| | | | 1 |
|-------------|------|------|--------|
| | | | 2 |
| Servo On | | | 3 |
| Motor State | | | 3 |
| | | | 4 |
| | | | 5 |
| | | | 7 |
| | | | 9 |
| | | | 11 |
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Motion Test

 \times ComilDE

ComilDE ComiIDE by COMIZOA (v1.3.7.3) Main View Setup Motion Control I Motion Control II 10 Custom IO Style ¢ **.** SlaveRW Alarm.H **)** d. P >_ ŵ R ¥= B DSP PCM Load M.Edit Scan Save Update Shell Install DLLs Servo Config PDO Tool Project Tool II д × Motor Monitor яx [0] COMI-LX554 (EtherCAT) × Axis 2 OFF Axis 3 OFF 3 Sinale Axis Sx Speed Item Details Compati • S.Mode 1,71,0,0 Firmware ОK 0.0 0.50 **2** Q.5* Work Driver 1, 5, 0, 1 ОK ąх Accel 1,5,0,3 οк Library Reset C.Pos F.Pos C.Spd F.Spd Torq Decel Init Axis 2 0 0 0 0.00 0 End Position 1 Axis 3 0.00 Position 0 Rpt. 0 0 ! Jerk 0 500 1234567 명령창(Shell)을 실행합니다. -0 100 % \Diamond € \Diamond Installer를 Driver 및 DLL을 설 수 있습니다. sô Device Inf DLL Finder를 실행합니다. 현재 COMIZOA의 DLL을 사용하는 모든 프로그램을 검색합니다. Emergency Р 0 1 R Α w Ν h Ψ× Axis 2 C Monitor를 실행합니다. PC의 leep, Freezing 여부를 확인할 수 !습니다. Log Level 1: Log only when error occured • Time Channel Code Command Info -Axis 3 18:53:44,221 netID 0 100 EtherCAT Load Complete Motion Editor(Shell)를 실행합니 다. 18:53:44,226 netID 1 100 EtherCAT Load Complete

, Style - Multi

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| 🗐 ComiIDE I | by COMIZOA | (v1.3.7.3) | | | | | | | |
|-------------|------------|-------------------|--------------|-----------|-----------|------------|-------|-----------|-------|
| Setup | Main | View | Motion | Control I | Motion | Control II | ю | Custom IO | Style |
| Change | Save | <u>ြာ</u> Load | BBB Multi | One | Clear | Simple | Scope | Gray | Blue |
| | Dock Style | | | | Dock Mode | | | | The |

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| • Network M [0] COM [1] COM | 1otion 11-LX554 (EtherC 11-LX554 (EtherC | CAT) CAT) |
|-----------------------------------|--|---------------|
| Item | Details | Compatibility |
| Firmware | 1,71,0,0 | ОК |
| Driver | 1, 5, 0, 1 | ОК |
| | | |

• DeviceList

Load

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• Device가

| Clear | Log Level | 1 : Log or | ly when error occure | ed 🚽 🚽 | Find |
|--------------|-----------|------------|----------------------|----------|------|
| Time | Channel | Code | Command | Info | |
| 23:21:32,750 | netID 0 | 100 | EtherCAT Load | Complete | |
| 23:21:32,773 | netID 1 | 100 | EtherCAT Load | Complete | |
| | | | | | |
| | | | | | |
| | | | | | |
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• LogView Load 가

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LogView
 Log View

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Servo On • Motor Monitor 7: ...

Servo_On

| Motor Monitor | | ņ | × |
|---------------|---------------|----------|---|
| Axis 2 ON | Axis 3 OFF | | |

- Motor Monitor Motor . ServoOn Stop
- Motor Monitor
 Motor Monitor



| MIO Monitor | | | | | | | oooo 🖡 🗙 |
|-------------|-----|-----|------|-----|-----|-----|----------|
| Emergency | RDY | ALM | WARN | NEL | PEL | ORG | INP |
| Axis 2 | - | - | - | - | - | - | - |
| Axis 3 | | - | | | | | - |

| • | , Alarm | , PEL (Limi | t+)/ | NEL(Limit-) | 가 |
|--------------|---------|-------------|------|-------------|---|
| , • Ready | | , RDY | 가 | | |

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• MIO Monitor **MIO Monitor** • AxisList

