Firs



sic control elements		 Connect the display Connect CAN and PWR connector leading from the display to a mating device 	3. Basic eva *Speed and p appropriate
tus LED nt reference ction command	Previous screen Default screen (long pres) In-screen navigation Next screen ON/OFF (long press) Emergency Stop Voltage reference	- Turn on the display by long pressing the ON/OFF	Voltage sta Current sta Actual c Command Change co [*Speed regulat Change co [*Position regula
ModeAnalogyDes0 -Freewheel (FRW)Image for the second of the second	Basic control modes cription Actor is kept in freewheeling state -Phase voltage(active Q efined by command(U = d ofthemotor is regulated. e)is determined by the load. I imited (not controlled) by can accelerate and brake -Phase current (active Q efined by the commnad(I = e of the motor is regulated. ed by the load and could be ot controlled). Motorcan rate and brake. h freewheeling-Very similar difference is that motor can't then the polarity of voltage is reverted) ecial case of voltage control ewheels from zero RPMuntil RPM(Back EMFishiger than	5. Graphical overview Information from controllers on the CAN bus No. of controllers on bus, Type of commutaion method Address of displayed device Controller limiters and events Battery information Graphical representation of the energy flow Total enrgy since start-up	6. Miscellane - Device addre - Parametric v - target_add
(VLB) + U U + starts to flow into the brake. Braking torockeep motor flow into the brake. Braking torockeep motor flow is the brake. Braking torockeep motor flow is the phase current control is for t	cmd). After that, currents e batteryand motor starts to ue has the exact amount to PM at treshold RPM. rol–Special case of current only one difference is that nsint from both componnets Q and D. Generated motor torque is mand (M = cmd*Mmax/The value is computed from ers/). Torque of the motor is determined by the load and d (not controlled). Motorcan rate and brake. ilar to mode 2, but current rection to generate brake is mode never accelerates. imilar to mode 6, it only orque. Motor in this mode		
A-Brake mode with Image: Current brake with freewheeling (BRF) Image: Current brake with F -Short circuit mode Image: Current brake with (Current brake with Image: Current brake with Brake torque is prop	r accelerates. freewheeling-Unidirectional ction is same as mode 8, for on motorfreewheels. e-Speed-dependentbrake. ortional to motor speed. The he higherbrake torque.		



valuation screen

d position loops need fine-tuning of te controller's PID parameters

- status bar (Umult) •
- status bar (Imult)
- l cotrol mode
- and status bar
- e control mode Jation-long press]
- control mode gulation-long press]

neous

- lress is 6
- variable:
- addr address of controlled controller - 255 (default value) for broadcast

