a) First (before powering-on the controller and drives), connect the servopacks to the controller using the Mechatrolink II communication cables. Connect a Mechatrolink terminator to each end of the network. Typically connect one terminator on the controller end and a second one on the last servopack connected. This may vary based on the physical layout or other design needs. The controller may be anywhere in the middle of the network. The MP2300Siec controller comes from the factory with one terminator included in the packaging.

Part Numbers:
Cables: JEPMC-W6003-** (** indicates length 0.5m to 50m)
Terminator: JEPMC-W6022 (includes built-in terminating resistance and inductance)

b) Next, turn the rotary dial switch (S1) on each servopack to a unique Mechatrolink address.
Possible Settings: 15 positions from 1 thru F that correspond to address 1-15.

c) Automatic Configuration: Start with the MP2300Siec and servopacks powered off. On SW1 of the controller, turn the "CNFG" DIP switch to the ON position.   Turn on the power to the controller and servopacks to start the automatic configuration sequence. When configuration is complete, the controllers green RDY light will illuminate.

d) Start a New Project using the template for the specific controller in use. Enter into the *Hardware Configuration*(CT) by clicking on the toolbar icon within the MotionWorks IEC software.
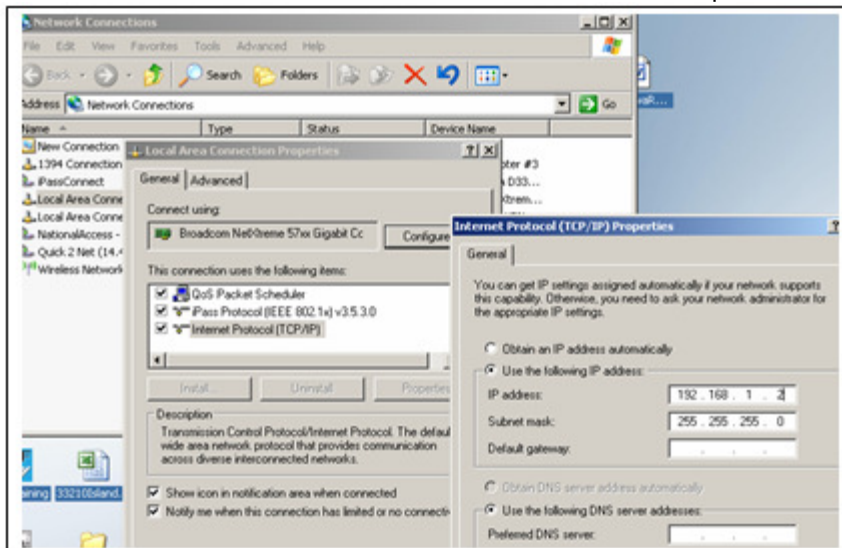

Hardware Configuration Icon -->

e) Connect to the controller using the RJ-45 "Ethernet Link" jack (100 or 10Mbps). If connecting directly to the controller one to one, determine if your PC has the ability to detect and perform auto crossover. Most newer PCs can do this, so simply use a standard patch cable. Otherwise if connecting directly, use a cross-over cable. Using a hub or switch will also work. Verify that the IP address is correct for each computer and controller. Default IP address for all MPiec controllers is "192.168.1.1", so it will be necessary to set a different IP address in your computer within the same subnet (such as 192.168.1.2). To set the IP address on the computer, open the following windows:
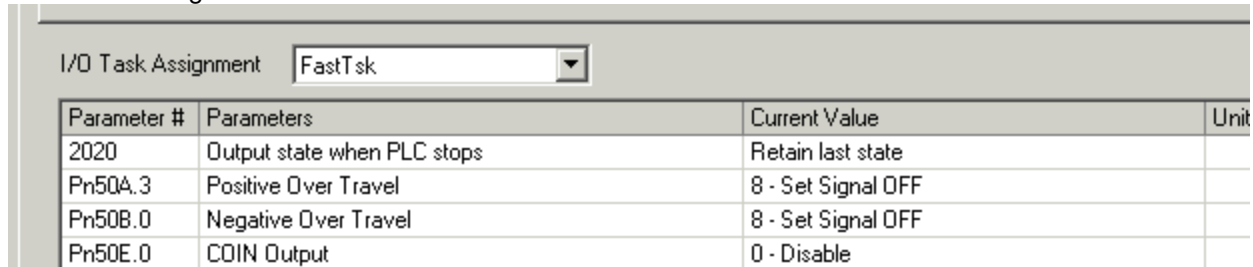1) Network Connections
2) Local Area Connection Properties
3) Internet Protocol (TCP/IP)
4) Properties

then set the IP address and subnet mask. Below is an example:

f) Connect to the controller using the Hardware Configuration. Confirm the IP address of the controller shows properly in the address fields and connect ONLINE. A confirmation message box will ask to use the configuration found during auto discovery. Click Yes.

g) If the motor is not connected to the load and the Positive / Negative Over-Travel switches are not wired to the CN1 connector on the servo, then it will be necessary to turn off the P-OT and N-OT inputs in order to jog the servo from the controller. P-OT / N-OT settings are located on the I/O tab of each servopack. Choose a setting of 8 to disable the end of travel limit.

I/O Task Assignment   FastTsk

Parameter #	Parameters	Current Value	Unit
2020	Output state when PLC stops	Retain last state	
Pn50A.3	Positive Over Travel	8 - Set Signal OFF	
Pn50B.0	Negative Over Travel	8 - Set Signal OFF	
Pn50E.0	COIN Output	0 - Disable	

h) Save the configuration while Online and cycle power on the system. The axes are now configured for use.

i) It is recommended to leave the "CNFG" DIP switch in the ON position.

Additional Resources:
There is also a quick start video, and a Hardware Configuration manual that will provide more a detailed account of the configuration process.

Quick Start Video:
http://www.yaskawa.com/site/dmcontrol.nsf/SearchV/86256EC30069B63486257475006C700D?OpenDocument&Source=SearchResultPage

Configuration Manual:
http://www.yaskawa.com/site/dmcontrol.nsf/SearchV/86256EC30069B6348625743B006CDEAB?OpenDocument&Source=SearchResultPage