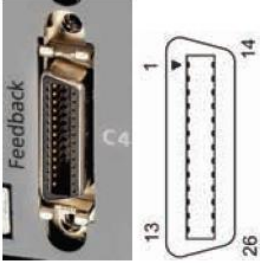
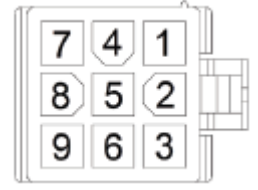


## 1.BAĞLANTILAR

### 1.1.C4 26 PIN KONNEKTOR ENKODER KABLOSU BAĞLANTISI

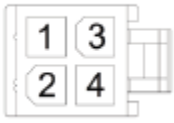


SÜRÜCÜ	SİNYAL	MOTOR
1	Serial Data +	1
14	Serial Data -	4
11	+5VDC	7
24	0V	8
26	SHIELD	9



### 1.2.MOTOR GÜÇ KABLOSU BAĞLANTISI

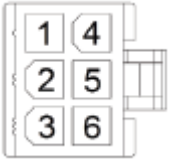
#### 1.2.1.FRENSİZ MOTOR GÜÇ KABLOSU BAĞLANTISI



1 - U    3 - W  
2 - V    4 - PE

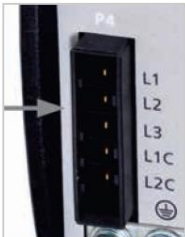


#### 1.2.2.FRENLİ MOTOR GÜÇ KABLOSU BAĞLANTISI



1 - U                      4 - W  
2 - V                      5 - PE  
3 - BRAKE 24V        6 - BRAKE 0V

### 1.3.SÜRÜCÜ BESLEME BAĞLANTISI

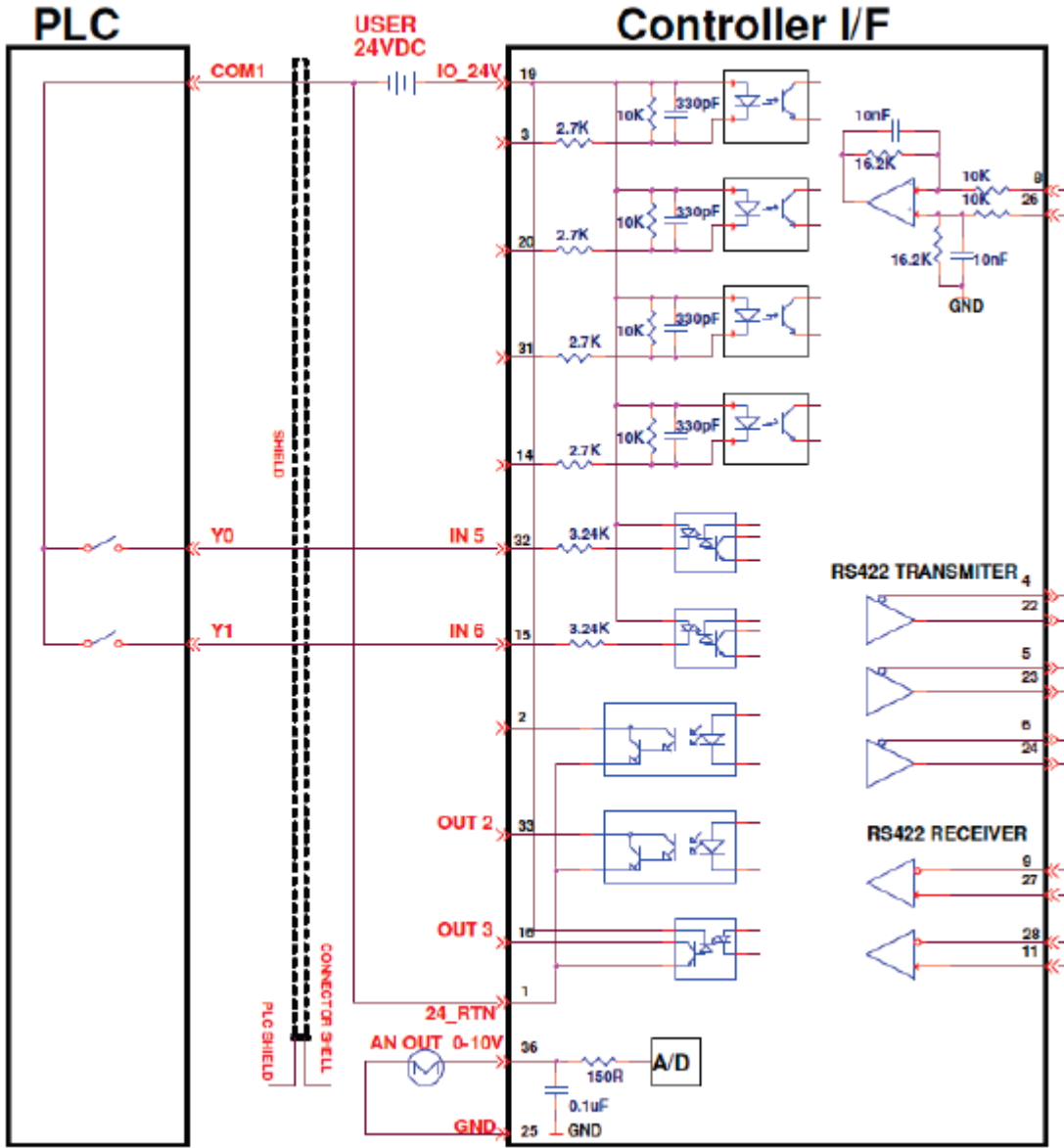


L1 - FAZ  
L2 - NOTR  
L1C - FAZ  
L2C - NOTR



GÖVDE - TOPRAK

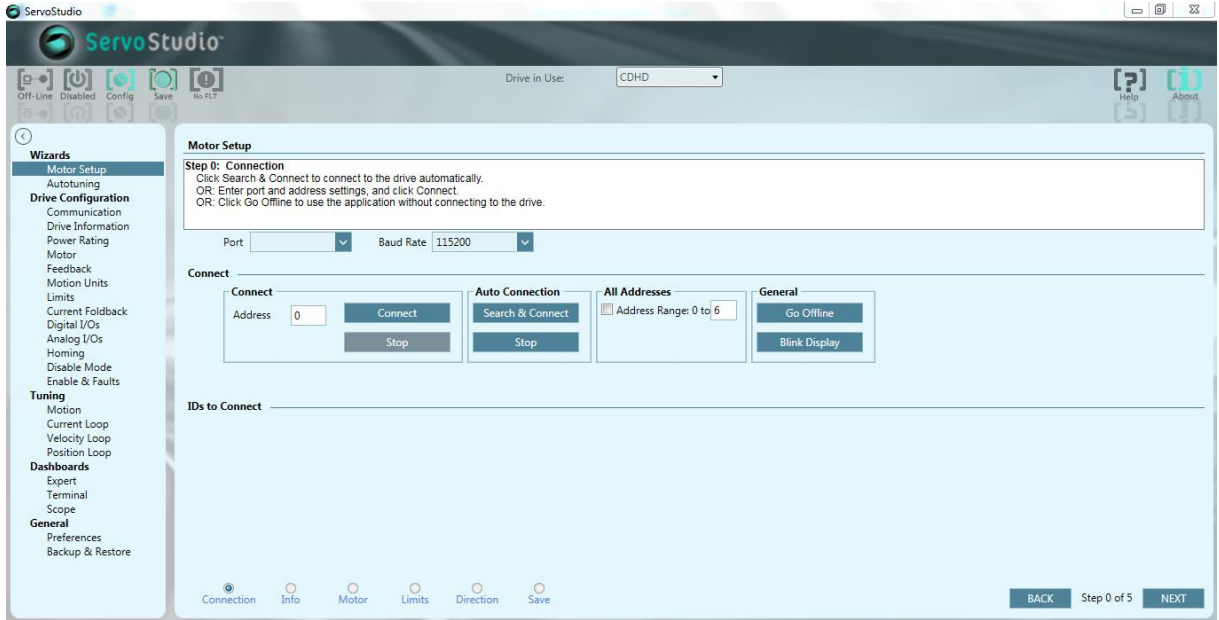
