



AC Servo Drive

E-DFASxxP series (Pulse type)

Quick Start Guide

V 0.1

Contents

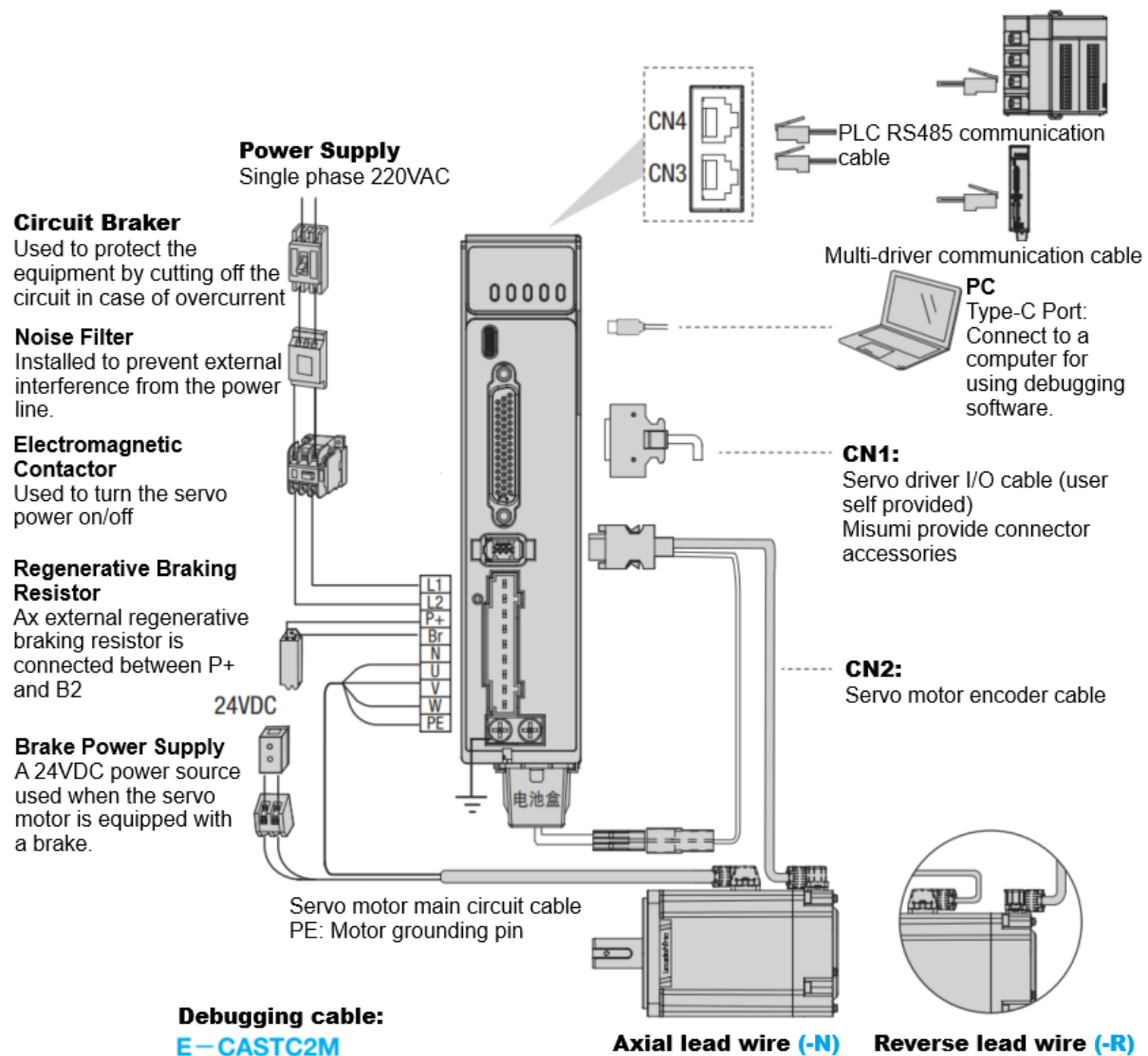
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Version Update Record

Version	Update date	Update content
V1.0	2025-07	First release

1. Wiring

Main Circuit Wiring Diagram



Control Signal Connector - CN1 Pin Assignment

To ensure I/O signal to not be affected by electromagnetic interference, a **shielded twisted pair cable** is recommended for this application.

Diagram	Function	Pin	Label	Signal	Description (default function)	
	Position command	41	PULSE+	Slow speed Pulse input	Low-frequency pulse command control method: - Differential input (5V) - Open collector (24V) PULSE+ and PULSE-: 5V differential input (500KHz) SIGN+ and SIGN-: 5V differential input (500KHz) PULLHI and PULSE-: 24V single end (200KHz) PULLHI and SIGN-: 24V single end (200KHz)	
		43	PULSE-	Slow speed Pulse input		
		37	SIGN+	Slow speed Direction input		
		39	SIGN-	Slow speed Direction input		
		35	PULLHI	Open collector 24V input common		
		38	HPULSE+	High speed Pulse input		4MHz High-frequency pulse train, 5V differential input
		36	HPULSE-	High speed Pulse input		
		42	HSIGN+	High speed Direction input		4MHz High-frequency pulse train, 5V differential input
		40	HSIGN-	High speed Direction input		
		General	17	+24V		Internal 24V power supply
14	COM-					
	General I/O	11	COM+	DI-COM	Common digital input	
		9	DI1	POT	Positive limit switch	
		10	DI2	NOT	Negative limit switch	
		34	DI3	INH	Signal inhibit	
		8	DI4	A-CLR	Alarm clear input	
		33	DI5	SRV-ON	Servo ON input	
		32	DI6	-	-	
		12	DI7	-	-	
		30	DI8	HOME-SEITCH	Home switch	
		7	DO1+	SRDY+	Servo ready signal output	
		6	DO1-	SRDY-		
		5	DO2+	INP+	Position reached feedback	
		4	DO2-	INP-		
		3	DO3+	BRK-OFF+	Release external brake	
		2	DO3-	BRK-OFF-		
		1	DO4+	ALARM+	Alarm output	
		26	DO4-	ALARM-		
		28	DO5+	HOME-OK+	Homing finish output	
		27	DO5-	JOME-OK-		
		Encoder output		21	A+	Encoder Output A phase
22	A-					
25	B+			Encoder Output B phase	Differential output, B phase signal	
23	B-					
13	Z+			Encoder Output Z phase	Differential output, Z phase signal	
24	Z-					

E-DFASxxP series (EtherCAT type) Quick Start Guide

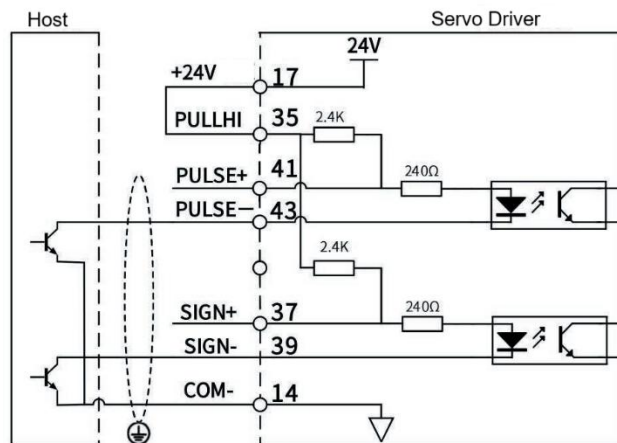
		44	OCZ	Encoder Output Z phase	Z phase signal Open collector output
		29	GND	Z phase signal Open collector output GND	Z phase signal Open collector output GND
	General	15	+5V	Internal 5V power supply	Internal 5V power supply, Max current 200mA
		16	GND		
		Shield	-	Shield	Frame grounding

1. Single-end pulse input

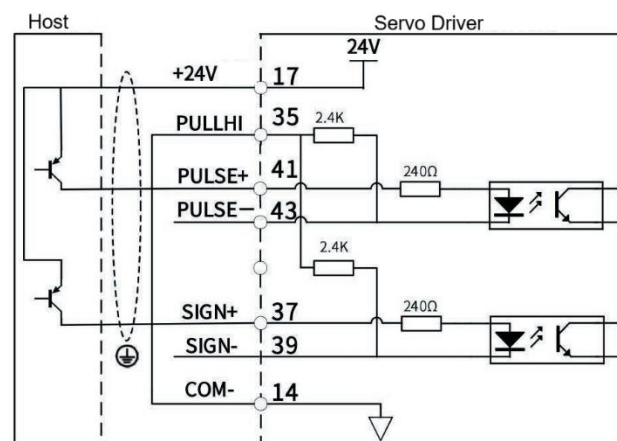
Max allowed frequency: 200kHz

Required input voltage: 12~24V

NPN connection:



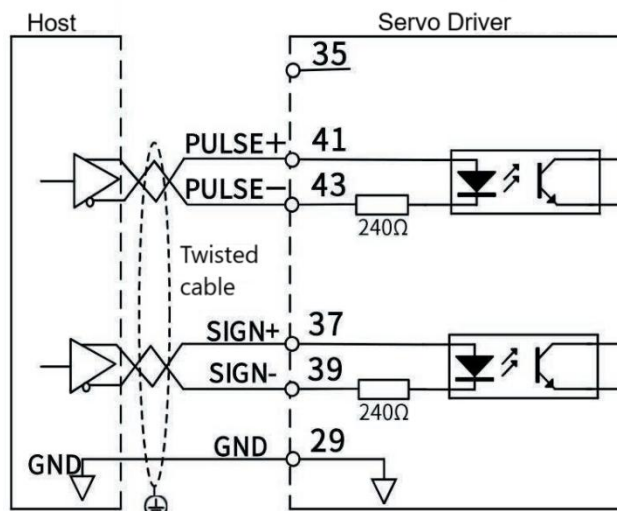
PNP connection:



2. 5V differential pulse input (low speed)

Max allowed frequency: 500kHz

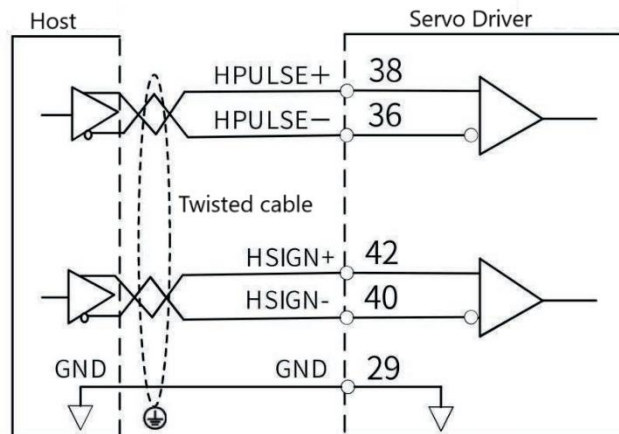
Required input voltage: ±3~6V



3. 5V differential pulse input (high speed)

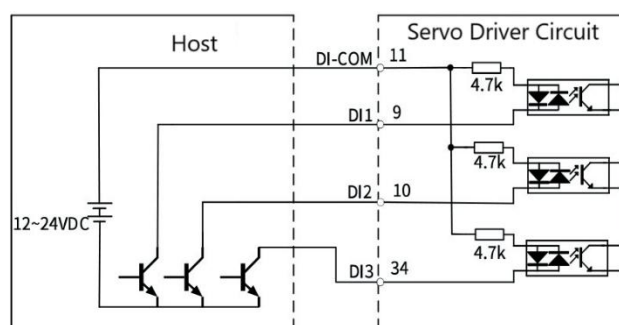
Max allowed frequency: 4MHz

Required input voltage: $\pm 5V$

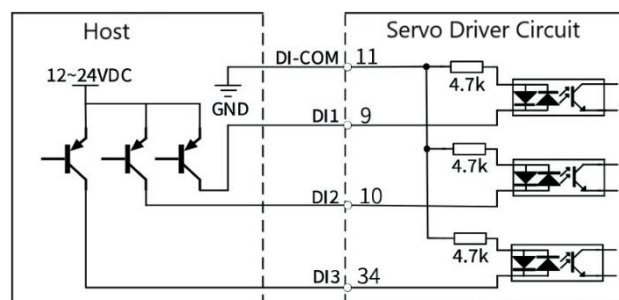


4. General digital input connection

NPN connection:

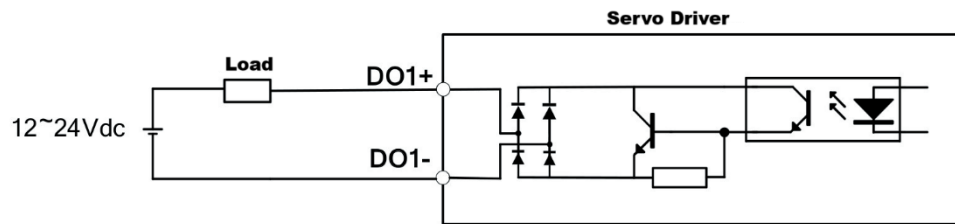


PNP connection:

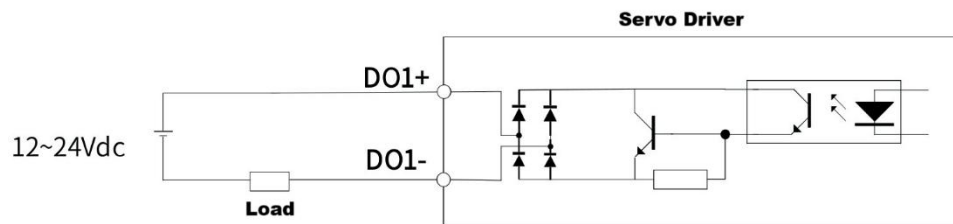


5. General digital output circuit

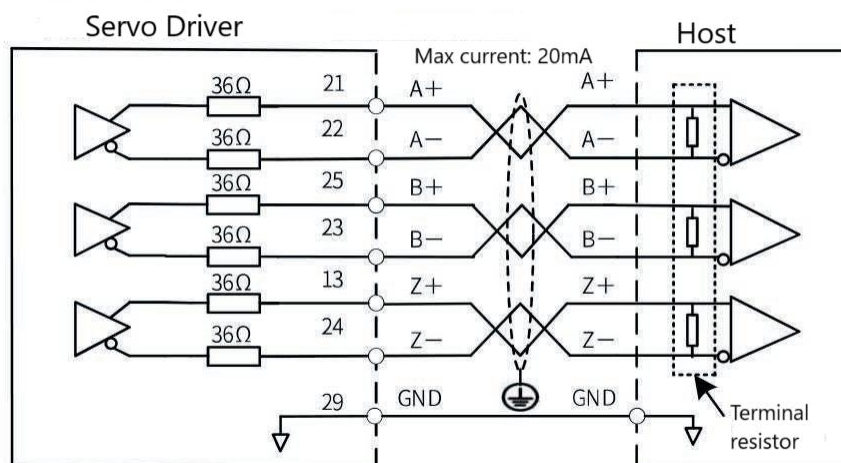
NPN connection:



PNP connection:



6. Encoder Output (differential output)



2. Precautions Before Operation

The driver and servo motor must be reliably grounded. The PE terminal of the driver must be securely connected to the equipment ground.

Ensure all wiring is correct before powering on.

An emergency stop circuit must be integrated to ensure the power supply immediately stops in case of a fault.

After a driver fault alarm, verify that the issue has been resolved before restarting, and ensure the SRV-ON signal is inactive.

Do not touch the driver within at least 5 minutes after power is turned off to prevent electric shock.

If the driver panel is unresponsive after powering on, check whether the input voltage is within the rated range and ensure there are no phase losses.

3. EDrive Configuration Software

Download EDrive Configuration Software.

Download link:

https://www.misumi.com.cn/linked/archive/me/MISUMI_EDrive_v1_0_0.zip

Installation

Just unzip or pull the 'MISUMI EDrive_v1.0.0' folder to the desktop.

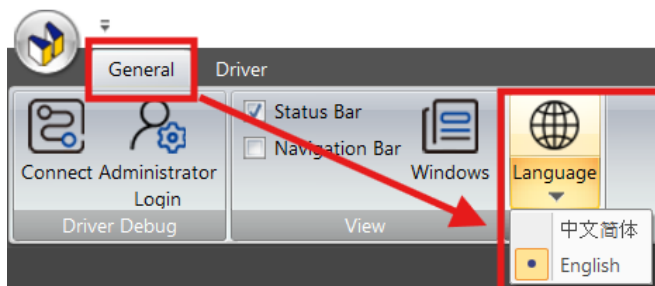
☐ Name	Date modified	Type	Size
 EDriver_v1.1.0_alpha	6/30/2025 10:55 AM	File folder	

Open Software

Double click 'EDrive.exe' to open the software.

☐ Name	Date modified	Type	Size
 Driver	6/30/2025 10:55 AM	File folder	
 DriverDefaultPara	6/30/2025 10:55 AM	File folder	
 Help	6/30/2025 10:55 AM	File folder	
 Init	6/30/2025 10:55 AM	File folder	
 Log	1/3/2025 5:11 PM	File folder	
 Motors	6/30/2025 10:55 AM	File folder	
 Pic	6/30/2025 10:55 AM	File folder	
 Record	10/21/2024 2:26 PM	File folder	
 Remark	6/30/2025 10:55 AM	File folder	
 Script	6/30/2025 10:55 AM	File folder	
 Tools	6/30/2025 10:55 AM	File folder	
 DATA.mdb	2/14/2025 10:37 AM	Microsoft Access ...	19,068 KB
 EDrive.exe	2/7/2025 11:14 AM	Application	7,085 KB
 inp_num.dll	2/7/2025 11:14 AM	Application extens...	8 KB
 Interop.dll	2/7/2025 11:14 AM	Application extens...	78 KB

After software opened, go to 'General' and change language to 'English'.

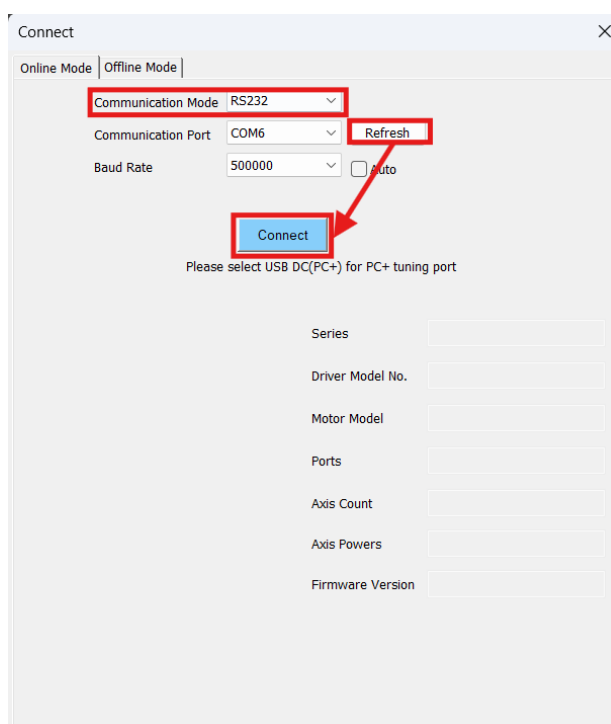


Connect to PC

Please use cable with one side USB type-A and the other side USB type-C.

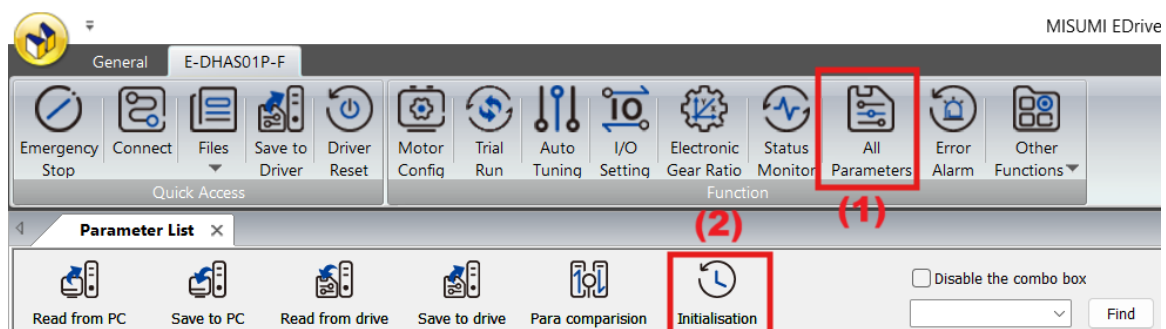


Open EDrive software and start connection. 'Communication Mode' please choose 'RS232', then click 'Refresh', then click 'Connect'.

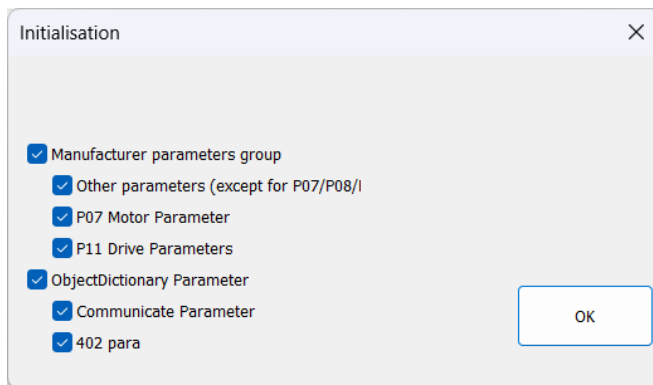


Trial Run

Before Trial Run, please initialize the driver. Click (1) 'All Parameters', choose (2) 'Initialisation'.

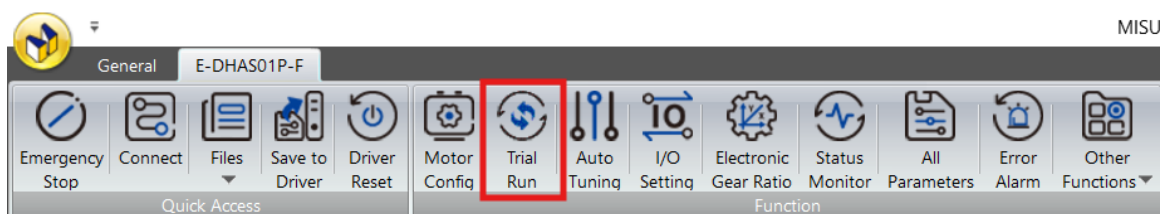


Select all and click 'OK'

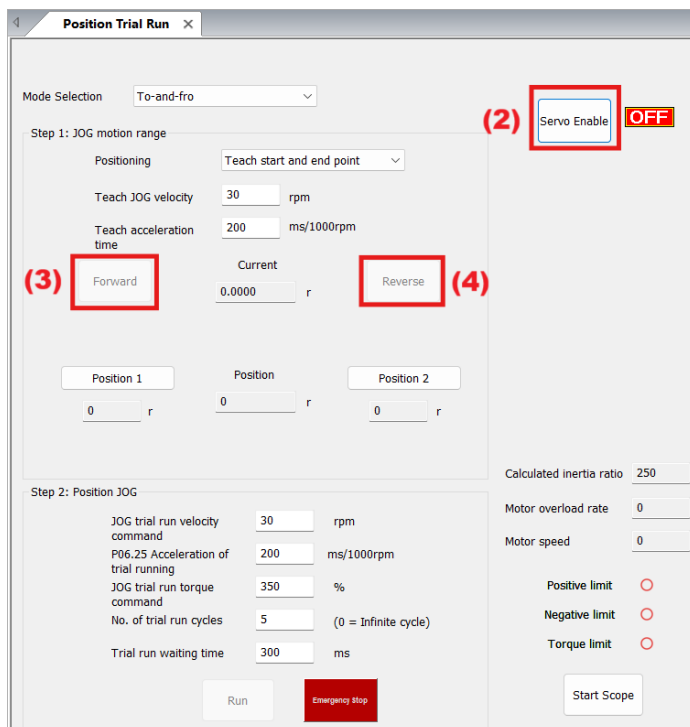


If you encounter motor abnormalities during operation, please power cycle the servo system. If the issue persists, proceed with initializing the system.

