











# Position Controller PS312P

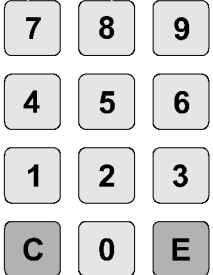












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## INSTRUCTION MANUAL

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<b>1.</b>	<b>Introduction</b>	<b>4</b>
<b>2.</b>	<b>Safety</b>	<b>5</b>
2.1	Personnel Qualifications	5
2.2	Proper use	5
2.3	Safety Notes	5
2.4	Safety Precautions	6
2.5	Warranty and Delivery Terms	6
<b>3.</b>	<b>Technical Data</b>	<b>7</b>
<b>4.</b>	<b>Commissioning</b>	<b>9</b>
4.1	Installation	9
4.2	Connection	9
4.3	Keypad and front panel	16
4.3.1	Displays	16
4.3.2	Key function	16
4.4	Parameter and Function Levels	17
4.4.1	Entering parameters, changing the device functions	17
4.4.2	Parameter functions	19
4.4.3	Parameter list	56
<b>5.</b>	<b>Handling</b>	<b>62</b>
5.1	Display and key functions	62
5.2	Key functions	62
5.2.1	 Quantity input	62
5.2.2	 Special functions	62
5.2.3	 Reference, set datum	62
5.2.4	 Program key	63
5.2.5	 Select keys	63
5.2.6	 Minus key	63
5.2.7	 Function key	63
5.2.8	 Enter key	63

		
5.2.9	Numerical keypad	63
5.2.10	 Start key	64
5.2.11	 Stop	64
5.2.12	 Forward, Retract key (Option)	64
5.2.13	 Lift, Lower key (Option)	64
5.2.14	 E-Stop	64
5.2.15	 Set the EEPROM to default	65
5.2.16	 Erasing the whole program memory	65
5.3	Displays	65
5.3.1	 Actual value display	65
5.3.2	 Demand value display	65
5.3.3	 Special function display	66
5.4	Program mode	67
5.4.1	Editor mode	67
5.4.2	Programming the tool outputs	69
5.4.3	Run mode	70
6.	Error compensation	71
7.	Closed loop adjustment	73
8.	RS232 for PS3xx controllers	73

# 1. Introduction

The one axis position controller PS312P is a complete ready to plug in device including a 42V DC drive for brushed or brushless motors.

Up to 99 programs or over 32000 datasets comprising demand values and quantities can be stored in the unit.

The large, 0.55-inch-wide 7 segment display can be read easily at a distance out of different viewing angles.

The operating guide is available in English and German.

The device with maximum equipage has 12 inputs and 8 driver outputs for various functions.

## 2. Safety

This operating guide contains instructions for ensuring safe and proper installation and operation. If you have any difficulties which cannot be resolved by consulting this guide, please consult the machine manufacturer or vendor for additional information.

Kentucky Gauge is not liable for any personal injury or equipment damage resulting from improper commissioning, incorrect operation, misunderstandings, or errors contained in this guide or on the display.

Kentucky Gauge reserves the right to make technical changes to the equipment or operating guide without prior notice. This means that errors in agreement between the equipment and the guide cannot be precluded.

Pay attention to hazard notices in this operating guide.

This equipment description should be read carefully in full before commissioning.

Use of the operating guide presumes that the user is technically qualified.

### 2.1 Personnel Qualifications

Commissioning, installation, and operation are to be performed only by qualified personnel. The personnel must have qualifications which are appropriate to their function and activity.

- Instruction and obligation to observe all application-related, regional, and in-house regulations and requirements.
- Training in accordance with the standards of safety technology in the use and care of commensurate safety and work protection equipment.
- Courses in first aid, etc.

### 2.2 Proper use

This position controller has been developed solely for use on industrial machinery.

Any further use is considered improper. The manufacturer assumes no liability for damages resulting from such misuse. This risk is assumed solely by the user.

### 2.3 Safety Notes

In the description of the device, the following symbols are used to denote hazards and other important notes:



The **Hazard** symbol warns of errors and hazards in commissioning and operation of the controller. This warning notice signifies a directly threatening hazard to the health of persons and contains special specifications and instructions as well as imperatives and prohibitions to prevent personal injury and damage to equipment.



The **Attention** symbol denotes a possible hazardous situation and contains special specifications and instructions as well as imperatives and prohibitions to prevent personal injury and damage to equipment.



The **Note** symbol indicates important and useful information and provides application tips.

## 2.4 Safety Precautions

The device must be secured in accordance with the relevant regulations.

The device may not be opened or have any of the screws removed from the housing!

The device should be, wherever possible, mounted on a metal plate that is connected to PE.

## 2.5 Warranty and Delivery Terms

We deliver exclusively under the general conditions for the supply of products and services of the electrical and electronics industry.

Kentucky Gauge warrants this product for a period of twenty-four (24) months from the date of shipment.

### 3. Technical Data

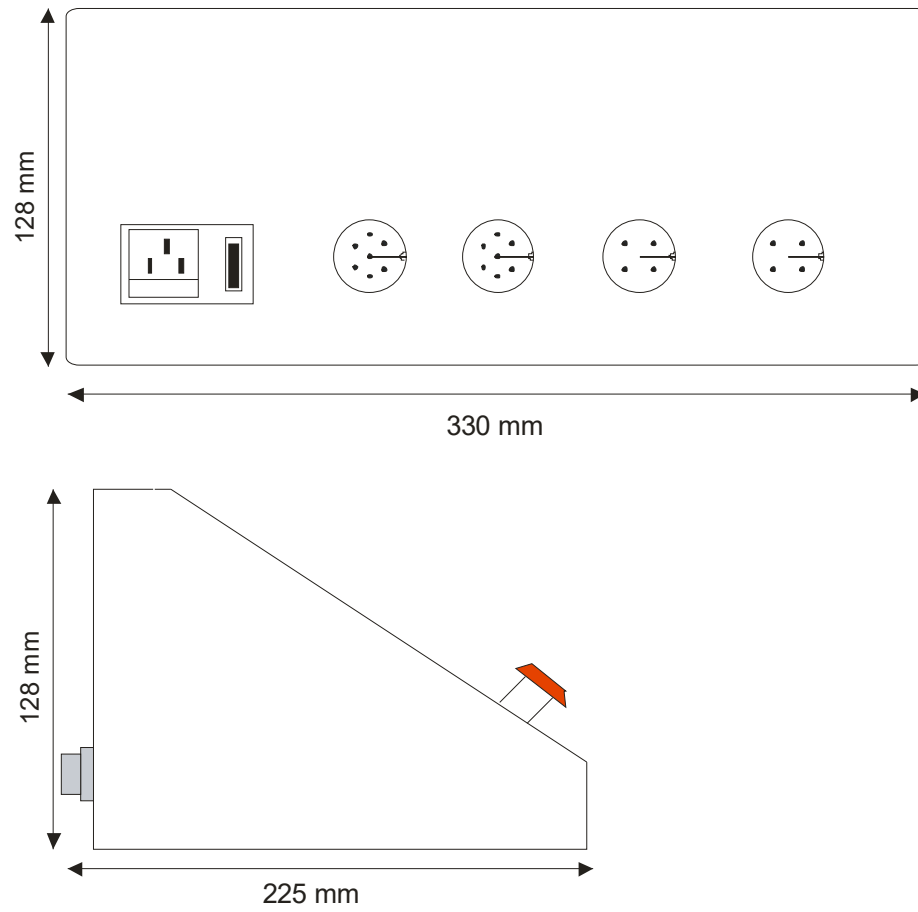


Fig. 1 Dimensions (illustration reduced)

<b>Supply voltage</b>	115V, or 230 V AC $\pm$ 10 %
<b>Current draw</b>	Max. 200 mA without motor current and current consumption of measuring system.
<b>Max. motor current</b>	6 A using the 30V AC standard transformer Optional 8A on demand
<b>Max. motor voltage</b>	42V using a 30V AC transformer 34V using a 24V AC transformer
<b>Display</b>	3 x 7-decade LED display Digit height 14 mm
<b>Input signals</b>	0 – 5 V    low active 10 - 30 V    high active
<b>Encoder</b>	Incremental encoder A, B, Z. 24V DC supply (Max. 100 kHz, four edge counting)
<b>Output Signals</b>	8 output drivers 24V, 700 mA, PNP sourcing
<b>Operating temperature</b>	0 – 40 °C
<b>Storage temperature</b>	-20 - + 65 °C
<b>Relative humidity</b>	max. 90 %
<b>Installation orientation</b>	Any
<b>Enclosure rating</b>	IP 54, frontside
<b>Dimensions</b>	330 x 128 x 225 mm <sup>3</sup> (W x H x D) Installation depth excluding connector



## 4. Commissioning



Most commonly damage to the device is a result of faulty cabling and incorrect parameter values. Therefore, commissioning is to be performed only by trained and expert personnel.

