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NI-9144

GETTING STARTED

NI SMD-7613/7614/7615/7616 Stepper Drives and NI 9512 C Series Modules

This document explains how to install and configure the NI SMD-7613/4/5/6 stepper drives for use with the NI 9512 C Series drive interface module.

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What You Need to Get Started

You need the following items to get started.

Hardware

- ☐ NI 9512 C Series stepper drive interface module
- ☐ NI Real-Time controller
 - CompactRIO controller and chassis that support the RIO Scan Interface



Tip To determine if your controller and chassis support the RIO Scan Interface go to ni.com/info and enter the Info Code `rdsoftwareversion`.

or

- NI 9146, 9147, 9148, or 9149 Ethernet RIO Expansion Chassis.

or

- NI 9144 distributed chassis and compatible RT controller

- ☐ +24 V power supply (such as the NI PS-15) for the CompactRIO controller (NI part number 781093-01)
- ☐ Separate +24 V power supply for the NI 9512 (such as the NI PS-15)
- ☐ NI PS-12 or NI PS-13 power supply for the NI SMD-7613/4/5/6
- ☐ NI SMD-7613/4/5/6 stepper drive
- ☐ NI or third-party stepper motor



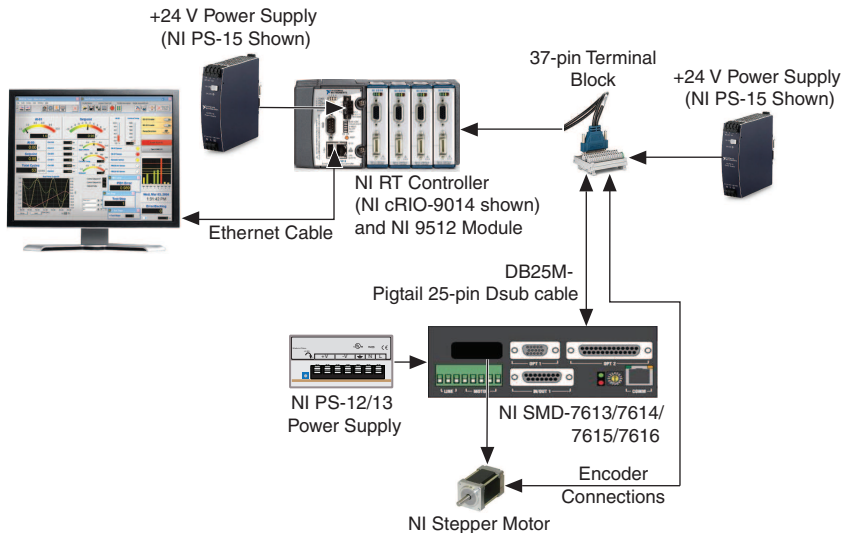
Note NI offers stepper motors matched to the NI SMD-7613/4/5/6. Refer to ni.com/motion for motor options. National Instruments highly recommends using these motors for the best user experience.

- ☐ (Optional) ENC-7740 encoder for ST17 motors (NI part number 748991-01) or ENC-7741 encoder for ST23 motors (NI part number 748992-01)
- ☐ Encoder cable to connect the encoder to the NI 951x terminal block (NI part number 783661-10)
- ☐ Ethernet connection and cable for the CompactRIO controller
- ☐ DB25M-Pigtail 25-pin Dsub cable (NI Part Number 190911-04)
- ☐ NI 951x Cable and Terminal Block bundle (NI part number 780553-01)

Software

- ☐ LabVIEW 2010 (minimum)
- ☐ LabVIEW 2010 Real-Time Module (minimum)
- ☐ LabVIEW 2010 f1 NI SoftMotion Module (minimum)
- ☐ NI-RIO 3.5.1 (minimum)

Figure 1. NI 9512 to NI SMD-7613/74/5/6 Connections



Hardware Installation and Configuration

This section covers the hardware setup for the Real Time system, NI 9512 C Series module, and NI SMD-7613/4/5/6 stepper drive.

Step 1: Set Up the Real Time System

Complete the following steps to set up the Real Time system depending on your hardware.

1. Refer to the Getting Started guide included with the Real-Time controller to assemble it, connect it to power, discover it on the network, and install the software in NI MAX.
2. Install the NI 9512 module in an available slot that supports High Speed Interface (HSI) in your chassis.



Note Older model chassis, such as cRIO-902x, cRIO-907x, cRIO-908x, NI 9144, and NI 9148, have HSI support on slots 1 through 4. Refer to your chassis documentation for more information about HSI slot support.

Step 2: Connect the NI 9512 to the 37-Pin Terminal Block

1. Connect the MDR and DSUB connectors on the NI 951x Y-cable to the MDR and DSUB connectors on the NI 9512 module.
2. Connect the 37-pin DSUB to the DSUB connector on the NI 951x terminal block.

Figure 2. NI 9512 37-Pin Terminal Block Pin Assignments

Forward Limit					Digital Output 1 [†]
Home					Reverse Limit
COM					Reserved
Digital Input 0					V _{sup}
COM					Reserved
Encoder 0 Index+					COM
Encoder 0 Index-					Encoder 0 Phase A+
COM					Encoder 0 Phase A-
+5V OUT					Encoder 0 Phase B+
Position Compare					Position Capture
Reserved					Encoder 0 Phase B-
Reserved					Reserved
Digital Output 0 [†]					Reserved
V _{sup} [†]					COM [†]
Digital Input 1 [†]					Drive Enable [†]
Direction (CCW)+ [†]					Digital Input 3 [†]
COM [†]					Direction (CCW)- [†]
Step (CW)+ [†]					Digital Input 2 [†]
Shield					Step (CW)- [†]

[†] Indicates DSUB connector signals.

