

本文介绍如何建立 TwinCAT3 和 AMC 驱动器的 EtherCAT 通讯,并通过 NC 功能和

PLC 功能实现运动控制。

注:在进行通讯测试之前,需要先通过驱动器调试软件正常驱动电机。

一、测试工具

- 1、AMC EtherCAT 驱动器型号:FE060-5-EM;
- 2、安装有 TwinCAT3 的电脑, 安装包版本: TC31-Full-Setup.3.1.4016.12;

二、接线

通过网线连接驱动器的 EtherCAT 口和电脑的网口;

三、参数配置

1、驱动器通讯参数设置

(1)、将 "Command Source" 设置为 "Communication Channel";





System Browser 🛛 📮 🔯	EtherCAT Settings
FE060-5-EM-Left Motor - Default Brushless Inputs / Outputs Limits Events Network Settings RPDO	Connection Network: EtherCAT Station Alias: 1
⊕ ∰ TPDO ⊕ ∰ Tuning ⊕ @ Base Motion	Initial Mode of Operation (6060) Profile Position (1)
⊕-ੴ Motion Engine	*Mode changes will be applied upon drive reset.
	Cyclic Mode Period

(2), 设置 6060 的上电初始值为 1, 即 Profile Position 模式;

(3) RPDO和 TPDO的设置保持默认;



到此, 驱动器通讯参数设置完成, 重启驱动器, 以"Read-Only"的方式连接驱动

器 以便在 EtherCAT 通讯时 监控驱动器的状态。

Access Control: Read-Only

;

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2、TwinCAT3 设置

(1)、安装驱动器的 XML 文件

将 "AMC_FP_01.00.01.00.xml" 和 "AMC_FP_Dict.xml" 复制到 TwinCAT3 安装路径

下的 "EtherCAT" 文件夹里;

件(E) 编辑(E) 查看(V) 工具(I) 帮助(H)			
目织 ▼ 包含到库中、	▼ 共享 ▼ 新建文件夹			
☆ 收藏夹	名称	修改日期	类型	大小
▶ 下载	Beckhoff AX5xxx	2021/8/19 星期	文件夹	
■ 卓面	👪 RES	2021/8/19 星期	文件夹	
1 最近访问的位置	@ AMC_FP_01.00.01.00.xml	2020/1/10 星期	XML 文档	8 KB
	AMC_FP_Dict.xml	2020/1/10 星期	XML 文档	485 KB
	🔮 Beckhoff AX2xxx.xml	2009/4/20 星期	XML 文档	290 KB
	Beckhoff AX5xxx.xml	2014/10/14 星期	XML 文档	800 KB
	Beckhoff BKxxxx.xml	2014/6/6 星期五	XML 文档	1,441 KB
	😬 Beckhoff CUxxxx.xml	2014/5/14 星期	XML 文档	130 KB
1 文档	Beckhoff CXxxxx.xml	2013/6/6 星期四	XML 文档	69 KB
□ 迅雷下载	🔮 Beckhoff EKxxxx.xml	2014/6/25 星期	XML 文档	166 KB
→ 音乐	Beckhoff EKxxxx-0080.xml	2012/12/14 星期	XML 文档	9 KB
	Beckhoff EL1xxx.xml	2014/11/11 星期	XML 文档	2,187 KB
🖳 计算机	Beckhoff EL2xxx.xml	2014/11/11 星期	XML 文档	7,015 KB
🏭 本地磁盘 (C:)	Beckhoff EL3xxx.xml	2014/9/26 星期	XML 文档	2,429 KB
	Beckhoff EL4xxx.xml	2014/7/24 星期	XML 文档	5,272 KB
	Beckhoff EL5xxx.xml	2014/11/12 星期	XML 文档	4,902 KB
	Beckhoff EL6xxx.xml	20 <mark>1</mark> 4/11/11 星期	XML 文档	13,609 KB
	Beckhoff EL7xxx.xml	201 <mark>4/11/14 星期</mark>	XML 文档	11,345 KB
新加老 (G:) ▼	🔮 Beckhoff EL9xxx.xml	2014/4/1 星期二	XML 文档	138 KB



