

# UDP Commander

(rev 1.70)

Setting and programming software for the DS, OS and LS  
stepper motor drives series.

**User's Manual**

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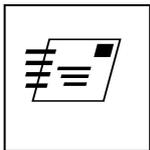


## 1 Notes, Terms and Warnings

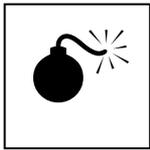
In this manual some symbols, whose meaning is listed below, are used to underline particular subjects .



There is a dangerous condition which must be accurately evaluated and avoided. The non-respect of indications marked with this symbol can cause serious damages and injury to people, animals and things.



The subject is very wide and could require a deeper examination with the technical support.



The non-observation of what described could damage the products.

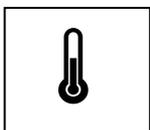


Characteristics and functionalities which cannot be easily found in other products.

A shortcut to reach a target is shown.



A change or repairing intervention which can be made directly by the user.



An aspect connected to the temperature or longevity of the product.

The terms listed below are also used:

*Product*

The software described in this manual.

*Device*

The item handled by the software.

*User*

Who selects and/or installs and /or uses the product.

*Application*

The machine, the equipment, the device, etc. on which the product is applied.

The symbol "x" is often used as wildcard and substitutes any character to identify group of products. For example the wording xS identifies all the drives belonging to the DS10, OS10 or LS10 series, in the same way the wording DSxx76 identifies the products DS1076, DS3076, DS5076, DS5276 and DS5476.

## 2 Product description

The *UDP Commander* allows to setup the stepper motor drives of the DS10, LS10, OS10, DS30 and DS5x series.

Each configuration or setting can be saved or loaded from a file. Therefore, it is possible, simply and safely, to set more drivers exactly alike, as well as to send all over the world the configuration of a specific application just transmitting a file.



Through *UDP Commander* it is also possible to view in real time the drive working status, as for example the inputs and outputs logic level, the motor status, etc.

Designed for Windows platform (Windows 98 version or greater), it has a simple and intuitive graphic interface which allows to be operative soon. The several tooltips<sup>1</sup> guide the user in an interactive way, providing a synthetic description of the buttons, fields, or menus that from time to time are met during the use of the program.

If the software revision is different from 1.70 it is possible that some of the following images and descriptions do not result complete, pertaining or applicable. This may happen also in case the firmware revision installed on the drives is different from 1.15 for the xS10 series and 1.00 for the DS30 and DS5x series.

Some subjects which are outside of the working description of *UDP Commander* are barely mentioned and for a deepening it is necessary to refer to the specific manual of the device.

### 2.1 Main features

- ✓ Single software for the whole range of microstepping drives (DS, OS and LS series)
- ✓ Compatible with all the operative Windows systems from Windows 98 (Windows 7 at 32bit and 64bit included)
- ✓ Multilanguage support
- ✓ Automatic device recognition
- ✓ Guided installation
- ✓ Easy to use
- ✓ Free

### 2.2 Minimum system requirements

*UDP Commander* can be installed and used on any PC with the following minimum characteristics:

- ✓ Operative system Windows 98, 98SE, ME, 2000, XP, Vista, Windows 7
- ✓ Processor Pentium III 300MHz
- ✓ 256Mbyte RAM
- ✓ 32Mbyte hard disk
- ✓ Video resolution 800x600

<sup>1</sup> The tooltips are short messages which appear positioning the mouse punter on a button, field, menu, etc.



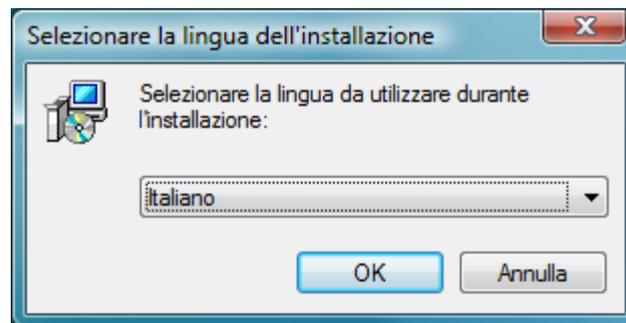
### 3 Installation

The installation of *UDP Commander* is simple and fast thanks to the multilanguage guided procedure.

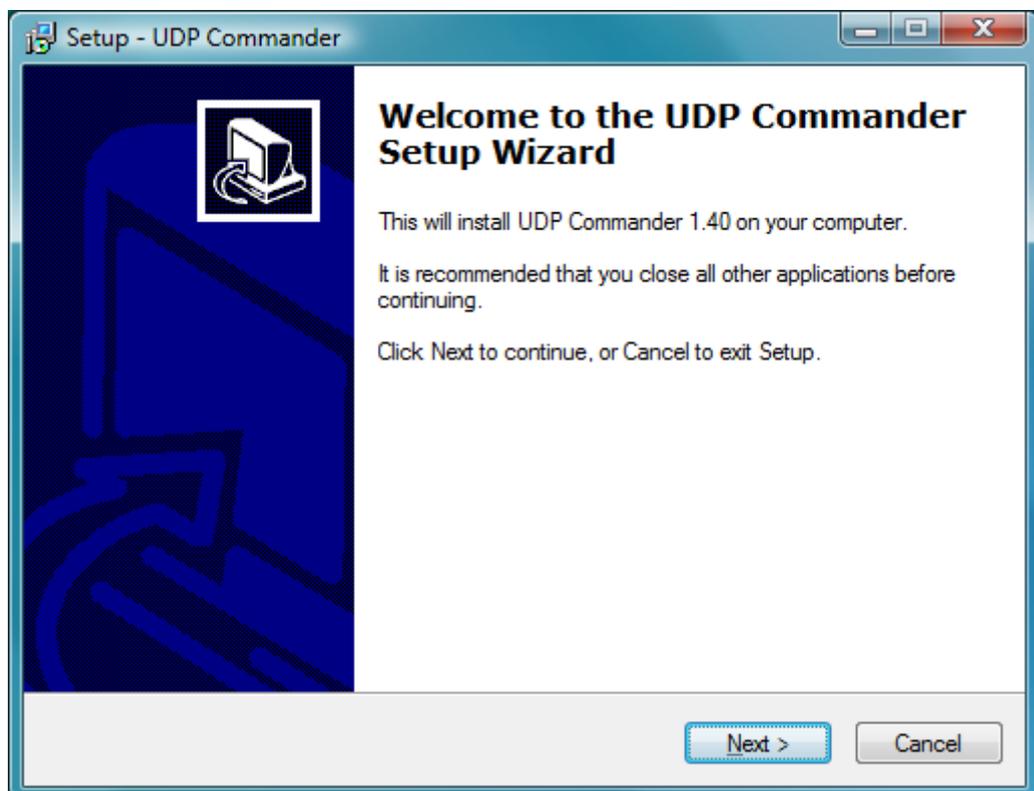
The following images have been acquired from the *Vista* edition of the Windows operative system. Different versions could generate a slightly different view, in this case follow the indication on the video.

Before proceeding with the installation, close all open applications.

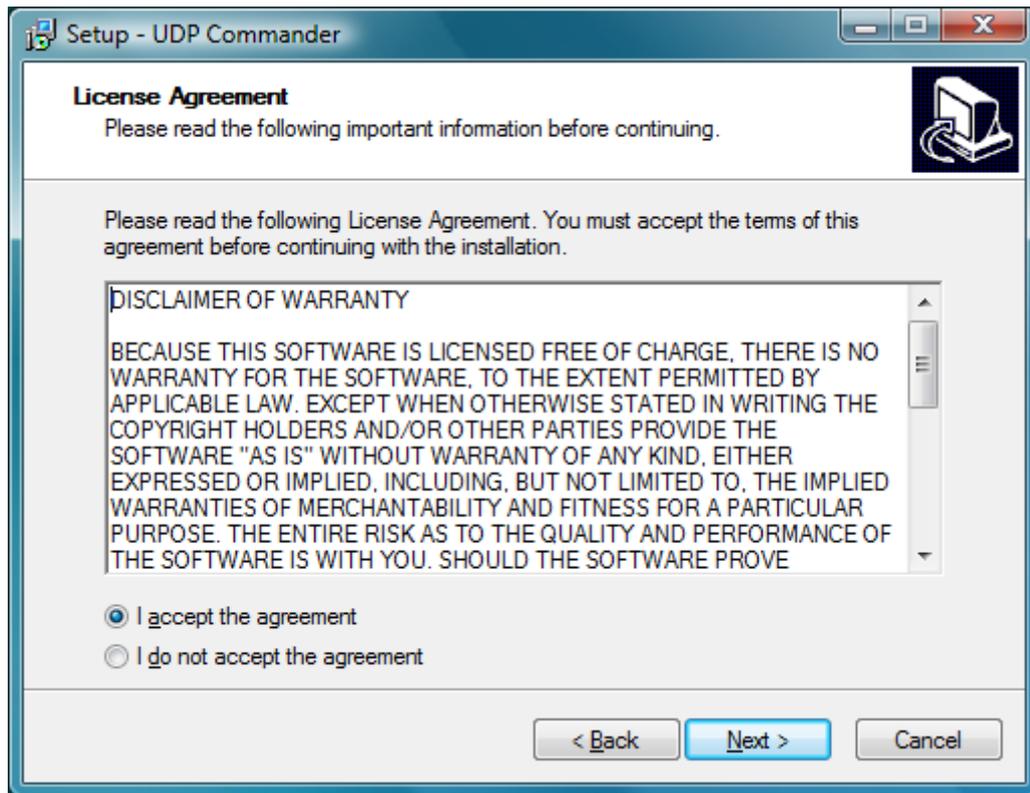
If necessary uncompact the files, then run *UDP Commander 1.41 setup.exe* .



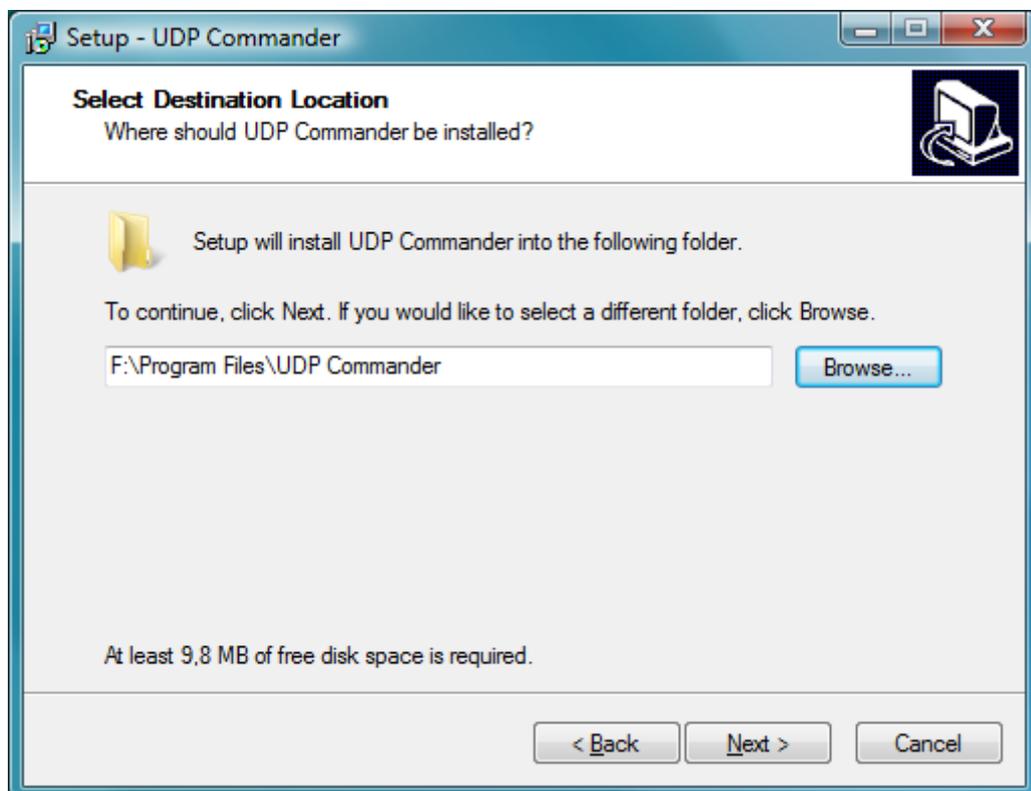
Select the preferred language and click *OK* button.



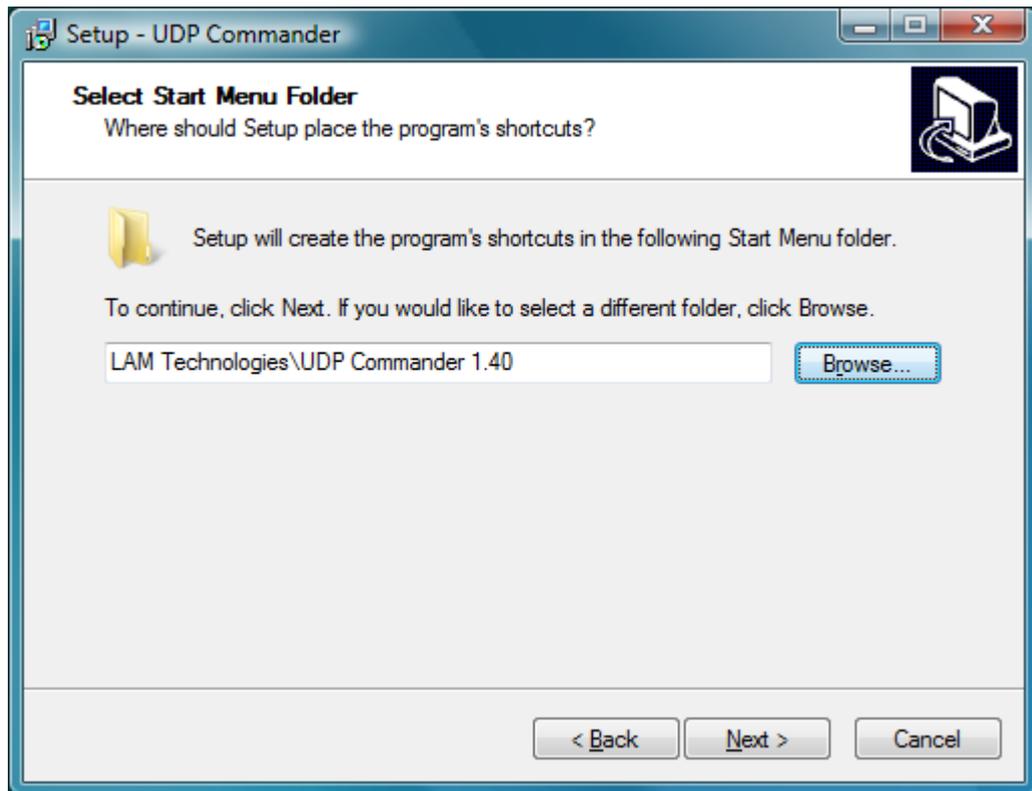
Click *Next* button to continue.



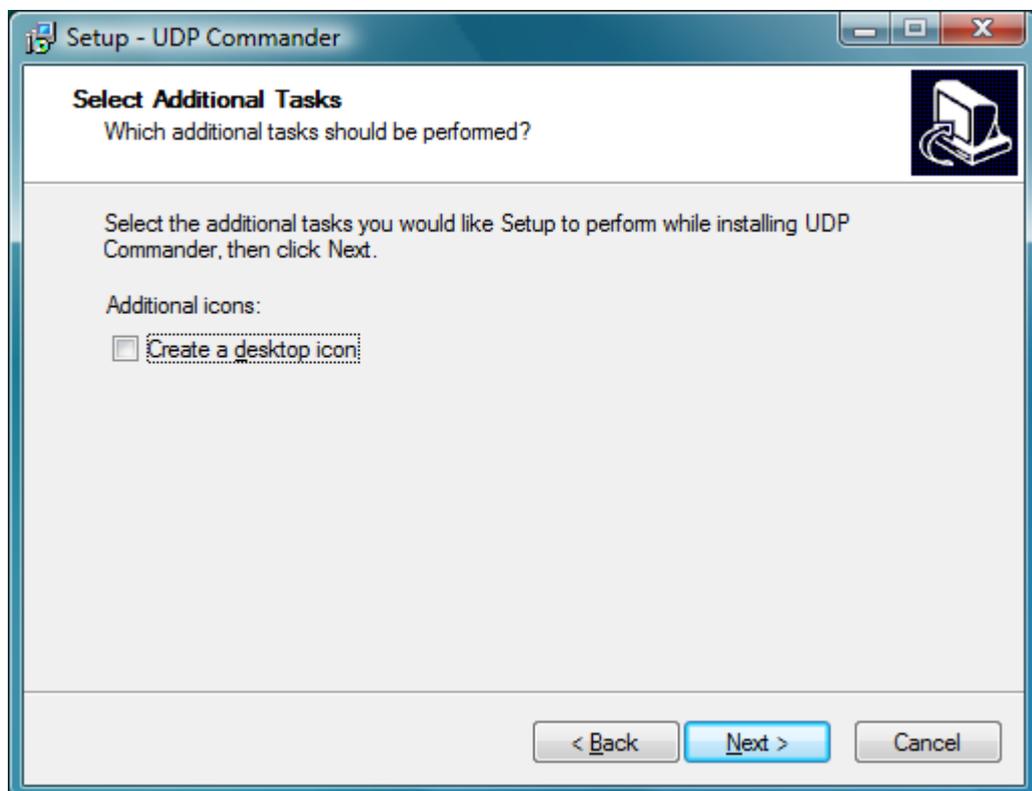
Read carefully the License Agreement and if all the conditions are comprehended and accepted select the *I accept the agreement* option, then click on *Next* button to continue.



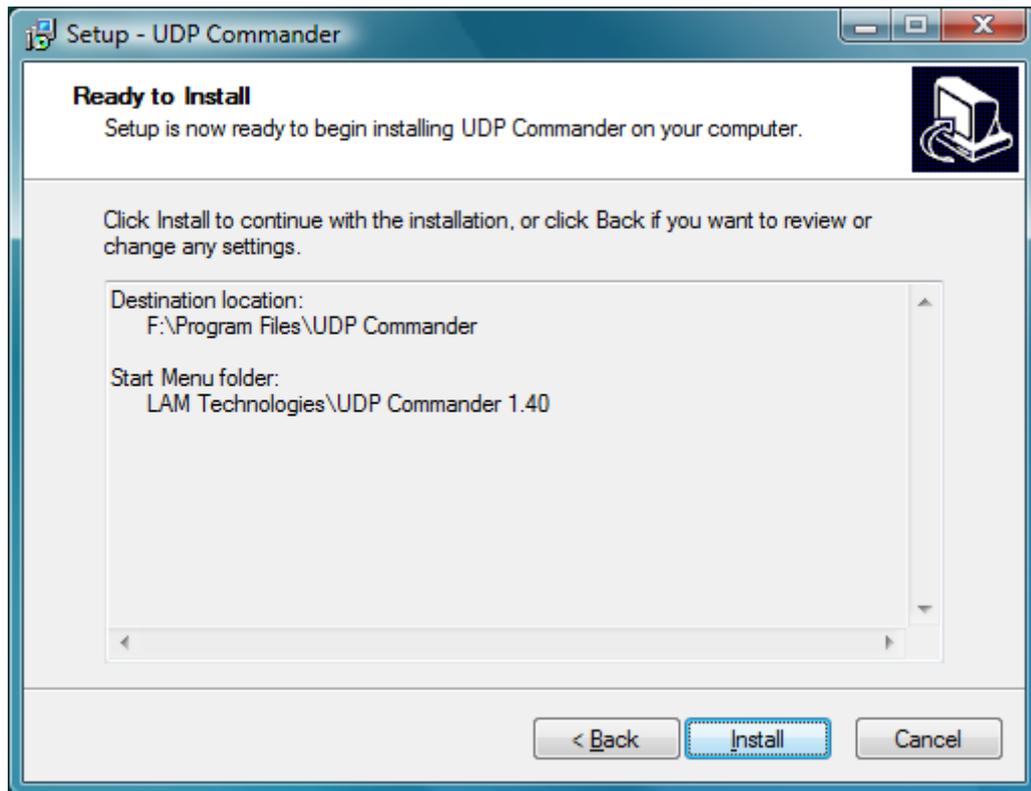
If needed click on *Browse* button to modify the installation folder, then click on *Next* button to continue.



