

MiSUMi

Linear motor actuator

E-RAM Series

EE100 Driver User Manual

Ver1.0

Thank you for purchasing our linear motor actuator.

This user manual is a supplement to the manufacturer's catalog, and its purpose is to provide users with more detailed and convenient usage instructions. We have attempted to ensure the accuracy and completeness of the content. Nevertheless, we recommend that users use the manufacturer's catalog as a guide.

Please take the time to read this manual carefully before use. Please keep it in a safe place so that you can view it whenever necessary.

List

One. Driver Overview	5
1.1 Manufacturer Information	5
1.2 Safety precautions	5
2. final	6
2.1 Main circuit	6
2.2 Control circuit	6
<input type="checkbox"/> I/O port definition	6
<input type="checkbox"/> I/O wiring diagram	7
3. Debugging	8
3.1 Software download and installation	8
<input type="checkbox"/> software download	8
<input type="checkbox"/> Software installation	8
3.2 Language settings	9
3.3 Communication between computer and driver	9
<input type="checkbox"/> final	9
<input type="checkbox"/> communication	9
3.4 Importing motor parameters	10
<input type="checkbox"/> Download parameter pack	10
<input type="checkbox"/> Importing parameter packs	11
<input type="checkbox"/> Motor Phase Finding	14
3.5 Commissioning	15
<input type="checkbox"/> Preliminaries	15
<input type="checkbox"/> Waveform acquisition	16
<input type="checkbox"/> Settlement time analysis	16
<input type="checkbox"/> Parameter Debugging	
<input type="checkbox"/> Check debugging results	18
3.6 Control	
<input type="checkbox"/> Select mode	19

□	Electronic gear ratio settings.....	19
□	I/O settings	20
□	Change of driving direction.....	21
□	Top computer matching	22
	3.7 Parameter backup & parameter recovery	22
□	Parameter backup	22
□	Parameter recovery	23

1. Driver Overview

1.1 Manufacturer Information

Driver manufacturer: Servotronix

Manufacturer's official website:<https://www.servotronix.cn/en>

The manufacturer model number table is as follows.

Misumi model number	Servotronix model number
EE100	CDHDE-0102AEB

1.2 Safety precautions

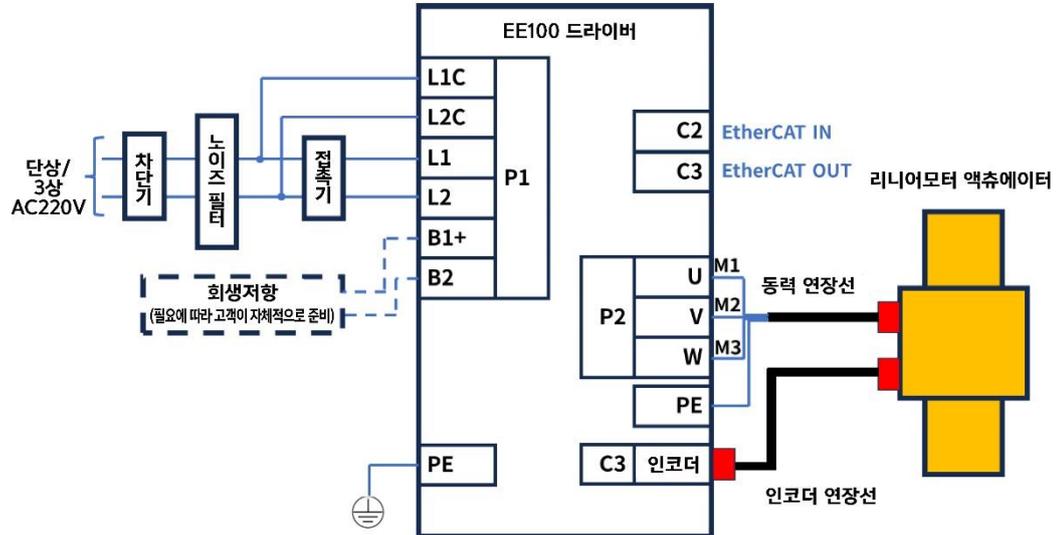
Before installation, please be sure to download and read all relevant materials from the manufacturer's website carefully, and use and operate the product exactly as required to ensure safety and accuracy.

Please use caution as improper handling may result in injury and/or equipment damage.