Step 3: Connect the 37-Pin Terminal Block to the +24 V Power Supply



Note Do not plug in or turn on the power supply until after you complete [Step 10: Power on the Drive and Verify Connections](#).

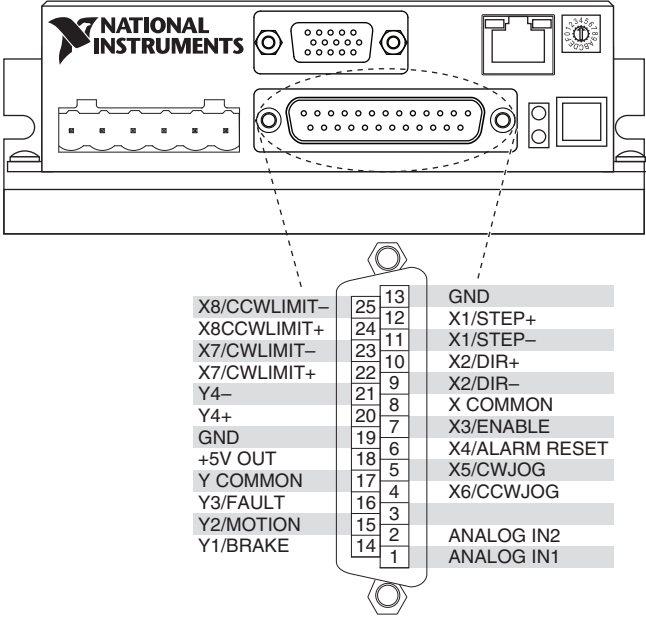
1. Connect the V+ terminal from the 24 V power supply to one of the two V_{sup} inputs on the 37-pin terminal block. The 37-pin terminal block provides a V_{sup} input for the NI 9512 on pin 14 and pin 22.
2. Connect the V- terminal from the 24 V power supply to one of the COM terminals on the 37-pin terminal block. The 37-pin terminal block provides COM on pins 3, 5, 8, 17, 24, and 32.

Step 4: Connect the Drive Command Signals

Complete the following steps to connect the Drive Command signals to the NI 9512 terminal block by using the DB25M- Pigtail 25-pin Dsub cable (NI Part Number 190911-04).

1. Connect the SMD-7613/4/5/6 STEP+ (pin 10) and DIR+ (pin 12) terminals to the 37-pin terminal block +5V OUT terminal (pin 9).
2. Connect the SMD-7613/4/5/6 STEP- (pin 11) terminal to the 37-pin terminal block Step (CW)+ terminal (pin 18).
3. Connect the SMD-7613/4/5/6 DIR- (pin 9) terminal to the 37-pin terminal block Direction (CCW)+ terminal (pin 16).

Figure 3. SMD-7613/4/5/6 Drive Command and I/O Connector



Step 5: Connect the Drive Enable Signal

The Drive Enable signal controls the enable function of the drive. To use this signal, connect the SMD-7613/4/5/6 X3/ENABLE terminal (pin 7) to the 37-pin terminal block Drive Enable terminal (pin 33).

Step 6: (Optional) Connect the Encoder Signals

If your motor includes an encoder, complete the following steps to connect the encoder to the NI 9512 by wiring the encoder cable to the 37-pin terminal block:



Note SMD-7614 and SMD-7616 include encoder inputs. The encoder signals must be connected to the NI 9512 for SoftMotion to have access to the Encoder Feedback.

1. If an NI Encoder is being used, connect the appropriate end of the encoder cable (NI part number 783661-10) to the encoder.
2. Connect the encoder wires to the 37-pin terminal block as indicated in Table 1.
3. Insulate any unused wires.

Table 1. NI SMD-7613/4/5/6 to 37-Pin Terminal Block Connections

Encoder Signal Name	Encoder Cable Wire Color	37-Pin Terminal Block Pin Number	37-Pin Terminal Block Signal Name
CH A	blue	25	Encoder 0 Phase A+
CH A-	blue/white	26	Encoder 0 Phase A-
CH B	yellow	27	Encoder 0 Phase B+
CH B-	yellow/white	29	Encoder 0 Phase B-
INDEX	orange	6	Encoder 0 Index+
INDEX-	orange/white	7	Encoder 0 Index-
GND	black	8	COM
+Vcc	red	9	+5V OUT

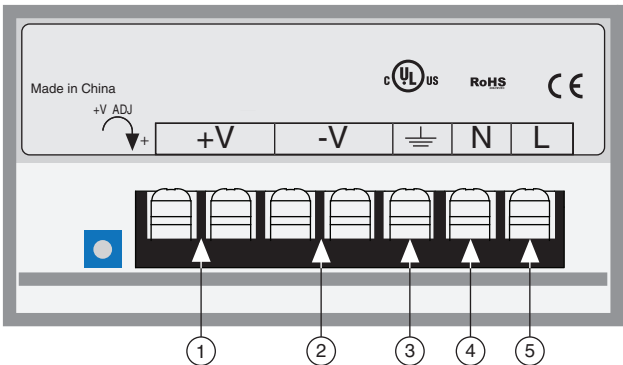
Step 7: Connect the NI PS-12/13 Power Supply to the NI SMD-7613/4/5/6



Note Do not plug in or turn on the power supply until after you complete [Step 10: Power on the Drive and Verify Connections](#).