New Project				? X
Recent Templates		.NET Framework 4 🔹 Sort by: Defau	lt 🗾 🏭 🔛	Search Installed Templates
Installed Templates	rement	TwinCAT XAE Project (XML format	t) TwinCAT Project	Type: TwinCAT Project TwinCAT XAE SystemManager Configuration
Name:	TestAMC	Viewal Studio 2010) Brojecte	-	Prouse
Solution name:	TestAMC	visuai studio 2010/Projects	<u> </u>	Create directory for solution
				OK Cancel

(2)、打开 TwinCAT3 软件,新建命名新的项目;

(3) 安装 EtherCAT 驱动

ernet Adapters	Update List
Installed and ready to use devices(realtime capable) Installed and ready to use devices(for demo use only)	Install
Compatible devices	Update
Incompatible devices ● 予结网络连接 - <u>Atheros AR9285 Wireless Net</u> work Adapter	Bind
- <mark>●】本地连接 - Realtek PCIe FE Family Controller</mark> ● Uisabled devices	Unbind
	Enable
	Disable
	Show Bindings

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选中电脑的有线网卡,点击"_______Install____",如下图所示,EtherCAT 驱动已

成功安装;

	Update List
Installed and ready to use devices(realtime capable) Installed and ready to use devices(for demo use only)	Install
— ➡ 本地连接 - Realtek PCIe FE Family Controller	Update
	Bind
	Unbind
	Enable
	Disable
	Show Bindings

(4)、将 TwinCAT3 切换到"Config"模式;





(5)、扫描 EtherCAT 从站

点击 "I/O" — "Dvices" — "Scan";





选择使用的有线网卡,点击" 0K ";	
1 new I/O devices found	x
✔Device 2 (EtherCAT) [本地连接 (Realtek PCIe FE Family Controller)]	OK
	Cancel
	Select All
	Unselect All
点击" 是) ;	
Microsoft Visual Studio	
Scan for boxes	
是(Y) 否(N)	
点击" —— 是) ",将扫描到的从站自动链接到 NC;	
Microsoft Visual Studio	
EtherCAT drive(s) added. Append linked axis to NC-Configuration	
是(Y) 否(N)	





此时,在TwinCAT3中出现了两台挂载在EtherCAT总线上的驱动器,并自动新建链接了两

个 NC 轴 ;





将 TwinCAT3 切换到 "Start/Restart" 模式;

	0	About TwinCAT	
	8	Event Viewer	
	6	TwinCAT Switch Runtime	
	60	TwinCAT XAE (VS 2010)	
	P	<u>R</u> ealtime Settings	
Start/Restart		Router	•
Config		<u>S</u> ystem	112

下图为 TPDO 的配置;

