Quickstart

Strategies for Commissioning and Optimization

JetMove 600

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Technical changes to improve the performance of the equipment may be made without notice!

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I General

This document provides you with strategies for the commissioning of the digital servo amplifier JetMove 600 and the optimization of its control loops.

These strategies cannot be universally valid. You may have to develop your own strategy, depending the specification of your machine.

However, the sequences that are presented here will help you to understand the basic methodology.

II Parameterization

II.1 Requirements

The manufacturer of the machine must create a hazard analysis for the machine, and is responsible for the machine with regard to functional, mechanical and personnel safety. This applies particularly to the initiation of movements with the aid of commissioning-software functions.

The commissioning of the servo drive with the aid of commissioning-software functions is only permitted in combination with an interlock device according to EN292-1, that operates directly on the drive circuitry.

- The servo amplifier is installed, and all the necessary electrical connections have been made. See Installations Manual, Chapter II.
- The 24V auxiliary supply and the 400V/480V main power supply are switched off.
- A personal computer, with the commissioning software installed, is connected.
- An interlock device according to EN292-1 is connected.
- The controls provide an LOW signal for the ENABLE input of the servo amplifier (Terminal X3/15), i.e. the servo amplifier is disabled.

II.2 Switch on auxiliary supply

<table>
<thead>
<tr>
<th>Switch on the 24V auxiliary supply for the servo amplifier.</th>
</tr>
</thead>
<tbody>
<tr>
<td>LED display : X.XX (firmware version)</td>
</tr>
<tr>
<td>BTB/RTO contact : open</td>
</tr>
<tr>
<td>After about 5 seconds :</td>
</tr>
<tr>
<td>LED display : YY. (amount of current, blinking point for CPU o.k.)</td>
</tr>
<tr>
<td>BTB/RTO contact : closed</td>
</tr>
<tr>
<td>Switch on personal computer</td>
</tr>
<tr>
<td>Start commissioning software</td>
</tr>
<tr>
<td>Click on the interface (COM1: or COM2:) that is used for communication with the servo amplifier.</td>
</tr>
<tr>
<td>The parameter are transmitted to the PC.</td>
</tr>
<tr>
<td>Click on the check box “SW-disable” at bottom right.</td>
</tr>
<tr>
<td>NO ENABLE now stands in the AXIS status field.</td>
</tr>
</tbody>
</table>
II.3 Basic parameterization

The servo amplifier remains disabled and the main power supply is switched off.

Set up basic parameters (address, ballast details, line/mains supply voltage etc.):
- Click on the SETTINGS button above the picture of the motor
- Alter the fields, if necessary
- Click on APPLY and then on OK

Select motor:
- Click on the MOTOR button below the picture of the motor
- Open the motor selection table, by clicking on the arrow in the field
  NUMBER-NAME
- Click on the motor that is connected
- Click on APPLY
- Answer the query about the brake
- Answer the query “Save to EEPROM/Reset” with NO
  (the data are in the RAM and will be permanently saved later)

Select feedback (resolver, encoder):
- Click on the FEEDBACK button
- The values that are displayed correspond to the default data that you have loaded for the motor.
- Alter the fields, if necessary
- Click on APPLY and then on OK

Set up the encoder emulation (ROD, SSI):
- Click on the ENCODER CONNECTOR button
- Select the desired encoder emulation
- Set up the corresponding parameters in the right half of the window
- Click on APPLY and then on OK

Configure the analog inputs/outputs:
- Click on the I/O ANALOG button
- Select the desired SW-FUNCTION
- Set the scaling relative to 10V for the SW input that is used.
- Set up the required output signals for MONITOR1 and MONITOR2
- Click on APPLY and then on OK

Configure the digital inputs/outputs:
- Click on the I/O DIGITAL button
- Assign the required functions to the digital inputs (left half of window) and enter the auxiliary variable X if it is necessary.
- Assign the required functions to the digital outputs (right half of window) and enter the auxiliary variable X if it is necessary.
- Click on APPLY and then on OK

Save parameters:
- Click on the button
- Answer the query RESET AMPLIFIER with YES

Click on the check box “SW-disable” at bottom right.
NO ENABLE now stands in the status field for AXIS
If you want to use the position control of the servo amplifier, then you must enter the specific parameters for your drive:

**Axis type:**
- Click on the **POSITION** button
- Click on the **POSITION DATA** button
- Select the **axis type** (linear or rotary)

**Resolution:**
- Enter the denominator and numerator for the resolution. Here you adjust the path traversed by the load in positioning units (length unit for linear axes, or °mech. for rotary axes) to match the number of turns of the motor.
  
Only integer entries are permitted.

  **Example 1:** Ratio = 3.333 mm / turn
  
  => resolution = 10000/3 µm/turn (all other path entries in µm)
  
  or
  
  => resolution = 10/3 mm/turn (all other path entries in mm)

  **Example 2:** Ratio = 180 °mech./turn
  
  => resolution = 180/1 °mech./turn (all other path entries in °mech)

  **vmax:**
  - Enter the maximum traversing speed for the load that results from the resolution at the rated speed of the motor. The dimensional unit is derived from the resolution (°mech./sec or length units/sec).

