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PL.FILTERTIME

General Information	
Type	R/W Parameter
Description	Sets the position command filter period.
Units	Milliseconds
Range	0, 0.5, 1, 2, 4, 8, 16, 32, 64, 128, 256, 512
Default Value	0
Data Type	Float
Start Version	M_01-08-01-000

Variants Supported

Variant	Supported
AKD Base	Yes
AKD with Position Indexer	Yes
AKD EtherCAT	Yes
AKD CANopen	Yes
AKD BASIC	Yes
AKD SynqNet	Yes*
AKD EtherNet/IP	Yes
AKD Profinet	Yes
AKD sercos® III	Yes
AKD-N	Yes
AKD-C	No

*In SynqNet, a parameter may be available in the firmware but have no effect on the system. See SynqNet Supported Parameters.

Fieldbus Information

If your drive type is listed as supported but no index, address, or instance number is listed, then this parameter is accessible through WorkBench, but not over your fieldbus type. For information on SynqNet parameters see SynqNet Supported Parameters.

Description

PL.FILTERTIME sets the period of a "boxcar" moving average filter on the position command. When PL.FILTERTIME is greater than zero, the filter is active.

The moving average filter is applied to all Command Source types, but only active when the AKD is in Position mode.

This feature is typically used for smoothing abrupt changes in position command, or filtering coarse command steps from low resolution controllers, or electronic gearing.

When the filter is on (PL.FILTERTIME > 0), total motion commanded will be delayed by the period the filter is set to.

Related Topics

[Electronic Gearing](#)

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