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

- I/O port definition 6
- I/O wiring diagram 7

3. Debugging 8

3.1 Software download and installation 8

- software download 8
- Software installation 8

3.2 Language settings 9

3.3 Communication between computer and driver 9

- final 9
- communication 9

3.4 Importing motor parameters 10

- Download parameter pack 10
- Importing parameter packs 11
- Motor Phase Finding 14

3.5 Commissioning 15

- Preliminaries 15
- Waveform acquisition 16
- Settlement time analysis 16
- Parameter Debugging .....
- Check debugging results 18

3.6 Control .....

- 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

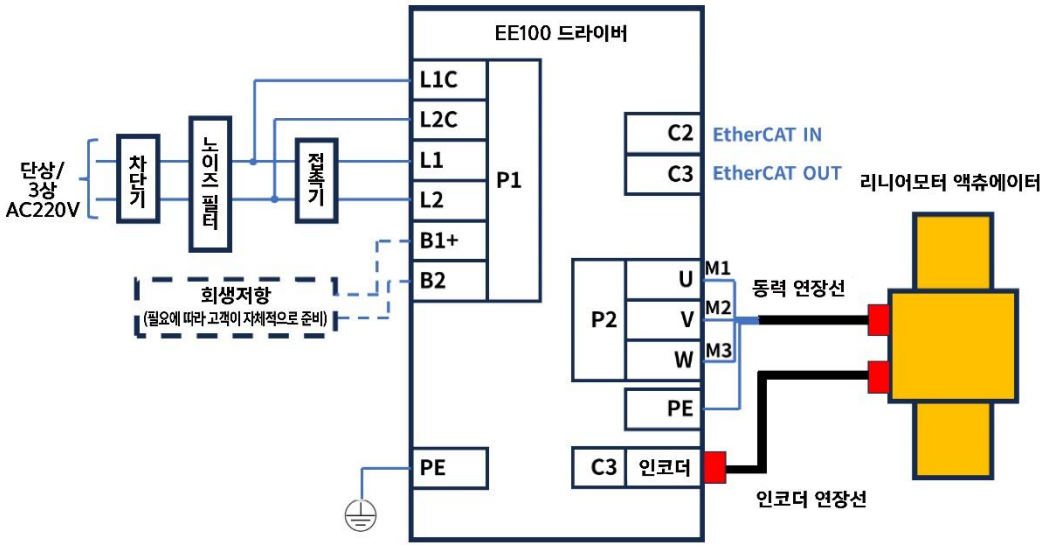
Before installation, please be sure to download and read all relevant materials from the manufacturer's website carefully, and use and operate the product exactly as required to ensure safety and accuracy.

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

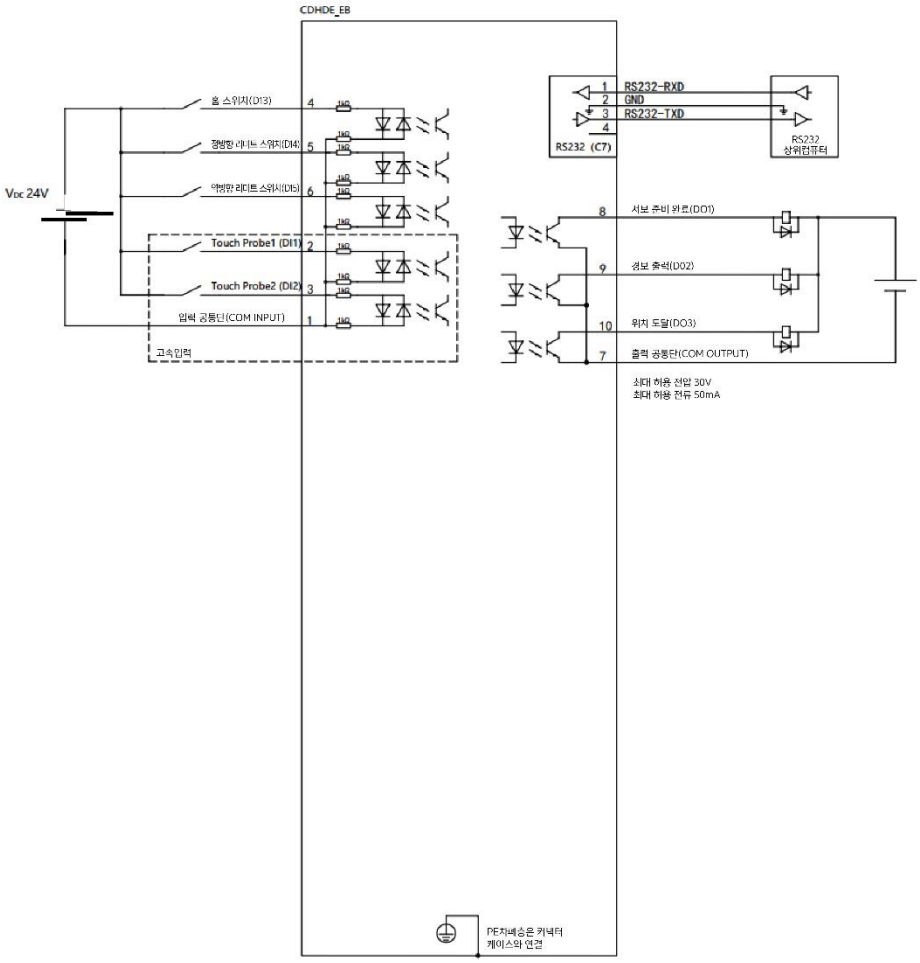
● I/O port definition

C4: I/O port 1394 10PIN			
One	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

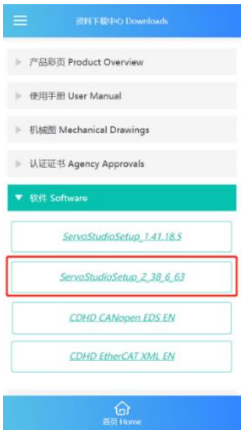
3.1 Software download and installation

- **software download**

Download from the manufacturer's website.