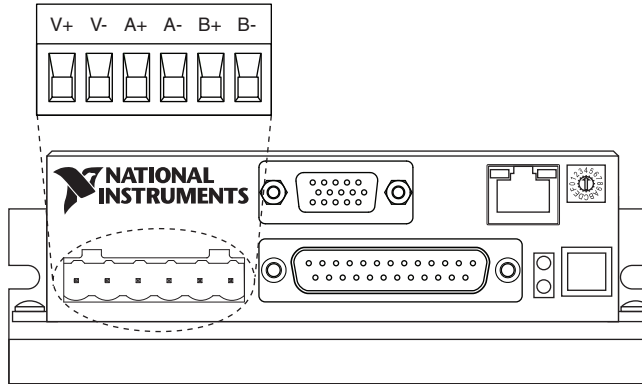
Complete the following steps to connect the power supply to AC input power and to the NI SMD-7613/4/5/6.

Figure 4. NI PS-12/13 Power Supply Terminals



- | | |
|---|--------------------|
| 1 +24 V (NI PS-12) or +48 V (NI PS-13) Output | 4 AC Input Neutral |
| 2 +24 V (NI PS-12) or +48 V (NI PS-13) Ground | 5 AC Input Line |
| 3 AC Input Ground (Protective Earth) | |

Figure 5. SMD-7613/4/5/6 Power and Motor Connector



1. Connect an AC input cable to the line, neutral, and protective earth connectors.
2. Connect the SMD-7613/4/5/6 V+ terminal to the power supply +V connector.
3. Connect the 7613/4/5/6 V- terminal to the power supply -V connector.
4. Connect the SMD-7613/4/5/6 green ground screw to earth ground.
5. Connect the NI 9512 COM to the NI PS-12/13 -V terminal to ensure a common reference.



Note Refer to the *NI SMD-7613/7614/7615/7616 User Manual* on ni.com/manuals for more information about connecting the power supply.

Step 8: Connect the SMD-7613/4/5/6 to the Motor

The drive supports various stepper motors. The connection to the stepper motor depends on the number of leads present. Refer to the following figures to connect your stepper motor.

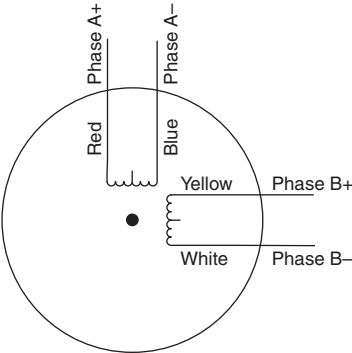


Note Motor wire colors are correct for NI stepper motors compatible with the NI SMD-761x. These wire colors may not match a third-party stepper motor.

Four Lead Motors

Four lead motors can only be configured according to the following diagram.

Figure 6. Four Lead Motor Connection



Six Lead Motors

Six lead motors can be connected in series or center tap.

Figure 7. Six Lead Motor Connected in Series

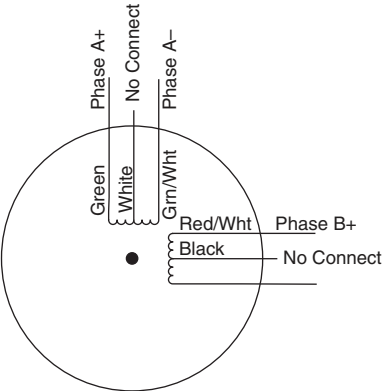
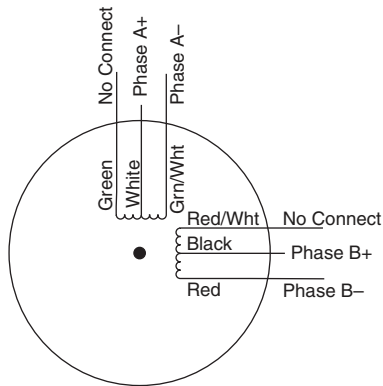


Figure 8. Six Lead Motor Connected in Center Tap



Eight Lead Motors

Eight lead motors can be connected in series or parallel.

Figure 9. Eight Lead Motor Connected in Series

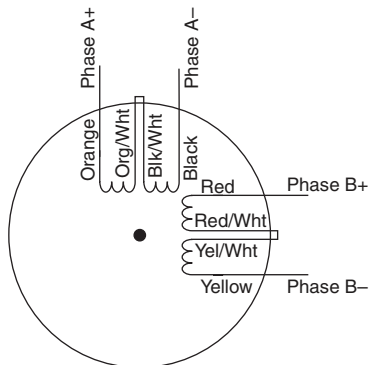
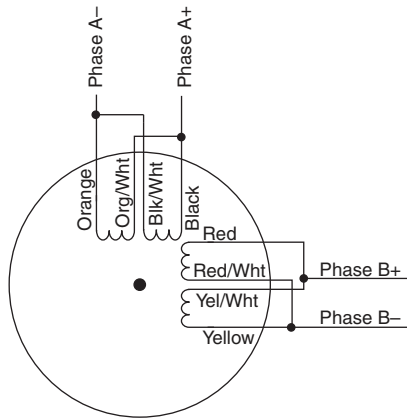


Figure 10. Eight Lead Motor Connected in Parallel



Step 9: Connect the NI SMD-7613/4/5/6 to the Network

1. Connect the NI SMD-7613/4/5/6 to an Ethernet network on the same subnet as the development computer.
2. Set the rotary switch to one of the preset IP addresses or to the F position to configure the drive to use DHCP.



