14: Linearizing.....0
- 15: Phase Search.....0

Control Word: **003Fh**

Override Value

Enable Manual Override

**Status Word**

Status

- 0: Operation Enabled.....0
- 1: Switch On Active.....1
- 2: Enable Operation.....1
- 3: Error.....0
- 4: Safety Volt. Enable...1
- 5: /Quick Stop.....1
- 6: Switch On Locked.....1
- 7: Warning.....1
- 8: Event Handler Active...0
- 9: Special Motion Active...0
- 10: In Target Position...0
- 11: Homed.....0
- 12: Fatal Error.....0
- 13: Motion Active.....0
- 14: Range Indicator 1.....1
- 15: Range Indicator 2.....0

Status Word: **40F6h**

Op. Main State **00h**

Op. Sub State **00h**

**General Monitoring**

Monitoring

Connection Status: Online

Firmware Status: Running (INTF stopped)

Motor Status: **Switched Off**

Op. State: **Not Ready to Switch On**

**Motor Not Homed**

Actual Position: **0.00 mm**

Demand Position: **0.00 mm**

Force Factor: Motor not homed!

Motor Current: **0.00 A**

Logic Supply Volt.: **26.21 V**

Motor Supply Volt.: **48.13 V**

**IO Panel**

Enable Manual Override

Override Value

Act

- X4.12 - Input
- X4.11 - Input
- X4.10 - Input
- X4.9 - Input
- X4.8 - Input
- X4.7 - Input
- X4.6 - Input
- X4.5 - Input
- X4.4 - Input
- X4.3 - Output

**Motion Command Interface**

Enable Manual Override: ☐

Command Category: Most Commonly Used

Command Type: No Operation (000xh)

Count Nibble (Toggle Bits): 0h ☐ Auto Increment Count Nibble

Name	Offs.	Description	Scaled Value	Int. Value (Dec)	Int. Value (Hex)
Header	0	000xh: No Operation	0	0	0000h

Read Command

Send Command

**IO Panel**

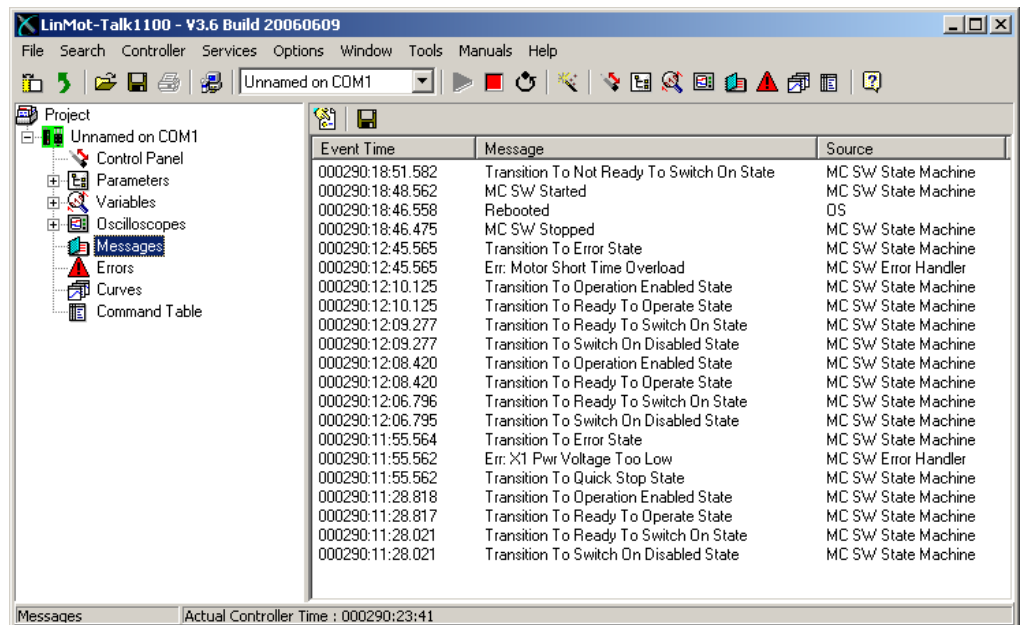
**Motion Command Window**

- **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 controller's MC software status word. It is updated automatically.
- **General Monitoring** This window displays actual motor and controller information
- **IO Panel** For commissioning; the user can take control of the X4 IOs on E1100 or X14 IOs on B1100 controllers.
- **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, parameterized and sent to the controller. Because the motion command interface is, independent of the interface running on the controller, the same, the commands can be exactly tested before programming them in the PLC.

## 2.3 Messages Panel

This panel reads out and shows all messages which are logged on the controller. As a feature of comfort, in this panel will be shown the errors too in chronological order. If logged in a B1100 series controller, this window does not appear, because those controllers do not support message logging.



### 2.4 Errors Panel

This panel reads out and shows all errors which are logged on the controller and displays them in chronological order.

Event Time	Error Code	Error Message	Source
000290:12:45:565	0023h	Err: Motor Short Time Overload	MC SW Error Handler
000290:11:55:562	0003h	Err: X1 Pwr Voltage Too Low	MC SW Error Handler
000290:11:09:884	0008h	Err: Pos Lag Always Too Big	MC SW Error Handler
000290:02:52:505	0080h	Timer Watchdog Error	OS
000289:49:23:880	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000289:45:24:319	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000259:09:31:287	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000258:27:04:202	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler
000256:28:25:072	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler
000255:45:46:154	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler
000237:53:44:906	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler
000237:53:44:906	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler
000237:22:18:629	0008h	Err: Pos Lag Always Too Big	MC SW Error Handler
000237:07:38:366	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler
000236:28:06:502	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000236:28:06:501	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000118:16:07:180	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000117:12:31:544	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000116:44:19:972	0064h	Cfg Err: No Motor Defined	MC SW Error Handler
000116:40:55:933	001Ch	Err: Supply DigOut X6 Fuse Blown	MC SW Error Handler

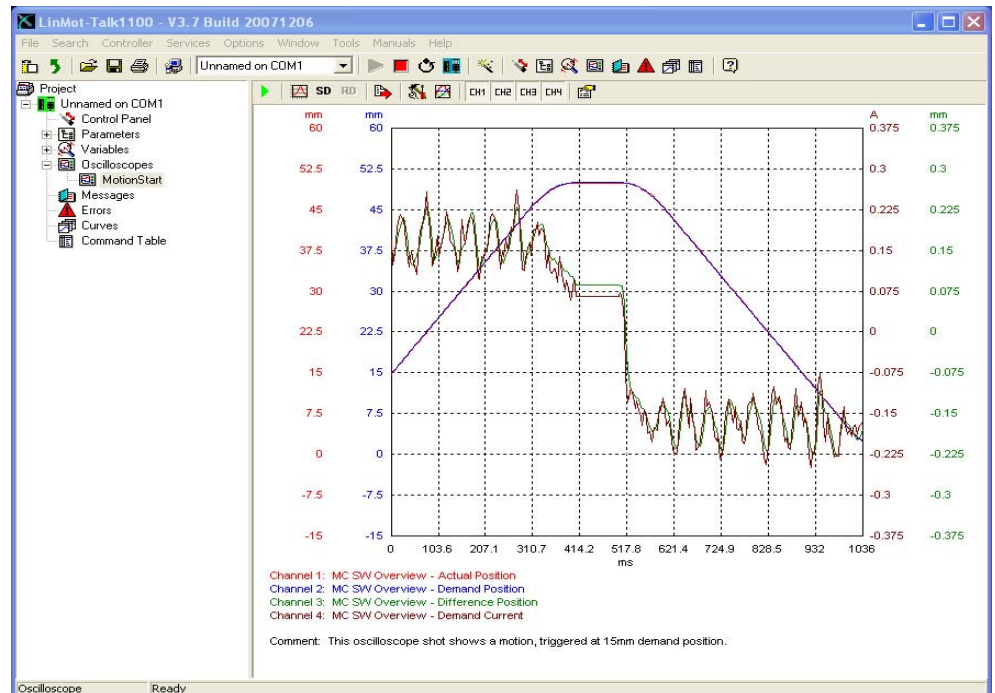
Errors | Actual Controller Time : 000290:24:22



## 2.5 Oscilloscope

The controller's built in oscilloscope, which can record up to 4 channels in real time, is controlled with the oscilloscope tool.