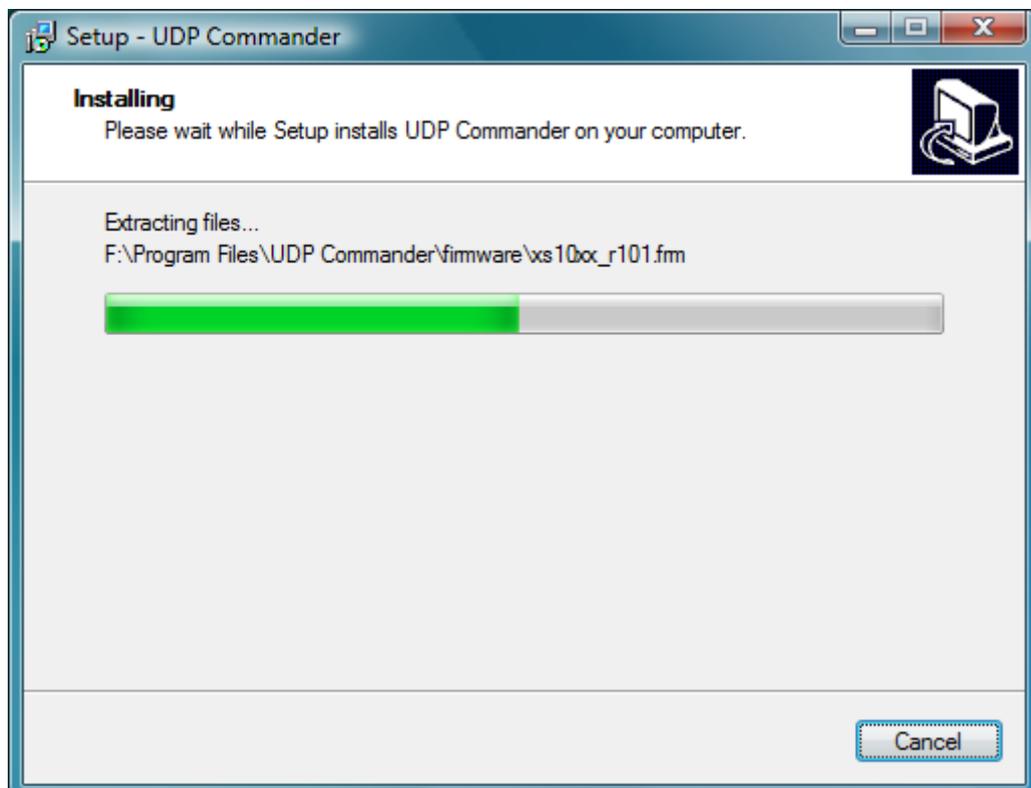
If needed click on *Browse* button to modify the start menu folder where the connection to the application will be saved, then click on *Next* button to continue.



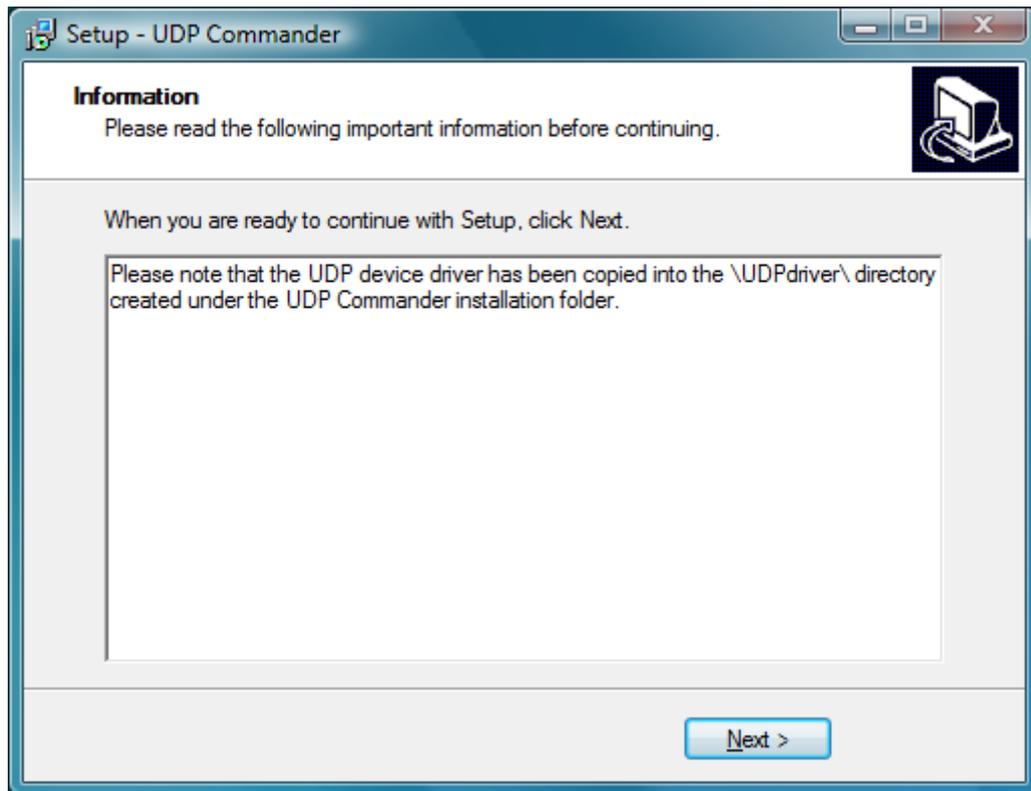
Select *Create a desktop icon* if a connection to the application on the desktop is needed, then click on *Next* button to continue.



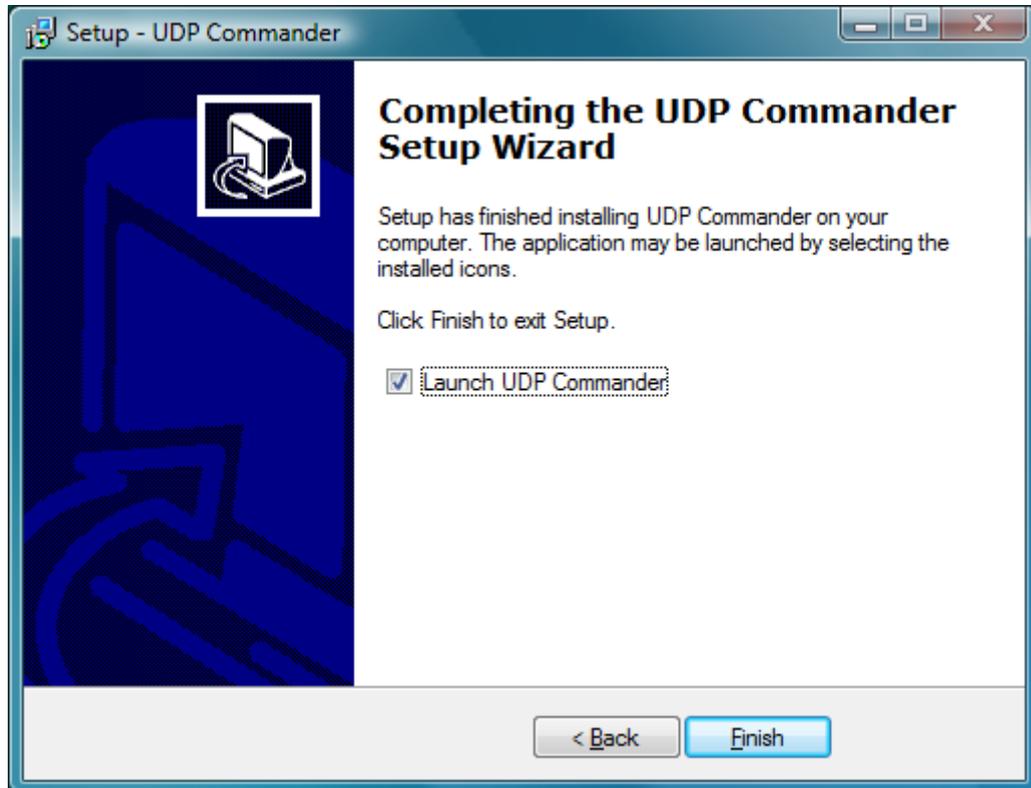
Verify that the installation data are correct and click on *Install* button to start the installation.



During the installation a bar will show the progress status.



Once the installation is completed you will be informed about the position of the folder where the *UDP30* interface drives have been copied (see the *UDP30* user's manual for an exhaustive description of the product). Click on *Next* button to continue.



The last dialogue window will inform you that the installation is complete. Clicking on *Finish* button you will terminate the installation procedure and if the *Launch UDP Commander* check box is selected you will start the application.



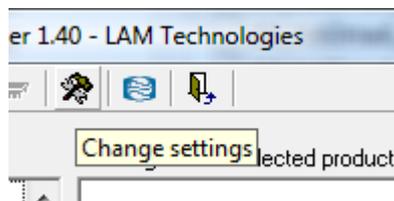
## 4 Operativeness

The dialogue window that appears at the start of the application allows to automatically connect to the drive, through the UDP30 interface, or to manually select the product on which to operate (off-line mode).

On the tool bar above there is the *Change settings* button which allows to you to setup the language.

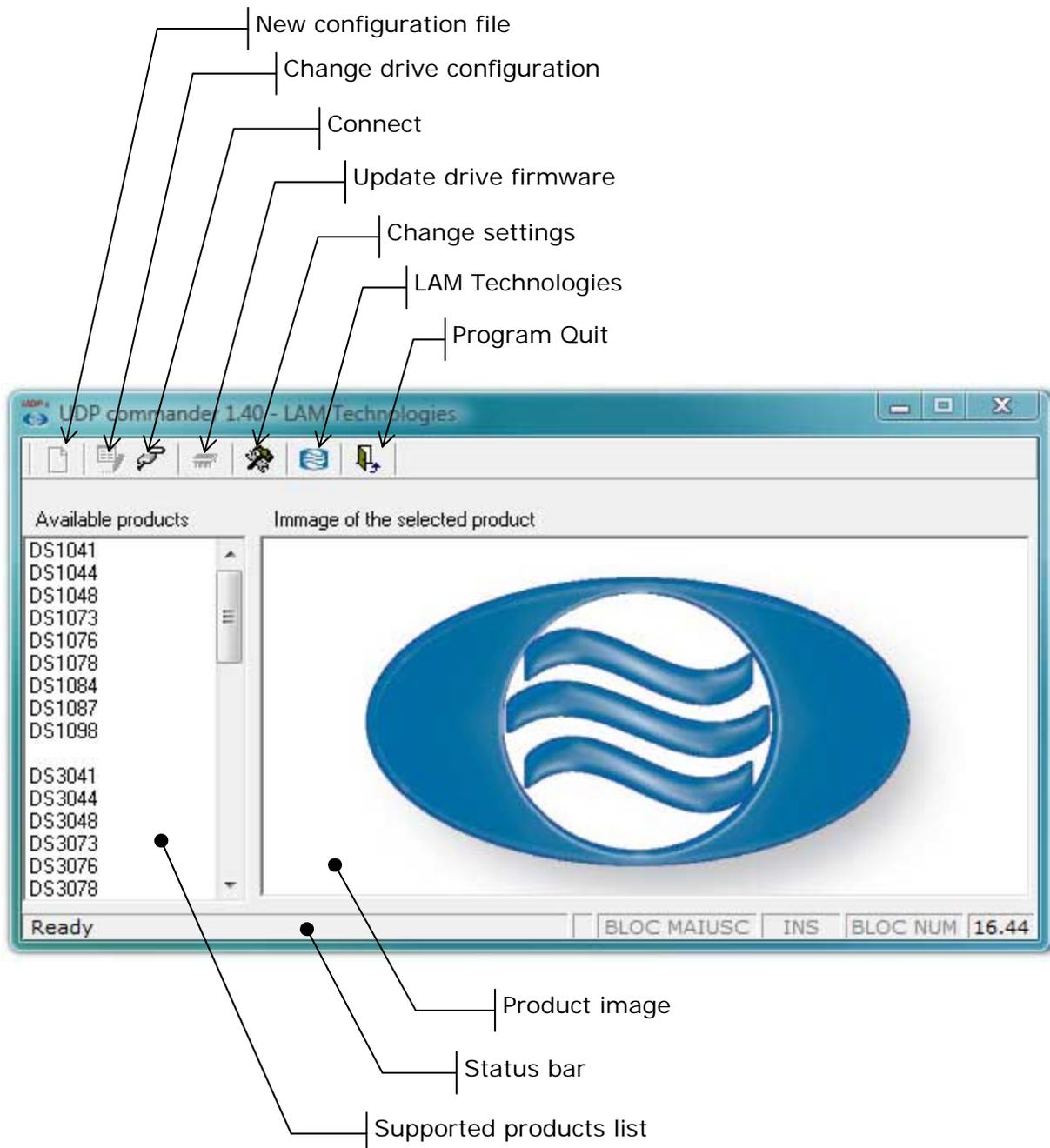


Positioning the mouse on each object of the interface a brief description of the object itself appears (as per figure below), this is useful to quickly and simply comprehend the functionalities of the product.



## 4.1 Main window

The following is a description of the elements and functionalities accessible from the main page.



### 4.1.1 Change settings

The page that appears clicking on the *Change settings* button allows to modify some characteristics of the program, as for example the language.

### 4.1.2 New configuration file

The *New configuration file* button is activated selecting from the *Supported products list* a drive's code. This button allows to have access, in off-line mode, to the setting or programming window associated to the selected drive (further on a detailed description of every window) .

### 4.1.3 Connect

Clicking on the *Connect* button the program verifies if the *UDP30* interface is connected to the computer and if there is a drive connected to the interface itself. In this last case the drive is automatically polled to identify the model, the serial number and the firmware revision installed. These information are displayed on the *status bar*.

The button has a bistable functioning and, if clicked while the connection with the drive is in progress, the connection itself is interrupted.

### 4.1.4 Change drive configuration

The *Change drive configuration* button is activated after a connection with the drive has been established (see *Connect* button). This button allows to have access, in on-line mode, to the setting or programming window associated to the connected drive (further on a detailed description of every window).

### 4.1.5 Update drive firmware

The *Update drive firmware* button is activated after a connection with the drive has been established (see *Connect* button). This button allows to choose the firmware file to be uploaded to the drive. Usually the firmware files are contained in the folder *\Firmware* inside the *UDP Commander* installation one. The name of the file has the following format:

**aaaaaa\_rmnn.frm**

where **aaaaaa** stands for the drive or the drive series and **mnn** for the revision of the firmware itself in the format **m.nn**. For example The file **xS10xx\_r115.frm** indicates that the firmware is suitable for all the xS10 series drives and that the revision is 1.15.

In case we should try to upload a non-suitable file on a drive, a message will signal the error.

### 4.1.6 LAM Technologies

Clicking on the *LAM Technologies* button an image with all the company contacts will appear (press ESC key on the keyboard to close).

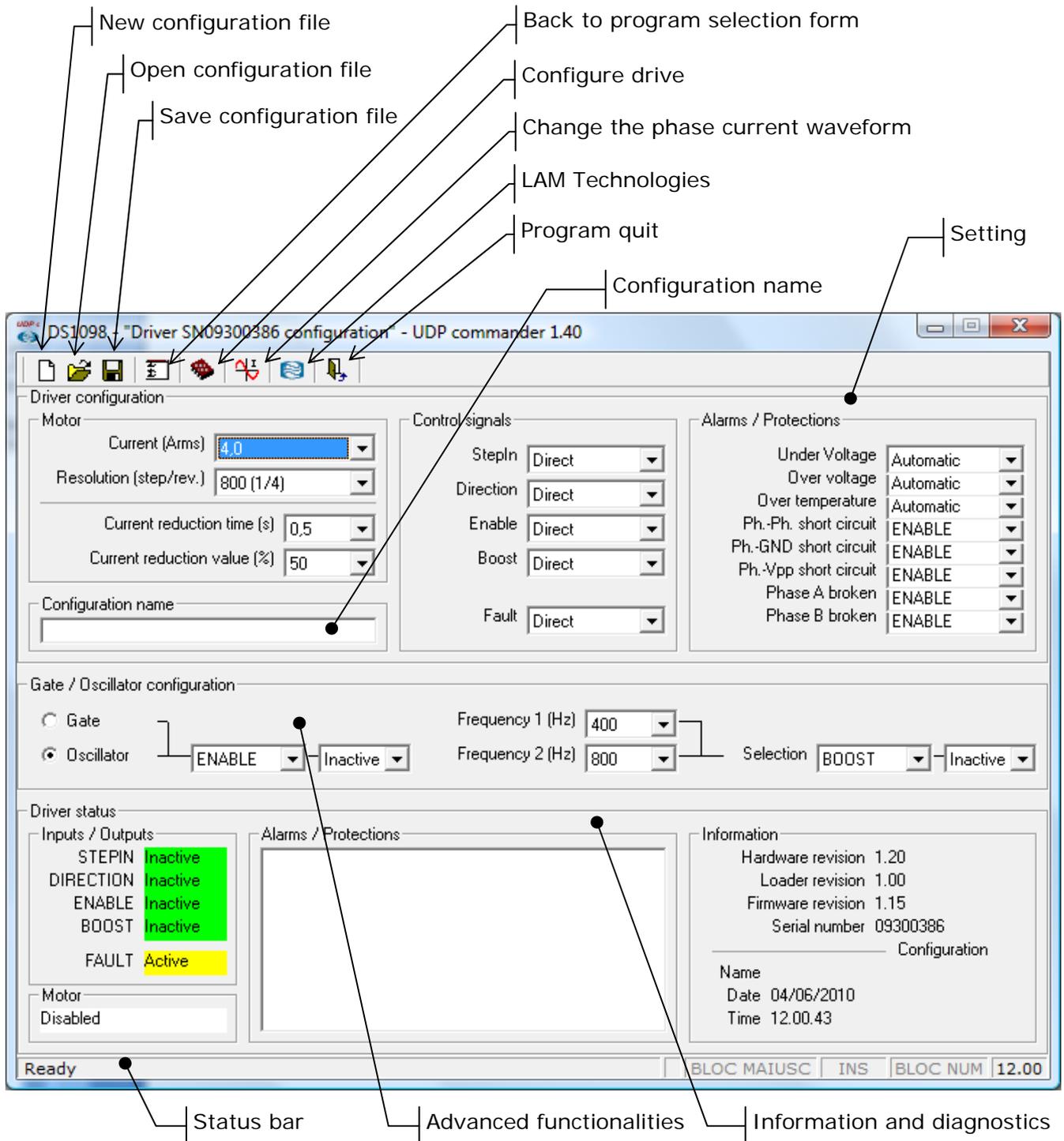
### 4.1.7 Program Quit

Click on the *Program Quit* button to quit the *UDP Commander*.

## 4.2 xS10 series drive configuration window

To access to this window connect to or select a drive belonging to the DS10, OS10 or LS10 series.

The window is divided into three frames. The one at the top, soon under the button bar, allows the drive setting, the central zone allows to activate and use the advanced functionalities, while the one on the bottom displays in real time the status of the drive.



#### 4.2.1 New configuration file

Clicking on the *New configuration file* button the values of the setting parameters are substituted with the default standard ones proper to the selected drive model (visible on the top on the title bar).

#### 4.2.2 Open configuration file

Clicking on the *Open configuration file* button it is possible to load a file containing a parameters configuration set.

### 4.2.3 Save configuration file



Clicking on the *Save configuration file* button it is possible to save the configuration parameters to upload them again successively and quickly set other drives in the same way.

### 4.2.4 Back to program selection form

Clicking on the *Back to program selection form* button the configuration window is quit to go back to the main window.

### 4.2.5 Configure drive

Clicking on the *Configure drive* button all the configuration parameters are transferred to the drive where they are permanently saved.

After having modified one or more parameters it is necessary to click on this button to transfer the new configuration to the drive.



For safety reasons, during the transfer of parameters, the drive disables the motor with subsequent torque annulment. Once the transfer is done, the motor is enabled again or not according to the inputs status and to the new configuration.

The *Configure drive* button is not available when the drive is not connected (off-line mode).