Click 'Trial Run'.

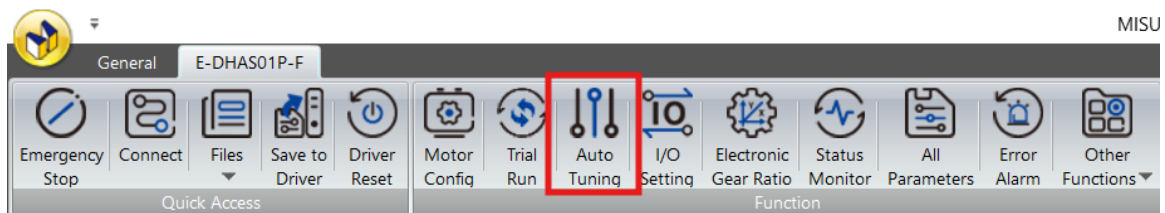


Click (2) 'Servo Enable', if driver already Servo ON through IO, please tick check box (3) 'External enabling disabled', then click (4) 'Forward' or (5) 'Reverse', to move the motor.



Auto Tuning

Click 'Auto Tuning'.



Click (2) 'Next'.

Note: Other parameters are not necessary, suggest not to change.

The screenshot shows the 'Auto Tuning' configuration window. At the top, there are four tabs: 'Tuning settings' (active), 'Range of motion', 'Tuning operation', and 'Tuning result'. Below the tabs, there are several sections: 'Select axis' with a dropdown menu set to 'Axis1'; 'Tuning response' with three radio buttons: 'High response [suitable for applications with high mechanical stiffness]', 'Medium response [suitable for applications with medium mechanical stiffness]' (selected), and 'Low response [suitable for applications with low mechanical stiffness]'; 'Tuning mode' with two radio buttons: 'Positioning mode' (selected) and 'Track Mode'; 'Target in position range' with 'Unit selection' set to 'Encoder unit' (selected), 'Command uni' (unselected), and '0.0001rev' (unselected); and 'In position range' with a text input field containing '20' and a 'Pluse' button. At the bottom right, there is a 'Next' button highlighted with a red box and labeled '(2)'.

Click (3) 'Servo Enable'. (Note: If driver already Servo ON through IO, please tick check box 'External enabling disabled')

Click (4) 'Forward'. After motor reaches starting position, click (5) 'Position 1'. Then click (6) 'Reverse'. After motor reaches ending position, click (7) 'Position 2'. (Note: Please always make sure motor is in between of starting position and ending position) Click (8) 'Next', and follow the instruction to finish Auto Tuning.

One-Click Tuning

Tuning settings >> Range of motion >> Tuning operation >> Tuning result

Motion mode and range

Mode Selection: To-and-fro

Teach JOG velocity: 30 rpm

Teach acceleration: 200 ms/1000rpm

(3) Servo Enable **OFF**

(4) Forward Current 0.0000 r (6) Reverse

(5) Position 1 0 r Position 2 (7) 0 r

Note: Before tuning, start and end point must be set through JOG operation and the position

Inertia Ratio

Default Inertia Ratio: 250 ☐ Disable inertia ratio identification failure alarm

Tuning speed limit

Speed limit: 1500 rpm

Note: This speed limit is only effective in the tuning process. Default value is 50% of the rated

Previous (8) Next Warning: The setting distance ranges from 0.5 to 30r

Click (9) 'Done', and follow the instruction to save parameters.

Tuning result >> Range of motion >> Tuning operation >> Tuning result

Tuning result | Manual fine adjustment | Para comparison

Tuning result : Success, Used time 96 s.

Performance evaluation

In position range(Pluse)	20
Arrival counts	54
Arrival time(ms)	24
Overshoot	17
Jitter counts	1
Maximum current(%)	66
Maximum velocity(mm/s)	398

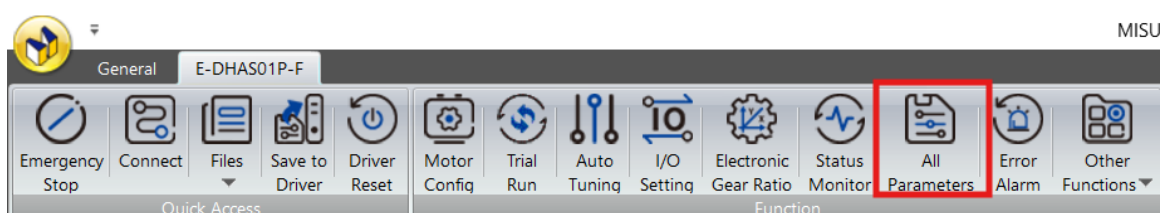
Emergency Stop

Export parameter file Back to Step 1 (9) Done

Parameter Backup and Download

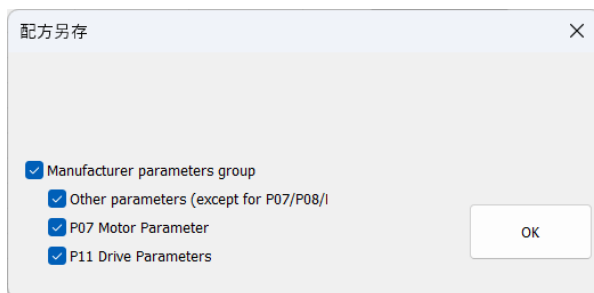
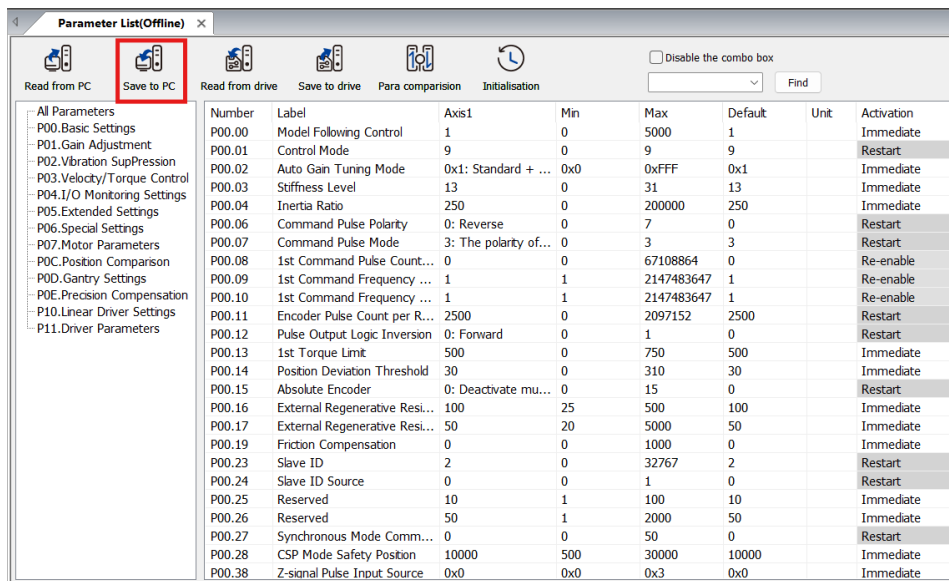
Please refer to following steps to backup parameters.

Click 'All Parameters'.

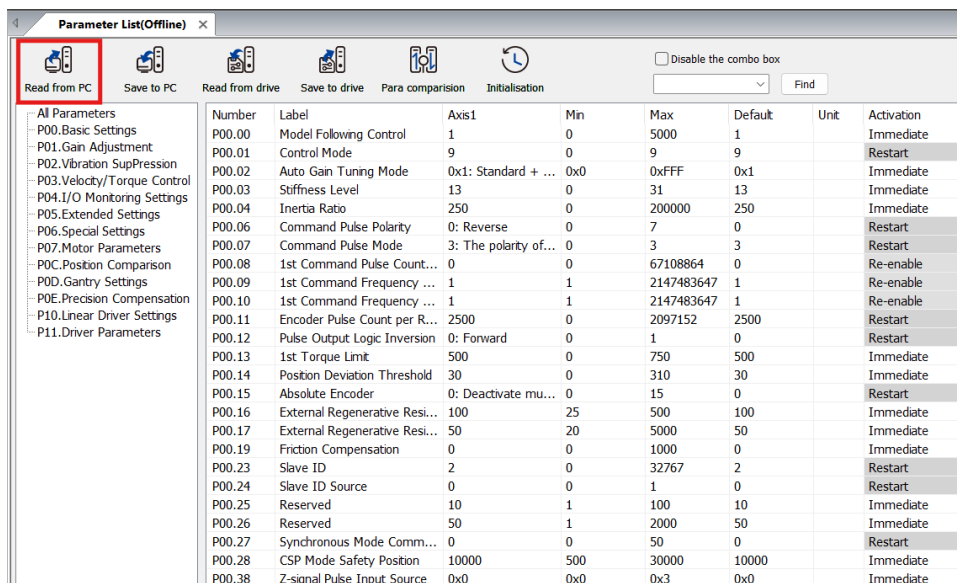


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Click 'Save to PC' and follow the instruction to finish saving.



When download parameters, click 'Read from PC'.



Choose the parameter file you saved, and it will be shown in a new tab (4). Click (5) 'Save to drive', then click (6) 'Driver Reset'. Follow the instruction to finish saving.

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MISUMI EDrive

General E-DHAS01P-F (6)

Emergency Stop Connect Files Save to Driver Driver Reset Motor Config Trial Run Auto Tuning I/O Setting Electronic Gear Ratio Monitor Parameters All Error Alarm Other Functions

Quick Access Function

Parameter List Par_B.msm (4)