### 4.1 Installation



The device can be mounted on a mounting plate and fixed with two M4 screws.

The screws should not intrude more than 15 mm into the housing.

### 4.2 Connection



The device is operated with 115V or 230V.

With 115V or 230V AC voltage the relevant regulations for contact protection must be observed to prevent personal injury.

Before connecting, compare the part label on the back of the device with the desired connection voltage.



Electrical cables are to be routed in accordance with the respective national regulations. Route measuring, signal, and power cables separately.

We recommend using only shielded cable connected to GND on the device.

Ensure that no ground loops are created.

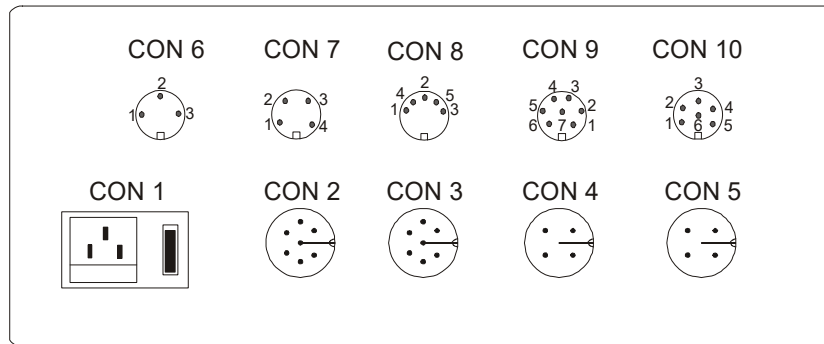


Fig. 2 Wiring diagram

### Connector and pinouts

#### CON1 Supply voltage

Cold-device plug with fuse

- Pin 1 L, 115V, or 230V AC, max. 100 mA (refer to type plate!)
- Pin 2 N, 115V, or 230V AC, max. 100 mA (refer to type plate!)
- Pin 3 Shield

#### CON2 Standard measuring system input (for RS422 signals refer to Con 9)



Connector female 7 pin

- Pin 1 GND
- Pin 2 + 24V encoder supply max. 150 mA
- Pin 3 Signal A
- Pin 4 Signal B
- Pin 5 Signal Z
- Pin 6 N/C
- Pin 7 Shield

### CON3 Quantity-, limit switch inputs



Connector male 7 pin

- |       |   |
|-------|---|
| Pin1  | GND   |
| Pin 2 | + 24V supply for switching inputs max. 50 mA  |
| Pin 3 | Limit switch plus<br>When the limit switch is a normal open, the input must be left open or connected to GND to start the motor.<br>When the limit switch is a normal closed, the input must be connected to 24V, to start the motor.                   |
| Pin 4 | Limit switch minus<br>When the limit switch is a normal open, the input must be left open or connected to GND to start the motor.<br>When the limit switch is a normal closed, the input must be connected to 24V, to start the motor.                  |
| Pin 5 | Quantity- and drive free input<br>When the quantity switch is a normal open, the input must be connected to 24V to start the motor.<br>When the quantity switch is a normal closed, the input must be left open or connected to GND to start the motor. |
| Pin 6 | GND   |
| Pin 7 | Shield  |

### CON4 Brake



Connector male 4 pin

- |       |  |
|-------|--|
| Pin 1 | N/C  |
| Pin 2 | Brake open, closed<br>Output source 24V when positioning is active |
| Pin 3 | GND  |
| Pin 4 | Shield   |

**CON5 Motor**

Connector female 4 pin

Pin 1	Motor +
Pin 2	Motor -
Pin 3	N/C
Pin 4	Shield

**CON6 Outputs 1 (Option)**

Connector female 3 pin

Pin 1	Tool Output 4 (P06/ALL = 0) Pneumatic arm extend (P06/ALL = 1)
Pin 2	Tool Output 8 (P06/ALL = 0) Pneumatic arm retract (P06/ALL = 1)
Pin 3	GND

**CON7 RS232 (Option)**

Connector female 4 pin

Pin 1	Shield
Pin 2	RxD
Pin 3	TxD
Pin 4	GND

**CON7 Internal and external E-Stop (Option)**

Connector female 4 pin

Pin 1	A potential-free switch must be connected between Pin 1 and Pin 4 for external E-Stop function.
Pin 2	Pin 1 of the internal E-Stop switch (NC)
Pin 3	Pin 2 of the internal E-Stop switch (CO)
Pin 4	A potential-free switch must be connected between Pin 1 and Pin 4 for external E-Stop function. (24V DC out)

**CON8 Output 2 (Option)**

Connector female 5 pin

Pin 1	N/C
Pin 2	N/C
Pin 3	GND
Pin 4	Tool Output 1 (P06/ALL = 0) Pneumatic arm lift (P06/ALL = 1)
Pin 5	Tool Output 2 (P06/ALL = 0) Pneumatic arm lower (P06/ALL = 1)

or

**CON8 Measuring system input for RS422 Signals**

Connector female 8 pin (not in combination with brushless motors)

The shield must be connected to the metal housing

Pin 1	GND
Pin 2	+24V or +5V refer to type plate
Pin 3	Signal A
Pin 4	Signal A/
Pin 5	Signal B
Pin 6	Signal B/
Pin 7	Signal Z
Pin 8	Signal Z/

or

### CON8 Rotor position encoder for brushless motors



Connector female 5 pin (not in combination with RS422 measuring systems)

The shield must be connected to the metal housing

- Pin 1 GND
- Pin 2 for rotor position encoder supply 5V or 12V.
- Pin 3 Hall sensor C (Motor phase T)
- Pin 4 Hall sensor B (Motor phase S)
- Pin 5 Hall sensor A (Motor phase R)

### CON9 Inputs (Option)



Connector female 7 pin

- Pin 1 Go to datum switch
- Pin 2 Protection Hood, Offset 2
- Pin 3 +24V
- Pin 4 External E-Stop 1, connect to pin 7 to switch off the E-Stop. (When CON 7 isn't used)
- Pin 5 Offset activation or material sensor
- Pin 6 GND
- Pin 7 External E-Stop 2, connect to pin 4 to switch off the E-Stop. (When CON 7 isn't used)

## CON10 Outputs 3 (Option)



Connector female 6 pin

Pin 1	Position reached Active when demand value = actual value.
Pin 2	N/C
Pin 3	N/C
Pin 4	End of program Active high when program is finished. Active low when program is running.
Pin 5	Quantity reached Active high when quantity is 0. Active low when quantity is not 0.
Pin 6	GND

## 4.3 Keypad and front panel

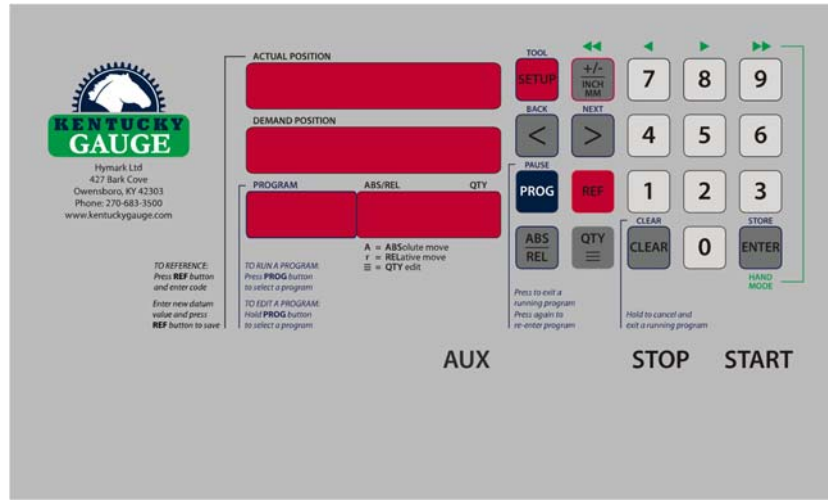


Fig. 3 Front panel

### 4.3.1 Displays

The upper display is used for visualizing the actual position.




The display in the middle is used for visualizing the demand value as well as the parameter number in the parameter levels.

The lower display is used for visualizing the Quantity, position modes and steps in program mode.

### 4.3.2 Key function

1. The keys **0 – 9** are used to change any kind of numerical values.
2. The **ENTER** key opens a parameter level, completes the setting of a parameter value or demand value in the program editor. It is also used to acknowledge any fault and to switch between the automatic and manual adjustment of a motor.
3. The **CLEAR** key sets the input value to zero.
4. The **QTY** key activates and deactivates the quantity setting.
5. The **REF** key opens and closes the datuming level.
6. The **PROG** key opens and closes a program in the run and editor mode.
7. The **<** and **>** keys can be used to switch between parameters in the parameter levels, to select program numbers or to switch between the steps in program mode.



8. The  key can be activated to change the sign of an input value, or to change between inch or mm display.
9. The  key activates or deactivates the parameter levels.
10. The  can be activated to change between absolute and relative position mode.

