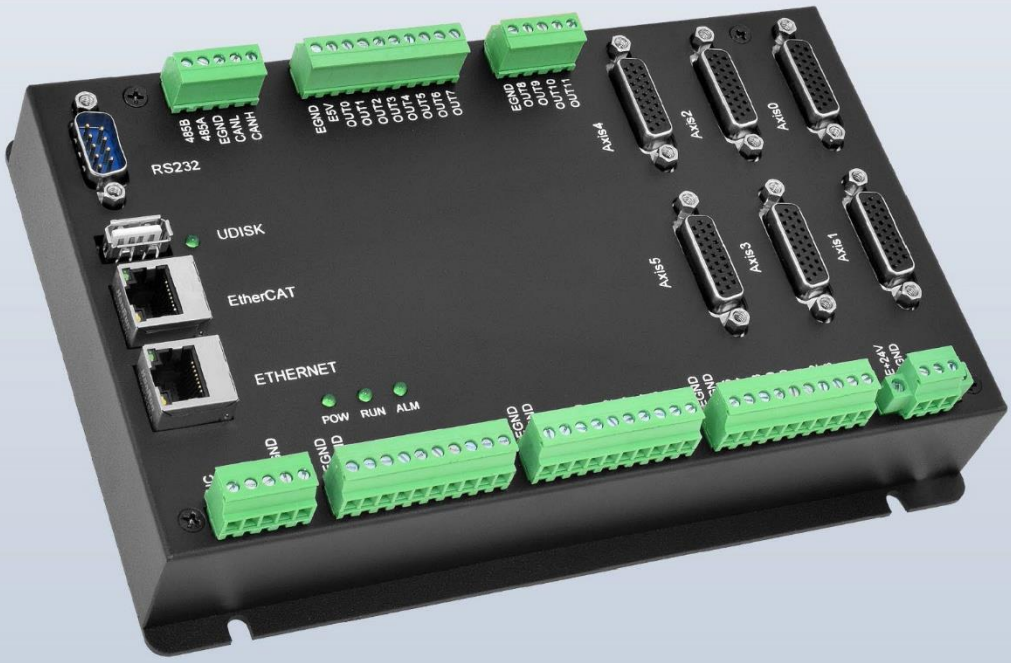
Zmotion®
正运动技术

做更好用的运动控制，智造美好生活
Better Motion Control, Smarter Life

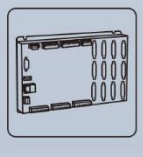
Pulse & EtherCAT Motion Conrtroller

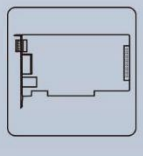
ZMC406-V2

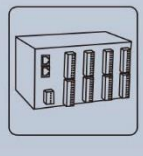


This manual is mainly for ZMC06-V2, ZMC406R-V2.


Vision Motion Controller


Motion Controller


Motion Control Card


IO Expansion Module


HMI

Statement

Thank you for choosing our Zmotion products. Please be sure to read this manual carefully before use so that you can use this product correctly and safely. Zmotion is not responsible for any direct or indirect losses caused by the use of this product.

The information in this manual is for reference only. Due to design improvements and other reasons, Zmotion reserves the right of final interpretation of this information! Contents are subject to change without prior notice!

➢ Notes

In order to prevent possible harm and damage caused by incorrect use of this product, the following instructions are given on matters that must be observed.

■ Danger

Do not use it in places with water, corrosive or flammable gases, or near flammable substances.	May cause electric shock, fire, damage, etc.
When installing or disassembling, make sure the product is powered off.	
Cables should be connected securely, and exposed parts that are energized must be insulated by insulators.	
Wiring work must be performed by professionals.	

■ Notes

It should be installed within the specified environmental range.	May cause damage, mis-operation, etc.
Make sure there are no foreign objects on the product hardware circuit board.	
After installation, the product and the mounting bracket should be tight and firm.	
After installation, at least 2-3cm should be left between the product and surrounding components for ventilation and replacement.	
Never disassemble, modify, or repair it by yourself.	

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Chapter I Production Information

1.1. Product Information

ZMC is the abbreviation of the motion controller model launched by Zmotion Technology.

ZMC4 series support Zmotion XPLC function, and they can be configured and displayed through the network.

ZMC406-V2 high-performance multi-axis motion controller is a stand-alone motion controller that is compatible with EtherCAT bus and pulse type. The controller itself supports complex continuous trajectory control requirements of up to 6 axes.

ZMC4 series high-performance multi-axis motion controller can be applied in robots (SCARA, Delta, 6 joints), electronic semiconductor equipment (testing equipment, assembly equipment, locking equipment, soldering machine), dispensing equipment, non-standard equipment, printing and packaging equipment, textile and garment equipment, stage entertainment equipment, medical equipment, assembly line, etc.

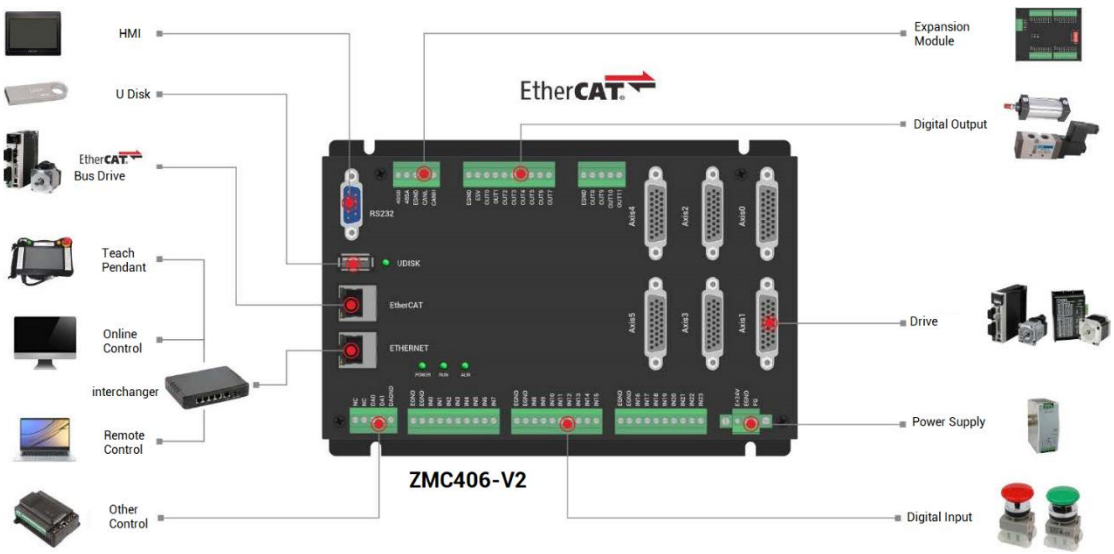
1.2. Function Features

- Motion control of up to 6 axes.
- Pulse output mode: pulse / direction or dual pulses or quadrature pulse.
- Maximum pulse frequency output of each axis: 10MHz.
- IO can be expanded through ZCAN and EtherCAT, and 4096 isolated inputs and 4096 isolated outputs can be extended at most.
- Axis position limit signal / origin signal port can be configured as any input at will.
- The maximum output current of general digital outputs can reach 300mA, which can

directly drive some kinds of solenoid valves.

- Interfaces: EtherCAT, RS232, RS485, U Disk, Ethernet.
- Support linear interpolation, any circular interpolation, helical interpolation, and spline interpolation of 6 axes at most.
- Support electronic cam, electronic gear, position latch, synchronous follow, virtual axis, etc.
- Support hardware comparison output (HW_PSWITCH2), hardware timer, precision output in motion.
- Support pulse closed loop, pitch compensation and other functions.
- Multi-file and multi-task programming in ZBasic.
- A variety of program encryption methods to protect the intellectual property rights of customers.
- Support power failure detection and power failure storage. (It can detect and save when power-off)

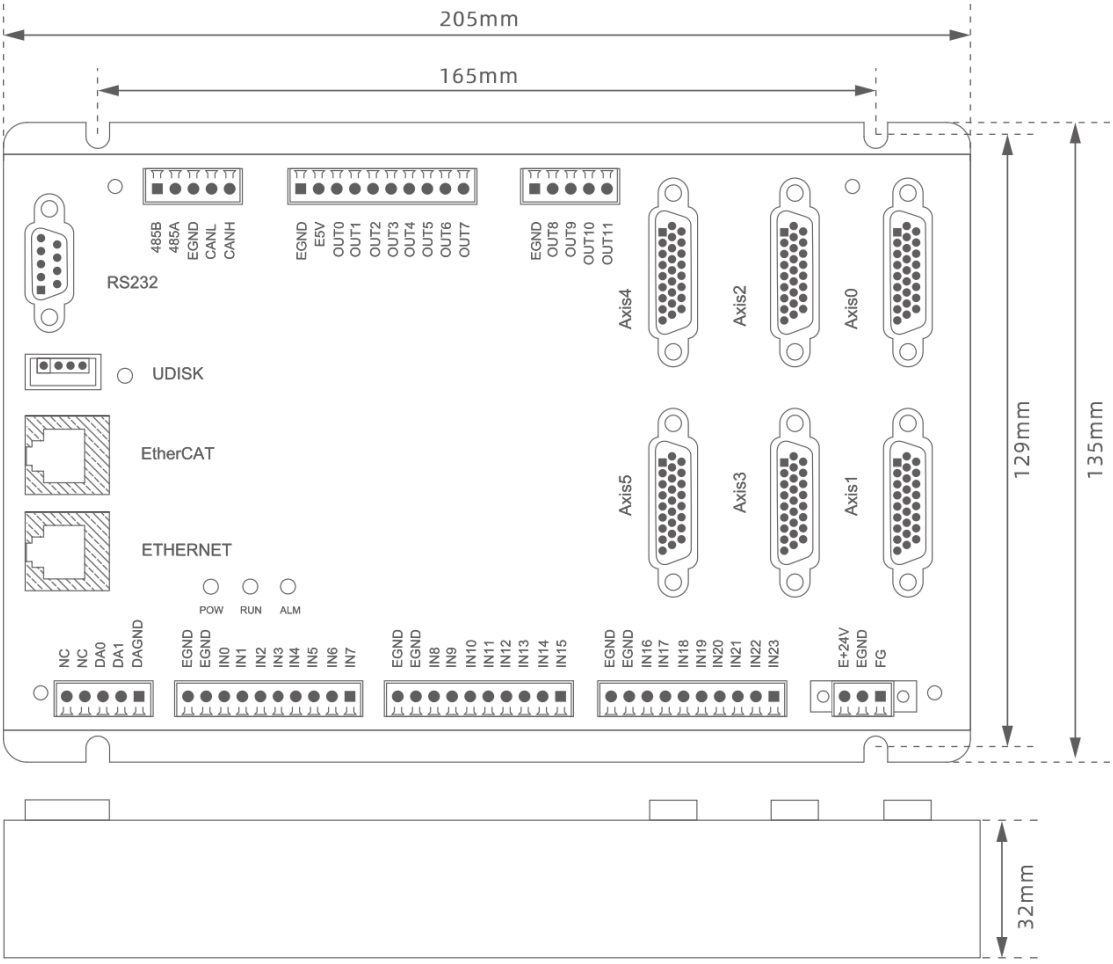
1.3. System Frame



1.4. Hardware Installment

The ZMC406-V2 motion controller adopts the horizontal installation method of screw fixing, and each controller should be installed with 4 screws for fastening.

→ Unit: mm → Installment Hole Diameter: 4.5mm



Installation attention	• Non-professionals are strictly prohibited to operate. Specifically, professionals who had been trained related electrical equipment, or who master electrical knowledge. • Please be sure to read the product instruction manual and safety precautions carefully before installation. • Before installation, please ensure that the product is powered off. • Do not disassemble the module, otherwise the machine may be damaged.

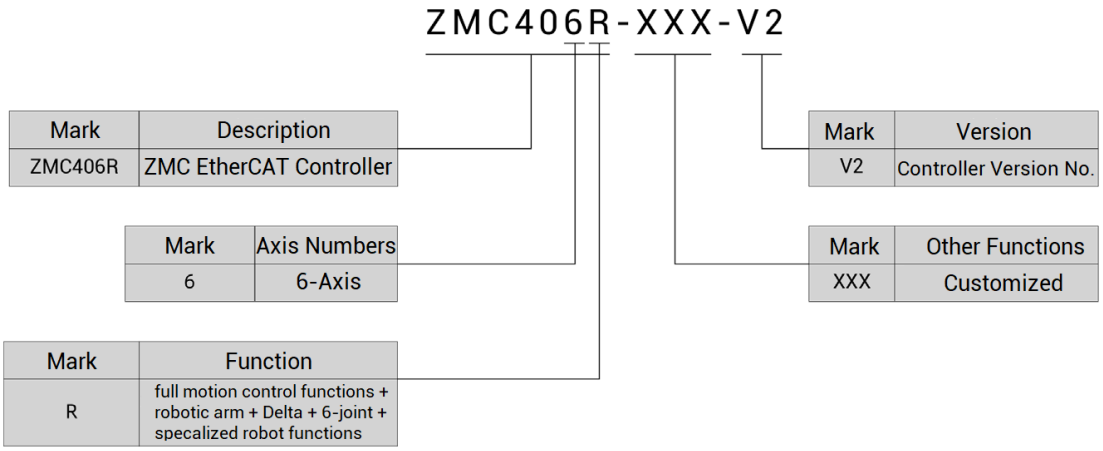
	● In order to facilitate ventilation and controller replacement, 2-3cm should be left between the upper and lower parts of the controller and the installation environment and surrounding components. ● Considering the convenient operation and maintenance of the controller, please do not install the controller in the following places: a) places where the surrounding ambient temperature exceeds the range of -10°C-55°C b) places where the ambient humidity exceeds the range of 10%-95% (non-condensing) c) places with corrosive gases and flammable gases d) places with many conductive powders such as dust and iron powder, oil mist, salt, and organic solvents e) there is direct sunlight

Chapter II Product Specification

2.1. Basic Specification

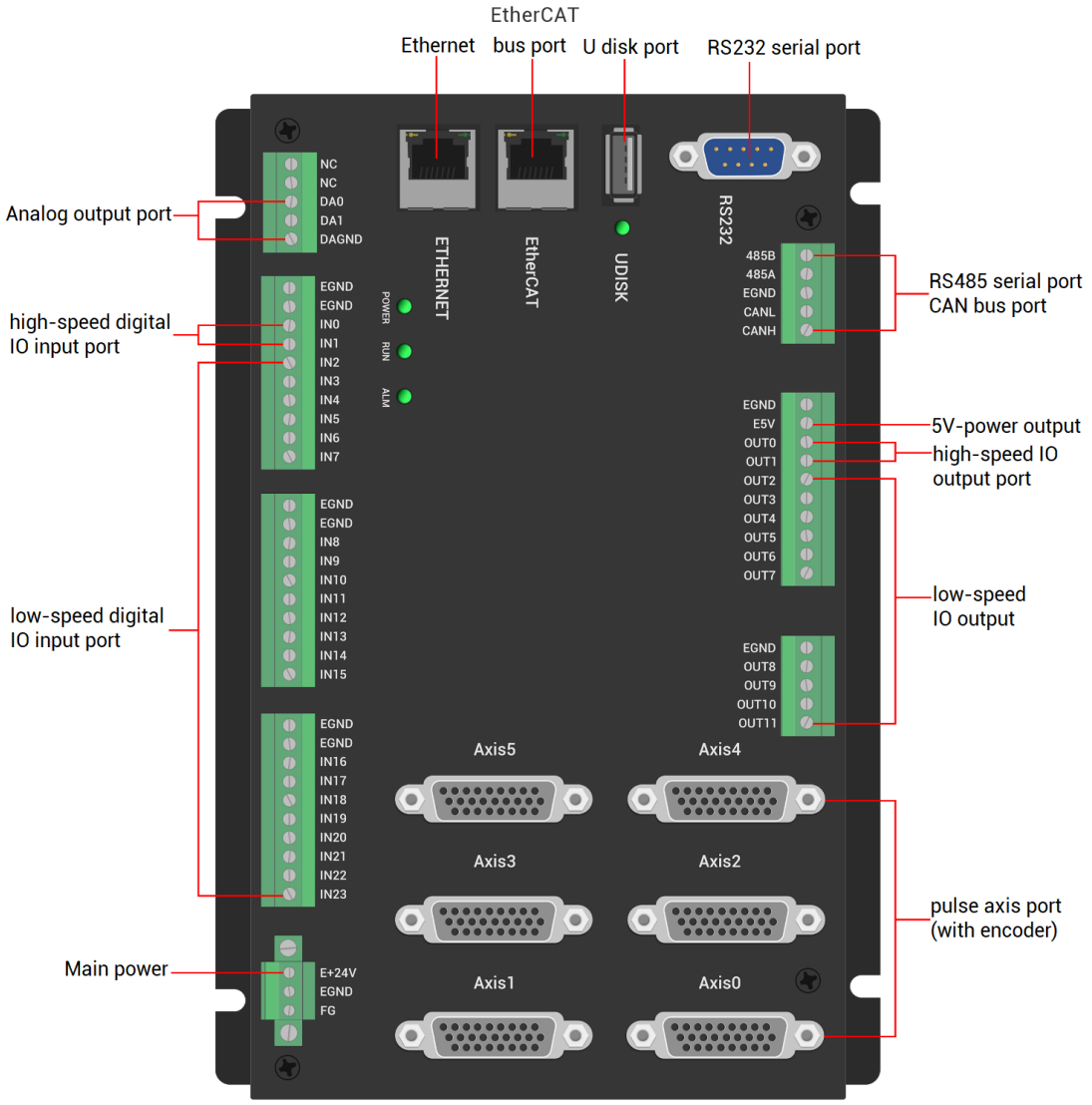
Item	Description	
Model	ZMC406-V2	ZMC406R-V2
Basic Axes	6	6
Max Extended Axes	32	32
Basic Axes Type	EtherCAT, 6 local pulse axes	
General Digital IO	24 inputs, 12 outputs	
IO in “Axis” Interface	1 input, 1 output	
Max Extended IO	4096 inputs, 4096 outputs	
PWM	4	
AD/DA	2 general DAs, 0-10V	
Max Extended AD/DA	1000 ADs, 1000 DAs	
Pulse Bit	64	
Encoder Bit	64	
Speed & Acceleration Bit	64	
Highest Pulse Frequency	10MHz	
Motion Buffer of Each Axis	4096	
Array Space	320000	
Program Space	32MByte	
Flash Space	256MByte	
Power Supply Input	24V DC input	
Communication Interfaces	RS232, RS485, Ethernet, U disk, CAN, EtherCAT	
Dimensions	205mm*135mm	

2.2. Nameplate & Model



Model	Description
ZMC406-V2	6 axes, point to point, linear, circular, electronic cam, continuous trajectory motion, robotic car instructions.
ZMC406R-V2	Functions of ZMC406-V2 + Delta + 6-joint robotic arm instructions.