  **Example 1:** resolution = 10000/3 µm/turn, n_{nom} = 3000 turns/min
  
  => vmax = resolution * n_{nom} = 10000/3 * 3000 µm/min = 10 000 000 µm/min
  
  or
  
  => vmax = resolution * n_{nom} = 10/3 * 3000 mm/min = 10 000 mm/min

  **Example 2:** resolution = 180 °mech/turn, n_{nom} = 3000 turns/min
  
  => vmax = resolution * n_{nom} = 180 * 3000 °mech/min = 9000 °mech/s

  **t_{acc/dec_min}**:
  - Enter the time in ms that the drive requires, with the **mechanically permissible** maximum acceleration, to accelerate from zero speed to vmax.

  **InPosition**:
  - Enter the window for InPosition. This value is used for the InPosition message. The dimensional unit is derived from the resolution (°mech. or length unit).
    
    Typical value: e.g. approx. resolution * 1/10 turn
  - Click on **APPLY** and then on **OK**
  - Answer the query "Save to EEPROM/Reset" with **NO**
    (the data are in the RAM and will be permanently stored later)

  **max. following error**:
  - You now see the screen page **POSITION**
  - Enter the window for the following error. This value is used for the message **FOLLOWING ERROR**. The dimensional unit is derived from the resolution (°mech. or length unit).
    
    Typical value: e.g. approx. resolution * 1/10 turn

  **Save parameters**:
  - Click on the **button**
  - Answer the query **RESET AMPLIFIER** with **YES**
III Optimization

III.1 Requirements

The basic parameterization described in Chapter II is finished.

III.2 Preparation

| OPMODE          | Set the OPMODE “1,analog speed”               |
| Setp. function  | Set the analog I/O-function to “0,Xsetp=SW1”  |
| Save the parameters |
| - Click on the [button] button |
| - Answer the query RESET AMPLIFIER with YES |
| SW/SETP.1       | Short-circuit the setpoint input 1 or apply 0V to it |
| OSCILLOSCOPE    | Channel1 : n_act Channel2 : I_act            |
| Reversing mode  | Go to the screen page OSCILLOSCOPE/SERVICE/PARAMETER and set the parameters for reversing mode to values that are safe for your machine, also when the positioning control loop is switched off (approx. 10% of the final limit speed). |

During operation of the service function “Reversing mode” the analog setpoint input is switched off and the internal positioning control is disabled.

Make sure that the individual motion of the selected axis is possible without any hazard.
For safety, only operate the ENABLE signal of the amplifier with an interlock switch, and check the EMERGENCY STOP function for this axis.

III.3 Checking the current controller

If a suitable amplifier-motor combination is used, the current controller will already have a stable setting for almost all applications.

Ipeak:
- Reduce Ipeak to the Irated value for the motor (protection of the motor)
Switch on the mains/line power.

Provide the analog setpoint:
- Setpoint1 = 0V

Enable the amplifier:
- High signal at Enable input X3/15. In the AXIS status field: NO SW-EN
- Click on the SW-Enable check box. ENABLE now stands in the AXIS status field.
The motor now stands under speed control, with n=0 rpm. If the current controller is not stable in operation (motor oscillates with a frequency clearly above 100Hz), please contact our applications department.
III.4 Optimizing the speed controller

SETP. OFFSET:
Leave the amplifier enabled. If the axis is drifting, alter the parameter SW-Offset until it stands still (or use the function AUTO-OFFSET).

SETP. RAMP +/-:
The setpoint ramps are used to smooth the setpoint input (filter effect).
Set the mechanical time constant for the complete system, i.e. the rise time for the speed from 0 to \( n_{\text{cmd}} \).
As long as the ramps that are set are shorter than the mechanical response time for the complete system, the response speed will not be affected.

LIMIT SPEED:
Set the desired final limit speed.

KP/Tn:
Increase KP until the motor starts to oscillate (audible, and visible on the oscilloscope) and then reduce KP again until the oscillations have definitely stopped and stability is assured.
Use the motor-specific default value for Tn.

Start reversing mode:
Start the reversing mode (F8, \( \pm 10\% \) of \( n_{\text{nom}} \) for the motor).
Observe the speed response on the oscilloscope. If the settings are correct, there must be a stable step response in both directions.

Diagram: Step response

\[
\begin{align*}
\text{n} &= \text{speed} \\
\text{n}_{\text{cmd}} &= \text{set speed} \\
\text{SW} &= \text{setpoint} \\
\text{t} &= \text{time} \\
1 &= \text{optimum} \\
2 &= \text{KP too high}
\end{align*}
\]

KP:
You can produce a fine tuning of the speed response by cautiously increasing KP.
Aim: the smallest overshoot, but still retaining good damping.
A larger total moment of inertia make it possible to use a larger value for KP.

PID-T2:
You can dampen out disturbances, such as a small amount of play in the gearing, by increasing PID-T2 to about 1/3 the value of Tn.