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

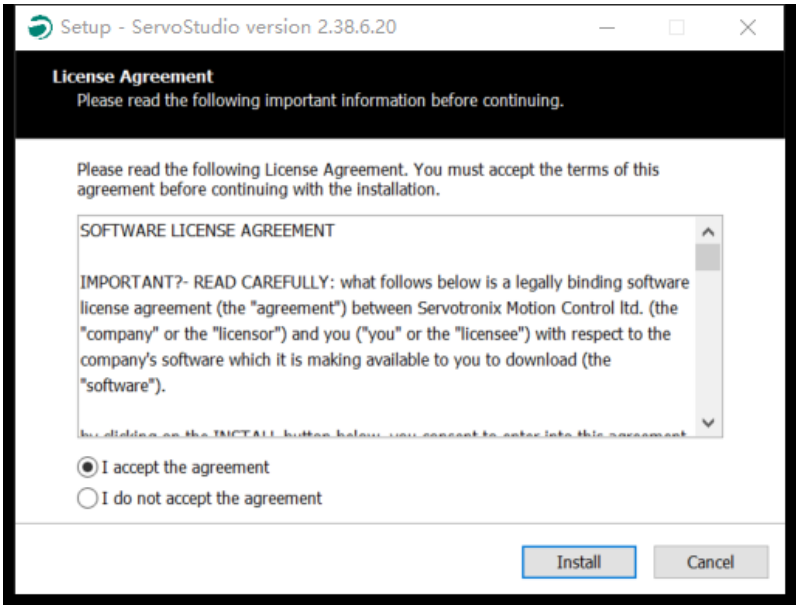
All software versions ServoStudioSetup_2_38_6_20 and higher are available.



- **Software installation**

ServoStudioSetup_2_38_6_20.exeDouble-click to complete the installation,

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

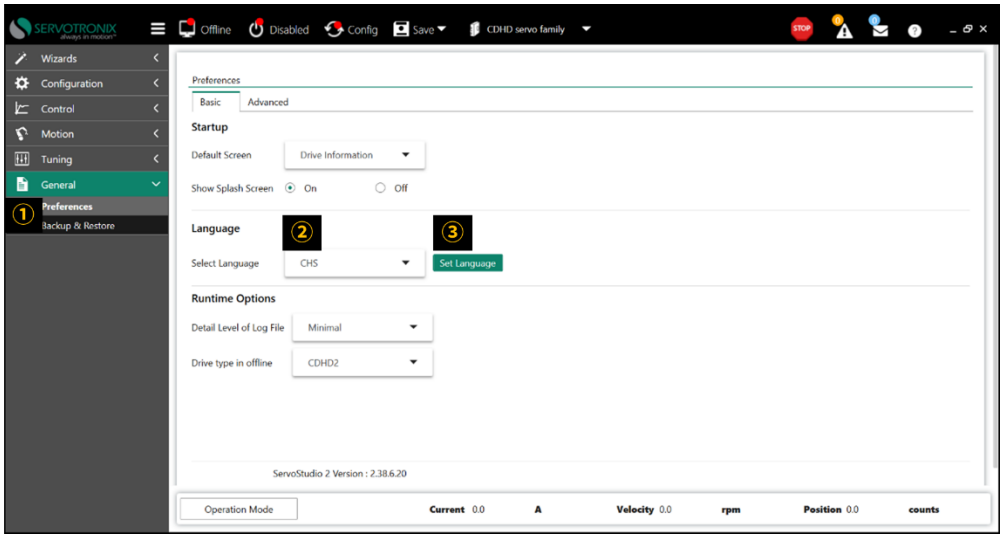


3.2 Language settings

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.

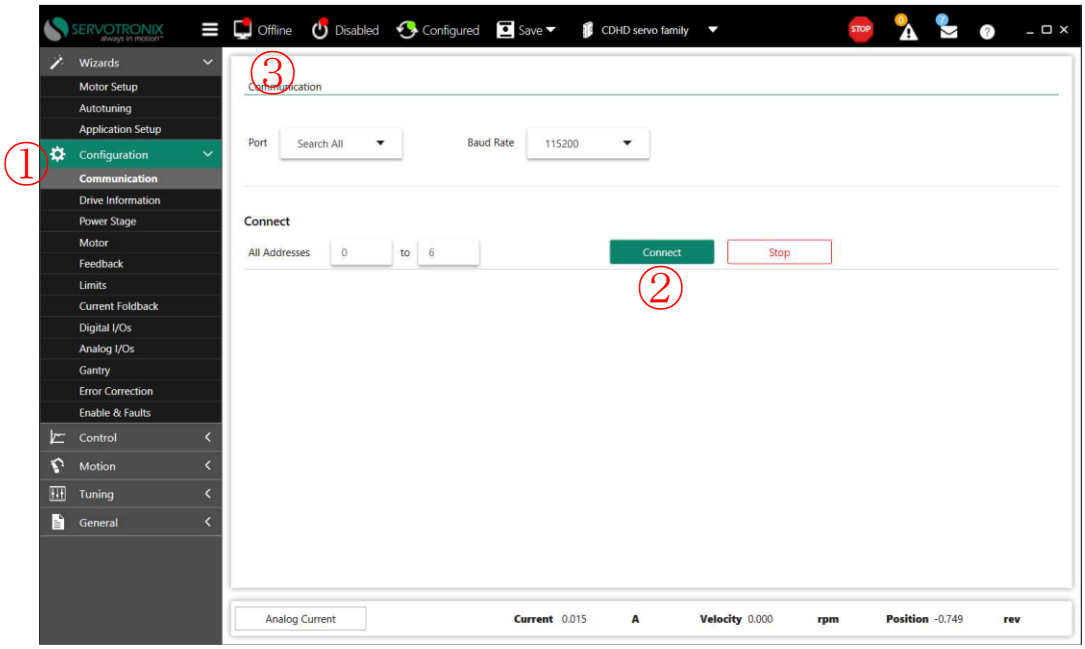
! Before turning on the power, be sure to check that all wiring is correct.

! 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.