2.3. Interface Definition



→ Interface Description

Mark	Interface	Number	Description
POW	Status Indication Light	1	Power indicator: it lights when power is conducted.
RUN		1	Run indicator: it lights when runs normally
ALM		1	Error indicator: it lights when runs abnormally
RS232	RS232 serial port	1	Use MODBUS_RTU protocol

	(port0)		
RS485	RS485 serial port (port1)	1	Use MODBUS_RTU protocol
EtherCAT	EtherCAT bus interface	1	EtherCAT bus interface, connect to EtherCAT bus drive and EtherCAT bus expansion module
ETHERNET	Ethernet	1	Use MODBUS_TCP protocol, expand Ethernet through interchanger, the number of net port channels can be checked through "?*port", default IP address id 192.168.0.11
UDISK	U disk interface	1	Insert U disk equipment
E+24V	Main power	1	24V DC power supplies for controller
CAN	CAN bus interface	1	Connect to CAN expansion module and other standard CAN devices
IN	Digital IO input	24	NPN type, 2 high-speed inputs, and IN0-1 have latch function.
OUT	Digital IO output	12	NPN type, OUT0-3 have PWM and hardware comparison output function
DA	Analog output	2	Resolution: 12 bits, 0-10V
AXIS	Pulse axis	6	It includes differential pulse output and differential encoder input

2.4. Work Environment

Item		Parameters
Work Temperature		-10℃-55℃
Work relative Humidity		10%-95% non-condensing
Storage Temperature		-40℃ ~ 80℃ (not frozen)
Storage Humidity		Below 90%RH (no frost)
vibration	Frequency	5-150Hz
	Displacement	3.5mm(directly install)(<9Hz)

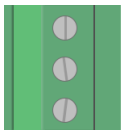
	Acceleration	1g(directly install)(>9Hz)
	Direction	3 axial direction
Shock (collide)		15g, 11ms, half sinusoid, 3 axial direction
Degree of Protection		IP20

Chapter III Wiring & Communication

3.1. Power Input

The power supply input adopts a 3Pin (there are all 3 terminals, E+24V, EGND and FG) screw-type pluggable wiring terminal, and the interval (means the gap distance between two ports, namely, between E+24V and EGND) should be 3.81mm. This 3Pin terminal is the power supply of the controller.

→ Terminal Definition:

Terminal	Name	Type	Function
	E+24V	Input	Positive (+) terminal of DC power input (connect positive of power to positive of controller)
	EGND	Input	Negative (-) terminal of power input
	FG	Connect to ground	Protection

3.1.1. Power Specification

→ Specification

Item	Description
Input Voltage	DC24V(-5%~5%)
Opening Current	≤0.5A
Work Current	≤0.4A
Anti-reverse connection	YES
Overcurrent Protection	YES

3.2. RS485, CAN Communication Interface

The communication interface adopts a 5Pin screw-type pluggable wiring terminal and the gap spacing between 2 terminals should be 3.81mm. For both RS485 communication and CAN communication, they can be used by connecting the corresponding interface.

→ Terminal Definition:

Terminal	Name	Function
	485B	485-
	485A	485+
	EGND	Communication Public End
	CANL	CAN Differential Data -
	CANH	CAN Differential Data +

3.2.1. RS485, CAN Communication Specification & Wiring

The RS485 serial port supports the MODBUS_RTU protocol and custom communication, mainly including 485A, 485B and public end.

The CAN interface of the controller adopts the standard CAN communication protocol, which mainly includes three ports, CANL, CANH and the public end. And it can connect to CAN expansion modules and other standard CAN devices.

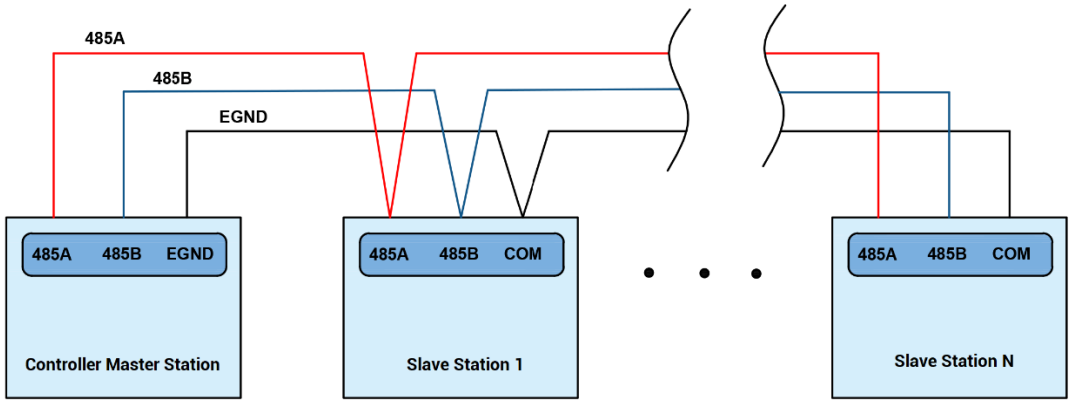
→ Specification

Item	RS485	CAN
Max Communication Rate (bps)	115200	1M
Terminal Resistor	No	120Ω
Topology	Daisy chain connection structure	
Nodes can be extended	Up to 127	Up to 16
Communication Distance	Longer communication distance, lower	

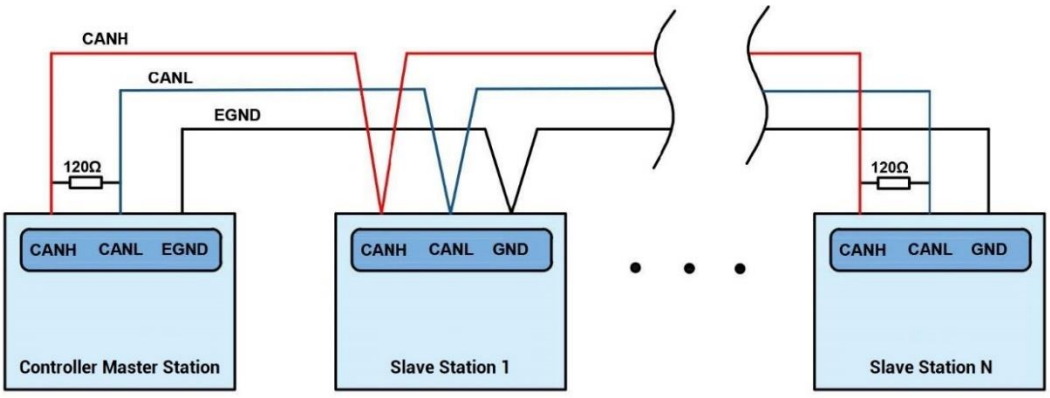
	communication rate, max 30m is recommended.

→ Wiring Reference

Connect 485A and 485B of RS485 to 485A and 485B of the controller correspondingly, and connect the public ends "EGND" of RS485 communication parties together.



Connect the CANL and CANH of the standard CAN module to the CANL and CANH of the other side correspondingly. And public ends of the CAN bus communication both parties are connected together. In CAN bus left and right sides, connect a 120Ω resistor respectively (please see below graphic).



→ Wiring Notes:

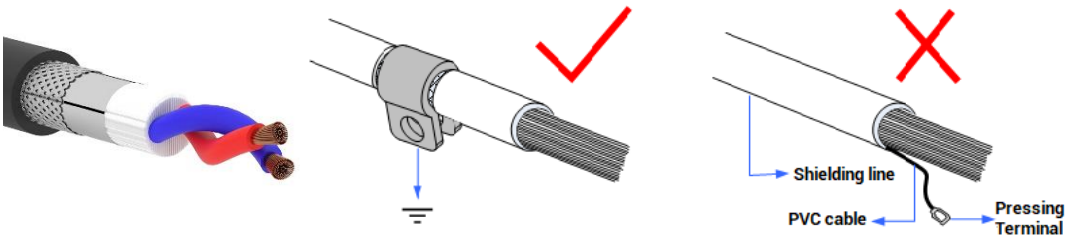
- As above, the daisy chain topology is used for wiring (the star topology structure cannot be used). When the use environment is ideal and there are no many nodes,

the branch structure also can be used.

- Please connect a 120Ω terminal resistor in parallel to each end of the CAN bus for matching the circuit impedance and ensuring communication stability.
- Please be sure to connect the public ends of each node on the CAN bus to prevent the CAN chip from burning out.
- Please use STP (Shielded Twisted Pair), especially in bad environments, and make sure the shielding layer is fully grounded.
- When on-site wiring, pay attention to make the distance between strong current and weak current, it is recommended for the distance to be more than 20cm.
- It should be noted that the equipment grounding (chassis) on the entire line must be good, and the grounding of the chassis should be connected to the standard factory ground pile.

→ Cable Requirements:

Shielded Twisted Pair, and the shielded cable is grounded.



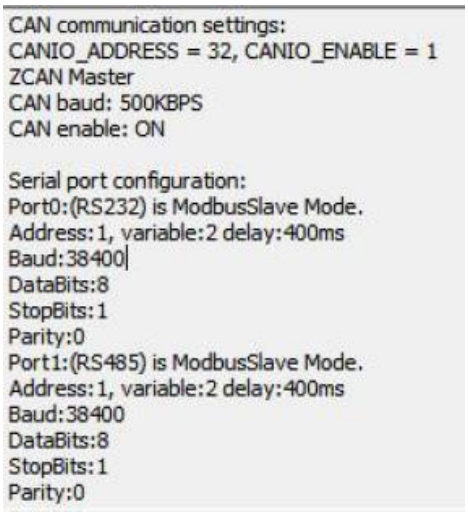
3.2.2. Basic Usage Method

(1) Please follow the above wiring instructions to wiring correctly.

(2) After powered on, please use any one interface among the three interfaces (ETHERNET, RS232, RS485) to connect to RTSys;

(3) Please use the "ADDRESS" and "SETCOM" commands to set and view the protocol station number and configured parameters, see "Basic Programming Manual" for details.

(4) Please use the "CANIO_ADDRESS" command to set the master's "address" and "speed" according to the needs, and use the "CANIO_ENABLE" command to enable or disable the internal CAN master function, or through "RTSys/Controller/State the Controller/Communication Info" to view the CAN status intuitively, and refer to the “ZBasic Programming Manual" for details.



(5) According to their respectively instructions, correctly set the relevant parameters of the third-party equipment to match the parameters of each node.

(6) Correctly set the "address" and "speed" of the slave station expansion module according to the manual of the slave station.

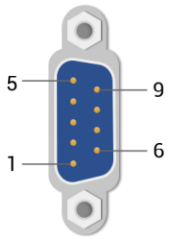
(7) After all the settings are completed, restart the power supply of all stations to establish communication.

(8) Note that the "speed" settings of each node on the CAN bus must be consistent, and the "address" settings cannot cause conflicts, otherwise the "ALM" alarm light will be on, and the communication establishment will fail or the communication will be disordered.

3.3. RS232 Serial Port

RS232 is in a standard DB9 (male) socket and supports MODBUS_RTU protocol and custom communication.

→ Interface Definition:

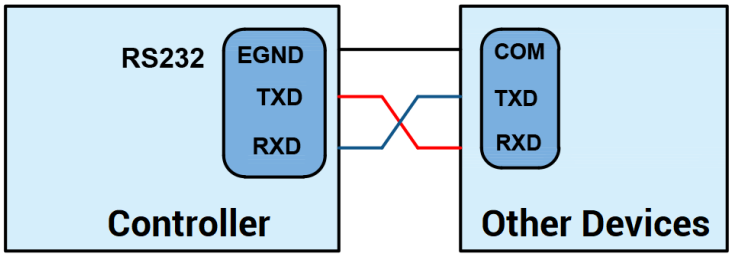
Terminal	PIN	Name	Type	Function
	1, 4, 6, 7, 8	NC	Spare	Reserved
	2	RXD	Input	RS232 signal, receive data
	3	TXD	Output	RS232 signal, send data
	5	EGND	Output	Negative pole output of 5V power, and output for the public end
	9	E5V	Output	Positive pole output of 5V power, maximum is 300mA

3.3.1. RS232 Communication Interface Specification & Wiring

→ Specification:

Item	RS232
Max Communication Rate (bps)	115200
Terminal Resistor	No
Topology	Connect correspondingly (1 to 1)
Nodes can be extended	1
Communication Distance	Longer communication distance, lower communication rate, max 5m is recommended.

→ Wiring Reference:

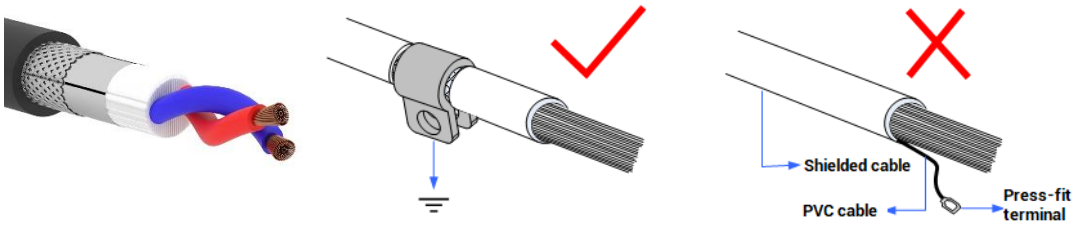


→ Wiring Notes:

- The wiring of RS232 is as above, it needs to cross-wiring for sending and receiving signals, and it is recommended to use a double-female head cross line when connecting to a computer.
- Please be sure to connect the public ends of each communication node to prevent the communication chip from burning out.
- Please use STP, especially in bad environments, and make sure the shielding layer is fully grounded.

→ Cable Requirements:

Twisted pair shielded wire, and shielded cable grounded.



3.3.2. Basic Usage Method

(1) Please follow the above wiring instructions for correct wiring.

