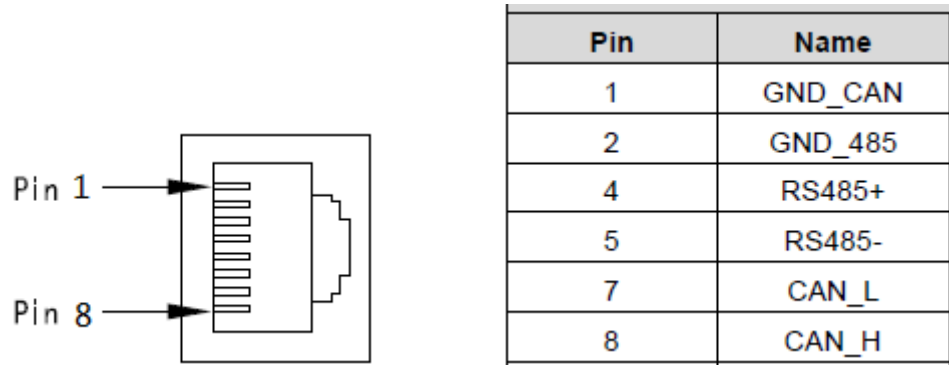


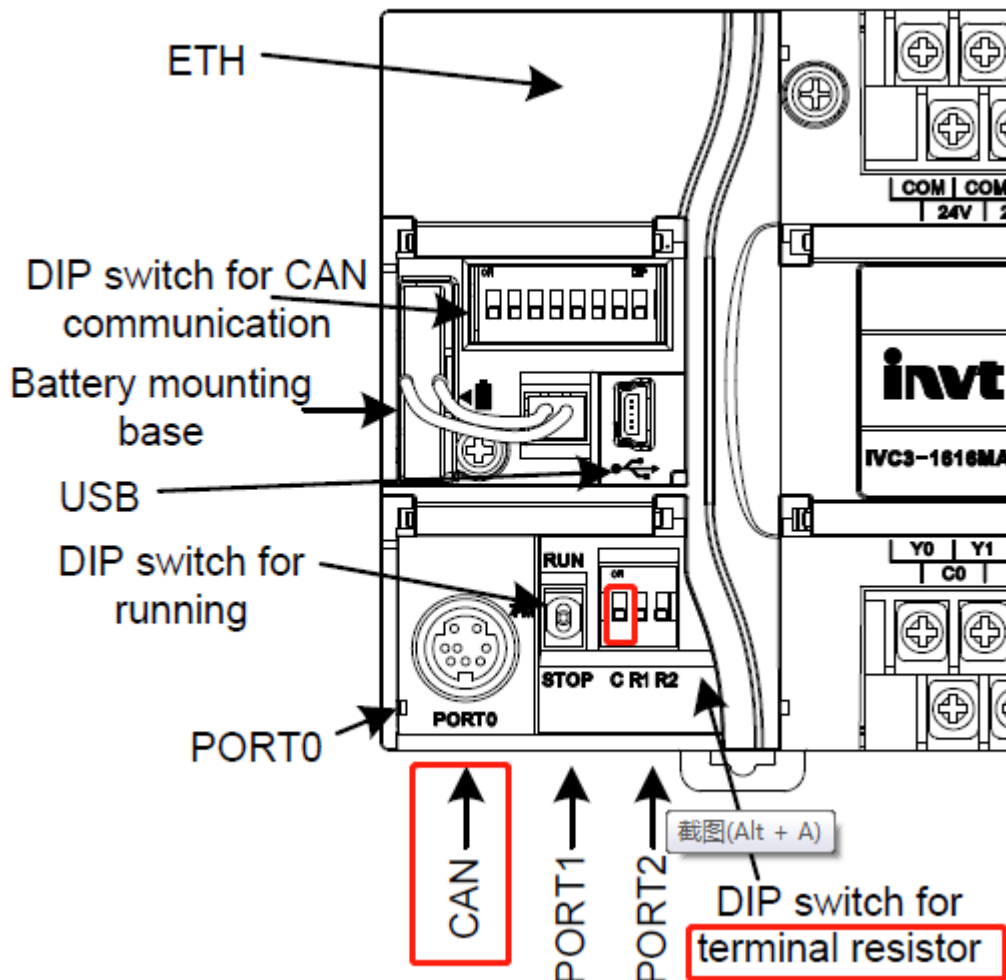
IVC3 and DA200 CANopen Communication

1, Hardware connection

CN3 interface of Servo



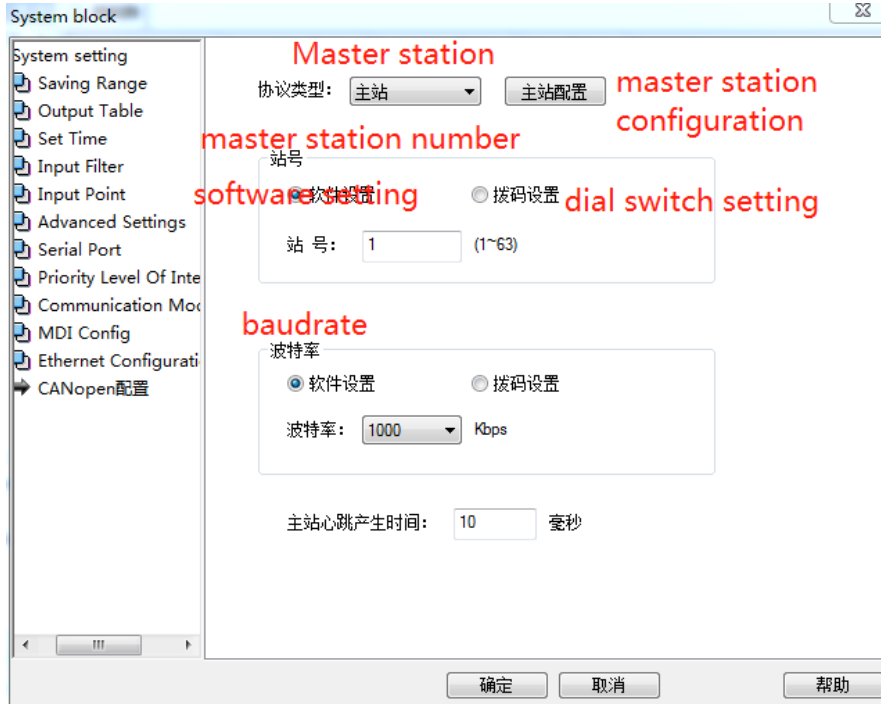
Connect CAN_L, CAN_H and GND to IVC3, and make terminal resistance of CANOpen on ;