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



The oscilloscope is controlled with the buttons

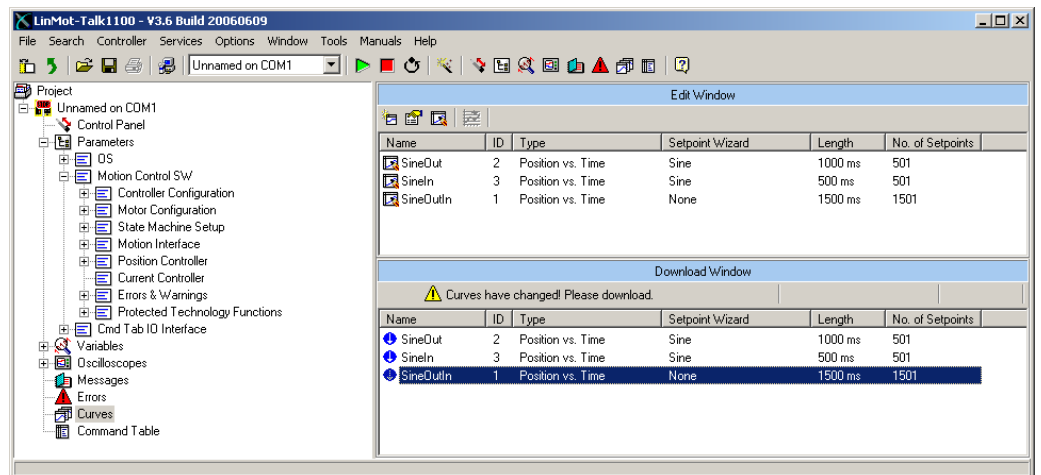


The functions are (from left):

- **Start/Abort** Start or abort an oscilloscope shot.
- **Fit view** Displays the recorded channels such as they fit best in the scope window.
- **Save Display** stores the settings for zoom, scaling and offset.
- **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.
- **Import Data** Import and display an oscilloscope shot from file.
- **Oscilloscope Settings** Switch to setup mask for channels, triggers, times and modes.
- **Show/Hide** Show and hide the oscilloscope channels.
- **Edit Properties:** The oscilloscope name and comment can be set individually.

### 2.6 Curves

With the curve tool, motor motion profiles can be easily created, joined, uploaded, downloaded and saved. NOTE: The curve tool is only shown for E1100 series controllers, B1100 controllers do not support the curve feature.



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 together. A wizard will be started for defining the curve properties of the joined curve.

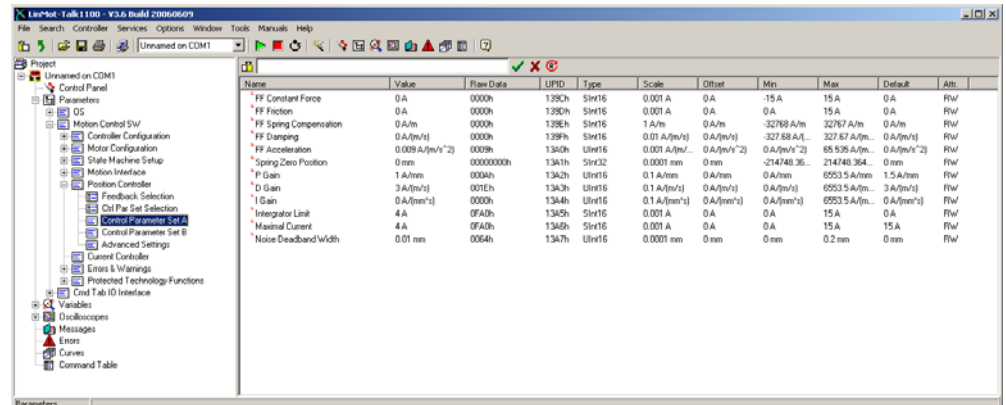
The download window is used to manage the curves which are stored on the controller or have to be downloaded. Modifications in this window will show up the message “Curves have changed! Please download.” After pressing the download into controller button the window and the controller will be synchronized.




- **Upload Curves from Controller** All curves stored on the controller will be uploaded and displayed.
- **Download Curves to Controller** The controller’s curve sector will be synchronized with the download window.
- **Auto Numerate Curves** The curve ID, which must be unique, will be set automatically.

## 2.7 Parameters

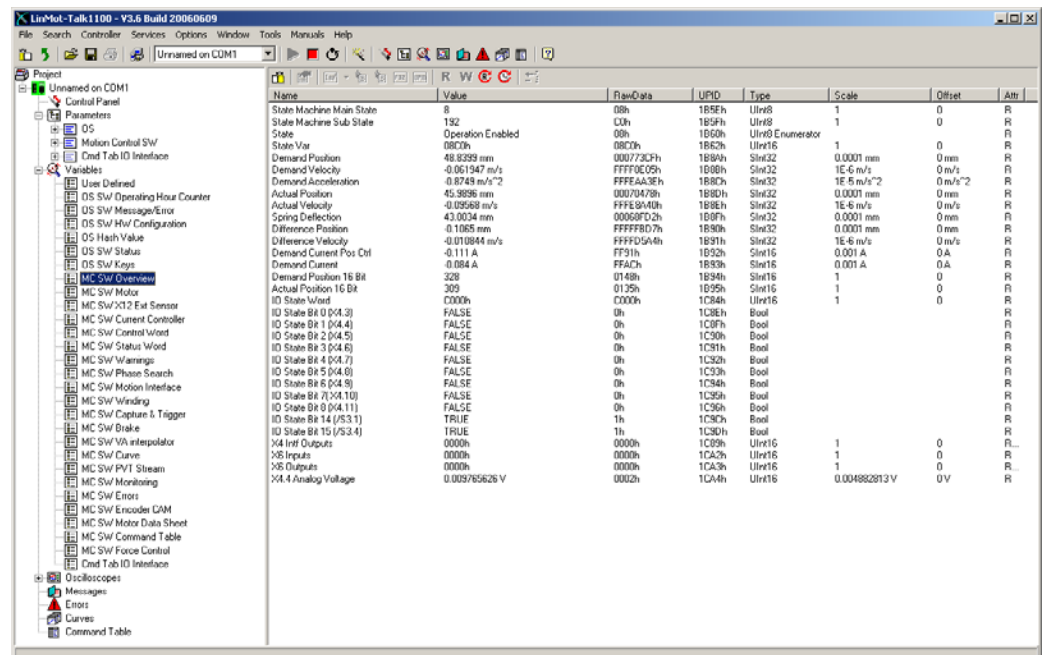
The controller's parameters are displayed in a tree view.