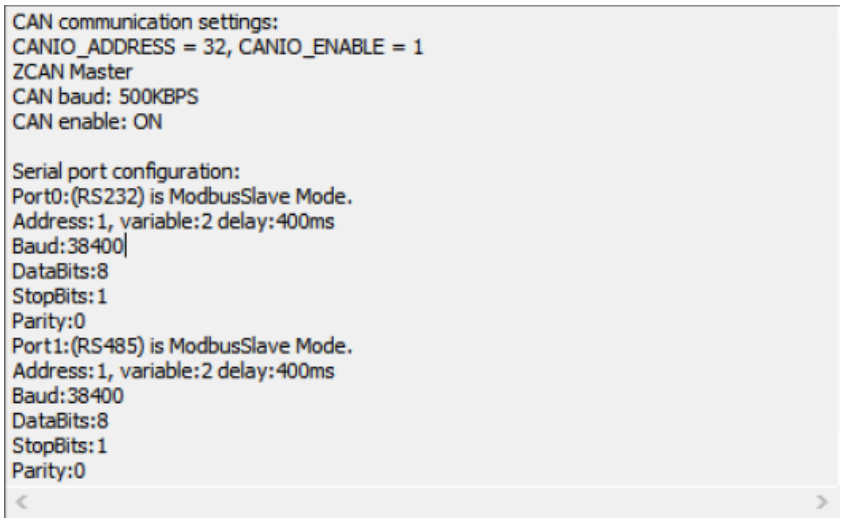
(2) After power on, please use any of the three interfaces ETHERNET, RS232 (default parameter, it can be connected directly) and RS485 (default parameters, it can be connected directly, for hardware, adapter is needed) to connect to RTSys.

(3) Please use the "ADDRESS" and "SETCOM" commands to set and view the protocol station number and configuration parameters, see "Basic Programming Manual" for details.

(4) Correctly set the relevant parameters of the third-party equipment according to their respective instructions to match the parameters of each node.

(5) When all is configured, it can start to do communicating.

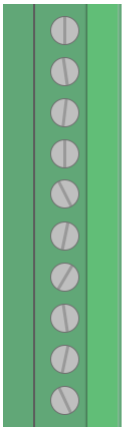
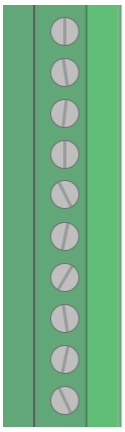
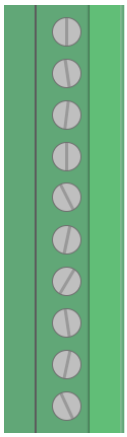
(6) Communication data of RS232 / RS485 can be directly viewed through “RTSys / Controller / State the Controller / CommunicationInfo".



3.4. IN Digital Input & High-Speed Latch Port & Single-Ended Encoder

The digital input adopts 3 groups of 10Pin (there are 3 groups of 10 terminals) screw-type pluggable terminals, and the gap distance between terminals should be 3.81mm. In addition, the high-speed latch function is integrated in digital input signals.

→ Wiring Definition

Terminal	Name	Type	Function 1	Function 2	Function 3
	EGND	/	IO Public End	/	/
	EGND	/		/	/
	IN0	NPN type, high-speed input	Input 0	High Speed Latch	EA (AXIS 6)
	IN1		Input 1		EB (AXIS 6)
	IN2	NPN type, low-speed input	Input 2	/	
	IN3		Input 3	/	
	IN4		Input 4	/	
	IN5		Input 5	/	
	IN6		Input 6	/	
	IN7		Input 7	/	
	EGND	/	IO Public End	/	
	EGND	/		/	
	IN8	NPN type, low-speed input	Input 8	/	
	IN9		Input 9	/	
	IN10		Input 10	/	
	IN11		Input 11	/	
	IN12		Input 12	/	
	IN13		Input 13	/	
	IN14		Input 14	/	
	IN15		Input 15	/	
	EGND	/	IO Public End	/	
	EGND	/		/	
	IN16	NPN type, low-speed input	Input 16	/	
	IN17		Input 17	/	
	IN18		Input 18	/	
	IN19		Input 19	/	
	IN20		Input 20	/	
	IN21		Input 21	/	
	IN22		Input 22	/	
	IN23		Input 23	/	

Note:

For specialized firmware version, IN0-1 support single-ended encoder function, but it needs to use AXIS_ADDRESS command to map, and configure axis type by ATYPE. While mapping, please use physical axis 6. If not use AXIS_ADDRESS to map, only set ATYPE, it can't recognize physical axis 6, that is, if you operate axis 6 now, axis 0 will be recognized and operated, then error will appear. When ATYPE=0, IN0-1 are normal inputs.

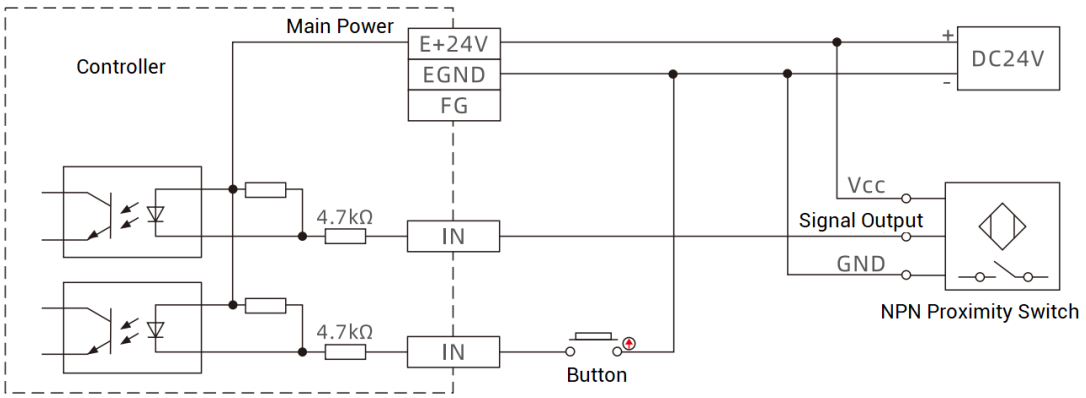
3.4.1. Digital Input Specification & Wiring

→ Specification

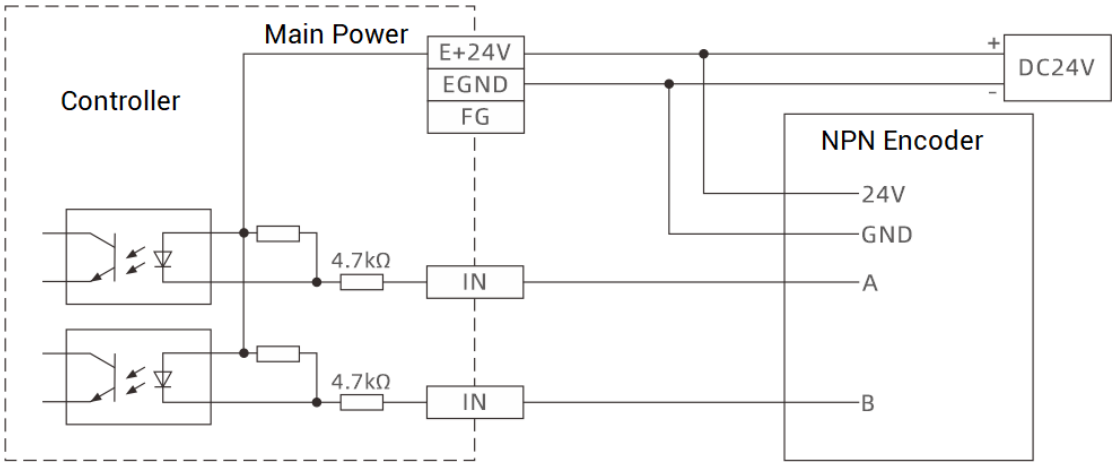
Item	High-Speed Input (IN0-1)	Low-Speed Input (IN2-23)
Input mode	NPN type, the input is triggered when there is low level	
Frequency	< 100kHz	< 5kHz
Impedance	3.3KΩ	4.7KΩ
Voltage level	DC24V	DC24V
The voltage to open	<15V	<14.5V
The voltage to close	>15.1V	>14.7V
Minimal current	-2.3mA (negative)	-1.8mA (negative)
Max current	-7.5mA (negative)	-6mA (negative)
Isolation mode	optoelectronic isolation	optoelectronic isolation
Note: the above parameters are standard values when the voltage of controller power supply (E+24V port) is 24V.		

→ Wiring Reference

General Wiring:



Single-Ended Encoder Wiring:



→ Wiring Note:

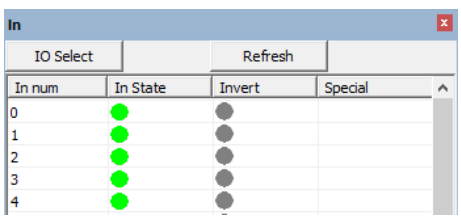
- The wiring principle of high-speed digital input IN (0-1) and low-speed digital input IN (2-23) is shown in the figure above. The external signal source can be an optocoupler, a key switch or a sensor, etc., all can be connected as long as the requirements on output of electric level can be achieved.
- For the public end, please connect the "EGND" port on the power supply to the "COM" terminal of the external input device. If the signal area power supply of the external device and the power supply of the controller are in the same power supply system, this connection also can be omitted.

3.4.2. Basic Usage Method

(1) Please follow the above wiring instructions to wiring correctly.

(2) After powered on, please select any one interface among the three interfaces ETHERNET, RS232 and RS485 to connect to ZDevelop.

(3) State values of relative input ports can be read directly through “IN” command, also, it can be read through “ZDevelop/View/In". Please refer to “ZBasic” for details.



(4) Latch function can be set and triggered through “REGIST” instruction, in software, use REG_INPUTS to configure. Please refer to “ZBasic” for details.

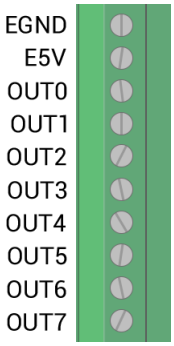
(5) How to map axis while using IN0-1 single-ended encoder function

AXIS_ADDRESS (axis No. to be mapped) = (-1<<16) + the local pulse axis No. to be modified, now physical axis 6 is used.
BASE (axis No. to be mapped)
ATYPE = 0
BASE (the local pulse axis No. to be modified, now physical axis 6 is used)
ATYPE = 0
BASE (axis No. to be mapped)
ATYPE = the axis is with encoder

3.5. OUT (Digital Output, PWM Terminal, Hardware Comparison Output, Single-Ended Pulse)

The digital output adopts 2 sets of screw-type pluggable terminals with a spacing of 3.81mm, and the PWM and hardware comparison output functions are integrated in digital output signals.

→ Terminal Definition

Terminal	Name	Type	Function 1	Function 2	Function 3	4
	EGND	/	IO public end	/	/	
	E5V	/	5V power output, max is 300mA	/	/	
	OUT0	NPN type, high-speed out	Output 0	PWM 0	Hardware Comparison Output	PUL (AXIS 6)
	OUT1		Output 1	PWM 1		DIR (AXIS 6)
	OUT2	NPN type, low-speed output	Output 2	PWM 2		PUL (AXIS 7)
	OUT3		Output 3	PWM 3		DIR (AXIS 7)
	OUT4		Output 4	/	/	
	OUT5		Output 5	/	/	
	OUT6		Output 6	/	/	

	OUT7		Output 7	/	/	
	EGND	/	IO public end	/	/	
	OUT8	NPN Leakage type, low-speed out	Output 8	/	/	
	OUT9		Output 9	/	/	
	OUT10		Output 10	/	/	
	OUT11		Output 11	/	/	

Notes:

✧ The E5V power output port is used for PWM or common anode wiring of single-ended axis. It is not recommended for other purposes due to lower power.

✧ OUT0-3 have the functions of PWM and hardware comparison output, among which OUT2 and 3 are low-speed outputs.

✧ For special firmware, OUT0-3 support single-ended pulse-axis (axis 6 & axis 7), and it must use AXIS_ADDRESS command to map, then configure ATYPE. When ATYPE = 0, they are general outputs.

3.5.1. Digital Output Specification & Wiring

→ Specification

Item	High Speed Output (OUT0-1)	Low Speed Output (OUT2-11)
Output mode	NPN type, it is 0V when outputs	
Frequency	< 400kHz	< 8kHz
Voltage level	DC24V	DC24V
Max output current	+300mA	+300mA
Max leakage current when off	25μA	25μA
Respond time to conduct	1μs (resistive load typical value)	12μs
Respond time to close	3μs	80μs
Overcurrent protection	Support	Support
Isolation method	optoelectronic isolation	

Note:

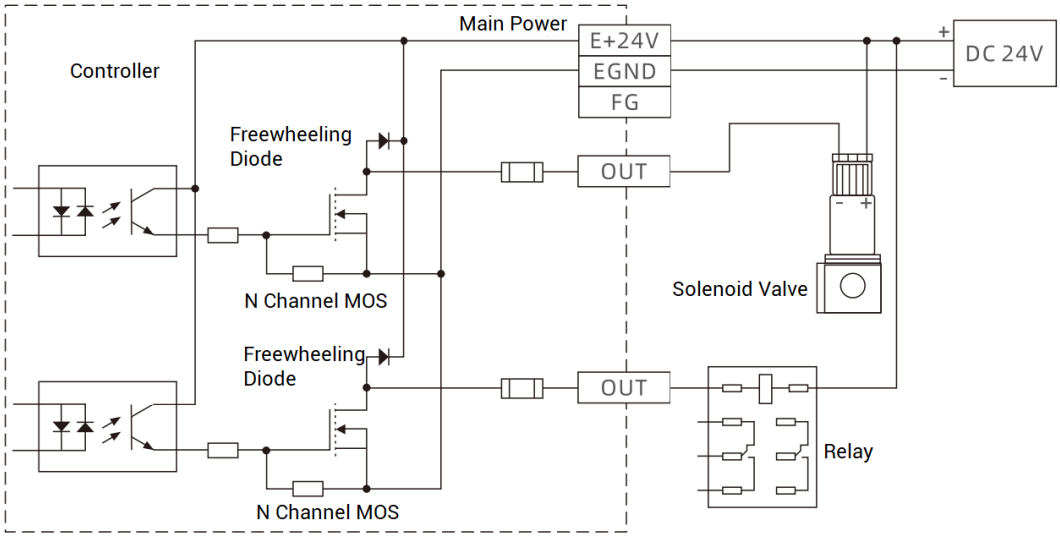
✧ The times in the form are typical based on the resistive load, and may change

when the load circuit changes.

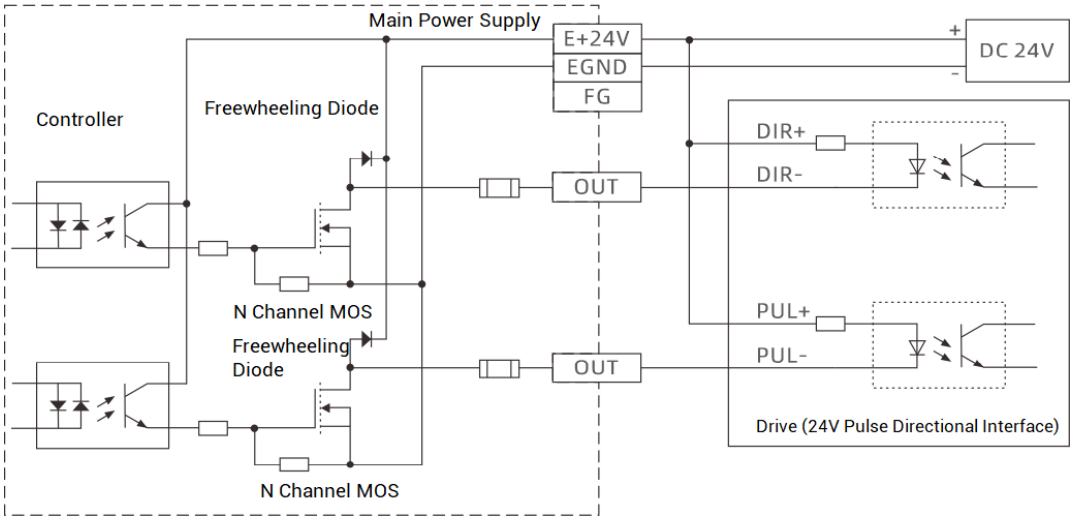
✧ Due to the leak-type output, the shutdown of the output will be obviously affected by the external load circuit, and the output frequency should not be set too high in the application.