Read from PC Save to PC Save to drive (5) Para comparison Help

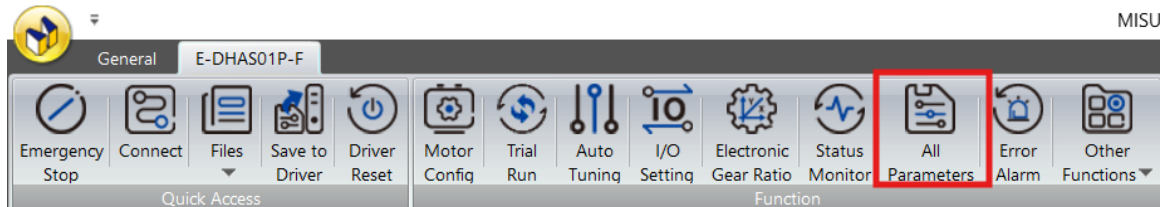
☐ Disable the combo box

	Number	Label	Axis1	Min	Max	Default	Unit	Activation
All parameters								
P00. Basic settings	P00.00	Model-following bandwidth	1	0	5000	1	0.1Hz	Immediate
P01. Gain adjustment	P00.01	Control Mode Settings	9	0	9	9	model	Restart
P02. Vibration Suppression	P00.02	Real time Auto Gain Adjus...	0x1: Standard + ...	0x0	0xFFFF	0x1	--	Immediate
P03. Velocity / Torque Contr	P00.03	Real time auto stiffness a...	13	0	31	13	--	Immediate
P04. I/O Monitoring Settings	P00.04	Inertia ratio	250	0	200000	250	%	Immediate
P05. Extension settings	P00.06	Probe signal polarity settin...	0: The comman...	0	7	0	--	Restart
P06. Special Settings	P00.07	Command pulse counts p...	3: Probe 1 and P...	0	3	3	--	Restart
P07. Motor parameters	P00.08	1st command pulse count...	0	0	67108864	0	--	Re-enable
P0C. Position Comparison	P00.09	1st command frequency d...	1	1	2147483647	1	--	Re-enable
P0D. Gantry settings	P00.10	1st command frequency d...	1	1	2147483647	1	--	Re-enable
P0E. Precision compensation	P00.11	Encoder pulse output per r...	2500	0	2097152	2500	P/rev	Restart
P11. Drive parameters	P00.12	Pulse output logic inversion	0: No Reversal	0	1	0	--	Restart
	P00.13	1st Torque Limit	350	0	500	350	%	Immediate
	P00.14	Excessive Position Deviatio...	30	0	310	30	0.1rev	Immediate
	P00.15	Absolute Encoder settings	0: Disable multi-t...	0	15	0	--	Restart
	P00.16	Regenerative resistance	100	25	500	100	Ω	Immediate
	P00.17	Regenerative resistor pow...	50	20	5000	50	W	Immediate
	P00.19	Friction compensation setti...	0	0	1000	0	--	Immediate
	P00.23	Slave Alias	2	0	32767	2	--	Restart
	P00.24	Slave Alias Source	0: The master st...	0	1	0	--	Restart
	P00.25	Retain Parameters	10	1	100	10	--	Immediate
	P00.26	Retain Parameters	50	1	2000	50	--	Immediate
	P00.27	Synchronization mode co...	0	0	50	0	--	Restart
	P00.28	CSP mode safe selfrunnin...	10000	500	30000	10000	--	Immediate
	P00.30	Encoder feedback mode	2	0	3	2	--	Restart

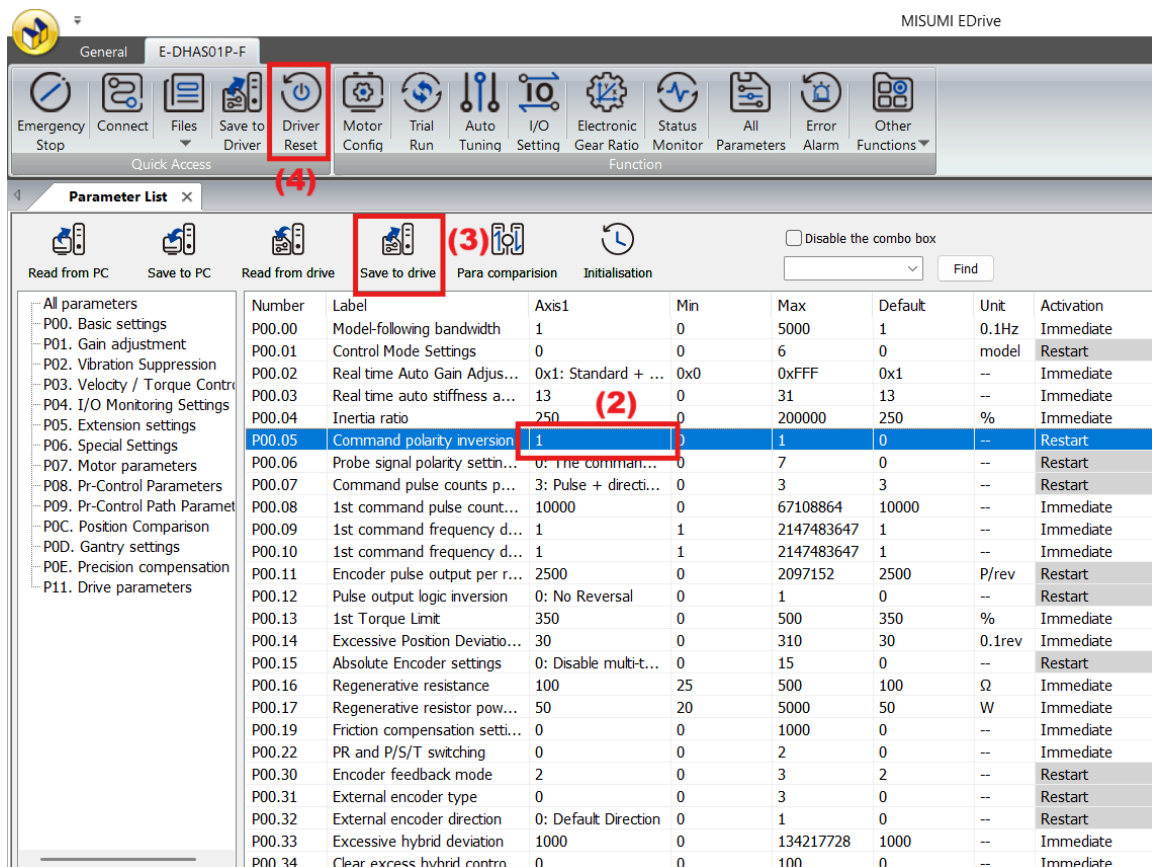
4. Change Pulse Signal Type

Servo Driver support two types of Pulse Signal and the default type is 24V single-end pulse signal (200kHz) or low speed $\pm 5V$ differential pulse signal (500kHz). If want to switch to 5V differential signal, please follow below steps:

Click 'All Parameter'.



Change (2) P00.05 'Command Pulse Input' to 1, then click (3) 'Save to drive'. Click (4) 'Driver Rest' and follow the instructions to finish the saving.



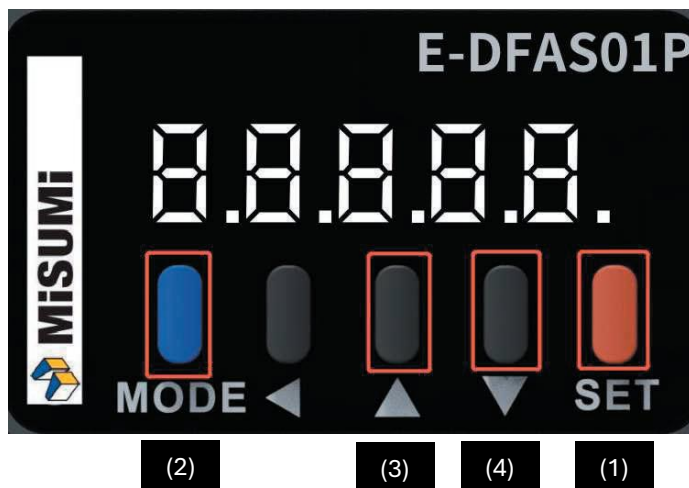
5. Change Motion Direction

If controller pulse train or command is positive direction, but motor moves to negative direction, direction change is needed.

P00.06	Label	Command Pulse Polarity					Valid mode(s)			F
	Range	0~1	Unit	-	Default	0	Activation	Restart	485 address	0x0000
P00.06: Sets the polarity of the command pulse input. It only changes the motor rotation direction; it does not invert the sign of the command. When velocity or torque mode is inverted, parameters P03.03 and P03.20 are disabled.										
	Value	Position Mode		Velocity Mode		Torque Mode				
	0	Not Inverted		Not Inverted		Not Inverted				
	1	Inverted		Not Inverted		Not Inverted				
	2	Not Inverted		Inverted		Not Inverted				
	3	Inverted		Inverted		Not Inverted				
	4	Not Inverted		Not Inverted		Inverted				
	5	Inverted		Not Inverted		Inverted				
	6	Not Inverted		Inverted		Inverted				

Method 1: Set with Front Panel

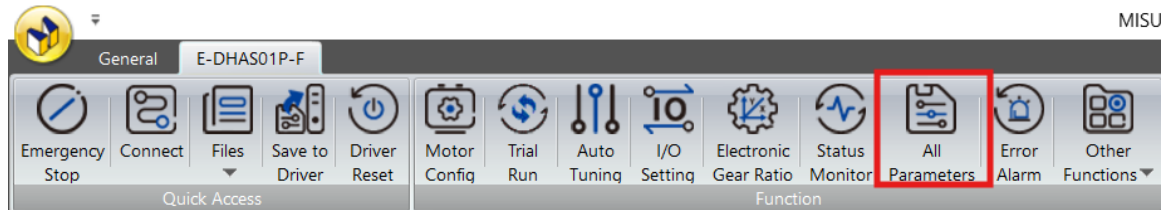
- Press (1) 'S' button, front panel shows 'd345E'. Press (2) 'M' button, front panel shows 'P00.00'. Press (3) ↑ button and change to 'P00.06', then press (1) 'S' button to show the current 'Command Pulse Polarity' setting.



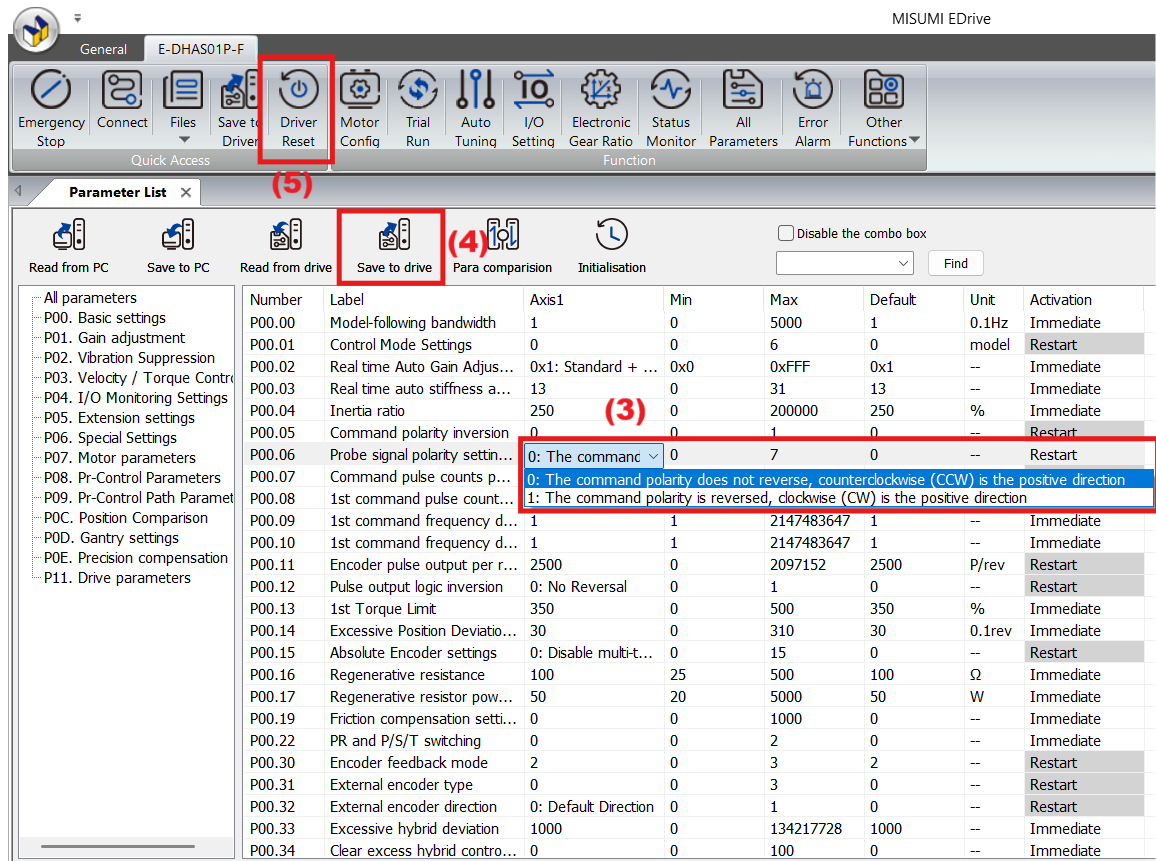
- If now 'Command Pulse Polarity' setting is '0', press (3) ↑ button and change to '1'. If it's '1', then press (4) ↓ button and change to '0'.
- After changing the parameter, restart the driver to activate the setting.

