		·	1
1. Configurate	or Download	Dictionary	1
2. SDO	Torque Limit		1

.

x	(Torque Limit)
[]

1. Configurator Download Dictionary

Setup	Main	Motion View	Motion Control I	Motion Control II	IO Custom IC) Style					-		
Scan S	Save I	.oad Update	EV Install	DLLS PCM	Shell Scripter	Servo FW	Config Slaves	Alarm,H PC	DO Dictional		DSP		
	Project		Reset	Tool	To	ol II	G C	Tool E	EtherCAT		Gi .		
Device List		Ψ×							Ν	otor Monitor			ţ
[0] CO	MI-LX550	Configu	rator										
		Setur	Main Main	Connection Addre	ss Config 401								
			Address Cut	tom Auto	402								
			Scanned List							Axis 4 INITIAL			
		Slave	Count 2										
		#00 [02 #01 [00	FFh] MASTER-DC 105h] SGD7S-xxxxA0x (laster DC								
				Delay . 0									
Item	Deta	ils		5GD75-x0	ERVO				P	osition Monitor			
Driver	2, 39, 1	.0		Delay . U						Reset	C.Pos F.Pos	C.Spd F.Spd	Tor
Library	2, 3, 4	.0		Cycle T	ime					Axis 4	1,025,0 1,025,0 00 00	0 0	2
<		>		Set :	1000								
Navigator		4 ×		Curr Max	ent : 30 : 50								
Menu	Project	^		Aver Process	age : 31.15 Cycle								
Double Click	this, for m	pr		App	30								
	되바일순률 제기로드립	ć		1101.									
	D.'								~ N	IO Monitor			
	ComilDE에. 설정된 각 홈 설정값 및 프			<	r Initial	ProOP SofoOP	OP Undate		> ESC Info	Emergency	RDY AL WA	NEL PEL	OR IN
	젝트 속성을 로젝트 설정 일로 저장한	LogView		> Discon End		Theor Saleor	on opuate		₽ ×	Axis 4			
	6	🔗 Clear	Log Level 3 : L	og when command func	ti 👻	Q Search							
ê 🗐	ComilDE에. 저장된 프로 트 설정 파의	Time	Channel C	ode Command	Info				^ ^				
	불편읍니다.	13:02:07,11	D EtherCAT -	103 ecSIV_HeadCoe 183 ecSIV_ReadCoe	ecern_imprope	R_AL_STATE (AL-ST R_AL_STATE (AL-ST	IATE가 적절하지 않은 경 TATE가 적절하지 않은 경	s 두) (netil) = 0, sla 홍무) (netil) = 0, sla	veP				
3	프로젝트 설 파일은 WorkData 즼	정 13:02:07,11	D EtherCAT ·	183 ecSlv_ReadCoe	ecERR_IMPROPE	R_AL_STATE (AL-ST	「ATE가 적절하지 않은 겯	병우) (netID = 0, sla	veP				
	에 ini 파일형 음로 저장됩	13:02:07,11	1 EtherCAT -	183 ecSlv_ReadCoe	ecERR_IMPROPE	RLALLSTATE (AL-ST	「ATE가 적절하지 않은 경 「ATE기 저작하지 아우 크	명우) (netID = 0, sla 명우) (netID = 0, sla	veP				
		Tordendr, TT	Elleren	ico econemendede	SCENTERN HOPE				×				
	C			Main	D: -+:								