→ Wiring Reference

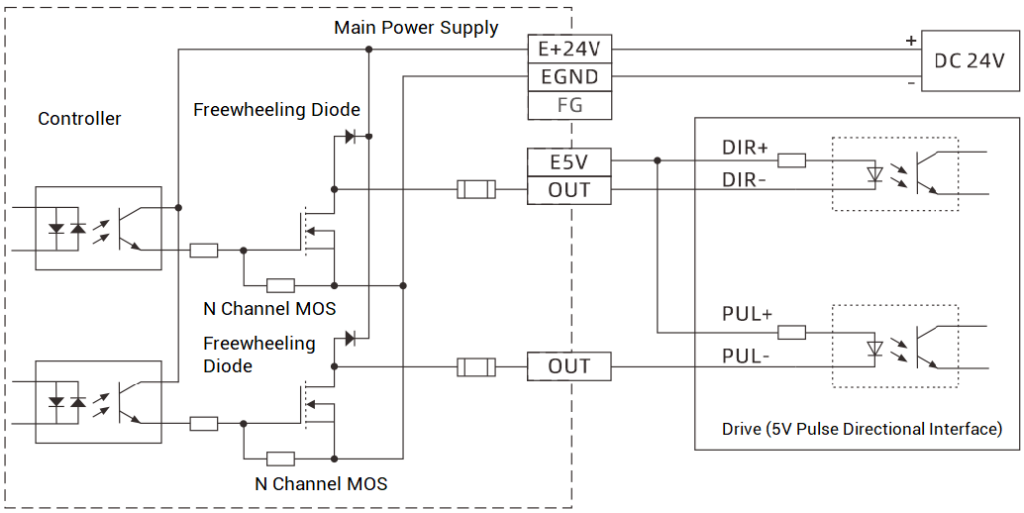
General Wiring:



Single-Ended Pulse Wiring (24V):



Single-Ended Pulse Wiring (5V):



→ Wiring Note:

- The wiring principle of high-speed digital output OUT (0-1) and low-speed digital output OUT (2-11) is shown in the figure above. The external signal receiving end can be an optocoupler or a relay or solenoid valve, all can be connected as long as the input current does not exceed 300mA.
- For the connection of the public end, please connect the "EGND" port on the power supply to the negative pole of the DC power supply of the external input device. If the DC power supply of the external device and the controller power supply are in the same power supply system, this connection can also be omitted.
- The E5V port is a 5V power output port, which can be used when some loads need to provide an external 5V power input, the maximum current is 300mA.

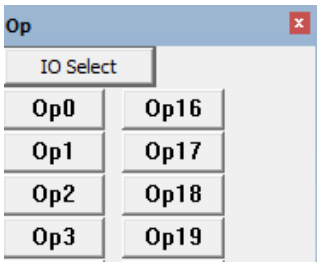
3.5.2. Basic Usage Method

(1) Please follow the above wiring instructions to wiring correctly.

(2) After powered on, please use any one interface among the three interfaces ETHERNET, RS232 and RS485 to connect to RTSys.

(3) Open or close output port directly through “OP” command, also, it can be opened or

closed through “RTSys/Tool/Op”. Please refer to “Basic” for details.



(4) The PWM function, set the frequency and duty cycle through “PWM_FREQ” and “PWM_DUTY”. Please refer to ZBasic for details.

(5) Hardware comparison output can be set and opened through “HW_PSWITCH2”. Please refer to ZBasic for details.

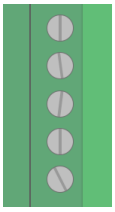
(6) How to map axis when using OUT0-3 single-ended pulse function:

AXIS_ADDRESS (axis No. to be mapped) = (-1<<16) + the local pulse axis No. to be modified, now physical axis 6 and axis 7 are used.
BASE (axis No. to be mapped)
ATYPE = 0
BASE (the local pulse axis No. to be modified, now physical axis 6 and axis 7 are used)
ATYPE = 0
BASE (axis No. to be mapped)
ATYPE = the axis is with pulse output

3.6. DA Analog Output

The analog port adopts a set of 5Pin screw-type pluggable terminals with a spacing of 3.81mm.

→ Terminal Definition

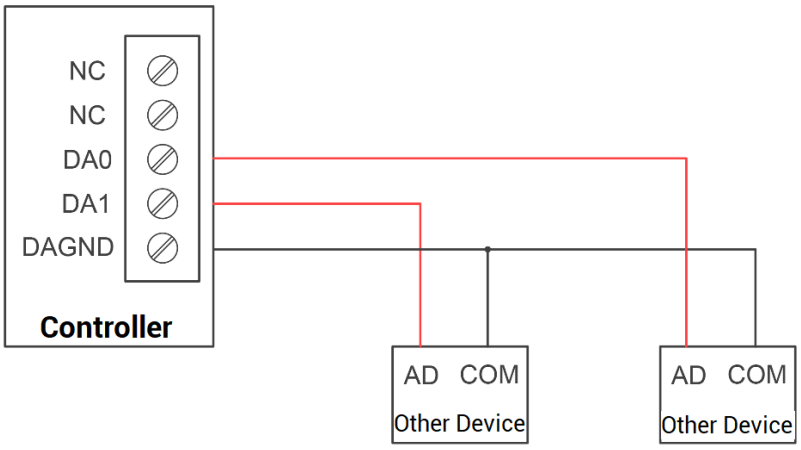
Terminal	Name	Type	Function
 NC NC DA0 DA1 DAGND	NC	Spare	Reserved
	NC		Reserved
	DA0	Output	Analog output terminal: AOUT(0)
	DA1		Analog output terminal: AOUT(1)
	DAGND	Public End	Analog public end

3.6.1. Analog Output Specification & Wiring

→ Specification

Item	DA（0-1）
Resolution	12-bit
Data range	0-4095
Signal range	0-10V output
Data refresh ratio	1KHz
Voltage output load	>1KΩ

→ Wiring Reference

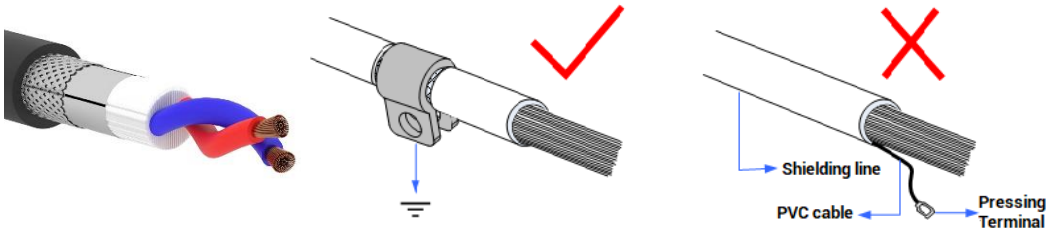


→ Wiring Note:

- The analog input/output wiring method is as shown in the figure above, and the external load signal range must match with this signal range.
- Please use STP, especially in bad environments, and make sure the shielding layer is fully grounded.

→ Cable Requirements:

Shielded Twisted Pair, and the shielded cable is grounded.

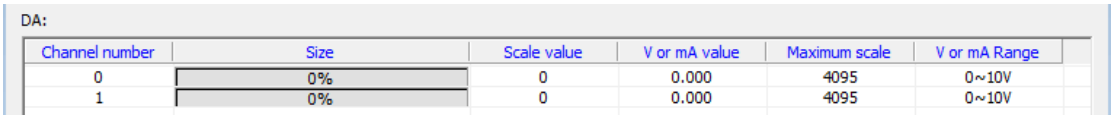


3.6.2. Basic Usage Method

(1) Please follow the above wiring instructions to wiring correctly.

(2) After powered on, please use any one interface among the three interfaces ETHERNET, RS232 and RS485 to connect to RTSys.

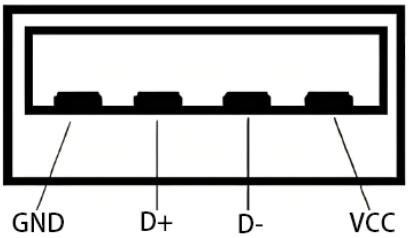
(3) Analog input voltage can be read through “AIN” command and corresponding analog voltage can be output through “AOUT” command, also, data of each channel can be checked through “RTSys/Tool/AD/DA”. Please refer to “Basic” for details.


DA:

Channel number	Size	Scale value	V or mA value	Maximum scale	V or mA Range
0	0%	0	0.000	4095	0~10V
1	0%	0	0.000	4095	0~10V

3.7. U Disk

The ZMC406-V2 motion controller provides a USB communication interface, which can insert the U disk device. It is used for ZAR program upgrading, controller data importing and exporting, file 3 executing, etc. Its schematic diagram is shown in the figure below:

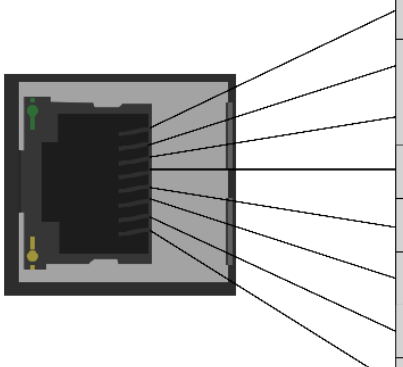


→ **Specification**

Item	USB2.0
Highest Communication Ratio	12Mbps
Max Output Current of 5V	500mA
Whether Isolates	No

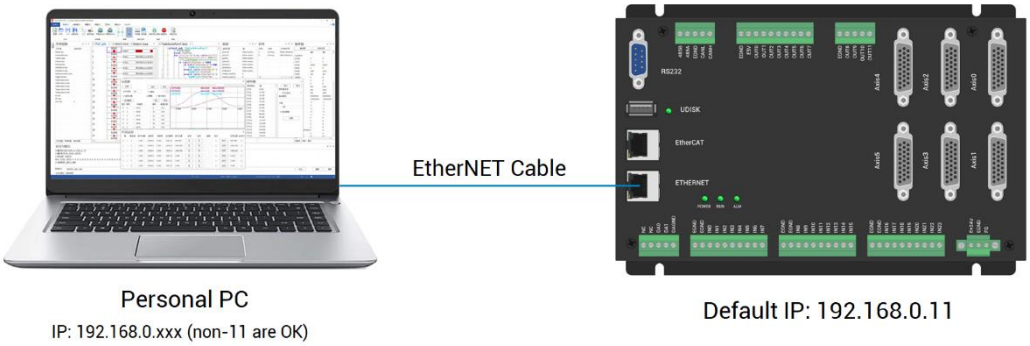
3.8. ETHERNET

ZMC406-V2 motion controller has a 100M network port, and it supports MODBUS_TCP protocol and custom communication, the default IP address is 192.168.0.11. While connecting to controller, both sides' IP are in same network segment, but with different IP addresses (for example: personal PC default network segment is 192.168.0.xxx (non-11 are OK)). Following shows PIN definitions:

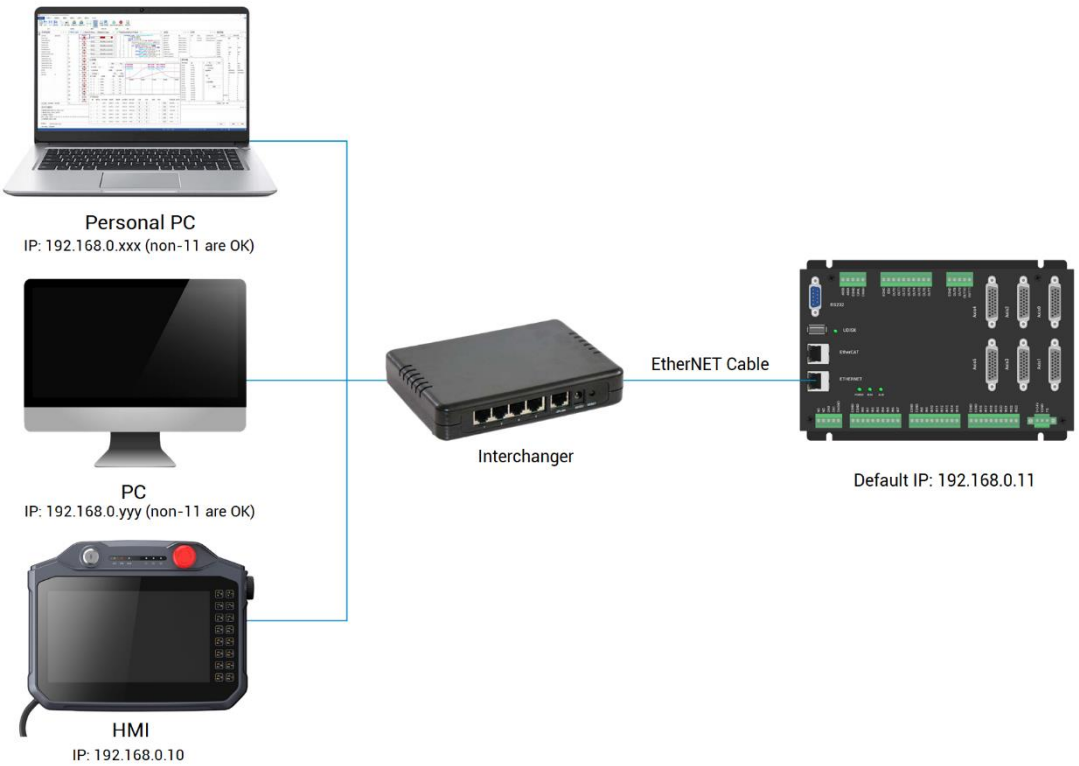


PIN	Signal	Description
1	TX+	Send signal (+)
2	TX-	Send signal (-)
3	RX+	Receive signal (+)
4	NC	Reserved
5	NC	Reserved
6	RX-	Receive signal (-)
7	NC	Reserved
8	NC	Reserved

The Ethernet port of the controller can be connected to a computer, HMI, etc. through an Ethernet cable, and point to point connection method is used. Following shows PIN:

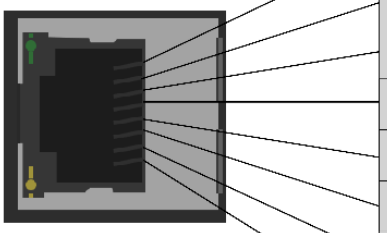


The controller can also be connected to the interchanger through an Ethernet cable, and then use interchanger to connect to other devices, then multi-point connection can be achieved. The schematic diagram is as follows:



3.9. EtherCAT Bus Interface

ZMC406 -V2 motion controller has a 100M EtherCAT communication interface, and it supports EtherCAT protocol. In addition, EtherCAT driver or EtherCAT expansion module can be connected. The pin definition is as follows:



PIN	Signal	Description
1	TX+	Send signal (+)
2	TX-	Send signal (-)
3	RX+	Receive signal (+)
4	NC	Reserved
5	NC	Reserved
6	RX-	Receive signal (-)
7	NC	Reserved
8	NC	Reserved

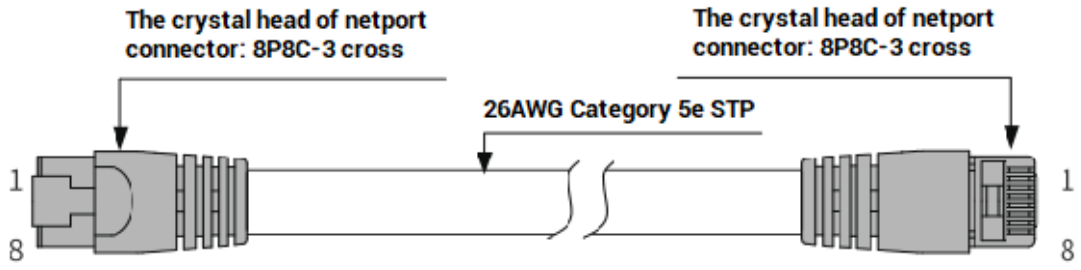
→ Specification

Item	Specification
Communication protocol	EtherCAT protocol
Valid service	CoE(PDO, SDO), FoE
Synchronization method	IO adopts input and output synchronization / DC-distributed clock
Physical level	100BASE-TX
Duplex mode	Full duplex
Topology	linear topology
Transfer media	Cable
Transfer distance	It is less than 100M between 2 nodes
Process data	Maximum 1486 bytes of one single frame
Synchronization shaking of two slave stations	<1us
Refresh	For 1000 digital inputs and outputs, about 30us

→ Communication Cable Requirements

Both ETHERNET communication interface and EtherCAT communication interface adopt standard Ethernet RJ45 interface.

The network cable adopts Category 5e STP, and the crystal head has a metal shell to reduce interference and to prevent information from being eavesdropped. As shown below:



Item	Specification
Cable type	Flexible crossover cable, Category 5e
traverse	Dual twisted pair
Line pairs	4
Isolation	cross skeleton

Connector	Crystal head with iron shell
Cable material	PVC
Cable length	Less than 100m

Use RJ45 network cable connection method:

- When installing, hold the crystal head that is with the cable and insert it into the RJ45 interface until it makes a "click" sound (kada).
- In order to ensure the stability of communication, please fix the cables with cable ties.
- When disassembling, press the tail mechanism of the crystal head, and pull out the connector and the module in a horizontal direction.

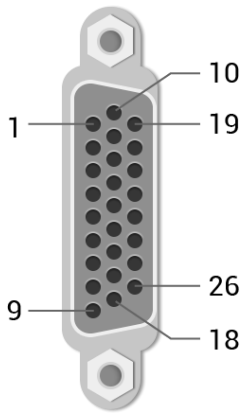
Please use tube-type pre-insulated terminals and cables with appropriate wire diameters to connect the user terminals.