## 4.4 Parameter and Function Levels

### 4.4.1 Entering parameters, changing the device functions



When changing control and calibration parameters, always consider the effects on the overall system:




The parameters may be protected against unintended changes by using a security code.

This may be selected by the machine manufacturer himself.

The device provides six levels

1. Datuming level
2. User level
3. Parameter level All
4. Parameter level Custom1
5. Parameter level Axis 1
6. Parameter level Special

The  must be pressed to activate or deactivate the parameter levels.



and are used to select a parameter level.





opens a parameter level and stores any parameter changes.









Changes in the parameter setting can result in malfunction, stopping or failure. Changes to the parameter settings should therefore be made only by knowledgeable personnel.

Example:

Changing P 5 parameter level Motor 1 (axis parameter):

1. Press  (Upper display shows dAtuM)
2. Press  4 times. (Upper Display shows Motor 1)

3. Press  (Display in the middle shows P 2)
4. Press  several times until P 5 is shown in the middle.
5. Change the parameter value, using the numerical keys
6. Store the new value by pressing 
7. Quit this parameter level, using  (Upper Display shows Motor 1)
8. Quit all parameter levels by pressing  again.

When the parameter level is locked by a code, then this code must be entered after step 2 and confirmed by pressing  before the parameter can be changed.

## 4.4.2 Parameter functions

The parameters shown in the following are all performed according to the sample



*Parameter number Name [unit, minimum/maximum value) Parameter description.*

Parameters in which P05 is entered as the unit refer to the unit specified in parameter P05 (parameter level Axis 1).

Parameters which are filled with index ro(Read Only) can only be read.

### Parameter level User:

**P00** *Sawblade kerf thickness [P05/ 0,5000]*

The user can enter the width of a saw blade which will be automatically calculated when using incremental positioning.

**P01** *Decrement value when quantity input is activated [quantity/ -20,20]*

The quantity counter is subtracted by the value set in this parameter, when the quantity input is activated.

**P02** *Automatic retract function when quantity input is active [no, function/ 0, 2]*

Setting	Function
0	The automatic retract function is disabled.
1	The automatic retract function is activated.
2	The automatic retract function is activated in single mode only. It is disabled in program mode.

**Parameter level User:**

**P03** *Move up to the first position, when a program is active [function/ 0,2]*

Setting	Function
0	The first position is drive up as programed in the first step.
1	<p>Trim cut with external sensor</p> <p>The first programed step is ignored until the trim cut position is reached.</p> <p>The motor goes to the sensor position, stops for a short moment, calculates the outstanding distance between actual position and trim cut position and moves to the trim cut position.</p> <p>The trim cut position is the dedicated sensor position, plus the sensor position in parameter P04.</p> <p>When this setting is used, the first step must always be programed as a relative distance.</p>
2	<p>Good part with external sensor, without trim cut</p> <p>The motor goes to the sensor position, stops for a short moment, calculates the outstanding distance between actual position and the position programed in the first step and moves to that position.</p> <p>The position is the dedicated sensor position, plus the sensor position in parameter P04 and the value programed in the first step.</p> <p>When this setting is used, the first step must always be programed as a relative distance.</p>

**Parameter level User:**

**P04** *Distance between photo eye and saw blade [P05/ 0,100000]*

The distance between the photo eye sensor and the sawblade is set here. When the first cut should be a trim cut, add the length of the cut out to the distance.

**P05** *Gauge speed from material sensor to first cut position [%/ 0,100]*

The gauge speed between the material sensor and the first cutting position can be set here.

**P80** *Initialize the Bluetooth interface [no, yes / 0,1]*

When the device has an optional Bluetooth interface, this parameter is used to scan the surrounding for other Bluetooth devices.

**P90** *LAN address setting MSB [Address / 0,255.255]*

Set the most significant bytes of the LAN address here in case a direct setting of the LAN interface is not possible.

**P91** *LAN address setting LSB [Address / 0,255.255]*

Set the least significant bytes of the LAN address here in case a direct setting of the LAN interface is not possible.

**P92** *LAN subnet mask [Mask / 0,4]*

Setting	Subnet mask
0	255.255.255.0
1	255.255.240.0
2	255.255.0.0
3	255.0.0.0
4	Restore factory setting

**Parameters P90 to P92 are read once from the LAN box after power up. Therefore, changes on these parameters take effect only after power up.**

**Parameter level All:**

**P02** *Software version [read only/-----,-----]*

Number of the software currently in use in the device.

**P03** *Language for text messages [language/0,1]*

Setting	Language
0	German
1	English

**P06** *Operation Mode [ 0/1]*

Setting	Machine type
0	Tool Output Active via CON6, Pin 1+2 CON8, Pin 4+5
1	Pneumatic retract and pneumatic lift/lower Via CON6 + CON8

**P07** *CN number for special devices [ro/-----,-----]*

**P08** *Customer number for special devices [ro/-----,-----]*

**P21** *Security code for parameter level [7-decade number/ 0, 9999999]*

The parameters may be protected against unintended changes by using a security code.

Data can only be entered in the parameter level All and Motor1 and Special after entering this code.

## Parameter All:

**P22** *Security Code for calibrate level [7-decade number/ 0, 9999999]*

By entering a security code, the device can be protected from calibration.

Calibration to a new value is only possible after entering this code.

**P23** *Code for parameter level customer [7-decade number/ 0, 9999999]*

The parameters in the parameter level Custom1 can be protected against unintended changes by using a security code.

Data can only be entered in the parameter level Custom 1 after entering this code.

**P60** *Maximal number of programs [max. Programs/ 3, 99]*

The user can determine how many programs will be required in the future by means of this parameter.

The device can store over 32000 steps.

These steps are divided among the number of programs.

The maximal number of steps per program is 999.

Maximal Length = available steps/number of programs.

When this parameter is set to a value smaller than 33, a part of the memory will not be used.

Changes carried out to the parameter setting after some programs



have already been stored, causes a displacement in the existing programs.

This may lead to the loss of stored programs.



## Parameter level All:

### **P61** Program sequence mode [Sequence/ 0, 15]

Setting	Function
0	First address line always absolute position even if the device is equipped with an incremental function.
1	First address line as entered.
2	When the program cannot be finished with one workpiece, the motor goes to a park position where a new workpiece can be loaded. For example, when a tube is too short to cut out all programmed parts.
3	Combination of 1 and 2
4	The keys   on the keyboard are activated when a program is running, to switch between the steps.
5	Combination of 1 and 4
6	Combination of 2 and 4
7	Combination of 1,2 and 4
8	Automatic program restart when the last address line is reached.
9 -15	Combination of the former functions.



## Parameter level All:

### **P70** Switching input logic 1 [binary code/ 0,255]

In engineering both normally open and normally closed devices are used as electrical switches.

To adapt the device quickly to suit any hardware, the switching behavior of the inputs can be determined using this parameter.

The input is connected with a NO contact by pressing 1, and it is connected with a NC contact by pressing 0.

Up to 256 various combinations are possible with the first 8 inputs.

The following table gives a more detailed description of the procedure.

Input	0	1	2	3	4	5	6	7
Switch	O/S	O/S	O/S	O/S	S	S	O/S	O/S
Binary value	1/0	1/0	1/0	1/0	0	0	1/0	1/0
Decimal value	1	2	4	8	16	32	64	128

S = NO normal open (Binary value 0)

O = NC normal closed (Binary value 1)

### Parameter level All:

The following inputs are used in this software

Input 0 = not used – BCD Code 1

Input 1 = Protective hood – BCD Code 2

Input 2 = Datuming switch – BCD Code 4

Input 3 = Quantity input – BCD Code 8

Input 4 = not used – BCD Code 16

Input 5 = not used – BCD Code 32

Input 6 = Limit switch min. – BCD Code 64

Input 7 = Limit switch max. – BCD Code 128

To calculate parameter value to be entered, determine if input 1 to 8 is needed as NO or NC. Then multiply the binary value with the decimal value for each input and add up the results of each input.

Example: Input 0, 1, 2, 4, 5, 6, 7 = NO.

Input	NC / NO	Binary	Decimal	Binary x Decimal	
0	NO	0	1	0	+
1	NO	0	2	0	+
2	NO	0	4	0	+
3	NC	1	8	8	+
4	NO	0	16	0	+
5	NO	0	32	0	+
6	NO	0	64	0	+
7	NO	0	128	0	=
			Total	8	

Enter "8" in parameter All/P70 to get required input configuration

**Parameter level All:**

**P71** Switching input logic 2 [binary code/ 0,15]

Switching input logic of internal components is in accordance with the P70 parameter, but only for 4 inputs.

The following inputs are used in this software.

Input 0 = Not used– BCD Code1

Input 1 = Not used – BCD Code 2

Input 2 = Not used – BCD Code 4

Input 3 = Material detection sensor – BCD Code 8

**Parameter level All:**

**P74** *Switching output logic 1 [binary code/ 0,255]*

The switching characteristic of the outputs 1 – 8 can be inverted with This parameter.