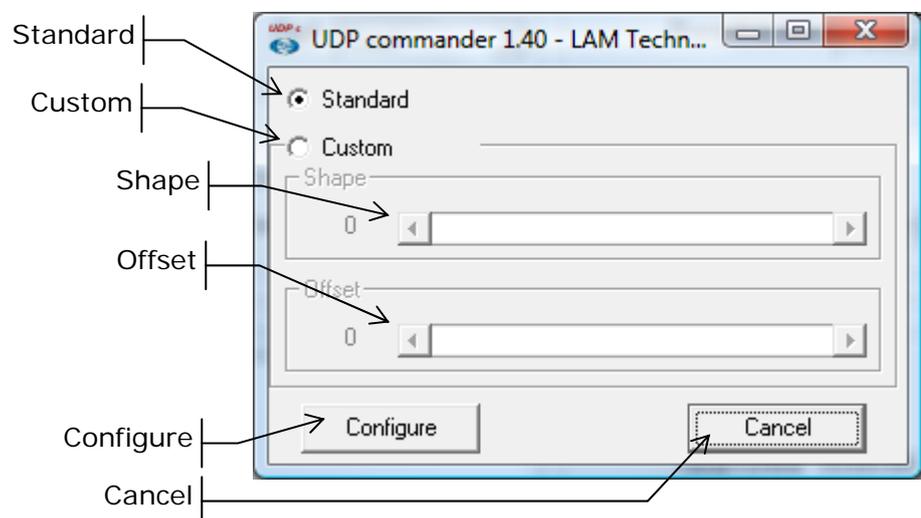
### 4.2.6 Change the phase current waveform

Through the *Change the phase current waveform* button it is possible to change the waveform of the current supplied by the drive to the motor.



This feature, very rare to be found in market common drives, allows to better adapt the drive to the motor to obtain a smooth rotation.

Clicking on the button the following window appears:



#### 4.2.6.1 Standard

The *Standard* option is selected by default and indicates that the waveform of the current supplied by the drive to the motor is a pure sinusoidal wave.

#### 4.2.6.2 Custom

Selecting the *Custom* option the *Shape* and *Offset* cursor keys are activated and allow to personalize the current waveform.

#### 4.2.6.3 Shape

The *Shape* cursor key acts on the harmonic content of the current supplied to the drive. The optimal regulation value must be found experimentally and depends to the type of motor. For LAM Technologies motors this value is usually included between 0 and -4.

#### 4.2.6.4 Offset

The *Offset* cursor key allows to operate on the current offset in respect to the 0.

Usually this parameter does not need to be modified and can be left at the default value (zero).

#### 4.2.6.5 Configure

Clicking on the *Configure* button the settings are transferred to the drive.



For safety reasons, during the transfer of parameters, the drive disables the motor with subsequent torque annulment. Once the transfer is done, the motor is enabled again or not according to the inputs status and to the new configuration.

The *Configure* button is not available when the drive is not connected (off-line mode).

#### 4.2.6.6 Cancel

Clicking on the *Cancel* button the page of the current waveform setting is closed.

#### 4.2.7 LAM Technologies

Clicking on the *LAM Technologies* button an image with all the company contacts will appear (press ESC key on the keyboard to close).

#### 4.2.8 Program Quit

Click on the *Program Quit* button to quit the *UDP Commander*.

#### 4.2.9 Setting

The *Setting* frame includes all the controls that allow to better adapt the drive to the application requirements.



Thanks to the several and accurate regulations, impossible to be obtained through the common dip-switches, it is possible to set the drive to adapt itself to the control system signals, to the type of motor used, etc. without the need to add external components as resistors, etc.

### 4.2.9.1 Current

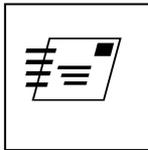
The setting of the phase current must be made very carefully as an incorrect calibration can permanently damage the motor.

Typically the drive must be calibrated at the nominal current of the motor as declared by the motor manufacturer.

In some cases, if the work cycle allows it, it is possible to setup a higher current, anyway not beyond the 30% in respect to the rated current of the motor. Similarly, if the full torque the motor is able to supply is not required, it is possible to setup a lower current value, in order to reduce the heating on the motor itself.



Particular attention must be given to the motors which have 6 or 8 wires as they often can be used with serial or parallel connection and, according to the chosen connection, the calibration current of the drive may also vary of factor 2. If for example a motor, characterized by the manufacturer for a phase current of 6Arms with parallel connection, is used with serial connection, it is necessary to calibrate the drive to half of the nominal current value, i.e. 3Arms. If we left the drive calibrated at 6Arms the motor would be permanently damaged.



In case of doubts about the current setting it is a best practice to contact the manufacturer of the motor.



In the end, note that the current is expressed in effective value and not peak value ( $A_{pk}$  or  $A_{max}$ ), as in some marketed drives. The effective value of a sinusoidal current is 40% higher than the peak current! This means that if you are already using mini or microstep sinusoidal drives calibrated at for example  $8A_{pk}$  current (or  $8A_{max}$ ), you must set in *UDP Commander* a current reduced by  $\sqrt{2}$  (i.e.  $5,7A_{rms}$ ), if you need the application continues to work in the same way. This means that a  $5,7A_{rms}$  LAM Technologies drive (effective Ampere) performs the same work of an  $8A_{pk}$  (or  $8A_{max}$ ) sinusoidal drive!

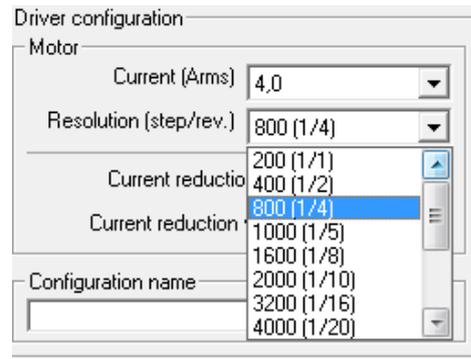
### 4.2.9.2 Resolution

A stepper motor is created with its own number of steps per revolution. In the industrial automation it is prevalent the division in 200 steps/rev where each step, called full step, is equal to a movement of the motor shaft of  $1,8^\circ$ . Anyway, there are also motors with 400 full steps/rev (step angle of  $0,9^\circ$ ) or with 100 full steps/rev (step angle of  $3,6^\circ$ ), and so on.



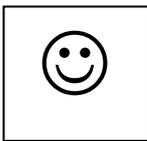
The drives belonging to the xS series are able to electronically divide the full step of the motor, to increase the resolution and to reduce the vibrations.

Both binary and decimal divisions are available, as displayed in the below image.



The first value of each line of the list indicates the number of divisions of the motor revolution, and it is referred to a 200 full steps/rev. motor (step angle of  $1,8^\circ$ ). In case of a 400 full steps/rev. motor, this values must be doubled while in case of a 100 full steps/rev. motor they must be halved. The number in parenthesis instead indicates the parts in which the full step is divided and it is independent of the division numbers of the motor. In case of a  $\frac{1}{4}$  full step resolution the step angle will be of  $0,45^\circ$  on a 200 full steps/rev. motor ( $1,8^\circ$ ).

#### 4.2.9.3 Current reduction



The current reduction can be personalized both in terms of time, from the reception of the last step impulse, and in terms of reduction percentage.

The calibration must be performed according to the application requirements. Take present that to set a current reduction value of 0% is equal to exclude the current reduction itself, while setting a value of 100% is equal to annul the motor current when this is still. For further information see the user's manual of the drive.

#### 4.2.9.4 Input signals conditioning



The *Control signals* frame allows to define how the drive must read and handle the various input and output digital signals.

This extraordinary flexibility allows to invert the working logic of a signal, to force it always active or to disable it.

#### 4.2.9.5 Alarms and protections



The *Alarms and protections* frame allows to define the action necessary to remove an alarm or a fault signal.

- *Automatic*, the drive is automatically re-enabled at cease of the alarm condition.
- *Permanent*, the alarm signal remains till the power off of the drive.
- *ENABLE*, the alarm signal remains till the drive is disabled through the ENABLE signal.

- *Disabled*, the alarm signal is suppressed (for security reasons some alarms cannot be deactivated).

For more information about the several alarms and faults see the user's manual of the drive.

#### 4.2.9.6 Configuration name

In the space inside the *Configuration name* frame it is possible to digit a string, max 25 characters long, which will be saved in the drive.

This field is frequently used to assign a name to the configuration defined for the drive (ex. "X-assis").

#### 4.2.10 Advanced functionalities

The xS10 microstepping drive series has exclusive functionalities which differentiate it from the common marketed drives controllable through impulse train.

The following is a brief description of these functionalities, for more information see the user's manual of the drive.

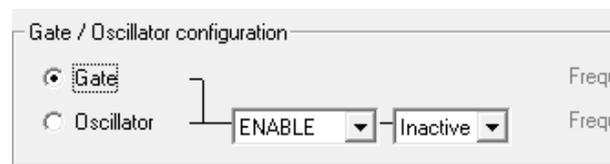
##### 4.2.10.1 Gate



The *Gate* function is useful to control more drives with one only step signal (generated for example by a PLC or by an axis control board).

After having selected the *Gate* option it is sufficient to choose the signal to be used to enable or not the reception of the impulses applied to the *STEPIN* input.

In the below image, for example, it has been selected the *ENABLE* signal.



The last necessary operation consists to define the enable signal conditioning amongst the *Direct*, *Inverted*, *Active*, *Inactive* options. For more information see paragraph 4.2.9.4 Input signals conditioning.

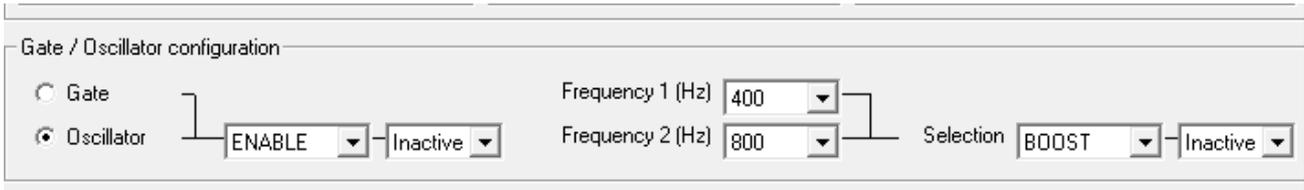
Take present that the chosen signal for the *Gate* function continues to perform also its natural function and that consequently it could be necessary to intervene in the Control Signals frame to set it as *Active* or *Inactive*.

##### 4.2.10.2 Oscillator



The *Oscillator* function allows to control the motor rotation through a start/stop signal instead of through the impulse train. Note that when the oscillator is not active the *STEPIN* input performs its natural function.

As displayed in the below image, to set the oscillator it is sufficient to select the *Oscillator* option and to define the signal, and its conditioning (see paragraph 4.2.9.4 Input signals conditioning), which will have to be used to command the motor rotation.

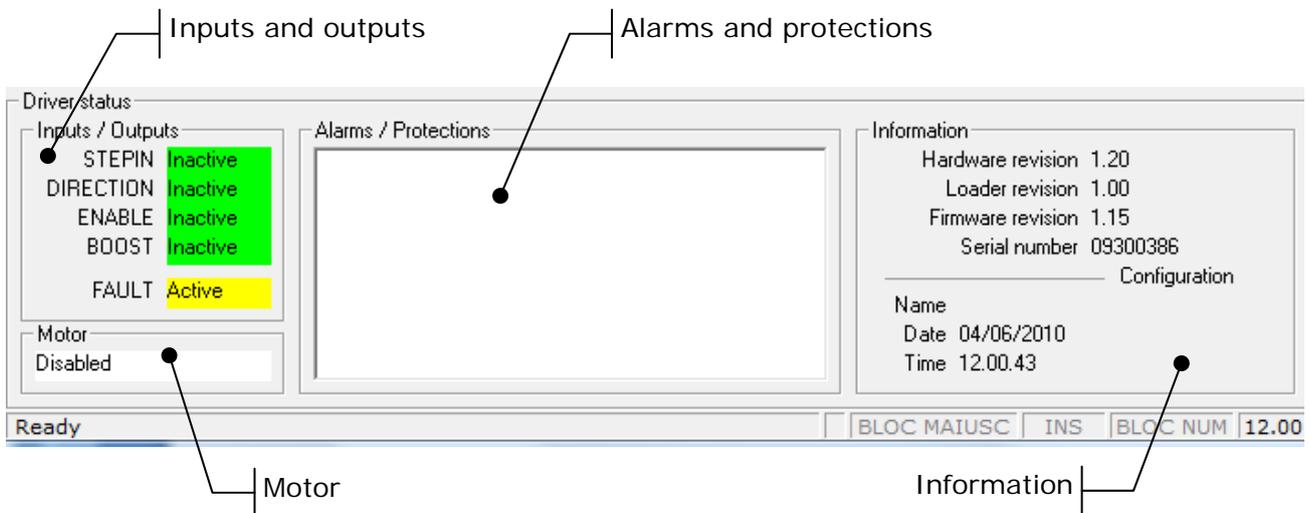


In the central part of the frame it is possible to define two different frequencies generated by the oscillator which will produce two different motor rotation speeds, according to how the step resolution has been set (see paragraph 4.2.9.2 Resolution).

In the end, from the list on the right of the frame it is possible to choose the signal to be used to select one between the two available frequencies. When the signal is inactive the oscillator is set to *Frequency 1*, when the signal is active the oscillator will use the *Frequency 2*. Also this signal can be conditioned as the previous ones (see paragraph 4.2.9.4 Input signals conditioning).

**4.2.11 Information and diagnostics**

The *Drive status* frame gives a complete view on the alarms eventually present, on the inputs and outputs status and on the hardware and software revisions of the drive.



**4.2.11.1 Inputs and outputs**

The *Inputs/Outputs* area shows the active or inactive status of each single I/O.

**4.2.11.2 Motor**

The *Motor* frame allows to know in real time the status of the motor.

**4.2.11.3 Alarms and protections**

The *Alarms/Protections* area changes its color if at least an alarm is present and a message explaining the problem found

#### 4.2.11.4 Information

The *Information* frame shows the revision of the product's hardware, of the Loader (a software that allows the update of the product) and of the firmware together with the drive serial number.

Below the configuration line there is the name of the configuration (see the paragraph 4.2.9.6 Configuration name) and the date and hour in which the configuration has been written in the drive (this information are taken from the clock of the PC).

### 4.3 DS30 and DS5x series drive setting and programming window

To access to this window connect to or select a drive belonging to the DS30 or DS5x series.

The window is divided into three frames. The one on the left contains the instruction blocks which compose the application program, high on the right there are the programming tools, while the frame on the right bottom displays in real time the status of the drive.

In the fields that accept numerical values it is possible to use also the hexadecimal format preceding the number with the prefix "0x". For example 0x10, 0xA5, 0xF2DC, etc. are valid hexadecimal numbers.

The screenshot shows the UDP Commander software interface. The main window is titled "DS5x76 - 'Sample\_1' - UDP commander 1.70 (beta 1)". The interface is divided into several sections:

- Application program:** A list of program blocks, each with a checkbox and a description. Block 001 is selected and highlighted. The blocks are:
  - 001: Assign: `bEnable=ACTIVE_BOOL` (Enable the motor)
  - mainLoop:
  - 002: Jump to `reverseRotation` if: `DigitalInput(1)=ACTIVE_BOOL` (If the digital input 1 is active)
  - 003: Assign: `RefVel=100` (Set low speed rotation)
  - 004: Jump to `mainLoop` always (Jump to beginning)
  - reverseRotation:
  - 005: Assign: `RefVel=-100` (Set reverse low speed rotation)
  - 006: Jump to `mainLoop` always (Jump to beginning)
- Programming Tools:** A panel for configuring blocks. It includes tabs for Assignment, Jump/Wait, Math, Logic, Variables, and Configuration. The "Assignment" tab is active, showing a configuration for block 001 where `bEnable` is assigned to `ACTIVE_BOOL`. There are fields for "Block entry label" and "Block number" (001), and an "Update" button. Below this, there are sections for "Always", "Conditioning", and "Function" with dropdown menus and assignment operators. A "Comment" field contains "Enable the motor".
- Drive Status:** A panel showing the status of the drive. It includes sections for Digital I/O, Analog I/O, and Motion. The Motion section shows parameters like Speed (0,0 rpm), Angle (0,0 Degree), and Current (DIS Arms). There is also a "Faults / Errors" section.
- Status bar:** At the bottom, it displays "Compiling succeeded. Application program memory used 1,9%".

Arrows from the text labels point to the following elements in the interface:

- New application program (to the New icon)
- Open the application program (to the Open icon)
- Save the application program (to the Save icon)
- Export application program in text format (to the Export icon)
- Import application program in text format (to the Import icon)
- Copy and remove the selected block (to the Copy icon)
- Copy the selected block (to the Copy icon)
- Insert the copied block (to the Paste icon)
- Information on the drive (to the Drive icon)
- Back to program section form (to the Back icon)
- Compile the application program (to the Compile icon)
- Download the application program into the drive (to the Download icon)
- Field BUS setup (to the Field BUS icon)
- Settings (to the Settings icon)
- LAM Technologies (to the LAM Technologies icon)
- Quit the program (to the Quit icon)
- Status bar (to the bottom status bar)
- Block number (to the block number in the application program list)
- Block enable (to the checkbox in the application program list)
- Application program (to the application program list)
- Diagnostics (to the Drive Status panel)
- Programming tools (to the Programming Tools panel)

#### 4.3.1 New application program

Clicking on the *New application program* button the application program eventually present is deleted and the programming tools return to their default status.

#### 4.3.2 Open the application program

Clicking on the *Open the application program* button it is possible to upload a file containing an application program previously saved.

#### 4.3.3 Save the application program



Clicking on the *Save the application program* button it is possible to save the application program and all the associated parameters to be able to successively upload them and quickly set other drives in the same way.

#### 4.3.4 Export application program in text format

Clicking on the *Export application program in text format* button it is possible to save the program in text format, for example to successively print it.

#### 4.3.5 Copy and remove the selected block

Clicking on the *Copy and remove the selected block* button the selected block (highlighted by an sketched squared) is cut from the list and copied into the scratchpad.

#### 4.3.6 Import application program in text format

Clicking on the *Import application program in text format* button it is possible to load the program in text format. This function makes it possible to modify the program externally using any text editor.

The syntax of the file must match that used for export by *UDP Commander*, otherwise the import fails. If in doubt on how a particular block must be written for the import to succeed it is recommended to export the same block and view the syntax used by *UDP Commander*.

#### 4.3.7 Copy the selected block

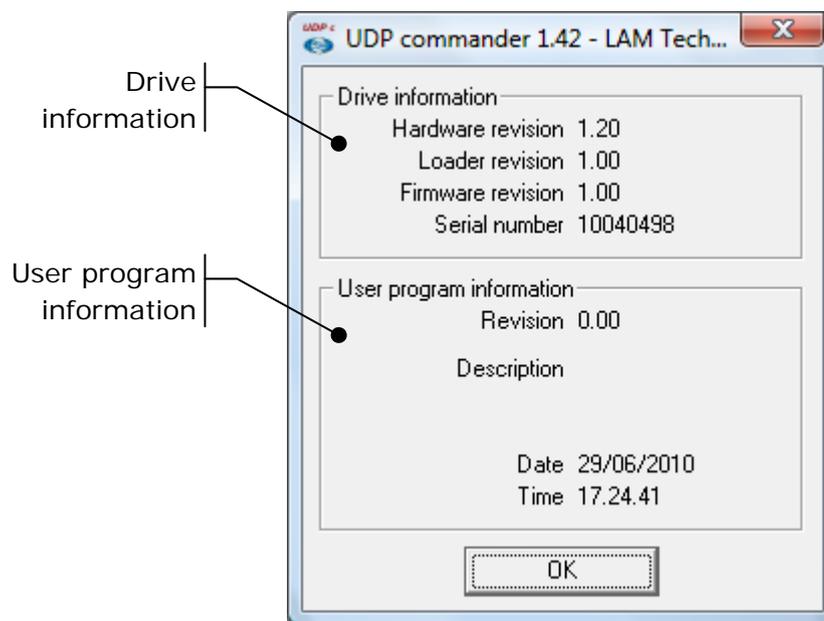
Clicking on the *Copy the selected block* button the selected block (highlighted by a sketched squared) is copied into the scratchpad.

#### 4.3.8 Insert the copied block

Clicking on the *Insert the copied block* button the block present in the scratchpad gets ready to be inserted (the mouse punter changes).

### 4.3.9 Information on the drive

Clicking on the *Information on the drive* button it appears a window that includes the characteristic data of the connected drive as displayed in the below image.