2. SDO Torque Limit

2025/07/04 13:51



2/3

🔕 ComilDE	by COMIZOA	(v1.6.4.0)														-	
Setup	Main	Motion View	Motion Control I	Moti	on Control II	IO Custom IO Style											
	(a) (i	5) 🐼	()			約 🚺	h									
Scan	Save L	.oad Update	FW Install	DLLs	PCM	Shell Scripter Servo	FW C	onfig	Slaves Ala	arm.H PDO	Dictionary	ESC	DSP				
	Project		Reset	Tool		Tool II				Tool EtherC	AT		G				
A 1 111						1	191										
Device List	T.	Object Dictionary		_						_		itor			000000000000000000000000000000000000000		
L. [0] (COMI-LX550	01 : [0005] SGD7S-xxxxA0:	x CoE Drive		Update	Auto Update Update In	nterval 200				Config						
		- EtherCAT			Index	Name	Туре	Size	Value	Value_Hex	Flags	^					
		📥 Net 0			0×609A	Homing acceleration	UDINT	4	0	0x0000	rw BT						
		00 ÷ [02F	F] MASTER-DC		0x60A4	Profile jerk	DT60A4	6		0x0	ro						
			5] SGD7S-xxxxABx C		0×60B1	Velocity Offset	DINT	4	0	0×0000	rw BT						
					0×60B2	Torque Offset	INT	2	0	0×00	rw BT	L.					
					0×60B8	Touch probe function	UINT	2	0	0×00	rw BT						
					0×60B9	Touch probe status	UINT	2	0	0×00	ro T						
					0×60BA	Touch probe 1 position value	DINT	4	0	0×0000	ro T						
					0×60BC	Touch probe 2 position value	DINT	4	0	0×0000	ro T						
				E	0×60C1	Interpolation data record	DT60C1	6		0×0	ro						
Itom	Data			Ħ	0×60C2	Interpolation time period	DT60C2	4		0x0	ro						
item	Deta				0×60E0	Positive Torque Limit Value	UINT	2	0	0×00	rw BT	inito	r				
Firmware	e 2,39,1				0×60E1	Negative Torque Limit Value	UINT	2	0	0×00	rw BT	et	C.Po	s F.Pos	C.Spd	F.Spd	Tor
Driver	2, 3, 1			E.	0×60E4	Additional Position Actual Value	DT60E4	6		0×0	ro	-			oropa	nopu	
Library	2, 3, 4				0x60F2	Positioning option code	UINT	2	0	0x00	rw B	4	1,025	,0 1,025,0) 0	0	2
					UX6UF4	Following error actual value	DINT	4	U	UXUUUU	ro I						
<					UX6UFC	Position demand internal value	DINT	4	U	0x0000	ro I						
					UX60FD	Digital Inputs	DUDINT	4	U	0,0000	roi						
Navigator					0x00FE	Transfer training	DINT	10	0	0x0	ru 						
					0.00000	Purported drive modes	LIDINT	4	0	0x0000	rw n i						
Menu	Project				0x0502	Interpolation cub mode coloct	INIT	*	0	0x0000	ru						
Double Cli	ck this, for m				0x0000	merpolation sub-mode select	DT2720	19	U	0x00	199						
0	디바이스를	<	>		0v2731	noistion data configuration for 2nd pr	DT2730	18		0×0	10						
	캙/모드립	Index Order	ID Order]	0x2732	Internolation profile select	USINT	1	n	0x0	rw BT						
<u></u>	Lr.											Monuor					
	ComilDE01	4		<							>			AL 16	^		1P
°	_ 설정된 각 족 _ 설정값 및 프	-		Di	scon Er	ror Initial PreOP Sat	feOP (P IIr	date +	- ESC	Info	mergenc	y RDY	M F	NEL	PEL	G ∎
	젝트 속성을 로젝트 설정			>				. 01	ruato .			Avia 4					
	일로 저장합 다	LogView									ų×	AAIS 4					
_		🔗 Clear	Log Level 3 : L	og when	command fur	icti • Q Sear	ch										
â-	ComilDE에	서 제 Time	Channel (ode	Command	Info					^						
S	시장된 프로 톱 설정 파일	13:06:32 775	EtherCAT	183	ecSly BeadCo	ecEBB IMPROPER AL STATE (4	AL-STATE 74	전적하고 '	같으 견으) (n	ettD = 0_slaveP							
	물러봅니다.	10:00:02,110	EtherCAT	100	- Clu Baado			ㅋ르이지 퍼져린 편 :	3 C 3 C 1 C 1 C	etD = 0, slaver							
	프로젝트 섬	정 13:06:32,775	EtherCA1 ·	103	ecolv_HeadCo	ecentrumphuper_al_STATE (A	al-STATE가	억열하시 '	당은 경우)(n	ettu = U, staveP,							
3	파일은 WorkData 클	13:06:32,775	EtherCAT ·	183	ecSlv_ReadCo	ecERR_IMPROPER_AL_STATE (4	AL-STATE7	적절하지 '	같은 경우) (n	etID = 0, slaveP							
8	에 ini 파일함	13:06:32,775	EtherCAT ·	183	ecSlv_ReadCo	ecerr_IMPROPER_AL_STATE (A	AL-STATE7	적절하지 '	않은 경우) (n	etID = 0, slaveP							
	and the second se																

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

- 1. Value
- 2. Value

enter.



From: http://comizoa.co.kr/info/ - -

Permanent link: http://comizoa.co.kr/info/doku.php?id=faq:motion:ethercat:07_torque_limit_setup&rev=1659507987

Last update: 2024/07/08 18:22