2. finaldo

2.1 Main circuit

Driver rated input current 10A, maximum current 30A



2.2 Control circuit

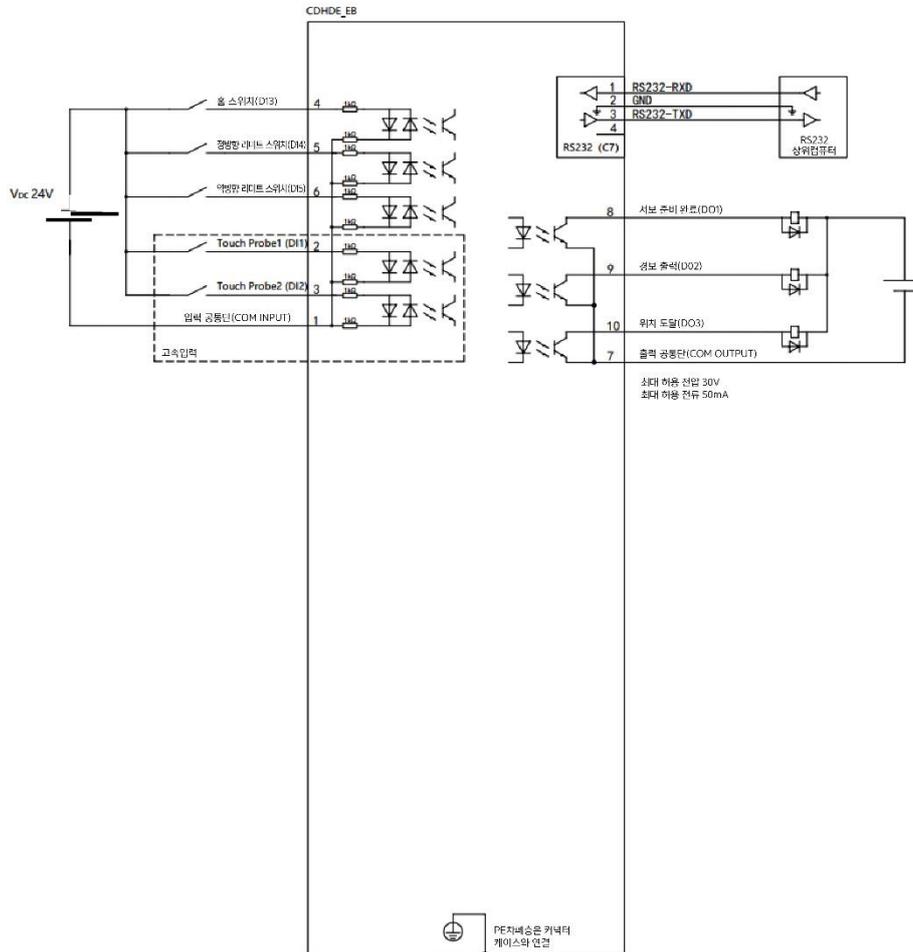
● I/O port definition

C4: I/O port 1394 10PIN			
On	input common end	6	Digital input 5
2	One touch digital input 1	7	output common end
3	One touch digital input 2	8	digital output 1
4	Digital input 3	9	digital output 2
5	digital input 4	10	Digital output 3

● I/O wiring diagram

! Pin 1 is connected to 24V or 0V, depending on whether the input method is sinking or sourcing.

The image below shows the wiring method for sinking input.



3. Debugging

3.1 Software download and installation

● software download

Download from the manufacturer's website.

Download link:<http://m.servotronix.com.cn/col.jsp?id=197>

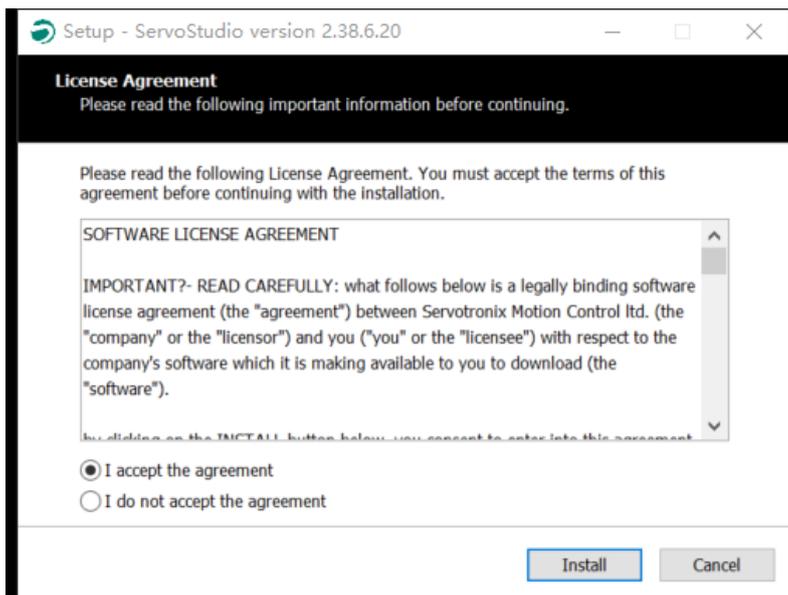
All software versions ServoStudioSetup_2_38_6_20 and higher are available.



● Software installation

 ServoStudioSetup_2_38_6_20.exe Double-click to complete the installation,

 ServoStudio.exe Double click to open the software and you are ready to use it.

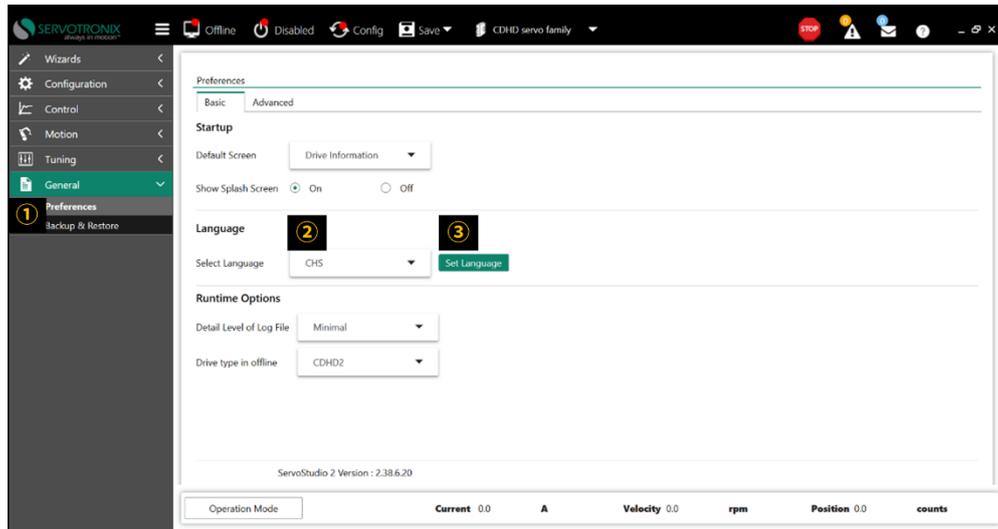


3.2 Language settings

①Click <Preferences>, ②You can change it to <ENG> or <CHS>. If you want to change the language, select the language you want to change , Click ③<Set Language>.

If you close the program and turn it back on, it will change to the set language.

! When selecting a language, CHS represents Chinese and ENG represents English.



3.3 Communication between computer and driver

● final

① Connect the computer and the driver with a communication cable, then turn on the driver.

! Before turning on the power, be sure to check that all wiring is correct.

! Communication cables can be purchased from MISUMI, and the model number is USB-AM-MBM-2.