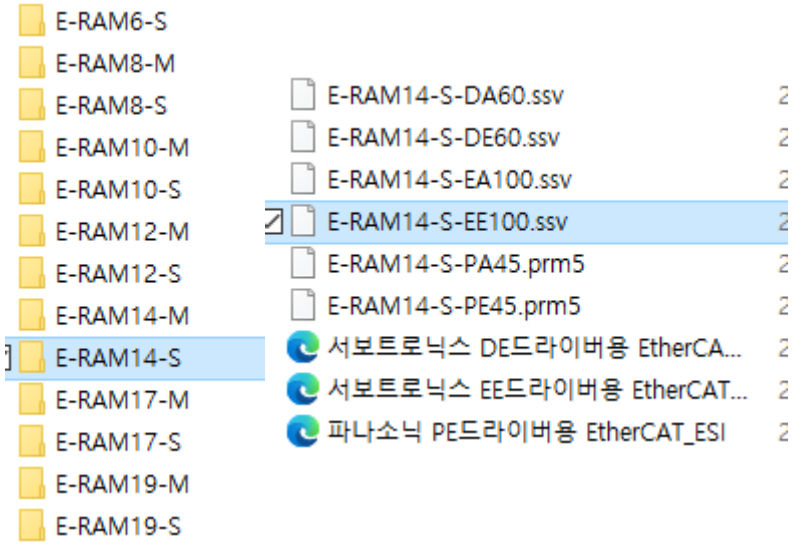
3.4 Importing motor parameters

● 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.

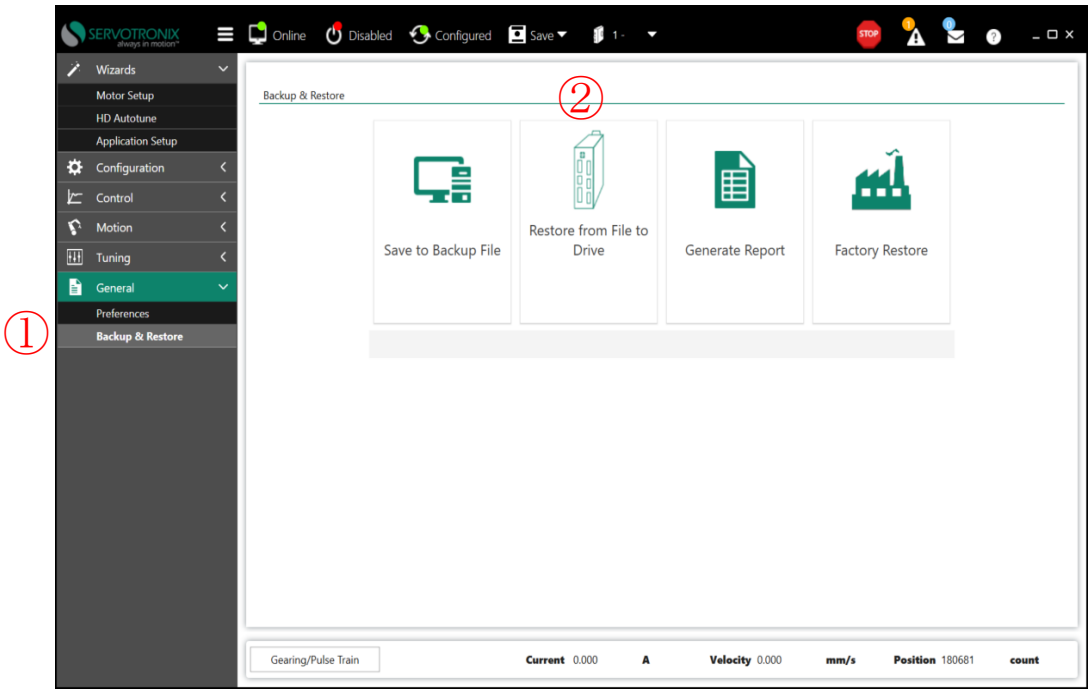
Example) If the model number of the linear motor actuator is E-RAM14-S-600-EE100-C3, the corresponding parameter pack is E-RAM14-S-EE100.



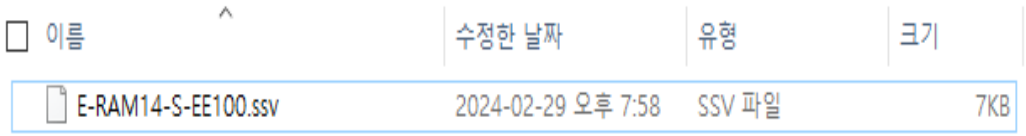
● Importing parameter packs

Operate in the following order:

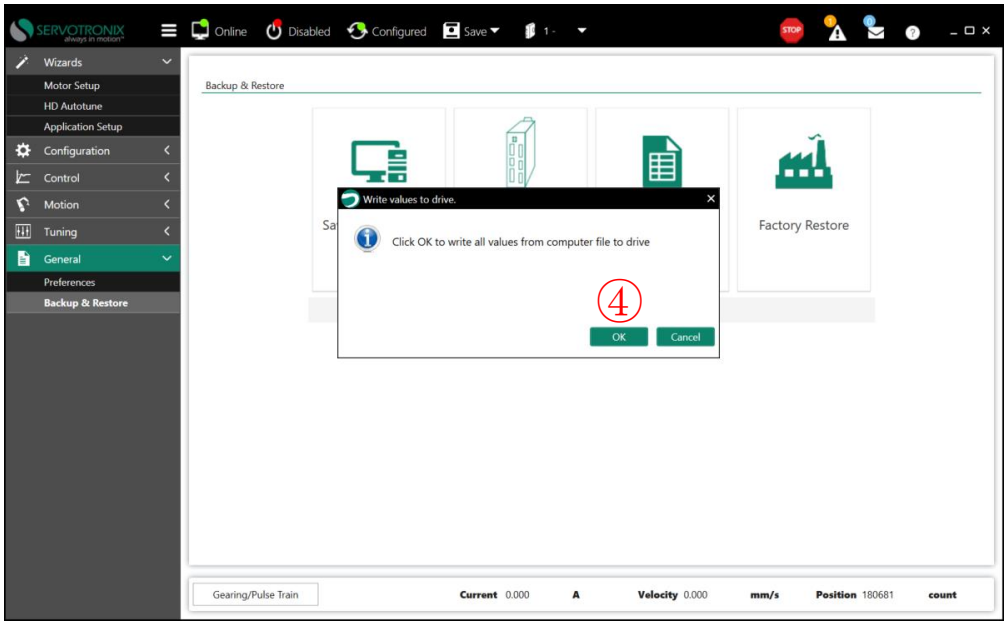
1 Click <Backup & Restore>, and click ②<Restore from File to Driver>.



