Start the communication program
The first window is

- Disable the drive (if it is enabled)
- Set the OPMODE to mode 8: Position Motion Tasks
- Open the Digital I/O window and feed the program with the shown data. Not required if commands are giving from the serial port.

- Apply
- Save to EEPROM & Reset Amplifier? YES
- Restart the software again
- Disable the drive again (if it is enabled)
Open the **Position** window and feed the program with the shown data.

- Press Apply and OK

Open the **Homing** window and feed the program with the shown data.

- Press Apply and OK

Change to the **Position data** window and put in the shown values
Click on this arrow to select the motion task input table.

Selecting the Motion Task no.

Double click on the Motion Task no. to open it.
• put in the shown values

• Press Apply and OK

• Change to the motion task number 2

If you see the button Apply only in grey like shown here, you had forgotten to set the software disable

• Press Apply and OK

• Save the data to EEPROM
• Reset the drive
  first window (see page 1) button STATUS = ... and then button RESET and YES
• Restart the program
• Set the digital I/O’s to low level
• Enable the drive (hardware and software)
• Control the drive by the digital IO

<table>
<thead>
<tr>
<th>DIGITAL-IN 1</th>
<th>DIGITAL-IN 2</th>
<th>PSTOP</th>
<th>NSTOP</th>
<th>comment</th>
</tr>
</thead>
<tbody>
<tr>
<td>17: Start_MT IO</td>
<td>9: MT_No_Bit</td>
<td>20 Start_Jog v =x</td>
<td>12: Reference</td>
<td>Function of this dig.IO</td>
</tr>
<tr>
<td>High</td>
<td>Low</td>
<td>Low</td>
<td>Low</td>
<td>Start Reference Traverse (=Motion Task with the No. 0)</td>
</tr>
<tr>
<td>High</td>
<td>Low</td>
<td>Low</td>
<td>High</td>
<td>Activate the Home Switch, now the motor will stop and the reference point is set.</td>
</tr>
<tr>
<td>Low</td>
<td>Low</td>
<td>Low</td>
<td>Low</td>
<td></td>
</tr>
<tr>
<td>Low</td>
<td>Low</td>
<td>Low</td>
<td>Low</td>
<td>Set Motion Task No. 1 (2^0)</td>
</tr>
</tbody>
</table>
The motor runs from position 0 to 4000 µm (4 resolutions) with 5000 µm/s (300rpm), decelerates to zero, has a brake from 1 second and starts Motion Task 2. It turns anticlockwise back to position 250 µm with 125 µm/s (7.5 rpm). The DIG.-OUT 1 (INPOS) is low, if the actual position is outside the In_Position window range.

The DIG.-OUT 2 (Next-INPOS) is low, while Motion Task 1 is active and high after the start of Task 2.

After using the Jog command the motor will go to the defined position from motion task 1, if you start this motion task.

- Operating the S600 in Serial Positioning from serial commands

- MH (serial command to start homing)
- Motion task higher than 192 can be changed without rebooting by coldstarting the drive information is saved in the RAM, below 192 are saved in the Eeprom.
- Move is the serial command that starts a move from the motion task table. Example (Move 1) Starts Motion Task no. 1

- What is an Order?
- An Order is the serial command for the Motion Task. The Order below has the same information as in the Motion Task table below.

ORDER 1 20 4 8200 1 1 0 0 2 0

ORDER 1 20 4 8200 1 1 0 0 2 0