Sync	Manager:		-	PDO List:						
SM	Size	Туре	Flags	Index	Size	Name	Fla	igs SM	SV	
0	612	MbxOut		0x1A00	14.0	1st Tr	ansmit PDO Mapping	3	0	
1	612	MbxIn		001000	14.0	IST Ne	cerve ruo mapping	Z		
2	14	Out								
3	14	Inputs								
	.ssignmer 1600	III at (0x1C12	:):	PDO Conter	it (0x1A)	00):			2 2 20	
< DO A ✔Ox	ssignmer 1600	III nt (Ox1C12	>):	PDO Conter Index	ut (Ox1A) Size	00): Offs	Name	Туре	Default	-
< DO A	ssignmer 1600	111 (Ox1C12	:):	PDO Conter Index 0x604	t (Ox1A) Size 2.0	00): Offs 0.0	Name Statusword	Type INT	Default	
< L DO A ✔Ox	ssignmer 1600	111 (Ox1C12	>):	PDO Conter Index 0x604 0x606	t (0x1A) Size 2.0 4.0	00): Offs 0.0 2.0	Name Statusword Position Actual Value	Type INT DINT	Default	
A OU	ssignmer 1600	111 (Ox1C12	> :):	PDO Conter Index 0x604 0x606 0x606	size 2.0 4.0 9.0	00): Offs 0.0 2.0 6.0	Name Statusword Position Actual Value Velocity Actual Value	Type INT DINT DINT	Default	/
< DO Å	.ssignmer 1600	III ht (0x1C12	>):):	PDO Conter Index 0x604 0x606 0x606 0x607 0x607	t (0x1A) Size 2.0 4.0 4.0 2.0	00): 0ffs 0.0 2.0 6.0 10.0 12.0	Name Statusword Position Actual Value Velocity Actual Value Torque Actual Value Persumadi	Type INT DINT DINT INT	Default	
< DO A	ssignmer 1600	III at (0x1C12	>):	PDO Conter Index 0x604 0x606 0x606 0x607 0x202	xt (0x1A) Size 2.0 4.0 4.0 2.0 2.0	00): 0ffs 0.0 2.0 6.0 10.0 12.0 14.0	Name Statusword Position Actual Value Velocity Actual Value Torque Actual Value Reserved1	Type INT DINT DINT INT VINT	Default	I
OD A Ox Ox	nload	III ht (0x1C12	>):	PDO Conter Index 0x604 0x606 0x606 0x202 Predefine	st (0x1A) Size 2.0 4.0 2.0 2.0 2.0 2.0	00): 0ffs 0.0 2.0 6.0 10.0 12.0 14.0 ssignment	Name Statusword Position Actual Value Velocity Actual Value Torque Actual Value Reserved1	Type INT DINT DINT INT VINT	Default	
A OD A OT Source Down	nload PDO Assi	m nt (Ox1C12):):	PD0 Conter Index 0x606 0x606 0x607 0x202 Predefine Load PD0	t (0x1A) Size 2.0 4.0 2.0 2.0 2.0 d PDO As	00): 0ffs 0.0 2.0 6.0 10.0 12.0 14.0 signment m device	Name Statusword Position Actual Value Velocity Actual Value Torque Actual Value Reserved1 (none)	Type INT DINT DINT INT VINT	Default	



下图为 RPDO 的配置;