3.10. AXIS Differential Pulse Axis Interface

This product provides 6 local differential pulse axis interfaces, each interface is a standard DB26 female socket. Each terminal provides 0V and +5V output, which can provide 5V power for the encoder.

Before the axis is used, use ATYPE instruction to configure the axis type.

→ Interface Definition

Interface	Pin	Signal	Description
	1	EGND	Negative pole of IO 24V power
	2	IN24-29/ALM	General input (recommended as driver alarm)
	3	OUT12-17/ENABLE	General output (recommended as driver enable)
	4	EA-	Encoder differential input signal A-
	5	EB-	Encoder differential input signal B-
	6	EZ-	Encoder differential input signal Z- / SSI_DAT- / BISS_DAT -
	7	+5V	Positive pole of 5V power of

			pulse/encoder signal
	8	Reserved	Reserved
	9	DIR+	Servo or step directional output differential signal +
	10	GND	Negative pole of 5V power of pulse/encoder signal
	11	PUL-	Servo or step pulse output differential signal - / SSI_CLK- / BISS_CLK -
	12	Reserved	Reserved
	13	GND	Negative pole of 5V power of pulse/encoder signal
	14	OVCC	Positive pole of IO 24V power
	15	Reserved	Reserved
	16	Reserved	Reserved
	17	EA+	Encoder differential input signal A+
	18	EB+	Encoder differential input signal B+
	19	EZ+	Encoder differential input signal Z+ / SSI_DAT+ / BISS_DAT +
	20	GND	Negative pole of 5V power of pulse/encoder signal
	21	GND	
	22	DIR-	Servo or step direction output differential signal -
	23	PUL+	Servo or step pulse output differential signal + / SSI_CLK+ / BISS_CLK +
	24	GND	Negative pole of 5V power of pulse/encoder signal
	25	Reserved	Reserved
	26	Reserved	Reserved

Note:

- ALM and ENABLE are recommended to be used as axis IO, because the drive capacity is small.
- OVCC, +5V are only used for communication between the controller and the servo driver, please do not use it as power supply for other places.

- ✧ SSI / BISS absolute values use PUL signal to do as CLK output, and use EZ signal to do as DAT input, therefore, they can't use as pulse-axis at the same time. But when EZ is not needed for AB encoder, synchronous use can be valid.
- ✧ If the controller's firmware is with Ssi, which means it supports SSI/BISS absolute value encoder.
- ✧ Then, check the controller state, it can be seen ZMC406-V2 Axis 4 and Axis 5 support SSI/BISS absolute value encoder.
- ✧ When using absolute encoders, please note the resolution and clock frequency of controller and encoder, if the clock frequency is different, it will affect the communication, which can be modified by ENCODER_BITS, after set, please power down and restart the controller to make it effect.

Pulse-axis PIN and IO corresponding relation:

Pulse-Axis No.	Corresponding IN (PIN2)	Corresponding OUT (PIN3)
AXIS 0	24	12
AXIS 1	25	13
AXIS 2	26	14
AXIS 3	27	15
AXIS 4	28	16
AXIS 5	29	17

3.10.1. AXIS Interface Signal Specification & Wiring

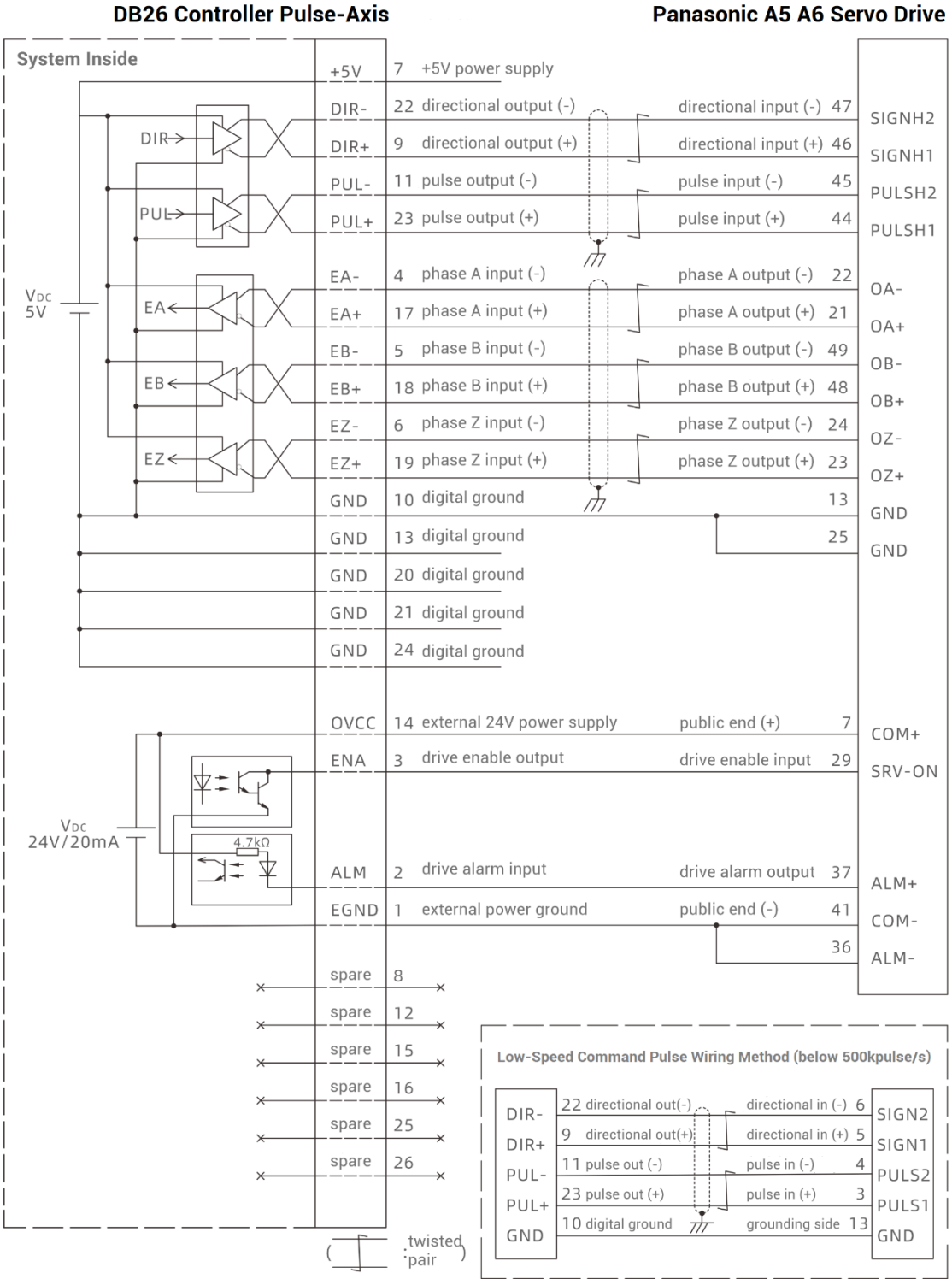
→ Specification:

Signal	Item	Description
PUL/DIR	Signal type	Differential output signal
	Voltage range	0-5V
	Maximum frequency	10MHz
EA/EB/EZ	Signal type	Differential input signal
	Voltage range	0-5V
	Maximum frequency	5MHz
IN24-29	Input method	NPN type, it is triggered when low electric level is input.

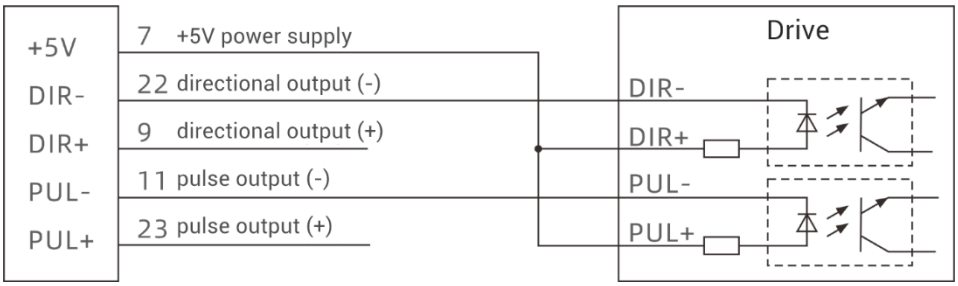
	Frequency	< 5kHz
	Impedance	6.8KΩ
	Voltage level	DC24V
	The voltage to open	<10.5V
	The voltage to close	>10.7V
	Minimal current	-1.8mA (negative)
	Maximum current	-4mA (negative)
	Isolation	Optoelectronic isolation
OUT12-17	Output method	NPN type, it is 0V when outputs
	Frequency	< 8kHz
	Voltage level	DC24V
	Maximum current	+50mA
	Overcurrent protection	No
	Isolation	Optoelectronic isolation
+5V, GND	Maximum output current for 5V	50mA
OVCC, EGND	Maximum output current for 24V	50mA

→ Wiring Reference:

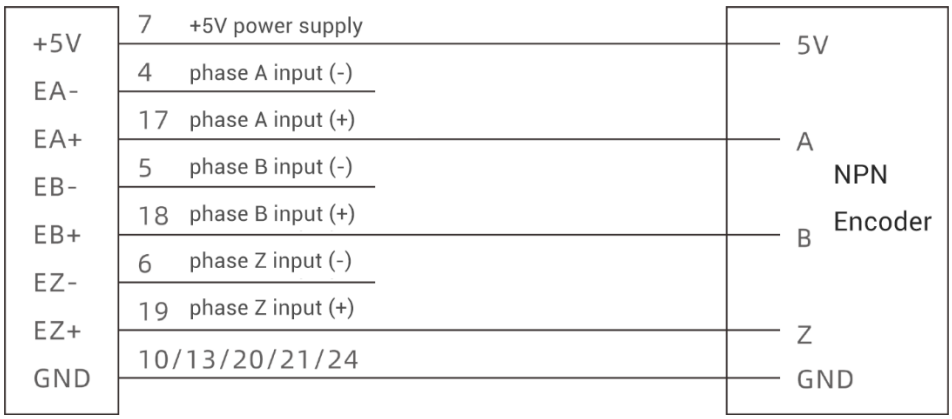
Reference example of wiring with Panasonic A5/A6 servo driver.


DB26 Controller Pulse-Axis
Panasonic A5 A6 Servo Drive
System Inside
+5V 7 +5V power supply
DIR- 22 directional output (-)
DIR+ 9 directional output (+)
PUL- 11 pulse output (-)
PUL+ 23 pulse output (+)
EA- 4 phase A input (-)
EA+ 17 phase A input (+)
EB- 5 phase B input (-)
EB+ 18 phase B input (+)
EZ- 6 phase Z input (-)
EZ+ 19 phase Z input (+)
GND 10 digital ground
GND 13 digital ground
GND 20 digital ground
GND 21 digital ground
GND 24 digital ground
OVCC 14 external 24V power supply
ENA 3 drive enable output
ALM 2 drive alarm input
EGND 1 external power ground
spare 8
spare 12
spare 15
spare 16
spare 25
spare 26
DIR
PUL
EA
EB
EZ
VDC 5V
VDC 24V/20mA
4.7kΩ
twisted pair
directional input (-) 47
directional input (+) 46
pulse input (-) 45
pulse input (+) 44
phase A output (-) 22
phase A output (+) 21
phase B output (-) 49
phase B output (+) 48
phase Z output (-) 24
phase Z output (+) 23
13
25
public end (+) 7
drive enable input 29
drive alarm output 37
public end (-) 41
36
SIGNH2
SIGNH1
PULSH2
PULSH1
OA-
OA+
OB-
OB+
OZ-
OZ+
GND
GND
COM+
SRV-ON
ALM+
COM-
ALM-
Low-Speed Command Pulse Wiring Method (below 500kpulse/s)
DIR-
DIR+
PUL-
PUL+
GND
22 directional out(-)
9 directional out(+)
11 pulse out (-)
23 pulse out (+)
10 digital ground
directional in (-) 6
directional in (+) 5
pulse in (-) 4
pulse in (+) 3
grounding side 13
SIGN2
SIGN1
PULS2
PULS1
GND

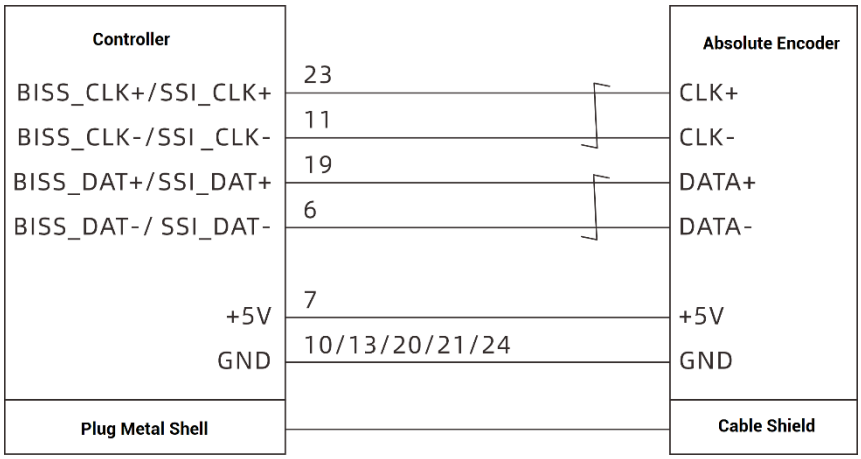
Wiring Reference of PUL/DIR common anode:



Wiring Reference of EA/EB/EZ single-ended:



Wiring of absolute encoder:



→ Wiring Note:

✧ The wiring principle of the differential pulse axis interface is shown in the figure above, and the wiring methods of different types of drivers are different, please

connect carefully.

✧ Please use STP, especially in bad environments, and make sure the shielding layer is fully grounded.

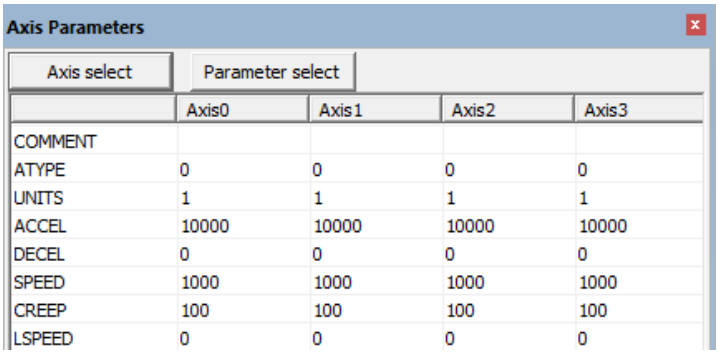
3.10.2. Basic Usage Method

(1) Please follow the above wiring instructions to wiring correctly.

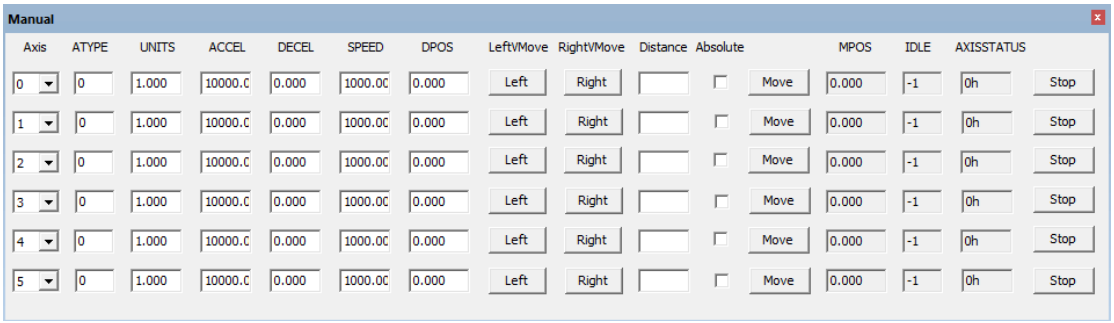
(2) After powered on, please use any one interface among the three interfaces ETHERNET, RS232 (default parameter, it can be connected directly) and RS485 (default parameters, it can be connected directly, but for hardware, adapter head is needed) to connect to RTSys.

(3) Set axis parameters, such as, ATYPE, UNITS, SPEED, ACCEL, FWD_IN, REV_IN, etc.

(4) There are many parameters related to pulse axis, they can be set and checked through relative instructions, please see “axis parameter and axis status" of “Basic", or see “RTSys/View/Axis parameter".



(5) Control corresponding motion through “View – Manual".