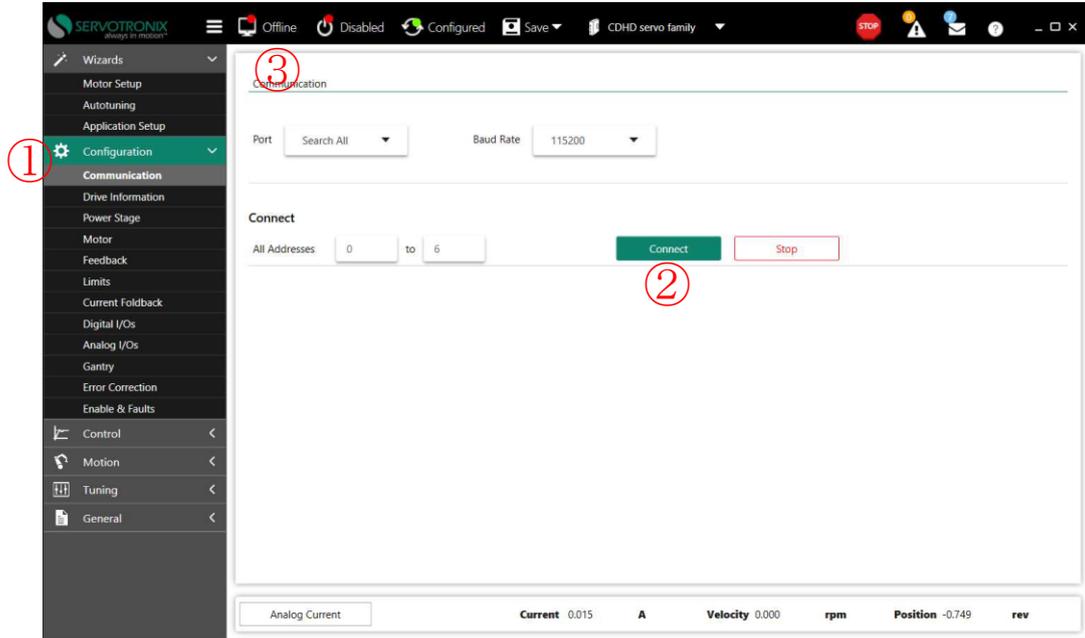


● communication

1 If communication is successful by clicking <Communication> and clicking ②<Connect>,

③<Disconnected> will appear.  Online changes to .

! If communication is not possible, reconnect the communication cable, reboot the computer, turn the driver power back on, and replace the communication cable.



3.4 Importing motor parameters

● Download parameter pack

You can download the parameter pack from the MISUMI website or request it from MISUMI customer service staff.

Select the parameter pack according to the model number of the actuator you purchased.

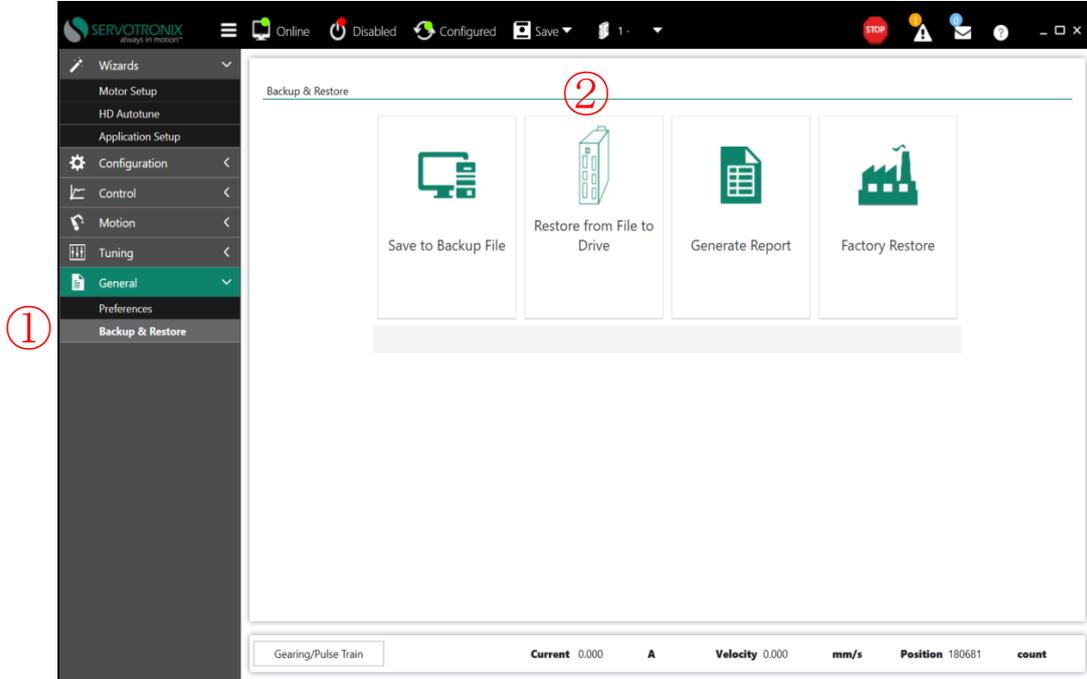
Example) If the model number of the linear motor actuator is E-RAM14-S-600-EE100-C3, the corresponding parameter pack is E-RAM14-S-EE100.

E-RAM6-S		
E-RAM8-M		
E-RAM8-S	E-RAM14-S-DA60.ssv	2
E-RAM10-M	E-RAM14-S-DE60.ssv	2
E-RAM10-S	E-RAM14-S-EA100.ssv	2
E-RAM12-M	E-RAM14-S-EE100.ssv	2
E-RAM12-S	E-RAM14-S-PA45.prm5	2
E-RAM14-M	E-RAM14-S-PE45.prm5	2
E-RAM14-S	서보트로닉스 DE드라이버용 EtherCA...	2
E-RAM17-M	서보트로닉스 EE드라이버용 EtherCAT...	2
E-RAM17-S	파나소닉 PE드라이버용 EtherCAT_ESI	2
E-RAM19-M		
E-RAM19-S		

● Importing parameter packs

Operate in the following order:

