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1 = Neg, end switch, zero pulse

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 1 = Neg. end switch, zero pulse

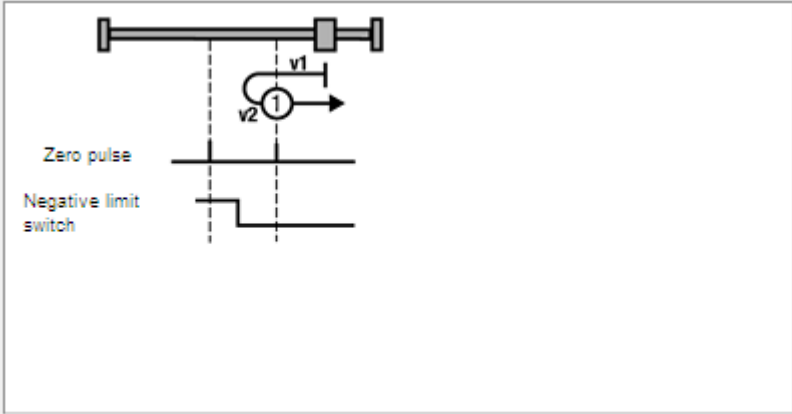
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



2 = Pos, end switch, zero pulse

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 2 = Pos. end switch, zero pulse

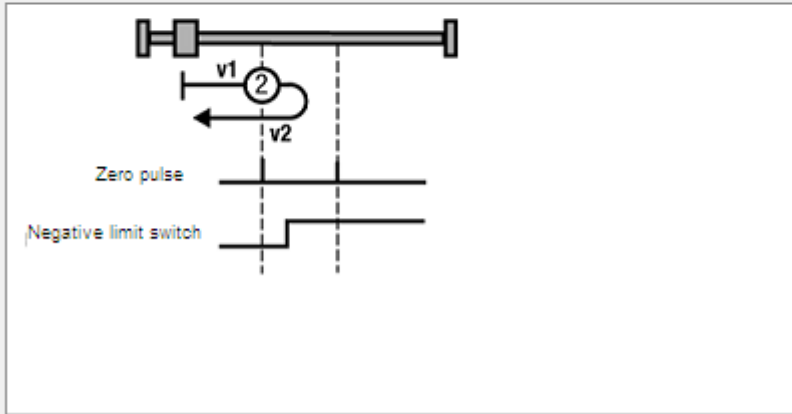
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



3 = Pos, reference cams, zero pulse at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 3 = Pos. reference cams, zero pulse at RefNock=Low

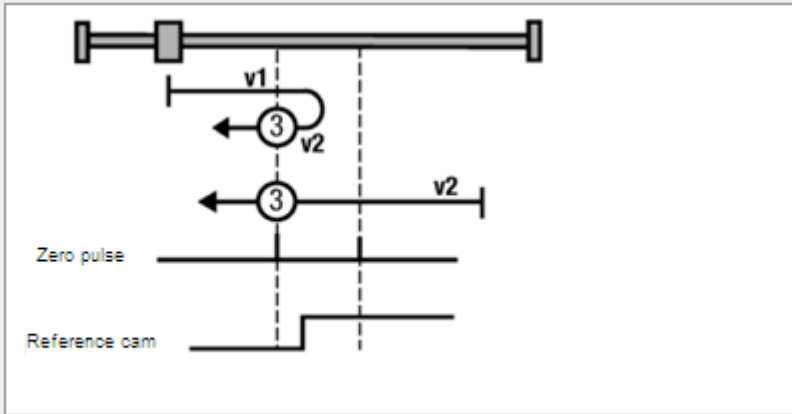
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



4 = Pos, reference cams, zero pulse at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 4 = Pos. reference cams, zero pulse at RefNock=High

