N6-1-2... , N6-2-2...

Short instructions
Translation of the

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Introduction

The *N6* is a controller for the *open-loop* or *closed loop* operation of stepper motors and the *closed loop* operation of BLDC motors.

This manual describes the functions of the controller and the available operating modes. It also shows how you can address and program the controller via the communication interface.

You can find further information on the product on **us.nanotec.com**.

Copyright

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Intended use

The *N6* serves to control stepper motors and BLDC motors and is used as a component in drive systems in a wide range of industrial applications.

Use the product as intended within the limits defined in the technical data (in particular, see **Permissible operating voltage**) and the approved **Environmental conditions**. This Nanotec product may under no circumstances be integrated as a safety component in a product or system.

All products containing a component manufactured by Nanotec must, upon delivery to the end user, be provided with corresponding warning notices including instructions for safe use and safe operation. All warning notices provided by Nanotec must be passed on directly to the end user.

Target group and qualification

The product and this documentation are directed towards technically trained specialists staff such as: development engineers, plant engineers, installers/ service personnel, and application engineers.

Only specialists may install, program and commission the product. Specialist staff are persons who

- have appropriate training and experience in working with motors and their controller,
- are familiar with and understand the content of this technical manual,
- know the applicable regulations.

Warranty and disclaimer

Nanotec shall not be liable for damage and malfunctions attributable to installation errors, failure to observe this document or improper repair. The plant engineer, operating company and user shall be responsible for the selection, operation and use of our products. Nanotec shall not take responsibility for integration of the product in the end system. The general terms and conditions listed at www.nanotec.de shall apply. **Note:** Conversion/modification as well as opening of the product are prohibited.

Other applicable regulations

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

- Accident-prevention regulations
- Local regulations on occupational safety

EU directives for product safety

The following EU directives were observed:

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

Safety and warning notices

NOTICE

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.

NOTICE

Damage to 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.

NOTICE

Damage to the electronics through improper handling of ESD-sensitive components!

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

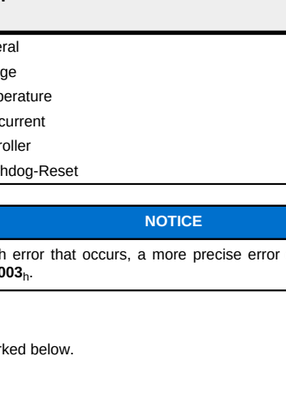
Environmental conditions

Environmental condition	Value
Protection class	IP20
Degree of contamination	2
Ambient temperature (operation)	-10 … +40°C
Ambient temperature (storage and transport)	-25 … +85°C
Relative humidity (operation), non-condensing	0 … 85%
Relative humidity (storage and transport), non-condensing	0 … %
Absolute humidity (storage and transport), non-condensing	30 g/m^3
Max. altitude of site above *sea level*	2000 m (drop in performance above 1000 m: -1%/100 m)
Max. altitude of site above *sea level* (storage and transport)	3000 m

Electrical properties and technical data

Property	Description / value
Operating voltage	12 V -5%…57.6 V DC
Rated current	6 A_{rms}
Peak current	N6-1-… (*low current*): 6 A_{rms} N6-2-… (*high current*): 18 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*, *Homing Mode*, *Interpolated Position Mode*, *Cyclic Sync Position Mode*, *Cyclic Sync Velocity Mode*, *Cyclic Synchronous Torque Mode*, *Clock-Direction Mode*
Set value setting / programming	*CANopen*, *Clock-direction*, *analog*, *NanoJ program*
Interfaces	CANopen, USB
Inputs	• 6 inputs, 5 V/24 V (=UB_Logic), switchable by means of software, factory setting: 5 V • 2 analog inputs 0 to +24 V, 12-bit resolution
Outputs	3 outputs, 5 V/24 V (=UB_Logic), switchable by means of software, 100 mA
Brake connection	1 PWM output, max. 1.5 A, 20 kHz
Sensor inputs	1 incremental encoder (5 V), 3 Hall sensors (5 V), 1 SSI encoder (10 V)
Property	Description / value
Protection circuit	Overvoltage and undervoltage protection Overtemperature protection (> 75° Celsius on the power board) Polarity reversal protection

Dimensioned drawings and installation options



You can secure the controller by its side tabs to a flat mounting surface using screws or mount it on a TH35 DIN rail in your switch cabinet using the supplied DIN rail clip.