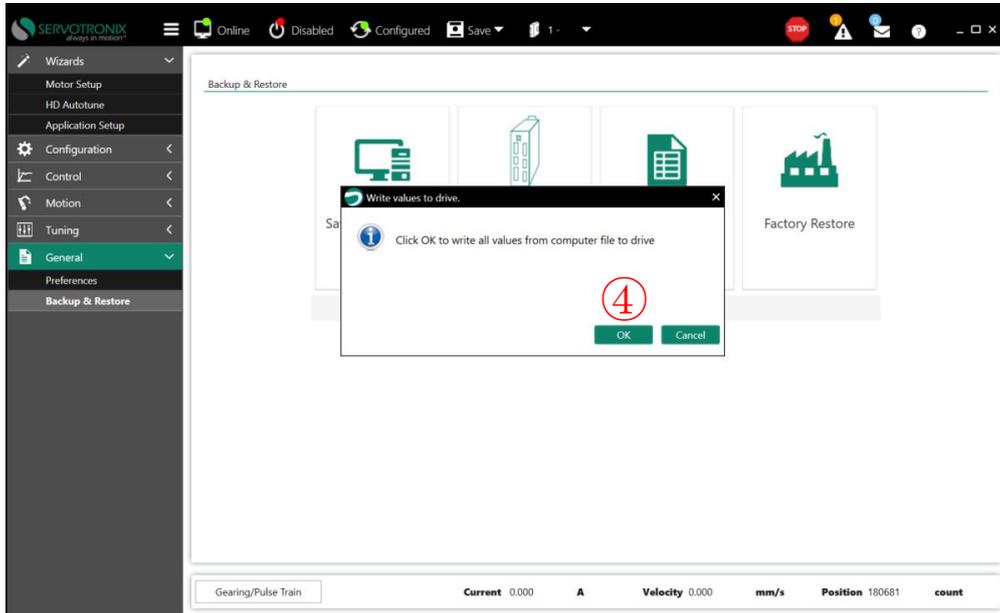
- 1 Click <Backup & Restore>, and click ②<Restore from File to Driver>.



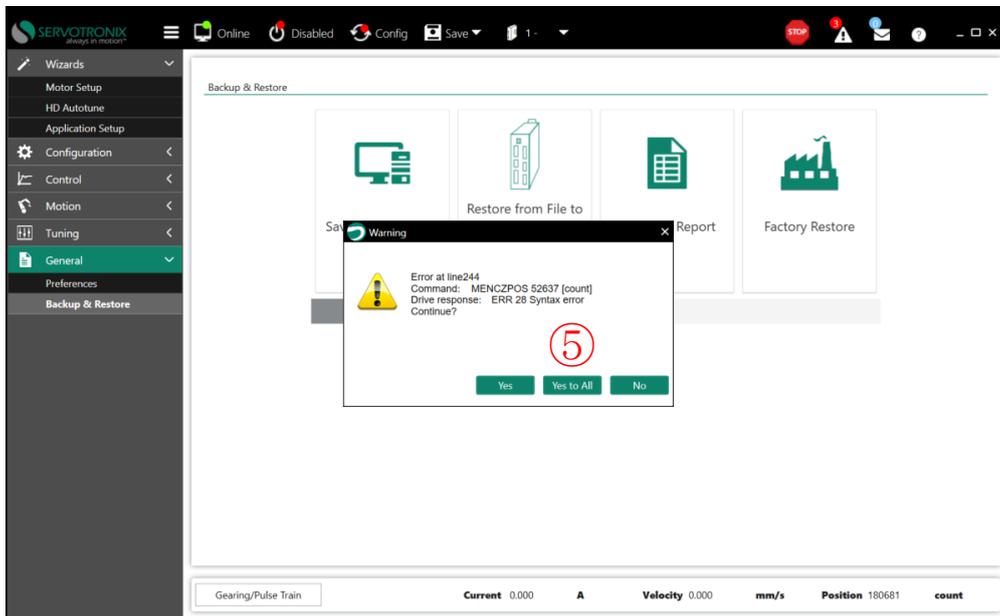
- ③ Double-click the parameter pack saved locally.

이름	수정한 날짜	유형	크기
E-RAM14-S-EE100.ssv	2024-02-29 오후 7:58	SSV 파일	7KB

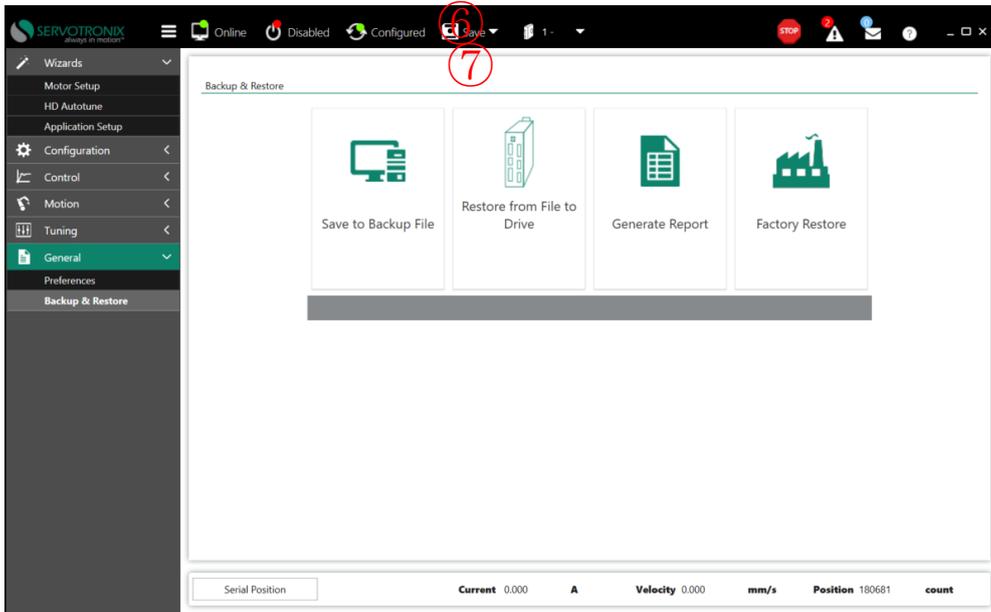
④ Click <Confirm>.



⑤ Click <All>.

