1,	在接驱动器

通过调试软件 DriveWave 测试位置控制,下图为转向驱动器图片

根据接线板定义, 接好逻辑电源线 (P4-1 接 5VDC, P4-2 接 0V), 接 RS232 通讯线;

USB 转 232 线缆的 Com 端口号需小于 Com9;

	Download/Upload Project	
	Download Upload	
点击" Connect ",连接驱动器,弹出对话框"	, <b>"</b> , "	先
择" <sup>Upload</sup> ",上传驱动器内部的配置;		

注:在 Can 总线控制下,只是想通过 DriveWare 软件监控驱动器的参数,那么 Access

Connect To Drive	
Interface:	RS232 -
Settings	
Drive Address:	63
Serial Port:	COM6 ▼
Baud Rate:	115200 👻
Restore Defau	Its Auto Detect
Restore Defau Access Contr	Its Auto Detect

Control 需设置为 Read-Only , 如下图所示。

2、首先确认驱动器设置为位置模式,并且已经调试好了位置环和速度环参数,如下图

## 所示。

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3、通过 Scope 的 Waveform Generator 测试位置环

(1)确保 Preset Position 的值为0,点击"Set"按钮,将 Position Measured

和 Position Target 设为 0,注意此时的电机轴位置即为零点;

Preset Position:	0	ct
	Set	
Measured Position	: 00	t
Target	0	t

(2)点击"Presets"按钮,选择 Position,在 Scope 通道中出现 Position Target 和 Position Measured 两个变量,再点击"Add"按钮,选择 Current Measured, 监控电机实际电流;

	Signal	Units / Div	Offset	🔶 Add 🚽
	Position Target	1 kct	0.000 kct	😤 Change 🗸
	Position Measured	1 kct	0.000 kct	
-	Current Measured	1 A	0.000 A	Lemove
				Presets 🔻

(3) Units/Div为Y轴方向每一格的值,鼠标左键单击选中所需要更改的变量, 通过 Scale 右边的上下箭头来调整此值, Position Target 和 Position Measured 的 Units/Div 必须保持一致;





(4) Mode 选"Roll",即曲线为滚动显示;Target 选"Command Limiter",即 为带有速度和加减速限制的位置模式,Type 选"DC"; 点击"On/Off"按钮,左 边的圆形 LED 从红色变为绿色,即表示波形发生器功能激活;





(5)点击软件上部的"Enable"按钮,正常情况下,软件下部状态指示变为绿色, 电机使能,在 Offset 中填入目标位置,点击"回车"键,目标值下发,电机转到 目标位置;到此为止,位置测试完成;