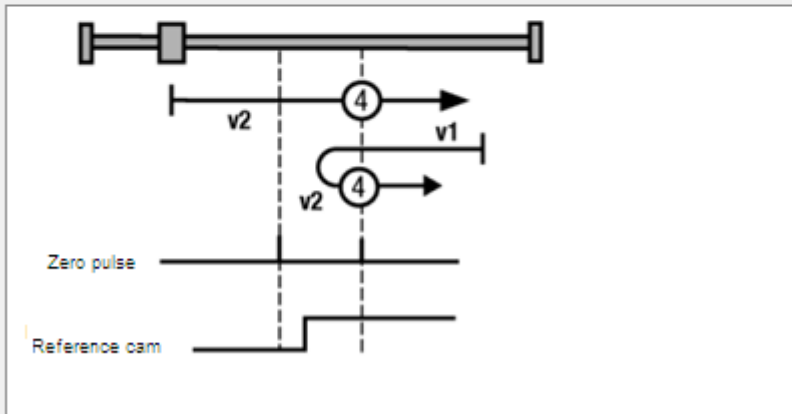
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



5 = Neg, reference cams, zero pulse at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 5 = Neg. reference cams, zero pulse at RefNock=Low

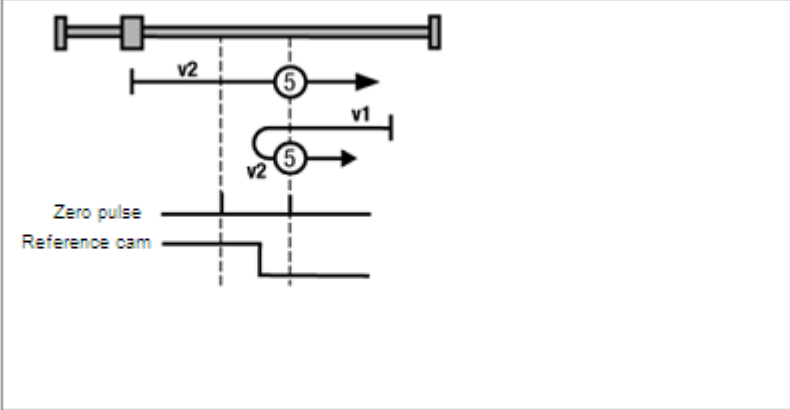
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



6 = Neg, reference cams, zero pulse at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 6 = Neg. reference cams, zero pulse at RefNock=High

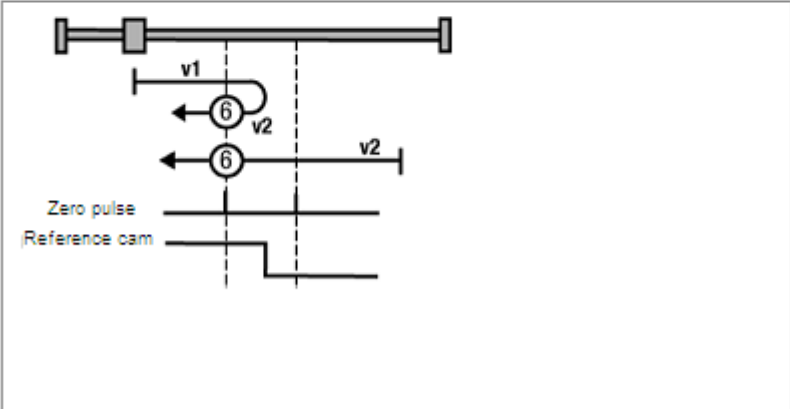
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



7 = -> left reference cam polarity, zero pulse at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 7 = -> left reference cam polarity, zero pulse at RefNock=Low

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram illustrates the motion profile for mode 7. It features a horizontal axis representing position and a vertical axis representing time. A reference cam signal is shown as a step function that transitions from low to high and then back to low. The velocity profiles for the 'lièvre' (V1) and 'tortue' (V2) phases are shown as curves. The 'Zero pulse' signal is a single pulse that occurs when the reference cam signal is low. The motion starts at the beginning of the cam pulse, moves left at speed V2, then right at speed V1, and finally left at speed V1. The 'Zero pulse' occurs during the first leftward movement at speed V2.

8 = -> left reference cam polarity, zero pulse at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 8 = -> left reference cam polarity, zero pulse at RefNock=High

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram illustrates the motion profile for mode 8. It features a horizontal axis representing position and a vertical axis representing time. A reference cam signal is shown as a step function that transitions from low to high and then back to low. The velocity profiles for the 'lièvre' (V1) and 'tortue' (V2) phases are shown as curves. The 'Zero pulse' signal is a single pulse that occurs when the reference cam signal is high. The motion starts at the beginning of the cam pulse, moves right at speed V1, then left at speed V2, and finally right at speed V1. The 'Zero pulse' occurs during the first rightward movement at speed V1.

