



JetMove 2xx
Version Update
from V. 2.05 to V. 2.06



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1 Introduction

Overview of Version Updates			
Version	Function	upgraded	corrected
V 2.05	Function "Table"	✓	
	Evaluation of the encoder	✓	
	"MotionStop" instruction	✓	
	I-component of the speed controller	✓	
	Multi-channel position capture	✓	
	I ² t-monitoring of the motor	✓	
	Compensation of dead time for the master position	✓	✓
	Limit switch monitoring		✓
	Referencing		✓
	Standardisation of the current		
V 2.06	Time synchronisation		✓

2 Expansions

2.1 Busy-Flags

By the following commands, the busy-flag is set in the status-word now (100.13):

- Command 1 - Activate the controller
- Command 2 - Deactivate the controller
- Command 3 - Set reference
- Command 4 - Stop and re-synchronise the setpoint generator towards actual position
- Command 8 - Acknowledge the error

Command 4 (stop and re-synchronise the setpoint generator towards actual position) now also sets the destination window flag in the status-word (register 100.2).

2.2 Index-Test for Table-Configurations

At command 46 "Start Table", the maximum and the minimum index of the table configuration to be started is checked. If the maximum index is smaller, or equal to, the minimum index, the table is not started, while, for reporting, bit 21 is set in register 170. Register 170.21 is reset by starting a valid table configuration.

2.3 Short-Circuit Warning for Digital Outputs

The status bit of the driver-component for the digital outputs of JetMove 215 is now reported as warning number 9 in register 581 bit 9.

3 Corrections

3.1 Time Synchronisation

As of version 2.04R11, the timer being responsible for JetMove would occasionally be initialised by an incorrect reload value. When JetMove was run as a time master at the moment of time synchronisation, it would transmit its synchronisation frames to the time slaves by a slightly incorrect frequency. The time slaves would not be able to adjust to the time master by means of their synchronisation controller. For this reason, synchronous data transmission to the motion slaves would not be possible.

This problem has been solved since version 2.06.

As a workaround, register 508 "PWM-Frequency" can be read out and be written into again. The controller must be switched off during this action.

3.2 Getting Cogged in Blocked Condition

As of version 2.05R5, the controller would occasionally cog at being repeatedly activated and deactivated by means of commands 1 and 2 in deactivated status. This error only occurred after deactivating the automatic control of the motor brake (register 540.0 = 0).

3.3 Step Change of the Modulo after Issuing Command 2

As of version 2.05, after issuing command 2, a modulo step change would occasionally occur, which could - for the brake blockage duration (register 548) - move the axis. This problem has been solved since version 2.06.

3.4 Axis Configuration

Register 180 "Max. acceleration" and register 181 "Max. jerk" now also trigger recalculating of the configuration data, which will be taken over into axis configuration.

3.5 Referencing to Limit Switch via K0

From now on, referencing towards limit switch only via K0 also functions, if K0 is within the switch hysteresis. So far, the message "Error Pos. / Neg. Limit Switch" used to occur in this case.

This problem has been solved since version 2.06.

3.6 Positive Step Change at the End of the Deceleration Ramp

In case of Motion/Move/Point to Point instructions, combined with long travel distances and very low speeds, the setpoint position would occasionally perform a change of step at the end of the deceleration ramp due to faulty table access.

This problem has been solved since version 2.06.

3.7 Modulo Axis

If the first positioning run was started in relation to the actual position, and if set and actual value were in different modulo turns, the modulo axes would run too far after referencing.

This problem has been solved since version 2.06.

3.8 Bugs regarding the Actual Position Value

As of version 2.05, the actual position value displayed in register109 would occasionally be influenced by position capturing. The control accuracy would not be affected, though.

If the respective controller is used as a motion master periodically transmitting its actual position to the motion slaves (R151 BusTxMode = 101), this will effect the running smoothness of the motion slaves.

There is the possibility of a workaround by changing over from actual value coupling to set value coupling (register 151 BusTxMode = 104).

This problem has been solved since version 2.06.

3.9 Software Limit Switch

The software limit switches would not be activated by writing these values into register 114 Pos. Software Limit Switch and register 115 Neg. Software Limit Switch.

This problem has been solved since version 2.06.