Nanotec® PLUG & DRIVE

Short instructions
Original: de

Version 1.0.0

Introduction

The *N5* is a controller for the *open loop* or *closed loop* operation of stepper motors and the *closed loop* operation of BLDC motors.

This document describes the installation and commissioning of the controller. You can find the detailed documentation for the product on the Nanotec website **us.nanotec.com**. The short instructions do not replace the technical manual oft he product.

Copyright, marking and contact

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Intended use

The *N5 controller* is used to control stepper and BLDC motors and is designed for use under the approved **Environmental conditions**.

Any other use is considered unintended use.

Note

Changes or modification to the controller are not permitted.

Warranty and disclaimer

Nanotec produces component parts that are used in a wide range of industrial applications. The selection and use of Nanotec products is the responsibility of the system engineer and end user. Nanotec accepts no responsibility for the integration of the products in the end system.

Under no circumstances may a Nanotec product be integrated as a safety controller in a product or construction. All products containing a component part manufactured by Nanotec must, upon delivery to the end user, be provided with corresponding warning notices and instructions for safe use and safe operation. All warning notices provided by Nanotec must be passed on directly to the end user.

Our general terms and conditions apply: **en.nanotec.com/service/general-terms-and-conditions/**.

Specialist staff

Only specialists may install, program and commission the device:

- Persons who have appropriate training and experience in work with motors and their control.
- Persons who are familiar with and understand the content of this technical manual.
- Persons who know the applicable regulations.

EU directives for product safety

The following EU directives were observed:

- RoHS directive (2011/65/EU, 2015/863/EU)
- EMC directive (2014/30/EU)

Other applicable regulations

In addition to this technical manual, the following regulations are to be observed:

- Accident-prevention regulations
- Local regulations on occupational safety

Safety and warning notices

Note

- Damage to the controller.
- Changing the wiring during operation may damage the controller.
- Only change the wiring in a de-energized state. After switching off, wait until the capacitors have discharged.

Note

- Fault of the controller due to excitation voltage of the motor.
- Voltage peaks during operation may damage the controller.
- Install suitable circuits (e.g., charging capacitor) that reduce voltage peaks.

Note

- There is no polarity reversal protection.
- Polarity reversal results in a short-circuit between supply voltage and GND (earth) via the power diode.
- Install a line protection device (fuse) in the supply line.

Note

- The device contains components that are sensitive to electrostatic discharge.
- Improper handling can damage the device.
- Observe the basic principles of ESD protection when handling the device.

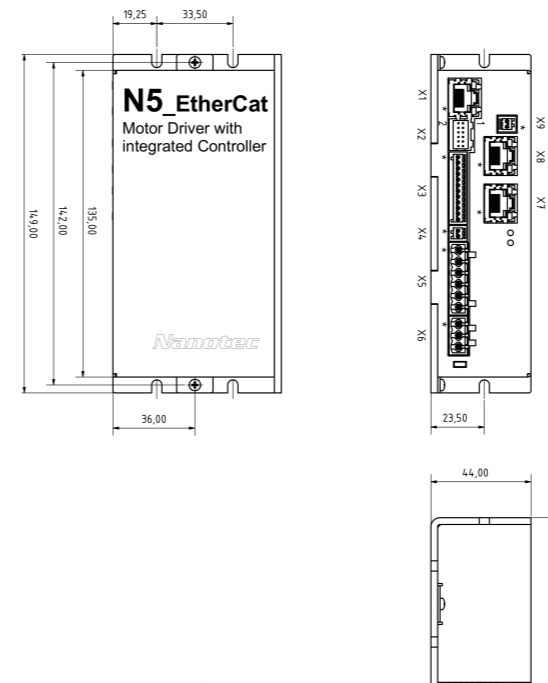## Technical details and pin assignment

Environmental conditions

Environmental condition	Value
Protection class	IP20
Ambient temperature (operation)	-10 … +40°C
Air humidity (non-condensing)	0 … 95 %
Altitude of site above *sea level* (without drop in performance)	1500 m
Ambient temperature (storage)	-25 … +85°C