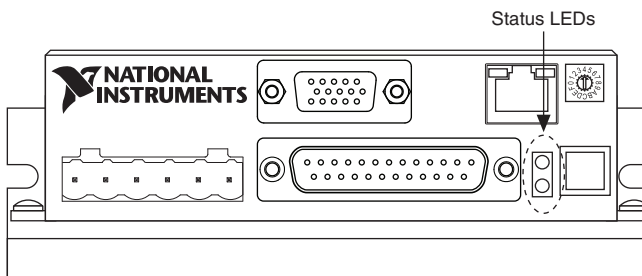
Note This document assumes you have configured the drive for DHCP. For information about other settings refer to the *NI SMD-7613/7614/7615/7616 User Manual* on ni.com/manuals.

Step 10: Power on the Drive and Verify Connections

After all hardware connections have been made complete the following steps to confirm the hardware setup.

1. Turn on all power supplies.
2. Verify that the Drive Status LED on the NI SMD-7613/4/5/6 flashes or is solid green. Figure 11 shows the location of the Drive Status LED.

Figure 11. Drive Status LED Location



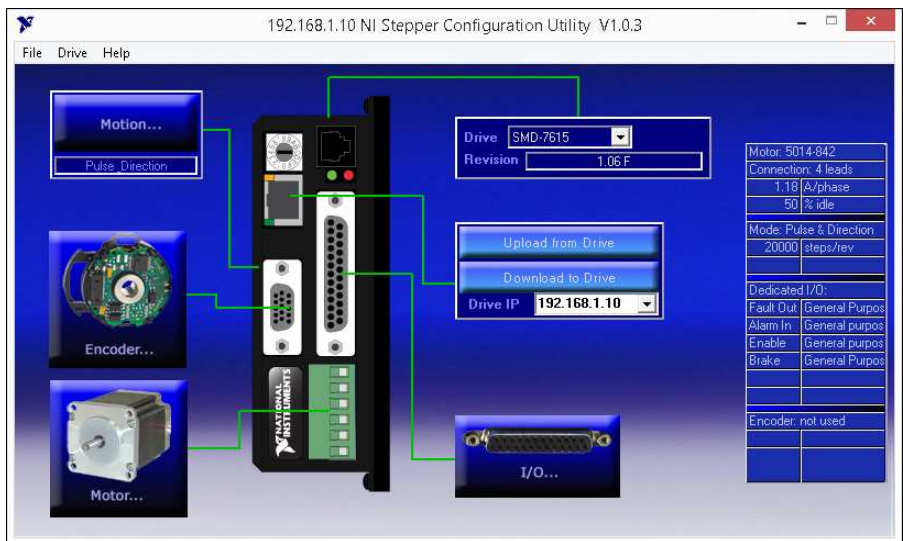
If the Drive Status LED does not flash or turn solid green, turn off all power, verify the connections, and try again. Refer to the [Worldwide Support and Services](#) section for additional tips.

Step 11: Configure the Drive using NI Stepper Configuration Utility

The NI Stepper Configuration Utility allows the drive to be customised for a specific motor. Complete the following steps to customize the motor by using the NI Stepper Configuration Utility.

1. Visit ni.com/downloads to download the NI Stepper Configuration Utility.
2. Install and open the Stepper Configuration Utility on the computer connected to the same network as the drive.

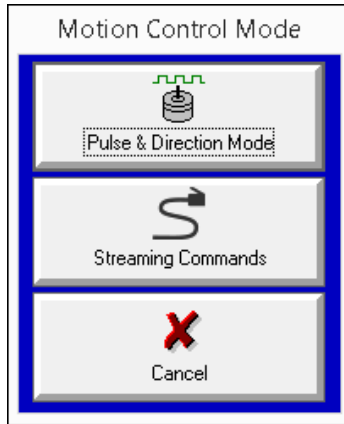
Figure 12. The NI Stepper Configuration Utility Window



3. Enter the IP address of the drive as configured using the rotary switch in the previous steps and click Upload from Drive. This will retrieve the model number of the drive you are using.

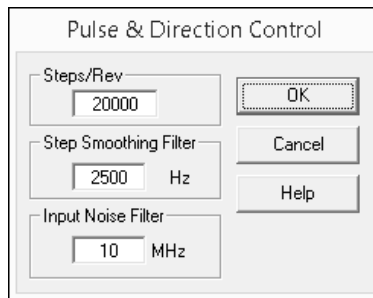
- Click **Motion...** button in the top-left corner. The option to select the Motion Control mode is displayed.

Figure 13. Motion Control Mode



- Click **Pulse & Direction Mode** to program the drive to receive step and direction signals from the NI 9512 module.

Figure 14. The Pulse & Direction Mode window



- In the Pulse & Direction Control window, enter the microstepping resolution in the **Steps/Rev** control. By default, this value is set to **20,000 steps/revolution**. Click **OK**.
- Click **Motor...** button in the bottom-left corner to configure the motor connected to the drive.