9 = -> right reference cam polarity, zero pulse at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 9 = -> right reference cam polarity, zero pulse at RefNock=High

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram shows a horizontal axis with a carriage on the left. Three velocity profiles are shown: v1 (top), v2 (middle), and v2 (bottom). The top v1 profile starts at a high speed, decelerates to zero, and then accelerates back to high speed. The middle v2 profile starts at a high speed, decelerates to zero, and then accelerates back to high speed. The bottom v2 profile starts at a high speed, decelerates to zero, and then accelerates back to high speed. Below the velocity profiles are two digital signals: 'Zero pulse' and 'Reference cam'. The 'Zero pulse' signal is a single pulse that occurs when the velocity profiles reach zero. The 'Reference cam' signal is a square wave that is high during the deceleration phase and low during the acceleration phase.

10 = -> right reference cam polarity, zero pulse at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 10 = -> right reference cam polarity, zero pulse at RefNock=Low

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram shows a horizontal axis with a carriage on the left. Three velocity profiles are shown: v1 (top), v2 (middle), and v2 (bottom). The top v1 profile starts at a high speed, decelerates to zero, and then accelerates back to high speed. The middle v2 profile starts at a high speed, decelerates to zero, and then accelerates back to high speed. The bottom v2 profile starts at a high speed, decelerates to zero, and then accelerates back to high speed. Below the velocity profiles are two digital signals: 'Zero point' and 'Reference cam'. The 'Zero point' signal is a single pulse that occurs when the velocity profiles reach zero. The 'Reference cam' signal is a square wave that is high during the deceleration phase and low during the acceleration phase.

11 = <- right reference cam polarity, zero pulse at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 11 = <- right reference cam polarity, zero pulse at RefNock=Low

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram illustrates the motion profile for mode 11. It shows a horizontal axis with a carriage and a reference cam. The velocity profiles for the 'lièvre' (V1) and 'tortue' (V2) phases are shown as curves. The digital signals include a 'Zero pulse' which is active (low) when the reference cam is in its high state, and a 'Reference cam' signal which is high during the reference position. A 'Negative limit switch' signal is also shown, which is active (low) when the carriage reaches the negative limit.

12 = <- right reference cam polarity, zero pulse at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 12 = <- right reference cam polarity, zero pulse at RefNock=High

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram illustrates the motion profile for mode 12. It shows a horizontal axis with a carriage and a reference cam. The velocity profiles for the 'lièvre' (V1) and 'tortue' (V2) phases are shown as curves. The digital signals include a 'Zero point' which is active (low) when the reference cam is in its low state, and a 'Reference cam' signal which is high during the reference position. A 'Negative limit switch' signal is also shown, which is active (low) when the carriage reaches the negative limit.

13 = <- left reference cam polarity, zero pulse at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 13 = <- left reference cam polarity, zero pulse at RefNock=High

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram illustrates the motion profile for mode 13. It shows a horizontal axis with a carriage moving from left to right. Three velocity profiles are shown: v1 (top), v2 (middle), and v3 (bottom). Each profile starts with a ramp-up phase at acceleration 1000 Grad/s², followed by a constant velocity phase, and ends with a ramp-down phase at deceleration 1000 Grad/s². The v1 profile has a higher velocity than v2 and v3. The v2 profile has a higher velocity than v3. The v3 profile has a higher velocity than the zero pulse. The zero pulse is a single high pulse. The reference cam is a square wave that is high during the acceleration and deceleration phases and low during the constant velocity phase.

14 = <- left reference cam polarity, zero pulse at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 14 = <- left reference cam polarity, zero pulse at RefNock=Low

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

The diagram illustrates the motion profile for mode 14. It shows a horizontal axis with a carriage moving from right to left. Three velocity profiles are shown: v1 (top), v2 (middle), and v3 (bottom). Each profile starts with a ramp-up phase at acceleration 1000 Grad/s², followed by a constant velocity phase, and ends with a ramp-down phase at deceleration 1000 Grad/s². The v1 profile has a higher velocity than v2 and v3. The v2 profile has a higher velocity than v3. The v3 profile has a higher velocity than the zero pulse. The zero pulse is a single low pulse. The reference cam is a square wave that is high during the acceleration and deceleration phases and low during the constant velocity phase.