Electrical properties and technical data

Property	Description / value
Operating voltage	• 12 V -5% …72 V +4% DC for *low-current version* with designation N5-1-1 • 12 V - 48 V +/-5% DC for the *high-current version* with designation N5-2-1 and up to **hardware version** w007 • 12 V -5% …57.4 V DC for the *high-current version* with designation N5-2-1 and from **hardware version** w007b
Rated current	N5-1-1 (*low current*): 10 A$_{rms}$ N5-2-1 (*high current*): 18 A$_{rms}$
Peak current	N5-1-1 (*low current*): 10 A$_{rms}$ N5-2-1 (*high current*): 40 A$_{rms}$ for 5 seconds
Commutation	Stepper motor – open loop, stepper motor – closed loop with encoder, BLDC motor – closed loop with Hall sensor, and BLDC motor – closed loop with encoder
Operating modes	*Profile Position Mode, Profile Velocity Mode, Profile Torque Mode, Velocity Mode, Homing Mode, Interpolated Position Mode, Cyclic Sync Position Mode, Cyclic Sync Velocity Mode, Cyclic Synchronous Torque Mode, Clock-Direction Mode*
Set value setting / programming	*EtherCAT, Ethernet* (REST with the NanoIP user interface), *clock-direction, analog, NanoJ program*
Interfaces	EtherCAT, Ethernet

Property	Description / value
Inputs	• 4 inputs, 5 V/24 V (inputs 1 to 4) individually switchable by means of software, factory setting: 5 V • 2 inputs, wide range 5-24 V (inputs 5 and 6); • 2 analog inputs -10 to +10 V or 0–20 mA (switchable by means of software)
Outputs	2 outputs, (open drain, 0 switching, max. 24 V and 500 mA)
Encoder input	5 V or 24 V signal, differential or single-ended (switchable by means of software), max. resolution 65536 increments per revolution (16-bit)
Protection circuit	Overvoltage and undervoltage protection Overtemperature protection (> 75° Celsius on the power board) Polarity reversal protection: In the event of a polarity reversal, a short-circuit will occur between supply voltage and GND over a power diode; a line protection device (fuse) is therefore necessary in the supply line. The values of the fuse are dependent on the application and must be dimensioned • greater than the maximum current consumption of the controller • less than the maximum current of the voltage supply. If the fuse value is very close to the maximum current consumption of the controller, a medium / slow tripping characteristics should be used.

Dimensioned drawings

N5_EtherCat
Motor Driver with integrated Controller

19,25 33,50 169,00 142,00 135,00 36,00 23,50 44,00 74,00

Overtemperature protection

Above a temperature of approx. 75°C on the power board (corresponds to 65–72°C outside on the cover), the power part of the controller switches off and the error bit is set . After cooling down and confirming the error , the controller again functions normally.

LED signaling

Power LED

Normal operation

In normal operation, the green power LED L1 flashes briefly once per second.

Case of an error

If an error has occurred, the LED turns red and signals an error number.

The following table shows the meaning of the error numbers.

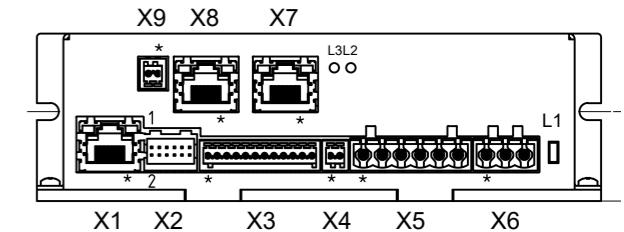| Flash rate	Error
1	General
2	Voltage
3	Temperature
4	Overcurrent
5	Controller
6	Watchdog-Reset

Note

For each error that occurs, a more precise error code is stored in object **1003**$_h$.

Pin assignment

Pin 1 is marked with an asterisk "*".

