

K66 Parameters

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Version: 1.0.0

K66 Value	Output Values	Streaming	Notes
1	Target Speed	When Running	
2	Current Position	When Running	
3	Current Speed	When Running	
4	Current Torque	When Running	
5	Current Position	When Running	(Always in full resolution)
6	Current Speed (Same as 3?)	When Running	
7	Current Torque	When Running	Tx.1=xxx
8	Motor status, Overload alarm delay	When Running	Overload Alarm Delay=K57/32*5 (Alarm: XX, XX)
9	Current Iq, Iq Target, Current Id, Id Target	When Running	Iq=Torque Generating current Id= Non-torque generating current
10	ADIU0, ADIV0, ADSIN, ADCOS	When Running	Encoder Feedback
11	AngleRealComp, angleReal, Position at full resolution	Always	AngleRealComp = Position Sensor Angle after calculation of sensor phase offset AngleReal = Position Sensor Angle before offset
12	SinOffset, CosOffset, Position Offset	Always	SinOffset/CosOffset = Position sensor level offset Position Offset = Encoder Calibration Offset
13	Rotation Count, Distance Target, Distance Real, Position Target, Current Position, Schedule Ready, Distancereal memo, vgenerated	Always	Rotation Count = Current number of full rotations of full resolution Distance Target = Distance Real = Position Target = Target Motor Position Position Real = Current Motor Position Schedule Ready = Ready to schedule new motion Distance Real Memo = Vgenerated = Speed Target
14	vGenerated, VelocityReal	Always	
15	VoltageFilter4, OS_input420, ADAIN0	Always	Voltage Filter 4 = IN4 Analog Input Voltage full resolution followed by motor ID OS_Input420 = Filtered Analog Input Value ADAIN0 = Filtered Analog Input Value
16	H infinity motor current , Maximum Current Limit	Always	
17	H infinity motor current	Always	
18	Integrator State	Always	
19	Torque.torMeasure.1 Torque.torU.1	Always	
20	Position error	Always	
21	Rolling Average of Torque Squared for Overload detection	Always	
22	Current Torque Squared	Always	Used in Overload Detection
23	Manual Feed Speed	Always	
24	External Encoder count	Always	
25	Slow speed display	Always	10s rolling average speed at full resolution
26	Current position at full resolution, CurrentAngleReal	Always	AngleReal = Position Sensor Angle before offset
27	NA	Always	

28	ADCOS, ADSIN, Current AngleReal, Current position at full resolution	Always	
29	TaskCounter, tm4, positionFilterRes	Always	
30	OUT1 status, OUT2 status	Always	