17 = Neg, end switch

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 17 = Neg. end switch

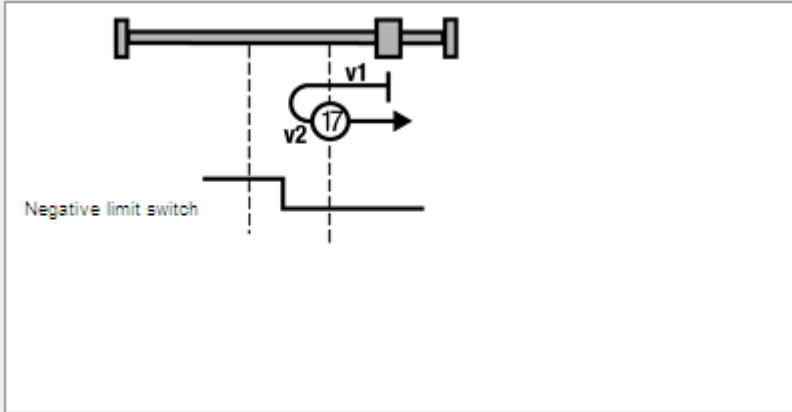
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



18 = Pos, end switch

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 18 = Pos. end switch

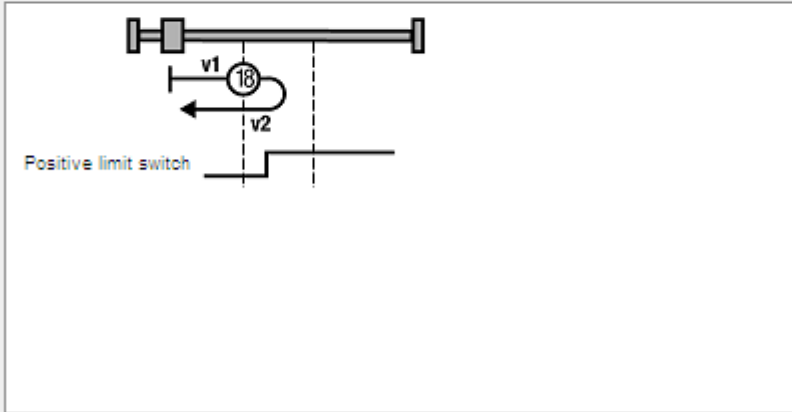
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



19 = Pos, reference cams, Stop at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 19 = Pos. reference cams, Stop at RefNock=Low

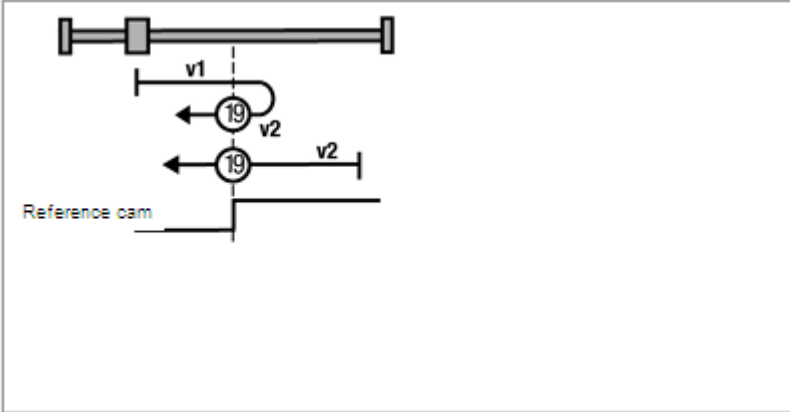
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



20 = Pos, reference cams, Stop at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 20 = Pos. reference cams, Stop at RefNock=High

