
Sommario

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MDI_P1R44F-024: Installer Manual

1. Information

1.1 Release



Quality in Electronic
Manufacturing

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01	New manual		12/22/2023

Specifications

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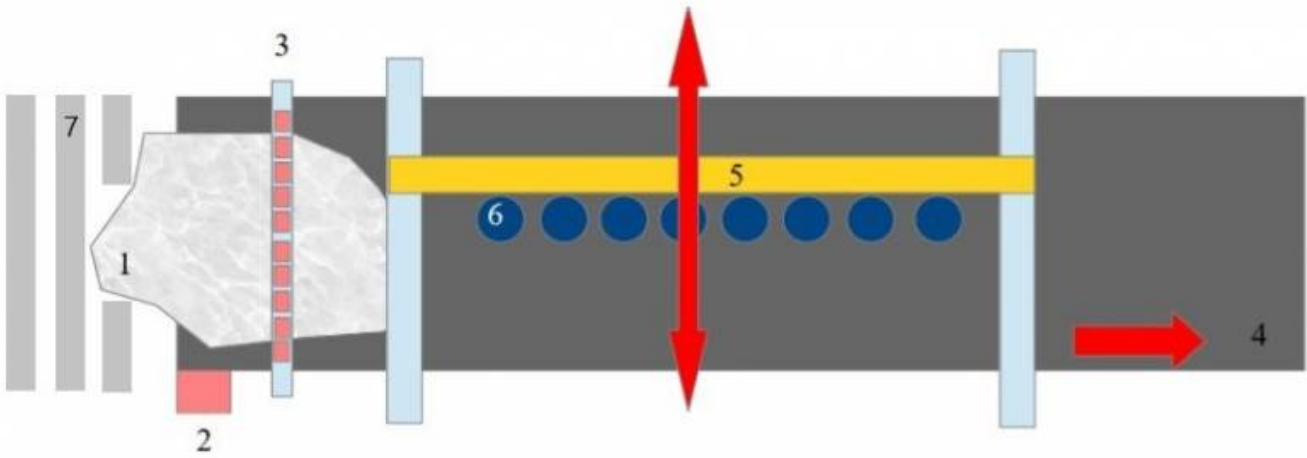
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2. Setup

2.1 Machine Overview

Machine top view:



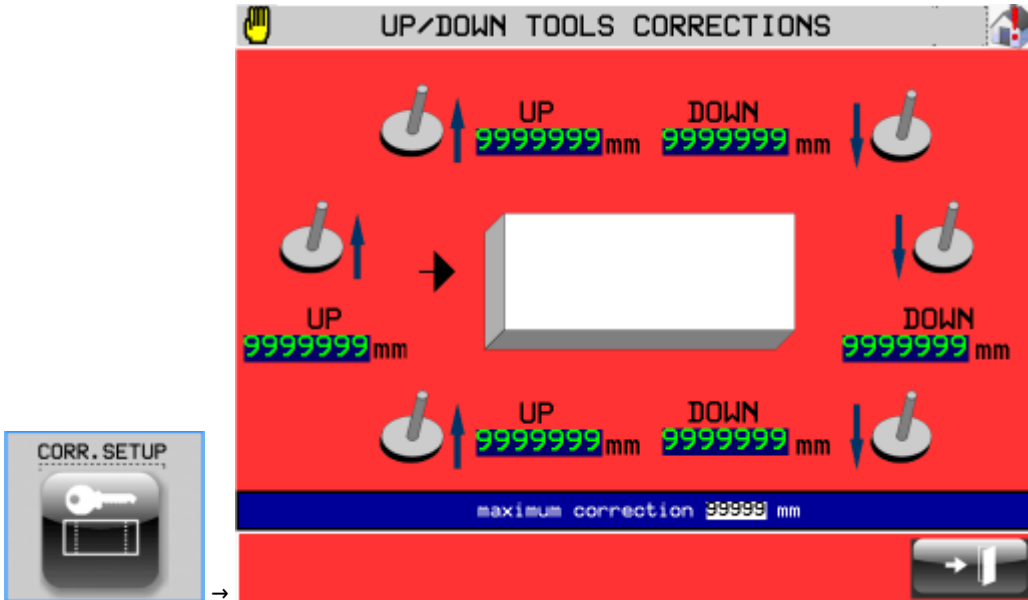
n:	Description:
1	Raw Slab
2	Conveyor Belt Encoder
3	Limit Switch Bar
4	Conveyor Belt direction
5	Moving Bridge
6	Polishing Heads
7	Infeed Roller

2.2 Access to Setup

Access to the setup can be done from the MENU page by entering the password **035**.









There is a dedicated setup for the correction of the head up/down movement, accessible by entering the password **123**.