Overtemperature protection

Above a temperature of approx. 75°C on the power board the power part of the controller switches off and the fault bit is set. After cooling down and resetting the fault , the controller again functions normally.

LED signaling

Power LED

The power LED indicates the current status.

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.

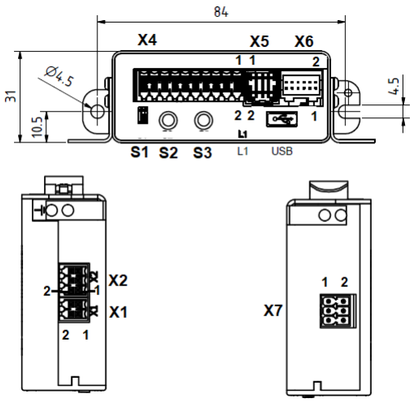
Flash rate	Error
1	General
2	Voltage
3	Temperature
4	Overcurrent
5	Controller
6	Watchdog-Reset

NOTICE

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

Pin assignment

Pin 1 and 2 are marked below.



Connector	Function	Pin assignment / description
X1 min. : 1 mm^2 (AWG 17)	Motor **Note:** Motor wires are to be routed through ferrites (74271222 from Würth or equivalent).	1. **A** (Stepper) **U** (BLDC) 2. **A** (Stepper) **V** (BLDC) 3. **B** (Stepper) **W** (BLDC) 4. **B** (Stepper)
X2 UB: 1 mm^2 (AWG 17) UB_Logic; 0.8 mm^2 (AWG 18)	Supply	1. **GND_L-**, GND for the Logic Supply UB_Logic 2. **+UB_Logic**;12 V - 30 V DC 3. **Ballast-** 4. **Ballast+** 5. **GND_P**, GND for the Main Supply UB 6. **+UB**;12 V - 57,6 V DC
X4	In- / Outputs	1. **+10 V**; Output voltage, max. 350 mA 2. **GNDD**; GND for digital In/Outs 3. **+5 V**; Output voltage, max. 350 mA 4. **GNDD**; GND for digital In/Outs 5. **Digital output 1**:5 / 24 V (UB_Logic) switchable, 100 mA 6. **Digital output 2**: :5 / 24 V (UB_Logic) switchable, 100 mA 7. **Digital output 3**: :5 / 24 V (UB_Logic) switchable, 100 mA 8. **GNDD**; GND for digital In/Outs 9. **Digital input 1**; 5 V / 24 V, switchable 10. **Digital input 2**; 5 V / 24 V, switchable 11. **Digital input 3**; 5 V / 24 V, switchable 12. **Digital input 4**; 5 V / 24 V, switchable 13. **Digital input 5**; 5 V / 24 V, switchable 14. **Digital input 6**; 5 V / 24 V, switchable 15. **GNDA**; GND for Analog input 16. **Analog input 1**: 0 V…+24 V, 12-Bit-resolution 17. **GNDA**; GND for Analog input 18. **Analog input 2**: 0 V…+24 V, 12-Bit-resolution 19. **Brake-**: GND for brake 20. **Brake+**: PWM-controlled output, 5 V / 24 V switchable, up to 20 KHz, max. 1500 mA
X5	SSI Encoder	1. **GND** 2. **SHIELD** 3. **n.c.** 4. **DATA B** 5. **DATA A** 6. **CLCK B**; up to 10 MHz 7. **CLCK A**; up to 10 MHz 8. **Vcc**; +10 V DC, outputs- und Supply voltage for SSI Encoder, max. 350 mA