FEEDBACK:
You can further improve the smooth running by using FEEDBACK, especially for small drives with a low torque.

End reversing mode:
Finish the reversing mode operation (F9).

Set up the correct, motor-specific value for Ipeak (current controller) again. Start up reversing mode again, and observe the step response. If there is any tendency to oscillation, reduce KP slightly.

Save the present parameter set in the EEPROM. Click on the button.
III.5 Optimizing the position controller

Preparation

OPMODE:
Select OPMODE 8

Position the load in a middle position:
The aim is, to use the CONSTANT SPEED function to move the load to approximately
the middle of the motion path.
- Click on the POSITION button
- Click on the SETUP MODE button
- Check that the parameter \(v\) (CONSTANT SPEED) is set to 1/10 of the
  preset speed limit \(v_{\text{max}}\). Alter the value if necessary, and click on APPLY.
- Start the function CONSTANT SPEED by using the function key F4.
  Now use F4 to move the load to approximately the middle of the motion path.

WARNING:
If the drive moves in the wrong direction, release the F4 function key
and alter the sign of the parameter \(v\). Click on APPLY
and use F4 to move the load to approximately the middle of the motion path.

Set reference point:
- Set the homing type to activate “0, set reference point”.
  Start the homing run. The momentary position is set as the reference point.
- Stop the homing run
- Click on the check box “SW-disable” in the amplifier window

Define test motion blocks:
- Click on the POSITION button
- Click on the POSITION DATA button
- Click on the selection list for the motion tasks, and select task 1.
  Enter the values from the table below, then select task 2 and
  enter the corresponding values.

<table>
<thead>
<tr>
<th>units</th>
<th>Task 1</th>
<th>Task 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>type</td>
<td>REL setpoint</td>
<td>REL setpoint</td>
</tr>
<tr>
<td>(s_{\text{cmd}})</td>
<td>+10% of total path</td>
<td>-10% of total path</td>
</tr>
<tr>
<td>(v_{\text{cmd}})</td>
<td>digital</td>
<td>digital</td>
</tr>
<tr>
<td>(v_{\text{cmd}})</td>
<td>10% of (v_{\text{max}})</td>
<td>10% of (v_{\text{max}})</td>
</tr>
<tr>
<td>(t_{\text{acc_tot}})</td>
<td>10 * (t_{\text{acc_dec_min}})</td>
<td>10 * (t_{\text{acc_dec_min}})</td>
</tr>
<tr>
<td>(t_{\text{dec_tot}})</td>
<td>10 * (t_{\text{acc_dec_min}})</td>
<td>10 * (t_{\text{acc_dec_min}})</td>
</tr>
<tr>
<td>ramp</td>
<td>trapeze</td>
<td>trapeze</td>
</tr>
<tr>
<td>next motion task</td>
<td>with</td>
<td>with</td>
</tr>
<tr>
<td>next number</td>
<td>2</td>
<td>1</td>
</tr>
<tr>
<td>acc./dec.</td>
<td>to target position</td>
<td>to target position</td>
</tr>
<tr>
<td>start condition</td>
<td>immediately</td>
<td>immediately</td>
</tr>
<tr>
<td>APPLY/OK</td>
<td>click</td>
<td>click</td>
</tr>
</tbody>
</table>

Save parameters:
- Click on the button
- Answer the query RESET AMPLIFIER with YES
III.5.1 Optimization

The starting of motion tasks with the aid of commissioning-software functions is only permitted in combination with an interlock device according to EN292-1, that operates directly on the drive circuitry.

Start motion task:
- Click on the POSITION button
- Click on the POSITION DATA button
- Click on START, motion task 1 is started and, because of the definition of the motion task sequence, the drive moves in position-controlled reversing operation.

Optimize parameters

- PID-T2, FEEDBACK:
  The speed controller is not used in OPMODES4, 5 and 8. The position controller includes an integral speed controller, that takes on the preset parameters for PID-T2 and FEEDBACK from the screen page "Speed controller".

- KP, Tn:
  If KP is set too low, the position controller tends to oscillate. Use the value for the optimized speed controller for KP. Tn should be 2...3 times as large as the Tn value for the optimized speed controller.

- KV:
  The acceleration behaviour of the motor should be well damped (no tendency to oscillation) with a minimum following error. If KV is larger, the tendency to oscillation increases. If it is smaller the following error increases and the drive becomes too soft. Vary KV until the desired response is achieved.

- FF:
  The integral component of the control loop is in the position controller, not the speed controller, so no following error results at constant speed (pure proportional control). The following error that arises during acceleration is affected by the FF parameter. This error is smaller if the FF parameter is increased. If increasing FF does not produce any improvement, then you can increase KP a little, to make the speed control loop somewhat stiffer.

If the drive does not run satisfactorily under position control, first look for external causes such as:

- mechanical play in the transmission chain (limits the KP)
- jamming or slip-stick effects
- self-resonant frequency of the mechanical system is too low
- poor damping, drive is too weakly dimensioned

before trying to optimize the control loop again.