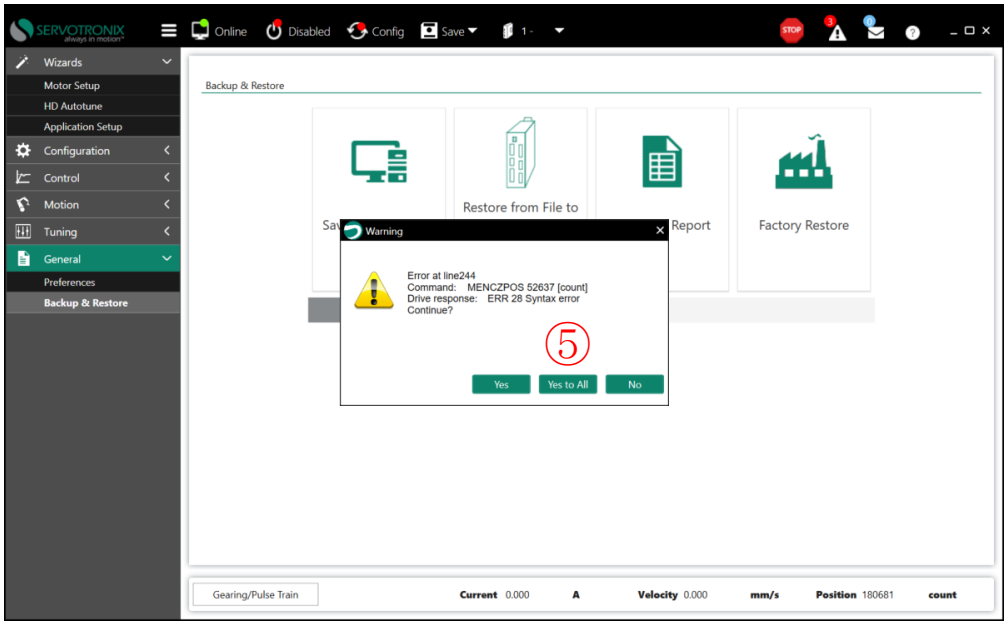
③Double-click the parameter pack saved locally.



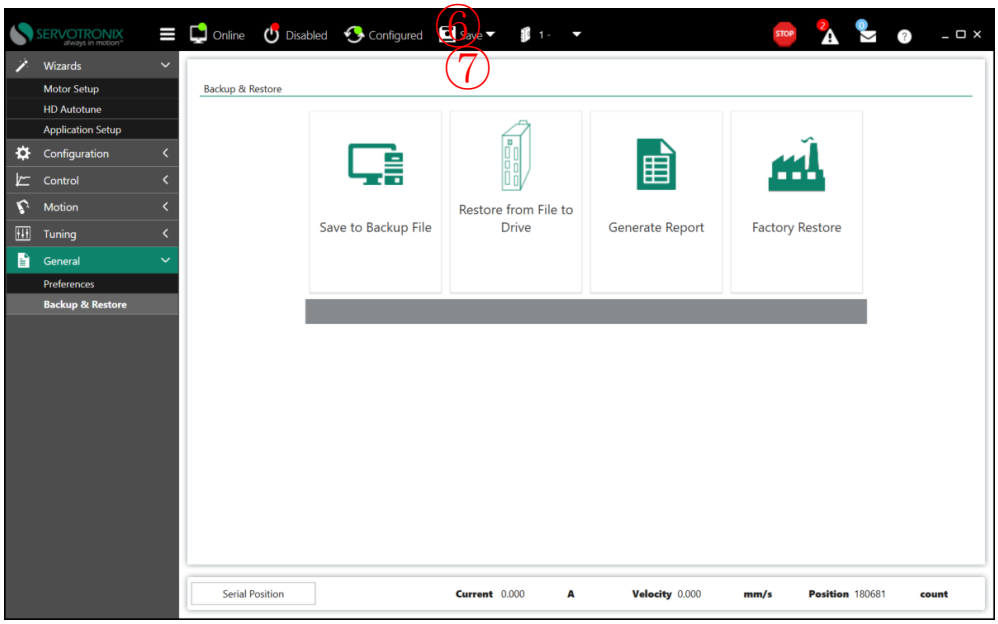
④Click <Confirm>.



⑤Click <All>.