Connector	Function	Pin assignment / description
X6	Incrmental encoder and Hall sensor Max. 1 MHz	**1. GND** **2. Vcc**: +5 V DC, output,Supply voltage for Encoder / Hall Sensor; max. 350 mA **3. A** **4. B** **5. A** **6. B** **7. I** **8. I** **9. Hall 1** **10. Hall 2** **11. Hall 3** **12. Shielding** Connector for the shileding
X7	CANopen IN / OUT	**1. GND** **2. GND** **3. CAN_L** **4. CAN_L** **5. CAN_H** **6. CAN_H**
S1	DIP switch for 120 Ω termination for CAN-Bus.	**OFF (down)**: The CAN bus termination is off. **ON (up)**: The CAN bus termination is on.
S2 and S3	Two Hex coding switches for setting the *Node-ID* and baud rate: • *S2*: 16^1 • *S3*: 16^0 	**Value of the switches** / **Node-ID** / **Baud rate** 0_h / Object **2009**$_h$ / 1MBd $1\text{-}7F_h$ / Value of the switches / 1MBd 80_h / Object **2009**$_h$ / Object **2005**$_h$ $81_h\text{-}FF_h$ / (Value of the switches)-128 / Object **2005**$_h$

NOTICE

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 (810911010 from Würth or equivalent) is to be inserted in the DC supply line(s) as close as possible to the controller/motor.

► Long data or supply lines are to be routed through ferrites.

► Motor wires are to be routed through ferrites (74271222 from Würth or equivalent).

Commissioning

The *Plug & Drive Studio 3* 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: User Manual* at **us.nanotec.com**.

CAUTION

STO

The loss of the safety function due to incorrect wiring may lead to injuries!

Incorrect wiring or the use of unsuitable external components may lead to the loss of the safety function. This could result in injuries.

► Only use components that correspond to the safety category of the application.

► Check the electrical installation (wiring, pin assignment) and validate the STO function prior to the initial commissioning and after every intervention in the wiring and each time components/ equipment are replaced.

► Do not bypass the STO function. If the wiring for the initial commissioning does not correspond to the required safety category of the application, remove it immediately after the initial commissioning.

CAUTION

STO

The loss of the safety function due to electromagnetic interference may lead to injuries!

External interference may affect and result in the loss of the safety function.

► Observe the maximum permissible cable length of 30 m for all STO signals. Longer cables reduce the interference immunity (EMC) and require additional interference-suppression and protection measures.

► Use shielded cables for the STO signals.

► Lay supply, signal and control cables physically separate from one another.

Configuration via USB

General

The following options are available for configuring the controller via USB:

Configuration file

This file can be saved to the controller via the USB connection. For further information, read chapters **USB connection** and **Configuration file**.

NanoJ program

This program can be programmed, compiled and then transferred to the controller with *NanoJ* via USB. *NanoJ* is integrated in the *Plug & Drive Studio 3* software. You can find further information in document *Plug & Drive Studio 3: User manual* at **us.nanotec.com**.

After connecting to a voltage supply, the controller reads out the configuration in the following order:

1. The configuration file is read out and processed.
2. The NanoJ program is started.

USB connection

NOTICE

Damage of the product and/or external hardware due to potential differences on the USB.

Connecting the USB cable while the electronic is powered on (Hot-Plugging) possibly causes damage.

► Connect the USB bevor you switch on the voltage supply.

► If possible, balance any potential differences between PC and the product or use a USB isolator.

► Connect the USB cable first to the product and then to the PC.

If the controller is connected to a PC via a USB cable, an MTP device is created in the Windows file explorer, which contains a data storage device.

Three files are displayed: the configuration file (`cfg*.txt`), the *NanoJ program* (`nanoj*.usr`) and the firmware file (`*.fw`).

You can thereby store the configuration file or the *NanoJ program* on the controller. The voltage supply of the controller must also be connected during USB operation.

Configuration file

General

The `cfg.txt` configuration file is used to preset values for the object dictionary to a certain value during startup. This file uses a special syntax to make accessing the objects of the object dictionary as easy as possible. The controller evaluates all assignments in the file from top to bottom.