Refer to BASIC Routine:

```
BASE(0,1)              'select axis 0 and axis 1
ATYPE = 1,1            'set axis 0 and axis 1 as pulse axes
UNITS = 1000,1000      'set pulse amount as 1000 pulses
SPEED = 10,10          'set axis speed as 100 units/s
ACCEL = 1000,1000      ‘set axis acceleration as 1000*1000 pulse/s/s
FWD_IN = -1,-1         'prohibit using axis positive hardware position limit
REV_IN = -1,-1         'prohibit using axis negative hardware position limit
MOVE(10) AXIS(0)       'axis 0 moves distance of 10*1000 pulses in positive
MOVE(-20) AXIS(0)      'axis 0 moves distance of 20*1000 pulses in negative
```

Chapter IV Expansion Module

The controller can expand digital IO, analog IO, pulse axis and other resources through CAN bus or EtherCAT bus. That is, it can use together with ZIO series CAN expansion modules, EIO series EtherCAT expansion modules, or ZMIO310 series vertical expansion modules. For details, please refer to corresponding user manual.

4.1. CAN Bus Expansion

ZIO series expansion modules or ZMIO310-CAN coupler with sub modules can be used.

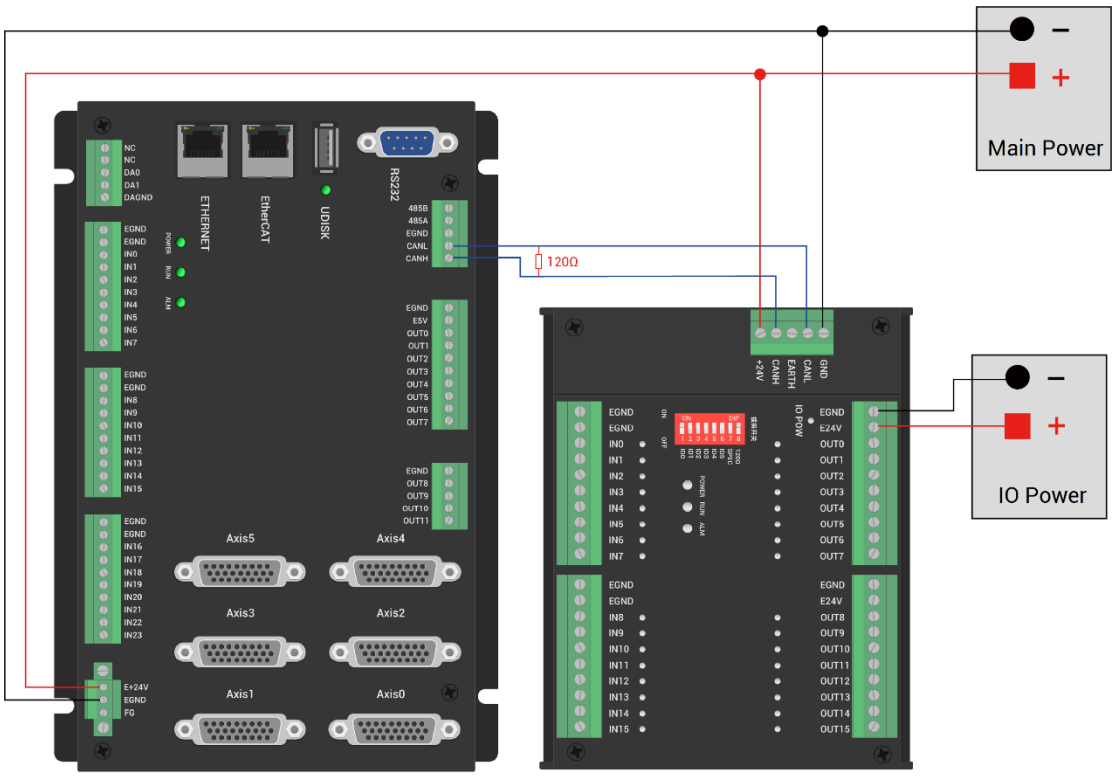
4.1.1. CAN Bus Expansion Wiring

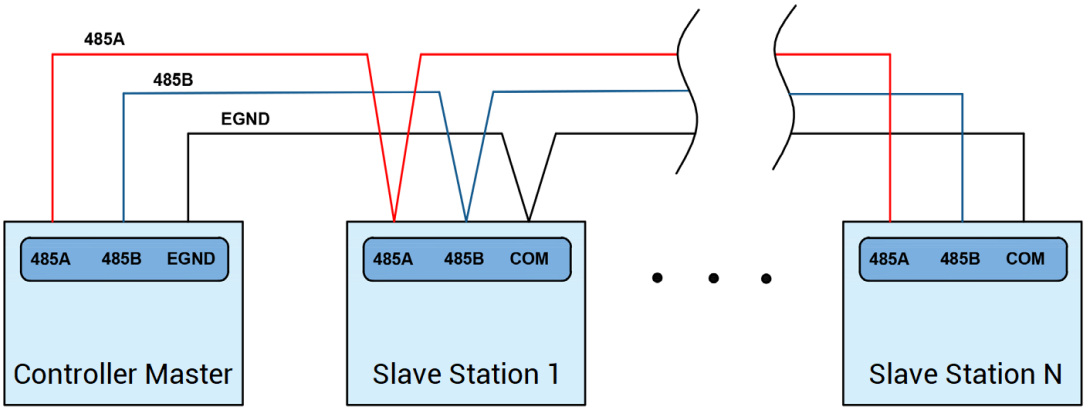
The ZIO expansion module is powered by the dual power supply. Except the main power supply, an additional IO power supply is required to supply independent power for IO. Both the main power supply and the IO power supply use 24V DC power supply. For ZAIO, it only needs to connect to the main power supply.

To prevent interference, separate the IO power supply from the main power supply.

Please select the expansion module according to the requirements, and select IO mapping or axis mapping according to the resources of the expansion module. Attention the No. must be different while mapping.

Wiring reference of connection between ZIO expansion module and control card and standard wiring of CAN bus are shown as below:



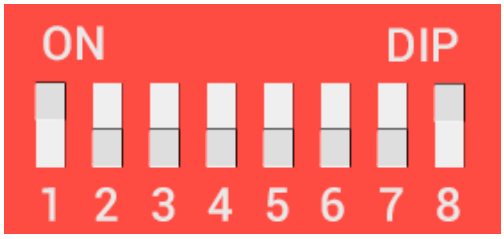


→ Wiring Note:

✧ ZMC406-V2 controller uses the single power, and ZIO expansion module uses dual-power. When using, main power supply of expansion module and main power supply of controller can share one power. When they use different power supplies, controller power EGND needs to connect to expansion module power GND, otherwise CAN may be burnt out.

✧ When connecting multiple ZIO expansion modules on the CAN bus, a 120-ohm resistor needs to be connected in parallel between the CANL and CANH terminals, for the ZIO expansion module that is with 8-digit dialing codes, the terminal resistor can be realized by dialing the code (DIP).

4.1.2. CAN Bus Expansion Resource Mapping



The ZCAN expansion module generally has an 8-code DIP switch, dial ON to take effect, and the meaning of the DIP is as follows:

1-4: they are used for ZCAN expansion module IO address mapping, the corresponding value is 0-15.

5-6: CAN communication speed, corresponding value is 0-3, four different speeds are optional.

7: reserved.

8: 120 ohm resistor, dial ON means a 120 ohm resistor is connected between CANL and CANH.

The IO numbers of the entire control system cannot be repeated, and existed numbers must be avoided when mapping resources. And the DIP switch must be dialed before power-on , if re-dial after power-on, it is invalid. It needs to be powered on again to take effect.

Dial 1-4 to select the CAN address, and the controller sets the IO number range of the corresponding expansion module according to the CAN DIP address. When each is dialed as OFF, the corresponding value is 0, when it is ON , it corresponds to a value of 1, and the address combination value = dial 4 × 8 + dial code 3 × 4 + dial code 2 × 2+ dial code 1.

Dial code 5-6 to select CAN bus communication speed, speed combination value=dial code 6 × 2 + dial code 5×1, the combined value range is 0-3.

The corresponding speeds are as follows:

DIP 5-6 combination value	CANIO_ADDRESS high 8-bit value	CAN communication speed
0	0 (corresponds to decimal 128)	500KBPS (default value)
1	1 (corresponds to decimal 256)	250KBPS
2	2 (corresponding to decimal 512)	125KBPS
3	3 (corresponding to decimal 768)	1MBPS

The controller side sets the CAN communication speed through the CANIO_ADDRESS

command. There are also four speed parameters that can be selected. The communication speed must be consistent with the communication speed of the expansion module that corresponds to the combination value, then they can communicate with each other.

The factory default communication speed is 500 KBPS on both sides, there is no need to set this, unless you need to change the speed.

The CANIO_ADDRESS command is a system parameter, and it can set the master-slave end of CAN communication. The default value of the controller is 32, that is, CANIO_ADDRESS=32 is the master end, and the slave end is set between 0-31.

The CAN communication configuration can be viewed in the "State the Controller" window.

→ IO Mapping:

IO mapping of the CAN expansion module uses code 1-4 of the DIP switch. According to the number of currently included IO points(the largest number in IN and OP must include IO point in the axis interface), use the code 1-4 to set the ID, so as to determine the number range of IO to be expanded.

If the controller itself contains 28 INs and 16 OPs, then the starting address set by the first extended board should exceed the maximum value of 28. According to below rule, the dial code should be set to the combination value 1 (binary combination value 0001, from right to left, dial code 1-4, at this time dial 1 is set to ON, and the others are set to OFF), the IO number on the expansion board = the expansion board number value + the initial IO number value, among them, the IOs that are vacant from 29-31 Numbers are not used. Subsequent extended boards continue to confirm the dial settings according to the IO points in turn.

The initial digital IO mapping number starts from 16 and increases in multiples of 16. The distribution of digital IO numbers corresponding to different dial IDs is as follows:

DIP 1-4 combination value	Starting IO number	Ending IO number
0	16	31
1	32	47
2	48	63
3	64	79
4	80	95
5	96	111
6	112	127

7	128	143
8	144	159
9	160	175
10	176	191
11	192	207
12	208	223
13	224	239
14	240	255
15	256	271

The initial IO mapping number of the analog AD starts from 8 and increases in multiples of 8. The initial IO mapping number of the analog DA starts from 4 and increases in multiples of 4. The allocation of digital IO numbers corresponding to different dial code IDs is as follows:

DIP 1-4 combination value	Starting AD number	End AD number	Starting DA number	End DA number
0	8	15	4	7
1	16	23	8	11
2	24	31	12	15
3	32	39	16	19
4	40	47	20	23
5	48	55	24	27
6	56	63	28	31
7	64	71	32	35
8	72	79	36	39
9	80	87	40	43
10	88	95	44	47
11	96	103	48	51
12	104	111	52	55
13	112	119	56	59
14	120	127	60	63
15	128	135	64	67

→ Axis Mapping:

When the CAN bus expansion mode is used to expand the pulse axis, ZIO16082M can be selected to expand two pulse axes. These two pulse axes need to be mapped and bound with the axis No., then access.

Extended axes need to perform axis mapping operations, using the AXIS_ADDRESS command to map, and the mapping rules are as follows:

AXIS_ADDRESS(axis No.)=(32*0)+ID

'the local axis interface of the expansion module AXIS 0

AXIS_ADDRESS(axis No.)=(32*1)+ID

'the local axis interface of the expansion module AXIS 1

The ID is the combined value of the DIP code 1-4 of the expansion module. After the mapping is completed and the axis parameters such as ATYPE are set, the expansion axis can be used.

Example:

```
ATYPE(6)=0                    'set as virtual axis
AXIS_ADDRESS(6)=1+(32*0)
        'ZCAN expansion module ID 1 axis 0 is mapped to axis 6
ATYPE(6)=8      'ZCAN extended axis type, pulse direction stepping or servo
UNITS(6)=100 0 'pulse equivalent 1000
SPEED(6)=100    'speed 100units/s
ACCEL(6)=1000    'acceleration 1000units/s^2
MOVE(100) AXIS(6) 'extended axis movement 100units
```

Extended resource viewing:

According to the CAN wiring, after the power is turned on, and the wiring resistance dial code is set correctly, the power indication led (POWER) and the running indication led (RUN), the IO power indication led (IO POWER) are on, but the alarm indication led (ALM) should be off. At the same time, the "Controller" - "State the controller" - "ZCanNodes" in the ZDevelop software displays the expansion module information and the extended IO number range.

The dial ID and the corresponding resource number when connecting multiple expansion modules are as follows:

Local	432-0(ZMC432)	32	30(0-29)	18(0-17)	0	2(0-1)
1	48(ZIO1632)	0	16(32-47)	32(32-63)	0	0
3	26(ZIO16082)	2	16(64-79)	8(64-71)	0	0
4	10(ZAIO0802)	0	0	0	8(40-47)	2(20-21)

ALMRM indicator light is on, please check whether the wiring, resistor and dial setting are correct, and whether the CANIO_ADDRESS command of the controller is set as the master (32), and whether the CAN communication speed is consistent.

4.2. EtherCAT Bus Expansion

The EIO expansion modules and ZMIO310-ECAT are expansion modules used by the EtherCAT bus controller. For example, EIO series can expand the resources of digital IO and pulse axis. When the resources of the controller are insufficient, the EtherCAT bus controller can be connected to multiple EIO expansion modules for expansion, you can view the maximum number of IO expansion points and the maximum number of expansion axes of the controller, and in this way, it supports IO remote expansion.

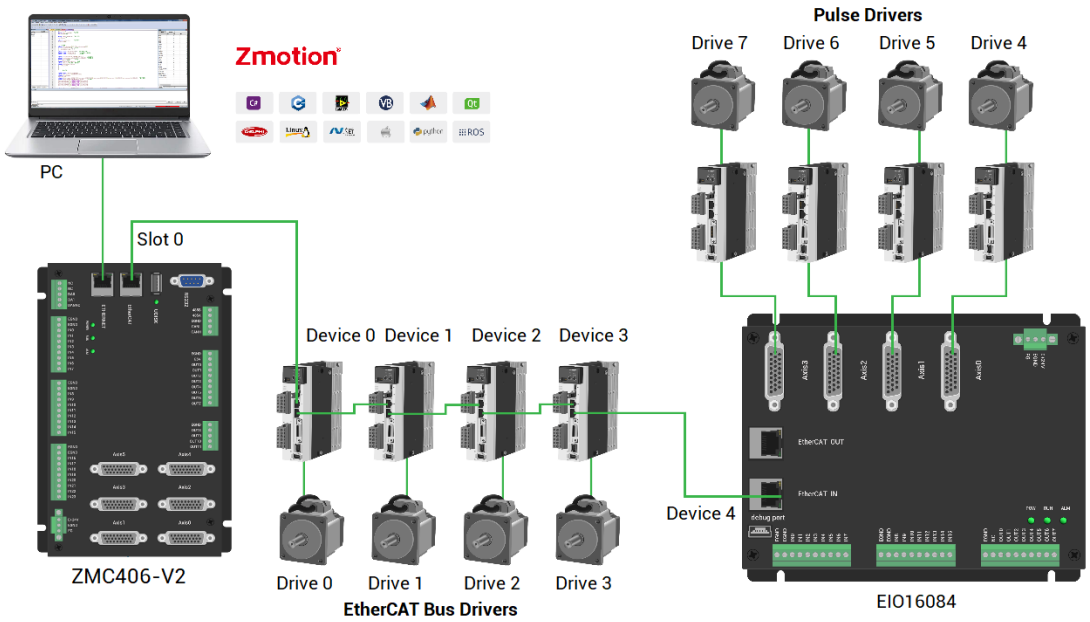
4.2.1. EtherCAT Bus Expansion Wiring

After the expansion wiring is completed, each EIO expansion module does not need to develop again. It only needs to manually configure the unique IO address and axis address in the EtherCAT master controller, and it can be accessed after the configuration is completed.

The IO address number is set through the bus command NODE_IO, and the program on the controller can access the resources on the expansion module only through the IO number. The configuration of the axis address uses the AXIS_ADDRESS command to map axis number, and when the binding is completed, specify the axis number through the BASE or AXIS command.

When wiring, pay attention that EtherCAT IN is connected to the upper-level module, and EtherCAT OUT is connected to the lower-level module. The IN and OUT ports cannot be mixed.

EIO expansion module wiring reference example:



Involved number concepts in above figure are as follows: the bus-related command parameters will use the following numbers:

Slot number (slot):

The slot number refers to the number of the bus interface on the controller, and the slot number of the EtherCAT bus is 0.

Device number (node):

The device number refers to the number of all devices connected to a slot. It starts from 0 and is automatically numbered according to the connection sequence of the devices on the bus. You can view the total number of devices connected to the bus through the NODE_COUNT(slot) command.

Drive number:

The controller will automatically identify the drive on the slot, and the number starts from 0, and the number is automatically numbered according to the connection sequence of the drive on the bus.

The drive number is different from the device number. Only the drive device number on the slot is assigned, and other devices are ignored. The drive number will be used when mapping the axis number.

