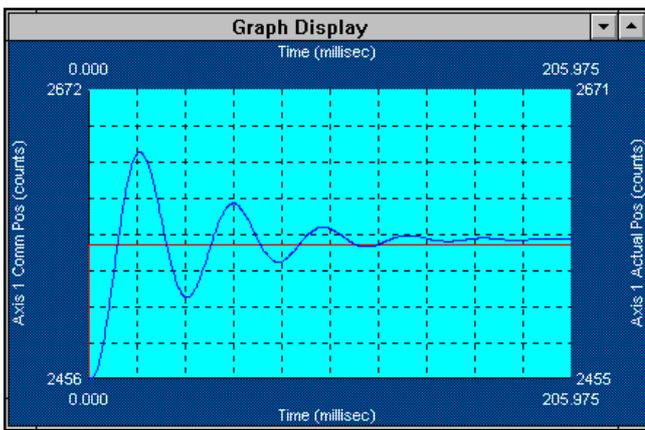


Servo tuning made simple with 6000 series software

Parker combines the 6000 Series servo controllers with Servo Tuner software and servo control becomes very straightforward.

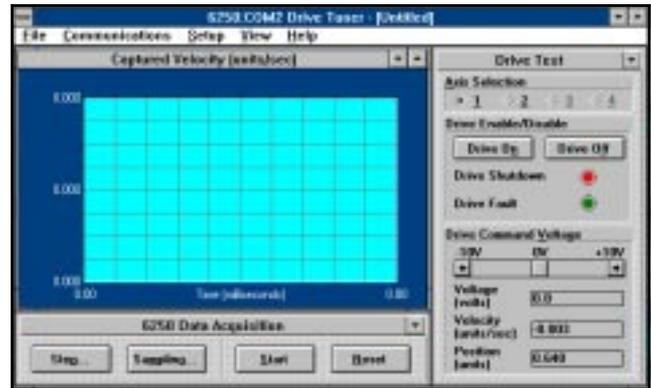
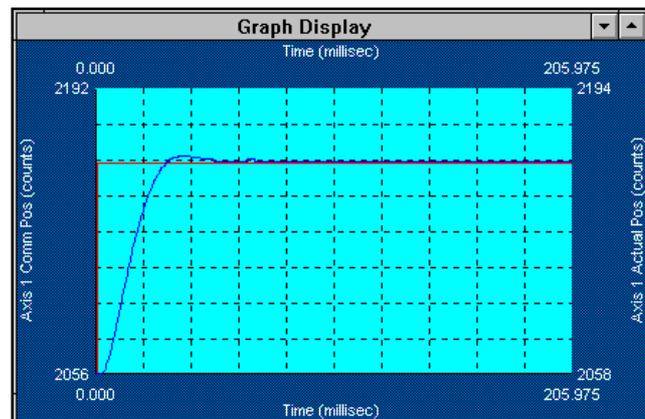
The Servo Tuner is an add-on module used to expand and enhance the capabilities of Motion Architect when used with the 6000 Series servo products.

Motion Architect and the Servo Tuner combine to provide graphical feedback of real-time motion information. The Servo Tuner makes determining necessary tuning gains and related system parameters simple, and then provides operations to save and recall tuning sessions.



Tuning your system in minutes

When using Motion Architect with the 6000 Series servo controls, you can add the benefit of a powerful Servo Tuning Module. Real-time move information—such as commanded velocity, actual position, etc.—is gathered and used to graphically display move data. You can see the results of changing tuning values in order to optimize motion profiles. In addition, multiple graphs can be saved, providing a history of the system's performance.



The Servo Tuner consists of two invaluable servo response analysis tools:

- The Drive Tuner utility offers a method for graphically tuning and setting up your velocity servo drive. The position loop control is turned off so that you can tune the drive system independently of the controller.
- The Position Loop Tuner allows you to tune the position loop of your system with a graph of actual vs. commanded moves. You can then change tuning values to optimize system performance.

The Servo Tuner also provides an automatic gain calculation tool where gains for specific response criteria can be empirically calculated and set as the initial gain settings.



Pushing START will automatically cause the motion to initiate and the system response to be graphed in front of you. Capture and display up to nine motion parameters. You can even graph velocity vs. position.

Optimize performance by modifying the gains. You will quickly achieve the desired performance graphed on the screen.