Method 2: Change through 'All Parameters' in EDrive software

1. Click 'All Parameters'.



2. Change value of (2) P00.06 'Command Pulse Polarity' from '0: Reverse' to '1: Forward' or vice versa. Then click (3) 'Save to drive', and click (4) 'Driver Reset'.



6. Change Electronic Gear Ratio

If the upper controller's pulse count is insufficient and the speed cannot meet the requirement, the motor command pulse count must be adjusted.

P00.08	Label	1st Command Pulses Count per Revolution					Valid mode(s)			F
	Range	0~67108864	Unit	-	Default	0	Activation	Re-enable	Index	2008h
This parameter sets the number of command pulses required for one full revolution of the motor. Note: This setting can also be configured via the object dictionary entries 608F, 6091, and 6092, but P00.08 takes priority when set.										

P00.09	Label	1st Command Frequency Divider/Multiplier Numerator					Valid mode(s)			F
	Range	0~2147483647	Unit	-	Default	0	Activation	Re-enable	Index	2009h
This parameter sets the numerator for scaling the input command pulses (for frequency division or multiplication). Corresponds to object dictionary 6091-01. Can be modified directly on the control panel to update the value of 6091-01. Effective only when P00.08 = 0.										

P00.10	Label	1st Command Frequency Divider/Multiplier Denominator					Valid mode(s)			F
	Range	0~2147483647	Unit	-	Default	0	Activation	Re-enable	Index	2010h
This parameter sets the denominator for scaling the input command pulses. Also corresponds to object dictionary 6091-01. Can be modified directly on the control panel to update the value of 6091-01. Effective only when P00.08 = 0.										

When setting the numerator and denominator for command pulse input scaling, you must first set P00.08 to 0.

To configure the denominator for frequency division or multiplication of the command pulse input, follow the steps below:

Definitions:

X – Number of command pulses input to the drive

Y – Encoder pulses after frequency division/multiplication

Z – Encoder pulses per motor revolution

W – Number of motor revolutions

Calculations:

- 1) Relationship between X and Y:

$$Y = X \times P00.10 / P00.09$$

Note: The values of P00.09 and P00.10 must each be less than 2^{24} (16,777,216).

Exceeding this range may result in incorrect frequency division or multiplication.

- 2) Explanation of Z (Encoder Resolution):

For a 17-bit motor: $Z = 2^{17} = 131,072$

For a 23-bit motor: $Z = 2^{23} = 8,388,608$

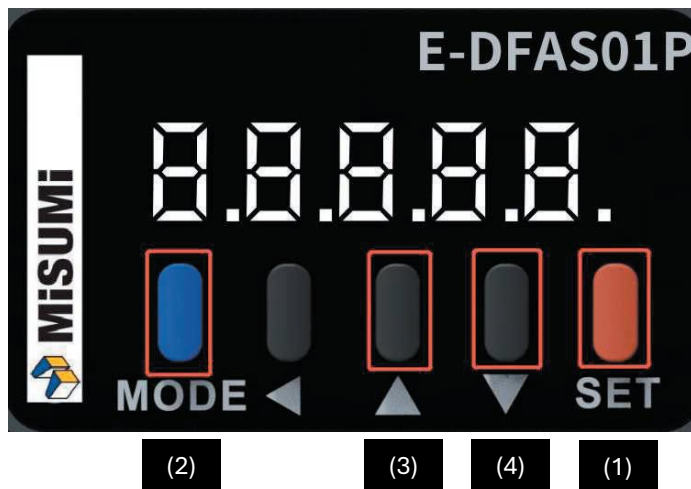
- 3) Relationship between Y, Z, and W:

$$W = Y / Z$$

Note: Although the numerator and denominator can be set to any value within the valid range, using extreme frequency division or multiplication ratios may cause the system to malfunction. If the resulting command pulses per motor revolution is less than 500, an Er1b1 alarm will be triggered.

Method 1: Set with Front Panel

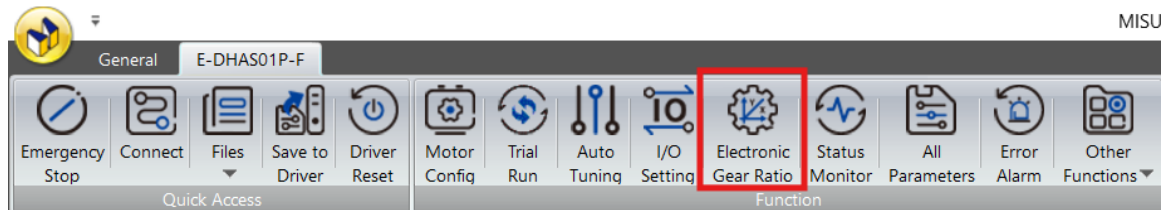
1. Press (1) 'S', display shows d345E. Press (2) 'M', display shows P00.00. Press (3) $\uparrow$ to scroll to P00.08. Press (1) 'S' again to enter the parameter setting for command pulses per motor revolution.



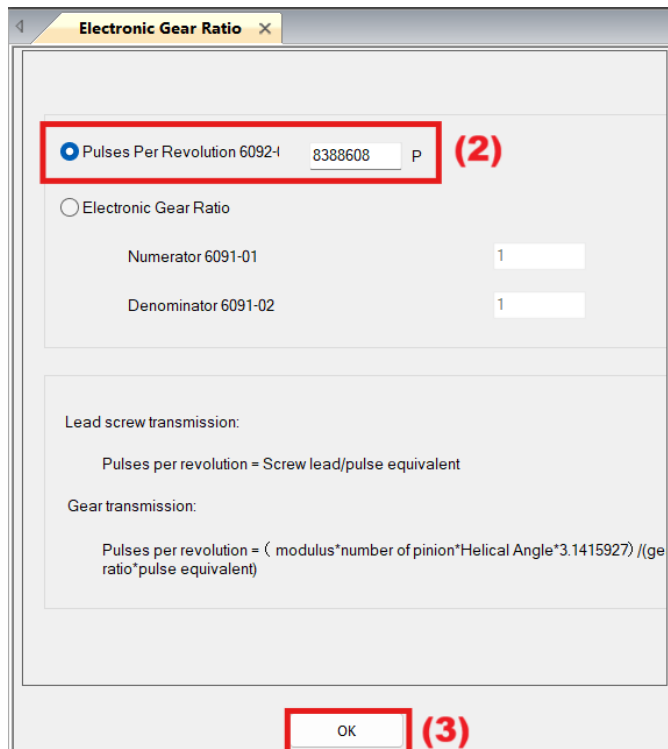
2. P00.08 must be set as an integer. To apply pulse input scaling (division/multiplication), first set P00.08 = 0, then configure P00.09: Numerator of the scaling ratio, P00.10: Denominator of the scaling ratio.
3. After modifying parameters, power cycle the driver for changes to take effect.

Method 2: Change through 'Electronic Gear Ratio' in EDrive software

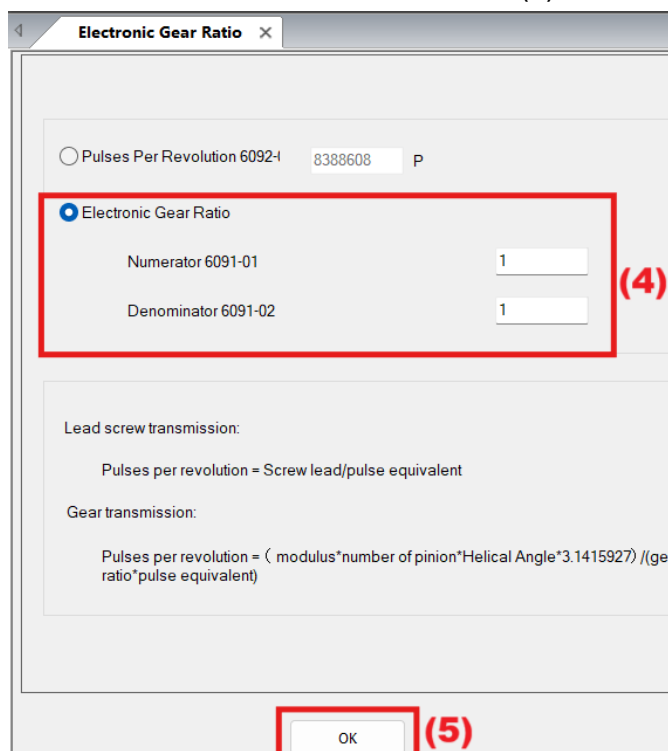
1. Click (1) 'Electronic Gear Ratio'.



2. Select (2) 'Pulse Per Revolution' to set the parameter, then click (3) 'OK'..

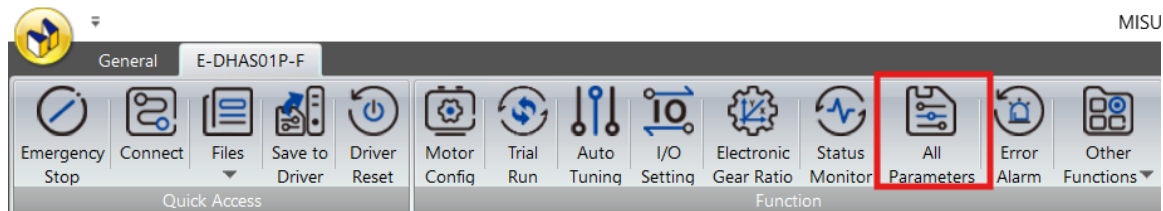


3. To apply pulse input scaling, select (4) 'Electronic Gear Ratio', set parameters 'Numerator' and Denominator'. Click (5) 'OK'.