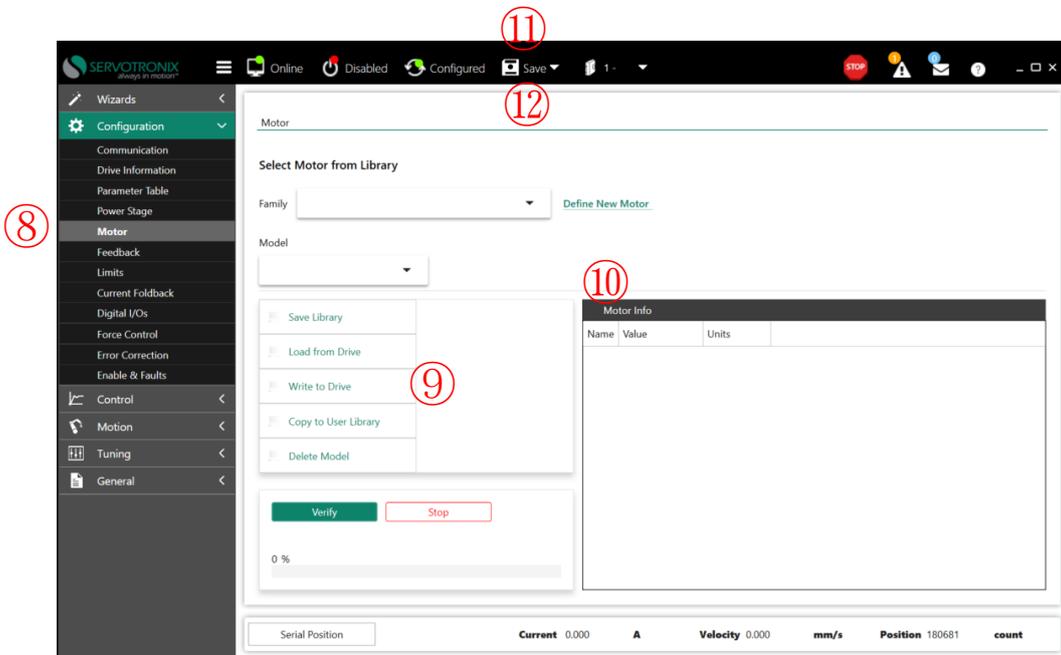


Click ⑥<Save>, and click ⑦<Save to Driver>.



Power off the driver, wait 5 seconds, and then power it back on to allow the computer to communicate with the driver.

Click ⑧<Motor>, click ⑨<Read from Driver>, check ⑩<Motor Information> to determine whether the parameters have been imported correctly, click ⑪<Save>, and click ⑫<Save as Driver>. do.



● Motor Phase Finding

First, turn off the driver and push the slider on the actuator to the middle position. Then turn it on to allow the driver to communicate with your computer.



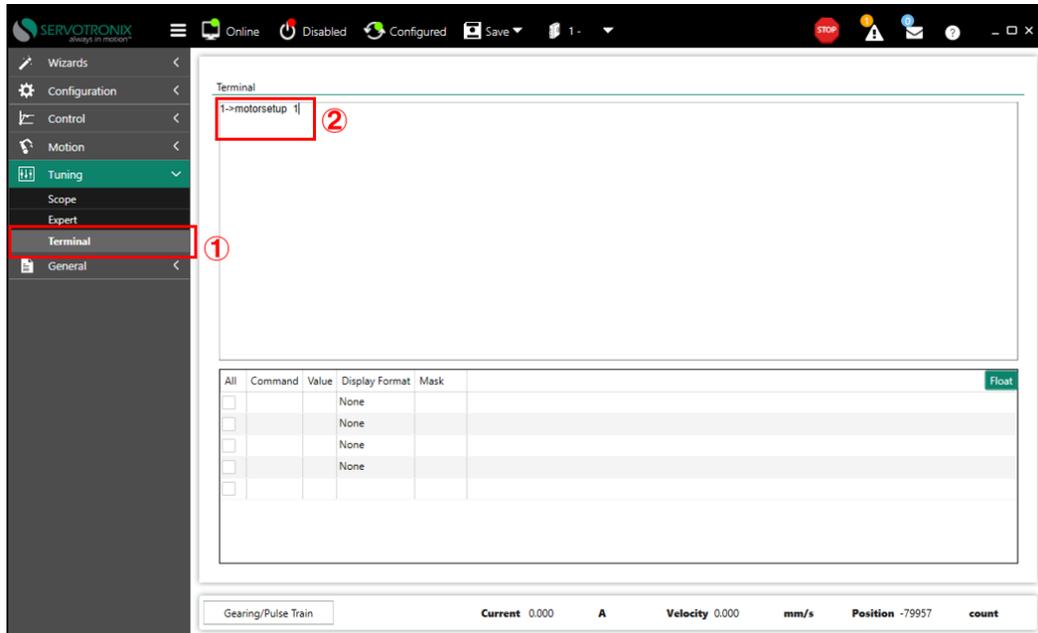
1 Click <Terminal>, enter motorsetup 1 in ② and press the Enter key.

At this time, the driver is activated ( Disabled go  Enabled), the slider will slowly move back and forth about 20 mm, and the activation will automatically break after success.

! Type motorsetup, press the space bar, and then type 1.

! If the slider does not move, check the following:

- 1) Check whether external activation is set for I/O.
- 2) Whether the driver has any other alarms



3.5 Commissioning preparation

● Preliminaries

- 1 Click <Scope> and set ② to <Serial Position>.
- ③ Set <Position>, <Velocity>, <Acc>, and <Dec>.
- ④ Change the name in <Trigger Setup> to <V>.
- ⑤ Change <Level> to <10>.
- ⑥ Change <Pre-Points> to <10>.
- ⑦ Select the variables to record in <Record Variables>.

! Confirm that the interface mode is <Serial/Pulse>, and refer to 3.6 for instructions.

! Position unit: 1counts=1µm Example) To move 10mm, enter 10000 counts.