2.2.1 Introduction to SETUP

List of parameters divided into

GENERIC 	general parameters
TOOLS 	parameters associated with the heads
BRIDGE 	parameters associated with the bridge
SENSORS 	parameters associated with the sensor bar
BELT 	parameters associated with the conveyor belt
VALVES 	parameters associated with the head up/down valves

2.3 Generic Setup



Parameter Name	Unit of Measurement	Default	Range	Description
PG01 : LANGUAGE	-	ITA	1 ÷ 2	1: ITALIAN 2: ENGLISH
PG02 : MAX CORRECTIONS	mm	0	0-9999	Maximum correction applicable for head up and down movement
PG03 : DECIMAL POINT	-	1	0 ÷ 3	It is the position of the decimal point in the display of measurements.
PG04 : PARTIAL LIFT TIMOUT	s	0	99.9	Timer after which the heads lift from a partial up movement.
PG05 : HORIZONTAL STEP	mm	50.0	-	Distance between the limit switches on the sensor bar. Allows detecting the shape of the slab.
PG06 : ORTHOGONAL STEP	mm	50.0	-	Space determined by the encoder. Allows detecting the shape of the slab.
PG07 : ENABLE BRIDGE SLAVE	-	OFF	ON - OFF	Enable/Disable slave bridge swing motor. Enable only if a second motor is used for bridge movement
PG08 : LINE MEASURE	mm	1	0 ÷ 999999	Indicates the distance, in measurement units, traveled by the conveyor belt to obtain the encoder pulses set in the <i>pulse</i> parameter.
PG09 : LINE PULSE	-	1	0 ÷ 999999	Indicates the pulses multiplied by 4 provided by the conveyor belt encoder to obtain the space set in the <i>measure</i> parameter. <i>The ratio between measure and pulse is the encoder resolution and must have values between 1 and 0.000935.</i>
PG10: SLAB ENTRY	-	LFT	LFT - RT	Indicates the slab entry position: LFT = slab enters the machine from the left RT = slab enters the machine from the right
PG11 : BRIDGE AUTO-LEARN	-	OFF	0 ÷ 1	Enables the option to automatically learn the minimum and maximum slab height to optimize bridge swing.
PG12 : ENABLE ABRASIVE MANAGEMENT	-	OFF	ON-OFF	Enables the reading of abrasive thickness and head height. Enable only if analog inputs are used for abrasive thickness measurement

Parameter Name	Unit of Measurement	Default	Range	Description
PG14 : HEADS ENABLE/DISABLE	-	TOUCH	TOUCH - SELECTORS	Mode of enabling/disabling heads: TOUCH = enable/disable heads via touchscreen SELECTORS = enable/disable heads via selectors
PG15 : AUTO/MANUAL SELECTOR	-	ON	0 ÷ 1	Enables manual/auto selector.
PG16 : PRESTART TIME	s	3.0	0 ÷ 9999.9	Time between start command and actual machine start (during this time, the warning signal is active). If less than the motor activation time, the greater of the two is applied.
PG17 : LUBRICATION TIME ON	s	0.0	0 ÷ 9999.9	Lubrication ON time.
PG18 : LUBRICATION TIME OFF	s	0.0	0 ÷ 9999.9	Lubrication OFF time.
PG19 : MOTORS TIME ON	s	1.000	0 ÷ 99.999	Pause time between the activation of one motor and the next (in sequential activation).
PG20 : MOTORS TIME OFF	s	0.200	0 ÷ 99.999	Pause time between the deactivation of one motor and the next (in sequential deactivation).
PG21 : BELT EXIT MOTOR TIME	s	0.000	0 ÷ 99.999	Wait time to start sequential motor deactivation, starting when there are no more pieces on the conveyor belt.
PG22 : ABRASIVE THICKNESS WARNING	mm	300	0 ÷ 999999	Minimum abrasive thickness measurement. If the abrasive thickness is less than or equal to the set value, a warning is displayed.
PG23 : ABRASIVE THICKNESS ALARM	mm	200	0 ÷ 999999	Minimum abrasive thickness measurement. If the abrasive thickness is less than or equal to the set value, an alarm is displayed.
PG24 : ABRASIVE ALARM TIMEOUT	ms	0	0 ÷ 999999	Timer for which if the abrasive thickness is below the warning or alarm value for the set time, the respective message appears.
PG25 : HEADS OUTPUT	-	CONST	CONST ÷ PULSE	Operating mode of the heads activation output. CONST = the output remains active for the entire head usage time, PULSE = the output remains active for a set time (PG27).
PG26 : BELT OUTPUT	-	CONST	CONST ÷ PULSE	Operating mode of the conveyor belt activation output. CONST = the output remains active for the entire conveyor belt usage time, PULSE = the output remains active for a set time (PG27).
PG27 : PULSE TIME	s	0.000	0 ÷ 99.999	Activation time of the heads and conveyor belt outputs if they are enabled as pulse outputs.
PG28 : BELT DELAY	s	0.000	0 ÷ 99.999	Delay time for activating the conveyor belt after the bridge starts.
PG29 : MAX SLAB HEIGHT	mm	-	0 ÷ 999.9	Maximum slab height on entry
PG30 : ANTICIPATION SPACE	mm	0.0	-9999.9 ÷ 9999.9	Anticipation space for the brush lowering.
PG31 : DELAY SPACE	mm	0.0	-9999.9 ÷ 9999.9	Delay space for brush lifting.
PG32 : REFERENCE SPEED	m/'	0.0	0 ÷ 9999.9	Reference speed for the use of brush anticipation and delay. If set to 0, no speed proportionality is applied, and the values are used in a constant manner.
PG34 : RAMP TYPE	-	1	0 ÷ 1	Ramp type. Logic level 0 = linear ramp Logic level 1 = S-shaped ramp
PG35 : EDGE-HEAD DISTANCE	mm	-	0 ÷ 99.999	Distance between the edge and the head center
PG36 : BRIDGE-HEAD DISTANCE	mm	-	0 ÷ 99.999	Distance between the bridge homing sensor and the head center
PG37 : SENSOR-HEIGHT DISTANCE	mm	-	0 ÷ 99.999	Distance between the sensor bar and the slab height reading sensor