Figure 15. The Motor Configuration window

The Motor Configuration window is titled "Motor". It features two radio buttons at the top: "Standard motor" (selected) and "Custom motor". The "Standard motor" option has a dropdown menu showing "ST17-1". The "Custom motor" option has a "Define Custom Motor..." button. To the right of these are "Cancel" and "OK" buttons. Below the radio buttons are three sliders: "Running Current" (set to 1.60 amps), "Idle Current" (set to 50 % (0.80 A)), and "Idle Current Delay" (set to 0.40 secs). To the right of these sliders is a "Motor Specs" section with a table of values: Connection (parallel), Holding Torque (31.4 oz in), Rated Current (1.6 A), Rotor Inertia (35.0 g cm2), Smoothing Gain (500), and Phase (-100). Below the "Motor Specs" section is a "Load Inertia" section with two radio buttons: "Standard" (selected) and "Custom". The "Standard" option has a dropdown menu showing ".00000 g cm2". The "Custom" option has a text box showing "1.0 X rotor inertia". At the bottom of the window are two checkboxes: "Electronic Damping/Anti-resonance Off" and "Waveform Smoothing Off".

Motor Specs	
Connection	parallel
Holding Torque	31.4 oz in
Rated Current	1.6 A
Rotor Inertia	35.0 g cm2
Smoothing Gain	500
Phase	-100

Load Inertia	
Standard	.00000 g cm2
Custom	1.0 X rotor inertia

8. If NI's ST-series stepper motor is being used, select **Standard motor** and use the dropdown menu to select the model.
9. If a third-party stepper motor is being used, select **Custom motor** then click **Define Custom Motor...** to enter the rated current, holding torque, and rotor inertia of the motor.
10. Configure the remaining parameters (Running Current, Idle Current, Idle Current Delay, and the Load Inertia) for your application. Refer to the **Help** menu for full descriptions of these parameters.
11. When configuration is complete, click **Download to Drive** to save these settings to the drive.

Software Installation and Configuration

This section covers installing and configuring software for the NI 9512 C Series module.



Note These instructions assume you have installed all required software from the *What You Need to Get Started* section on your development machine.

Step 1: Install Software on and Configure the NI RT Controller

Complete the following steps to configure the controller and install software on it.

1. Launch Measurement & Automation Explorer (MAX) on the development computer by clicking the MAX icon on the desktop, or by selecting **Start»All Programs»National Instruments»NI MAX**.
2. Select the controller under **Remote Systems** in the **Configuration** pane. If you do not see the controller, you may need to disable the firewall on the development computer.
3. Verify that the **Serial Number** in the **Identification** section matches the serial number on the device.
4. Expand the controller item in the tree, right-click **Software**, and select **Add/Remove Software**.
5. Select a recommended software set that includes NI-RIO 3.5.1 (minimum) with NI Scan Engine Support.
6. Click **Next** and enable the following add-ons:
 - LabVIEW SoftMotion Module
 - NI Industrial Communications for EtherCAT if using the NI 9144.
7. Click **Next** to install the selected software on the controller. Click **Help** if you need information about installing recommended software sets.
8. Close MAX.

Step 2: Create a Project and add NI RT Controller

Complete the following steps to create a LabVIEW project.

1. Launch LabVIEW by selecting **Start»All Programs»National Instruments»LabVIEW**.
2. Click the **Empty Project** link in the **Getting Started** window to display the **Project Explorer** window. You can also select **File»New Project** to display the **Project Explorer** window.
3. Select **Help** and make sure that **Show Context Help** is checked. You can refer to the context help throughout the tutorial for information about items on the block diagram.

Depending on the hardware configuration being used, continue to the following respective sections.

A. CompactRIO Controller

If you are using a CompactRIO controller, complete the following steps to add the device to the project and detect the C Series modules.

1. Right-click the top-level project item in the **Project Explorer** window and select **New»Targets and Devices** from the shortcut menu to display the **Add Targets and Devices** dialog box.
2. Make sure that the **Existing target or device** radio button is selected.
3. Expand **Real-Time CompactRIO**.
4. Select the CompactRIO controller to add to the project and click **OK**.
5. If you have LabVIEW FPGA installed, the **Select Programming Mode** dialog box appears. Select **Scan Interface** to put the system into Scan Interface mode.



Tip Use the **CompactRIO Chassis Properties** dialog box to change the programming mode in an existing project. Right-click the CompactRIO chassis in the **Project Explorer** window and select **Properties** from the shortcut menu to display this dialog box.

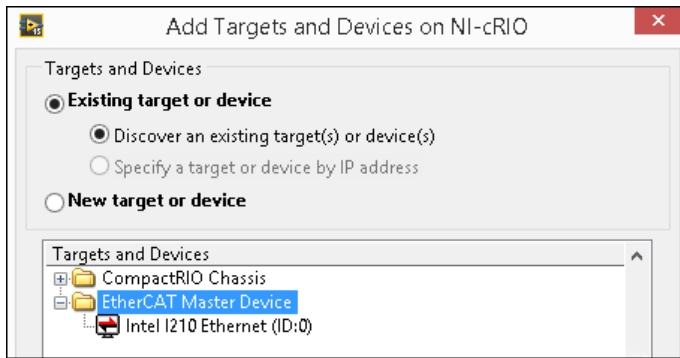
6. Click **Discover** in the **Discover C Series Modules?** dialog box if it appears.
7. Click **Continue**.
8. Right-click the controller item in the **Project Explorer** window and select **Properties** from the shortcut menu to display the **RT Target Properties** dialog box. Select **Scan Engine** from the **Category** list to display the Scan Engine page.
9. Set the **Scan Period** to 5 ms or lower.
10. Click **OK** to close the **RT Target Properties** dialog box.