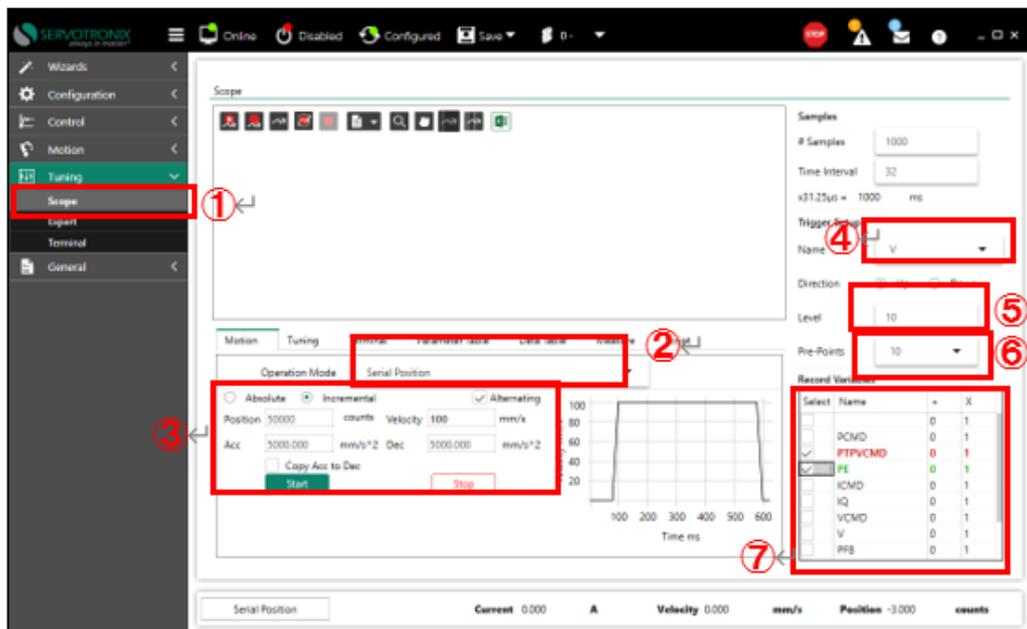
! Common variables include:

PTPVCMD position command speed

PE position error

ICMD current command

V actual speed

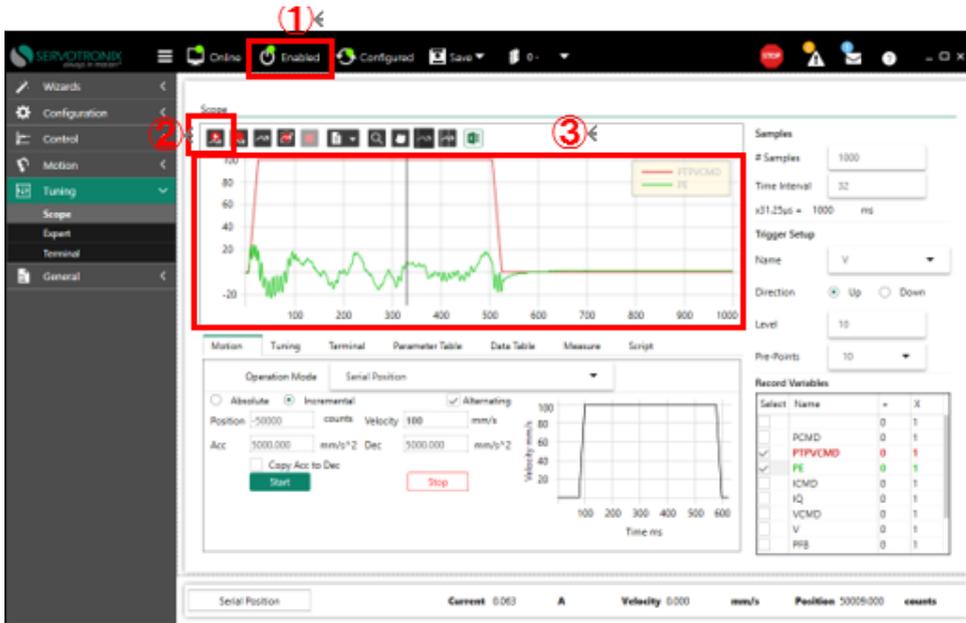


● Waveform acquisition

- 1  When you click , the button changes to <Start> and then the driver is activated.
- 2  When you click , the actuator starts operating, and when operation is completed,
 ③<Scope> is displayed.

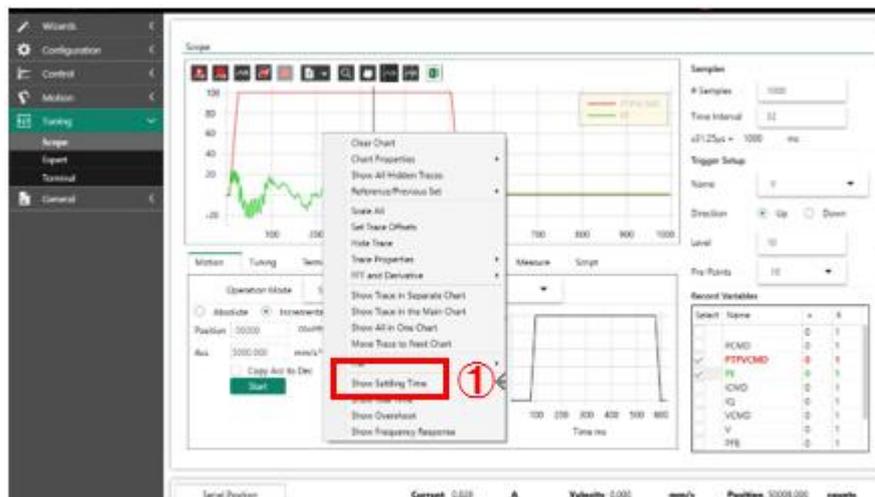
! It is normal for the actuator to emit an electromagnetic sound after activation.

! When you are finished driving, be sure to disable it for safety.



● Settling Time Analysis

Place the mouse at a random location on the scope, right-click, and select ①<Show Settling Time>.



- ① Set <PVPVCMD> in <Command>, and select <PE> in ②<Response>.

③Set the position accuracy error (unit μm) in <Acceptable Range>, and click ④<Show>.