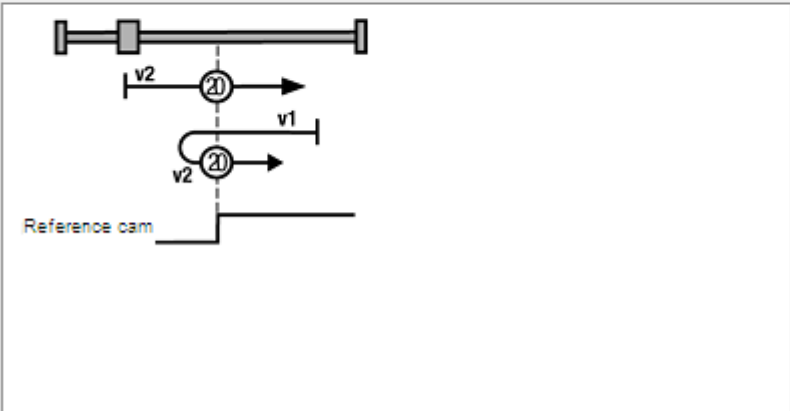
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



21 = Neg, reference cams, Stop at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 21 = Neg. reference cams, Stop at RefNock=Low

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

Reference cam

22 = Neg, reference cams, Stop at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 22 = Neg. reference cams, Stop at RefNock=High

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

Reference cam

23 = -> left reference cam polarity, Stop at RefNock=Low

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 23 = -> left reference cam polarity, Stop at RefNock=Low

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

Reference cam
Positive limit switch

24 = -> left reference cam polarity, Stop at RefNock=High

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: 24 = -> left reference cam polarity, Stop at RefNock=High

vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)

Reference cam
Positive limit switch

25 = -> right reference cam polarity, Stop at RefNock=High

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 25 = -> right reference cam polarity, Stop at RefNock=High

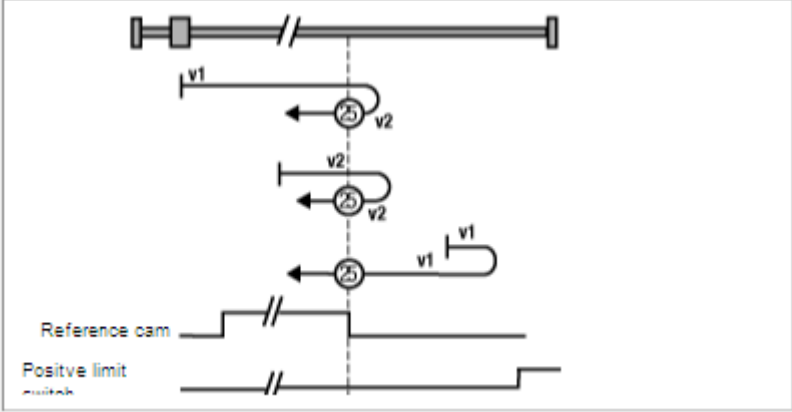
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



26 = -> right reference cam polarity, Stop at RefNock=Low

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 26 = -> right reference cam polarity, Stop at RefNock=Low

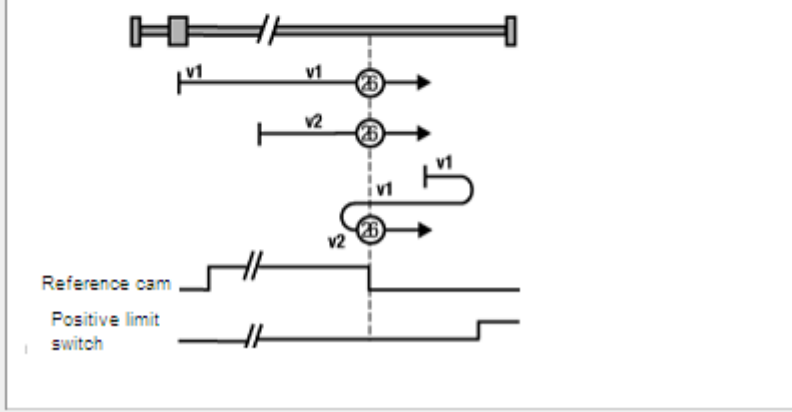
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



27 = <- right reference cam polarity, Stop at RefNock=Low

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 27 = <- right reference cam polarity, Stop at RefNock=Low