Parameters which are marked as live (  ) can be altered while the controller's firmware is running, other parameters can only be changed when the software is stopped.

## 2.8 Variables

The controller'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:



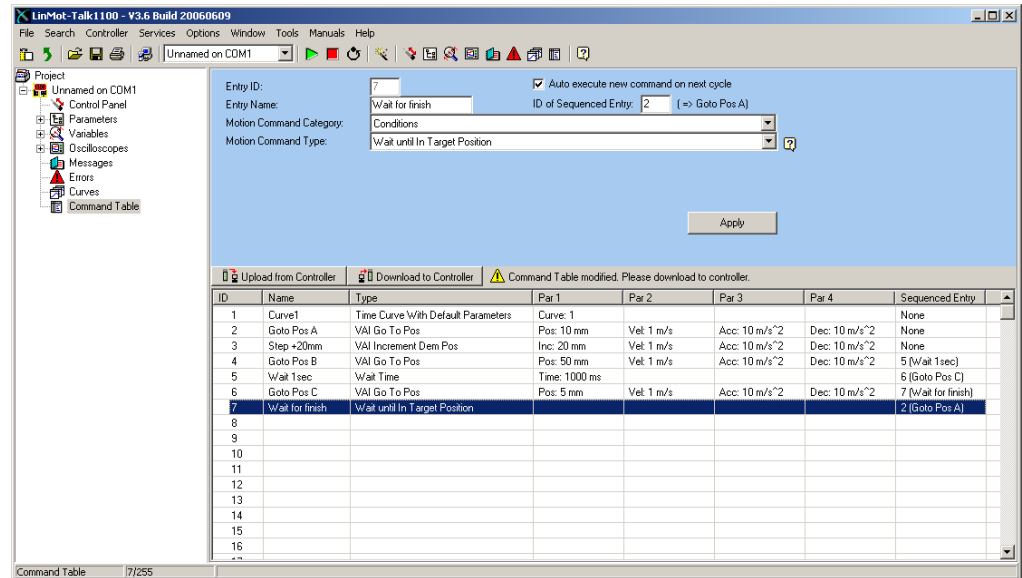
- **Show/Hide Details** Additional information for each parameter, such as unique parameter ID (UPID), scaling, min/max value, can be displayed on demand.
- **Read Variable** Reads the selected variable from the controller once.
- **Write Variable** Writes the selected variable to the controller.
- **Read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

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 Variable** 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.

## 2.9 Command Table

The controller supports the command table (CT) functionality, which means a set of up to 255 motion commands 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 Controller** reads and displays the entire command table from the controller.
- **Download to Controller** writes the (on the PC) edited table to the controller.

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 controller, 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 controller specific (pinned to the serial number). Under Controller\Set Access Code\ the following window will open:

**Set Access Code**

**Active Keys:**

Name	Value	Access Code
Key1	5A93h - Force Closed Loop Control	58328193h
Key2	0000h - No Key	
Key3	0000h - No Key	
Key4	0000h - No Key	

**Set Key Access Code:**

Name:  Value (HEX):  Access Code (HEX):

Note: The keys will not be activated on the controller until a reboot has been processed. Press the "activate" button to reboot.

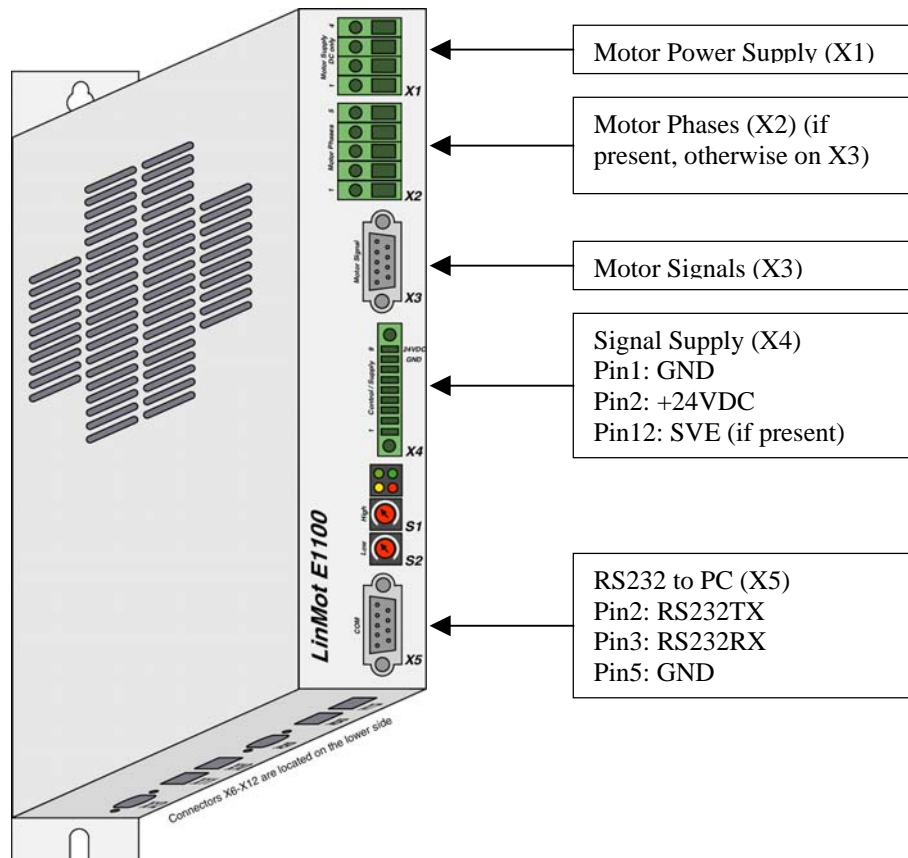
A maximum of four keys can be set on the controller. Under Active Keys all valid installed keys are listed (key value and access code). A new key can be set by selecting the key name and defining the value and access code. With the write button, the key and access code are written to the controller. As soon as the controller has rebooted (click the Activate button) the new key will be active, if the access code fits. Please note: Access codes are controller specific. They cannot be copied from one controller to another.

### 3 Quick Setup Guide

This chapter helps step by step to set up a system using an E1100 controller and the LinMot-Talk 1100 configuration software.

#### 3.1 Cabling


The following picture shows the connectors on the controller 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 controller and PC must be DSUB-9 F/F, 1:1 (X modem). If the PC has no COM port available, please use the USB to RS232 converter (LinMot article number 0150-3110).

