

Change Pn205 under the Absolute Encoder tab in the Configuration Tool (CT).

Limits | Configuration | I/O | Tuning | Test Move | Function | Absolute Encoder | Hardware | Alarm | Brake | Dual Encoder

**Changes in Red will not take effect until after changes are saved and power is cycled on the machine**

Parameter #	Parameters	Current Value	Units	Min	Max
Pn002.2	Absolute Encoder Usage	0 - Use absolute encoder as absolute encoder			
Pn008.0	Low Battery Voltage Alarm/Warning	0 - Display Alarm for low battery voltage			
<b>Pn205</b>	<b>Multi-Turn Limit Setting</b>	<b>59</b>	<b>Revolut</b>	<b>0</b>	<b>0</b>

For example, if the application uses a 60:1 gear ratio, in the configuration tab of the CT the following parameters are used:

Limits | Configuration | I/O | Tuning | Test Move | Function | Absolute Encoder | Hardware | Alarm | Brake | Dual Encoder

**Rotary Axis Position Calculation**

Machine Cycle

Feed Constant  Units

1 Rev X  $\frac{\text{Feed Constant}}{1 \text{ Rev}}$  X

Gear Ratio  Input =  Position Scale

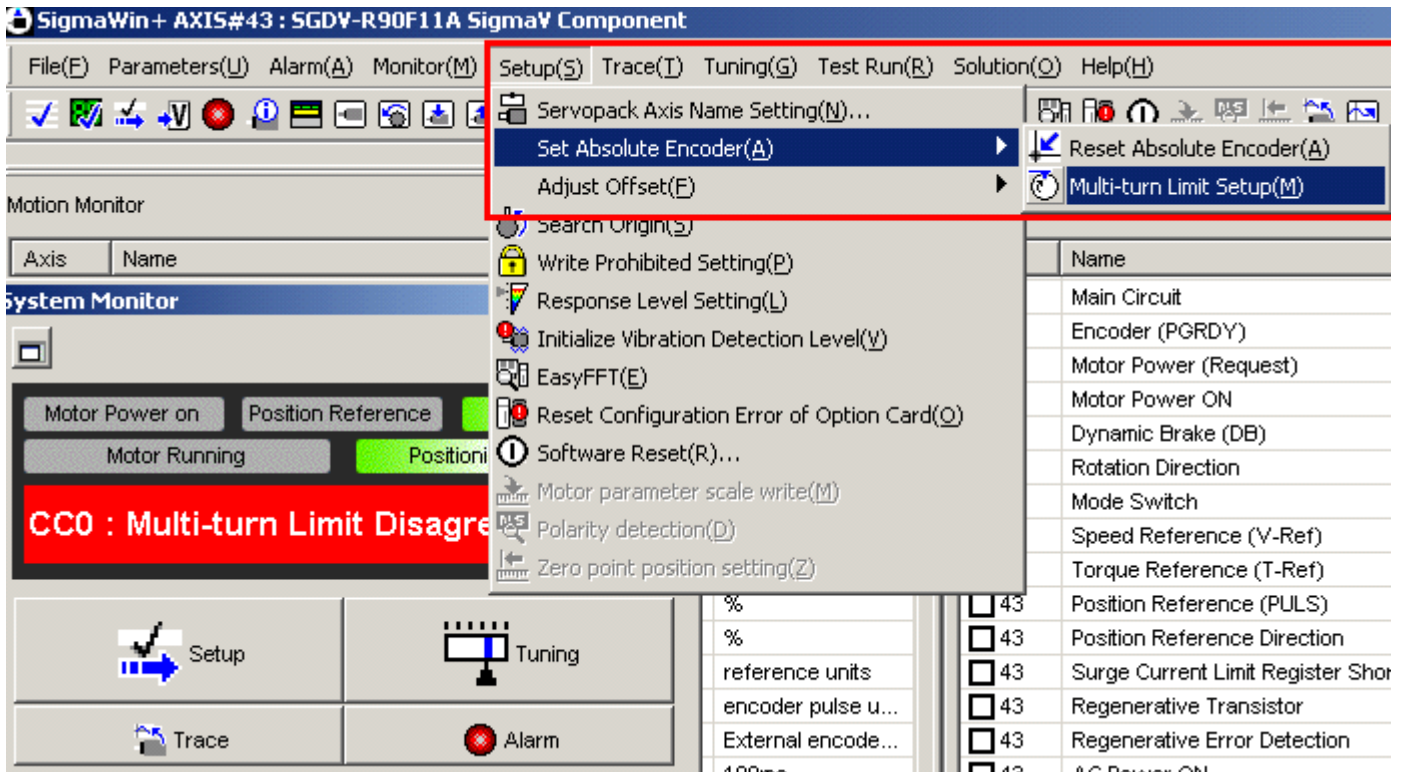
Output

User Units

Parameter #	Parameters	Current Value	Units	Min	Max
1007	Load Type	Rotary		0	1
1016	In Position Window	50	Degrees	1E-05	50000
1017	At Speed Window	50	Degrees/	1E-05	50000
1031	Logical Axis Number	3		1	512

Pn205 will have to be entered as 59 (this is because it is numbered using a zero base system). On saving the configuration and cycling power on the controller, the drive displays ACC0 alarm. In order to clear the multiturn disagreement alarm between the servopack Pn and the encoder, use SigmaWin+.

Connect to the servopack. Under Setup>Set Absolute encoder(A) > Multi-turn Limit Setup (M)



Click to write into the servomotor and cycle control power on the drive.