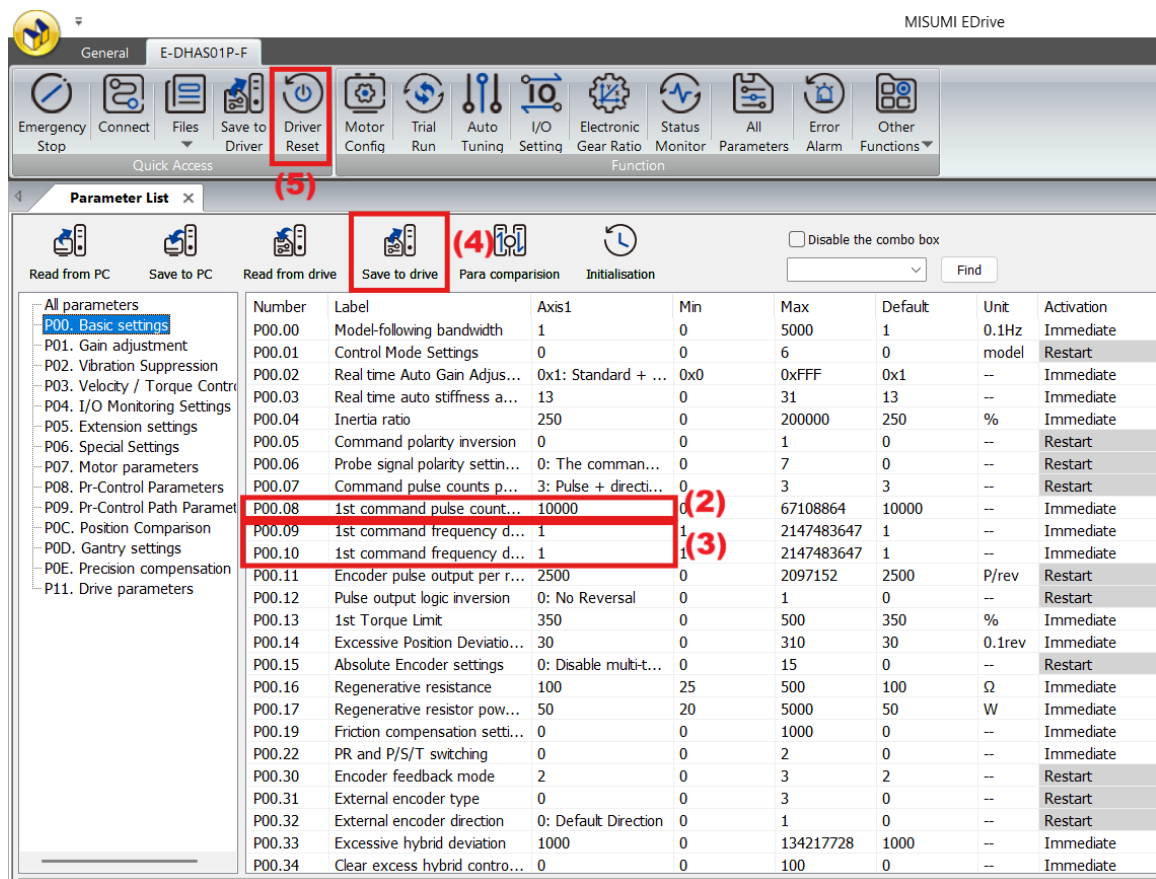


Method 3: Change through 'All Parameters' in EDrive software

1. Click 'All Parameters'.



2. Modify (2) P00.08 '1st Command Pulses Count per Revolution'. If setting scaling ratio, first set (2) P00.08 to 0, then configure (3) P00.09 '1st Command Frequency Divider/Multiplier Numerator' and P00.10 '1st Command Frequency Divider/Multiplier Denominator'. Click (4) 'Save to drive', then (5) 'Driver Reset'.



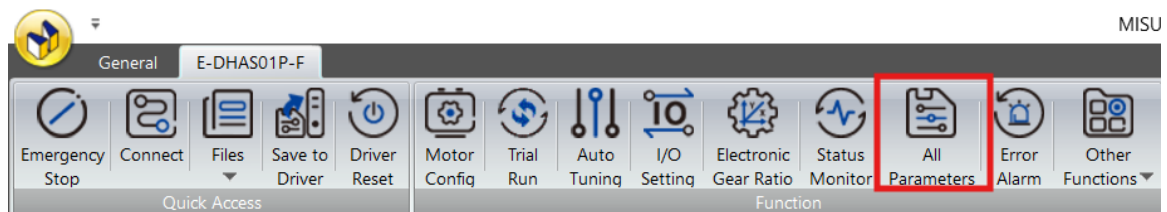
7. Parameter Setting

Method 1: Set with Front Panel

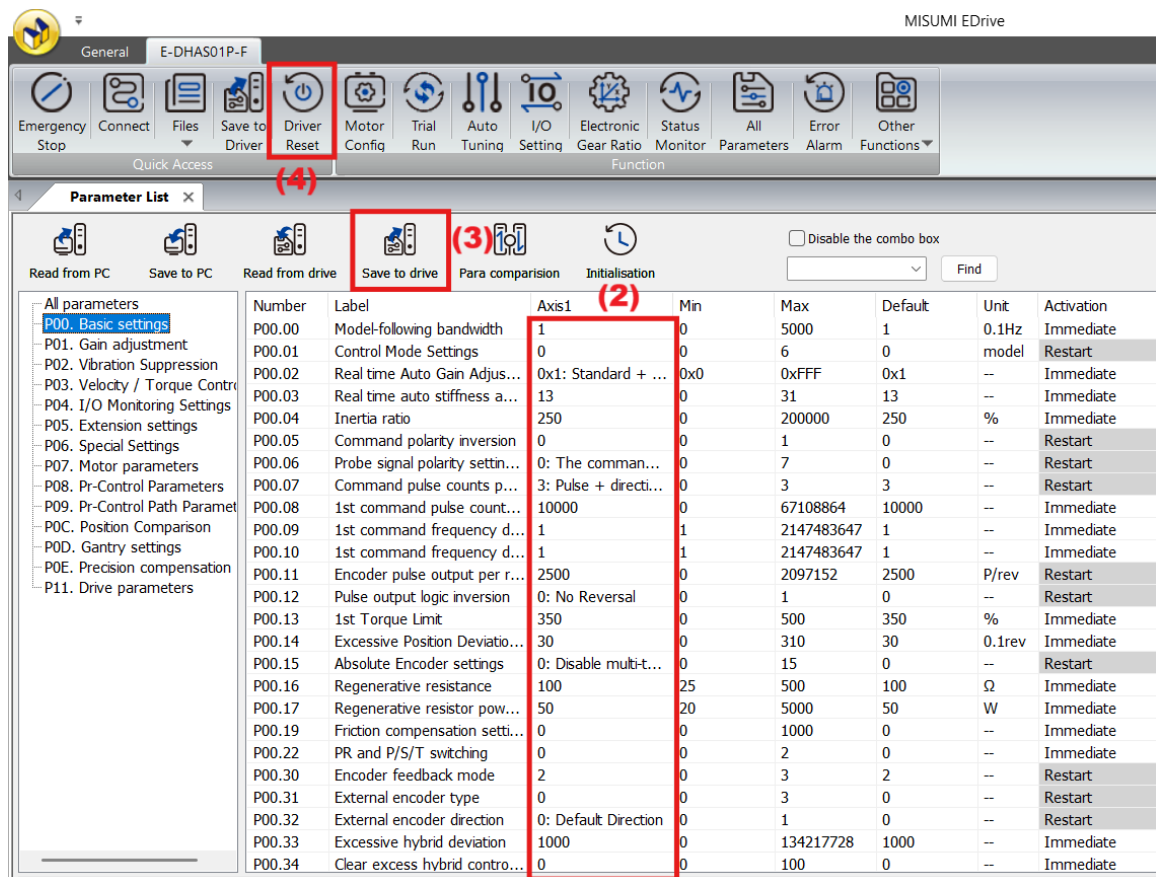
After the servo drive is powered on, Press button 'S', the display shows 'd34 5E'. Press button 'M', the display shows 'P00.00'. Scroll to the parameter code you want to adjust and press button 'S' again to enter the parameter setting page.

Method 2: Change through 'All Parameters' in EDrive software

1. Click 'All Parameters'.



2. In the (2) 'Axis 1' column, modify the desired parameter. After modification, click (3) 'Save to drive'. Then click (4) 'Driver Reset' to apply the changes.



8. PLC RS-485 Communication Example

PLC monitor and modify Servo Driver Object Dictionary via RS-485.

Hardware Used in This Case:

Servo Drive: Misumi E-DHAS01P

PLC: Siemens S7-1200, TIA Portal V20

System Wiring

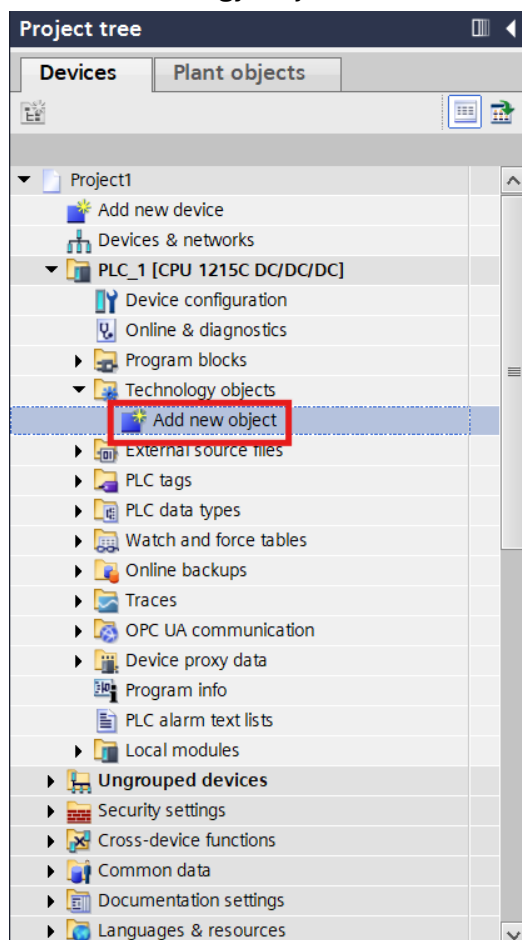
Connect the PLC communication module to the servo drive's Ethernet port.

Connect the PLC's DO (digital output) points to the servo drive's CN1 control signal terminals.

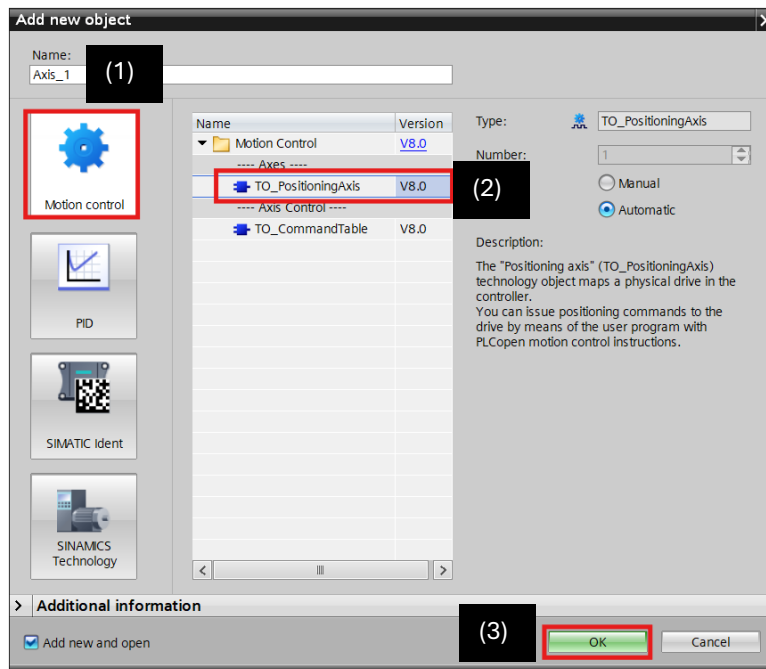
Power on the system.

TIA Portal Axis Technology Configuration

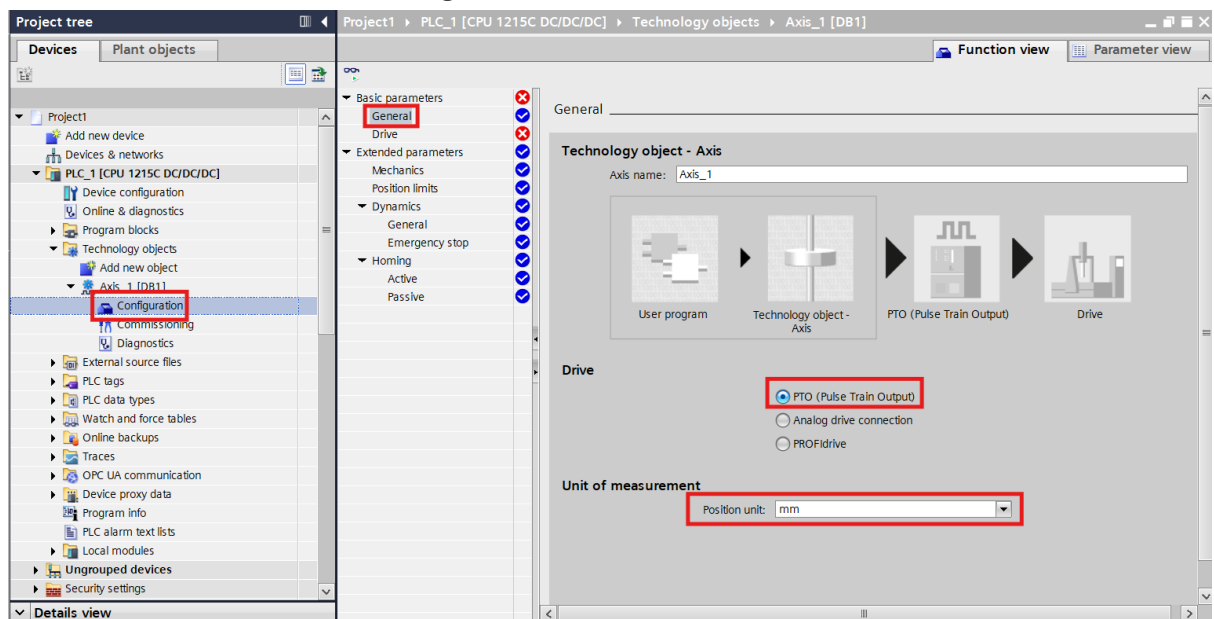
1. In the Technology Objects section of TIA Portal, double-click to add a new object.