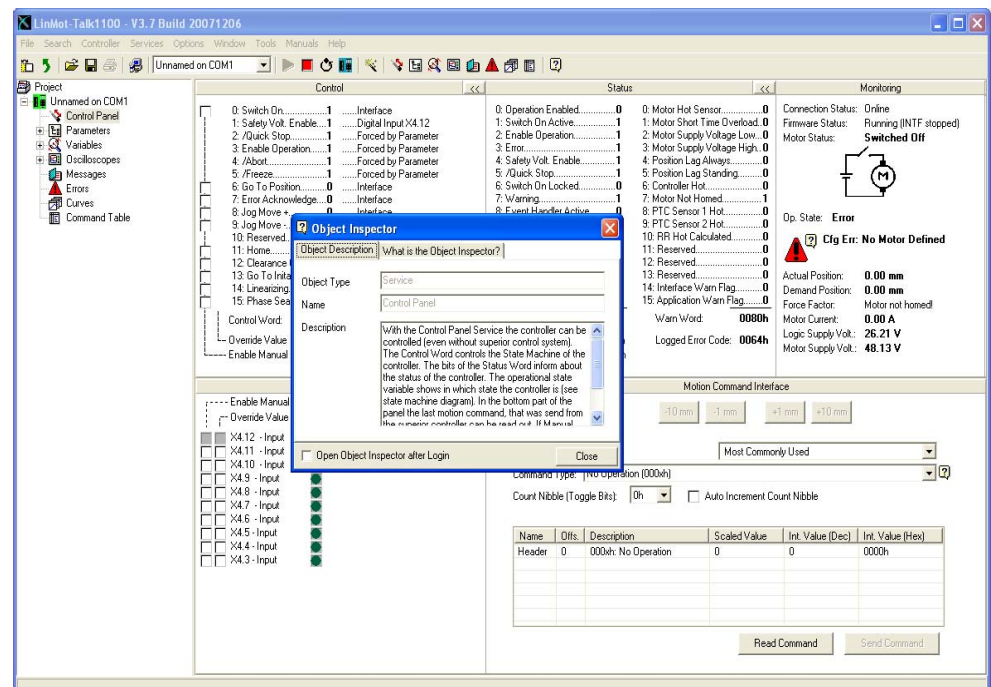


## 3.2 Firmware Download

As the cabling is done correctly now, turn on the controller's power and start up the LinMot-Talk 1100 software. Before using the controller the first time, the firmware has to be downloaded. Therefore press install firmware button  to start the wizard. Choose the file "Firmware\_V3S7\_Build20071206.sct" and press "Open". Then the wizard will start and guide through the installation. According to controller type, different interface and application software can be selected.

## 3.3 Login


When successfully finished downloading the firmware, login with \File\Login... , 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:

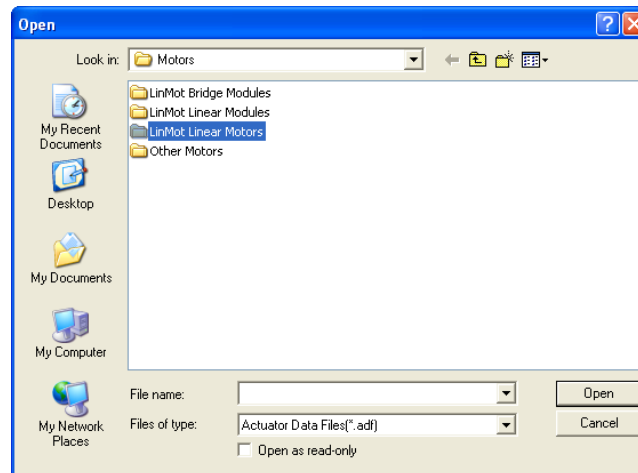


The Object Inspector window can be dragged away or closed. It can be reopened with F1.

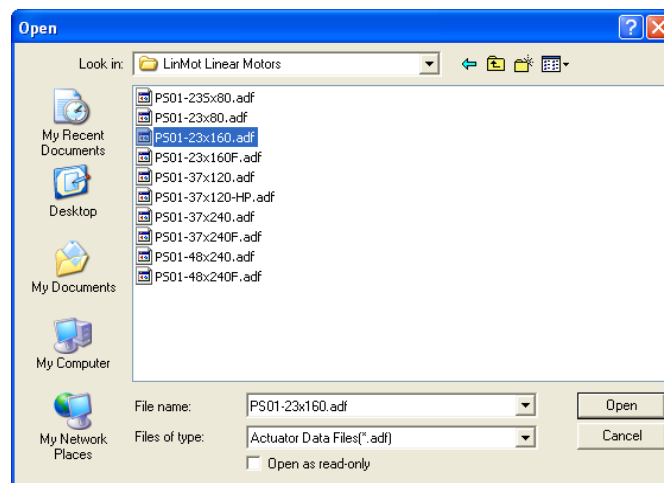


### 3.4 Motor Wizard

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.



Select the actuator type you have wired to the controller, then press Open.

The following steps will show forms including drawings and descriptive texts.

The first step is to define the stator and slider.

Motor Wizard

Step 1/9: Actuator Selection

Actuator Data File:

PS01-37x240.adf

Change Actuator ...

Stator:

PS01-37x240

Slider:

PL01-20x500/420

The slider can be identified by its length. Newer sliders have the type engraved on the surface.

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.

Derived Settings	Value	Comment
MOTOR	P01-37x240/160x360	
Maximal Stroke (S)	360 mm	
Shortened Stroke (SS)	160 mm	
Electromagnetic Zero Position (ZP)	130 mm	
Force Constant	40.8 N/A	
Edge Force (Fb)	58 %	
SLIDER	PS01-37x240	
Article Number	0150-1203	
Stator Length	347 mm	
Stator Mass	1365 g	
SLIDER	PL01-20x500/420	
Article Number	0150-1328	
Slider Length	500 mm	
Slider Mass	1064 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 next step is to choose the flange for defining the cooling capability.

[illegible]

Longer extension cables will have an effect to the motor's phase resistance. In step 3 can be defined 2 cable segments.

[illegible]

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

[illegible]

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:

The diagram illustrates a mechanical system where a slider moves along a horizontal track. A vertical bar is attached to the slider. To the right of the slider, there are three small diagrams representing different orientations: -90°, 0°, and +90°. Each orientation shows a red arrow pointing right and a blue arrow pointing left, indicating the direction of movement or force.

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	
FF Constant Force	0 A	Current for constant force compensation
FF Friction	0.049 A	Current for compensation of dry friction
FF Damping	0 A/(m/s)	Factor for compensation of viscous friction
FF Acceleration	0.038 A/(m/s^2)	Acceleration feed forward factor

Navigation buttons: Help, < Back, Next >, Finish, Cancel

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

**X Motor Wizard**

### Step 6/9: PID Position Controller

---

#### PID Position Controller Setting

P Gain	<input type="text" value="1"/>	A/mm	<input type="button" value="Set To Default Soft"/>	(P=1, D=3, I=0)
D Gain	<input type="text" value="3"/>	A/(m/s)	<input type="button" value="Set To Default Stiff"/>	(P=3, D=8, I=0)
I Gain	<input type="text" value="0"/>	A/(mm*s)		

#### Noise Filter

Dead Band  mm ☒ Enable Noise Filter

Beside the feed forward parameters (see previous step), the PID controller setup influences the control behavior. For the most applications it is possible to achieve good results with one of the given default settings (no additional loop tuning necessary).

The Noise Filter eliminates noise from the position feedback sensor when the motor stands still.

On Applications which require high positioning accuracy (typically together with an external position sensor) the Noise Filter should be disabled.

Derived Settings	Value	Comment
P Gain	1 A/mm	
D Gain	3 A/(m/s)	
I Gain	0 A/(mm*s)	
Integrator Limit	8 A	
Maximal Current	8 A	
Noise Filter Dead Band	0.02 mm	

Help   < Back   Next >   Finish   Cancel

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).

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

Press finish, all wizard settings will now be written to the controller.

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).