#### 4.3.9.1 Drive information

The *Drive information* frame shows the hardware revision of the device, the revision of the installed Loader, the firmware revision and the serial number of the drive.

#### 4.3.9.2 User program information

In the *User program information* frame there are the description and the revision of the user program assigned through the *Configuration* panel inside the *Programming tools* (for more information see paragraph 4.3.25.6 Configuration).

The last two rows show the date and the hour in which the user program has been download into the drive (this information are related to the PC clock).

### 4.3.10 Back to program selection form

Clicking on the *Back to program selection form* button the window is closed to go back to the main one where it is possible to make the manual selection of the product or to make the connection with the same.

### 4.3.11 Compile the application program

Clicking on the *Compile application program* button the application program is compiled and ready to be transferred in the drive. In this phase eventual errors, such as for example the lack of a jump destination label, are notified through pop up messages.

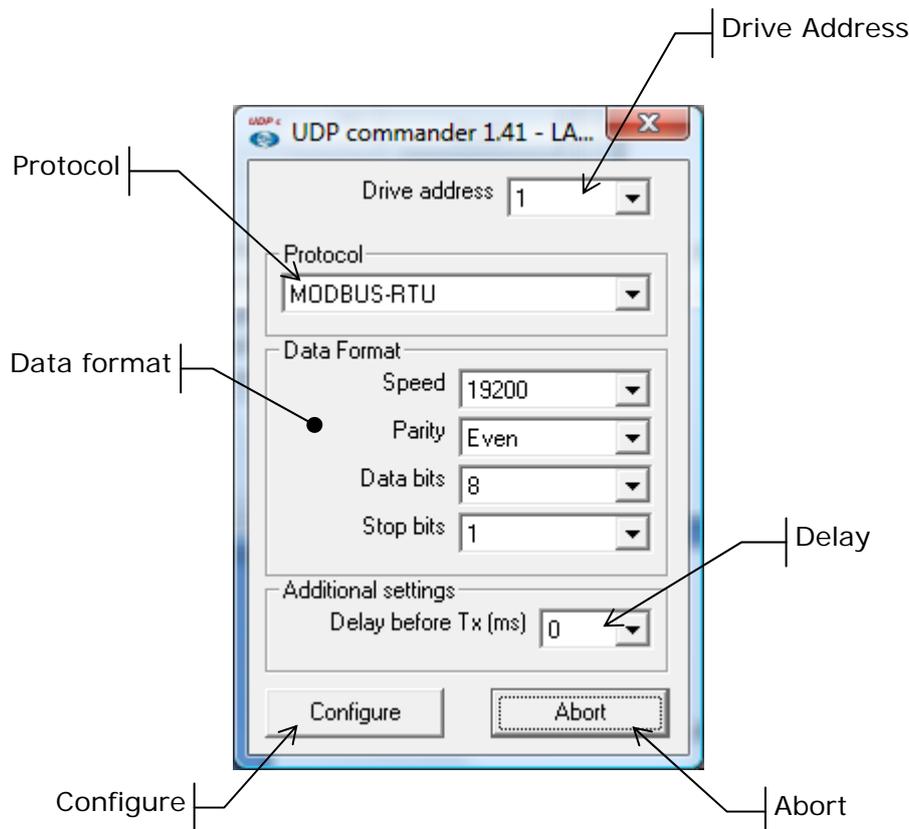
### 4.3.12 Download the application program into the drive

Clicking on the *Download the application program into the drive* button the compiled application program is transferred into the memory of the drive to be executed.

At the end of the transfer *UDP Commander* predisposes itself for execution and debug of the user program (for more information see paragraph 4.4 DS30 and DS5x series drive execution window).

### 4.3.13 Field BUS setup

The *Field BUS setup* button is activated when a drive belonging to the DS5x series is connected and it allows to access the communication parameters configuration window.



#### 4.3.13.1 Drive address

It allows to assign the drive identification address to the net between 1 and 247. The control master will use that value each time it will have to communicate with the drive.

#### 4.3.13.2 Protocol

It allows to select the communication protocol.

#### 4.3.13.3 Data format

Inside the *Data format* frame there are 4 menus which allow to select the communication baud rate, the parity, the number of the data bits and the number of the stop bits.

To successfully connect to the drive is necessary to setup the same data format exactly alike the one in use in the control master.

#### 4.3.13.4 Delay

In some physical layers, as for example *RS485*, the communication is *half duplex* type. In these cases the master transmits the message to the drive and successively puts itself in hearing the reply. In some master devices the time necessary to pass from transmission to reception can be of many ms and in this case there is the possibility that the reply sent by the drive is lost as too quick. Setting a delay it is possible to postpone the drive reply transmission to let the master device put itself in reception mode.

#### 4.3.13.5 Configure

Clicking on the *Configure* button the bus configuration is permanently transmitted into the drive.

#### 4.3.13.6 Abort

Clicking on the *Abort* button the configuration window is closed without modifying the configuration present in the drive.

#### 4.3.14 Settings

Clicking on the *Settings* button a window will appear allowing to set up the *UDP Commander* behaviour.



#### 4.3.15 Skip download

With this option enabled the download of the program will not be executed if in the drive is already loaded the same version. In this way it is possible to view the activity of the program and access the contents of registers and variables without interfering with the normal functioning of the drive.

#### 4.3.16 Overwrite warning

Selecting this option a message will promptly notify when the program present in the drive is going to be overwritten.

#### 4.3.17 LAM Technologies

Clicking on the *LAM Technologies* button an image with all the company contacts will appear.

#### 4.3.18 Program Quit

Click on the *Program Quit* button to quit the *UDP Commander*.

#### 4.3.19 Status bar

It gives information on last operation executed.

#### 4.3.20 Application program

The frame includes all the instruction blocks composing the application program.

**4.3.21 Block number**

It is a progressive number that identifies the instruction block.

**4.3.22 Block enable**

If flagged it includes the instruction block into the compiling process. If not flagged the block is not compiled and therefore not executed.

This functionality can be useful to exclude some block without having to take them off of the program.

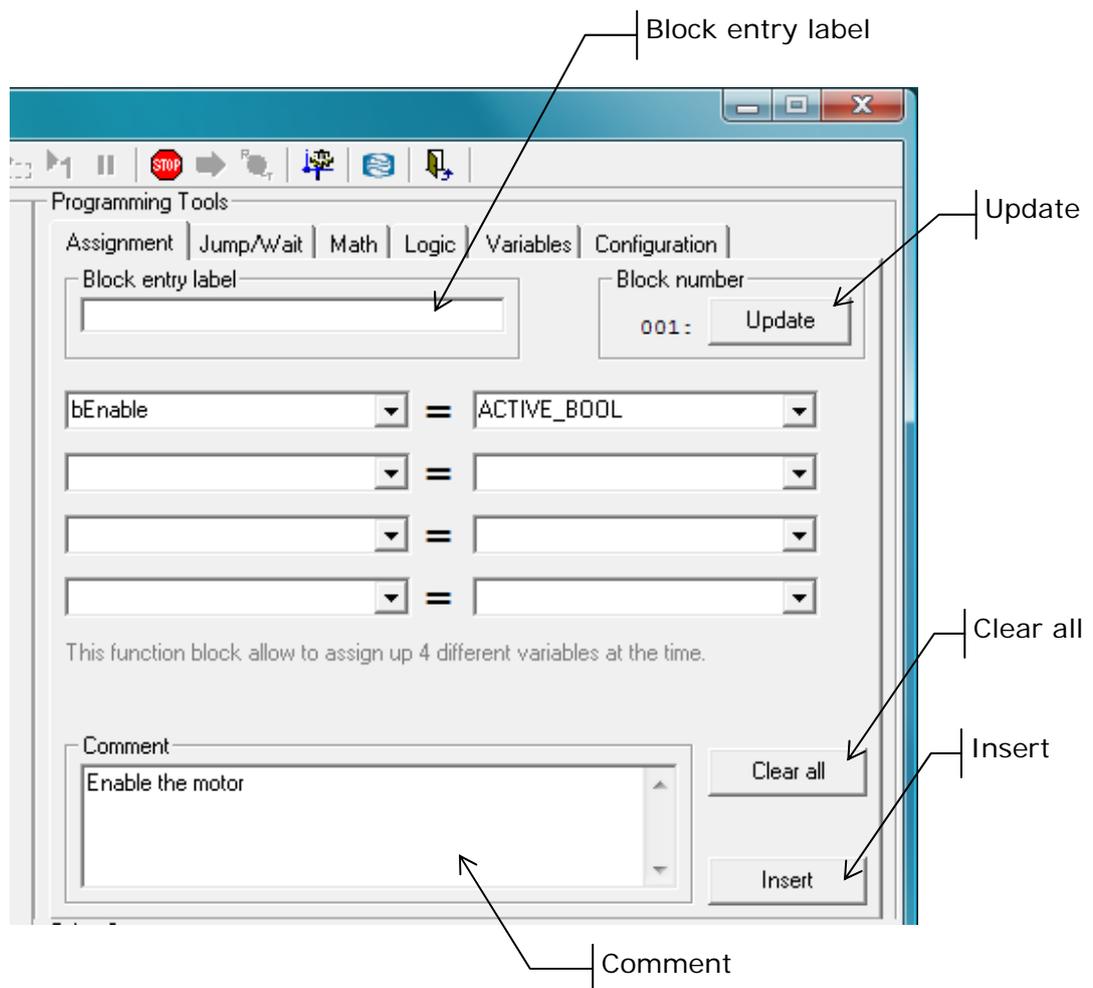
**4.3.23 Information and diagnostics**

Inside the frame there are the information about the inputs and outputs status, both digital and analog, the motor status and the presence of eventual alarms.

**4.3.24 Programming tools (introduction)**

From the programming tools area is possible to choose the instruction blocks that placed in sequence will give origin to the application program.

Some fields and buttons are common to all the instruction block as displayed in the below image.



#### 4.3.24.1 Block entry label

In this field can be inserted an alphanumeric string useful to identify the block (for example to execute a jump to itself).

#### 4.3.24.2 Update

Clicking on the *Update* button the block highlighted in the application program space (see paragraph 4.3.20 Application program) is replaced with the block activated in the programming tools.

#### 4.3.24.3 Clear all

Clicking on the *Clear all* button the whole content of the instruction block activated in the programming tools is set to the default value.

#### 4.3.24.4 Insert

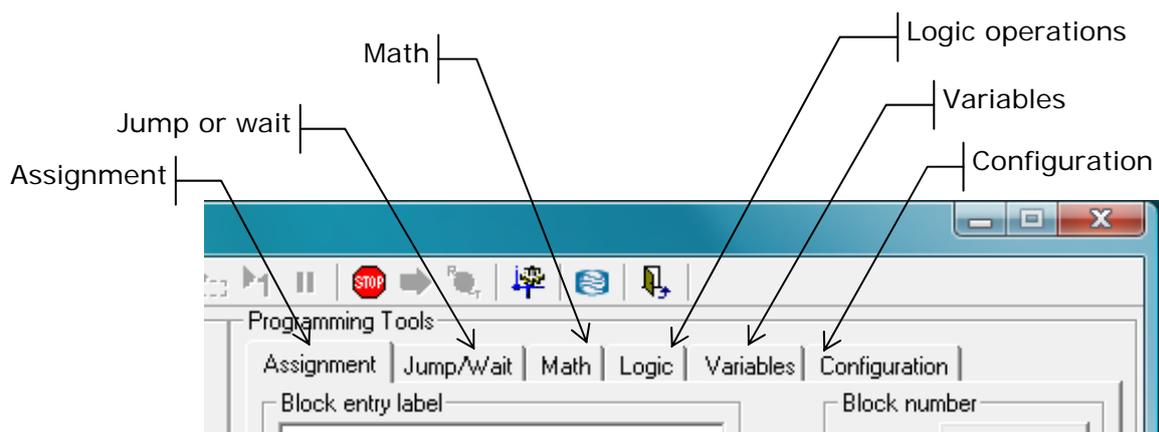
Clicking on the *Insert* button it is possible to insert the instruction block in the space on the left reserved to the application program.

#### 4.3.24.5 Comment

It is a field where it is possible to insert a comment to describe the functionality performed by the block or to note down important information.

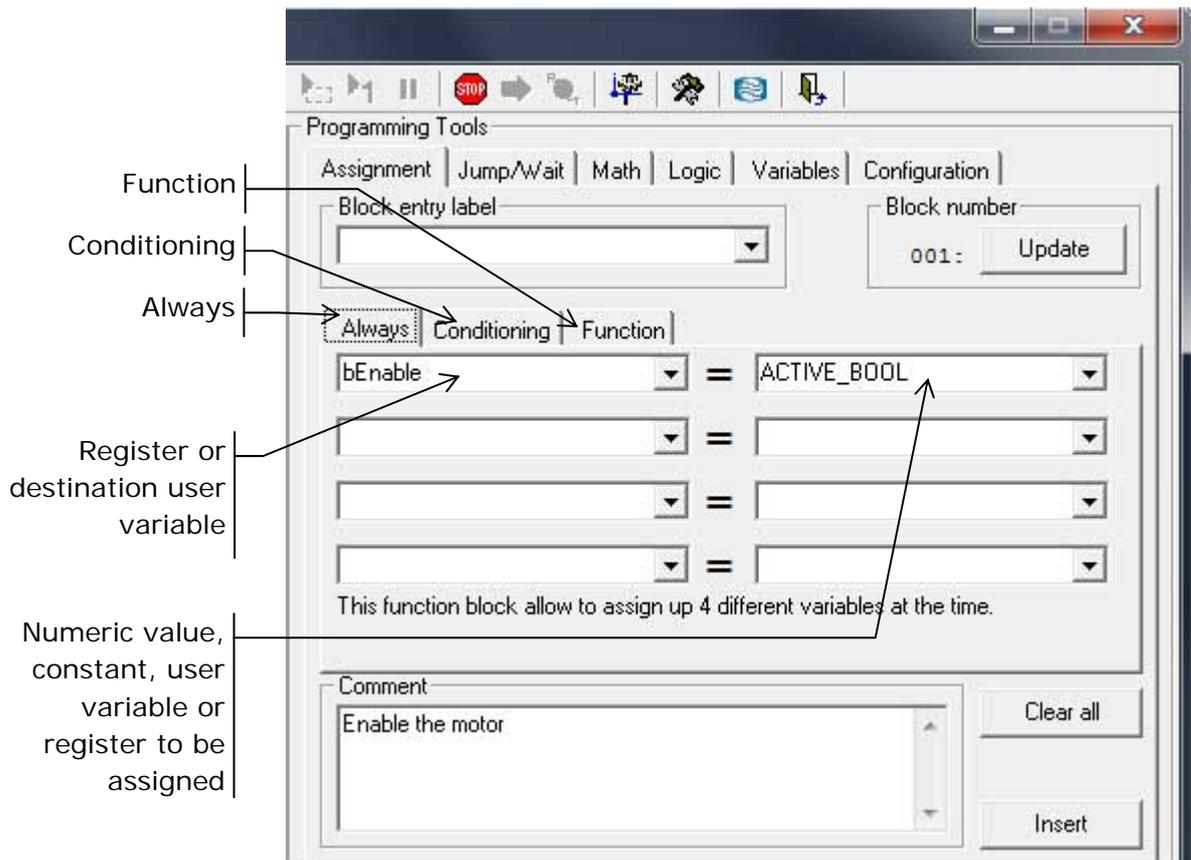
#### 4.3.25 Programming tools (details)

The following image shows the various tabs which contain the programming tools and the available configurations.



4.3.25.1 Assignment

The tab contains three under tabs which allow to select as much different instruction blocks. .



4.3.25.1.1 Always

Selecting the Always tab it is possible to insert an assignment block able to assign to a register or user variable an absolute value (a number) or the content of another register or variable.

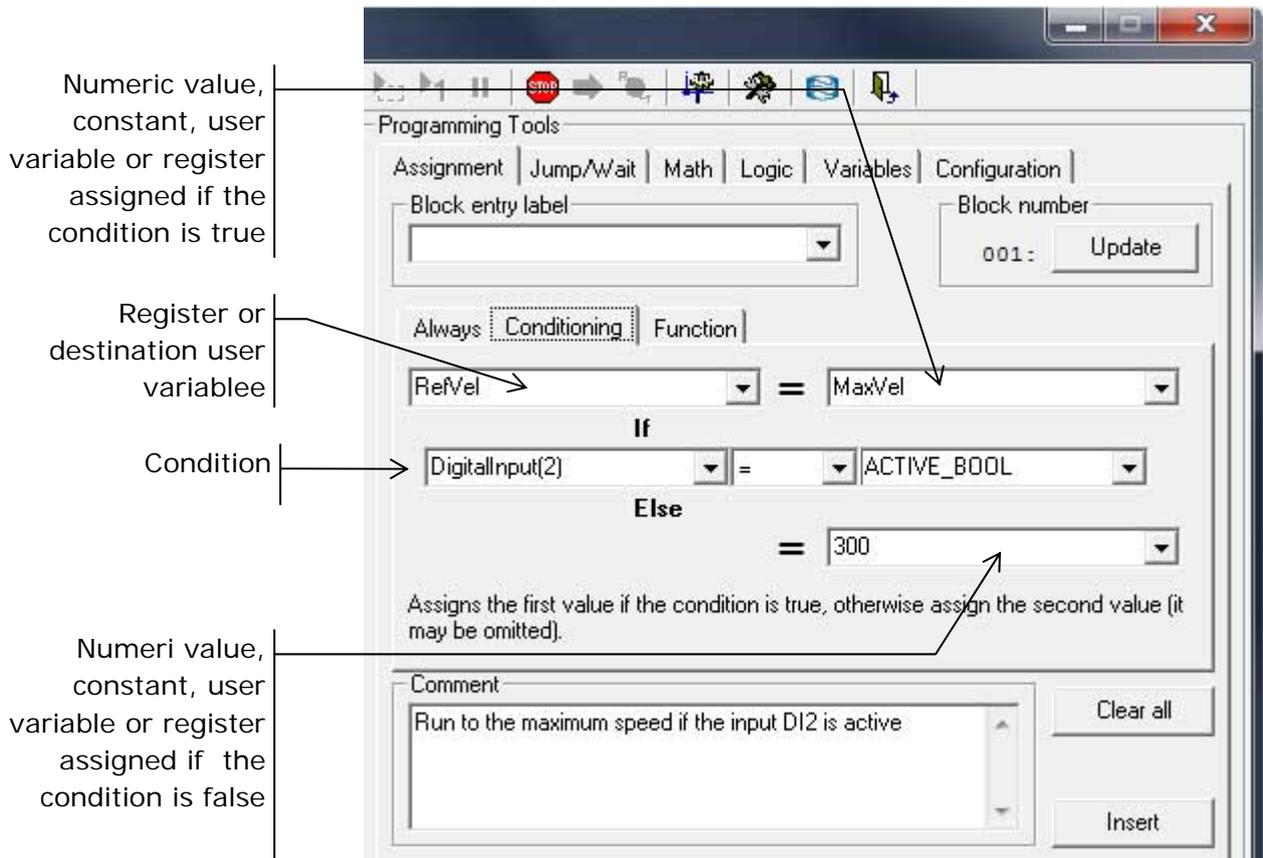
It is possible to assign up to 4 registers or user variables at time in each instruction block. To executer a greater number of assignments it is sufficient to put in cascade more instruction blocks.

Opening the menu on the left of the sign “=” it is possible to choose the register or destination variable (alternatively it is possible to digit the name manually) while in the menu on the right it is possible to digit the value to assign or to choose it from the ones in the list.

