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× (Torque Limit)

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1. Configurator Download Dictionary

The screenshot shows the ComilIDE (v1.6.4.0) interface. The main window is the 'Configurator' for an EtherCAT system. In the top toolbar, the 'Dictionary' icon is highlighted with a red box. The 'Device List' on the left shows a project named '[0] COMI-LX550'. The 'Scanned List' shows two slaves: '#00 [02FFh] MASTER-DC' and '#01 [0005h] SGD7S-xxxxA0x C0E'. The 'Cycle Time' section shows parameters like RoundTrip (Set: 1000, Current: 30, Max: 50, Average: 31.15) and ProcessCycle (App: 30, Net: 11). The 'Log View' at the bottom shows error messages: 'ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...'. The 'Motor Monitor' on the right shows 'Axis 4 INITIAL' and a table of motor parameters.

Reset	C.Pos	F.Pos	C.Spd	F.Spd	Torq
Axis 4	1,025,000	1,025,000	0	0	2

• Config→ Download Main Dictionary

2. SDO Torque Limit

Object Dictionary Table:

Index	Name	Type	Size	Value	Value_Hex	Flags
0x609A	Homing acceleration	UDINT	4	0	0x0000	rw RT
0x60A4	Profile jerk	DT60A4	6	0	0x0	ro
0x60B1	Velocity Offset	DINT	4	0	0x0000	rw RT
0x60B2	Torque Offset	INT	2	0	0x00	rw RT
0x60B8	Touch probe function	UINT	2	0	0x00	rw RT
0x60B9	Touch probe status	UINT	2	0	0x00	ro T
0x60BA	Touch probe 1 position value	DINT	4	0	0x0000	ro T
0x60BC	Touch probe 2 position value	DINT	4	0	0x0000	ro T
0x60C1	Interpolation data record	DT60C1	6	0	0x0	ro
0x60C2	Interpolation time period	DT60C2	4	0	0x0	ro
0x60E0	Positive Torque Limit Value	UINT	2	0	0x00	rw RT
0x60E1	Negative Torque Limit Value	UINT	2	0	0x00	rw RT
0x60E4	Additional Position Actual Value	DT60E4	6	0	0x0	ro
0x60F2	Positioning option code	UINT	2	0	0x00	rw R
0x60F4	Following error actual value	DINT	4	0	0x0000	ro T
0x60FC	Position demand internal value	DINT	4	0	0x0000	ro T
0x60FD	Digital inputs	UDINT	4	0	0x0000	ro T
0x60FE	Digital outputs	DT60FE	10	0	0x0	ro
0x60FF	Target velocity	DINT	4	0	0x0000	rw RT
0x6502	Supported drive modes	UDINT	4	0	0x0000	ro
0x60C0	Interpolation sub mode select	INT	2	0	0x00	rw
0x2730	Interpolation data configuration for 1st pr	DT2730	18	0	0x0	ro
0x2731	Interpolation data configuration for 2nd pr	DT2731	18	0	0x0	ro
0x2732	Interpolation profile select	USINT	1	0	0x0	rw RT

LogView Table:

Time	Channel	Code	Command	Info
13:05:31.691	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:05:31.691	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:05:31.692	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:05:31.692	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:05:31.692	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...