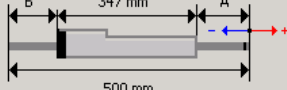
Other modes support homing on home switches, limit switches, indexer inputs or some combinations of those.

Step 8 is to define the slider home position. This is for the motor and controller 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 in each direction is able to move.

**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 controller 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). Hence you can move the motor manually to the Home Position. Then you can measure A or B (stator end to slider end) and 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

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.

Derived Settings	Value	Comment
Minimal Position (stroke range limit)	-70 mm	
Maximal Position (stroke range limit)	290 mm	
Distance C	20 mm	
Distance D	133 mm	

Help < Back Next > Finish Cancel

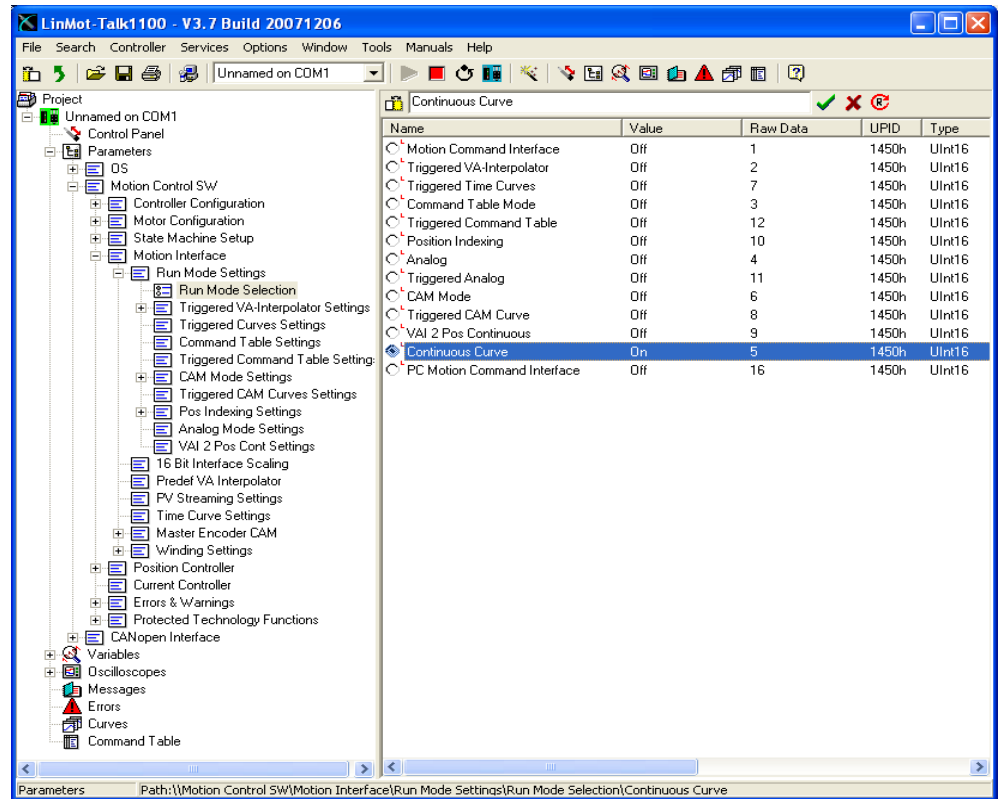
At the end press finish. If the firmware on the controller is still running, an appropriate message will be shown.

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.

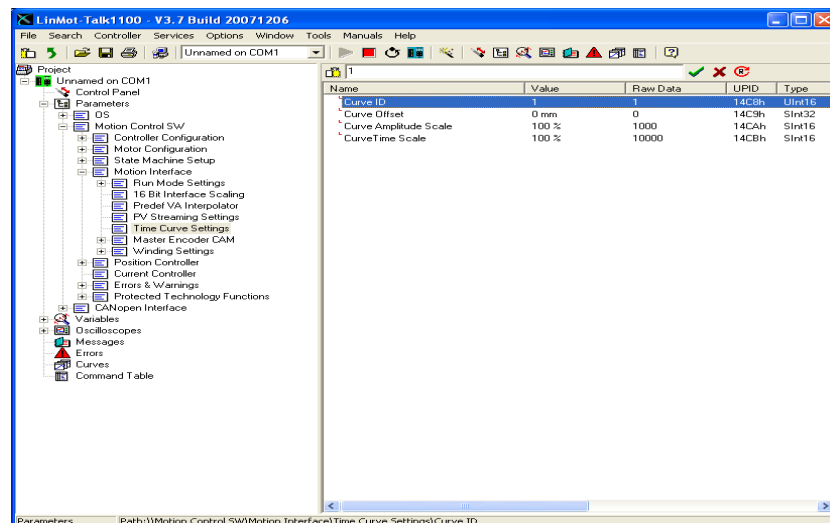


### 3.5 Continuous Curve Mode

To get running the motor for the first time, the easiest way is to define a curve which will be run continuously. The controller 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.





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\.

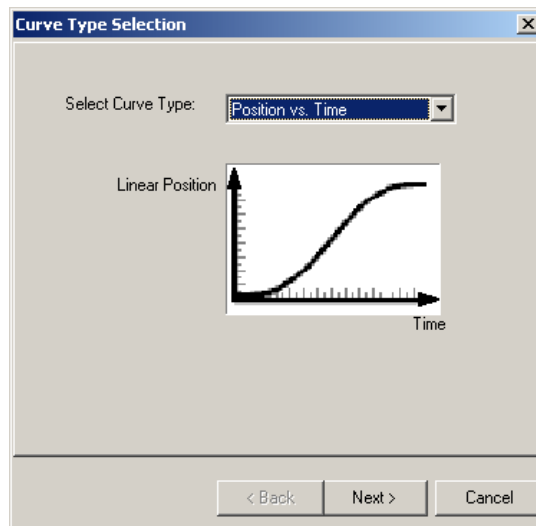


Before running the curve, it is advisable to define the curve we want to run.

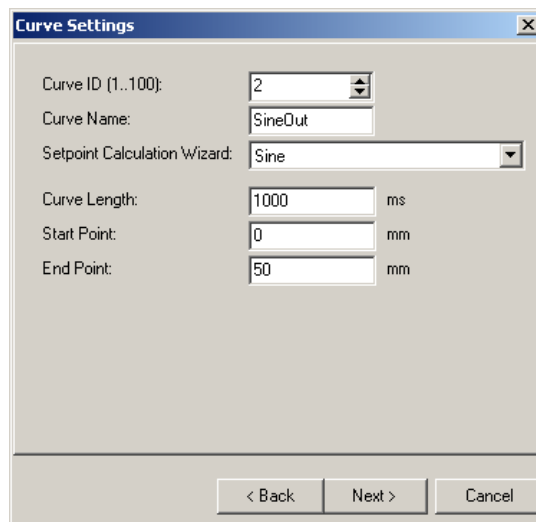
### 3.6 Defining Curves

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.

