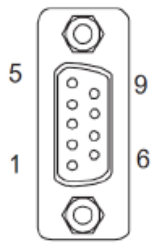


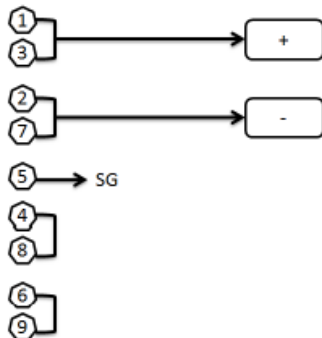
1. 測試品 : TSM17Q-3RG & TSM11Q-2RM
PROFACE GC-4401W

2. 接線方式 : PROFACE COM2 (RS422,RS485)

注意:PIN:4,8 , PIN:6,9 一定要短路

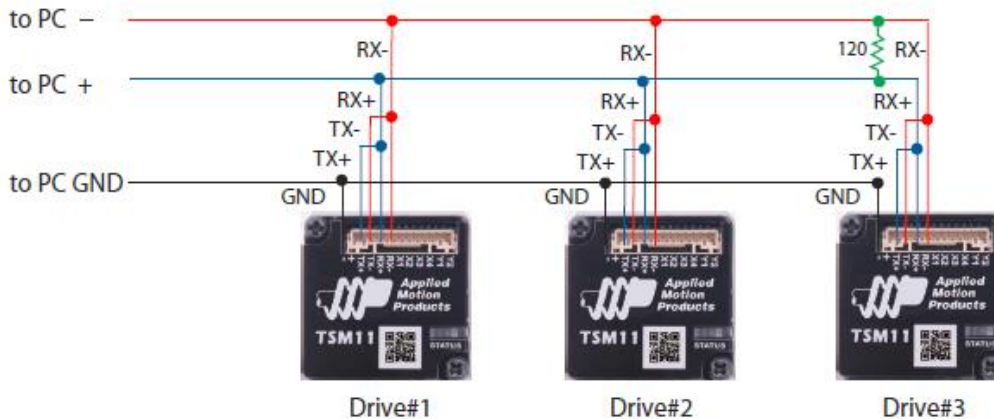
Pin Connection	Pin No.	RS-422/RS-485		
		Signal Name	Direction	Meaning
 (GP unit side)	1	RDA	Input	Receive Data A (+)
	2	RDB	Input	Receive Data B (-)
	3	SDA	Output	Send Data A (+)
	4	ERA	Output	Data Terminal Ready A (+)
	5	SG	-	Signal Ground
	6	CSB	Input	Send Possible B (-)
	7	SDB	Output	Send Data B (-)
	8	CSA	Input	Send Possible A (+)
	9	ERB	Output	Data Terminal Ready B (-)
	Shell	FG	-	Frame Ground (Common with SG)

一般 4 線式(4 wire、4W)代表 422，2 線式(2 wire、2W)代表 485。
連接 Modbus 控制器(RS-485)



TSM RS485 2 線制:

*.實測(近距離)時,GND 沒接時,亦能通訊



2. TSM 軟體設定:

控制模式:Modbus

*.以下模式參數設定，需與 PROFACE 對應

第1步: 配置	第2步: 參數整定	第3步: Q编程	运动仿真
1. 电机配置 电机型号 <input type="text"/> ... 速度限值 <input type="text" value="10 rps"/> <input type="checkbox"/> 使电机反向 加速度限值 <input type="text" value="1000 rps/s"/>		2. 控制模式 Modbus	
3. 控制模式设置 节点ID 节点ID <input type="text" value="1"/> SCL地址 <input type="text" value="1"/> 应答延时 <input type="text" value="2"/> 毫秒 <input type="checkbox"/> 上电时自动执行Q程序		波特率(重新上电有效) <input type="text" value="38400"/> bit/s(bps) 32位Word顺序 <input type="radio"/> Big Endian <input checked="" type="radio"/> Little Endian	
位置误差报警阈值 <input checked="" type="radio"/> <input type="text" value="20000"/> Counts(97656 Steps) <input type="radio"/> 不使用		电子齿轮 <input type="text" value="20000"/> Steps/Rev	