### 1.4.SÜRÜCÜ C2 KONNEKTOR GİRİŞ ÇIKIŞ BAĞLANTISI



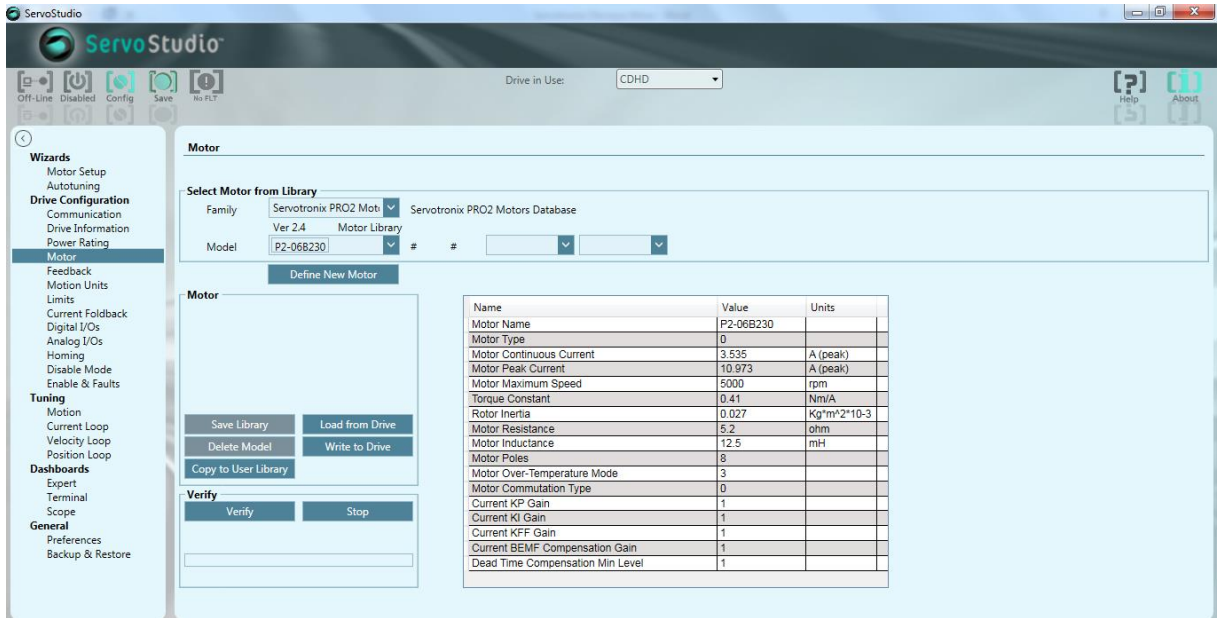
## 2.SÜRÜCÜ AYARLARI

(Aşağıdaki işlemler için <http://servotronix.com/download/664/> adresinden ServoStudio programını indirip bilgisayarınıza kurunuz.)

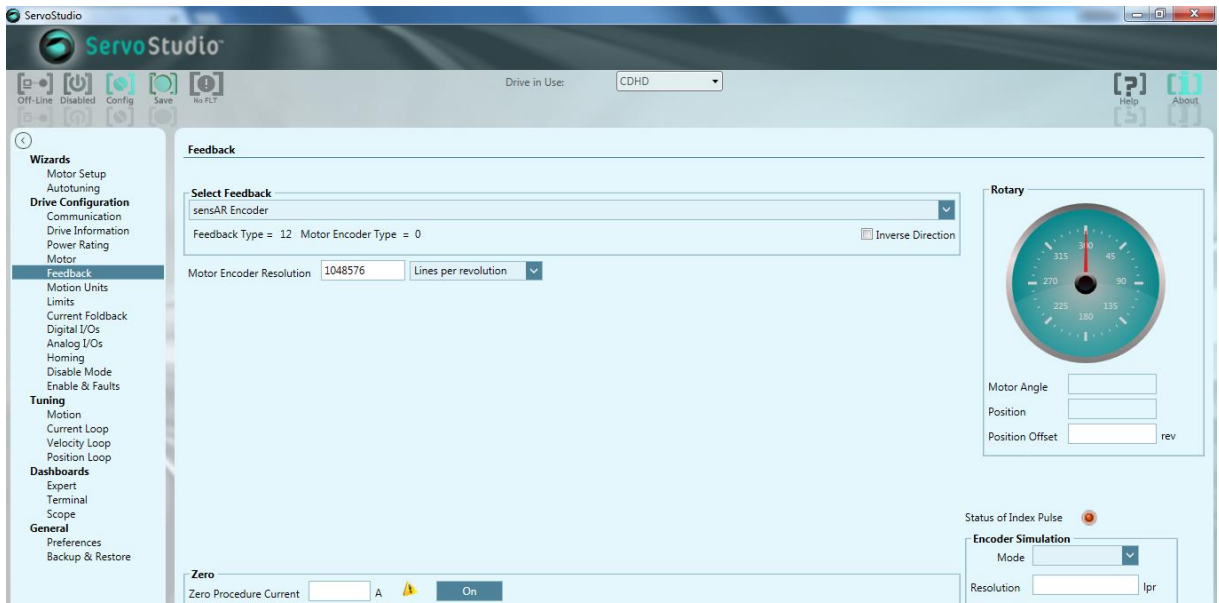
- Motor Setup bölümünden bilgisayarla sürücü arasında bağladığınız mini usb-usb kablosunun bağlı olduğu portu seçip connect butonuyla bağlantıyı kuruyoruz.



