J series DPLSR [G28] : Zero return – Initial direction reverse (the number of times to look for Z phase is 3)
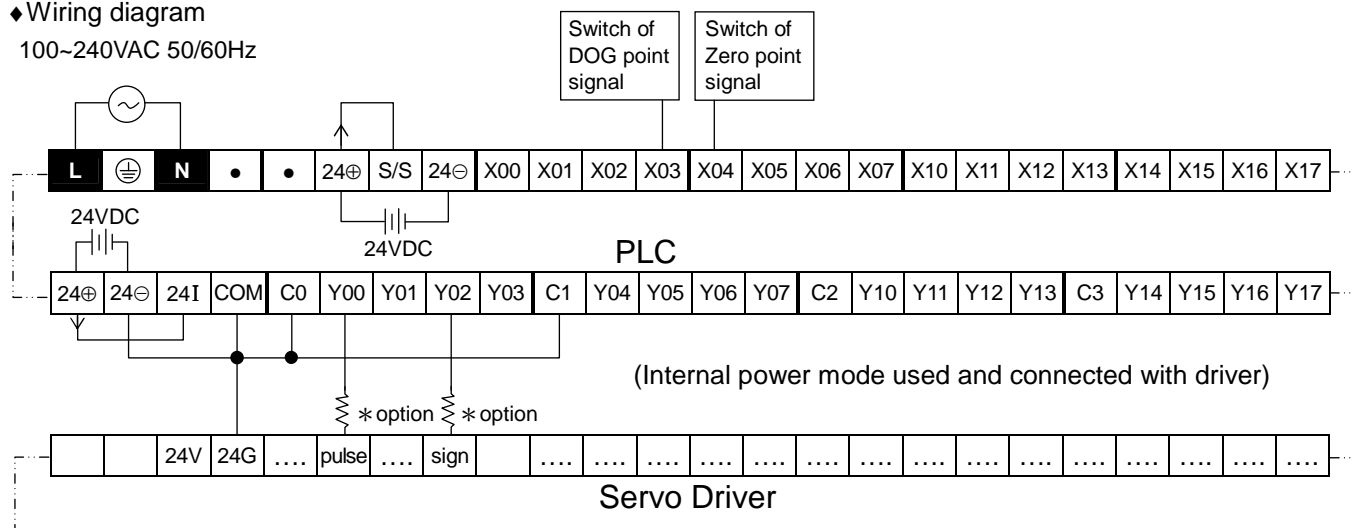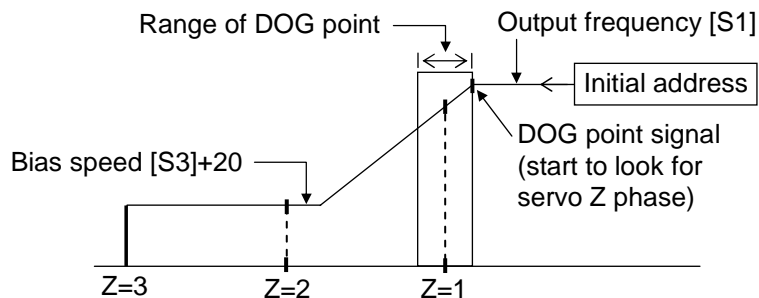
♦Wiring diagram

100~240VAC 50/60Hz

♦ Program exposition

M500 ON, looks for DOG signal through 10K speed (reverse)

X3(DOG) ON rising edge effective, decelerates to bias speed 100pps to look for zero-point signal (reverse)

X4(Servo Z) ON rising edge effective, after looks for (Servo Z) three times, then stop

♦ About sample program, please refer to next page

♦ Sample program

```
     M8002
    ──┤├──────┬──[ ZRST   D1000   D1099 ]
              │
              └──[ CALL    P10 ]

     M500
    ──┤↑├─────────[ RST    M510 ]      Clear zero-return complete flag

     M500
    ──┤├──────────[ DPLSR  D0   D2   D1000   Y0 ]
         M8029
        ──┤├──────┬──[ RST    M500 ]
                  │
                  ├──[ SET    M510 ]   Set zero-return complete flag. This example uses M510
                  │                    (User can define M register)
                  └──[ RST    M8029 ]

              ──────[ FEND ]

           M8000
P10       ──┤├──────┬──[ DMOV   K10,000   D0 ]      Output frequency (speed)
                    │
                    ├──[ DMOV   K10,000   D2 ]      Number of output pulses (address)
                    │
                    ├──[ MOV    K28    D1000 ]      Zero-return mode
                    │
                    ├──[ MOV    H0002  D1001 ]      Direction control point Y2
                    │
                    ├──[ MOV    H0043  D1024 ]      DOG point signal X3 rising edge effective; Zero point signal X4
                    │                               rising edge effective. Initial operation direction as reverse
                    └──[ MOV    K3     D1025 ]      Set the number of times to look for Z phase, speed of looking
                                                    for Z phase is as same as bias speed

           M8000
P11       ──┤├──────┬──[ MOV    H0     D1002 ]      Parameter setting
                    │
                    ├──[ DMOV   K100,000   D1016 ]  Maximum speed
                    │
                    ├──[ MOV    K100   D1020 ]      Bias speed
                    │
                    ├──[ MOV    K100   D1022 ]      Acceleration time (ms)
                    │
                    └──[ MOV    K100   D1023 ]      Deceleration time (ms)

              ──────[ SRET ]

              ──────[ END ]
```