3. Proface 設定

控制器/PLC 設定

控制器 / PLC	
加入控制器 / PLC 删除控制器 / PLC	
控制器 / PLC 1	
摘要 改變控制器 / PLC	
製造商	<input type="text" value="Modbus-IDA"/> 系列 <input type="text" value="General MODBUS SIO Master"/> Port <input type="text" value="COM2"/>
文字資料模式	<input type="text" value="1"/> 改變
通信設定	
SIO Type	<input type="radio"/> RS232C <input checked="" type="radio"/> RS422/485(2wire) <input type="radio"/> RS422/485(4wire)
Speed	<input type="text" value="38400"/>
Data Length	<input type="radio"/> 7 <input checked="" type="radio"/> 8
Parity	<input checked="" type="radio"/> NONE <input type="radio"/> EVEN <input type="radio"/> ODD
Stop Bit	<input checked="" type="radio"/> 1 <input type="radio"/> 2
Flow Control	<input checked="" type="radio"/> NONE <input type="radio"/> ER(DTR/CTS) <input type="radio"/> XON/XOFF
Timeout	<input type="text" value="3"/> (sec)
Retry	<input type="text" value="2"/>
Wait To Send	<input type="text" value="1"/> (ms) <input checked="" type="checkbox"/> Default Value
Mode	<input checked="" type="radio"/> RTU <input type="radio"/> ASCII
<input type="button" value="Default"/>	

規格設定





允許控制器 / PLC
的台數

31

[追加機器](#)

No. Device 名稱

設定

	1	TSM11Q		Slave Equipment Address=1, Rest of the bits in this wor
	2	TSM17Q		Slave Equipment Address=9, Rest of the bits in this wor

間接機器



設定:Device 名稱 & 位址設定

個別位址設定

TSM11Q

Equipment Configuration | Function Code and Max Query

Equipment Address

Slave Equipment Address: 1

Bit manipulation (set/reset) to Holding Register

Rest of the bits in this word: Clear Do not clear

Note on when selecting "Do not clear":
If the ladder program writes data to Holding Register during the read/write process, the resulting data may be incorrect.

IEC61131 Syntax

Address Mode: 0-based (Default)

If you change the setting, please reconfirm all address settings.

Variables

Double Word word order: Low word first(L/H)

Import Export Default

確定 (O) 取消

暫\存器對照表

Beijer HMI Memory	MB Register in Drive	Notes	Units
Drive Monitoring			
400001	40001	Alarm Code(AL)	
400002	40002	Status Code(SC)	
400003	40003	Immediate Expanded Inputs(IS)	
400004	40004	Driver Board Inputs (ISX)	
400005...6	40005...6	Encoder Position(IE)	Enc Counts
400007...8	40007...8	Commanded Position(IP)	Steps
400009...10	40009...10	Absolute Position Command(P reg)	Steps
400011	40011	Immediate Actual Velocity (IV0)	.25 rpm
400012	40012	Immediate Target Velocity (IV1)	.25 rpm
400013	40013	Immediate Drive Temperature (IT)	C
400014	40014	Immediate Bus Voltage (IU)	.1 VDC
400015	40015	Immediate Position Error (IX)	Enc Counts
Move Parameters(Point-to-Point)			
400028	40028	Point-to-Point Acceleration (AC)	10 rpm/sec
400029	40029	Point-to-Point Deceleration (DE)	10 rpm/sec
400030	40030	Velocity (VE)	.25 rpm
400031...2	40031...2	Point-to-Point Distance (DI)	Steps
Move Parameter(Jogging)			
400047	40047	Jog Accel (JA)	10 rpm/sec
400048	40048	Jog Decel (JL)	10 rpm/sec
400049	40049	Jog Velocity (JS)	.25 rpm
Endian Register			
400134	40134	Endianness Switch	
Command Register			
400125	40125	0x66(FL Point-to-Point Move)	
400125	40125	0x96(CJ Jogging)	
400125	40125	0xD8(SJ Stop Jogging)	
400125	40125	0(Idle State)	

Table 4: Register Mapping



範例說明

a. 數值顯示 : Alarm Code(AL)



b. GO 按鈕 :FL



400125 暫存器 :	常數:102	FL	400126:選擇 Q 程式編號
	常數:150	JOG MOVE	
	常數:216	JOG STOP	
	常數:120	Q 執行	
	常數:225	STOP	