4.2.2. EtherCAT Bus Expansion Resource Mapping

→ IO Mapping:

The program on the controller can access the resources on the expansion module only through the IO number. The IO number of the EtherCAT bus expansion module is set through the bus command NODE_IO, and the input and output are configured at the same time.

When IO mapping, first check the maximum IO number of the controller itself (including the external IO interface and the interface in the pulse axis), and then use the command to set.

If the extended IO coincides with the IO number of the controller itself, the two will work at the same time, so the mapped number of the IO mapping must not be repeated in the entire control system.

IO mapping syntax:

NODE_ IO(slot, node) = iobase

slot: slot number, 0-default

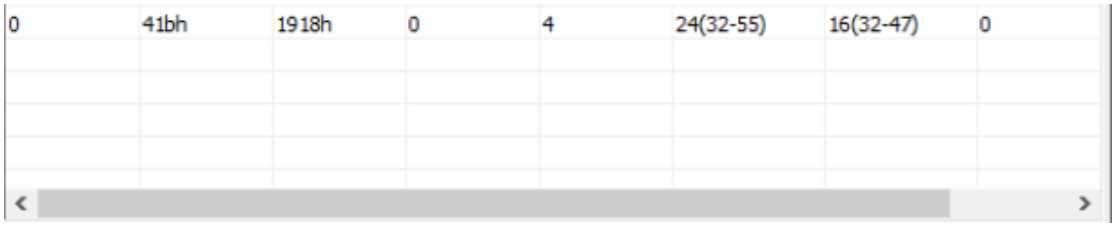
node: device number, starting from 0

iobase : mapping the IO start number, the setting result will only be a multiple of 8

Example:

NODE_IO(0,0)=32 'set the IO start number of slot 0 interface device 0 to 32

If device 0 is EIO16084, after configuration according to the above syntax, the IO numbers corresponding to input IN0-15 are 32-47 in turn, the general input port numbers in the axis interface are 48-55, and the drive alarm inputs of axes AXIS 0-3 are 48-51 respectively. The IO numbers corresponding to the output OUT0-7 are 32-39 in sequence, the general output port numbers in the axis interface are 40-47, and the drive enable outputs of the axes AXIS 0-3 are 40-43 respectively.



→ AXIS Mapping:

Before using the axis of the expansion module, you need to use the AXIS_ADDRESS command to map the axis number, and the axis mapping also needs to pay attention to the axis number of the entire system cannot be repeated. The mapping syntax of the EIO series extended axis is the same as that of the bus driver.

Axis mapping syntax:

AXIS_ADDRESS(axis number)=(slot number<<16)+driver number+1

Example:

AXIS_ADDRESS(0)=(0<<16)+0+1

'the first drive on the EtherCAT bus, drive number 0, bound as axis 0

AXIS_ADDRESS(1)=(0<<16)+1+1

'the second drive on the EtherCAT bus, drive number 1, bound as axis 1

If the first node is EIO16084, and EIO16084 is connected to drive, then driver 0 here is the first pulse driver connected to EIO16084, otherwise it is the EtherCAT driver.

Chapter V Programming

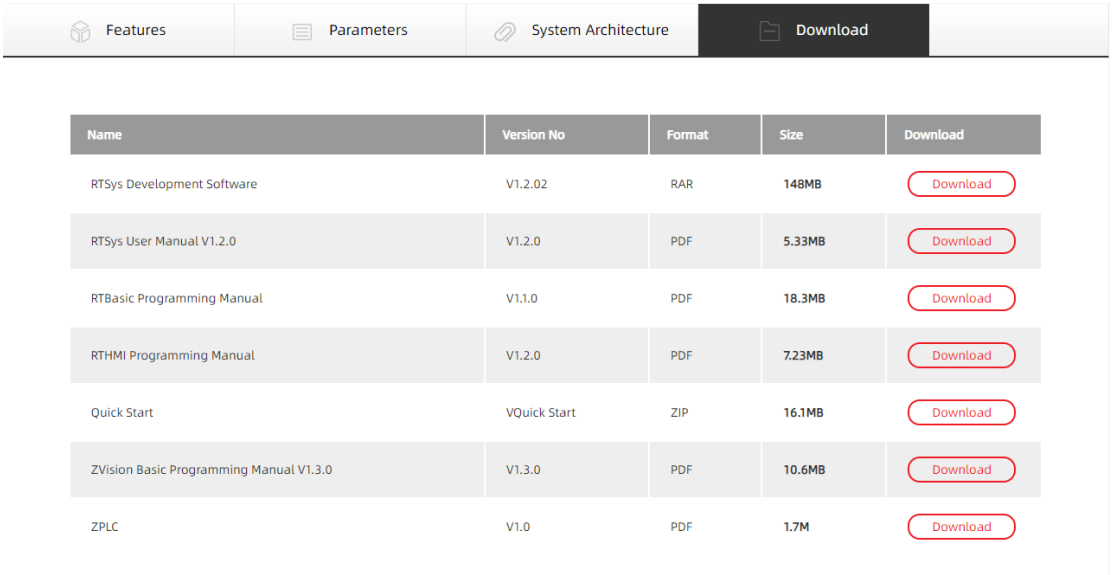
5.1. Program in RTSys Software

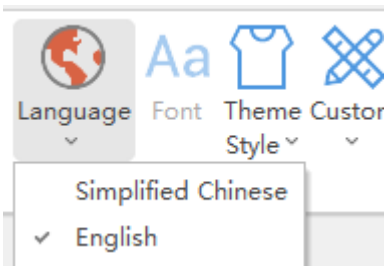
RTSys is a PC-side program development, debugging and diagnostic software for the Zmotion motion controllers. Through it, users can easily edit and configure the controller program, quickly develop applications, diagnose system operating parameters in real time, and debug the running program in real time. What's more, it supports Chinese and English bilingual environments.

In RTSys, there are 4 programming languages for motion control development, Basic, PLC, HMI and C language, they can run multi-tasks among them, especially for Basic, multi-task running can be achieved separately, hybrid programming is also OK with PLC, HMI and C language.

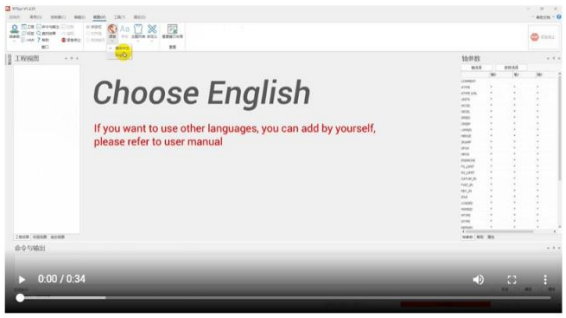
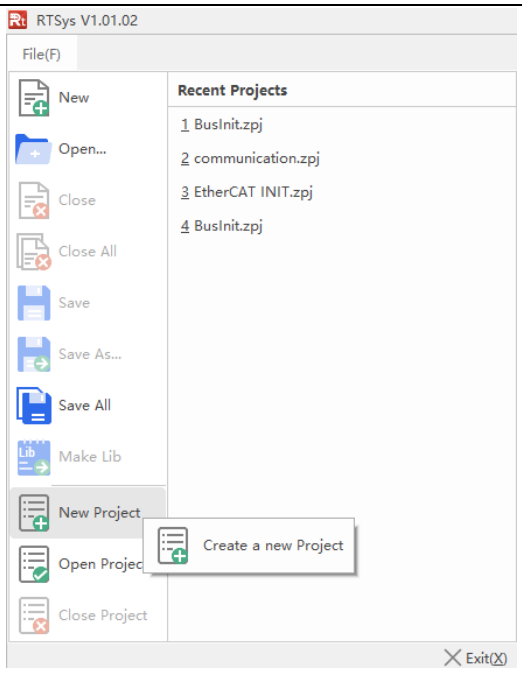
RTSys Downloading Address: https://www.zmotionglobal.com/pro_info_282.html

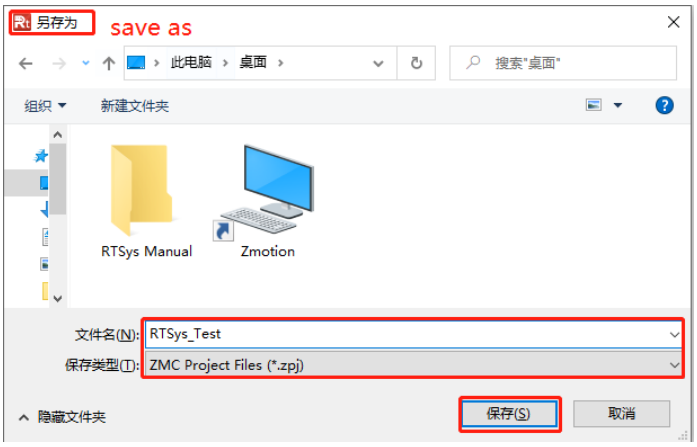
And related manuals can be found in "Download":

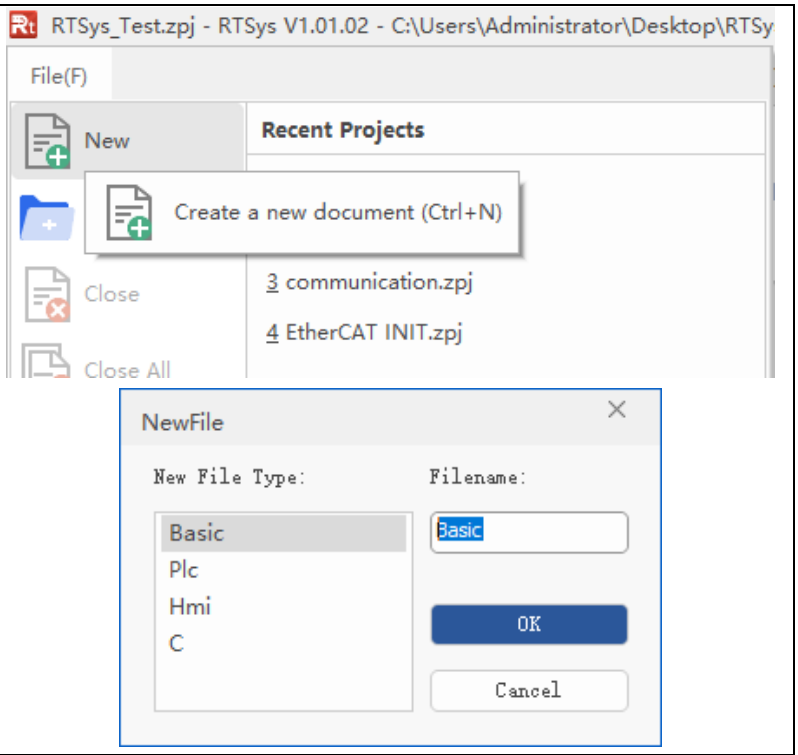
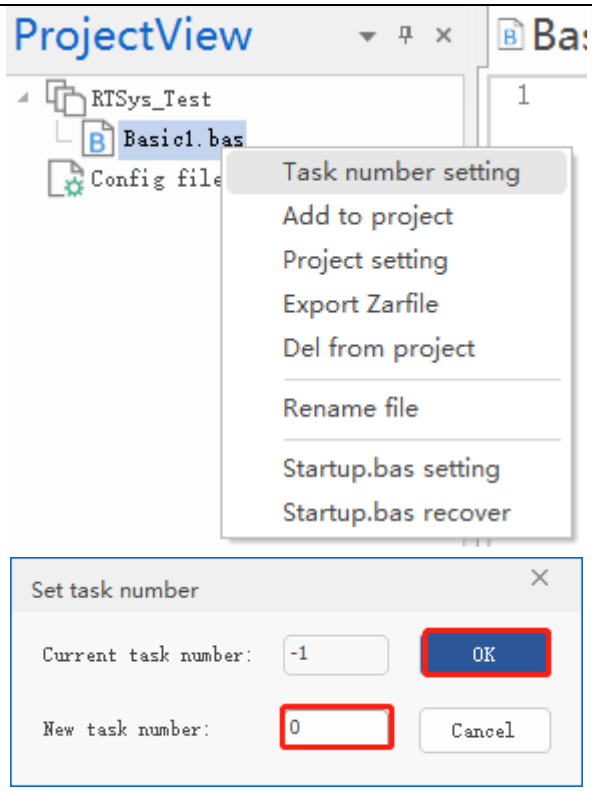


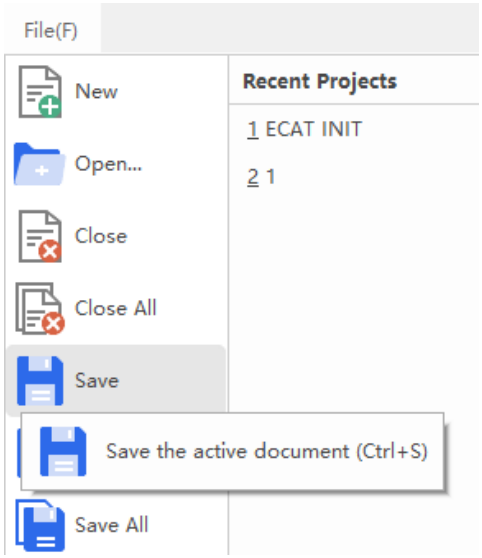
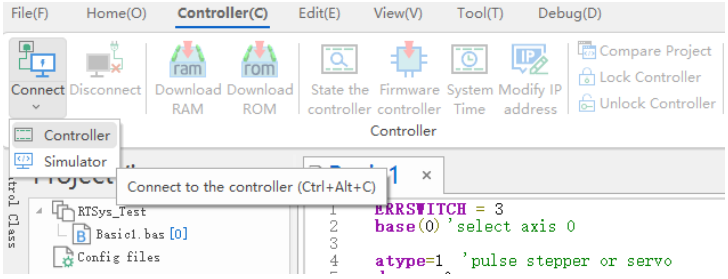
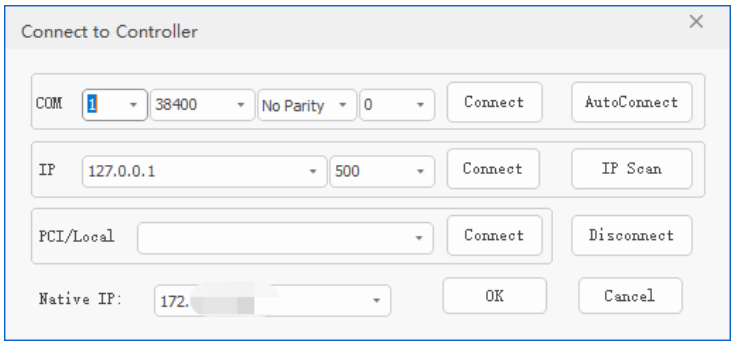
Step	Operations	Display Interface
1	Switch the Language: "Language" – "English", then there will pop	

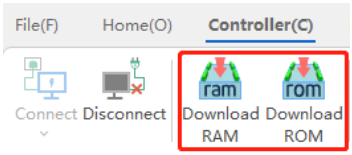
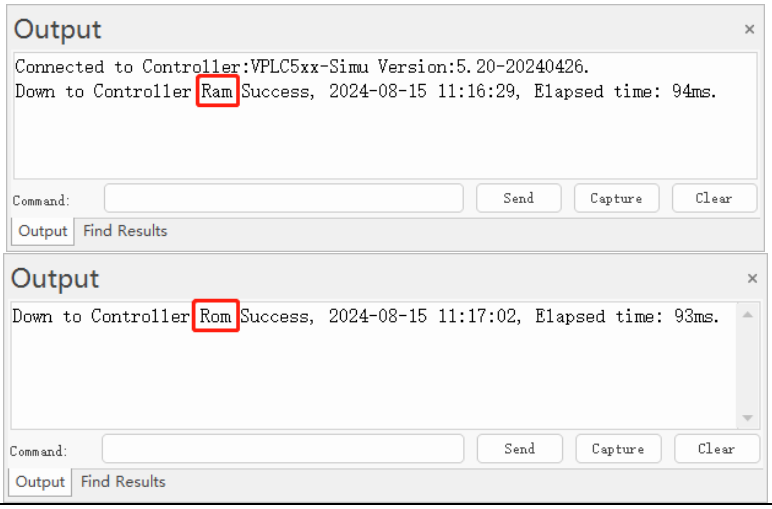
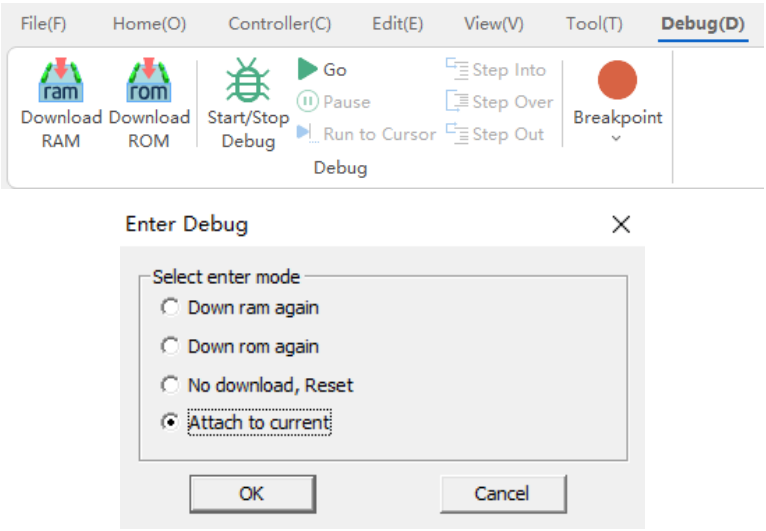
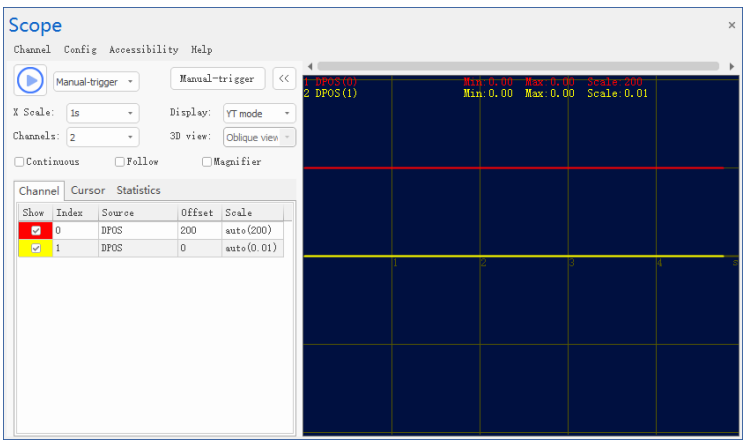
<table>
<tr>
<td></td>
<td>up one window, click OK, and restart it.</td>
<td>Language Switch Video Showing:

E. How to Switch the Language
Find "视图" (the fourth one in the above menu), then find the "语言", choose English, restart RTSys. Enligsh RTSys will take effect when opened again.
 