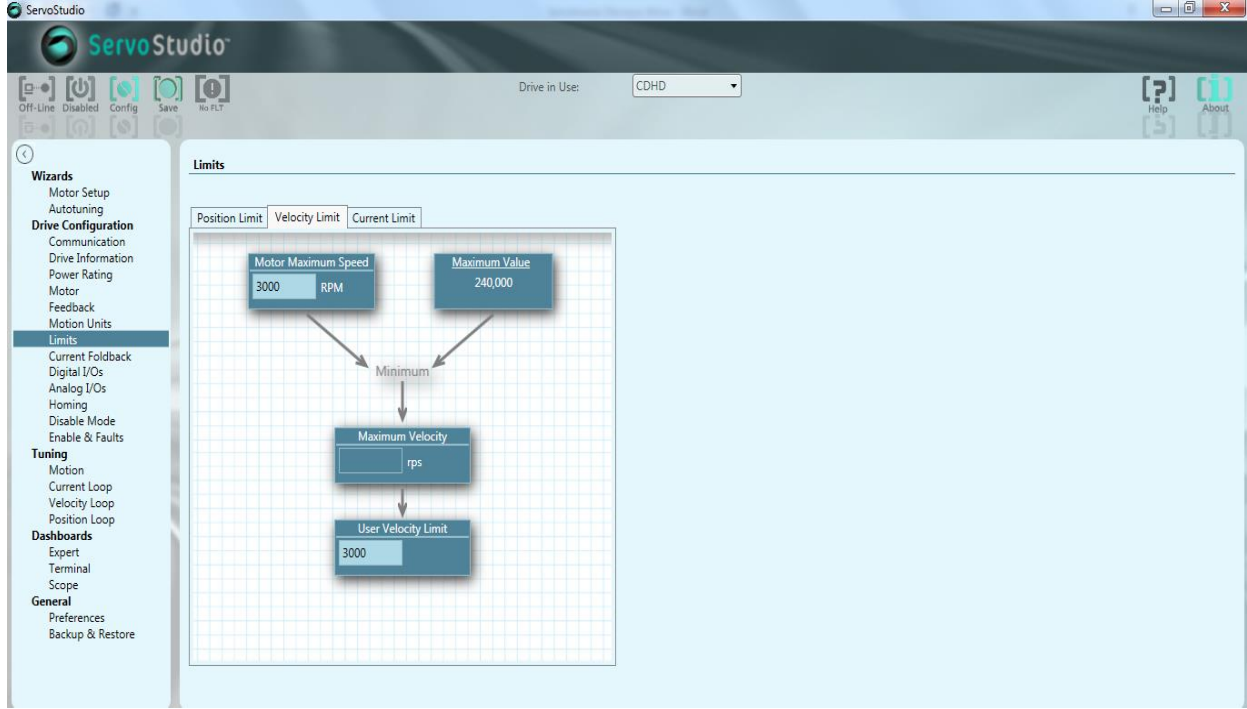
- Motor Setup -> Motor bölümünden sürücüye bağlı olan motoru seçiyoruz. Seçtikten sonra Write to Drive butonuna basıyoruz.



- Motor Setup -> Feedback bölümünden motor enkoder tipi ve bir turdaki pals sayısını giriyoruz.