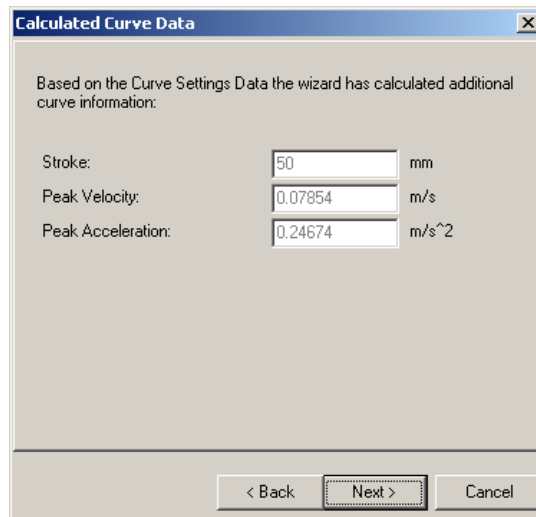
Now, step by step: Open the curve tool by clicking the “Show Curves” button  in the tool button bar. Then press the “New Curve” button  to start the curve wizard.



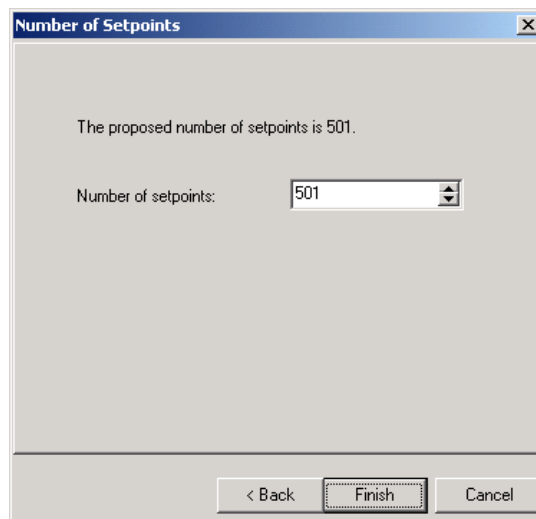
As we want to define a curve in position vs. time mode we can keep the default selection and press the next button.



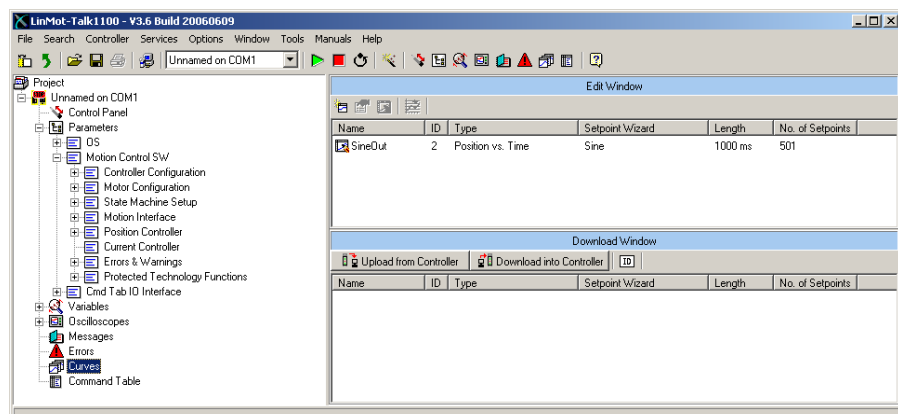
In this mask, we will set the curve ID to 2 (we will have the merged curve with ID 1 at the end) and as name we set e.g. “SineOut”. The end point is placed at 50mm. With “Next” the wizard will show some curve data:



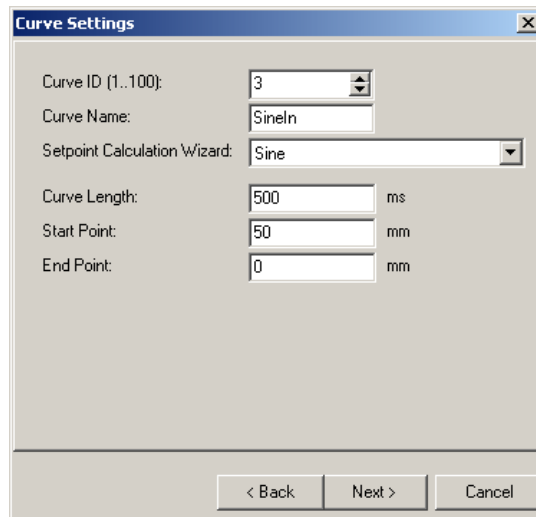
The next and last mask proposes a number curve setpoints. It is advisable to accept this proposal.



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:



Curve ID (1..100): 3

Curve Name: SineIn

Setpoint Calculation Wizard: Sine

Curve Length: 500 ms

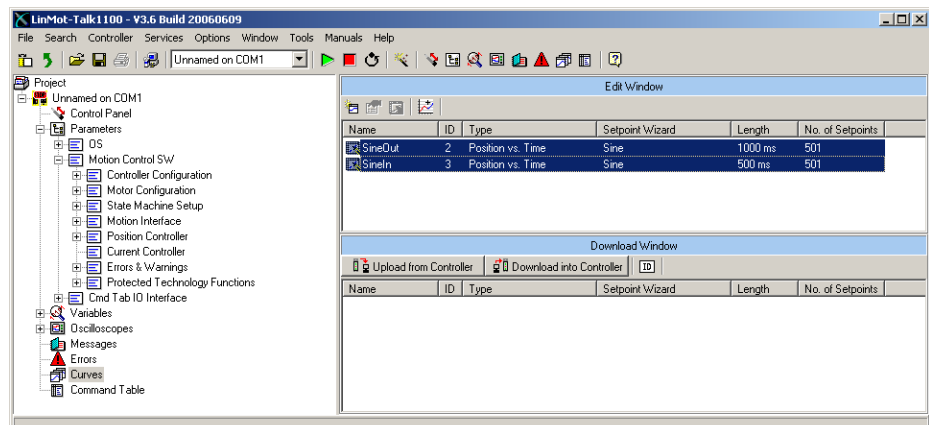
Start Point: 50 mm

End Point: 0 mm

< Back Next > Cancel

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



LinMot-Talk 1100 - V3.6 Build 20060609

File Search Controller Services Options Window Tools Manuals Help

Project: Unnamed on COM1

- Control Panel
- Parameters
  - OS
  - Motion Control SW
    - Controller Configuration
    - Motor Configuration
    - State Machine Setup
    - Motion Interface
    - Position Controller
    - Current Controller
    - Errors & Warnings
    - Protected Technology Functions
  - Cmd Tab IO Interface
- Variables
- Oscilloscopes
- Messages
- Errors
- Curves
- Command Table


Edit Window

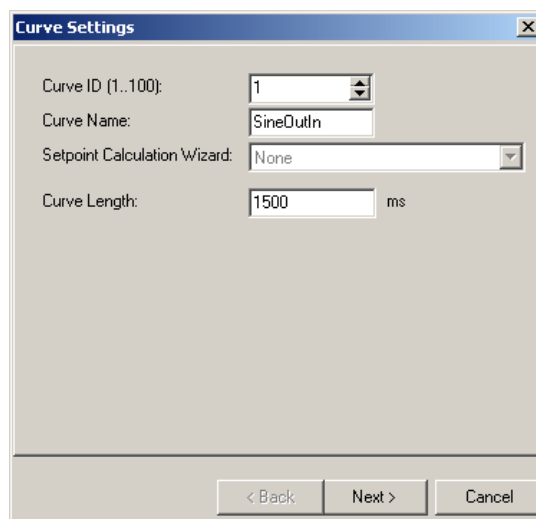
Name	ID	Type	Setpoint Wizard	Length	No. of Setpoints
SineOut	2	Position vs. Time	Sine	1000 ms	501
SineIn	3	Position vs. Time	Sine	500 ms	501