Example:

The following table gives a more detailed description of the procedure.

Output	0	1	2	3	4	5	6	7
Function	S	I	S	S	S	I	S	S
Binary value	0	1	0	0	0	1	0	0
Decimal value	1	2	4	8	16	32	64	128

S = Standard (Binary value 0)

I = Inverted (Binary value 1)

The following outputs are used in this software.

Output 0 = Brake – BCD Code 1

Output 1 = Arm lift, or auxiliary output 1 – BCD Code 2

Output 2 = Arm lower or auxiliary output 2 – BCD Code 4

Output 3 = Arm forward or auxiliary output 3 – BCD Code 8

Output 4 = Arm backward or auxiliary output 4 – BCD Code 16

Output 5 = Position reached– BCD Code 32

Output 6 = Program finished – BCD Code 64

Output 7 = Quantity reached – BCD Code 128

To calculate parameter value to be entered, determine if output 1 to 8 is needed as a standard or inverted.

Then multiply the binary value with the decimal value for each input and add up the results of each output.

**Parameter All:**

In our example on the last side, the parameter must be set to 34 when the outputs 1 and 5 should switch inverted.

**P81** *Baud rate for serial communication [Baud/ 4800/256000]*

When the device has a serial interface the baud rate for serial communication must be set here.

Setting	Baud rate
0	4800
1	9600
2	19200
3	38400
4	56000
5	115200
6	256000

**P82** *Device address for serial communication [Address/11,99]*

The following addresses are not allowed in this protocol.

All addresses smaller than 11 and addresses with whole tenner decades as 20,30,40....

These are used as group addresses.

**Parameter level All:**

**P96**     *Temperature offset [°C/ -20/+20]*

This parameter is used to compensate a temperature offset of the temperature sensor in the drive.

**P97**     *Shut down temperature of the drive [°C/ 0/95]*

The motor drive will be switched of, when it reaches the temperature set here to prevent it from overheating.

### Parameter level Motor 1:

Some of the parameters listed here can be found in the parameter level Custom 1 too. These parameters can be changed in either level.

These parameters are marked with “**Custom**”.

**P02** *Datum value [P05/ -999999,999999] **Custom***

Value first shown when a unit should be datumed, manually or the value the motor position is set when the go to datum routine is active.

**P03** *Software limit switch min. [P05/ -999999, 999999] **Custom***

The minimum input value, the device should accept as a demand value.

**P04** *Software limit switch max. [P05/ -999999, 999999] **Custom***

The maximum input value, the device should accept as a demand value.

**P05** *Distance for multiplication [any desired length unit/ 1, 10000]*

**Custom**

Contains any desired distance.

These two parameters are needed so that the counter can be set to various mechanical conditions, such as drives, spindle stroke, etc.

1. Any desired distance in the desired unit and resolution

(P05).

2. The number of increments sent by the encoder to the unit when travelling the distance in P05. (P06).

Only if these specifications are entered in P05 and P06 with no rounding error, will the counter operate correctly over the entire range.

Therefore, the distance selected should always be one where a whole number of pulses is sent by the encoder.

**P06** *Pulse/ distance [encoder resolution/1, 100000]*

**Custom**

Number of pulses per travel distance entered in P05 (the factor is automatically calculated from P05 and P06).

## Parameter level Motor 1:

- P07** *Maximum permanent motor current [x.xx Ampere/ 0.01, 20.00]*
- When the motor current exceeds the current set here for more than one second the motor will be stopped, and an error message appears on the display.
- The measured current may differ in a range of  $\pm 10\%$  of the real current.
- P08** *Number of automatic restarts [piece / 0, 10]*
- If the actual value lies outside the demand value +/- tolerance window when positioning has been completed, then positioning to the same demand value will be restarted. This process is repeated until the actual value lies within the tolerance window, but not more often than the value entered here.
- P09** *Tolerance window [P05/ 0, 250]*
- If the actual value is in the demand value  $\pm$  tolerance window range after positioning, then the demand value is displayed instead of the real actual value (P00 = P01).
- P10** *Brake activation delay time when position reached or stop*  
*[x.xx sec/ 0.00, 10.00]*
- To avoid the motor overheating unnecessarily when positioning has been completed, the drive free signal is switched off after the time entered here.
- If the time selected is too short, the motor may not dwell at the target point but continue beyond it due to inertia.

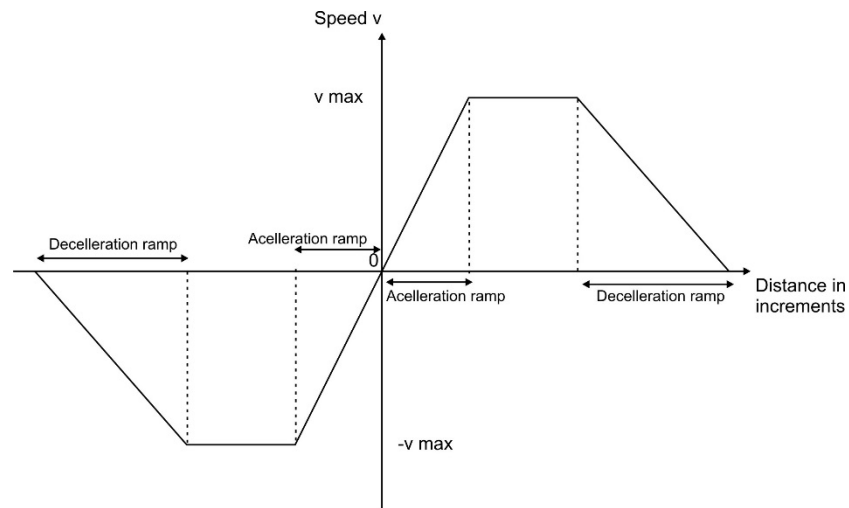


## Parameter level Motor 1:

### P11 *Maximum ramp distance for acceleration ramp [encoder pulses / 1, 250000] Custom*

This parameter determines the number of ramp steps the controller passes over in its complete range.

The negative and positive positioning process is presented in the following graph.



The ramp length determines how rapidly the controller should reach its maximum speed.

High values lead to long and low values lead to short ramp distances.

## Parameter level Motor 1:

**P12** *Maximum ramp distance for deceleration ramp*

*[encoder pulses / 1, 250000] Custom*

See P11 for more detailed information.

This parameter is used for the deceleration ramp.

If the ramp length is too short, it can cause the target to be overshoot, whereas if the ramp length is too long, it can lead to a long positioning time.

**P13** *Fast speed forwards and backwards [Percent 1, 100]*

1% ... 100%: percent of the maximum speed of automatic positioning and rapid manual operation.

**P14** *Manual slow speed [Percent / 1, 100]*

1% ... 100%: percent of the maximum speed of automatic positioning or rapid manual operation.

**P15** *Deceleration ramp after stop command [x.xx sec/ 1, 2000]*

The time interval the motor requires to reach standstill after a stop command.

**P17** *Backlash compensation time [x.xx sec/ 0, 10.00]*

The time during which the motor pauses at the loop reversal point before moving towards the target.

If P17 is set to 0, the backlash compensation function is deactivated.

## Parameter level Motor 1:

**P18** *Backlash compensation distance [P05/-10000,10000]*

Exceed demand values on this distance during backlash compensation.

The backlash compensation is driven to lower demand values when in the negative range, to higher demand values when in the positive range.

**P19** *Integral term [controller intervention all / 1, 9999]*

The integral term of the regulating algorithms determines, how often the I term should intervene in the closed loop control.

1 is equivalent with the time entered in P 22, 2 is equivalent with 2 x P22 etc.

1 = Max. gain (the controller intervenes in the positioning of all in the P22 set time field) The consequence is rapid start and sharp braking depending on the time set.

...

9999 = Min. reinforcement (the controller intervenes in the positioning of all 9999 in the P22 set time field.) The consequence is slow start and gentle braking depending on the time set.

**P20** *Integral term 2 [controller intervention all / 1, 9999]*

See parameter P19, however only for restarting if specified in P08

**P21** *Differential term for brake ramp [%/ 0, 100]*

The differential term only intervenes before the target during the declining ramp if the motor decelerates too much or comes to a standstill.

Setting = 0 deactivates the D term.

Setting = 100 sets the D term to its maximum

## Parameter level Motor 1:

**P22** *Feedback monitoring interval [sec/ 0.0001, 5.0000]*

### **Custom**

Measurement period during which the internal demand values and actual values of the controller must agree before it intervenes.

**P23** *Feedback acceleration ramp pulse no. [pulse/ 0, 200]*

The controller has a superimposed closed loop control to monitor stopping. During the period P22 the encoder must send the pulse value written in P23 to the controller.

If this does not occur, the controller identifies this as a stop and the superimposed control is activated.

A higher value leads to an early closed loop intervention

**P24** *Feedback deceleration ramp pulse no. [pulse/ 0, 200]*

The controller has a superimposed closed loop control to monitor

Stopping. During the period P22 the encoder must send the pulse value written in P24 to the controller.