4.3.25.1.2 Conditioning

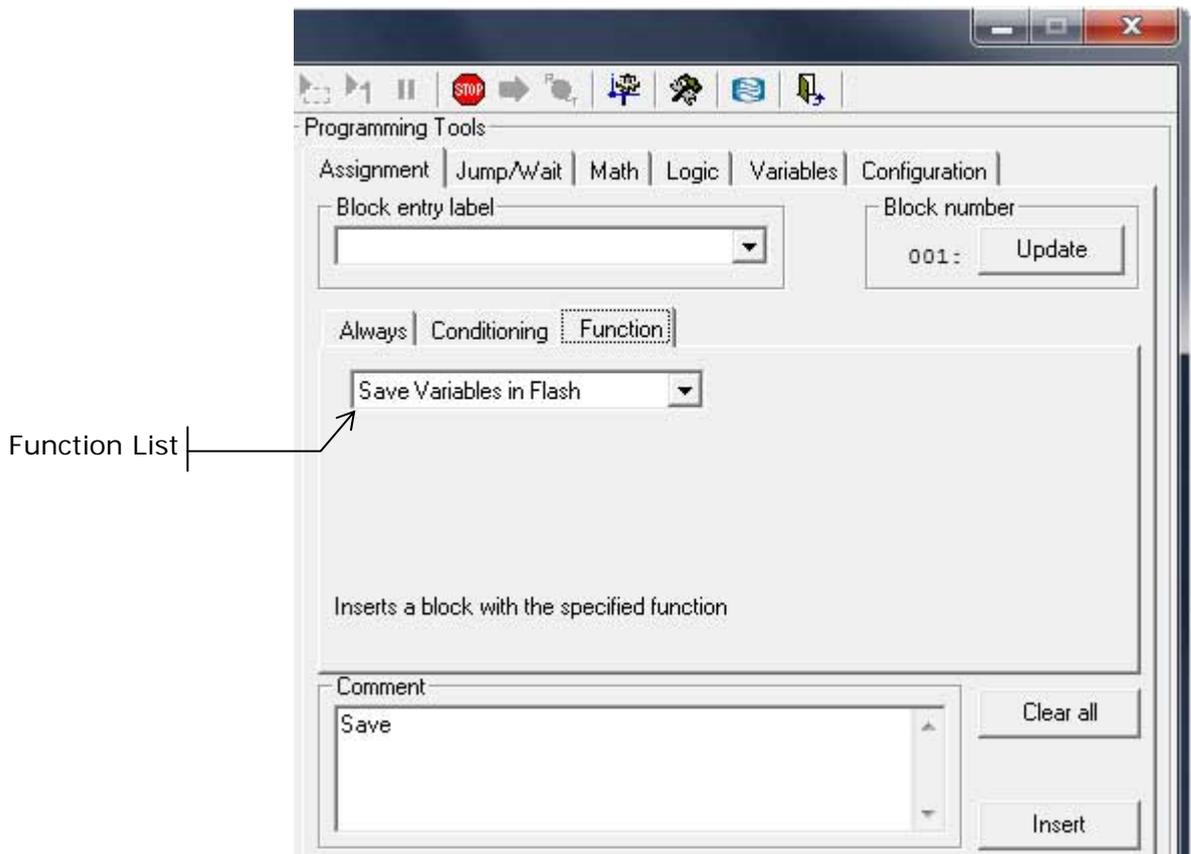


The assignment conditioning is a very useful feature that allows to assign a value to a register or a variable only if the specified condition is true. It is also possible to define a second optional value which is assigned to the register or variable if the condition is false (*else* case). . If the optional value is not specigied, and the condition is false, the register or the variable remain unchanged.



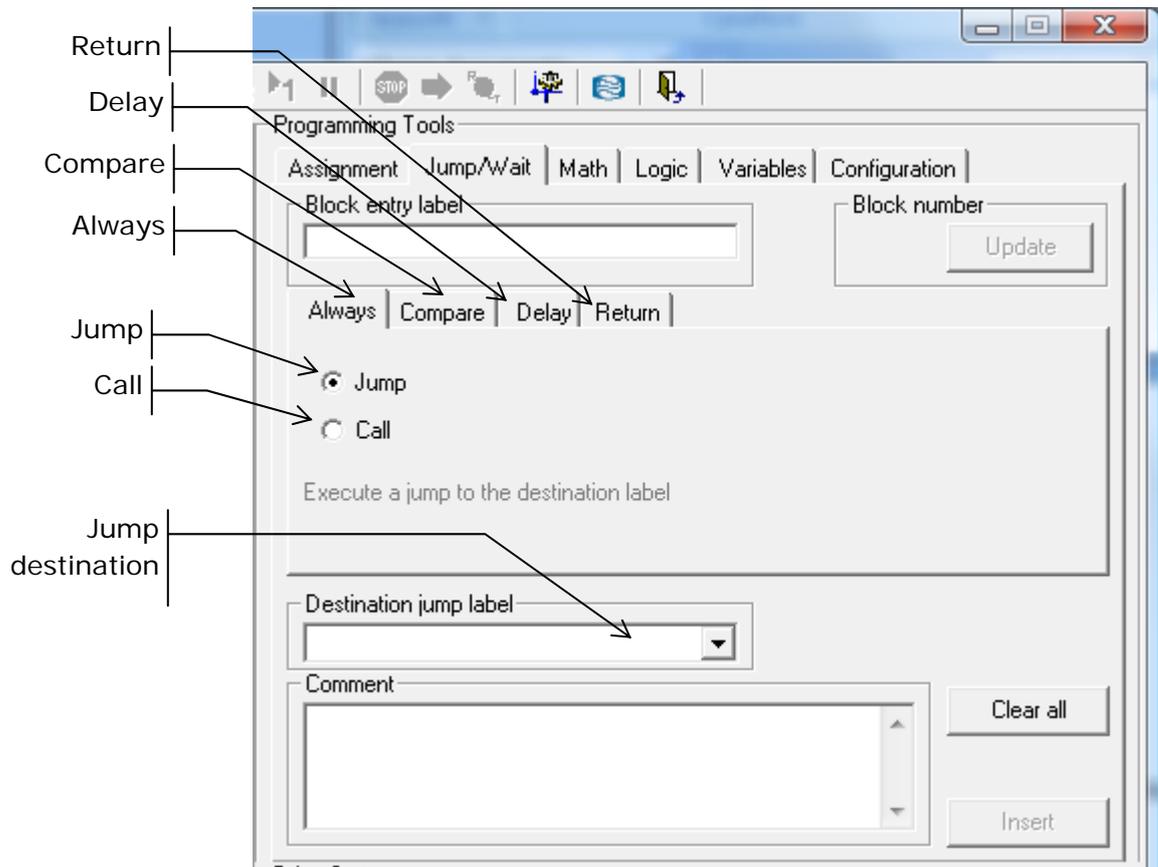
#### 4.3.25.1.3 Function

Selecting the *Function* tab it is possible to insert one of the available functions that can be selected from the list.



### 4.3.25.2 Jump or wait

The tab contains 4 under tabs which allow to select as many different instruction blocks.



#### 4.3.25.2.1 Always

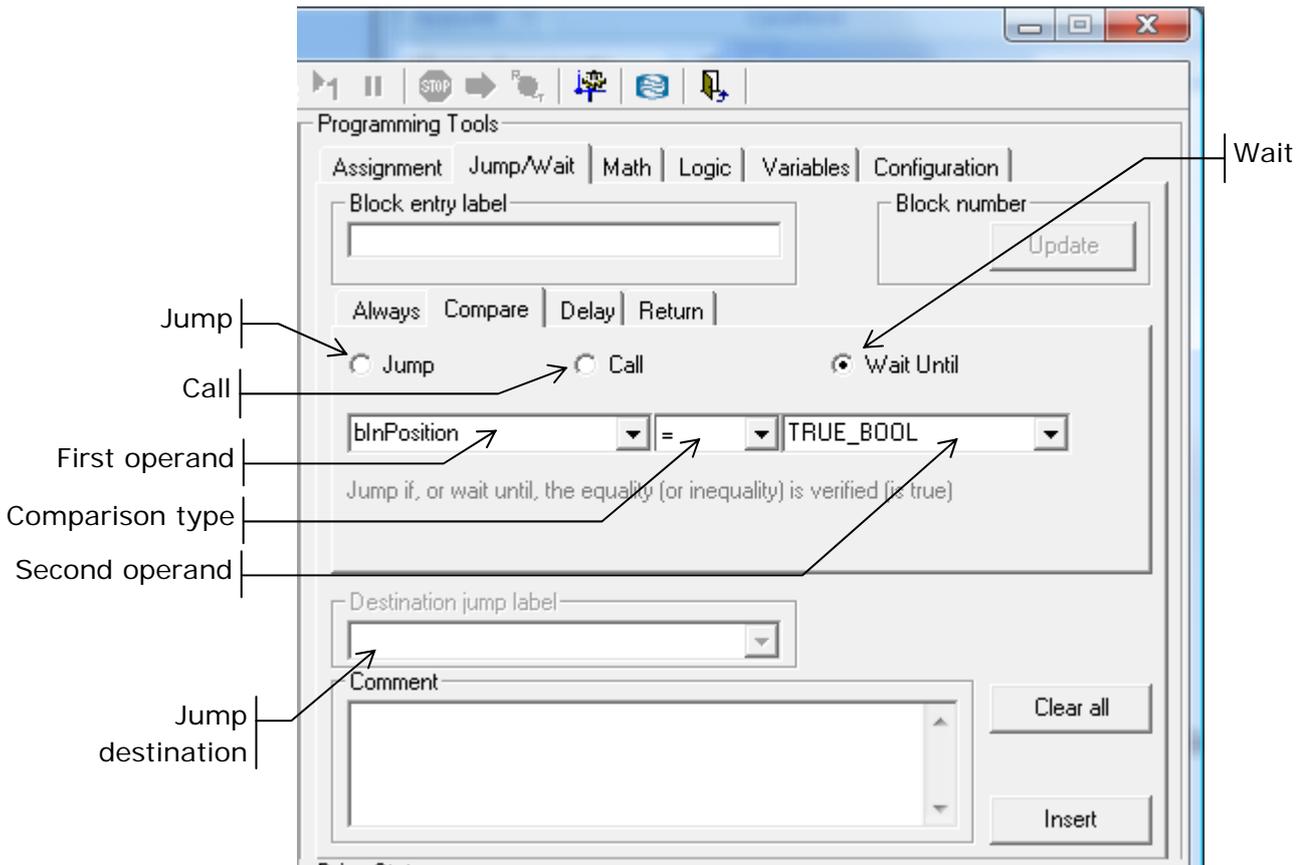
Selecting the *Always* tab it is possible to insert a block which will generate a jump to another block (the destination block) with the entry label (for more information see paragraph 4.3.24.1 Block entry label) exactly alike to the alphanumeric string present in the *Jump destination* field.

The *Jump destination* field can be manually compiled or can be selected from one of the labels in the dropdown list (the list is automatically updated each time a block is inserted).

The *Jump* or *Call* option allows to choose if to execute a jump without return or a jump with return. In this last case the drive memorizes the identifying code of the block subsequent to the jump instruction (return block) and when it meets the *Return* instruction block the execution of the program turns back to the return block, i.e. the block subsequent to the block which generated the jump (note that the reference to the return block is overwritten each time a *Call* jump is executed, therefore the *Return* instruction is always referred to the last *Call* executed).

#### 4.3.25.2.2 Compare

Selecting the *Compare* tab it is possible to insert an instruction block which will execute the jump only if a predetermined condition is true or will wait till when the specified condition becomes true (*Wait* option).



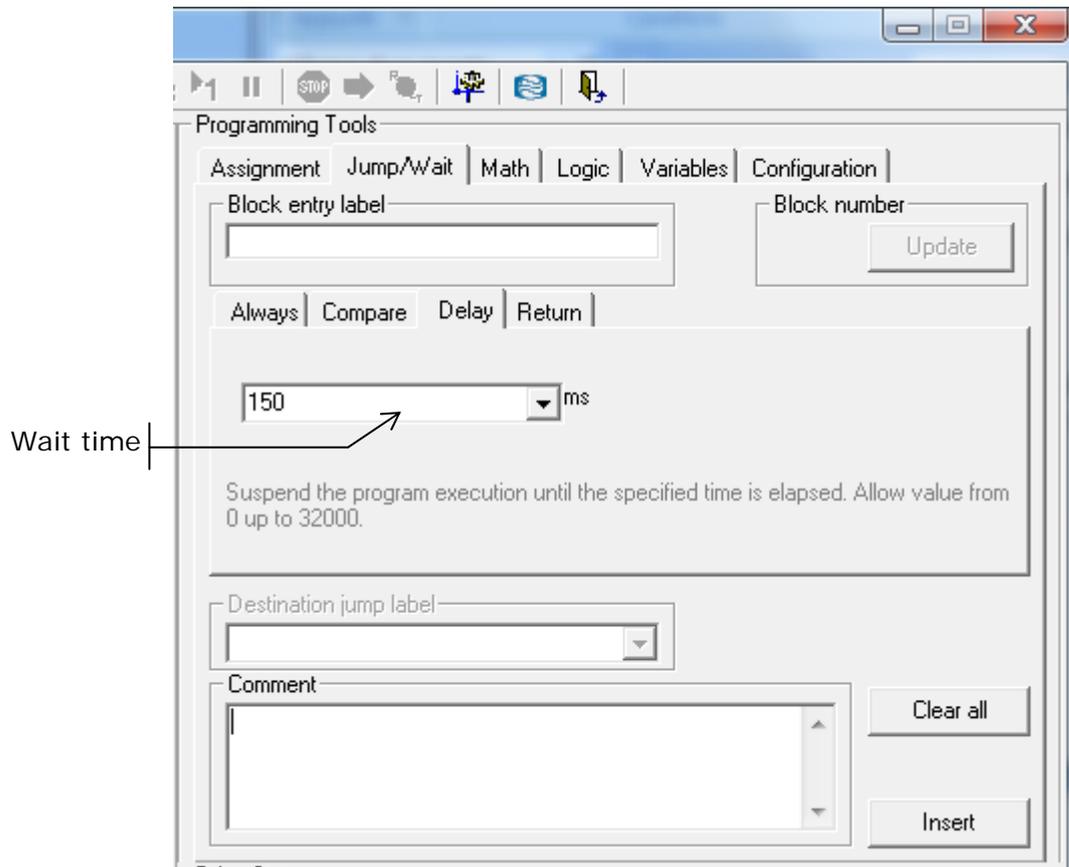
The *Jump* or *Call* option allows to choose if to execute a jump without return or a jump with return. In this last case the drive memorizes the identifying code of the block subsequent to the jump instruction (return block) and when it meets the *Return* instruction block the execution of the program turns back to the return block, i.e. the block subsequent to the block which generated the jump (note that the reference to the return block is overwritten each time a *Call* jump is executed, therefore the *Return* instruction is always referred to the last *Call* executed). Also note that the jump will be executed only if the equation defined by the *First operand*, by the *Comparison type* and by the *Second operand* is true, on the contrary the execution of the program will continue with the next instruction block.

Selecting the *Wait* option the block will suspend the execution of the program till when the equation defined by the *First operand*, by the *Comparison type* and by the *Second operand* is true, when it happens the execution of the program continues with the next block.

The *First operand*, the *Second operand* or the *Jump destination* field can be manually compiled or chosen in the dropdown list.

## 4.3.25.2.3 Delay

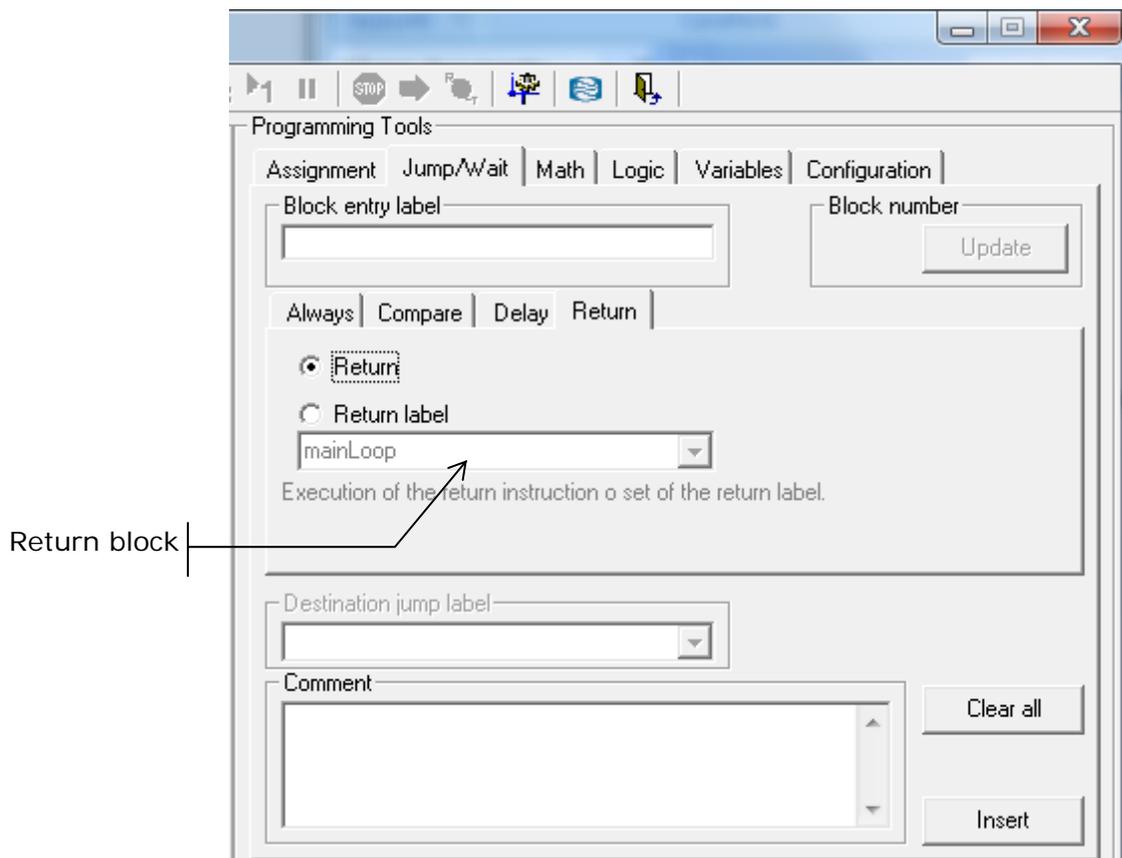
Selecting the *Delay* tab it is possible to insert a block which will suspend the execution of the program for the time set in the *Delay time* field. In this field it is possible to digit a numeric value or to select one in the dropdown list. It is also possible to select a register or an user variable, in this case the suspension term will depend to the value contained in the register or in the variable. Each unit is equivalent to 1ms and it is possible to set values between 0 and 32000.



## 4.3.25.2.4 Return

Selecting the *Return* tab it is possible to create two different instruction blocks; the first will make jump to the return block while the second will allow to setup the return block itself.

When the *Return* option is selected the instruction blocks gives back the control to the return block (the instruction block subsequent to the one that has executed the *Call*) while if the *Return label* option is selected the instruction block will modify the reference to the return block, setting it as specified in the *Return block* field. The *Return block* field can be manually compiled or can be selected one label in the dropdown list (the list is automatically updated each time a block is inserted).



