

# Can Open Mode of Operation

The supported modes of operation are:

| Modes Of Operation<br>0x6060 | Description                      |
|------------------------------|----------------------------------|
| 1                            | Profile position mode            |
| 6                            | Homing mode                      |
| 7                            | Cyclic synchronous position mode |
| 8                            | Cyclic synchronous position mode |

## Profile position mode

In this mode, the motion trajectory is calculated and generated internally. The standard motion profile is trapezoidal type.

These are the parameters:

| Address | Parameter            | Unit   |
|---------|----------------------|--------|
| 0x60C1  | Position setpoint    | INT32  |
| 0x6081  | Profile velocity     | UINT32 |
| 0x6083  | Profile acceleration | UINT32 |
| 0x6084  | Profile deceleration | UINT32 |

## Control word bits 0x6040 - motion function

| Bit position | Implemented Function                   |
|--------------|----------------------------------------|
| 2            | Quick stop                             |
| 4            | Start the move                         |
| 6            | Absolute or relative - (only absolute) |
| 8            | Pause/halt                             |

## Status word bits - 0x6041

| Bit position | Implemented Function |
|--------------|----------------------|
| 10           | target reached       |
| 12           | setpoint acknowledge |
| 13           | following error      |

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