Download Window

Upload from Controller Download into Controller ID

Name	ID	Type	Setpoint Wizard	Length	No. of Setpoints
------	----	------	-----------------	--------	------------------

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



Curve ID (1..100): 1

Curve Name: SineOutIn

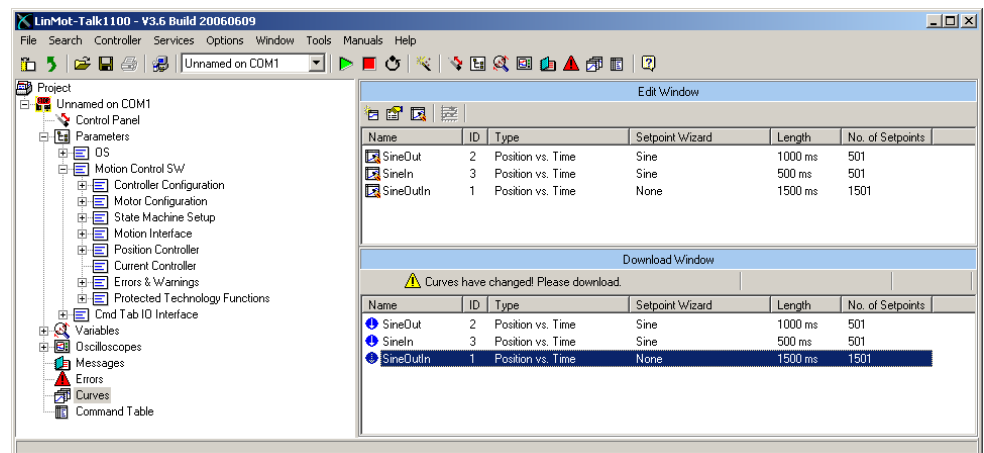
Setpoint Calculation Wizard: None

Curve Length: 1500 ms

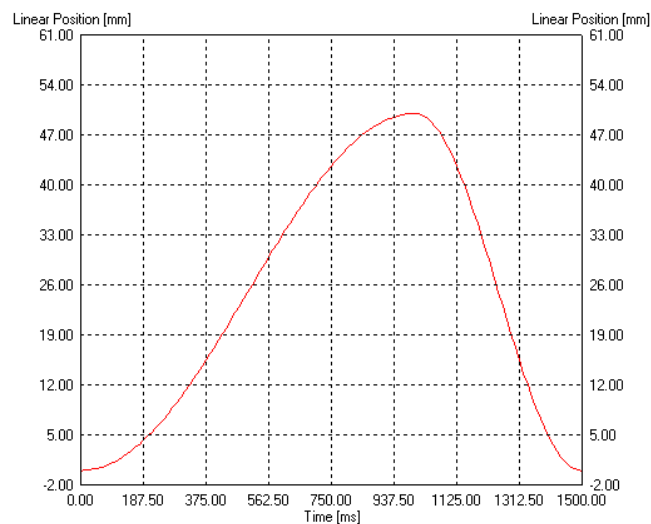
< Back Next > Cancel



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. 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 controller 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:

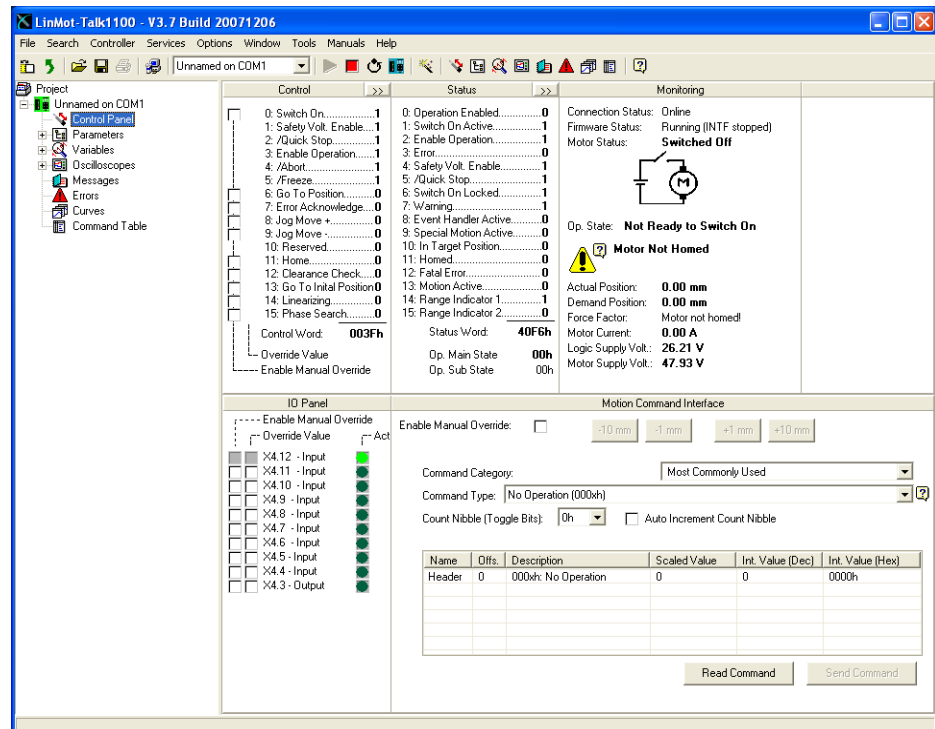


Now the curves must be downloaded to the controller. Therefore press the “Show Curves” button  and then the “Download Curves into Controller” button . Then a warning comes up which has to be confirmed and the progress window will display the actions taken to download the curves.

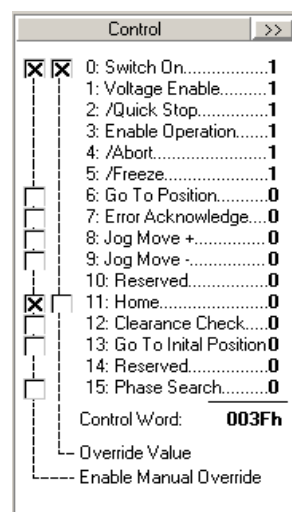
## 3.7 Control Status

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 controller'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.






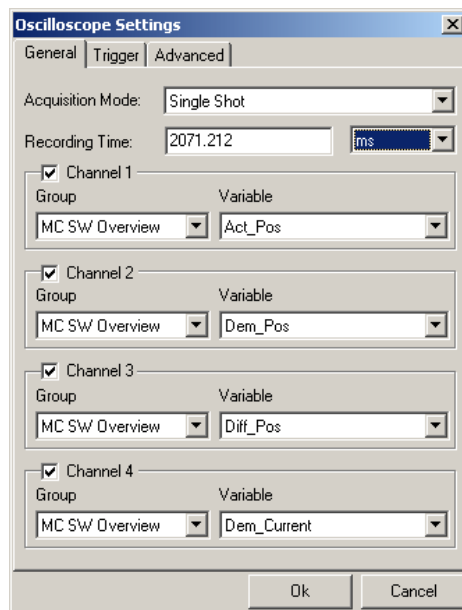
software manual.