Reading and writing the file

How to access the file:

1. Connect and switch on the voltage supply.
2. Connect the controller to your PC using the USB cable.
3. After the PC has detected the device as a removable storage device, navigate in the Explorer to the directory of the controller. File `cfg.txt` is stored there.
4. Open this file with a simple text editor, such as Notepad or Vi. Do not use any programs that use markup (LibreOffice or similar).

After you have made changes to the file, proceed as follows to apply the changes through a restart:

1. Save the file if you have not yet already done so. The motor stops.
2. Disconnect the USB cable from the controller.
3. Disconnect the voltage supply from the controller for approx. 1 second until the power LEDs stop flashing.
4. Reconnect the voltage supply. When the controller is now restarted, the values in the configuration file are read out and applied.

Establishing communication via CANopen

1. Connect the CANopen master to the controller via the CAN_L, CAN_H cables. Check the connection of your CAN-GND and that the necessary termination resistor **termination resistor** is present between CAN_H and CAN_L.
2. Supply the controller with voltage (+UB Logic).
3. Change the configuration values if necessary.
4. To test the interface, send bytes `40 41 60 00 00 00 00 00` to the controller.
   Statusword (6041_h) was read; you receive this response: `4B 41 60 00 XX XX 00 00`.

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.
- Object **6075**$_h$:00_h: rated current of the motor in mA (see motor data sheet)
- Object **6073**$_h$:00_h: maximum current (for a stepper motor, generally corresponds to the rated current, bipolar) in tenths of a percent of the set rated current (see motor data sheet). Factory settings: "1000", which corresponds to 100% of the value in **6075**$_h$.
- Object **3219**$_h$:01_h Maximum duration of the maximum current (**6073**$_h$) in ms (for initial commissioning, Nanotec recommends a value of 100 ms; this value is to be adapted later to the specific application).
- Setting the motor type:
  - Stepper motor:
    - Object **3202**$_h$ (Motor Drive Submode Select): Set bit 6 to "0" for stepper and choose via Bit 0 bewtween open and closed loop: value 0_h or 1_h.
    - Object **3219**$_h$:03_h (Open loop idle state current): value in tenths of percent, to which the rated current is to be reduced if current reduction is activated in *open-loop*.
  - BLDC motor:
    - Object **3202**$_h$ (Motor Drive Submode Select): Bit 6 for BLDC, bit 0 for recommended *closed-loop*: 00000041_h
- Motor with encoder without index: You must set the encoder parameters after the **Auto setup**, see chapter **Configuring the sensors** in the technical manual.
- 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 activated: 00000004_h
  - BLDC motor, brake control activated, *closed-loop*: 00000045_h

NOTICE

Due to the sine commutation and the sinusoidal current flow, the current of a motor winding can achieve an alternating current value that is briefly greater (by max. √2 times) than the set current.

At especially slow speeds or while at a standstill with full load, one of the windings can therefore be supplied with overcurrent for a longer period of time. Take this into account when dimensioning the motor and select a motor with larger torque reserve if necessary if required by the application.

Auto setup

To determine a number of parameters related to the motor and the connected sensors (encoders/Hall sensors), you must perform an auto setup.

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.

NOTICE

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.

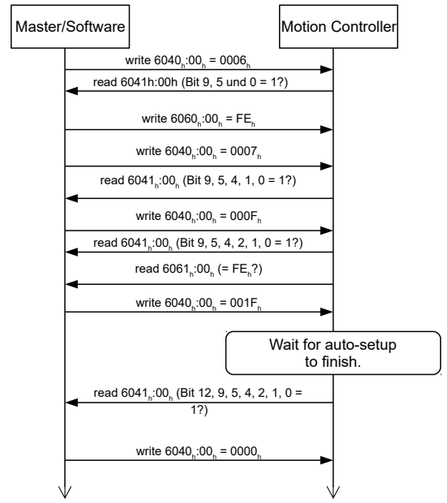
► No NanoJ programs may be running (object 2300_h:00_h bit 0 = "0").

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).

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!

Uncontrolled motor movements!

After the auto setup, the internal coordinate system is no longer valid. Unforeseen reactions can result.

► Restart the device after an auto setup. Homing alone does not suffice.