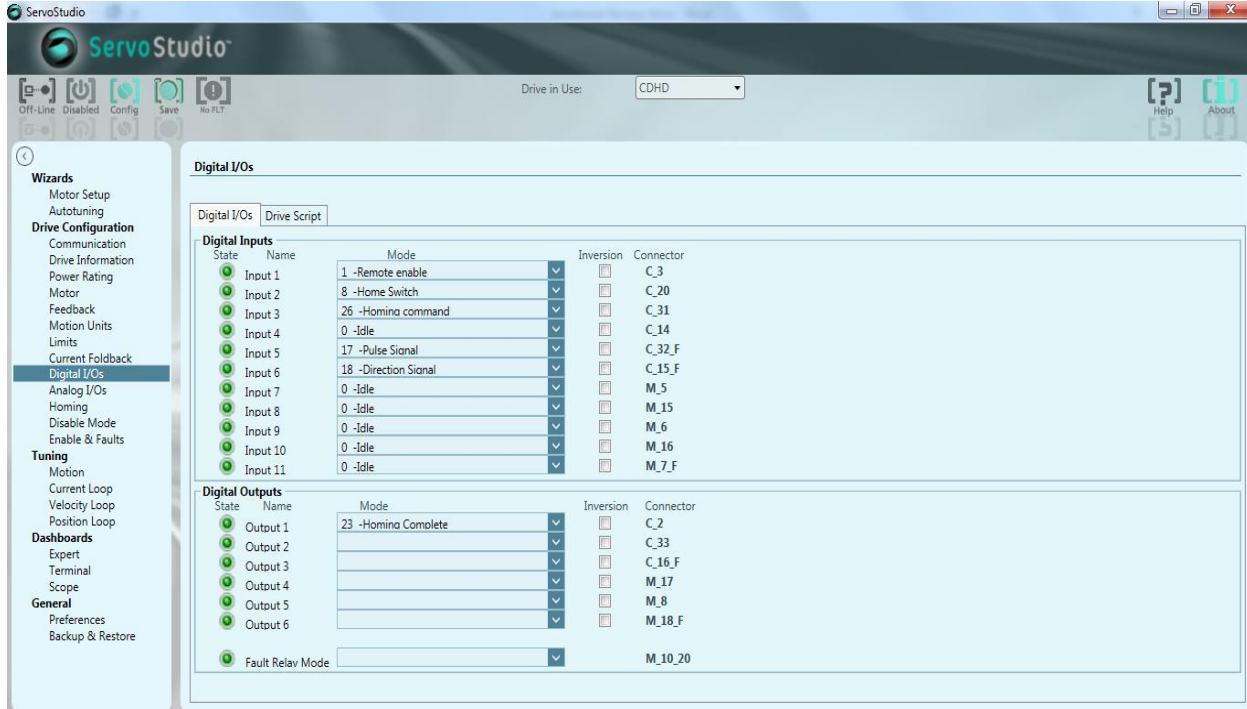


- Motor Setup -> Limits menüsünden pozisyon, hız ve akım limitlerini giriyoruz.



The screenshot shows the ServoStudio interface with the 'Limits' configuration window. The 'Velocity Limit' sub-tab is active. A flowchart illustrates the calculation of the User Velocity Limit. It starts with 'Motor Maximum Speed' set to 3000 RPM and 'Maximum Value' set to 240,000. These two values are compared to find a 'Minimum'. This minimum value is then used to determine the 'Maximum Velocity' in rps. Finally, the 'User Velocity Limit' is set to 3000.

- Motor Setup -> Digital I/Os bölümünden gerekli duyulan input output tanımlamaları yapılır.



The screenshot shows the ServoStudio interface with the 'Digital I/Os' configuration window. The 'Digital I/Os' tab is active, and the 'Digital Inputs' section is expanded. The table below shows the configuration for 11 digital inputs and 6 digital outputs.