If this does not occur, the controller identifies this as a stop and the superimposed control is activated.

A higher value leads to an early closed loop intervention

**P25** *Edge counting mode [Edge evaluation/ 4, 4]*

This must be set to 4 always.

### Parameter level Motor 1:

**P26** *Counting direction [direction/ 0, 1]* **Custom**

Altering this value from 0 to 1, or vice versa, reverses the counting direction of the unit.

0 = forwards

1 = backwards

**P28** *Incremental move mode [Modes/ 0, 3]*

Different applications require different incremental functions.

1. The incremental value is added or subtracted to the actual or demand value.
2. The set increment is always added to or subtracted from the current actual value (actual value mode), or after the first positioning, added to or subtracted from the demand value (demand value mode)

The various settings can be found in the table below.

Setting	Incremental Mode
0	Actual Mode. This is normally used for saws, where former occurred inaccuracies cannot be compensated.
1	Demand Mode. This is normally used for punches, where former occurred inaccuracies should be compensated.
2	Actual Mode. The demand value will be automatically set to minus.
3	Demand Mode. The demand value will be automatically set to minus.

## Parameter level Motor 1:

### **P29** *Retract distance [P05/ 0, 100000]*

The device can be applied for longitudinal stop with motor-driven and pneumatic retraction.

The distance the longitudinal stop moves with the motor-driven retraction can be entered here.

If 0 is entered in this parameter, the motor-driven retract function is deactivated.

### **P30** *P-term at the end of the ramp [sec/0.00, 1000.00]*

In some cases, this parameter can be helpful to reach the target quicker. Therefore, the controller multiplies the difference to the target with the factor set here and add this to the level of the drive.

### **P31** *Timer encoder monitoring [sec/0, 5.000]*

During the time set in this parameter, the controller must get two pulses from the connected measuring system.

Otherwise the controller stops the motor and shows an error message.

When this parameter is set to 0, the encoder monitoring is switched off.

### **P32** *Operating threshold for encoder monitoring (% / 0, 100)*

In some applications the connected motor must move very slowly to its target position.

Then the encoder frequency could fall below the frequency set in P31 and would cause an error message.

Setting the operating threshold in % of the maximum ramp value will prevent the system from faulty error messages.

Only when this threshold is exceeded, the encoder monitoring is active.

## Parameter level Motor 1:

### **P33** *Automatic start function (Function / 0, 3)*

To support an automatic operation of a machine, the quantity input can trigger an automatic start. The condition for an automatic start can be set in this parameter.

Setting	Function
0	The automatic start is switched off.
1	The automatic start is enabled in program mode only.
2	The automatic start is enabled in single mode only.
3	The automatic start is enabled in single and automatic mode.

### **P36** *Closed loop controller [Mode/0, 1]*

The controller has an integrated position control to ensure the motor stays at the defined point.

Setting	Function
0	Position control deactivated.
1	Position control activated.

Position control may only be used in machines which constitute no direct hazard to people or machines due to the continually active closed loop feature. This works constantly against mechanical influences such as pressure and tension.



Please note: the motor may overheat due to constant closed loop activity. In certain circumstances, this may lead to faster deterioration or even motor failure.

## Parameter level Motor 1:

**P37** *Closed loop gain factor (Gain factor / 0, 10.0000)*

The closed loop controller time is now constant.

This parameter set the force of the integral term of the controller.

A setting of 1.000 means, that an increment difference of the measuring system is sent 1:1 to the analog output of the unit.

**P38** *Closed loop window (increments / 0, 1000)*

After positioning if the actual value does not correspond to the demand value  $\pm$  position window in encoder increments, then the closed loop controller is activated automatically.

Within this position window the closed loop control is deactivated.

**P39** *Closed loop mode (mode / 0, 3)*

The closed loop controller can function in four different modes.

Setting	Mode
0	The closed loop controller is only activated when positioning is complete. (Closed loop to demand values only).
1	The closed loop controller sets to actual value after switch-on or stop, but when positioning is complete, to the demand value.
2	The closed loop function is active until the time in P10 (Axis1) is reached and the axis is inside the closed loop window.
3	Same as mode 0, but the drive free output is only deactivated after stop.

In this mode, if the stop key is repeatedly pressed, the closed loop controller is deactivated.



## Parameter level Motor 1:

**P40** *Closed loop P- term (amplification/ 0, 50000)*

The closed loop controller proportional term can be set in this parameter.

The value entered here is multiplied by the difference between the demand value and actual value (in encoder increments) and used as ramp increments.

This means that when there are long ramp lengths in P 11 Ach1, a higher value can be set. For shorter ramp lengths a lower value must be set to prevent oscillation.

This value should not be greater than 1% of the ramp length entered in P12 axis1 when running the first trials.

If no oscillation occurs, the value can be increased.

**P42** *Motor rotation direction (forwards, backwards / 0, 1)*

This parameter inverts the actual direction of the motor rotation.

If the motor is rotating in the wrong direction, this parameter must be altered or the cables connecting the motor must be changed.

**P44** *Go to datum enabled (disabled, enabled / 0, 1)*

This parameter enables the automatic go to datum routines in the software. Only set the parameter to 1, when the machine is equipped for automatic datuming!



**P45** *Go to datum speed (% / 0, 100)*

When the motor moves to the go to datum or limit switch this speed is used.

## Parameter level Motor 1:

### **P46** Go to datum mode (mode / 0, 7)

Depending on the machine equipment the Go to datum process can be done in different modes.

Setting	Mode
0	The motor moves in positive direction, until it reaches the reference cam, connected to Con 9. The motor stops and changes direction to the negative limit, using the speed stored in P14 axis 1. When the index signal of the measuring system is reached, the actual value is set to P02 in axis 1.
1	The motor moves in negative direction, until it reaches the reference cam, connected to Con 9. The motor stops and changes direction to the positive limit, using the speed stored in P14 axis 1. When the index signal of the measuring system is reached, the actual value is set to P02 in axis 1.
2	Same as mode 0, But the positive limit switch is used instead of the reference cam.
3	Same as mode 1, But the negative limit switch is used instead of the reference cam.
4	Same as mode 0, but without index signal. The actual value is set to P02 when the switch is left.
5	Same as mode 1, but without index signal. The actual value is set to P02 when the switch is left.
6	Same as mode 2, but without index signal. The actual value is set to P02 when the switch is left.
7	Same as mode 3, but without index signal. The actual value is set to P02 when the switch is left.

## Parameter level Motor 1:

**P47** *Parking position after “go-to-datum” routine [P05/ / -999999, 999999]*

After the “go-to-datum” routine, the positioning unit repositions to the parking position entered in this parameter.

If the motor should stop after the “go-to-datum” routine, then the calibration value + offset should be entered here.

**P48** *Go-to-datum offset (P05 / -999999, 999999]*

If the index pulse is reached during “go-to-datum”, after the reference cam is left, the new actual value is calculated from actual

value = calibration value + Offset

**P50** *Brake release delay time [seconds/ 0.01, 10.00]*

If the motor is held in position by a mechanical brake during still-stand, then, when repositioning takes place, it must be opened with respect to the break time needed to open this break before the motor can be repositioned.

The time can be entered in this parameter.

**P51** *Motor direction for manual mode [standard, inverted/ 0, 1]*

### **Custom**

The motor positioning direction can be reversed by using the manual key.

This is useful if the arrow key, which points to the left, would otherwise position to the right from the user's point of view.

## Parameter level Motor 1:

### **P58** *Error compensation step width [P05/ 0,60000] Custom*

The error compensation can be used to compensate differences between displayed and mechanical positions.

The step width of the measuring points can be set here.

For more information about the error compensation refer to the corresponding chapter at the end of this manual.

### **P59** *Error compensation mode [mode/ 0,2] Custom*

Setting	Function
0	The error compensation is disabled.
1	The editor for the error compensation values is activated.
2	The error compensation is running. The displayed values are calculated out of the stored compensation table.

For more information about the error compensation refer to the corresponding chapter at the end of this manual.

### **P70** *Deadman zone negative direction [P05/ -99999,9999999]*

For security reasons, some applications need a deadman zone.

When this parameter is set to a value not equal to 0, the operator must keep the start button pressed from the value set here, to the minimum software limit, when the motor moves in negative direction.

This function is monitored by software only. To reach a higher performance level, additional hardware must be added.

## Parameter level Motor 1:

**P71** *Deadman zone positive direction [P05/ -99999,9999999]*

For security reasons, some applications need a deadman zone.

When this parameter is set to a value not equal to 0, the operator must keep the start button pressed from the value set here, to the maximum software limit, when the motor moves in positive direction.

This function is monitored by software only. To reach a higher performance level, additional hardware must be added.

**P86** *Distance reference switch to zero pulse (cam index)  
of the encoder [read only increments)/ -----,----- ]*

When auto datuming is used this parameter shows the difference in increments between the reference switch and the first zero pulse of the encoder.