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| AxisList | | | | | × |
|------------------|---------|--------------|-------------|---------------|-----------------------------|
| 2 * | 3 | | | | |
| Single Axis | | | × | Sx Speed | |
| <u>Θ</u> "θ. | | • | 0. | Speed Mode | S-CURVE |
| Q.55* | 2:55 | | Q.55* | Work Speed | 100000 |
| | | | | Acceleration | 400000 |
| | | | | Deceleration | 400000 |
| | | | | Initial Speed | 0 |
| | | Dether | Deel/deel.4 | End Speed | 0 |
| | ! | Kpt.Interval | 1234567 | Jerk Ratio | 0.66 |
| | | 500 | 1204007 | | 100 % |
| | | | ¢> | <u></u> | |
| Device Info Sing | le Axis | | | | |

• AxisList

AxisList

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| Single Axis × | Sx Speed | X S-CURVE |
|------------------------------------|--------------|--------------|
| Q.5* Q.5* Q.5* | Work Speed | 100000 |
| | Deceleration | 400000 |
| Position 0 Rpt.Interval Position 1 | End Speed | 0 |
| 0 500 1234567 | Jerk Ratio | 0.66 |
| Device Info Single Axis | | |

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| AxisList | |
|------------------------------------|--|
| Single Axis | Sx Speed |
| | Work Speed 10000 Acceleration 40000 |
| | Deceleration 40000 |
| Position 0 Rpt.Interval Position 1 | End Speed 0.60 |
| | 100 % |
| Device Info Single Axis | |

• Setup

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- SetSpeed_Sx
- KeyPad KeyPad

• ¹⁾ RelativeMove-Mode .

| AxisList 2 * 3 | | × |
|------------------------------------|-----------------------------|---------|
| Single Axis × | Sx Speed Speed Mode S-CURV | × /E |
| Q.5* Q.55 Q.55* | Work Speed 10000 | 00 |
| | Deceleration 40000 | 00 |
| Position 0 Pot Interval Position 1 | End Speed | 0 |
| 0 I 500 1234567 | Jerk Ratio 0.6 | 66 % |
| | | |
| | | |

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• Distance

| AxisList | KeyPad | _ | × | |
|---|--------|----|------|------|
| 2* 3 | | | 1000 | ← |
| Single Axis × | << | >> | +, | /- |
| | 1 | 2 | 3 | OK |
| Distance 0 Rpt.Interval Distance 1 -100000 500 100000 | 4 | 5 | 6 | |
| | 7 | 8 | 9 | Evit |
| | н | 0 | | |
| | | | | - |

Move

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SingleAxis



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| Single Axis X Speed Mode S-CURVE Speed Mode S-CURVE Work Speed 100000 Acceleration 400000 Distance 0 Image: State of the state | AxisList 2 * 3 | <u>ا</u> |
|--|--|---|
| Vision Vision Work Speed 100000 Acceleration 400000 Acceleration 400000 Distance 0 Image: Speed 0 Image: Speed 0 -100000 Image: Speed 0 Image: Speed 0 -100000 Image: Speed 0 Image: Speed 0 Image: Speed Image: Speed Image: Speed 0 0 Image: Speed | Single Axis × | Sx Speed Speed Mode Speed Mode S-CURVE |
| Distance 0 Image: Constraint of the second of the seco | | Work Speed 100000 Acceleration 400000 |
| Distance 0 Rpt.Interval Distance 1 -100000 1000 1000 C Maye (+) Image: Compared to the second to th | | Deceleration 400000 Initial Speed 0 |
| | Distance 0Rpt.IntervalDistance 1-1000005001000 | Jerk Ratio 0.66 |
| | Device Info Single Axis | |

Position Monitor

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Command Position Feedback Position

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Position Monitor

Position Monitor

| Position Monitor | | | | | |
|------------------|------------|------------|---------|---------|--------|
| Reset | C.Position | F.Position | C.Speed | F.Speed | Torque |
| Axis 2 | 1 000 | 1 000 | 0 | 0 | 1.50 |
| Axis 3 | 0 | 0 | 0 | 0 | 0.00 |

- Feedback Position
- 2) 가 Motor ,

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Trouble Shooting

• EtherCAT TroubleShooting

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- PCI_Pulse TroubleShooting
- NEMO TroubleShooting
- 1)

2)

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Last update: 2024/07/08 18:23