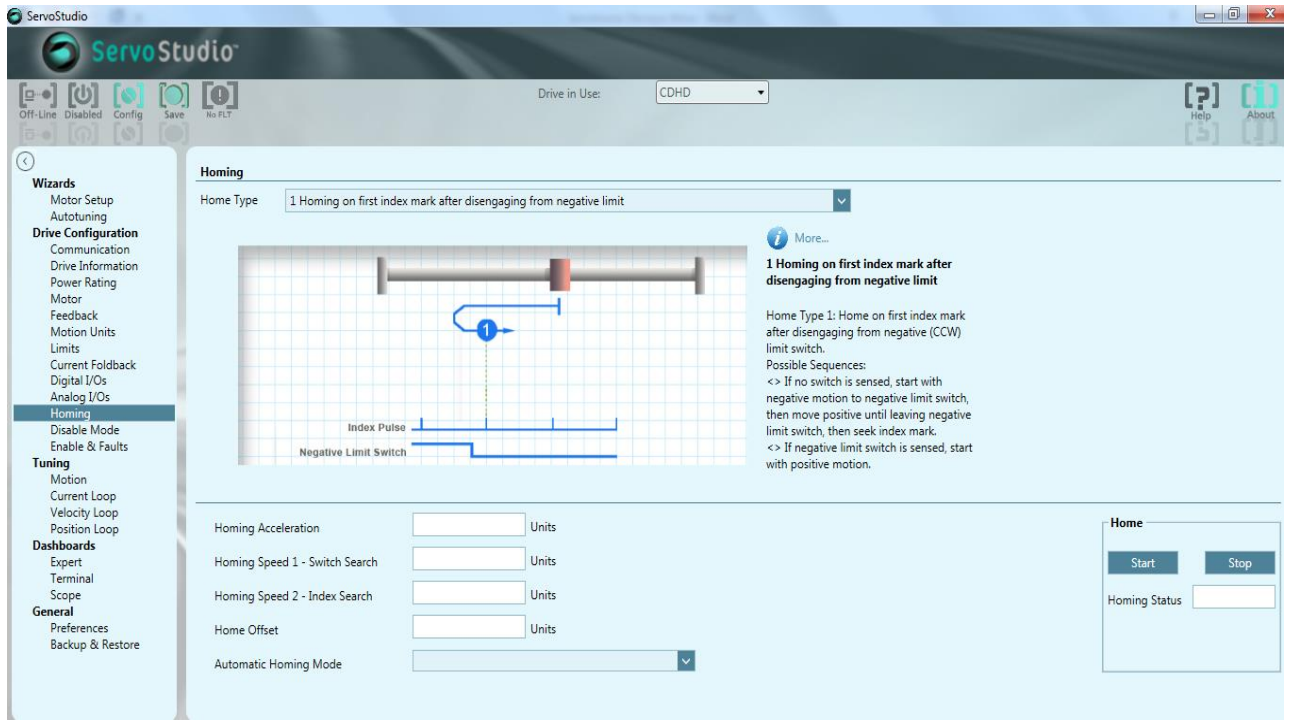
State	Name	Mode	Inversion	Connector
<input checked="" type="checkbox"/>	Input 1	1 -Remote enable	<input type="checkbox"/>	C_3
<input checked="" type="checkbox"/>	Input 2	8 -Home Switch	<input type="checkbox"/>	C_20
<input checked="" type="checkbox"/>	Input 3	26 -Homina command	<input type="checkbox"/>	C_31
<input checked="" type="checkbox"/>	Input 4	0 -Idle	<input type="checkbox"/>	C_14
<input checked="" type="checkbox"/>	Input 5	17 -Pulse Signal	<input type="checkbox"/>	C_32_F
<input checked="" type="checkbox"/>	Input 6	18 -Direction Signal	<input type="checkbox"/>	C_15_F
<input checked="" type="checkbox"/>	Input 7	0 -Idle	<input type="checkbox"/>	M_5
<input checked="" type="checkbox"/>	Input 8	0 -Idle	<input type="checkbox"/>	M_15
<input checked="" type="checkbox"/>	Input 9	0 -Idle	<input type="checkbox"/>	M_6
<input checked="" type="checkbox"/>	Input 10	0 -Idle	<input type="checkbox"/>	M_16
<input checked="" type="checkbox"/>	Input 11	0 -Idle	<input type="checkbox"/>	M_7_F