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

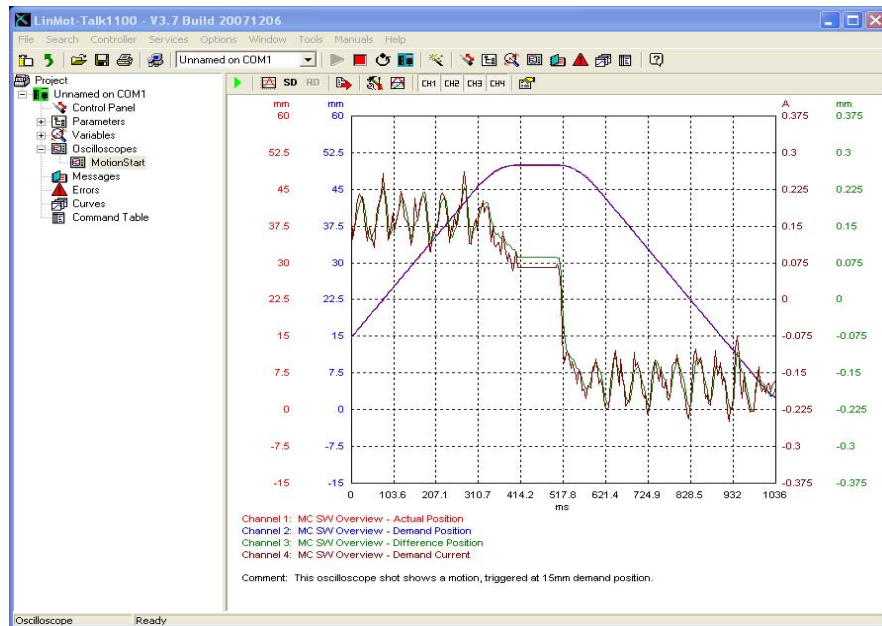
### 3.8 Oscilloscope

The oscilloscope is a very useful tool for tuning the motor. The LinMot Talk 1100 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 controller and displayed, which will look somehow like the following.

Possibly it is necessary to press button  (fit view).



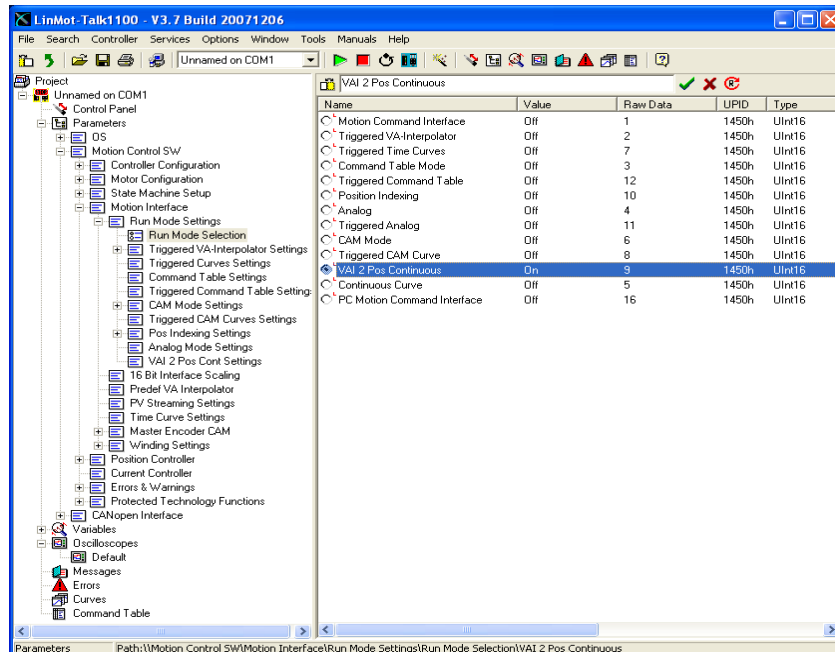
Tuning the system would be started at this point. One possibility is by restarting the Motor Wizard and changing the load or control parameter, another one is to change the parameters directly in the parameter tree.



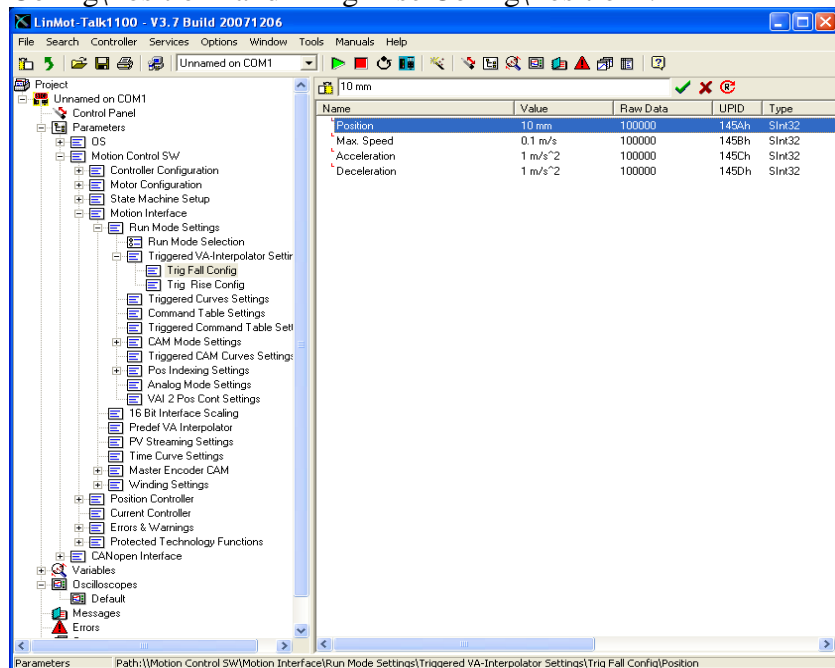
### 3.9 Continuous Two Point Mode

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 3.7 Control Status.

## 4 Trouble shooting

### 4.1 Set all Parameters to Default

All parameters of a E1100 controller can be set to their default values without the use of the LinMot Talk1100. This can be done according these steps:

1. Power off the controller
2. Set the two ID switches to \$FF
3. Power on the controller, the ERROR and WARN LEDs will flick alternately.
4. Set the two ID switches to \$00
5. Wait until the WARN and EN LEDs will flash together.
6. Power off and on again.

NOTE: This feature is not supported on B1100 series controllers.

### 4.2 Bootstrap OS

In case of \$B2 error, which means a communication timeout, if no rebooting or resetting the parameters will help, there is the option of bootstrapping the operating system. This can be done according to these steps:

1. Close the LinMot Talk1100 software.
2. Power on the controller
3. For E1100 controllers: Press with a spiky object into the small hole below the X5 connector. (If there are two holes take the unlabeled one). The controller's LEDs will all be off except for the green one.
4. For B1100 controllers: Switch S4.4 to "on". Only the green LED will light up.
5. Start the LinMot Talk1100 software.
6. Press the Install Firmware button.
7. For E1100 controllers: Select the file under \Firmware\OS\BootStrapOS\_RS\BootOS3\_E1100\_RS.sct and follow the instructions.
8. For B1100 controllers: Select the file under \Firmware\OS\BootStrapOS\_RS\BootOS3\_B1100\_RS.sct and follow the instructions.
9. After this procedure, the firmware can be installed as described under 3.2 Firmware Download.

### 4.3 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 "Interface" on controller'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).
- Paramter with UPID 2008h set to disable.
- Baud Rate and Node ID selection not correctly set (Parameters and/or ID switches on controller's front).

## 5 Contact Addresses

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262-723-6688

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**Web:** <http://www.linmot-usa.com/>

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