This parameter facilitates the adjustment of a rotary pulse encoder with index pulse.

Set this difference to be as large as possible so that the controller can always evaluate the same index pulse.

**P90** *Decimal place [Decimal place 0, 5]*

This parameter is used to set the decimal place within the display.

0 = turn off decimal point





1 = one decimal place etc.

Setting the decimal place has no effect on the display resolution.

This is only done using parameters P05 and P06 in Ach1.

### Parameter level Special:

**P01** Offset mode [mode / 0,4]

Setting	Mode
0	The offset mode for actual value is disabled.
1	<p>Offset mode using the   keys.</p> <p>When the  key is pressed the value set in P02 is subtracted from the actual value shown in the display.</p> <p>The offset symbol „ -„ is shown in the display on the lower left to show that the offset is activated.</p> <p>When the  key is pressed, and the offset is active, the value set in P02 is added to the actual value shown in the display.</p> <p>The offset symbol is switched off.</p> <p>Note: The offset symbol is only shown in single mode, because in program mode the window is used for other purposes.</p>
2	<p>Offset mode using an external switch.</p> <p><b>This function is only active, when P03 in level Special is set to 0.</b></p> <p>When using this function, the device must be connected to a switch that is activated by a hardware added to the machine.</p>
3	<p>Same as mode 1, but the offset value will also be subtracted from the lower limit switch.</p> <p>Then it can be possible to get closer to a tool, saw blade, when a lengthening is added.</p>
4	<p>Same as mode 2, but the offset value will also be subtracted from the lower limit switch.</p> <p>Then it can be possible to get closer to a tool, saw blade, when a lengthening is added.</p>

**Parameter level Special:**

**P02**    *Offset value [P05/ -999999,9999999]*

The value of the offset is set here.

**P03**    *Offset value 2 [P05/ -999999,9999999]*

The value of the offset activated by the protection hood input (Con 9, Pin 2) is set here.

**P04**    *Delay time for auto retract function [sec/ 0.00,50.00]*

The auto retract function can be delayed for a time entered here.

**P05**    *Program key "P" lock [off, on/ 0, 1]*

Setting	Function
0	The program Key is unlocked
1	The program key is locked

**P06**    *Datuming mode [mode/ 0, 1]*

Setting	Function
0	The actual value is set by pressing the E key.
1	The actual value is set by pressing the R key.

### Parameter level Special:

**P31** *Protection hood input function [Function/ 0,2]*

Setting	Function
0	The input is used to connect a protection hood. When active, Stop is shown in the display.
1	The input is used to activate the offset value2. This is added to the actual value.
2	The offset value 2 is added to the negative software limit. This makes it possible to change the limit variable.

**P32** *Enhanced E-Stop function [Function/ 0,1]*

Setting	Function
0	An active E-Stop signal stops the motor only and prevents a new start.
1	An active E-Stop signal stops the motor, prevents a new start and disables all switching outputs.

**P36** *Start delay in program mode [Seconds/ 0.00,60.00]*

When a connected peripheral needs some delay time in program mode, a next automatic start can be delayed here.



### Parameter level Special:

**P46** *Meaning of value in P47 [Meaning/ 0, 1]*

When the park position should be used in a program, the meaning of parameter P47 can be set here.

Setting	Meaning of P47
0	The value set in P47 is an offset for the park position.  The park position is calculated as:  Park position = Trim cut position + Offset (P47)
1	P47 is the absolute value of the park position.

**P47** *Park position [P05/ -999999,9999999]*

Set the value for the park position here.

**P48** *ABS/REL key locked in program mode [off, on/ 0, 1]*

To avoid incorrect entries while a program is edit, the F1 key can be disabled in all steps except the first one.

Setting	Function
0	F1 key always active
1	F1 key locked

### Parameter level Special:

**P65** *Position reached signal at trim cut, or good part position [P05/ -999999,9999999]*

For some applications it is not allowed to start a tool automatically in trim cut mode or a good part position.

In this software version this parameter is activated for all device types, even when the trim cut or good part function is deactivated.

Setting	Function
0	The tool must be started manually in trim cut, or good part position.
1	The position reached output is activated at any position. No manual tool start is needed.

**P67** *Switching forward/backward and lift/lower keys [no, yes. /0,1]*

The function of the forward/backward and lift/lower keys will be switched when this parameter is set to 1.

**P68** *Dwell time for program end output [Sec./0.00, 100.00]*

When this parameter is set to 0.00 the output is static. Otherwise it is switched on for the time set here.

## Parameter level Special:

### **P69** *Parameter base for the inch/mm key [base/ 0, 1]*

When the inch/mm key is pressed, several parameters in the different parameter levels will be changed from inch to mm or vice versa.

When the user opens a parameter level, the parameters should be shown in the unit of length programmed the first time.

Therefore, the controller must know the unit of length.

When all the parameters are set in inch, this parameter must be set to "inch".

Setting	Length unit
0	The parameters are stored in mm
1	The parameters are stored in inch

### **P70** Function of the key [Function/0, 2]

Setting	Function
0	Out of the parameter levels, the key is switched off.
1	The key changes the sign of the demand value.
2	The key changes the length unit from mm to inch or vice versa.

### **P71** Function of the key [Function/0, 1]

Setting	Function
0	The key is switched off.
1	The position mode is switched from absolute to relative or vice versa.

## Parameter level Special:

### **P72** *Enable the position reached output [Function/0, 5]*

Setting	Function
0	<p>The position reached output is disabled in manual mode.</p> <p>In program mode, the position reached output is active high, when the demand value = actual value.</p>
1	<p>Also, in manual mode, the position reached output is active high, when the demand value = actual value.</p>
2	<p>The position reached output is disabled in manual mode.</p> <p>In program mode, the position reached output is active high, when the demand value = actual value, if the quantity input is opened.</p> <p>P73 must be set to 0, when using this function.</p>
3	<p>Also, in manual mode, the position reached output is active high, when the demand value = actual value, if the quantity input is opened.</p> <p>P73 must be set to 0, when using this function.</p>
4	<p>The position reached output is disabled in manual mode.</p> <p>In program mode, the position reached output triggers the quantity input. The dwell time P73 must be set to a value not equal 0.</p>
5	<p>Also, in manual mode, the position reached output triggers the quantity input. The dwell time P73 must be set to a value not equal 0.</p>

**Parameter level Special:**

**P73** *Dwell time for position reached output [Sec./0.00, 100.00]*

When this parameter is set to 0.00 the output is static. Otherwise it is switched on for the time set here.

**P74** *Quantity auto decrement function, of a pneumatic length stop*

Setting	Function
0	The function is disabled.
1	When the pneumatic length stop moves to its home position after a pneumatic retract, depending on the setting, the quantity is decremented, or incremented.

**P75** *Retract function [Function. /0, 1]*

Setting	Function
0	The motor is used for the retract function.
1	A pneumatic arm is used for the retract function.

**P76** *Dwell time for pneumatic retract output [Sec./0.00, 10.00]*

The dwell time for the pneumatic forward and retract output can be set here. When this parameter is set to 0.00, the outputs are static.

**P77** *Dwell time for pneumatic lift lower function [Sec./0.00, 10.00]*

The dwell time for the pneumatic lift and lower output can be set here. When this parameter is set to 0.00, the outputs are static.

**Parameter level Special:**

**P78** *Lift and lower operation [operation. /0, 3]*

Setting	Operation
0	The lift and lower function are activated by a single operation of the key.
1	The lift and lower functions work in dead man mode.  The arm moves only if the key is pressed.
2	The motor can move from the maximum limit switch, to the value set in P79 while the arm is in upper position.
3	Combination of functions 1 and 2.

**P79** *Minimal software limit switch with arm in upper position [P05. /-999999, 999999]*

Insert the minimal position, where the motor can move with the arm in upper position here. When it is not allowed to move the motor when the arm is in upper position, this value must be set  $\geq$  the maximum software limit switch.

**Parameter level Special:**

**P80** Setting of Bluetooth interface [*Setting./0, 1*]

Setting	Function
0	The optional Bluetooth interface is missing.
1	The optional Bluetooth interface is assembled.

**P81** Scanner mode [*Mode./0, 3*]

Setting	Function
0	Only the demand value is sent by the scanner.
1	The demand value and quantity are sent by the scanner.
2	The decimal point is sent with the demand value.
3	The quantity and decimal point are sent with the demand value.

**Parameter level Factory:**

For staff off Kentucky Gauge only.

### 4.4.3 Parameter list



For service purpose it could be helpful to document the parameter setting of the device before the machine is shipped.

Therefore, the following table can be used.