B. EtherCAT Master and NI 9144 EtherCAT Expansion Chassis

If you are using the NI 9144 chassis, complete the following steps to add the EtherCAT master device and detect the C Series module.

1. Add the Master Real Time Controller to the project. Right click the top level project item in the **Project Explorer** window and select **New»Targets and Devices** from the shortcut menu to display the **Add Targets and Devices** dialog box.
2. Make sure that **Existing target or device** radio button is selected.
3. Expand the folder that corresponds to the device you are adding, such as Real Time Industrial Controller, Real Time PXI, and so on.
4. Select Real Time to add to the project and click **OK**.
5. In the LabVIEW **Project Explorer** window, right-click the master controller and select **New»Targets and Devices**.
6. In the **Add Targets and Devices** dialog window shown in Figure 16, select **Existing target or device** and expand the category EtherCAT Master Device to auto-discover the EtherCAT port on the master controller. An EtherCAT master device and modules can be added manually at any time.

Figure 16. Adding the EtherCAT Master



When all the slave devices are discovered, the LabVIEW **Project Explorer** window lists each slave device and any installed C Series modules.

C. NI 9146/7/8/9 Ethernet RIO Expansion Chassis

Complete the following steps to add the device to the project and detect the C Series modules if the NI 9146/7/8/9 Ethernet RIO Expansion chassis is being used.

1. Right-click the top-level project item in the **Project Explorer** window and select **New» Targets and Devices** from the shortcut menu to display the **Add Targets and Devices** dialog box.
2. Make sure that the **Existing target or device** radio button is selected.
3. Expand **Ethernet RIO**.
4. Select the Ethernet RIO expansion chassis to add to the project and click **OK**.
5. If you have LabVIEW FPGA installed, the **Select Programming Mode** dialog box appears. Select **Scan Interface** to put the system into Scan Interface mode.



Tip Use the **Chassis Properties** dialog box to change the programming mode in an existing project. Right-click the chassis in the **Project Explorer** window and select **Properties** from the shortcut menu to display this dialog box.

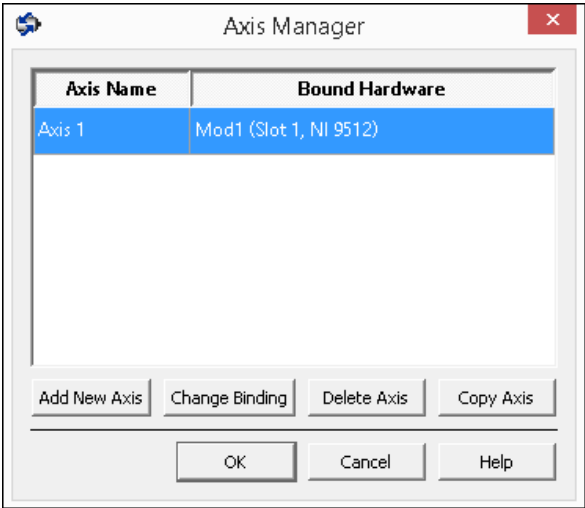
6. Click **Discover** in the **Discover C Series Modules?** dialog box if it appears.
7. Click **Continue**.
8. Right-click the controller item in the **Project Explorer** window and select **Properties** from the shortcut menu to display the **Ethernet RIO Properties** dialog box. Select **Scan Engine** from the **Category** list to display the Scan Engine page.
9. Set the **Scan Period** to 5 ms or lower.
10. Click **OK** to close the **Ethernet RIO Properties** dialog box.

Step 3: Add a SoftMotion Axis to the Project

Complete the following steps to create a LabVIEW project and add a SoftMotion Axis to it.

- 1. Right-click the controller item in the **Project Explorer** window and select **New» NI SoftMotion Axis** from the shortcut menu to open the **Axis Manager** dialog box.
- 2. Click **Add New Axis** to create an NI SoftMotion axis associated with the NI 9512 module. Axes are automatically bound to an available module. You can double-click the axis name to rename the axis and give it a descriptive name.

Figure 17. Axis Manager Dialog Box

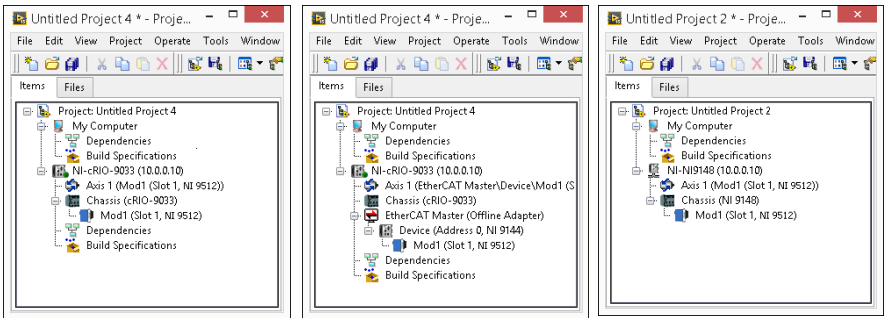


- 3. Click **OK** to close the **Axis Manager** dialog box. The new axis is added to the **Project Explorer** window.



Note You cannot associate more than one axis with the same C Series module.

