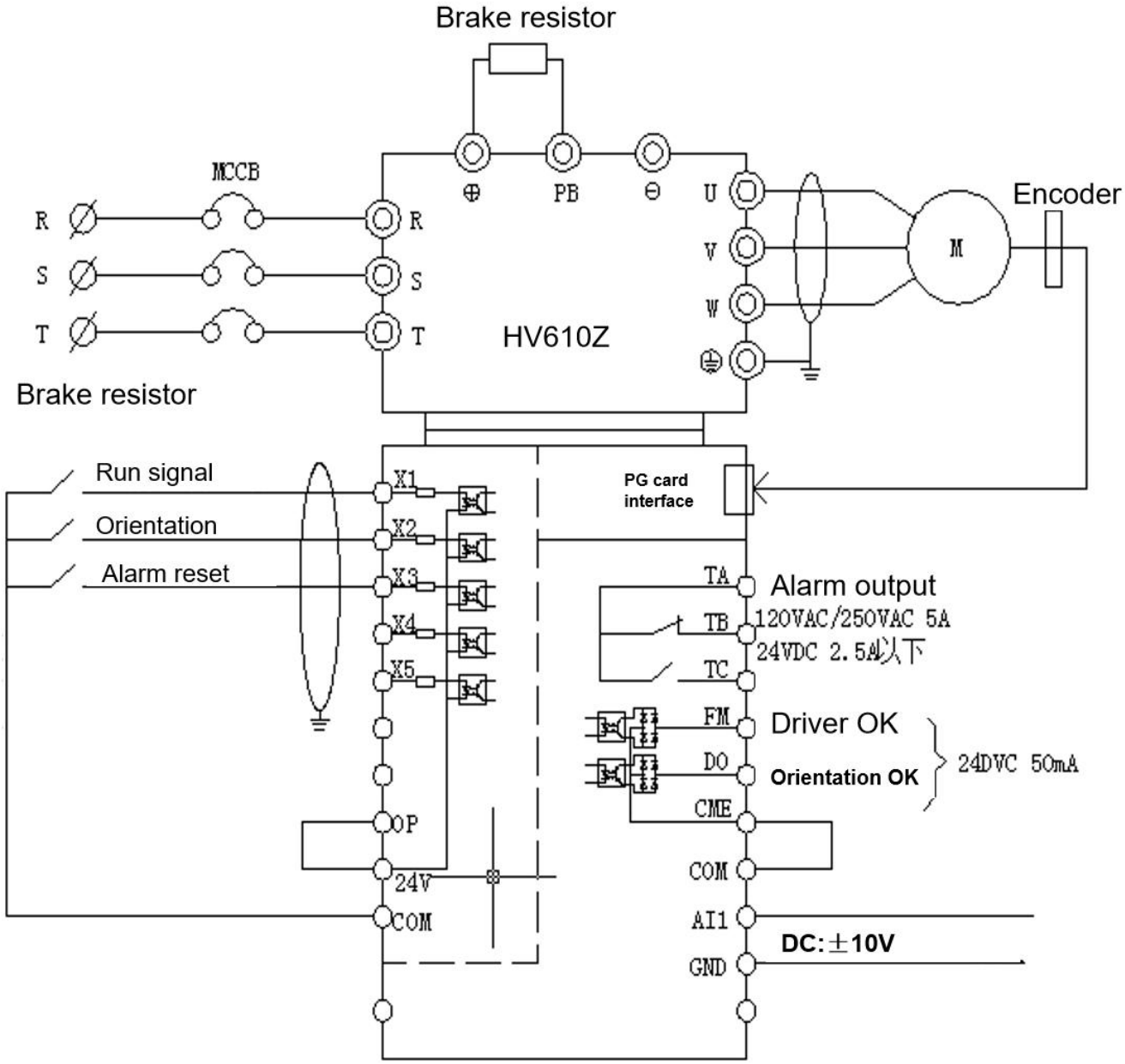
Note:

This document is applicable when the encoder is installed directly on the spindle motor.

In this example, only one spindle orientation position.



Diagram

1：Parameter setting.

F0-01：1 (FVC mode, close loop control)

F0-10：Maximum frequency

F0-12：Upper limit frequency

F1-01：Motor rated power

F1-02：Motor rated voltage

F1-03：Motor rated current

F1-04：Motor rated frequency

F1-05：Motor rated speed

F1-27： Encoder line number

F1-28：0，Encoder is ABZ incremental type, PG card is PG-DIF

2：Self-learning

F1-37：2

After successful learning, enter no-load operation and observe the operation status.The motor runs smoothly, enter the next step parameter setting. If the motor is not running smoothly, re-check the parameters before self-learning and repeat self-learning till motor runs smoothly.

3: Function parameters setting

F0-02：1 Terminal command channel
F0-03：2 Main frequency sourceAI1
F4-00：01 X1 is FWD run
F4-01：65 X2 is spindle orientation
F4-02：9 X3 Alarm reset
F4-13：-10 AI1 minimum input
F4-14：-100% AI2 minimum input corresponding setup
F4-15：10 AI1 maximum input
F4-16：100% AI2 maximum input corresponding setup
F5-00： 1 FM as switch type output
F5-01：15 Drive OK
F5-02： 2 Alarm output（Relay type output）
F5-04： 21 Orientation OK
A4-01：2 Angular orientation mode
A4-20：--- Orientation Angle
A4-21： 0 Angle source is A4-20
Note：
When set the orientation angle A4-20, please adjust the spindle to the target position, and check the value of u1-02, then store it in A4-20, then take this position as the target position when spindle orientation DI be active.