- SDO Torque Limit

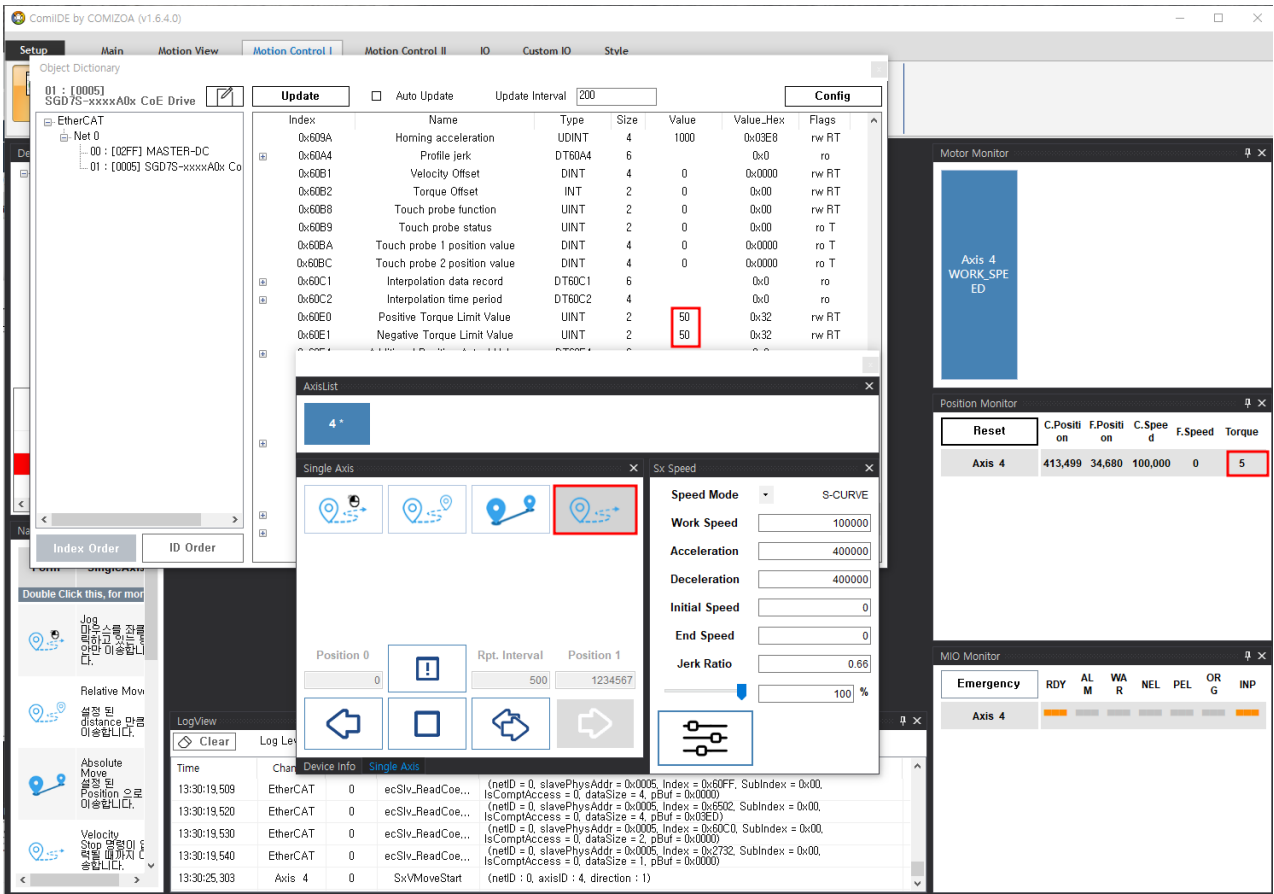
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0x60A4	Profile jerk	DT60A4	6	0	0x0	ro
0x60B1	Velocity Offset	DINT	4	0	0x0000	rw RT
0x60B2	Torque Offset	INT	2	0	0x00	rw RT
0x60B8	Touch probe function	UINT	2	0	0x00	rw RT
0x60B9	Touch probe status	UINT	2	0	0x00	ro T
0x60BA	Touch probe 1 position value	DINT	4	0	0x0000	ro T
0x60BC	Touch probe 2 position value	DINT	4	0	0x0000	ro T
0x60C1	Interpolation data record	DT60C1	6	0	0x0	ro
0x60C2	Interpolation time period	DT60C2	4	0	0x0	ro
0x60E0	Positive Torque Limit Value	UINT	2	0	0x00	rw RT
0x60E1	Negative Torque Limit Value	UINT	2	0	0x00	rw RT
0x60E4	Additional Position Actual Value	DT60E4	6	0	0x0	ro
0x60F2	Positioning option code	UINT	2	0	0x00	rw R
0x60F4	Following error actual value	DINT	4	0	0x0000	ro T
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0x2730	Interpolation data configuration for 1st pr	DT2730	18	0	0x0	ro
0x2731	Interpolation data configuration for 2nd pr	DT2731	18	0	0x0	ro
0x2732	Interpolation profile select	USINT	1	0	0x0	rw RT

LogView Table:

Time	Channel	Code	Command	Info
13:06:32.775	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:06:32.775	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:06:32.775	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:06:32.775	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...
13:06:32.775	EtherCAT	-183	ecSlv_ReadCoe...	ecERR_IMPROPER_AL_STATE (AL-STATE가 적절하지 않은 경우) (netID = 0, slaveP...

1. Value .
2. Value enter.



Velocity , 가 Limit

* Torque Limit . (Ex: Torque Limit = Maximum Current)

From:

<http://comizoa.co.kr/info/> - -

Permanent link:

http://comizoa.co.kr/info/doku.php?id=faq:motion:ethercat:07_torque_limit_setup

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