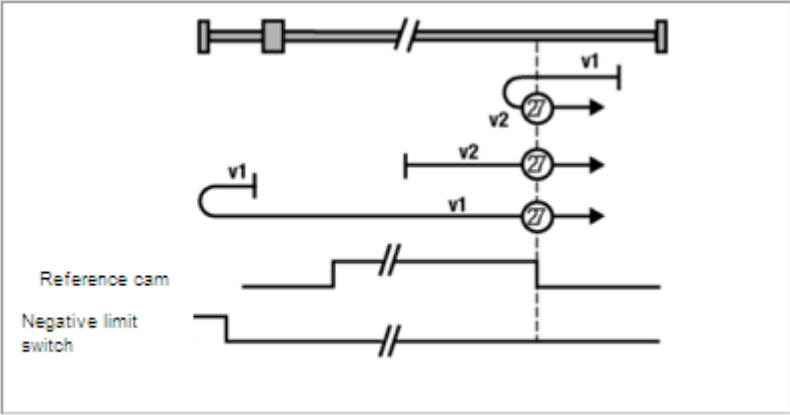
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



28 = <- right reference cam polarity, Stop at RefNock=High

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 28 = <- right reference cam polarity, Stop at RefNock=High

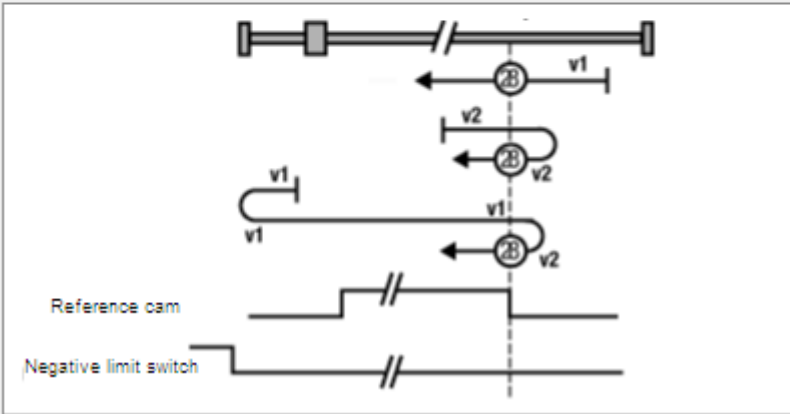
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



29 = <- left reference cam polarity, Stop at RefNock=High

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 29 = <- left reference cam polarity, Stop at RefNock=High

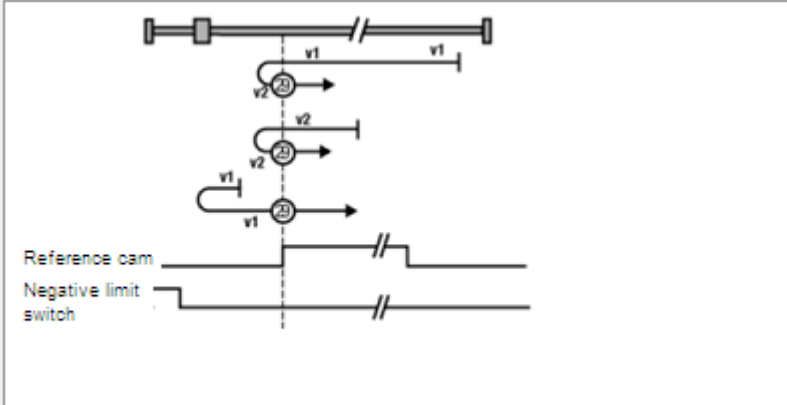
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



30 = <- left reference cam polarity, Stop at RefNock=Low

Déplacement | Prise d'origine | Fin de course | manuel

Type de prise d'origine: 30 = <- left reference cam polarity, Stop at RefNock=Low