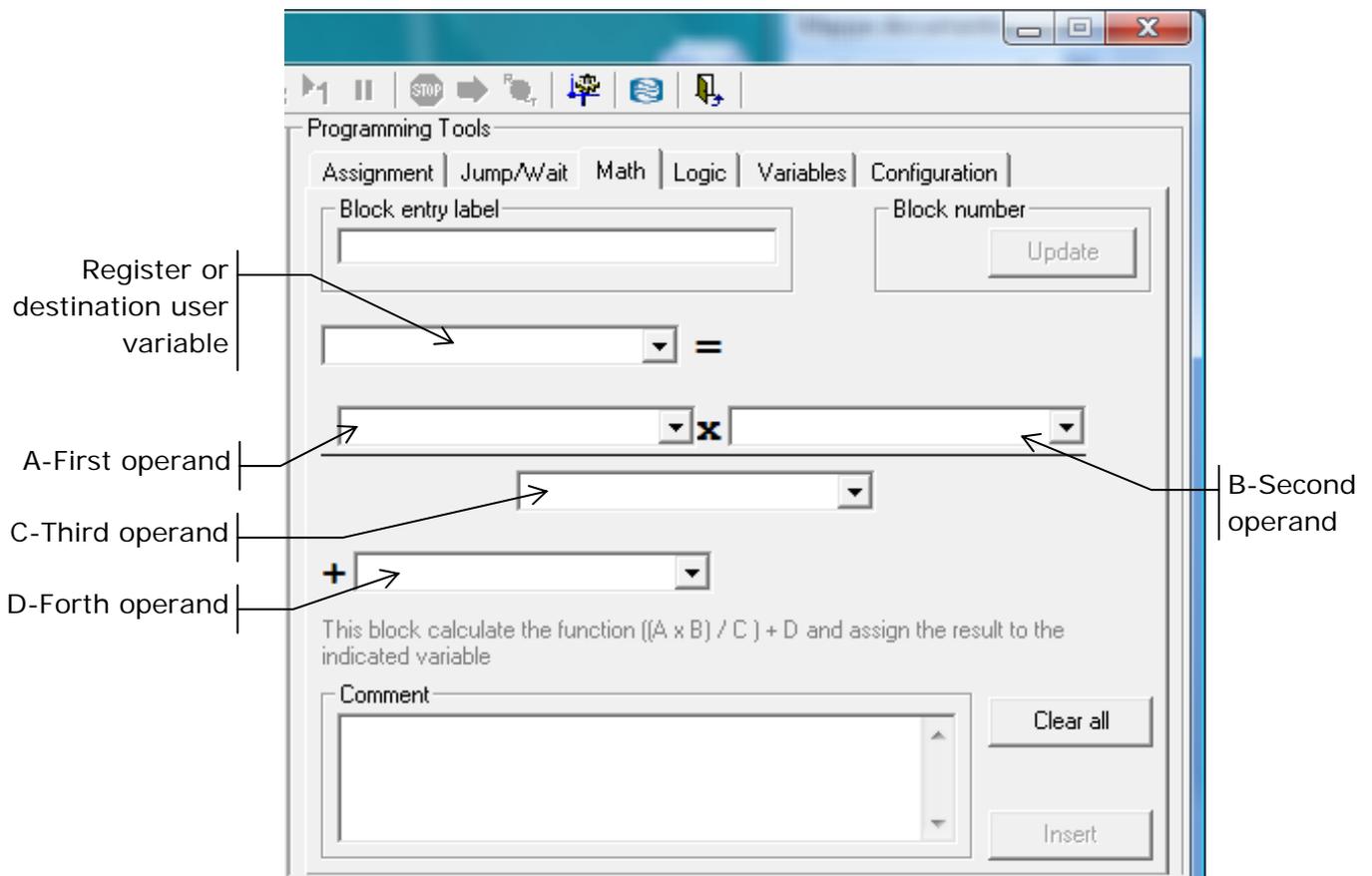
4.3.25.3 Math

The Math tab allows to create an instruction block able to execute mathematical calculations with numeric constants, registers and user variables.

The calculation applied is  $((A \times B) / C) + D$

If a simpler calculation is needed it is sufficient to leave empty the operand fields not used.

The first, the second and the fourth operand can be numbers, registers or user variables. The division coefficient (third operand) must be necessarily a power of 2 chosen in the dropdown list.



4.3.25.4 Logic operations

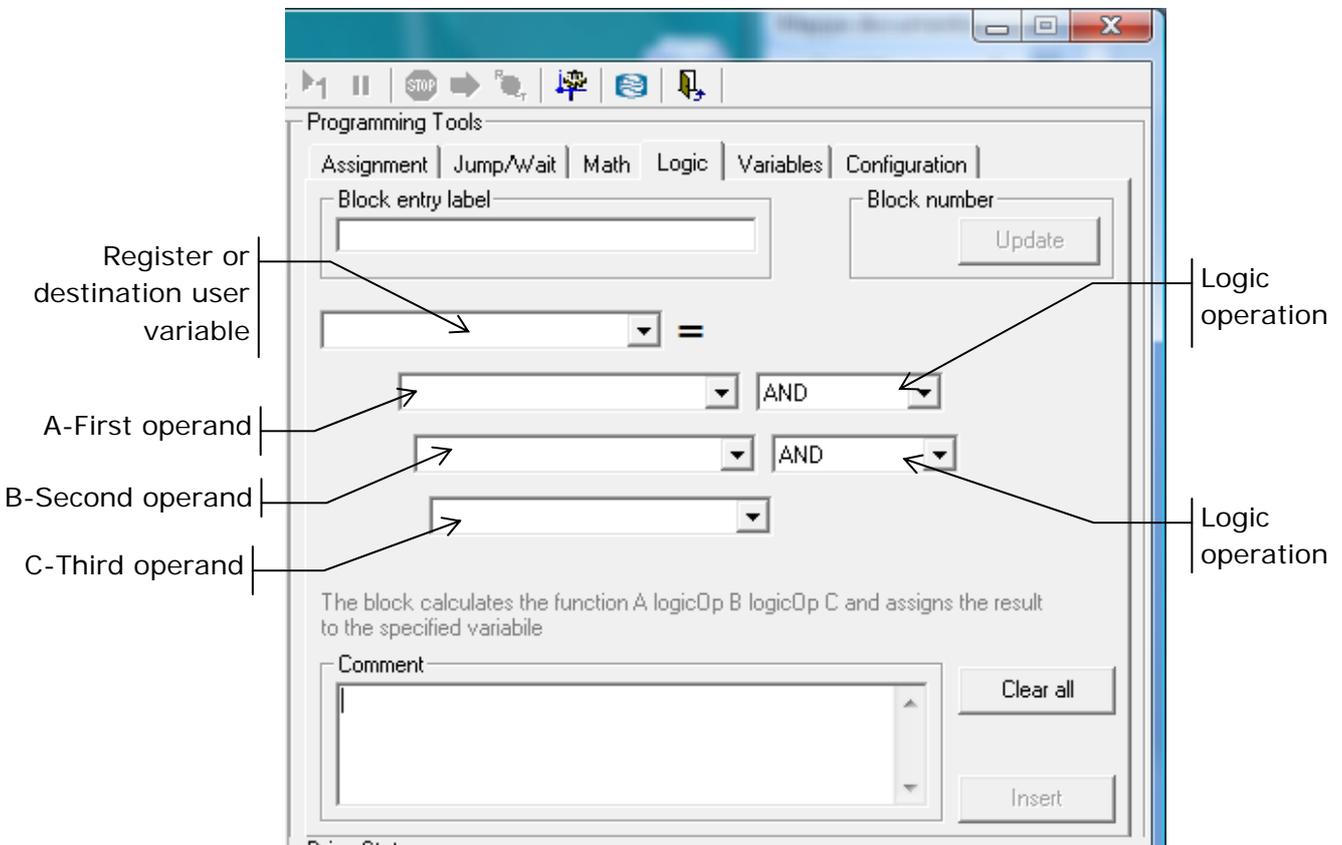
This tab allows to create an instruction block to handle bits of registers or of user variables.

One only instruction block can execute up to two logic operations at a time. The operation applied is:

$$(A \text{ opLogic } B) \text{ opLogic } C$$

Where A, B and C are three operands and opLogic is the chosen logic operation.

The SHIFT logic operation shift the content of the operand on the left by the number of bits specified by the operand in the right. In the case of SHIFT\_R the bits are shift towards right, while in the case of SHIFT\_L the bits are shift towards left (the remaining bits are put to 0).



4.3.25.5 Variables

The *Variables* tab allows to declare user variables which can be freely used inside the instruction blocks to compose the application program.

The *Variable name* field must be filled with the mnemonic assigned to the variable, while from the *Dimension* dropdown list is chosen the dimension in byte of the variable itself.

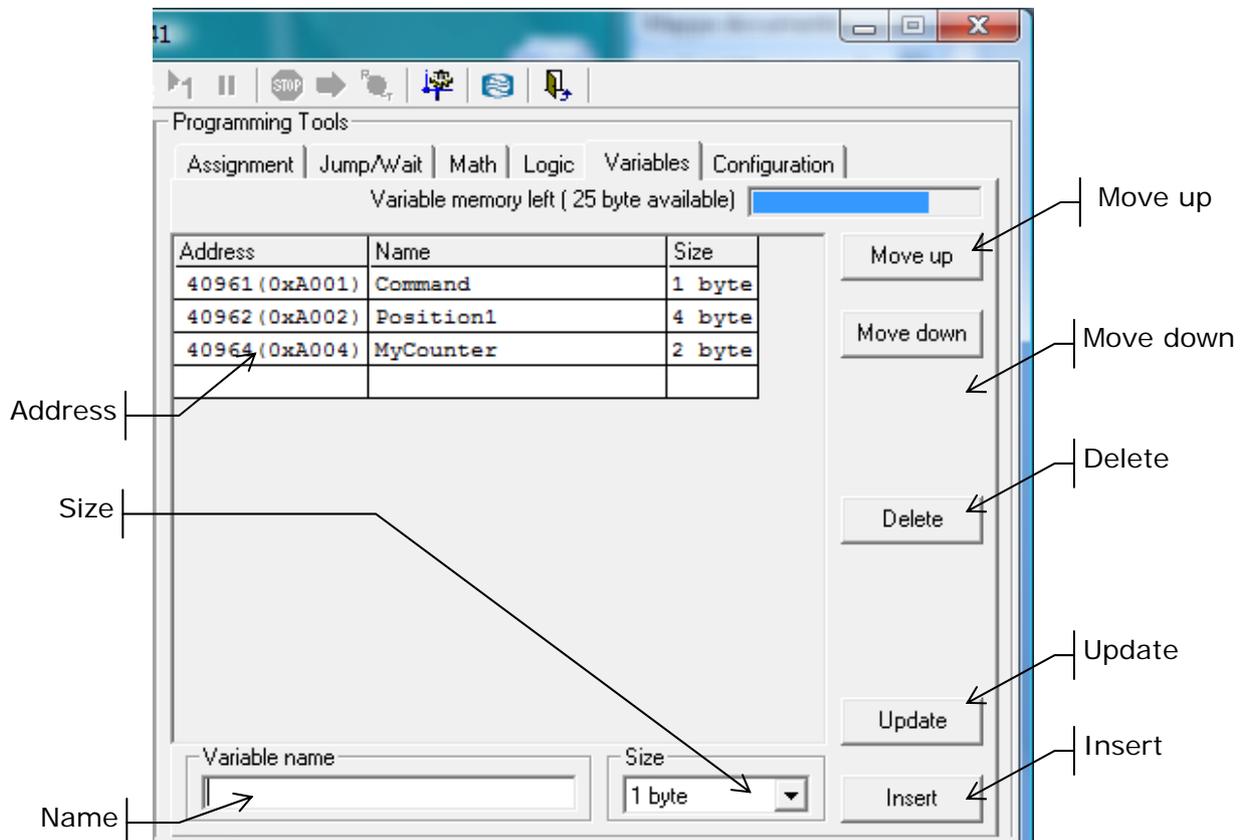
It is possible to choose a dimension among 1, 2, 3 or 4 bytes. The following chart displays the value range that the variable can contain according to the dimension:

Dimension	Min	Max
1 byte	-128	+127
2 bytes	-32768	+32767
3 bytes	-8388608	+8388607
4 bytes	-2147483648	+2147483647

Clicking on the *Insert* button the variable is inserted in the last free position in the variables list.

When a variable is highlighted in the variables list it is possible to delete it clicking on the *Delete* button or to move it through the *Move up* and *Move down* buttons.

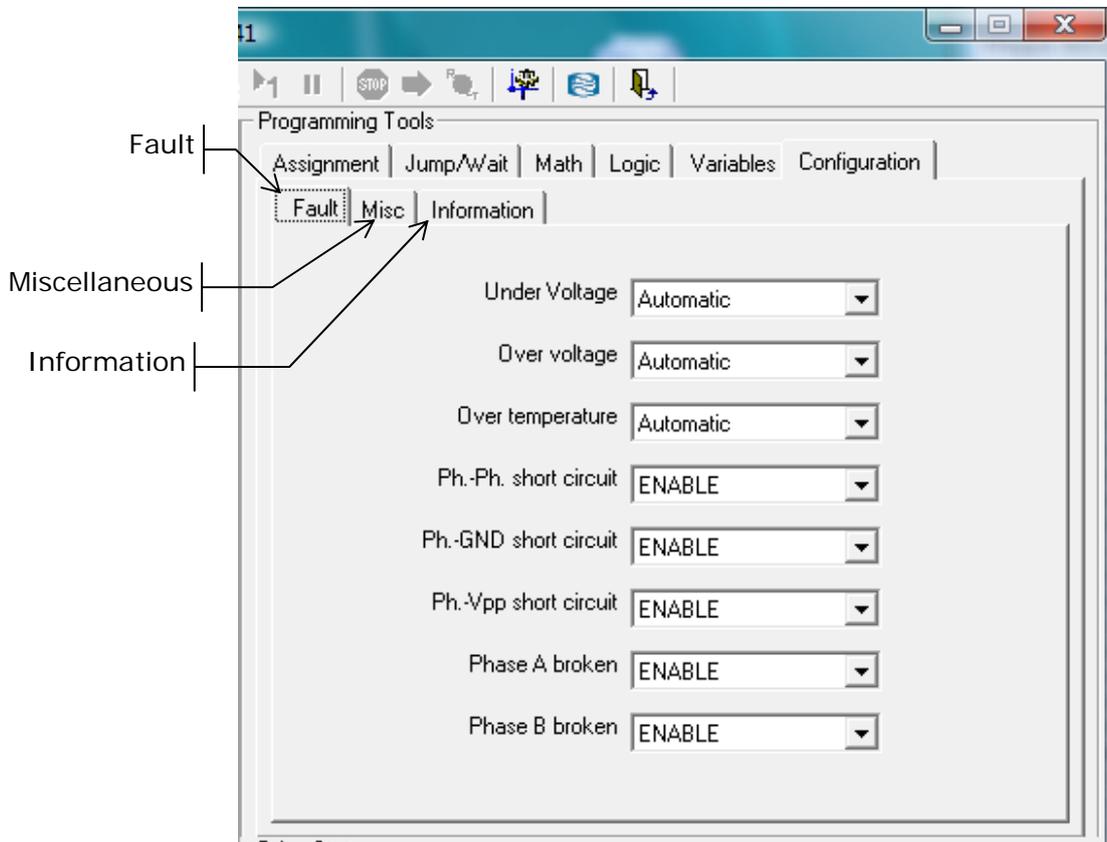
The *Address* column, in the variables list, displays the assigned address of each single variable. Such value is essential to access through the field bus to the variable itself. The address is automatically assigned and it depends to the variable dimensions and to the position in the list.



### 4.3.25.6 Configuration

The *Configuration* tab includes several options which can be permanently stored inside the drive but that cannot be changed during the execution of the program.

There are totally three under tabs.



#### 4.3.25.6.1 Fault



The *Fault* under tab allows to define the action necessary to remove an alarm or a fault signal.

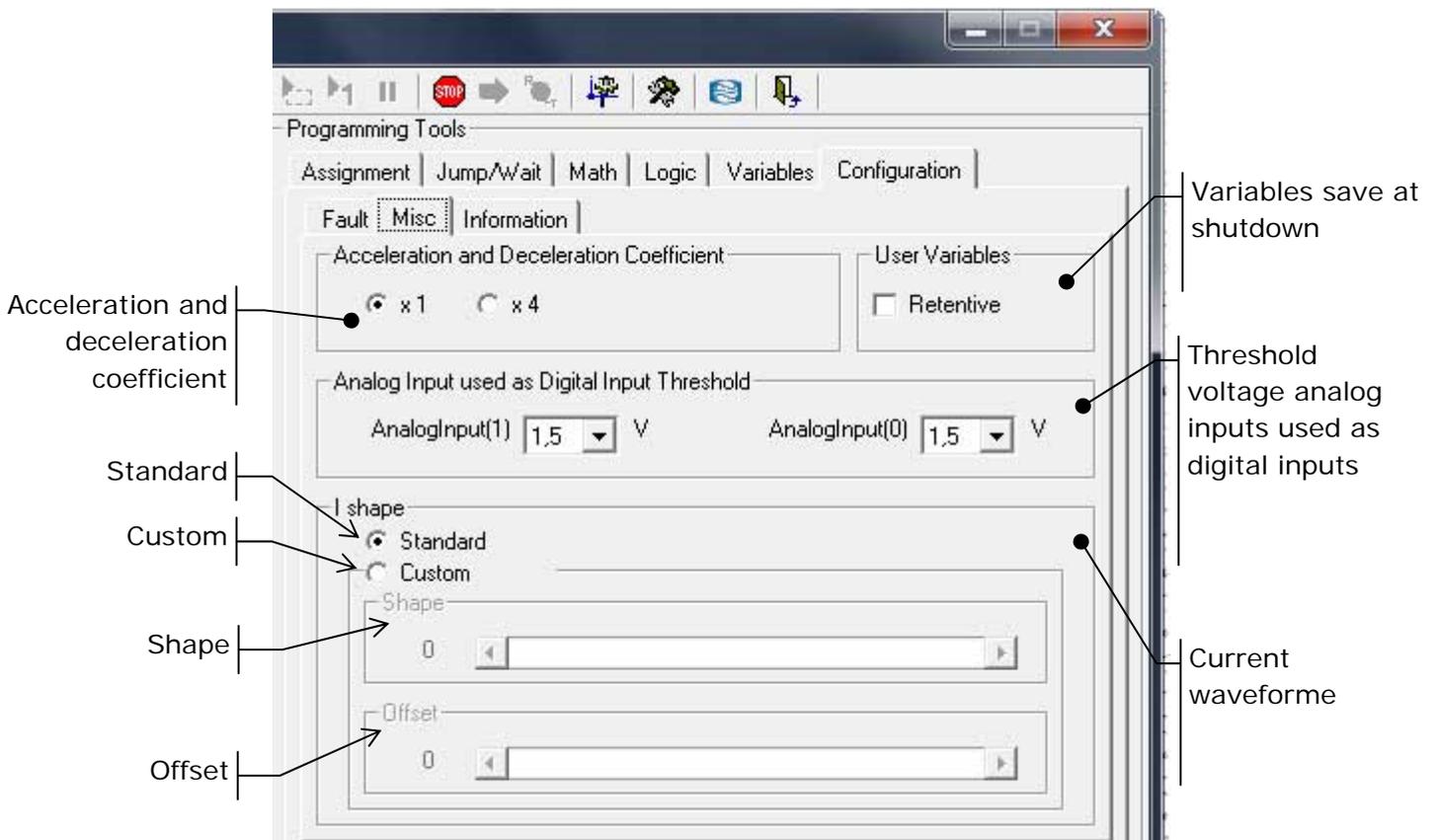
- *Automatic*, the drive is automatically enabled at the end of the alarm condition.
- *Permanent*, the alarm signal remains till the drive is powered off.
- *ENABLE*, the alarm signal remains till the drive is disabled.
- *Disabled*, the alarm signal is suppressed (for security reasons some alarms cannot be deactivated).

For more information on the several alarms and faults see the user's manual of the drive.

## 4.3.25.6.2 Miscellaneous

The *Miscellaneous* undertab contains the following settings

- Multiplication coefficient of the acceleration
- Activation of automatic variable save at shutdown
- Setting of the threshold voltage for the analog inputs used as digital inputs
- Setting of the current waveform



## 4.3.25.6.2.1 Acceleration and deceleration coefficient

Selecting the “x 4” option, in the *Acceleration and deceleration time* frame, the acceleration and deceleration values set in the program are quadrupled.

## 4.3.25.6.2.2 Variables save at shutdown

Enabling the save of variables at shutdown the drive will automatically copy in the flash memory the value of all the variables whenever the under voltage alarm is activated..At the next start of the program the variables will be loaded with the value previously saved in the flash memory.

The download of a new program will delete the values saved in the flash memory.

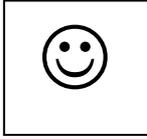
For more information see also the user’s manual of the drive.

## 4.3.25.6.2.3 Threshold analog inputs used as digital inputs

the analog inputs can be used also as digital inputs and it is possible to define the discrimination threshold voltage between 0 and 1 logic selecting it from the list.

#### 4.3.25.6.2.4 Current waveform

The *Current waveform* frame allows to intervene on the current waveform the drive supplies to the motor.



This feature, very rare to find in the common marketed drives, allows to better adapt the drive to the motor to obtain a smooth rotation.

Selecting the *Standard* option the current waveform the drive supplies to the motor is a pure sinusoidal wave. Selecting on the contrary the *Custom* option the *Shape* and *Offset* cursor keys are activated and allow to personalized the current waveform.

The *Shape* cursor key intervenes on the harmonic content of the current supplied to the drive. The optimal regulation value must be experimentally found and depends to the motor type. For the LAM Technologies motors this value is usually included between 0 and -4.

The *Offset* cursor key allows to intervene on the current offset in respect to the 0.

Usually this parameter does not need to be modified and can be left at the default value (zero).