X9 X8 X7 L3 L2 L1
X1 X2 X3 X4 X5 X6

Connector	Function	Pin assignment / description
X1	Ethernet	Configuration interface
X2	Encoder and Hall sensor 5 V / 24 V DC signal Max. 1 MHz Switching thresholds: **5 V (factory setting)**: On: >3.8 V; Off: <0.26 V **24 V**: On: >14.42 V; Off: <4.16 V	1. GND 2. Vcc: +5V (factory setting) /24 V DC output, switchable with object 2059$_h$ 3. A 4. B 5. A\\ 6. B\\ 7. I 8. I\\ 9. Hall 1 10. Hall 2 11. Hall 3 12. Shielding
X3	Inputs and outputs Switching thresholds for digital **inputs 1 - 4**: **5 V (factory setting)**: On: >3.8 V; Off: <0.26 V **24 V**: On: >14.42 V; Off: <4.16 V Switching thresholds for digital **inputs 5 - 6**: On: >3.25 V; Off: <2 V	1. GND 2. Digital input 1; 5 V / 24 V Signal, switchable with object **3240**$_h$ 3. Digital input 2; 5 V / 24 V Signal, switchable with object **3240**$_h$ 4. Digital input 3: 5 V / 24 V, switchable with object **3240**$_h$, max. 1 MHz; *direction input* in clock/direction mode 5. Digital input 4: 5 V / 24 V, switchable with object **3240**$_h$, max. 1 MHz; *clock input* in clock/direction mode 6. Digital input 5; 5…24 V signal, not switchable 7. Digital input 6; 5…24 V signal, not switchable 8. Analog input 1: 10 Bit, 0-10 V oder 0-20 mA, switchable with object **3221**$_h$ 9. Analog input 1: 10 Bit, 0-10 V oder 0-20 mA, switchable with object **3221**$_h$ 10. Digital output 1: Open drain, max 24 V/500 mA 11. Digital output 2: Open drain, max 24 V/500 mA 12. Shielding
X4	Brake 24V Brakes have to be connected using an appropriate circuit if **+UB**>24 V!	1. Brake+: internally connected to **+UB** 2. Brake -: PWM-controlled open-drain output, max 1.5 A

Connector	Function	Pin assignment / description

X5	Motor	1. Shielding
		2. A (Stepper)
		   U (BLDC)
		3. A\ (Stepper)
		   V (BLDC)
		4. B (Stepper)
		   W (BLDC)
		5. B\ (Stepper)
		6. Shielding

X6	Voltage supply Permissible operating voltage: See *Electrical properties and technical data*	1. **Shielding** 2. **+UB** 3. **GND**
X7	EtherCAT IN	
X8	EtherCAT OUT	
X9	Supply for Encoder/ Hall sensor, external logic supply To be connected if 24V encoder is used or logic supply of the controller desired.	1. **+UB Logic / Encoder**: +24 V 2. **GND**

> **Note**
> - EMC: For a DC power supply line longer than 30 m or when using the motor on a DC bus, additional interference-suppression and protection measures are necessary.
> - An EMI filter is to be inserted in the DC supply line as close as possible to the controller/motor.
> - Long data or supply lines are to be routed through ferrites.

Commissioning

The *Plug & Drive Studio* software offers you an option for performing the configuration and adapting the controller to the connected motor. You can find further information in document *Plug & Drive Studio: Quick Start Guide* at **us.nanotec.com**.

Observe the following note:

> **Note**
> - EMC: Current-carrying cables – particularly around supply and motor cables – produce electromagnetic alternating fields.
> - These can interfere with the motor and other devices. Nanotec recommends the following measures:
> - Use shielded cables and earth the cable shielding on both ends over a short distance.
> - Use cables with cores in twisted pairs.
> - Keep power supply and motor cables as short as possible.
> - Earth motor housing with large contact area over a short distance.
> - Lay supply, motor and control cables physically separate from one another.

Configuration via Ethernet

Establishing connection with the controller

Setting the IP address

Each of the connected devices (controller and communication partners) in an Ethernet network or with a point-to-point Ethernet connection requires a unique IP address. This can either be obtained automatically (DHCP) or generated (Auto-IP) or assigned statically. In the following, "communication partner" refers to a PC or laptop.

You can integrate the controller in an existing Ethernet network. To do this, you only need to establish the physical connection with a standard Ethernet cable. Provided DHCP and UPnP are activated on the controller (factory setting), the controller is also automatically detected on the network and can immediately be operated via a PC located on the network.

Setting DHCP/Auto-IP

IP addresses can be obtained dynamically in a network from a DHCP server or, for example, in the case of a PC direct connection, can be automatically self-generated without DHCP by the two communication devices (e.g., PC and controller). DHCP and UPnP are preset in the controller at the factory for automatically obtaining an IP address from a DHPC server or for automatic IP address generation. To establish the connection to the controller, it may only

be necessary to make a few settings on the communication partner (e.g., PC or laptop). Settings using the Windows 7 operating system as an example:

1. Press the Windows Start button and select *Control Panel*.
2. Select *Network and Sharing Center*.
3. Select *Change adapter settings*.
4. A list of the available network adapters is displayed. Open the properties on the adapter to which the controller is connected (e.g., click with the right mouse button).
5. *Select Internet Protocol version 4 (TCP/IPv4)* and press the *Properties* button.
6. Select the *Obtain an IP address automatically* option.
7. Confirm acceptance of the entries with the *OK* button.