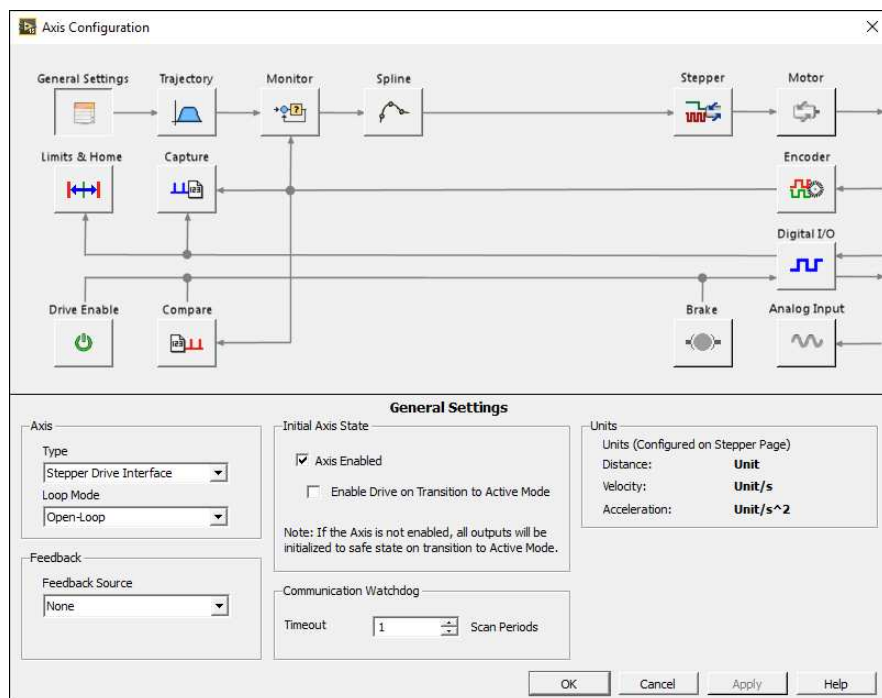
Figure 18. Project Explorer Window with Modules in Scan Interface Mode



Step 4: Configure the NI 9512 Axis


The **Axis Configuration** dialog box includes configuration options for stepper drive command signals, feedback devices, motion and digital I/O, trajectory, and axis setup. Figure 19 shows the parts of the **Axis Configuration** dialog box for the NI 9512 C Series module. Refer to the *SoftMotion Module* book of the *LabVIEW Help* for detailed information about each configuration option.

Figure 19. Axis Configuration Dialog Box




Note The **Axis Configuration** dialog box user interface may not match this image exactly depending on which version of the LabVIEW NI SoftMotion Module you are using.

Complete the following steps to configure the axis I/O settings for use with the NI SMD-7613/4/5/6 stepper drive.

1. Right-click the axis in the **Project Explorer** window and select **Properties** from the shortcut menu to open the **Axis Configuration** dialog box.
2. Configure the following settings on the **General Settings** page ().
 - a. Confirm that **Loop Mode** is set to **Open-Loop**. Axes configured in open-loop mode produce step outputs but do not require feedback from the motor to verify position.
 - b. Set **Feedback Source** to **Encoder 0**, if you have connected an encoder, or **None** if you do not have an encoder connected.
 - c. Confirm that the **Axis Enabled** and **Enable Drive on Transition to Active Mode** checkboxes contain checkmarks. These selections configure the axes to automatically activate when the NI Scan Engine switches to Active mode.



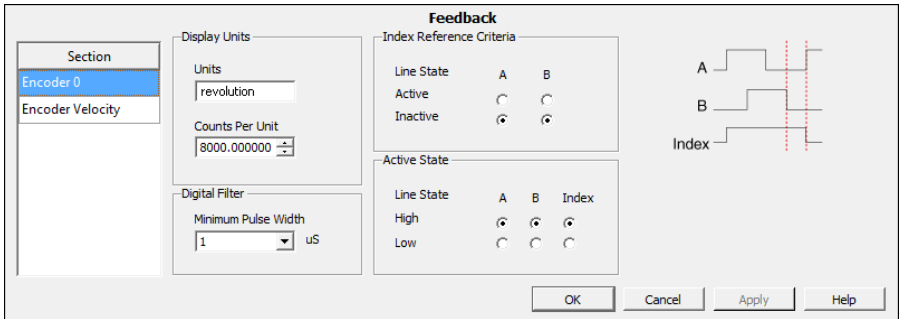
Note Disable these options to prevent axes from automatically activating when the NI Scan Engine switches to Active mode.

3. If you have connected an encoder, click the Encoder button () and configure the Units and Counts Per Unit.
 - a. In the **Active State** section set the **Line State** for **A**, **B**, and **Index** to **High**.
 - b. In the **Index Reference Criteria** section set the **Line State** for **A** and **B** to **Inactive**.
 - c. Select **rev** from the **Units** text box, or type **revolutions** if you prefer.
 - d. Set the **Counts per rev** to 8,000. This setting is the encoder resolution in quadrature counts per revolution and corresponds to the encoder lines per revolution multiplied by four.



Note The counts per revolution should be set accordingly if a dual shaft motor with a third party Encoder is being used.

Figure 20. Axis Configuration Encoder Page



Feedback			
Index Reference Criteria			
Line State	A	B	
Active	<input type="radio"/>	<input type="radio"/>	
Inactive	<input checked="" type="radio"/>	<input checked="" type="radio"/>	


Active State			
Line State	A	B	Index
High	<input checked="" type="radio"/>	<input checked="" type="radio"/>	<input checked="" type="radio"/>
Low	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>

4. Click the **Stepper** button () to open the **Stepper** page.

- a. Ensure that the Stepper Output settings match the following:
 - **Output Mode**—Step and Direction
 - **Output Type**—Single-Ended
 - **Active State**—Low
- b. Configure the Units and Steps Per Unit.
 - Select **rev** from the **Units** text box, or type **revolutions** if you prefer.
 - Set **Steps Per revolution** to 20,000.