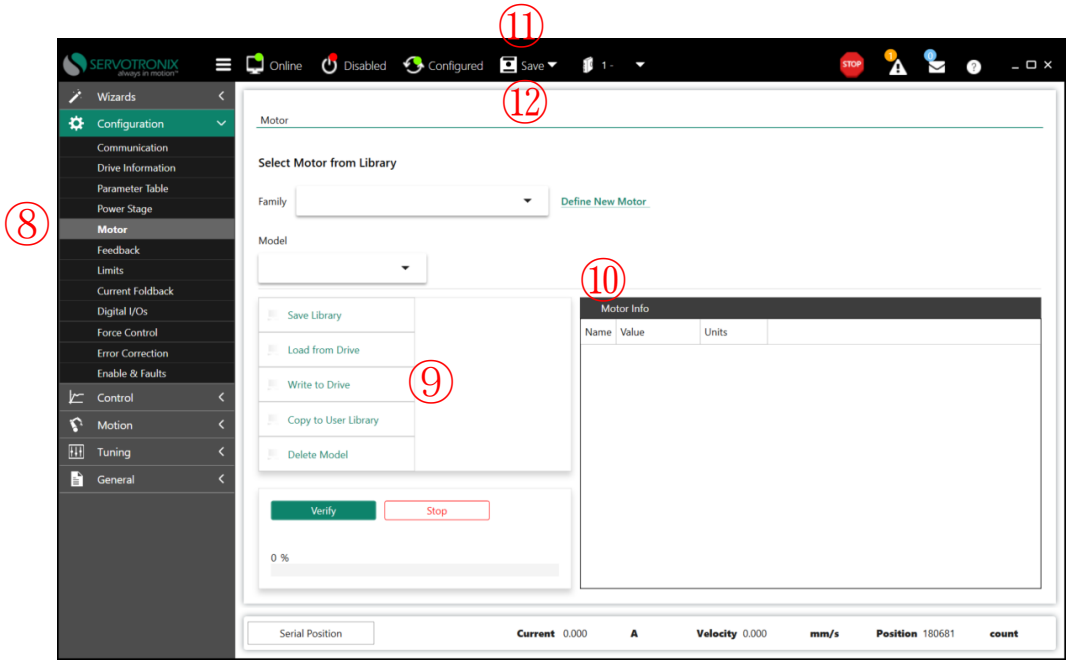


Click ⑥<Save>, and click ⑦<Save to Driver>.



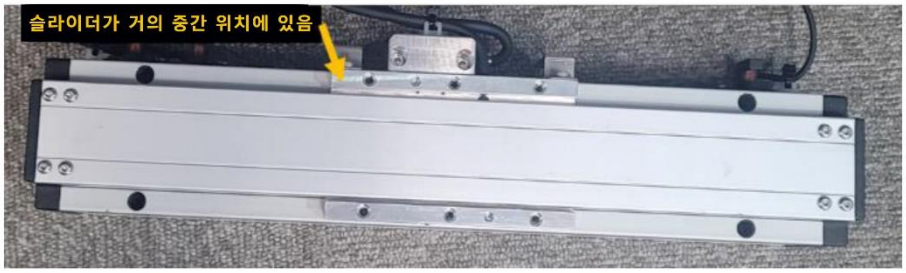
Power off the driver, wait 5 seconds, and then power it back on to allow the computer to communicate with the driver.

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.

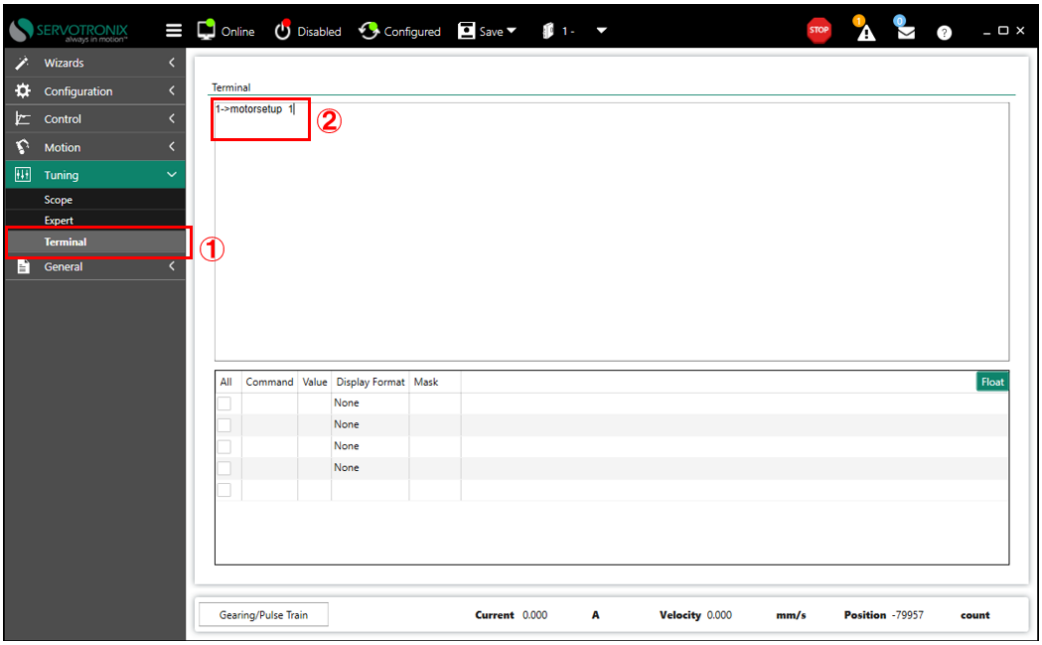
At this time, the driver is activated (Disabled go Enabled), the slider will slowly move back and forth about 20 mm, and the activation will automatically break after success.

! 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>,

③Set <Position>, <Velocity>, <Acc>, and <Dec>,

④Change the name in <Trigger Setup> to <V>, ⑤Change <Level> to <10>, ⑥Change <Pre-Points> to <10>.

⑦Select 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.

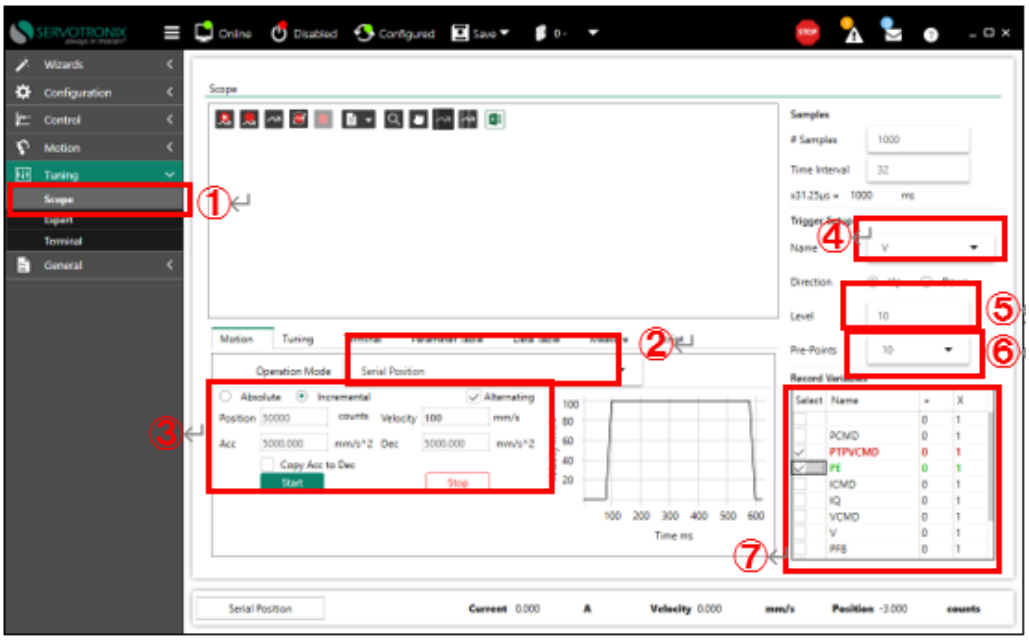
! Common variables include:

PTPVCMD position command speed

PE position error

ICMD current command

V actual speed



● Waveform acquisition

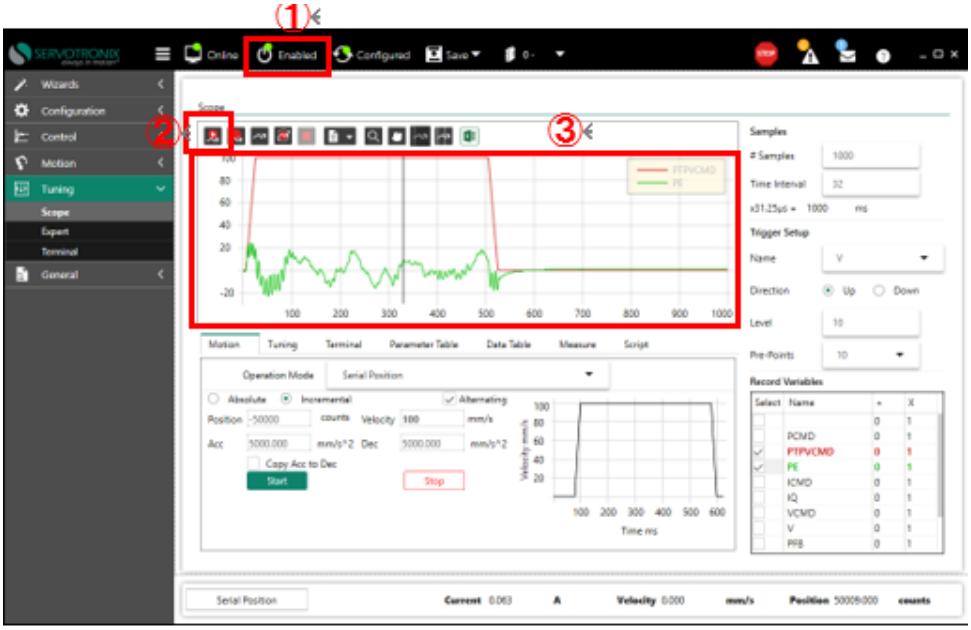
1

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.

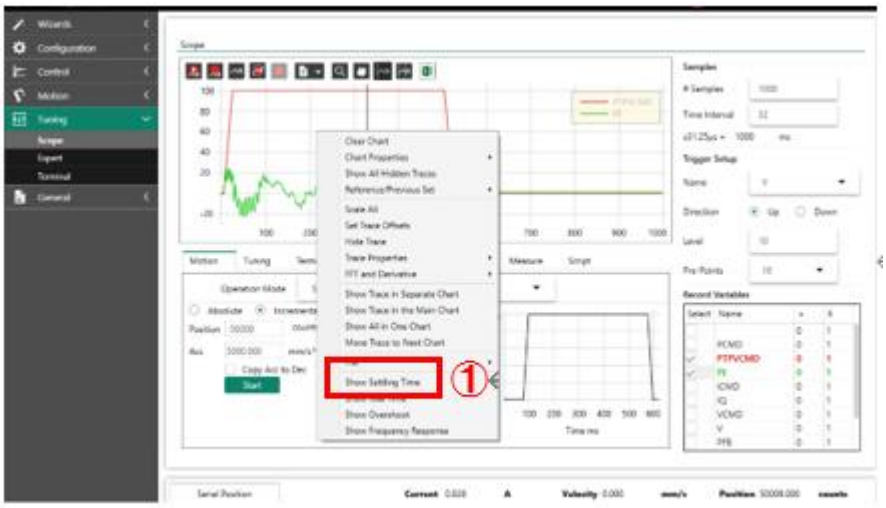
! It is normal for the actuator to emit an electromagnetic sound after activation.

! 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 5μm 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:

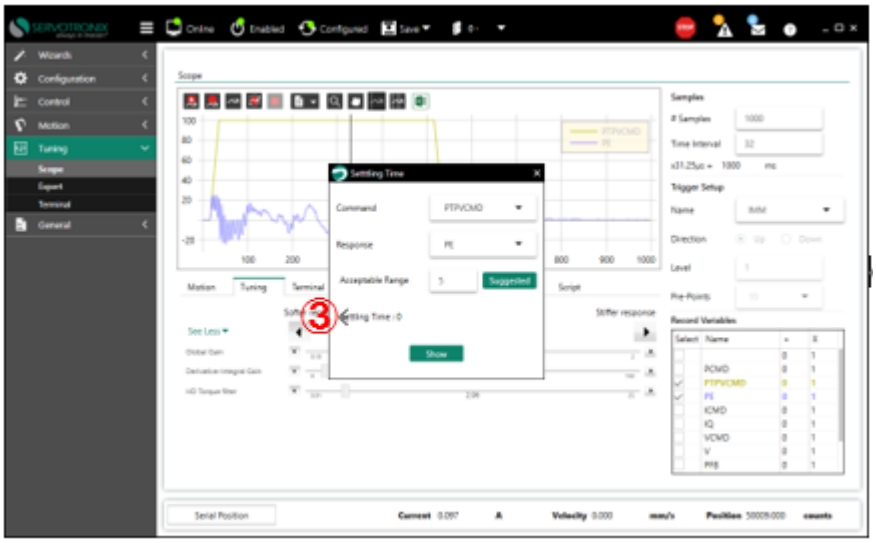
By adjusting the stiffness level, you can increase the responsiveness of the actuator or suppress module vibration and noise.