Parameter	Default	User Settings
<b>Parameter User</b>		
P00 Sawblade thickness	0.000	0.000
P01 Decrement value when quantity input is activated	1	1
P02 Automatic retract function when quantity input is active	0	0
P03 Move up to first position when a program is active	0	0
P04 Distance between sensor and saw blade	0.000	0.000
P05 Gauge speed from material sensor to the first cutting position	0-100	100
P80 Initialize the Bluetooth interface	0	0
P90 LAN address setting MSB	192168	192168
P91 LAN address setting LSB	1180	1180
P92 LAN subnet mask	0	0
<b>Parameter All</b>		
P02 Software version	Read Only	66
P03 Language for text messages	0 = German 1 = English	1
P06 Operation Mode	0 = Tool Outputs 1 = Lift Arm	0
P07 CN number for special devices	0	0



P08 Customer number for special devices	0	0
P21 Security code for parameter level	0	0
P22 Security code for calibrate level	0	0
P23 Security code for parameter level cutomer	0	0
P60 Maximal number of programs	99	99
P61 Program sequence mode	Setting 0 First address line always absolute 1 First address line as entered. 2 Program goes to Park Position. 3 Combined 1 + 2 4 < and > buttons enabled in a program 5 Combined 1 + 4 6 Combined 2 + 4 7 Combined 1+2+4 8 Automatic program restart. 9 -15 Combination of former functions.	1
P70 Switching input logic 1	0 (QTY=NC) 8 (QTY=NO)	0
P71 Switching input logic 2	0	0
P74 Switching output logic 1	0	0
P81 Baud rate for serial communication	0=4800 1=9600 2=19200 3=38400	1
P82 Serial Address	11	11
P96 Temperature offset	7	7
P97 Shut down temperature of drive	95	95
<b>Parameter Motor 1</b>		
P02 Datum value	10.000	10.000
P03 Software limit switch min	0.000	0.000

P04 Software limit switch max	999.999	999.999
P05 Distance for multiplication	1.000	1.000
P06 Pulse/distance	7200	5080
P07 Maximum permanent motor current	6.00	4.00
P08 Number of automatic restarts	0	1
P09 Tolerance window	0.000	0.006
P10 Delay time after position reached	0 – 2.50 seconds	0.20
P11 Maximum ramp distance for acceleration ramp	1 - 250,000	15000
P12 Maximum ramp distance for deceleration ramp	1 – 250,000	25000
P13 Fast speed forwards, backwards	100	100
P14 Manual slow speed	20	20
P15 Deceleration ramp after stop command	0.10	0.10
P17 Backlash compensation time	Reserved for ball screw control	0.00
P18 Backlash compensation distance	Reserved for ball screw control	0.0
P19 Integral term 1	1	1
P20 Integral term 2	1	1
P21 Differential term for brake ramp	0	0
P22 Feedback monitoring interval	0.0100	0.0100
P23 Feedback acceleration ramp pulse no.	1	1
P24 Feedback deceleration ramp pulse no.	1	1
P25 Edge counting mode	4	4

P26 Counting direction	0 = forwards 1 = backwards	0
P28 incremental move mode	0	0
P29 Retract distance	0.000	0.000
P30 P-term at the end of the ramp	0.00	0.00
P31 Timer encoder monitoring	0.00	0.00
P32 Operating threshold for encoder monitoring	50	50
P33 Automatic start function	0 Off 1 Program mode only. 2 Single mode only. 3 Single and automatic mode.	1
P36 Closed loop controller	0	0
P37 Closed loop gain factor	0.0100	0.0100
P38 Closed loop window	0	0
P39 Closed loop mode	0	0
P40 Closed loop P-term	10	10
P42 Motor rotation direction	0 = forwards 1 = backwards	0
P44 Go to datum enabled	0	0
P45 Go to datum speed	25	25
P46 Go to datum mode	0	0
P47 Park position after go to datum routine	0.000	0.000
P48 Go to datum offset	0.000	0.000
P50 Brake release delay time	0 – 2.50 seconds	0.20
P51 Motor direction for manual mode	0 or 1	0
P58 Error compensation step width	1.000	1.000
P59 Error compensation mode	0	0

P70 Deadman zone negative direction	0.000	0.000
P71 Deadman zone positive direction	0.000	0.000
P86 Distance reference switch to zero pulse	Read Only	Read Only
P90 Decimal place	1	3
<b>Parameter Special</b>		
P01 Offset mode	0	0
P02 Offset value	0.000	0.000
P03 Offset value 2	0.000	0.000
P04 Delay time for auto retract function	0.00 – 2.50 seconds	0.00
P05 Program key P locked	0 or 1	0
P06 Datuming mode	0 or 1	0
P31 Protection hood input function	0, 1, or 2	0
P32 Enhanced E-Stop function	0 or 1	1
P36 Start delay in program mode	0-60 seconds	0.00
P46 Meaning of value in P47	0 or 1	0
P47 Park position	0.000	0.000
P48 ABS/REL key locked in program mode	0=Active 1=Locked	0
P65 Position reached signal enabled first line	0=Disable 1=Enable	1
P67 Switching forward/backward and lift/lower keys	0 or 1	0
P68 Dwell time for program end output	0-100 seconds	0.20
P69 Parameter base for the inch/mm key	0=mm 1=inch	1
P70 Function of the inch/mm key	0, 1, or 2	1

P71 Function of ABS/REL key	0=Disable 1=Enable	1
P72 Enable the position reached output	0 - 5	0
P73 Dwell time for position reached output	0.00 - 100.00 seconds 0.00 = static	0.20
P74 Quantity auto decrement function of pneumatic length stop	0=Disable 1=Enable	0
P75 Retract function	0 or 1	0
P76 Dwell time for pneumatic retract output	0 – 10.00 seconds 0.00=Static	0.20
P77 Dwell time for pneumatic lift/lower	0 – 10.00 seconds 0.00=Static	0.20
P78 Lift and lower operation	0 - 3	1
P79 Minimal software limit switch with arm in upper position	0.000	0.000
P80 Setting of Bluetooth interface	0 or 1	0
P81 Scanner mode	0 - 3	0

## 5. Handling

### 5.1 Display and key functions

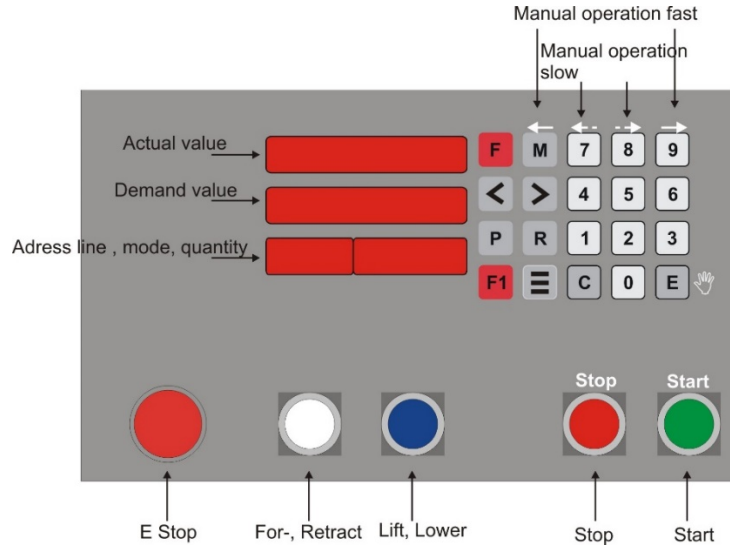



Fig. 4 Key functions, display

### 5.2 Key functions


#### 5.2.1 Quantity input








The quantity input is activated by pressing the  key. The quantity symbol appears in the mode display. After the quantity is entered another keystroke will leave the quantity input.

#### 5.2.2 Special functions

This key can activate different functions that can be activated in parameter P71 in the Special parameter level.


#### 5.2.3 Reference, set datum

By pressing  the actual value can be set to any value in the range of the software limits set in Motor1 P03 and P04.

Press  and enter the code     and press  or  determined by P06 in Special.

### 5.2.4 Program key

A short actuation of the  key opens the program run mode if there are any saved programs.

Holding the  key (approx. 2 seconds) will switch to the program editor mode.

Further information can be found in a subsequent chapter.

### 5.2.5 Select keys

These keys are used to select the parameter levels, or to switch between the different parameters, without saving them to ram.

### 5.2.6 +/- or Inch/MM key

The key changes the sign of a parameter or relative value from positive to negative.

Parameter P70 in the parameter level Special can allow this key to be used for other functions.

### 5.2.7 Setup key

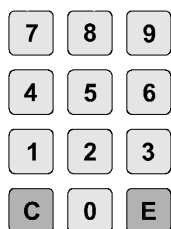
An actuation of this key switches to the parameter editor or back to normal mode (single mode).

### 5.2.8 Enter key

In Single mode, this key switches from automatic to manual mode and vice versa. When manual mode is active, “Hand” appears on the display.

An error message can also be confirmed.

The Enter key opens a parameter level or stores a parameter value to ram.



### 5.2.9 Numeric keypad

The numerical keypad is used to enter demand values, quantities, and different values when the program editor is active.


**5.2.10**  **Start Button**

Pressing the start button will start a program that is selected or move to a single demand position.