~	C ¹		777	T 1		17		773	C11	C 11	
SM	Dize	lype	Flags	Index	Dize	Name		flags	20	20	
0	612	MbxOut		0x1A00	14.0	1st Tr	ansmit PDO Mapping		3	0	
1	612	MbxIn		0x1600	14.0	1st Re	ceive PDO Mapping		2	0	
2	14	Out									
3	14	Inputs									
<		Ш	>								
<	ussi gamer	111 nt (0x1C12	2):	PDO Conter	1t (Ox160	00):			• ver date		_
< DO A	ussignmen :1600	III nt (0x1C12	2):	PDO Conter Index	nt (Ox16) Size	DO): Offs	Name	1	Гуре	Default	
< DO A	ussignmen :1600	III nt (0x1C12	2):	PDO Conter Index 0x604	nt (Ox16) Size 2.0	00): Offs 0.0	Name Controlword		[ype INT	Default	
< DO A	ussignmen :1600	III nt (0x1C12	2):	PDO Conten Index 0x604 0x607	nt (0x16) Size 2.0 4.0	00): Offs 0.0 2.0	Name Controlword Target Position	5	Type INT DINT	Default	
< DO A	ussignme 1600	III nt (0x1C12	>):	PDO Conter Index 0x604 0x607 0x60F	nt (0x16) Size 2.0 4.0 4.0	00): Offs 0.0 2.0 6.0	Name Controlword Target Position Target Velocity	1	Type INT DINT DINT	Default	
< YDO A YOx	ussignmen 1600	III nt (0x1C12	2):	PDO Conter Index 0x604 0x607 0x60F 0x607	nt (0x16) Size 2.0 4.0 4.0 2.0	00): Offs 0.0 2.0 6.0 10.0	Name Controlword Target Position Target Velocity Target Torque	1	Type INT DINT DINT INT	Default	
< DO A	ussignmen 1600	111 nt (0x1C12	2):	PD0 Conter Index 0x604 0x607 0x607 0x607 0x200	nt (0x160 Size 2.0 4.0 4.0 2.0 2.0	00): 0ffs 0.0 2.0 6.0 10.0 12.0	Name Controlword Target Position Target Velocity Target Torque Reserved3	1	Type INT DINT DINT INT TINT	Default	
< DO A	ssignme)	III nt (0x1C12	2):	PD0 Conter Index 0x604 0x607 0x607 0x607 0x200	nt (0x160 Size 2.0 4.0 4.0 2.0 2.0 2.0	00): 0ffs 0.0 2.0 6.0 10.0 12.0 14.0	Name Controlword Target Position Target Velocity Target Torque Reserved3	5 3 1 1 1 1	Type INT DINT DINT INT TINT	Default	×
< DO A OC	ssignmen 1600 nload	III nt (0x1C12	>);	PDO Conter Index 0x604 0x607 0x607 0x200 Predefine	nt (0x16) Size 2.0 4.0 4.0 2.0 2.0 2.0	00): 0ffs 0.0 2.0 6.0 10.0 12.0 14.0 :si gnment	Name Controlword Target Position Target Velocity Target Torque Reserved3 : (none)	1 1 1 1 1 1	Type INT JINT DINT INT JINT	Default	- <u> </u>

下图为 TPDO 和 RPDO 所映射驱动器的值,表示 TwinCAT3 和驱动器的 EtherCAT 通信已

成功建立 ;

Name	Online	Туре	Size	>Addr	In/Out	User ID	Linked to
🕫 Statusword	801	INT	2.0	51.0	Input	0	
🔁 Position Actual	42060	DINT	4.0	53.0	Input	0	
🔁 Velocity Actual	-1	DINT	4.0	57.0	Input	0	
🔁 Torque Actual V	14	INT	2.0	61.0	Input	0	
🔁 Reserved1	6	UINT	2.0	63.0	Input	0	
🔁 WcState	0	BIT	0.1	1522.1	Input	0	
🔁 InputToggle	0	BIT	0.1	1524.1	Input	0	
🗭 State	8	UINT	2.0	1559.0	Input	0	
📌 AdsAddr	192.168.3.23.3.1:1002	AMSADDR	8.0	1561.0	Input	0	
🔁 Chn0	0	USINT	1.0	1569.0	Input	0	
Controlword	6	INT	2.0	51.0	Output	0	
Target Position	41437	DINT	4.0	53.0	Output	0	
Target Velocity	0	DINT	4.0	57.0	Output	0	
🖙 Target Torque	0	INT	2.0	61.0	Output	0	
Reserved3	0	UINT	2.0	63.0	Output	0	



(6) NC 轴配置

①、设置电机的分辨率,本次测试所用电机的反馈装置为2000线的增量编

码器经过驱动器 4 倍频后, 电机旋转一圈, 反馈脉冲数变化 8000 个脉冲;

"Motion" — "NC-Task1 SAF" — "Axes" — "Axis 1" — "Enc" — "Parmeter"