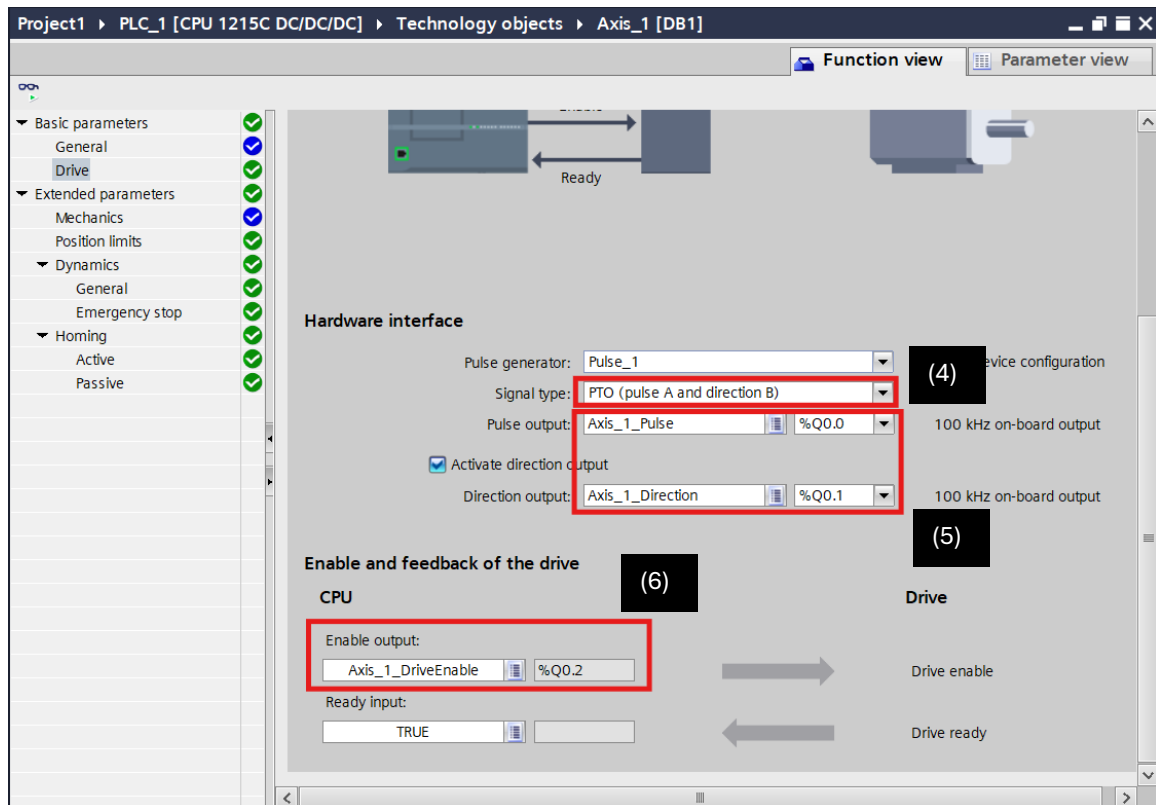
2. Select (1) 'Motion Control', click (2) 'TO_PositioningAxis', then click (3) 'OK'.



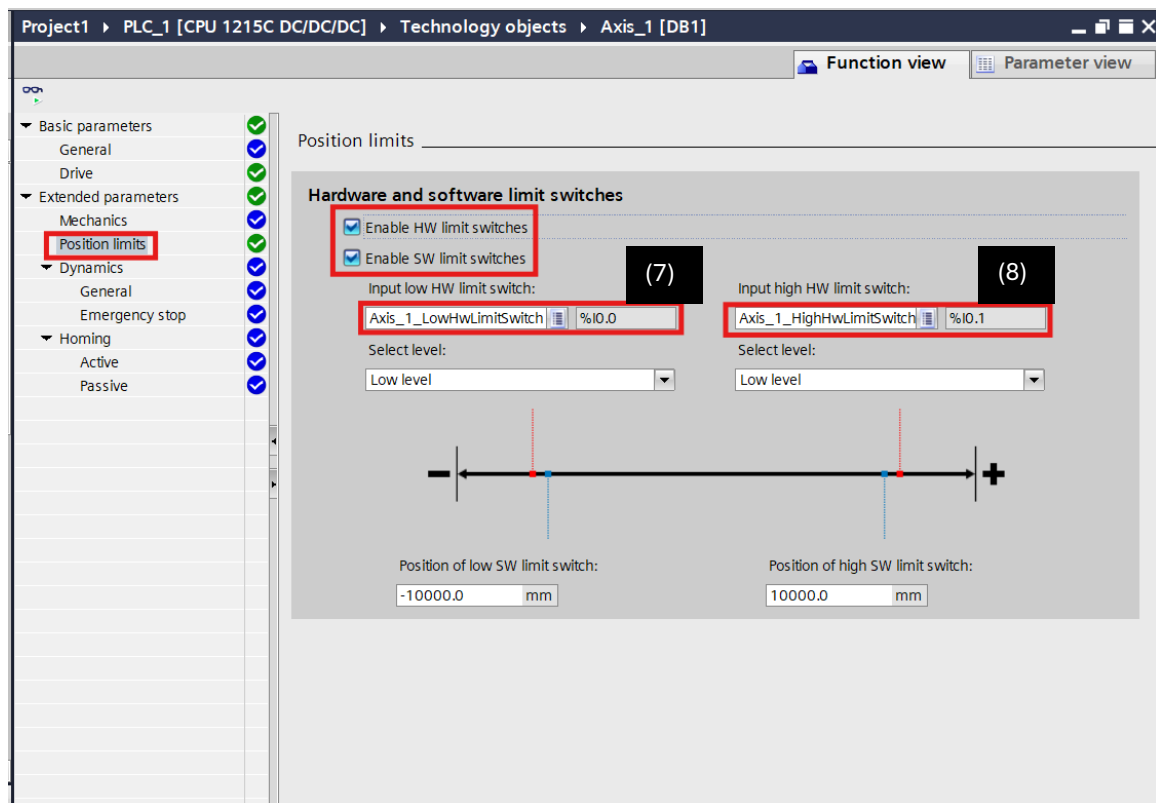
3. In the 'General' tab of the 'Configuration', set the control mode and units.



- In the 'Drive' tab, set (4) Signal Type to PTO. Configure (5) Pulse Output Address to Q0.0, Direction Output Address to Q0.1. Enable (6) Output Address to Q0.2.



- In the Position Limits tab, configure (7) 'Input low HW limit switch'. Configure (8) 'Input high HW limit switch'.



- In the 'General' tab, set (9) Velocity Unit, Maximum Speed, and Start/Stop Speed and (10) Acceleration and Deceleration.

Project1 ▶ PLC_1 [CPU 1215C DC/DC/DC] ▶ Technology objects ▶ Axis_1 [DB1]

Function view Parameter view

Basic parameters
General
Drive
Extended parameters
Mechanics
Position limits
Dynamics
General
Emergency stop
Homing
Active
Passive

General

Note: Changes in the velocity limits affect acceleration and deceleration; the ramp-up time and ramp-down time stay the same.

Velocity

Acceleration / deceleration

Unit of velocity limits:
mm/s

Maximum velocity:
250.0 mm/s

Start/stop velocity:
10.0 mm/s

Acceleration:
48.0 mm/s²

Deceleration:
48.0 mm/s²

5.0 s 5.0 s

- Optionally, click (11) Enable Jerk Limiting, then set (12) Jerk Parameters.

Project1 ▶ PLC_1 [CPU 1215C DC/DC/DC] ▶ Technology objects ▶ Axis_1 [DB1]

Function view Parameter view

Basic parameters
General
Drive
Extended parameters
Mechanics
Position limits
Dynamics
General
Emergency stop
Homing
Active
Passive

General

Velocity

Acceleration / deceleration

250.0 mm/s

250.0 mm/s

Start/stop velocity:
10.0 mm/s

10.0 mm/s

Acceleration:
48.0 mm/s²

Deceleration:
48.0 mm/s²

5.0 s 5.0 s

Ramp-up time: Ramp-down time:

(11) ☒ Enable jerk limit

Smoothing time: t₁: 0.25 s t₂: 0.25 s

Jerk:
192.0 mm/s³

(12)

Note: By enabling the jerk limit, the total time for acceleration and deceleration of the axis is increased.

8. In the emergency stop, can set the speed of (13) Emergency Deceleration.

Project1 > PLC_1 [CPU 1215C DC/DC/DC] > Technology objects > Axis_1 [DB1]

Function view | Parameter view

Basic parameters
General
Drive
Extended parameters
Mechanics
Position limits
Dynamics
General
Emergency stop
Homing
Active
Passive

Emergency stop

Velocity

Maximum velocity: 250.0 mm/s
250.0 mm/s
Start/stop velocity: 10.0 mm/s
10.0 mm/s

Deceleration

Emergency deceleration: 120.0 mm/s² (13)

2.0 s
Emergency stop ramp-down time:

9. In the Active Homing section, configure (14) Homing Switch Address, select (15) Homing Direction, choose (16) Homing Side.