⑤The required settling time is displayed in <Setting Time>.

Example) If Acceptable Range is set to 5 and Setting Time is displayed as 95, it indicates that the position accuracy error is within $5\mu\text{m}$ and the required settling time is 0.095 seconds.



● Gain Tuning

Adjust parameters according to the waveform to get the actuator in optimal condition.

! Debugging tips:

By adjusting the stiffness level, you can increase the responsiveness of the actuator or suppress module vibration and noise.

1 Click <Tuning> to set ②<Gain Level>.



● Check debugging results

After collecting the waveform again, the settling time is analyzed.

Example) After increasing the rigidity level from 26 to 29, the position accuracy error is within 5 μm , and the required correction time has been changed from 0.095 seconds to 0 seconds.

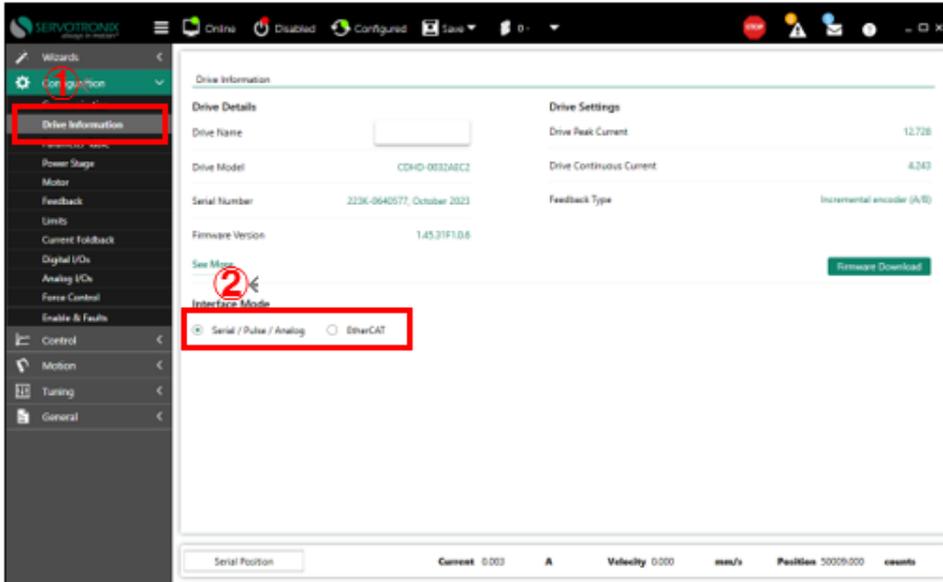


3.6 Control

- mode select

1 Click <Drive Information> and select ②<Interface Mode> as <EtherCAT>.

! For commissioning, change to <Serial/Pulse>.

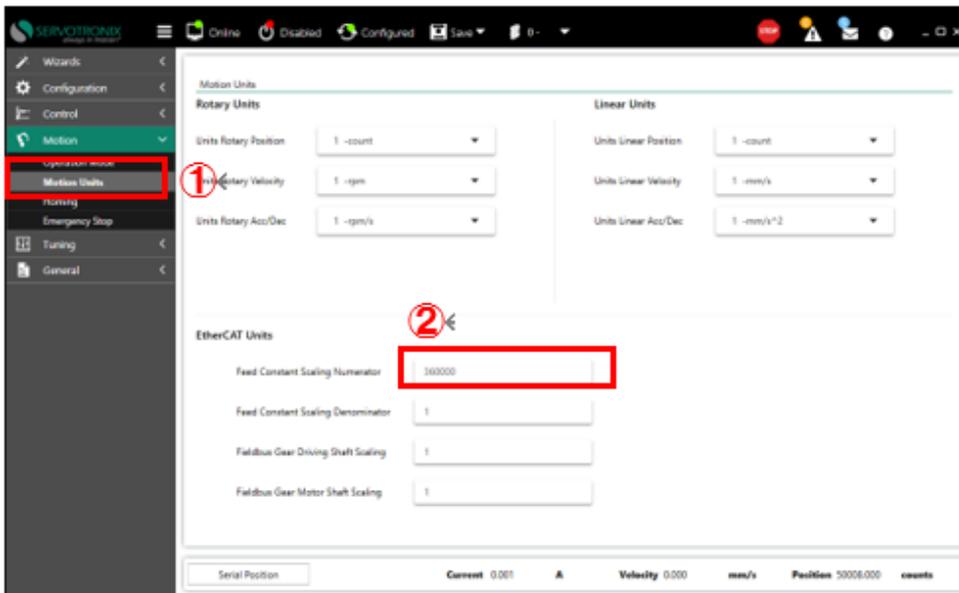


- Electronic gear ratio settings

1 Click <Motion>, and set ②<Feed Constant Scaling Numerator>.

Formula: Actual travel distance = command pulse x (unit conversion numerator/20000) x 0.001mm

! Be sure to press the Enter key after setting the parameters.



● I/O settings

Click ①<Digital I/O> to set ②<Mode> and ③<Polarity>.

! The <high level valid> polarity is NPN mode.

The screenshot displays the SERVOSETRONIX software interface for configuring digital I/Os. The left sidebar shows the 'Configuration' menu with 'Digital I/Os' selected. The main window is divided into 'Digital Inputs' and 'Digital Outputs' sections. In the 'Digital Inputs' section, the 'Mode' dropdown for all inputs is set to '-Idle' (circled 2), and the 'Polarity' dropdown for all inputs is set to 'Active High' (circled 3). The 'Digital Outputs' section shows 'Mode' dropdowns for Output 1-6 set to '-Idle' and 'Polarity' dropdowns set to 'Active High'. The 'Fault Relay Mode' is set to '-Close when no faults'. The status bar at the bottom shows 'Current 0.003 A', 'Velocity 0.000 mm/s', and 'Position 50008.000 counts'.