Scaling Factor Numerator			1.0	1.0		mm/IN0
Scaling Factor Denominator (defau	lt: 1.0)		8000.0	8000.0		1
lution Explorer	• 🕂 🗙 Te	stAMC ×				
		General NC-Er	coder Parameter Time Compensation On	line		
Solution TestANIC (I project) TestAMC	Â	Paramet	er	Offline Value	Online Value	Unit
SYSTEM		- Encoder	Evaluation:			
INC-Task 1 SAF		Invert En	coder Counting Direction	FALSE	FALSE	
NC-Task 1 SVB		Scaling F	actor Numerator	1.0	1.0	mm/INC
🛟 Image		Scaling F	actor Denominator (default: 1.0)	8000.0	8000.0	
Tables		Position	Bias	0.0	0.0	mm
A Axis 1		Modulo	Factor (e.g. 360.0°)	360.0	360.0	mm
D & Enc		Toler	ance Window for Modulo Start	0.0	0.0	mm
⊳. ➡ Drive		Encoder	Mask (maximum encoder value)	0xFFFFFFFF	0xFFFFFFFF	
The Ctrl		Encoder	Sub Mask (absolute range maximum value)	0x000FFFFF	0x000FFFFF	
Inputs		Reference	e System	'INCREMENTAL'	INCREMENTAL'	
A Avis 2	=	+ Limit Sw	itches:			
		+ Filter:				
III PLC						
PLC SAFETY		+ Homing				

②、运行相关参数设置,测试电机额定转速 3000rpm=50rev/s

NC 轴配置中的单位 mm 等同于 rev,即 mm=rev,mm/s=rev/s,mm/s²=rev/s²

"Motion" — "NC-Task1 SAF" — "Axes" — "Axis 1" — "Parmeter";

	Parameter	Offline Value	Online Value	Unit
•	Velocities:			
	Reference Velocity	40.0	40.0	mm/s
	Maximum Velocity	50.0	50.0	mm/s
	Manual Velocity (Fast)	20.0	20.0	mm/s
	Manual Velocity (Slow)	10.0	10.0	mm/s
	Calibration Velocity (towards plc cam)	10.0	10.0	mm/s
	Calibration Velocity (off plc cam)	10.0	10.0	mm/s
	Jog Increment (Forward)	5.0	5.0	mm
	Jog Increment (Backward)	5.0	5.0	mm
2	Dynamics:			
	Limit Switches:			
	Monitoring:			
	Setpoint Generator:			
	NCI Parameter:			
	Other Settings:			



Reference Velocity:参考速度

Maximum Velocity:最大速度

Manual Velocity (Fast): 手动快速

Manual Velocity (Slow): 手动慢速

Jog Increment (Forward): 正向寸动增量

Jog Increment (Backward):反向寸动增量

	Parameter	Offline Value	Online Value	Unit
	Velocities:			
-	Dynamics:			
	Acceleration	100.0	100.0	mm/s2
	Deceleration	100.0	100.0	mm/s2
	Jerk	200.0	200.0	mm/s3
	Fast Axis Stop Signal Type (optional)	'OFF (default)'	OFF (default)'	
	Fast Acceleration (optional)	0.0	0.0	mm/s2
	Fast Deceleration (optional)	0.0	0.0	mm/s2
	Fast Jerk (optional)	0.0	0.0	mm/s3
+	Limit Switches:			
+	Monitoring:			
+	Setpoint Generator:			
+	NCI Parameter:			
+	Other Settings:			

Acceleration : 加速度

Deceleration: 减速度

Jerk:加加速度



	Parameter	Offline Value	Online Value	Unit
+	Velocities:			
+	Dynamics:			
+	Limit Switches:			
-	Monitoring:			
	Position Lag Monitoring	FALSE	FALSE	
	Maximum Position Lag Value	5.0	5.0	mm
	Maximum Position Lag Filter Time	0.02	0.02	s
	Position Range Monitoring	FALSE	FALSE	
	Position Range Window	5.0	5.0	mm
	Target Position Monitoring	FALSE	FALSE	
	Target Position Window	2.0	2.0	mm
	Target Position Monitoring Time	0.02	0.02	s
	In-Target Alarm	FALSE	FALSE	
	In-Target Timeout	5.0	5.0	s
	Motion Monitoring	FALSE	FALSE	
	Motion Monitoring Window	0.1	0,1	mm
	Motion Monitoring Time	0.5	0.5	5
+	Setpoint Generator:			
+	NCI Parameter:			
+	Other Settings:			