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.

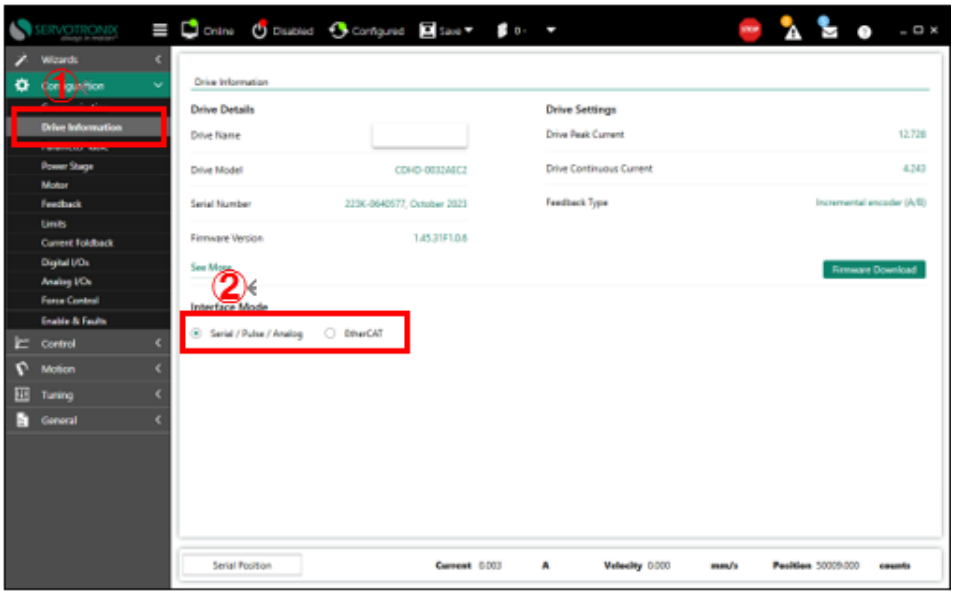


3.6 Control

● mode select

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

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

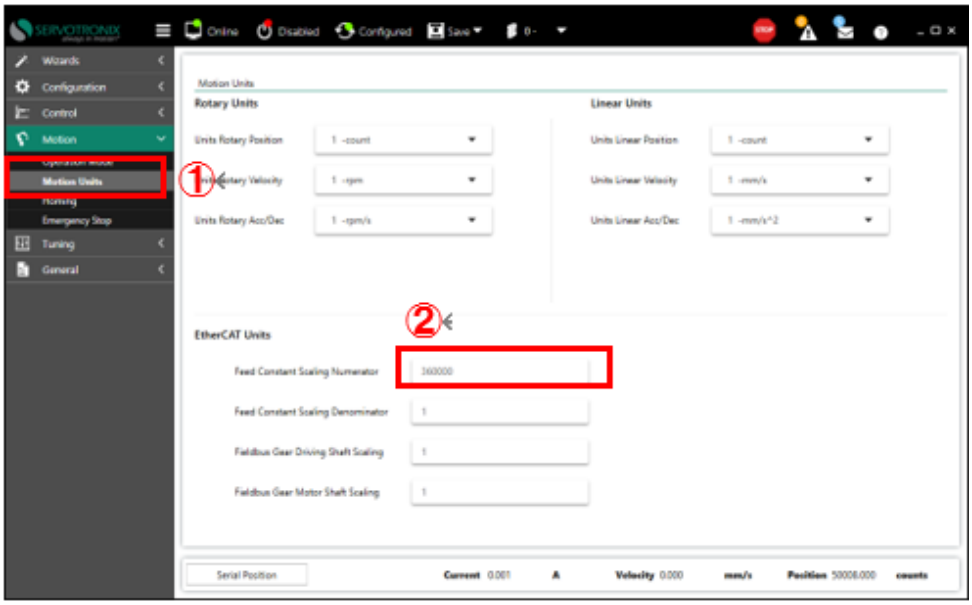


● Electronic gear ratio settings

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

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

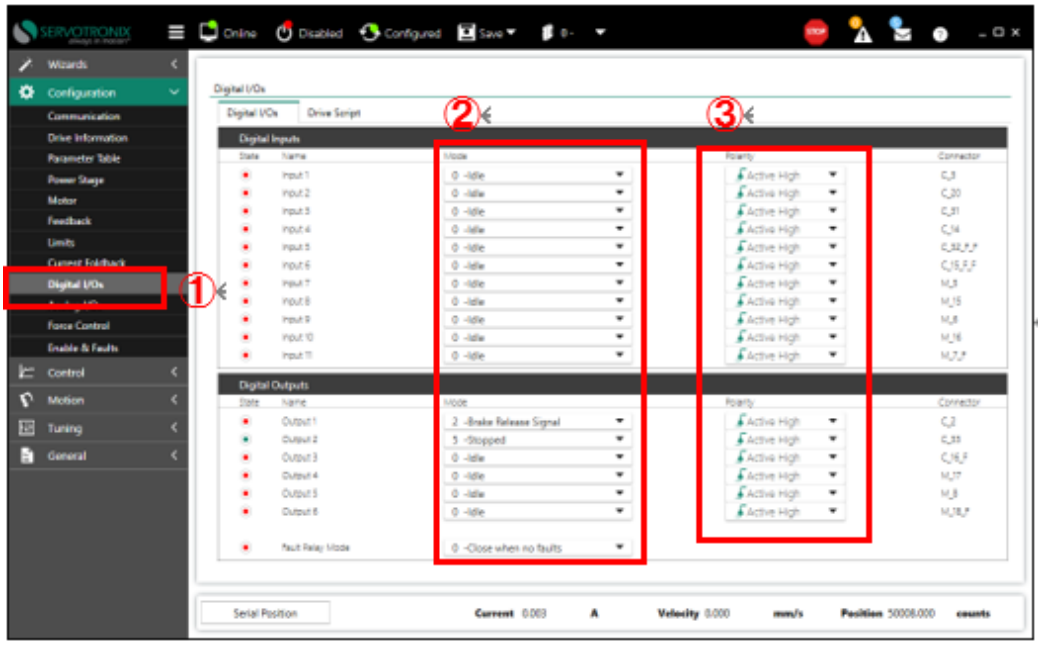
! Be sure to press the Enter key after setting the parameters.