Project1 > PLC_1 [CPU 1215C DC/DC/DC] > Technology objects > Axis_1 [DB1]

Function view | Parameter view

Basic parameters
General
Drive
Extended parameters
Mechanics
Position limits
Dynamics
General
Emergency stop
Homing
Active
Passive

Active

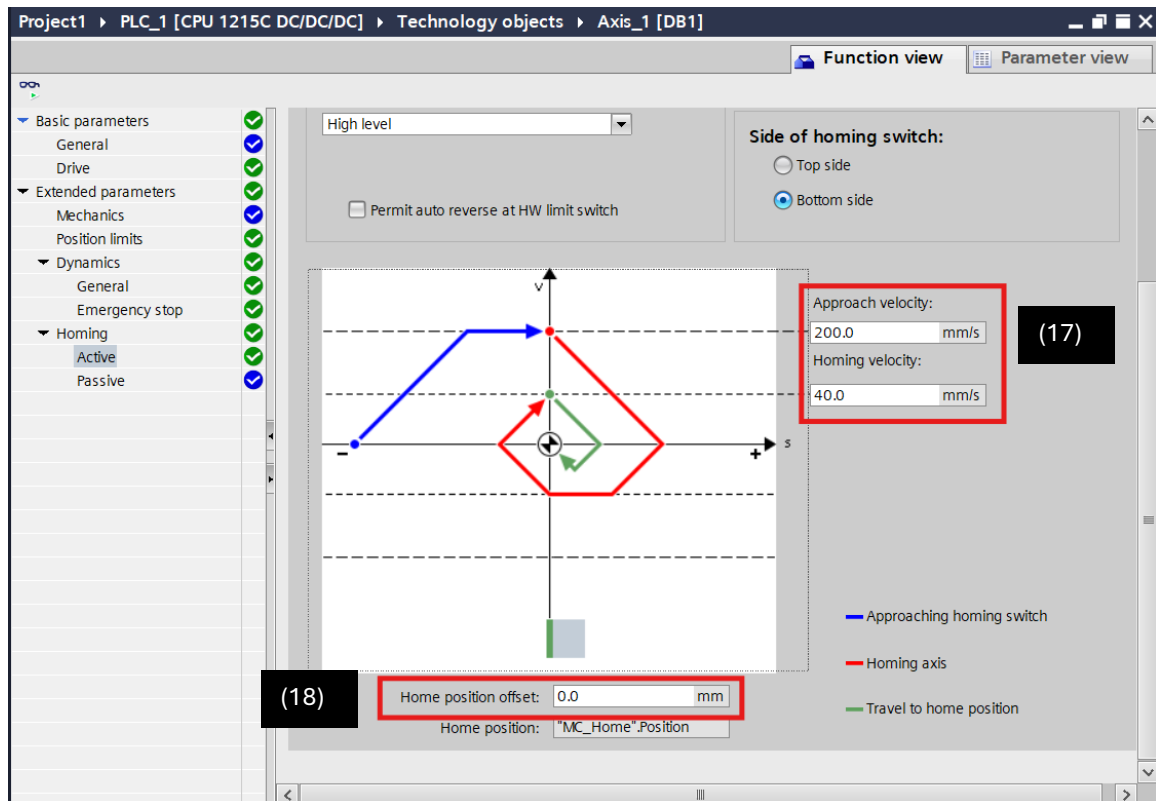
Digital input homing switch (14)
Homing-/Proximity switch: Axis_1_Homing switch %I0.2
Select level: High level
Permit auto reverse at HW limit switch

Approach/homing direction: (15)
Positive direction
Negative direction

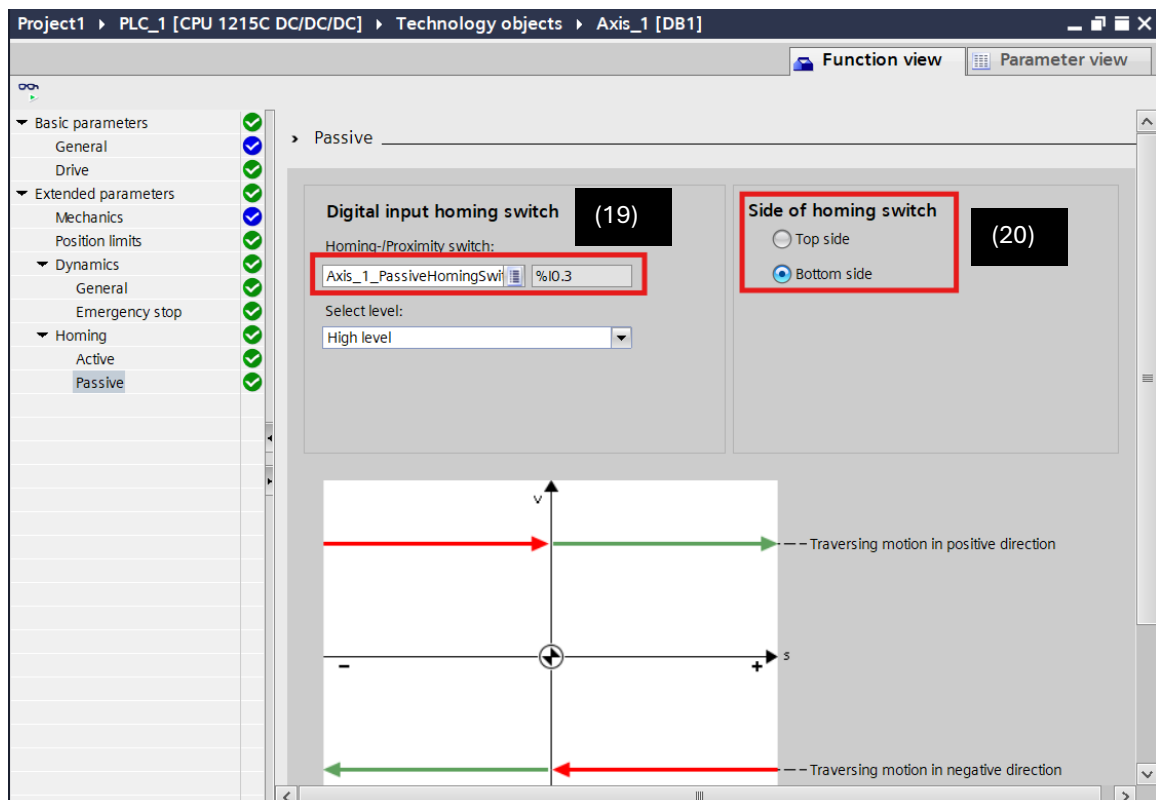
Side of homing switch: (16)
Top side
Bottom side

Approach velocity: 200.0 mm/s
Homing velocity: 40.0 mm/s

10. Set (17) Homing Speed and (18) Homing Offset.

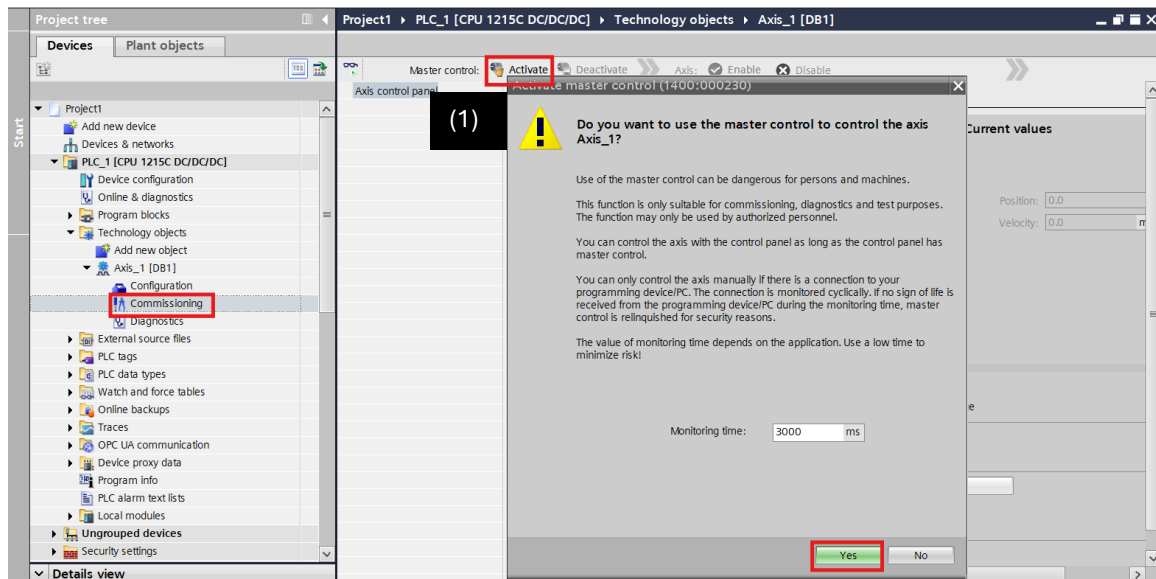


11. In the Passive Homing section, configure (19) Homing Switch Address, choose (20) Homing Side.

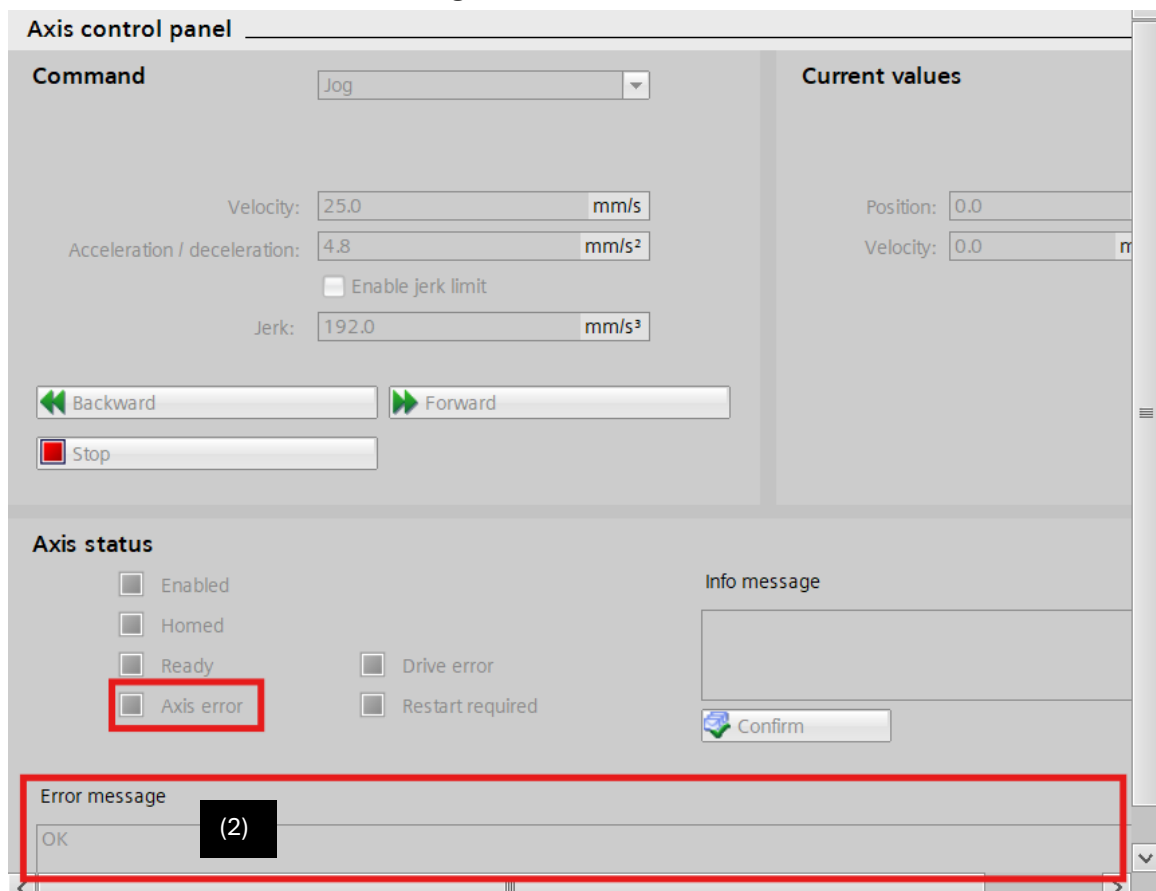


TIA Portal Axis Debugging

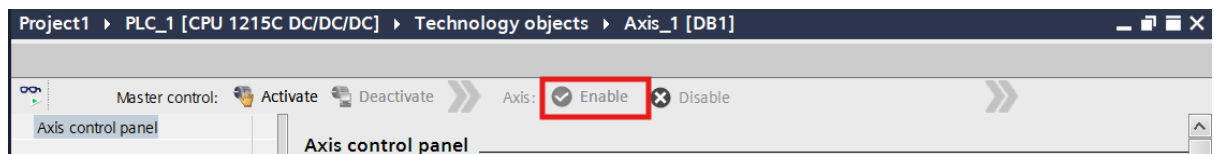
1. After downloading the program to the CPU, double-click 'Commissioning', then click (1) 'Activate'. A prompt will appear asking whether to control the axis—click 'Yes'.



2. In the Axis Status window, monitor the axis. If there are errors, check (2) Error Details and resolve them before enabling the axis.



3. Click Enable to activate the axis for debugging.



4. Once enabled, in (3) 'Command', select the motion type for the servo motor. In (4), control the motor (forward, reverse, stop). In (5), monitor the current position and speed of the axis.