Position Lag Monitoring、Position Range Monitoring 和 Target Position Monitoring

均设置为 OFF,关闭位置误差监控;

Axis2 和 Axis1 设置参数相同;

完成上述设置后,点击"TwinCAT"菜单下的"Activate Configuration";

0	Activat	te Configuration	241 52
	(Old Co	onfigurations will be	overwritten!)
		确定	取消



Microsoft Visual	Studio
Rest	art TwinCAT System in Run Mode
	确定取消
点击" 确	ī ;
3、NC 轴	生线测试
"Motion" —	"NC-Task1 SAF" — "Axes" — "Axis 1" — "Online" ;
E	General Settings Parameter Dynamics Online Functions Coupling Compensation
<u>位置跟随误差</u> 速度比例	当前位置 0.0129 Setpoint [mm] Lag Distance [mm] Actual Velocity: [mm/s] Setpoint [mm] 0.0000 (0.000, 0.000) 当前速度 0.0000 Setpoint [mm/s] 0.0000 (0.000, 0.000) 当前速度 0.0000 Setpoint [mm/s] 0.0000 100.0000 % Total / Control [%] Error: 100.0000 % 0.00 / 0.00 % 0.00 % 故障代码 0 (0x0)
触状态	Status (log.) Status (phys.) Enabling ▼Ready ▼NOT Moving Coupled Mode Controlle: Set Calibrated Moving Fw In Target Pos. Feed F*禁/使能控制 Has Job Moving Bw In Pos. Range Feed By
	Controller Kv-Factor: [mm/s/mm] Reference Velocity: [mm/s]
	Target Position: [mm] Target Velocity: [mm/s] 0 目标位置设定 ↓ 0 目标速度设定
	- + ++ ∅ ∅ € F1 F2 F3 F4 F5 F6 F8 F9
	手动 手动 手动 手动 启动 停止 复位 回零 反向 反向 正向 正向 快速 慢速 慢速 快速



(4),在"^{Functions}"中,也可以选择更多的运动测试模式;

eneral	Settings	Parameter	Dynamics	Online	Function	s Coupling	Compensati	
			9	9987	Set	point	[mm] 10.0000	
Exten	ded Start			19 30				
Start	Mode:		Absolute	Ý		Start		
Targe	t Position	:	Absolute		[mm]	Stop		
Targe	t Velocity	: 1	Relative Andless +		[mm/s]			
Ac	celeration	. I	Indless -		[mm/s2]			
	celeration		lodulo Iodulo shor	tast war		Lost Time:	[-]	
🗌 Jei	rk:	ĥ	Modulo shortest w Modulo plus direc Modulo minus dire	direct. s direct.	mm/s3]	Last IIme.	44400	
Raw D:	rive Outpu	t 🔤	Fog + Fog -					
Outpu	t Mode:		1			Start		
Outpu	t Value:		0.01		[%]	Stop		
Set A	ctual Posi	tion	0.001 - 1					
Absol	lute	¥ -	- 0.1			Set		
Set T	arget Posi	tion	- 0.01					
Absol	lute	✓ H	Reversing S	equence		Set		
<u>.</u>			Start/Stop /elo Ster S	Sequence				
		2	Sinus Seque	nce (Bod	e			
		1	Sinus Oscil	lation	1			

到这里,已经可以测试 AMC EtherCAT 驱动器,下面我们来使用 PLC 控制 AMC EtherCAT

驱动器。

四、通过 PLC 程序控制伺服轴

1、新建并命名程序,点击" 🖳 PLC ",右键选择" 🔛 Add New Item… "