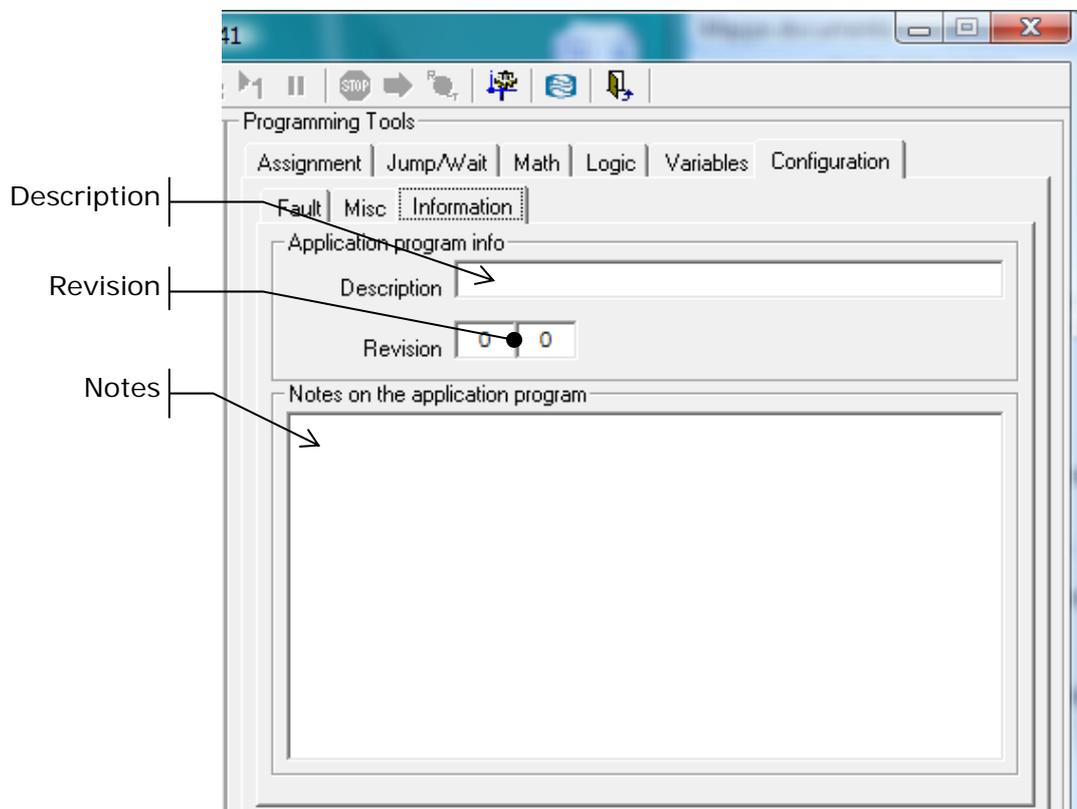
## 4.3.25.6.3 Information

The *Information* under tab can be used to assign a description and a revision number to the application program.

The *Description* field can contain a 32 characters alphanumeric string which is memorized inside the drive and that can be reread connecting with the drive itself.

The *Description* and the *Revision* are memorized inside the drive when the application program is transferred. The revision is stored in the **xx.yy** format where **xx** is the number inserted in the *Revision* field on the left and **yy** is the number in the field on the right.

The *Notes* field is not memorized inside the drive but it is saved together with the program file and can be useful to take notes of a description of the program, of eventual changes made, etc.



### 4.4 DS30 and DS5x series drive execution window



After that the application program has been compiled and downloaded inside the drive, the configuration window changes to supply the tools useful for the execution and the debug of the program.

The screenshot displays the 'Application program' window in the UDP Commander software. The interface includes a toolbar with various execution and debugging controls, a list of program instructions, and several monitoring panels.

**Toolbar Labels:**

- Start the application program execution
- Start until the selected box is reached
- Execute a single instruction block
- Suspend the application program execution
- Insert / remove break point
- Force the first block to be executed
- Perform the application program reset

**Application Program Instructions:**

- 001: Assign: bEnable=ACTIVE\_BOOL
- 002: Jump to reverseRotation if: DigitalInput(1)=ACTIVE\_BOOL (If the digital input 1 is active)
- 003: Assign: RefVel=100
- 004: Jump to mainLoop always (Jump to beginning)
- 005: Assign: RefVel=-100
- 006: Jump to mainLoop always (Jump to beginning)

**Debug Tools Panel:**

Application program status: STOP, Executing Block: 1, Follow the program (checkbox)

Name	Value (Dec)	Value (Hex)	Value (Bin)
TargetPos	0	0x00000000	b 0000 0000 0000 0000
Position	0	0x00000000	b 0000 0000 0000 0000
CPosition	0	0x00000000	b 0000 0000 0000 0000
RefVel	0	0x0000	b 0000 0000 0000 0000
MaxVel	2000	0x07D0	b 0000 0111 1101 0000
Velocity	0	0x0000	b 0000 0000 0000 0000
Acceleration	1000	0x03E8	b 0000 0011 1110 1000
Deceleration	1000	0x03E8	b 0000 0011 1110 1000
ControlMode	1	0x01	b 0000 0001
PhaseCurrent	10	0x0A	b 0000 1010
StByCurrent_Time	5	0x05	b 0000 0101
StByCurrent_Perce...	50	0x32	b 0011 0010
TimerA	0	0x0000	b 0000 0000 0000 0000
CounterA	0	0x0000	b 0000 0000 0000 0000
Status	-64	0xC0	b 1100 0000
ControlFlags	0	0x00	b 0000 0000
Fault	0	0x00	b 0000 0000
Frror	0	0x00	b 0000 0000

**Registers and user variables monitor:**

- Drive Status
- Digital I/O: DI(0): 0, DI(1): 0, DI(2): 0, DI(3): 0, DI(4): 1, DI(5): 1
- Analog I/O: AI(0): 297, AI(1): 303, AO(0): 0
- Motion: Quote 0, Speed 0,0 rpm, Angle 0,0 Degree, Current DIS Arms
- Faults / Errors

**Other Labels:**

- Back to the edit mode
- In execution
- Registers and user variables monitor
- Program execution status

#### 4.4.1 Back to the edit mode

Clicking the button the execution session ends and the program turns back to the edit mode.

In case the application program is in the *RUN* status the execution continues even getting out from the execution session.

#### 4.4.2 Start the application program execution

Clicking on the button the application program execution starts from the block indicated by the *In execution* blue arrow.

Usually the application program starts automatically within a second from the drive power-on.

#### 4.4.3 Start until the selected box is reached

The button starts the application program execution that will end when the selected block is reached (highlighted by a sketched frame).

#### 4.4.4 Execute a single instruction block

Clicking on the button only the instruction block indicated by the *In execution* blue arrow will be executed.

#### 4.4.5 Suspend the application program execution

Clicking on the button the application program execution is suspended.

#### 4.4.6 Insert / remove break point

The button allows to insert a *break point* (i.e. an interruption point) on the selected instruction block or to remove it if already present.

If during the execution the program meets a block with an active *break point*, the execution is suspended.

#### 4.4.7 Force the first block to be executed

During the test and debug operations could be useful to force the program execution starting from a particular instruction block. Clicking the button with a selected instruction block this becomes the next block to be executed.

#### 4.4.8 Perform the application program reset

The button allows to reinstate the content of variables and registers to the default status, as if the drive had just been powered on.

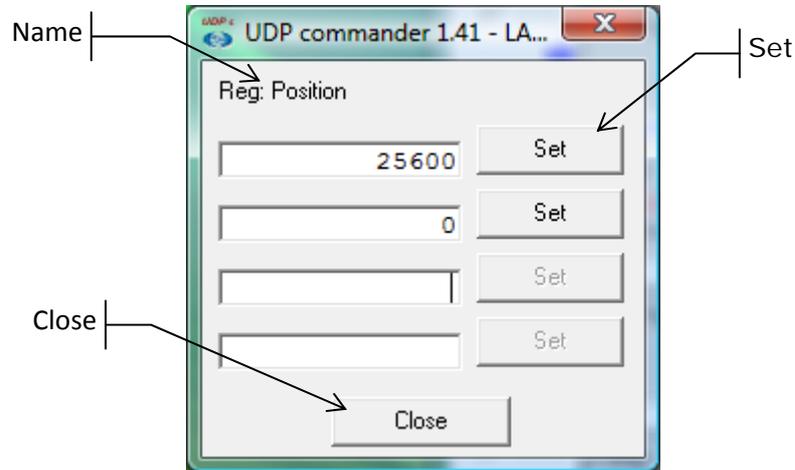
#### 4.4.9 Registers and user variables monitor



The *Registers and user variables monitor* is a very powerful tool which allows to supervise in real time the value of the registers or of the user variables (selecting the proper tab). This makes possible to observe how the content of registers and user variables changes during the execution of the several instruction blocks and/or the access of the field bus.

The value of each register is displayed in decimal, hexadecimal and binary format.

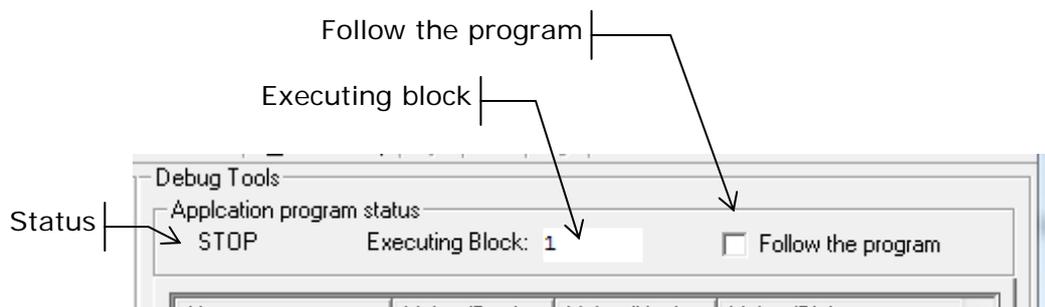
Making a double click on a register (accessible in writing mode) it appears a little window which allows to arrange up to 4 values. Each field has an its own *Set* button which allows to quickly write down the values of the register or variable indicated by the *Name* label.



#### 4.4.10 Program execution status

Inside the *Program execution status* frame there is the *Follow the program* box. If selected, the *In execution* blue arrow will show the current block in execution in real time. Take present that because of the high execution speed of the application program the *In execution* arrow will not be able to faithfully follow each single executed instruction block; anyway the given indication will be useful to know which section of the program is in execution from time to time.

The *Executing block* field specifies the number of the instruction block in execution while the *Status* label indicates if the program is in execution, in stopped or ended (respectively *RUN*, *STOP* or *END*).

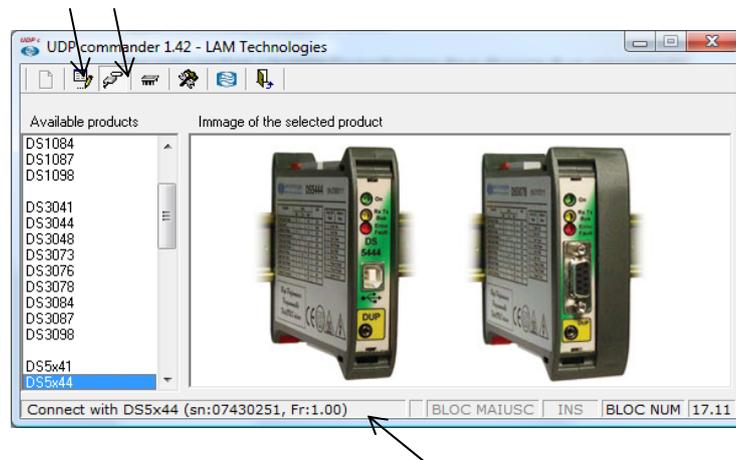


## 5 Exercising

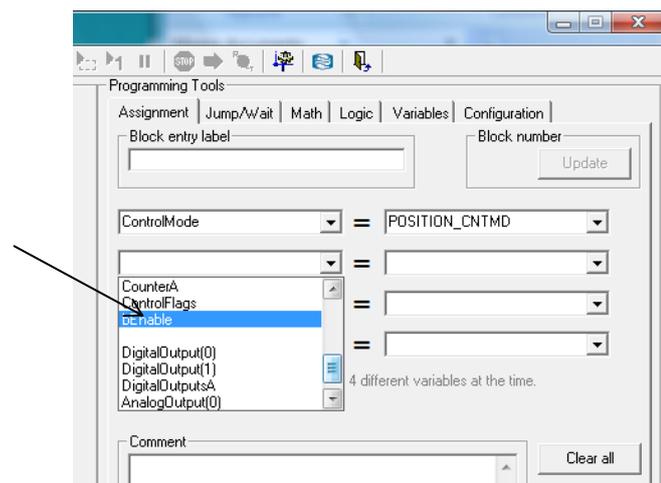
The follow exercise shows how is quick and simple to program the drives belonging to the DS30 and DS5x series. The program that will be written will make the motor move backwards and onwards of one rev.

To be able to complete the exercise we need one programmable drive (DS30 or DS5x series) correctly supplied, one motor compatible with the drive, the UDP30 interface correctly installed (green led on) and at the end a copy of the *UDP Commander* software installed on the PC (for more information see chapter 3 Installation).

Connect the UDP30 to the drive, already supplied, and click on *Connect* button in the main window (for more information see chapter 4.1.3 Connect). The status bar will show the result of the connection, as in the below image.



If the connection has successfully succeeded it is possible to click the *Change drive configuration* button to access the programming window.

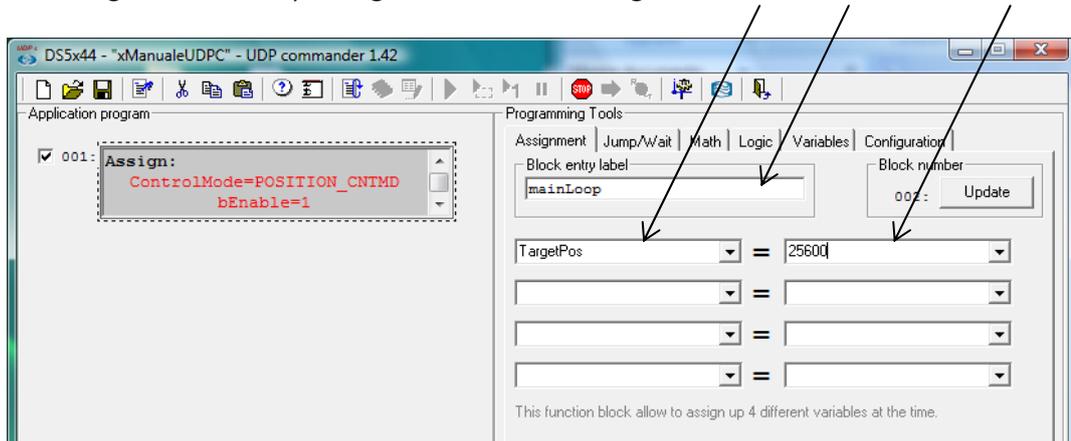


In the *Assignment* tab (for more information see chapter 4.3.25.1 Assignment) select in the first dropdown list the *ControlMode* register, then select in the dropdown list on the right the *POSITION\_CNTMD* constant. In the second dropdown list select the *bEnable* register, then digit in the space at the right of “=” the value 1.

Successively click on the *Insert* (for more information see chapter 4.3.24.4 Insert). The mouse punter will become an arrow. Move it to the left area and click to insert the block.

Click now on the *Clear all* button (for more information see chapter 4.3.24.3 Clear all) and select, from the first dropdown list of the *Assignment* tab, the *TargetPos* register. In the field on the right of the sign “=” digit the value 25600.

In the *Block entry label* field (for more information see chapter 4.3.24.1 Block entry label) digit the *mainLoop* string, as in the below image:

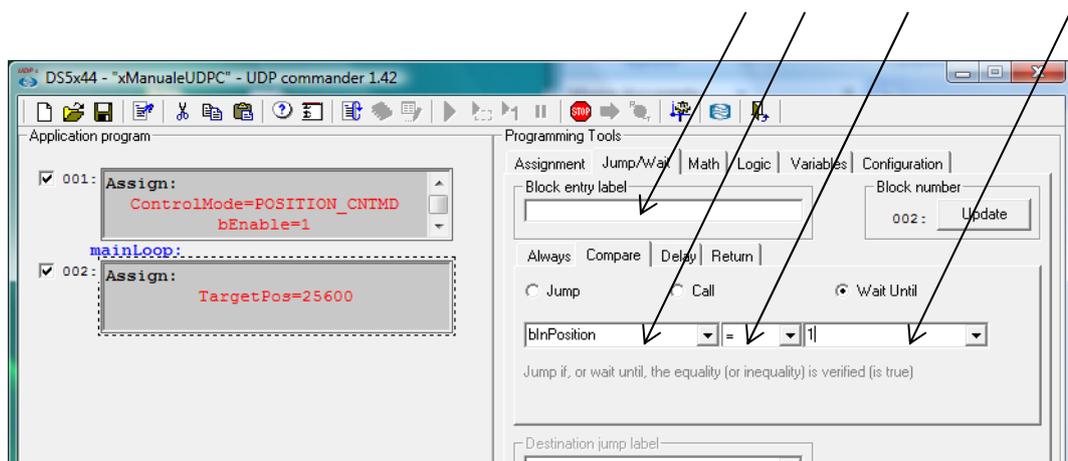


Click on the *Insert* button and position the new block under the previously inserted.

Select now the *Wait* option inside the *Compare* under tab, inside the *Jump or Wait* tab (for more information see chapter 4.3.25.2 Jump or wait ).

Select from the first dropdown list the *blnPosition* register, from the central dropdown list select the operator “=” and at then digit 1 in the field on the right.

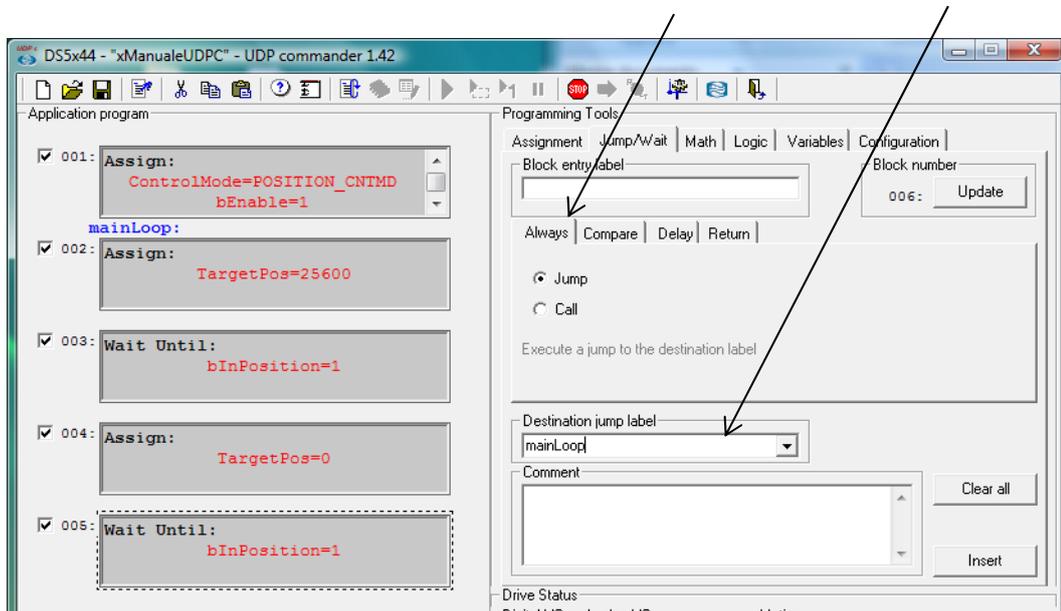
Remove the *mainLoop* string from the *Block entry label*, click then on the *Insert* button to position again the block under the one previously inserted.