For the communication partner to automatically detect the controller in the entire network or for a point-to-point connection (PC direct connection), network discovery must be switched on and the UPnP service must be started on the communication partner (e.g., PC or laptop). No further settings are necessary on the controller. Settings using the Windows 7 operating system as an example:

1. Switching on network discovery:
   a. Press the Windows Start button and select *Control Panel*.
   b. Select *Network and Sharing Center*.
   c. Select *Change advanced sharing settings*.
   d. Open the *Public* section.
   e. Under *Network discovery*, select the *Turn on network discovery* option.

2. Activating the UPnP service:
   a. Press the Windows Start button and then right-click on *Computer* and select *Manage*.
   b. Open the *Services and Applications* node and select *Services*.
   c. Double-click the *UPnP device host* service to open.
   d. As *Startup type*, select *Automatic* and press the *Start* button.
   e. Confirm acceptance of the entries with the OK button.

Configuration via EtherCAT

Software connection

> **Tip**
> The following description assumes that an EtherCAT master from Beckhoff with the *TwinCAT* software is used.

1. Connect the EtherCAT master to the controller, see **Technical details and pin assignment**.
2. Supply the controller with voltage.
3. Obtain the *ESI file* that corresponds exactly to the used **firmware version** from the following sources:
   a. Via the Nanotec homepage **us.nanotec.com**. The current version of the firmware and the *ESI file* can be found in the *Plug & Drive Studio* download folder.
   b. From Nanotec support.
4. Close the *TwinCAT* system manager if it is open.
5. Then copy the *ESI file* to the *TwinCAT* subfolder:
   - If you use *TwinCAT* version 2, use folder `<TWINCAT INSTALL DIR>/Io/EtherCAT`
   - If you use *TwinCAT* version 3, use folder `<TWINCAT INSTALL DIR>/3.1/Config/Io/EtherCAT`

   Example

   Example: If *TwinCAT* 2 is installed on your computer under path `C:\TwinCAT\`, copy the *ESI file* to path `C:\TwinCAT\Io\EtherCAT\`.

6. Open the *ESI file* with an editor. Find the *AddInfo* parameter. Enter:
   - the value "2" if you would like to integrate the controller as *Box* (factory settings)
   - the value "0" if you would like to integrate the controller as *NC-Axis*

   Save and close the file.
7. Now restart the *TwinCAT system manager*. The *ESI files* are read in again following a restart.

> **Note**
> The cycle time of the sync signal must always be set to 1 ms. You can set the bus cycle time (and, consequently, the interpolation time in $60C2_h$) to integer multiples of 1 ms.

Setting the motor data

Prior to commissioning, the motor controller requires a number of values from the motor data sheet.

- Number of pole pairs: Object 2030_h:00_h (pole pair count) The number of motor pole pairs is to be entered here. With a stepper motor, the number of pole pairs is calculated using the step angle, e.g., 1.8° = 50 pole pairs, 0.9° = 100 pole pairs (see step angle in motor data sheet). With BLDC motors, the number of pole pairs is specified directly in the motor data sheet.

- Setting the motor current / motor type:
  - Stepper motor only: Object 2031_h:00_h: Rated current (bipolar) in mA (see motor data sheet)
    ▸ Object 2031_h:00_h: Rated current (bipolar) in mA (see motor data sheet)
    ▸ Object 3202_h:00_h (Motor Drive Submode Select): Defines motor type stepper motor, activates current reduction on motor standstill: 0000008h.
    ▸ Object 2037_h (Open Loop Current Reduction Value/factor): the root mean square is specified to which the rated current is to be reduced if current reduction is activated in *Open Loop*.
  - BLDC motor only:
    ▸ Object 2031_h:00_h Peak current in mA (see motor data sheet)
    ▸ Object $203B_h$:01_h Rated current in mA (see motor data sheet)
    ▸ Object $203B_h$:02_h Maximum duration of the peak current in ms (for initial commissioning, a value of 100 ms is recommended; this value is to be adapted later to the specific application).
    ▸ Object 3202_h:00_h (Motor Drive Submode Select): Defines motor type BLDC: 00000041h

- Motor with encoder: Object 20592059_h:00_h (Encoder Configuration): Depending on the encoder version, one of the following values is to be entered (see motor data sheet):
  - Supply voltage 5V, differential: 00000000h
  - Supply voltage 24V, differential: 00000001h
  - Supply voltage 5V, single-ended: 00000002h
  - Supply voltage 24V, single-ended: 00000003h

- Motor with brake: Object 3202_h:00_h (Motor Drive Submode Select): The brake control is activated for the initial commissioning. Depending on the specific application, this configuration can be deactivated later if necessary. One of the following values is to be entered depending on the motor type:
  - Stepper motor, brake control (and **current reduction** while at standstill) activated: 0000000Ch
  - BLDC motor, brake control activated: 00000044h

Auto setup

To determine a number of parameters related to the motor and the connected sensors (encoders/Hall sensors), an auto setup is performed. **Closed Loop** operation requires a successfully completed auto setup.