When the motor is inside the dead man zone this key must be held until the target is reached.

**5.2.11**  **Stop Button**

The motor is stopped after the current cycle is finished.

**5.2.12**  **Forward, Retract key (Option)**

Starts and ends a movement to the retract position,  
or activates the forward and retract outputs alternately.

**5.2.13**  **Lift, Lower key (Option)**

The lift and lower outputs are activated or deactivated.

**5.2.14**  **Emergency-Stop**

The e-stop stops the motor and disconnects the drive from the motor by an internal relay.

When the security stop is active, “EStoP” appears in the display.





### 5.2.15 Set the EEPROM to default

Make sure you have a list of your machine specific parameters before attempting this.



If the controller does not start during power up caused by corrupted parameters in the EEPROM.

In this unlikely case it is possible to set the EEPROM to its factory value.

To set the EEPROM to its default value, switch off the device, keep  and  pressed and switch the power on again.

When the display shows “ErASE EEProM” the keys can be released.

### 5.2.16 Erasing the whole program memory

Pressing the keys   while the device is switched on will erase the whole program memory. P1 and the actual program address is shown during the erase cycle. Make sure you have a written copy of all programs stored on the controller before attempting this.

## 5.3 Displays

### 5.3.1 Actual value display

The actual value display shows the actual value of the motor position in Single mode.

When selecting or editing a parameter level the display shows the name of the parameter level.

In program mode the display shows the actual value, or the actual program number in editor mode.

### 5.3.2 Demand value display

In single or program mode, the demand value display shows the demand value. This display also shows various messages like,

1. EStOP
2. LiMit M for negative limit switch active
3. LiMit P for positive limit switch active
4. hand for manual mode active

When a parameter level is active, this display shows the parameter number.

### 5.3.3

## Special function display

When a parameter level is active the parameter value is shown here.

In all other cases the display line shows different functions and states.

### 5.3.3.1 Address line display

The address line display shows the step number during program mode.

In single mode it can also show the offset sign when the offset is active.

### 5.3.3.2 Mode display

In the mode display 5 different symbols can appear



quantity input active



the displayed values are absolute values



the displayed values are relative values



the motor moves to a park position



the motor moves to a trim cut, or good part position


### 5.3.3.3 Quantity display

Shows the actual quantity.

## 5.4 Program mode

In program mode it is possible to store a sequence of steps and run the controller step by step.




### 5.4.1 Editor mode

Start the editor mode by holding the  button until "Edit" appears in the second line. This is about 2 seconds.


#### 5.4.1.1 Creating a new program

In the upper line the program number of the last active program appears.

When the program number is flashing, the program is still empty.

A new program can be selected by pressing the   keys or searched by pressing the  key.


It is also possible to insert a program number using the numerical keypad as well.


When a program is selected it must be opened by pressing the  button.

The upper line shows the program number.

In the address line display the actual step is shown.

The demand value is flashing and now ready for entering a value.


When a new demand value is entered it must be confirmed by the  key and it will be switched to the quantity window automatically.

When the  key is enabled to switch between absolute and relative positions it is possible to change this at every time.

The quantity value must be confirmed with the  key and it will be switched to the next step in the program.

When all steps are stored in the program, it is possible to add a park position at the end.

To enter a park position, set the quantity in this step to 0.

When all steps are entered, the editor mode can be left by pressing the  key.


This can only be done when the demand value is flashing.


A step with demand and quantity value set to 0 shows the end of a program.

When a sensor is used to detect the beginning of the material, the first step must be programmed always as a relative demand position.


Then the park position at the end of the program is created automatically.

### 5.4.1.2 Editing an existing program


Start the editor mode by pressing  permanent until “Edit” appears in the second line and P1 appears in the upper line.

The desired program number can be entered or selected by the select keys.  will open the program.

Select the step that should be changed by the select keys.

The values can now be changed and must be confirmed by pressing .


When additional steps are needed at the end of the old program, a last step with demand value and quantity set to 0 must be added at the end.

Exit the editor mode by pressing .

### 5.4.1.3 Erasing an existing program

Start the editor mode by pressing  permanent until “Edit” appears in the second line.

The desired program number can be entered or selected by the select keys.

A permanent keystroke of  erases a program.

When the program is erased, the program number is flashing.

### 5.4.2 Programming the Tool Outputs

The tool outputs can be assigned to every step when P06 in ALL is set to 0.


The outputs are binary coded, and the value can be set in a range of 0 to 15. The four outputs are connected to Con 6, pin 1 and 2 and Con 8, pin 4 and 5. 16 different combinations are possible

<b>Setting</b>	<b>Active outputs</b>
0	No output
1	Con 8, Pin4
2	Con 8, Pin5
3	Con 8, Pin4 + Pin5
4	Con6, Pin1
5	Con 6, Pin1 Con 8, Pin4
6	Con 6, Pin1 Con 8, Pin5
7	Con 6, Pin1 Con 8, Pin4 + Pin5
8	Con 6, Pin2
9	Con 6, Pin2 Con 8, Pin4
10	Con 6, Pin2 Con 8, Pin5
11	Con 6, Pin1 Con 8, Pin4 + Pin5
12	Con 6, Pin1 + Pin2
13	Con 6, Pin1 + Pin2 Con 8, Pin4
14	Con 6, Pin1 + Pin2 Con 8, Pin5
15	Con 6, Pin1 + Pin2 Con 8, Pin4 + Pin5

When the program run mode is active, the tool outputs stay active, if the assigned step is active.

To assign a tool output press the  button in the specific step.

In the demand line “Tool” appears and in the quantity window the value of the tool output.

Change the value and press the  button again.

The outputs are now assigned to the step.


### 5.4.3 Run mode

To enter the program run mode press the  button but do not hold the button down or the controller will go into edit mode.

The program number appears in the upper line and “run” is shown in the second.

The desired program number can be entered or selected by the

  buttons.

Pressing the  button will open the program.

The program can now be started by pressing the start button.

When a program has finished the program number will appear on the display again.

When a program is interrupted by pressing the  button the program will be set to the beginning again.

## 6. Error compensation

The error compensation can be used to compensate mechanical tolerances of the machine.

The error compensation can only be used for positive values in this software version.

Up to 126 tolerance steps can be set. The first and the last step will be set automatically.

Before the error compensation can be executed, a comparison measurement must be done with a system accuracy ten times higher than the accuracy of the PS312.

When the comparison measurement system is connected to the machine, parameter P59 in the parameter level Motor 1 must be set to 1. Set the step width of the compensation values in P58.

When the step width should be 100mm for example enter 100.0.

Then the motor must be moved to the minimal software limit switch. Measure this position as exact as possible and datum the device at this position.

Then press  to start the compensation measuring function.


All parameters related to a length are now automatically multiplied with 10 to show the same accuracy as the comparison system.

This means, if the accuracy was set to 1/10mm it now will show 1/100mm. Additionally some parameters like tolerance window, automatic restart, or closed loop controller are switched off.


The address line shows "Comp" and in the quantity window the number of the actual compensation value is shown.

When the first compensation value is active the values in the actual and demand line should be identical after the system was datumed.


We recommend storing the measured value somewhere. Then the values can be restored should the device become damaged.



Confirm all compensation values with the  button. The compensation value number is incremented and the value set to P58 will be added to the demand value.

After the start key is pressed, the motor moves to the next demand position.

The demand value must now be replaced by the value of the comparison system and confirmed with .

This step must be repeated as often as needed until the end of the measuring section is reached.

When  is pressed one value higher than the positive limit switch is added to the list and stored to the EEPROM.

With the   keys the compensation list can be scrolled forward and backward.

Now that the editor mode is activated it is possible to control or change both values shown in the display. The address shows "Edit" and the value ready for editing is flashing.

With this function it is also possible to measure out all steps and enter these values into the device afterwards.

When start is pressed again the device switches back to the compensation measuring function and "Comp" will be shown again.

To activate the compensation in the production process, P59 in parameter level Motor 1 must be set to 2.

The accuracy of the display switches back to the former one.

But internally the device is still calculating with the higher accuracy and

all the parameter values in the parameter level related to a length are still shown in the higher accuracy.



## 7. Closed loop adjustment

The closed loop function is used to hold the motor in position after a positioning is finished for a certain time, or until the brake is activated.

(Refer to P39 in parameter level Motor1)

The closed loop function should not be activated until all other control parameters are finally set.

First set parameter P09 and P37 in level Motor1 to 0.

Afterwards set P38 in Motor1 to the desired accuracy. When the value is set too small this could cause a long delay until the drive will report that the target is reached.

Then increase P40 until the target is hit, or nearly hit. When the parameter is set too high, the motor may swing around the target position. Then decrease this value again.

Then increase P37 until the target is hit consistently in the desired amount of time.

Finally set P09 in level Motor1 to the desired value again.

## 8. RS232 for PS3xx controllers

The RS232 communication protocol for these controllers can be requested separately at Kentucky Gauge.