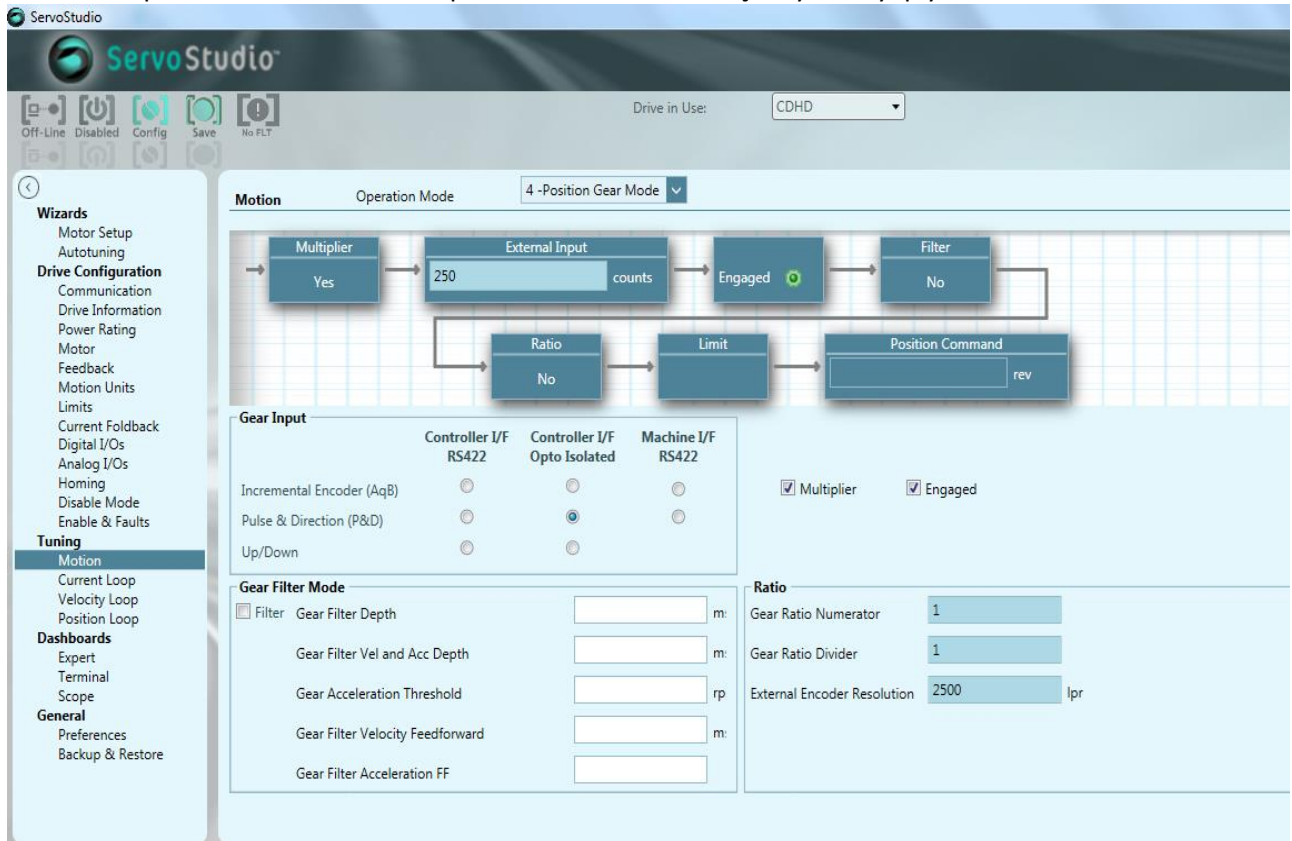
State	Name	Mode	Inversion	Connector
<input checked="" type="checkbox"/>	Output 1	23 -Homina Complete	<input type="checkbox"/>	C_2
<input checked="" type="checkbox"/>	Output 2		<input type="checkbox"/>	C_33
<input checked="" type="checkbox"/>	Output 3		<input type="checkbox"/>	C_16_F
<input checked="" type="checkbox"/>	Output 4		<input type="checkbox"/>	M_17
<input checked="" type="checkbox"/>	Output 5		<input type="checkbox"/>	M_8
<input checked="" type="checkbox"/>	Output 6		<input type="checkbox"/>	M_18_F

Below the outputs, there is a 'Fault Relav Mode' dropdown menu set to 'M\_10\_20'.

- Motor Setup -> Homing bölümünden home işlemi sürücü tarafından yapılması isteniliyorsa homing yöntemi için gerekli ayarlamalar yapılır.



- Motor Setup -> Motion bölümünden puls direction kullanımı için ayarları yapıyoruz.



Ayarlar bittikten sonra terminal bölümünden 'Config' ve 'Save' işlemlerini yaptıktan sonra Autotuning yapıp sistemi çalıştırabiliriz.