> **Note**
> - Note the following prerequisites for performing the auto setup:
> - The motor must be load-free.
> - The motor must not be touched.
> - The motor must be able to turn freely in any direction.
> - No NanoJ programs may be running (object 2300_h:00_h bit 0 = "0", see **2300h NanoJ Control**).

> **Tip**
> As long as the motor connected to the controller or the sensors for feedback (encoders/Hall sensors) are not changed, auto setup is only to be performed once during initial commissioning.

Execution

1. To preselect the *auto setup* operating mode, enter the value "-2" (="FE_h") in object 6060_h:00_h.
   The *power state machine* must now switch to the *Operation enabled* state.

2. Start *auto setup* by setting bit 4 *OMS* in object 6040_h:00_h (controlword). While the auto setup is running, the following tests and measurements are performed in succession:

   To determine the values, the direction of the measurement method is reversed and edge detection re-evaluated.

   Value 1 in bit 12 *OMS* in object 6041_h:00_h (statusword) indicates that the auto setup was completely executed and ended. In addition, bit 10 *TARG* in object 6041_h:00_h can be used to query whether (= "1") or not (= "0") an encoder index was found.
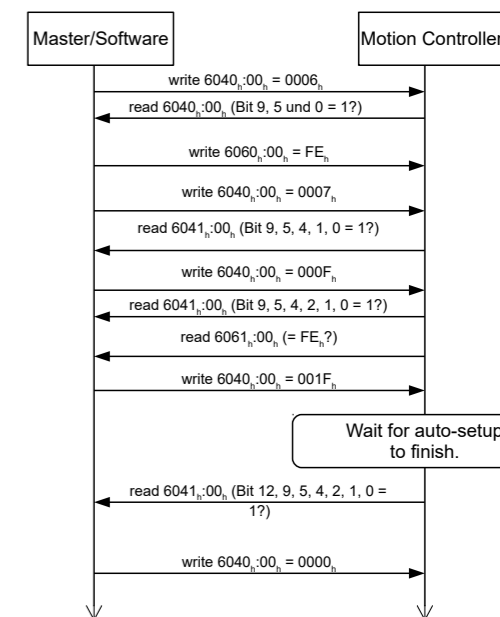
> **CAUTION**
> - After executing auto setup mode, the internal coordinate system is no longer valid.
> - *Homing* alone does not suffice! If the controller is not restarted, unexpected reactions may result.
> - Restart the device after an auto setup!

Test run

As an example, the **Velocity** operating mode is used.

The values are transferred from your *EtherCAT master* or to the controller. After every transfer, the *master* should use the status objects of the controller to ensure successful parameterization.

1. Select the *Velocity* mode by setting object 6060_h (Modes Of Operation) to the value "2".
2. Write the desired speed in 6042_h.
3. Switch the *power state machine* to the *Operation enabled* state.

   The following sequence starts *Velocity* mode; the motor turns at 200 rpm.
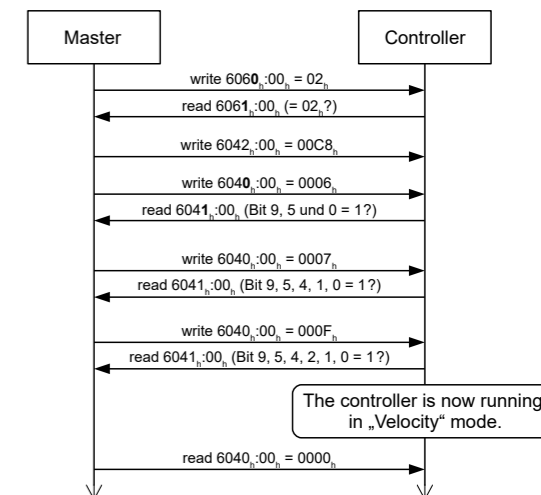
4. To stop the motor, set controlword (6040_h) to "0".