I/O settings

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

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



● Change of driving direction

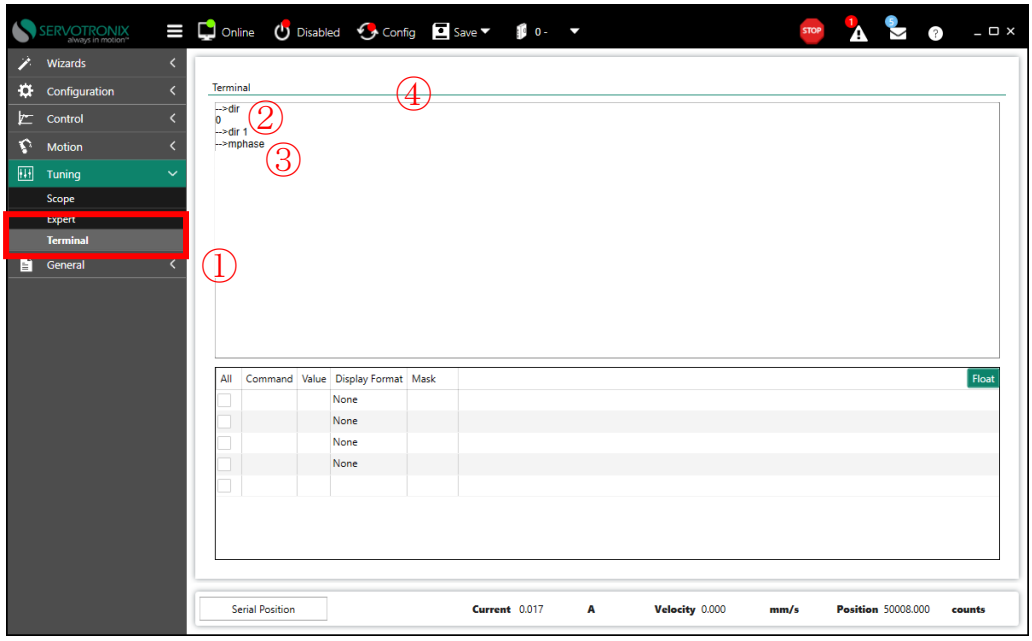
①Click <Tuning>, enter dir in ②<Terminal>, then press Enter to check ③<Result>.

③If <Result> is 0, enter dir 3 in ②<Termianl>.

3　If <Result> is 3, enter dir 0 in ②<Termianl>.

4　Click <Config>.

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



● 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

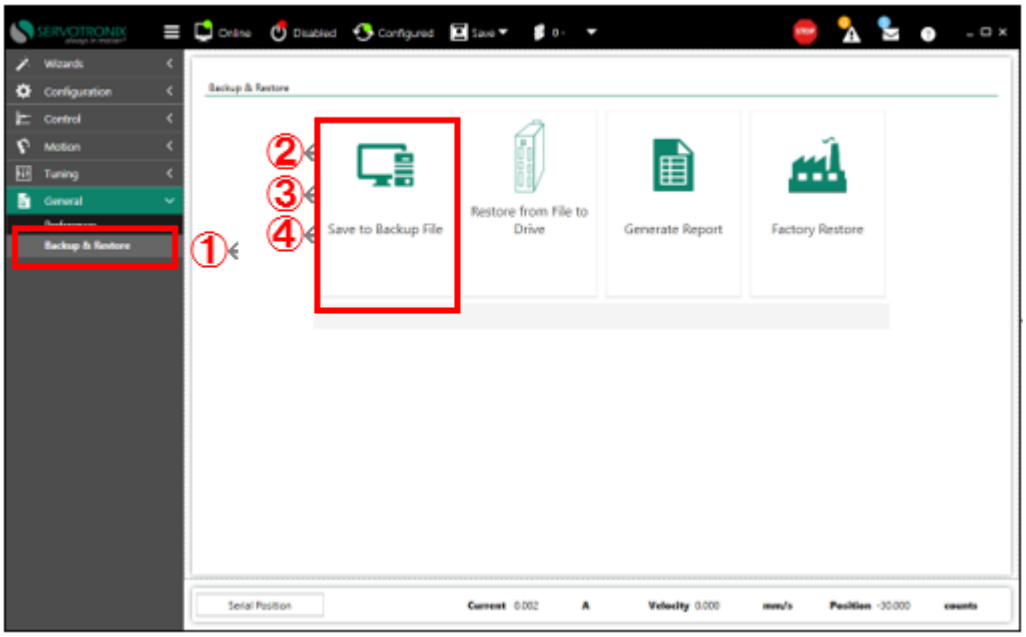
Select the adaptive file according to the model number of the actuator you purchased.

3.7 Parameter backup & parameter recovery

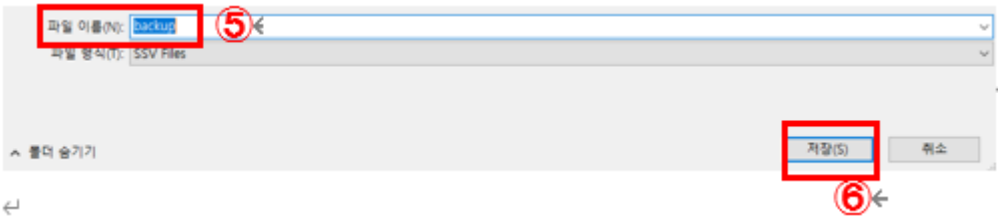
● Parameter backup

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

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.