Add New Item - TestAMC					? X
Installed Templates	Sort by:	Default	•		Search Installed Templates
Plc Templates	01	Standard PLC Project		Plc Templates	Type: Plc Templates
Online Templates	0	Empty DI C Project		Pls Templates	Creates a new TwinCAT PLC project containing a task and a program.
Name:	estAMC				
Location: D	:\Documents\Visual Studio	2010\Projects\TestAMC	\TestAMC\		Browse
					Add Cancel

2、添加库文件 Tc2_MC2

3
- 2
ancel
an

新建轴变量 "M1", 新建使能模块 "MC_Power", 新建使能信号 "Enable_M1";

	1	PROGRAM MAIN	^
	2	VAR	
	3	M1:AXIS_REF; //新建轴	
	4	MC_Power_M1: MC_Power; // 使能电机	
	5	Enable_M1:BOOL; // 使能电机信号	=
	6	END VAR	
	7		
			~
<		III >	1
	1	MC Power M1 (Axis:= M1, Enable:= Enable M1, Enable Positive:= Enable M1, Enable Negative:= Enable M1,	
	2	Override:= 100, BufferMode:= , Options:= , Status=> , Busy=> , Active=> , Error=> , ErrorID=>)	-
将轴	±Μ	11 链接到 NC 轴,先点击" · · · · · · · · · · · · · · · · · · ·	

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TestAMC - Microsoft Visual Studio (Administr	ator)
File Edit View Project Build Debug	winCAT PLC Tools Scope Window Help
i 🛅 • 🕮 • 🎯 🔛 🥔 👗 🖎 👘 👪	Activate Configuration
Solution Evolorer	Restart TwinCAT System
	Restart TwinCAT (Config Mode)
	Reload Devices
TertAMC	Scan
a restaivic	
TestAMC - Microsoft Visual Studio (Administrator)	
File Edit View Project Build Debug IwinCAT PLC Tools Scope	e Window Help e 🔹 TwinCATRT (x86) 🔹 1 🚧 👘 👘
Solution Explorer • P × MAIN Te	stAMC ×
Genera	ettings Parameter Dynamics Online Functions Coupling Compensation
Axes Link To I	/0 Drive 1 (AMC Servo Drive)
Link To P	L3
b ■ Outputs Axis Type: b == 0 Drive	CANopen DS402/Profile MDP 742 (e.g. EtherCAT CoE Drive) 🛛 🤟
Ind. Ctrl Unit:	mm v Display (Only)
 Inputs Imputs Imputs 	Select Axis PLC Reference ('Axis 1')
→ ➡ Axis 2 ■ ■ PLCBesult -	Inone) 5 OK
TestAMC Fosition TestAMC Project	a: 4 Cancel
The External Types	● Unused
Axis Cyc DUTs Divider	le' ⊖∆i
🚰 GVLs Modulo:	
MAIN (PRG)	
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登录到 PLC;	
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启动 PLC;

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Exp	pression	Туре	Value	Prepared value	Address	Comment	
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	Enable_M1	BOOL	FALSE	TRUE		使能电机信号	
				5-27			
<				ш			>

将 "TRUE" 写入 "Enable_M1", 电机使能; 写入 "FALSE", 电机禁能;

到现在,我们已经可以通过 PLC 程序来控制驱动器了。

五、TPDO 和 RPDO 配置

1、在驱动器调试软件的"Network—RPDO 和 Network—TPDO"菜单中,根据需要

添加相应的 PDO;添加完后,保存到驱动器,并重启;

www.a-m-c.cn

192.168.3.23.3.1:1001 AMSADDR

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BIT

UINT

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Reserved1

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State

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InfoData

Drive 2 (AMC Servo Drive) Mappings Mortask 1 SAF - Device 2 (EtherCAT) 1

NC-Task 1 SAF - Device 2 (EtherCAT RO-Task 1 SAF - TestAMC Instance

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