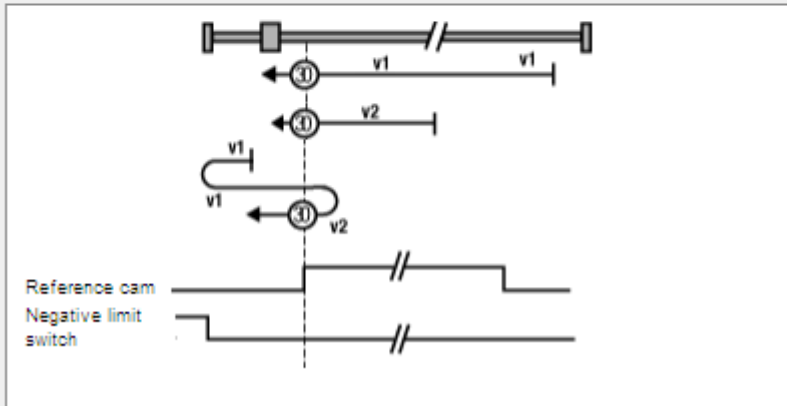
vitesse lièvre V1: 1000 Grad/s

vitesse tortue V2: 500 Grad/s

accélération: 1000 Grad/s²

offset sur point zéro: 0 Grad

conditions de démarrage: OFF (0) = On request (Dig. Input, Bus, PLC)



33 = Next left zero pulse

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: **33 = Next left zero pulse**

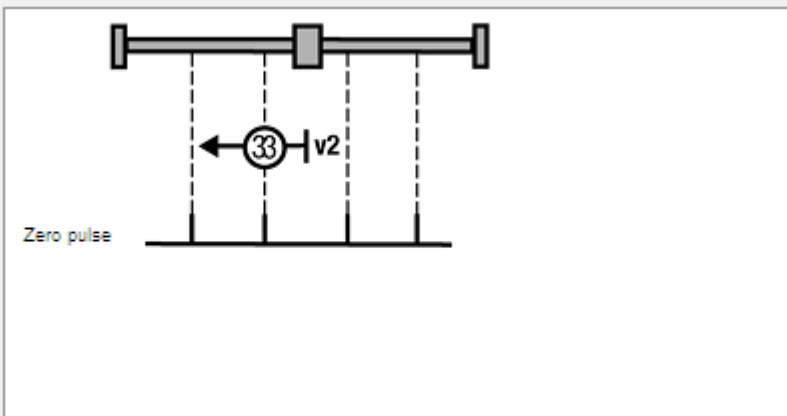
vitesse lièvre V1: Grad/s

vitesse tortue V2: Grad/s

accélération: Grad/s²

offset sur point zéro: Grad

conditions de démarrage: **OFF (0) = On request (Dig. Input, PLC)**



Zero pulse

34 = Next right zero pulse

Déplacement | **Prise d'origine** | Fin de course | manuel

Type de prise d'origine: **34 = Next right zero pulse**

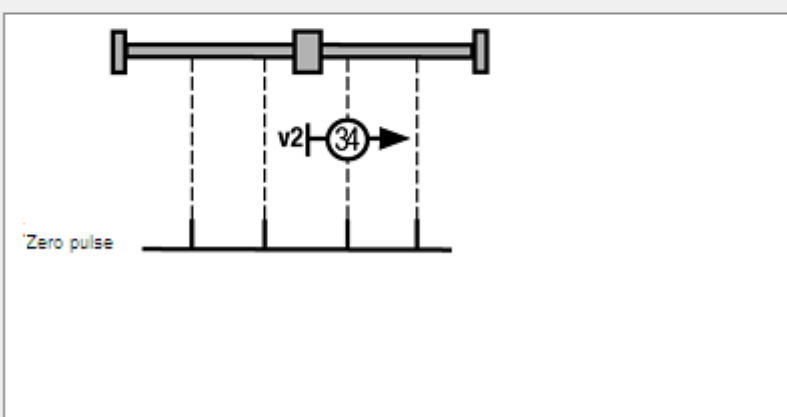
vitesse lièvre V1: Grad/s

vitesse tortue V2: Grad/s

accélération: Grad/s²

offset sur point zéro: Grad

conditions de démarrage: **OFF (0) = On request (Dig. Input, Bus, PLC)**



Zero pulse

35 = Actual position = Reference position

Déplacement	Prise d'origine	Fin de course	manuel
Type de prise d'origine	35 = Actual position = Reference position		
vitesse lièvre V1	1000	Grad/s	
vitesse tortue V2	500	Grad/s	
accélération	1000	Grad/s ²	
offset sur point zéro	0	Grad	
conditions de démarrage	OFF (0) = On request (Dig. Input, Bus, PLC)		
<div style="border: 1px solid black; height: 150px; width: 100%;"></div>			