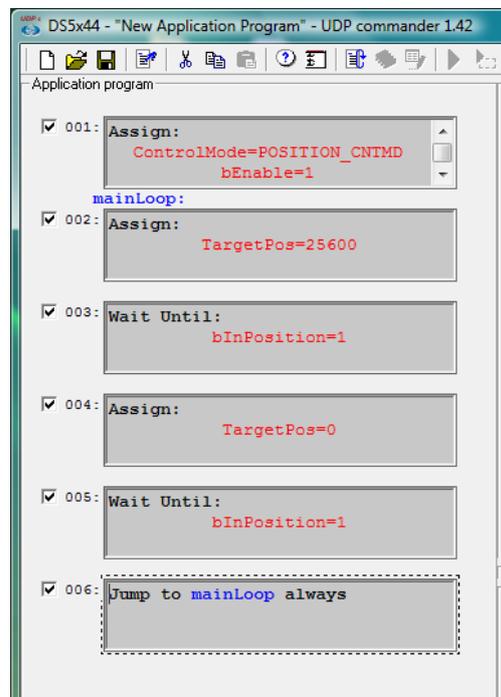
Move again to the *Assignment* tab and insert a further instruction block assigning to the *TargetPos* register the value 0.

After having positioned the block, select again the *Jump or Wait* tab and insert a block exactly alike the previous one (the field should be still filled so, definitively, it is sufficient to click on the *Insert* button).

Remaining inside the *Jump* or *Wait* tab, select the *Always* under tab (for more information see chapter 4.3.25.2.1 Always). From the *Destination jump label* dropdown list select the *mainLoop* label (as an alternative it is possible also to digit it in full). Then click on the *Insert* button to insert this last block at the end of all the others.

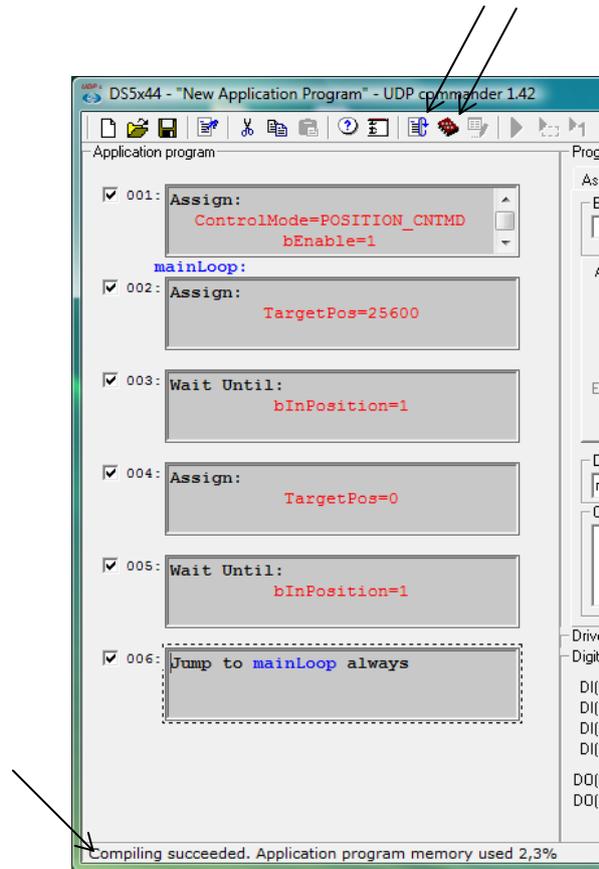


At the end of this operation the area reserved to the *Application program* will appear as follows:



Click on the *Compile the application program* button (for more information see chapter 4.3.11 Compil) to compile the application program and to arrange to be transferred into the drive. At the end the *Status bar* will show the result of the operation and the quantity of memory used.

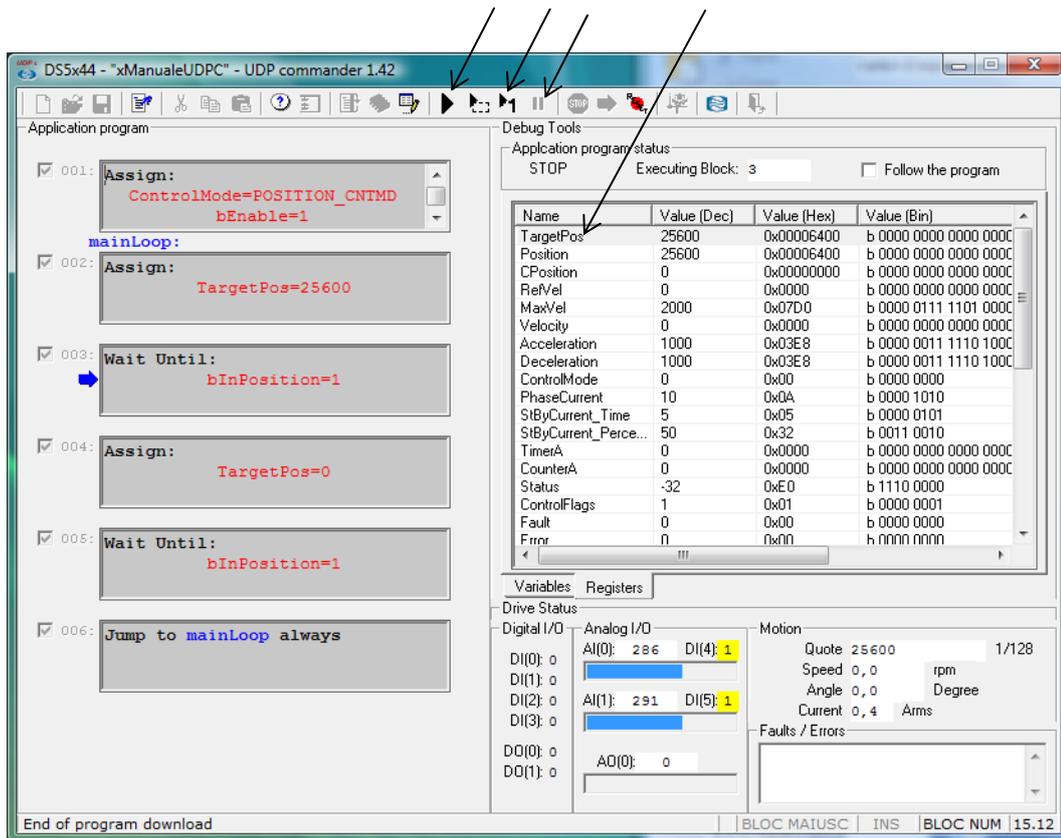
Click on the *Download the application program* button (for more information see the chapter 4.3.12 Download the application program into the drive) to transfer the application program into the drive.



At the end of the transfer the *UDP Commander* will be in execution mode.

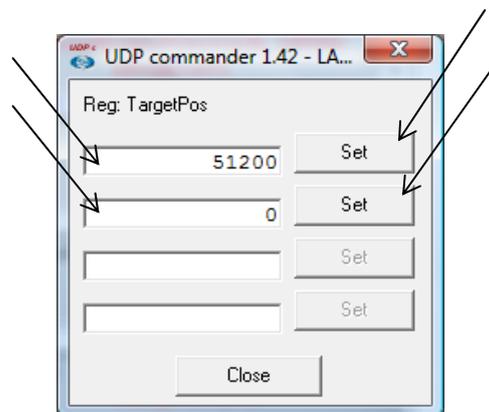
Click on the *Start the application program execution* to start the execution of the program (for more information see chapter 4.4.2 Start the application program execution); the motor will start to rotate onwards and backwards of one rev.

Clicking on the *Suspend the application program execution* button (for more information see per chapter 4.4.5 Suspend the application program execution) the execution of the program can be suspended. Clicking on the *Execute a single instruction block* button (for more information see chapter 4.4.4 Execute a single instruction block) the program can be made to advance one block at the time, to observe its behavior.



Making a double click on one of the registers contained in the *Register and user variables monitor* area (for more information see chapter 4.4.9 Registers and user variables monitor) the value of any register can be modified.

Try and make a double click on the *TargetPos* register and insert, in the first field of the window that appears, the value 51200 then click on *Set*; the motor will move immediately to the 51200 position. Insert now in the second field the value 0 and click on the corresponding *Force the first block to be executed* button; the motor will rotate in inverse sense to reach the quote 0. Click on *Close* to quit the window.



To quit from the execution mode it is sufficient to click on the *Back to the edit mode* (for more information see chapter 4.4.1 Back to the edit mode).



## 6 Command line use

*UDP Commander* can be used from command line and this makes it suitable to be invoked by other programs or simple batch file.

When *UDP Commander* is used from command line no output is shown on the video and no string is sent to the console. Upon completion *UDP Commander* simply returns an exit code (error code) that indicates whether the requested operation succeeded or not. The program or batch file that invoked *UDP Commander* can use this information to take the appropriate action.

The operations that *UDP Commander* can do when launched from the command line are:

- Updating of the firmware of the drive
- Configuring and / or setting of the drive
- Setting of the fieldbus communication parameters (valid only for xS5x drives series)

When you start *UDP Commander* from command line the UDP30 interface must be already connected, the PC's USB port and the drives properly installed (green colored LED ON, for more information see the UDP30 interface instruction manual), and the DUP port cable already connected to the drive.

If more than one UDP30 interface are connected to the PC it is possible to specify the serial number of the device you want to use, to communicate with the drive using the */udp* parameters.

Finally, *UDP Commander* can perform multiple operations in sequence simply specifying multiple parameters on the command line.

### 6.1 */udp* (UDP30 interface serial number)

The */udp* parameter indicates to *UDP Commander* the specific UDP30 interface to use to communicate with the drive. If the */udp* parameter is omitted *UDP Commander* will use the first available UDP30 interface connected to the PC.

The serial number of the UDP30 interface you want to use must be specified after the */udp* parameter and preceded by the character “:”, as shown in the following example:

```
UDPCommander.exe /udp:10071688
```

In this way *UDP Commander* will use exclusively the UDP interface with serial number 10071688 to connect to the drive.

### 6.2 */frm* (firmware update)

The */frm* parameter specifies to *UDP Commander* to update the firmware of the drive.

The file containing the firmware must be specified after the */frm* parameter and preceded by the character “:”. If the file is located in a folder different from the *UDP Commander* installation one, it is then necessary to specify the full path of the file, as shown in the following example:

```
UDPCommander.exe /frm:C:\work\samplecmdline\xs10xx_r115.frm
```

*UDP Commander* will update the firmware of the drive with the one contained in the file *xs10xx\_r115.frm* present in the folder *C:\work\samplecmdline\*.

The firmware update process takes about 40 seconds after which *UDP Commander* will return the exit code 0 if the firmware has been correctly updated, or a different value if an error has been reported (for more information about the possible return codes see chapter 6.5 *Error codes*).

### 6.3 /prg (setting or configuring)

The */prg* parameter indicates to *UDP Commander* to configure (xS10 drives series) or set (xS30 and xS5x drives series) the drive with a specific user’s program.

The file containing the configuration or the user’s program must be specified after the */prg* parameter and preceded by the character “:”. If the file is located in a folder different from the *UDP Commander* installation one it is then necessary to indicate the full path as shown in the examples below:

```
UDPCommander.exe /prg:C:\work\samplecmdline\test1cmd1.dup
```

```
UDPCommander.exe /prg:C:\work\samplecmdline\DS1098s1.dcf
```

Launching the first command the *UDP Commander* will set the drive (xS30 or xS5x series) with the user’s program *test1cmd1.dup* present in the folder *C:\work\samplecmdline\*, while launching the second command *UDP Commander* will configure the xS10 series drive with the configuration file *DS1098s1.dcf* (also contained in the folder *C:\work\samplecmdline\*).

The configuration or setting process takes about 10 seconds after which *UDP Commander* will return the exit code 0 if the drive has been correctly set or configured, or a different value if an error has been reported (for more information about the return codes see chapter 6.5 *Error codes*).

Note that the *UDP Commander* automatically compiles the program before sending it to the drive and converts it from the xS30 series to the xS5x series and vice versa if necessary.

Running *UDP Commander* with the */prg* parameter it is possible to specify also the following subparameters:

- */run*, if it is present at the end of the setting process, the program downloaded into the drive is immediately executed. If the */run* parameter is not present the program will be launched at the next restart of the drive.

- */mrg*, allows to specify a correspondence text file which will be used, before the compiling, to replace one or more parameters in the user's program. More, the */mrg* option allows to modify the behavior of an user's program or parameterize it for each single application or drive.

Below is a more detailed description of the */run* and */mrg* parameters.

### 6.3.1 */run* (user's program execution)

The */run* parameter can be specified only if the */prg* is present too.

At the end of the setting process (xS30 and xS5x series drives) *UDP Commander* verifies if the */run* parameter has been specified and executes the downloaded program, if present.

Without the */run* parameter the user's program downloaded into the drive will be executed at the next restart of the drive.

### 6.3.2 */mrg* (replacement of the user's program parameters)

The */mrg* parameter can be specified only if the */prg* parameter is present too.

The correspondence file, containing the list of parameters to be replaced in the user's program, must be specified after the */mrg* parameter and preceded by the character ":". If the file is located in a folder different from the *UDP Commander* installation one, it is then necessary to indicate the full path as shown in the example below:

```
UDPCommander.exe /prg:C:\work\samplecmdline\test1cmd1.dup
/mrg:C:\work\samplecmdline\applcst1.txt
```

*UDP Commander* will set the drive (xS30 or xS5x series) with the user's program `test1cmd1.dup` present in the folder `C:\work\samplecmdline\` after having replaced the parameters according to the correspondence contained in the file `applcst1.txt`, also present inside the folder `C:\work\samplecmdline\`.

The correspondence file must be in text format and must use a different command for each correspondence. The name of the parameter present in the user's program to be replaced must be followed by the character ":" which will be followed by the value object of the replacement.

For example, if the correspondence file contains the following command:

```
MaxHomeTravel:1200000
```

and the user's program the following block:

<p><b>Jump to homeNotFound if:</b> Position &gt; MaxHomeTravel</p>
--

the drive is set as if the program block were written:

**Jump to homeNotFound if:**  
Position > 1200000

In other words, before compiling, *UDP Commander* will replace all the parameters of the user's program also present in the correspondence file with the relative value.

Note that there shall not be any distinction between registers, variables, jump destinations (both *Jump* and *Call*), therefore if the correspondence file contains the name of a register (*Position*, for example) this will be replaced in the user's program at each occurrence, probably generating unexpected behaviors. For this reason it is recommended to highlight with a very recognizable syntax, such as the use of parentheses, each parameter to be replaced before compilation in order to make explicit, both in the program and in the correspondence file, this intent. Consequently, the above example can be rewritten as follows:

Correspondence file:

```
(MaxHomeTravel) :1200000
```

Block of the user's program:

**Jump to homeNotFound if:**  
Position > (MaxHomeTravel)

In the correspondence file everything following the character ";" is ignored and therefore it is possible to use the character ";" to insert comments as shown in the example below:

```
; START substitution file
(MaxHomeTravel):1200000 ;Maximum travel before home not found error
; END substitution file
```

## 6.4 /bus (Field BUS configuration)

The */bus* parameter indicates to *UDP Commander* to configure the field BUS (only for the xS5x series drives).

The parameters which define the field BUS behavior must be specified after the */bus* parameter and preceded by the character ":". Each parameter must be separated from the other by the character ",", as shown in the example below:

```
UDPCommander.exe /bus:pvt,add,brate,pvt,nbit,sbit,txdly
```

The following table describes the meaning of each parameter and the range of the allowed values.

Parameter	Possible values	Description
<i>prt</i>	MODBUS-RTU	Protocol. Specifies the communication protocol
<i>add</i>	1..247	Address. Assigns the drive ID address on the web
<i>brate</i>	1200 2400 4800 9600 19200 38400	Baud rate. Communication speed (bit rate) expressed in baud.
<i>prt</i>	N E O	Parity . Specifies the parity: <ul style="list-style-type: none"> <li>• N, <u>no</u> parity</li> <li>• E, <u>even</u> parity</li> <li>• O, <u>odd</u> parity</li> </ul>
<i>nbit</i>	8	Number of data bit
<i>sbit</i>	1	Number of stop bit
<i>txdly</i>	0..40	Delay in the response transmission in ms

For example, launching the following command line the bus of the drive will be configured with a Modbus-RTU communication protocol and will reply to the address 7, it will have a baud rate of 9600baud with no parity, 8 data bits and one stop bit and at the end it will respond to the master with 10ms transmission delay.

```
UDPCommander.exe /bus: MODBUS-RTU, 7, 9600, N, 8, 1, 10
```

## 6.5 Error codes

At the end of the operations required by the command line, *UDP Commander* returns a code indicating whether or not errors occurred. The exit code 0 indicates that all the operations have been successfully completed while a value different from 0 designates that there have been impediment to one or more operations.

The following table shows the meaning of error codes returned by *UDP Commander* with some indications about the causes and the possible remedies.

Code	Description	Notes
10	Error in the command line	Verify the parameters syntax and if the application rules are conformity with the instruction contained in this manual.
20	Error connecting with the UDP30	Verify the proper installation of the drive. Check the USB connection with the PC and eventually replace the USB cable.
22	UDP30 not found	It was not possible to connect with the interface UDP30. Verify there is at least one UDP30 interface connected to the PC with the green led ON and that this interface is not already in use (for example by another application of the <i>UDP Commander</i> program in execution).
24	UDP30 with the serial number specified not found	It was not possible to connect with the UDP30 with the serial number specified. Verify that the UDP30 interface with the serial number specified is connected to the PC, with the green led ON and that this interface is not already in use (for example by another application of the <i>UDP Commander</i> program).
30	Connection with the drive failed	The UDP30 interface was found but it was not possible to communicate with the drive. Verify that the UDP30 cable is properly connected to the DUP port of the drive.
40	Error during loading file	Verify to have correctly specified the type and location of the file for the setting/configuration of the firmware and/or correspondence.
50	Compile error	Verify the user's program by compiling it with the windows version of the <i>UDP Commander</i> . Verify that the eventual correspondence file contains all the parameters that must be replaced in the user's program, if one of them is not replaced it is possible it leads to a compiling error.
52	Firmware update necessary	One or more operations cannot be completed because the firmware currently installed in the drive is obsolete and must be updated to the latest available version.
58	Syntax error in the correspondence file	Verify the syntax used in the correspondence file and make the appropriate adjustments. Make sure that the comments are preceded by the character ";".
60	Error during program download	Verify that the UDP30 cable is properly connected to the DUP port of the drive and repeat the operation.
66	Error during field BUS configuration	An error occurred during the configuration of the field BUS. Verify that the UDP30 cable is properly connected to the DUP port of the drive and repeat the operation.
68	Error during firmware update	An error occurred during the firmware update of the drive. Verify that the UDP30 cable is properly connected to the DUP port of the drive and repeat the operation.
70	Unable to start the program	The user's program has been correctly transferred in the drive, but an error occurred at the start of the program. Verify that the UDP30 cable is properly connected to the DUP port of the drive and repeat the operation.
90	Error log file	<i>UDP Commander</i> was not able to complete the requested operation because of a problem. Inside the installation folder of the <i>UDP Commander</i> is a file called <i>log.txt</i> containing the description of the problem occurred.
99	Generic error	

## 6.6 Use inside a batch file

To automate the operations *UDP Commander* can be launched within a batch file. At the exit from the program the system variable `ERRORLEVEL` will contain the error eventually returned by *UDP Commander*, or the value 0 if all the required operations were successfully completed. Inside the batch file, the variable `ERRORLEVEL` can be tested to execute further operations.

In the following example is a file batch that, evoking *UDP Commander*, will update the firmware of the drive using the file `xS50xx_r104.frm`, then will configure the field BUS with the Modbus-RTU protocol address 5, speed 9600baud with no parity, 8 data bits one stop bit and 0ms of delay before sending the response to the master, therefore will set the drive with the program `app2.dup` after having executed the replacements contained in the file `cstPROD.txt` and then will execute the program itself. To communicate with the drive *UDP Commander* will use the UDP30 interface with serial number 09401282.

At the exit of the program the variable `ERRORLEVEL`, containing the *UDP Commander* return code (read code error) is tested and if the value is 0 the console displays the message "SUCCESS.". Instead, if the value contained in the variable `ERRORLEVEL` is different from 0 then the message displayed is "FAIL. Error code:xx" with xx equal to the code returned by *UDP Commander*.

For more information on the batch files consult the documentation of the operative system in use.

```
@ECHO OFF
```

```
UDPCommander.exe /prg:app2.dup /udp:09401282 /mrg:cstPROD.txt /run /bus:MODBUS-  
RTU,5,9600,N,8,1,0 /frm:xS50xx_r104.frm
```

```
IF %ERRORLEVEL%==0 (ECHO SUCCESS.) ELSE (ECHO FAIL. Error code:%ERRORLEVEL%)
```

```
PAUSE
```



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