State	Name	Mode	Polarity	Connector
Input 1	Input 1	-Idle	Active High	C,3
Input 2	Input 2	-Idle	Active High	C,20
Input 3	Input 3	-Idle	Active High	C,31
Input 4	Input 4	-Idle	Active High	C,14
Input 5	Input 5	-Idle	Active High	C,34,F,F
Input 6	Input 6	-Idle	Active High	C,15,F,F
Input 7	Input 7	-Idle	Active High	M,3
Input 8	Input 8	-Idle	Active High	M,5
Input 9	Input 9	-Idle	Active High	M,8
Input 10	Input 10	-Idle	Active High	M,16
Input 11	Input 11	-Idle	Active High	M,7,F

State	Name	Mode	Polarity	Connector
Output 1	Output 1	-Brake Release Signal	Active High	C,2
Output 2	Output 2	-Stopped	Active High	C,35
Output 3	Output 3	-Idle	Active High	C,16,F
Output 4	Output 4	-Idle	Active High	M,7
Output 5	Output 5	-Idle	Active High	M,8
Output 6	Output 6	-Idle	Active High	M,18,F

● Change of driving direction

- ① Click <Tuning>, enter dir in ②<Terminal>, then press Enter to check ③<Result>.
- ③ If <Result> is 0, enter dir 3 in ②<Terminal>.
- 3 If <Result> is 3, enter dir 0 in ②<Terminal>.
- 4 Click <Config>.

! Type dir, followed by a space, then 3 or 0. Otherwise, an error will occur.

The screenshot shows the SERVOTRONIX software interface. The sidebar on the left has 'Terminal' highlighted with a red box. The terminal window contains the following text:

```
Terminal  
-->dir ②  
0  
-->dir ③  
-->mpbase  
④
```

Below the terminal window is a table with the following columns: All, Command, Value, Display Format, Mask, and a 'Float' button. The table contains several rows with 'None' in the Value column.

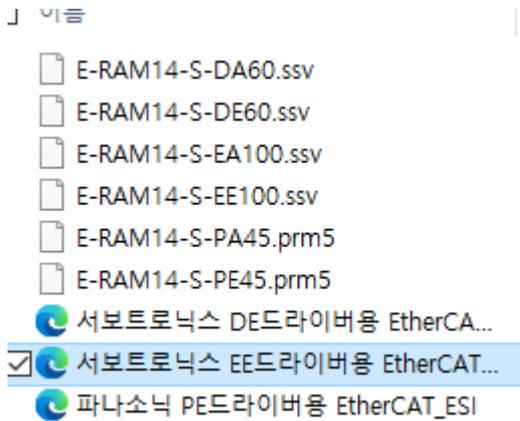
At the bottom of the interface, the status bar displays: Serial Position, Current 0.017 A, Velocity 0.000 mm/s, and Position 50008.000 counts.

● Top computer matching

Please download and use the file matching the parent computer from the following address.

Download link: https://www.misumi.com.cn/guide/doc/Motor_Data.zip

Select the adaptive file according to the model number of the actuator you purchased.

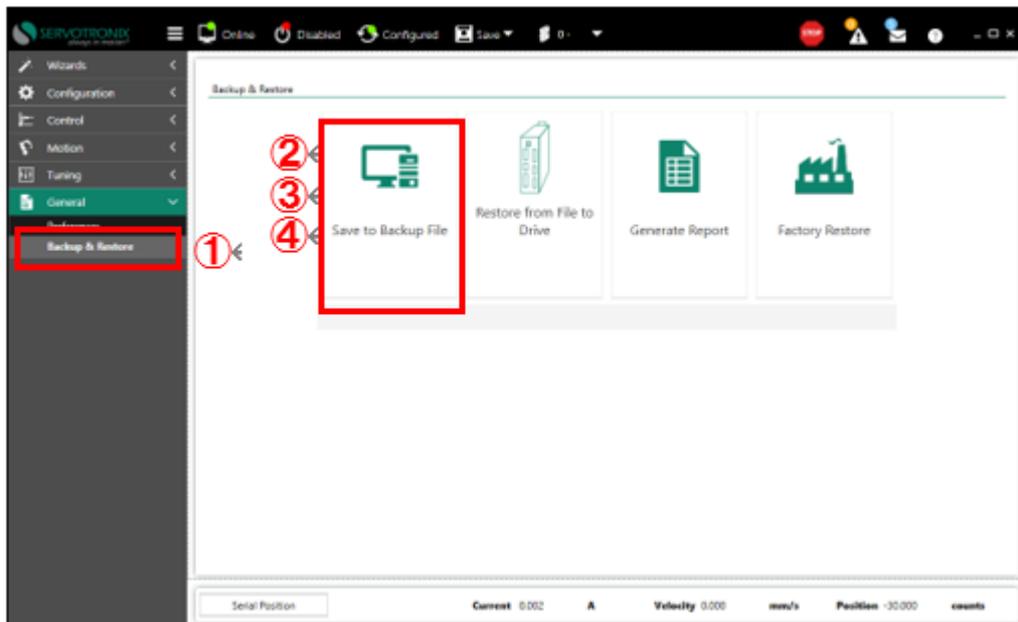


3.7 Parameter backup & parameter recovery

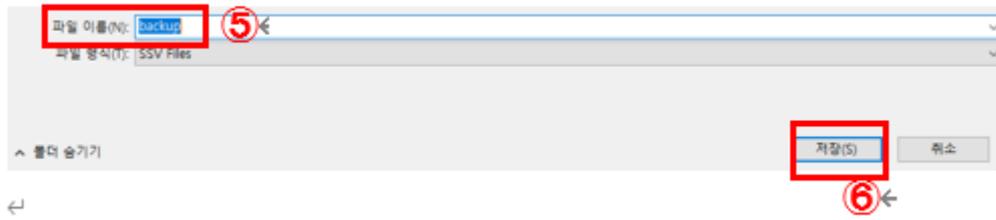
● Parameter backup

Click ①<Backup & Recovery>, click ②<Save>, then click ③<Save to Driver>,</p></div>

④Click <Save to backup file>.



Enter the file name in ⑤ and click ⑥<Save>.



● Parameter recovery

For recovery method, please refer to <3.4 Importing Motor Parameters>.

The differences are as follows:

1. The parameter pack is changed to the saved parameter pack.
2. No need to do motor phase search.