Note The **Steps Per revolution** setting *must* match the configuration in the Stepper Configuration Utility. If you change the Steps/Rev setting using the Stepper Configuration Utility, update this setting to match.

- c. (Optional) Click the **Monitor** button () and make the following changes to enable NI SoftMotion to disable the drive and turn off the Drive Enable signal when the specified position error limit is exceeded.




Note The **Monitor** button is greyed out if **Feedback Source** on the **Axis Settings** page is set to **None**.


- Enable the **Enforce Position Error Limit** checkbox.
- Set **Position Error Limit** to a reasonable tolerance for your system, such as 1.


5. Click the **Drive Enable** button () and ensure that the Drive Enable settings match the following:

- **Output Type**—Sourcing
- **Active State**—Off
- **Safe State**—On

6. If you connected the Out+/Out- signal, click the Digital I/O button () and complete the following steps to configure the DI 0 signal:

- a. Double-click the text in the **Mapping** column and select **Drive Fault/Alarm** from the dropdown list.
- b. Ensure that the DI 0 settings match the following:
 - **Input Type**—Sinking
 - **Active State**—On
 - **Digital Filter**—50 μ s

7. Complete the following additional steps if you do not have limits and home connected at this time:
 - a. Click the **Limits & Home** button ().
 - b. In the **Forward Limit** and **Reverse Limit** sections ensure that the settings match the following:



Note These configuration settings disable limits for initial setup and testing purposes. National Instruments recommends connecting and enabling limits in your final application. The SMD-7613/4/5/6 has limit switch inputs for use in Ethernet streaming mode. When used with the NI 9512, limit switches should be wired to the 37-pin connector block.

 - Clear the **Enable** checkbox from both **Forward Limit** and **Reverse Limit**.
 - Set the **Active State** for both **Forward Limit** and **Reverse Limit** to **Off**. This prevents a limit warning even though limits are turned off.
 - c. Open the **Home** section and clear the **Enable** checkbox.
8. Configure any additional I/O settings according to your system requirements, such as position compare or position capture signals.
9. Click **OK** to close the **Axis Configuration** dialog box.
10. Right-click the controller item in the **Project Explorer** window and select **Deploy All** to deploy the axis information.
11. Select **File»Save Project** to save the project.

Step 5: Enable and Test the Drive Using LabVIEW

Use the Interactive Test Panel to test and debug your motion system and configuration settings on the selected axis. With the Interactive Test Panel you can perform a simple straight-line move and monitor feedback position and position error information, move and I/O status information, change move constraints, get information about software errors and faults, and view position or velocity plots of the move.



Complete the following steps to test your setup after configuring the axis using the **Axis Configuration** dialog box.

1. Right-click the axis in the **Project Explorer** window and select **Interactive Test Panel** from the shortcut menu. Opening this dialog box sends the axis settings to the hardware and activates the I/O on the module.
2. On the **Move** tab set **Move Mode** to Relative Position and **Target Position** to 20 rev.

3. On the **Move Constraints** tab set **Velocity** to 2 rev/sec, **Acceleration** and **Deceleration** to 20 rev/sec², and **Acceleration Jerk** and **Deceleration Jerk** to 200 rev/sec³. Using the encoder counts per revolution and stepper steps per revolution values specified in this tutorial the motor will move 20 revolutions at 120 rpm.



Tip Click the **Help** button (?) on the bottom of the dialog box for detailed information about the items available in this dialog box.

4. Click the **Enable** button () on the bottom of the dialog box to enable the drive.
5. Click the **Start** button () on the bottom of the dialog box to start the move with the configured options.
6. Use the **Status** and **Plots** tabs to monitor the move while it is in progress.
Finalize your motion system setup by connecting and configuring additional I/O such as limits as required by your system using the 37-pin terminal block.

Where To Go From Here

The following documents contain additional information that you may find helpful. All referenced documents ship with the product and are available at ni.com/manuals.

- Operating instructions for the controller and C Series module.
- *NI SMD-7613/7614/7615/7616 User Manual*
- *LabVIEW NI SoftMotion Module Help*—Use this help file to learn about using the NI SoftMotion Module in LabVIEW including information about function blocks and using the NI SoftMotion Module with the LabVIEW Project. To access this help file from LabVIEW, select **Help»LabVIEW Help**, then expand the *LabVIEW NI SoftMotion Module* book on the **Contents** tab.
- *LabVIEW Help*—Use the *LabVIEW Help* to access information about LabVIEW programming concepts, step-by-step instructions for using LabVIEW, and reference information about LabVIEW VIs, functions, palettes, menus, tools, properties, methods, events, dialog boxes, and so on. The *LabVIEW Help* also lists the LabVIEW documentation resources available from National Instruments. Access the *LabVIEW Help* by selecting **Help»LabVIEW Help**.
- *SoftMotion Examples*—After the configuration and testing of the motion system is complete, use SoftMotion API to program the motion control application in LabVIEW. Access the SoftMotion Examples by selecting **Help»Find Examples»Hardware Input and Output»Motion Control»SoftMotion**.

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