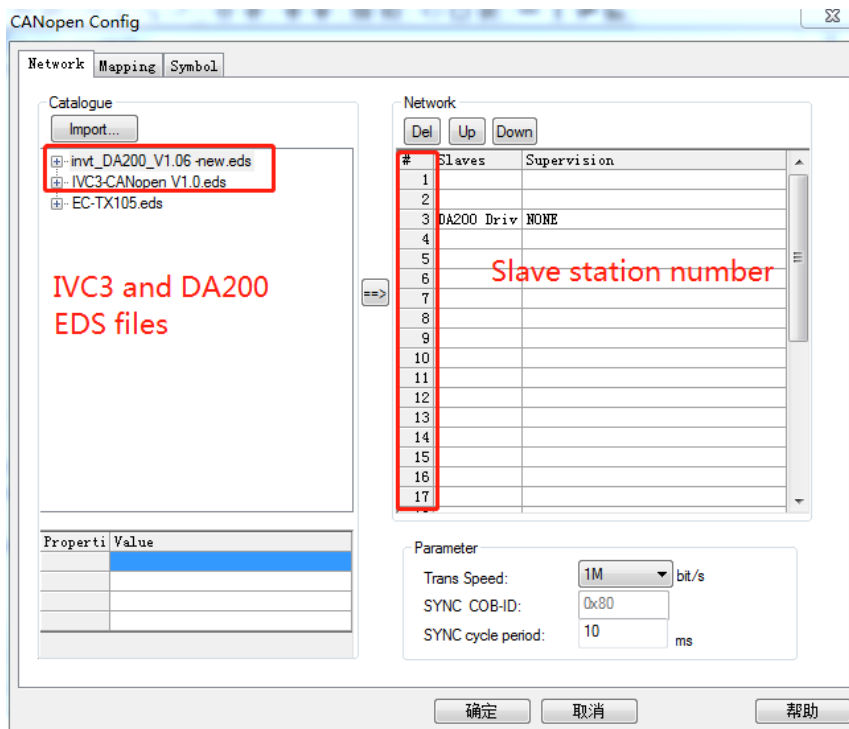
2, Software settings

1) PLC settings

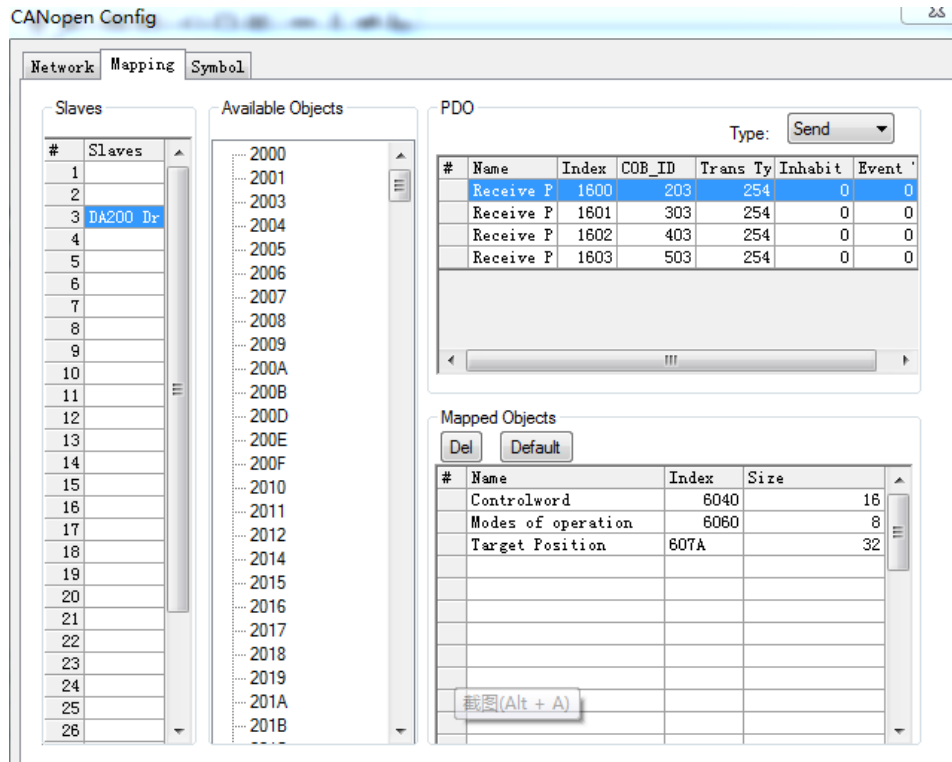
Master station 1, slave station 3; baudrate 1M;



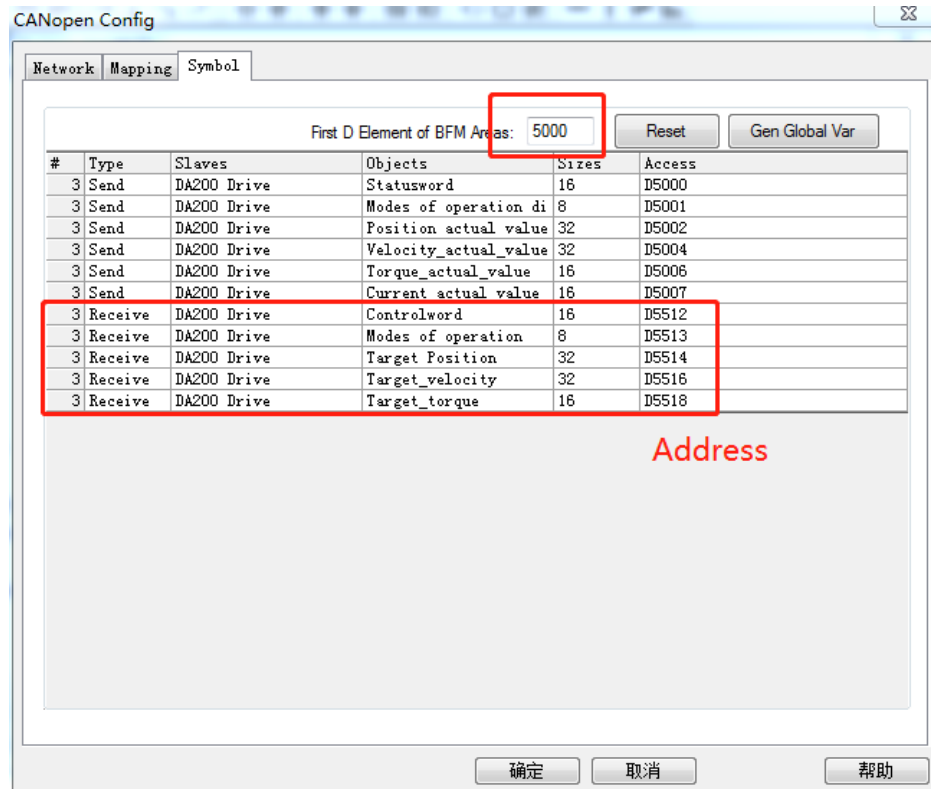
Import EDS files of DA200 and IVC3, configure slave station numbers;



Add the address you need



Here you can see the address of parameters



2) Servo settings

Parameter Setting

P0	P1	P2	P3	P4	P5	P6	PtP0	PtP1	PtP2	P8
Function Code	Parameter Name						Current Value	*	U	
P0.00	Motor Type						0		-	
P0.01	Encoder type selection						unknown		-	
P0.02	Motor Forward Direction						CCW		-	
P0.03	Control Mode Selection						CANopen mode		-	
P0.04	Internal servo enabling						Disable		-	
P0.05	Jog speed						0		r	

Parameter Setting

P0	P1	P2	P3	P4	P5	P6	PtP0	PtP1	PtP2	P8	P9	P10	Differen
Function Code	Parameter Name						Current Value	*	Unit	Min			
P4.01	485 Local communication address						0		-	1			
P4.02	Can baudrate selection						1M		-	0			
P4.03	Communication baudrate selection						9600		-	0			
P4.04	Communication parity mode						N 8 1		-	0			
P4.05	Can Local communication address						3		-	1			
P4.06	485 Local communication address						Keep fault		-	0			
P4.07	EtherCAT synchronisation period						250us		-	0			

3, following target speed control program for reference