</td>
</tr>
<tr>
<td>2</td>
<td>New Project: “File” – “New Project”, Save as window will pop up, then enter file name, save the project file with suffix “zpj.”.</td>
<td> 

 
</td>
</tr>
</table>

3	New File: "File" – "New File", select file type to build, here select Basic, click "OK".	
4	Set Auto Run No.: right click the file, open task number setting window, enter task No., which can be any + value, no priority, but not the same.	

5	Save File: edit the program in program editing window, click "save", new built file will be saved under "zpj." project automatically. "Save all" means all files under this project will be saved.	
6	Connection: Click "controller – connect", if no controller, select connect to simulator.	
	Then, "connect to controller" window will pop up, you can select serial port or net port to connect, select matched serial port parameters or net port IP address, then click "connect".	
7	Download Program into	● **RAM:** it will not save when power off. ● **ROM:** it will save data when power off, and when the program

	Controller: "Ram/Rom" – "download RAM / download ROM", if it is successful, there is print indication, at the same time, program is downloaded into controller and runs automatically.	is connected to controller again, running according to task No.  
8	Debug: "Debug" – "Start/Stop Debug" to call "Task" and "Watch" window, because it was downloaded before, here select "Attach the current".	
9	Scope function: Click "View" – "Scope" to open oscilloscope. It can capture needed data, for debugging.	

Notes:

- When opening an project, choose to open the zpj file of the project. If only the Bas file is opened, the program cannot be downloaded to the controller.
- When the project is not created, only the Bas file cannot be downloaded to the controller.
- The number 0 in automatic operation represents the task number, and the program runs with task 0, and the task number has no priority.
- If no task number is set for the files in the entire project, when downloading to the controller, the system prompts the following message WARN: no program set autorun

5.2. Upgrade Controller Firmware

Firmware upgrade can be achieved by downloading zfm firmware package in RTSys. zfm file is the firmware upgrade package of controller, please select corresponding firmware because different models are with different packages, please contact manufacturer).

How to update:

a. Open ZDevelop / RTSys software, then click "controller – connect", find PCI/LOCAL method, click "connect". If connected, there will be "Connected to Controller: PCIE464 Version: 4.93 – 20231220." In "output" window.

b. Click "controller – state the controller", find basic info, then current software version can be checked.

c. Click "controller – update firmware", current controller model and software version can be viewed.

d. Click "browse", and select saved firmware file, click "update", then one window will pop up, please click "ok".

e. After that, "connect to controller" window appears again, and please select "PCI/Local" again, and click "connect".

f. When connection is successful, "firmware update" interface is shown. Now

system enters ZBIOS state, please click “update” again.

g. When it is loaded, “firmware update” window disappears, now in output window, it shows “Update firmware to Controller Success”.

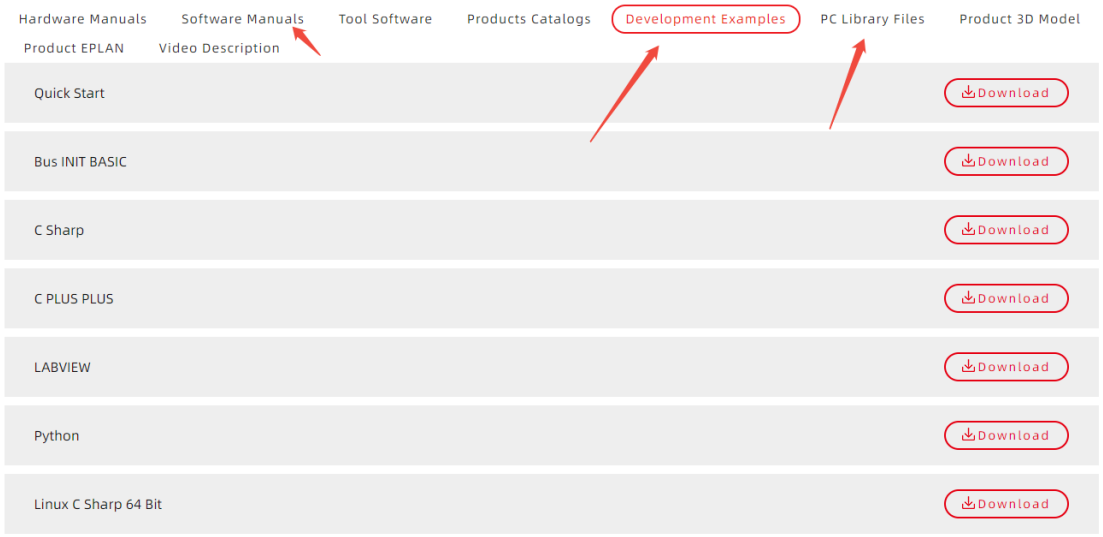
h. Do step a and step b again, check whether the firmware is updated or not.

5.3. Program in Host-Computer by PC Languages

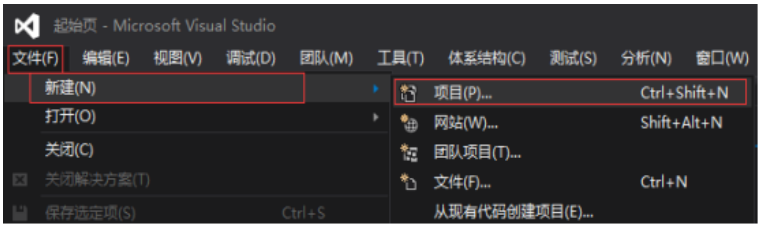
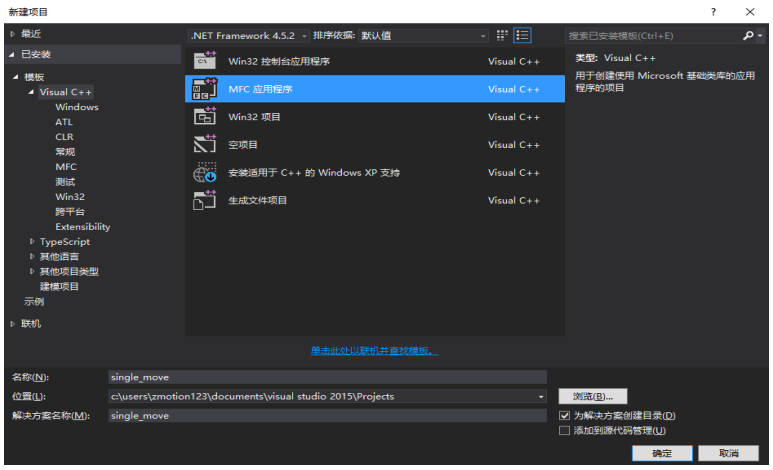
The controller supports development under various operating systems such as windows, linux, Mac, Android, and wince, and provides dll libraries in various environments such as vc, c#, vb.net, and labview, as shown in the figure below. PC software programming refers to "Zmotion PC Function Library Programming Manual".

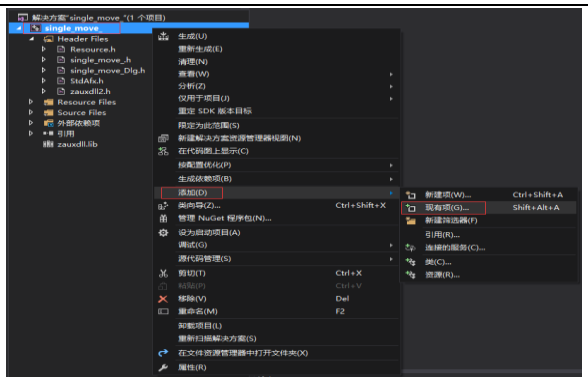
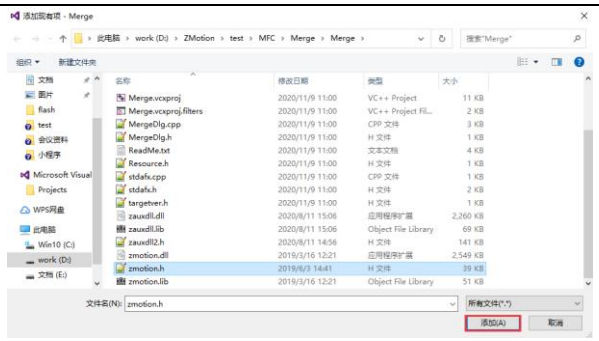
The program developed using the PC software cannot be downloaded to the controller, and it is connected to the controller through the dll dynamic library. The dll library needs to be added to the header file and declared during development.

- Get PC library file, example: https://www.zmotionglobal.com/download_list_17.html



The c++ project development process in VS is as follows:

Step	Operations	Display Interface
1	Open VS, click “File” – “New” – “Project”.	
2	Select development language as “Visual C++” and the select program type as “MFC application type”.	
3	Select “Based on basic box”, click “next” or “finish”	
4	Find C++ function library provided by manufacturer. Routine is below (64-bit library)	
5	Copy all DLL related library files under the above path to the newly created project.	

<table>
<tr><td rowspan="2">6</td><td rowspan="2">Add a static library and related header files to the project. Static library: zauxdll.lib, zmotion.lib
Related header files: zauxdll2.h, zmotion.h</td><td>1) Right-click the header file first, and then select: "Add" → "Existing Item".</td><td>  </td></tr>
<tr><td>2) Add static libraries and related header files in sequence in the pop-up window.</td><td>  </td></tr>
<tr><td>7</td><td>Declare the relevant header files and define the controller connection handle, so far the project is newly created.</td><td colspan="2">

```
// single_move_Dlg.cpp : implementation file
//

#include "stdafx.h"
#include "single_move_.h"
#include "single_move_Dlg.h"
#include "zauxdll2.h"

#ifdef _DEBUG
#define new DEBUG_NEW
#undef THIS_FILE
static char THIS_FILE[] = __FILE__;
#endif

/////////////////////////////////////////////////////////////////////////////
// CSingle_move_Dlg dialog

ZMC_HANDLE      g_handle = NULL;            //控制器链接句柄
```

</td></tr>
</table>

Chapter VI Operation and Maintain

The correct operation and maintenance of the device can not only guarantee and extend the life cycle of the equipment itself, but also take technical management measures according to the pre-specified plan or the corresponding technical conditions to prevent equipment performance degradation or reduce the probability of equipment failure.

6.1. Regular Inspection and Maintenance

The working environment has an impact on the device. Therefore, it is usually inspected regularly based on the inspection cycle of 6 months to 1 year. The inspection cycle of the device can be appropriately adjusted according to the surrounding environment to make it work within the specified standard environment.

Check item	Check content	Inspection standards
power supply	Check whether the voltage is rated	DC 24V (-5%~5%)
surroundings	Whether the ambient temperature is within the specified range (when installed in the cabinet, the temperature inside the cabinet is the ambient temperature)	-10°C - 55°C
	Whether the ambient humidity is within the specified range (when installed in the cabinet, the humidity in the cabinet is the ambient humidity)	10%-95% non-condensing
	Is there direct sunlight	No
	With or without droplets of water, oil, chemicals, etc.	No
	Whether there is dust, salt, iron filings, dirt	No
	Whether there is corrosive gas	No
	Whether there are flammable and	No

	explosive gases or articles	
	Whether the device is subjected to vibration or shock	Should be within the range of vibration resistance and impact resistance
	Is the heat dissipation good	Keep good ventilation and heat dissipation
Installation and Wiring Status	Whether the basic unit and the expansion unit are installed firmly	The mounting screws should be tightened without loosening
	Whether the connecting cables of the basic unit and the expansion unit are fully inserted	The connection cable cannot be loosened
	Are the screws of the external wiring loose	Screws should be tightened without loosening
	Whether the cable is damaged, aged, cracked	The cable must not have any abnormal appearance

6.2. Common Problems & Solutions

Problems	Suggestions
Motor does not rotate.	1. Check whether the ATYPE of the controller is correct. 2. Check whether hardware position limit, software position limit, alarm signal work, and whether axis states are normal. 3. Check whether motor is enabled successfully. 4. Confirm whether pulse amount UNITS and speed values are suitable. If there is the encoder feedback, check whether MPOS changes. 5. Check whether pulse mode and pulse mode of drive are matched. 6. Check whether alarm is produced on motion controller station or drive station. 7. Check whether the wiring is correct. 8. Confirm whether controller sends pulses normally.

The position limit signal is invalid.	1. Check whether the limit sensor is working normally, and whether the "input" view can watch the signal change of the limit sensor. 2. Check whether the mapping of the limit switch is correct. 3. Check whether the limit sensor is connected to the common terminal of the controller.
No signal comes to the input.	1. Check whether the limit sensor is working normally, and whether the "input" view can watch the signal change of the limit sensor. 2. Check whether the mapping of the limit switch is correct. 3. Check whether the limit sensor is connected to the common terminal of the controller.
The output does not work.	1. Check whether IO power is needed. 2. Check whether the output number matches the ID of the IO board.
POWER led is ON, RUN led is OFF.	1. Check whether the power of the power supply is sufficient. At this time, it is best to supply power to the controller alone, and restart the controller after adjustment. 2. Check whether the ALM light flickers regularly (hardware problem).
RUN led is ON, ALM led is ON.	1. Program running error, please check ZDevelop error code, and check application program.
Fail to connect controller to PC through serial port.	1. Check whether the serial port parameters are modified by the running program, you can check all the current serial port configurations through ?*SETCOM. 2. Check whether the serial port parameters of the PC match the controller. 3. Open the device manager and check whether the serial driver of the PC is normal.
CAN expansion module cannot be connected.	1. Check the CAN wiring and power supply circuit, whether the 120 ohm resistor is installed at both

	ends. 2. Check the master-slave configuration, communication speed configuration, etc. 3. Check the DIP switch to see if there are multiple expansion modules with the same ID. 4. Use twisted-pair cables, ground the shielding layer, and use dual power supplies for severe interference (the main power supply of the expansion module and the IO power supply are separately powered)
Fail to connect controller to PC through net port.	1. Check IP address of PC, it needs to be at the same segment with controller IP address. 2. Check controller IP address, it can be checked and captured after connection through serial port. 3. When net port led is off, please check wiring. 4. Check whether controller power led POWER and running indicator led RUN are ON normally. 5. Check whether the cable is good quality, change one better cable to try again. 6. Check whether controller IP conflicts with other devices. 7. Check whether controller net port channel ETH are all occupied by other devices, disconnect to other devices, then try again. 8. When there are multiple net cards, don't use other net cards, or change one computer to connect again. 9. Check PC firewall setting. 10. Use “Packet Internet Groper” tool (Ping), check whether controller can be Ping, if it can't, please check physical interface or net cable. 11. Check IP address and MAC address through arp-a.