2.4 Belt Setup

Belt Axis Resolution



Parameter Name	Unit of Measure	Default	Range	Description
MEASURE	mm	0.1	0 to 99999.9	Indicates the space, in units of measurement, traveled by the belt to obtain the encoder pulses set in the <i>pulse</i> parameter.
PULSE	-	1	0 to 999999	Indicates the pulses multiplied by 4 provided by the belt encoder to obtain the space set in the measure parameter. The ratio between measure and pulse is the encoder resolution and must have values between 1 and 0.000935.
+	JOG FORWARD			
-	JOG BACKWARD			

2.5 Bridge Setup



= GANTRY ENABLED (master and slave bridge move together)



= GANTRY DISABLED (master and slave bridge move independently)

BRIDGE SETUP





PB01: TOLERANCE	999999 mm	<div style="border: 1px solid black; background-color: #f4a460; padding: 5px; margin-bottom: 5px; text-align: center;">RESOLUTION</div> <div style="border: 1px solid black; background-color: #f4a460; padding: 5px; margin-bottom: 5px; text-align: center;">P. I. D. MASTER</div> <div style="border: 1px solid black; background-color: #f4a460; padding: 5px; margin-bottom: 5px; text-align: center;">P. I. D. SLAVE</div> <div style="border: 1px solid black; background-color: #f4a460; padding: 5px; text-align: center;">JOG SLAVE</div>
PB02: ENABLE TIME	99999 s	
PB03: DISABLE TIME	99999 s	
PB04: MAXPOS MASTER	9999999 mm	
PB05: MINPOS MASTER	9999999 mm	
PB06: ACCELETATION TIME	99999 s	
PB07: DECELERATION TIME	99999 s	
PB08: INVERSION TIME	99999 s	
PB09: DEACTIVATIO TIME	99999 s	
PB10: OUTPUT MODE	MOVE	
PB11: CHANGE ABR POSIT	9999999 mm	
PB12: PRESET POSITION MASTER	9999999 mm	
PB13: PRESET POSITION SLAVE	9999999 mm	
PB14: PRESET VELOCITY	999%	
PB15: PRESET SLOW VELOCITY	999%	
PB16: PRESET DIRECTION MASTE	FORWARD	
PB17: PRESET DIRECTION SLAVE	FORWARD	
PB18: HOMING MODE GANTRY	MOVE	
PB19: MAX DISALIGN.	9999999 mm	
PB20: MAX HOMING DISALIGN	9999999 mm	
PB21: SLAVE HOMING OFFSET	9999999 mm	
PB22: MAXPOS SLAVE	9999999 mm	
PB23: MINPOS SLAVE	9999999 mm	
PB24: HOMING MAX TIME	9999999 s	

Parameter Name	Unit of Measure	Default	Range	Description
PB01: TOLERANCE	mm	5.0	0 to 99999.9	Defines a tolerance range around the positioning dimensions. If the positioning falls within this range, it is considered correct.
PB02: ENABLE TIME	s	0.200	0.000 to 9.999	Advance enabling of the bridge movement.
PB03: DISABLE TIME	s	0.200	0.000 to 9.999	Delay in disabling the bridge movement.
PB04: MAX MASTER POSITION	mm	99999.9	-99999.9 to 99999.9	Maximum position reachable by the master bridge.
PB05: MIN MASTER POSITION	mm	-99999.9	-99999.9 to 99999.9	Minimum position reachable by the master bridge.
PB06: ACCELERATION TIME	s	1.00	0.00 to 9.99	Time required to go from speed 0 to maximum speed.
PB07: DECELERATION TIME	s	1.00	0.00 to 9.99	Time required to go from maximum speed to speed 0.
PB08: REVERSAL TIME	s	0.50	0.00 to 9.99	Used to prevent mechanical stress due to too rapid changes in direction of movement.
PB09: DEACTIVATION TIME	s	0	0 to 99999	Rest time of the bridge beyond which the axis enabling output is deactivated.
PB10: OUTPUT MODE	-	STILL	MOVE, STILL	Axis enabling output operation mode.\ MOVE: The output activates before axis movement and deactivates after it has finished, following the timing set in parameters PB04 and PB05.\ STILL: The output activates before movement and deactivates only when the state enters emergency.
PB11: ABRASIVE CHANGE POSITION	mm	0.0	-99999.9 to 99999.9	Bridge positioning when requested to interrupt the cycle for abrasive change.
PB12: MASTER PRESET POSITION	mm	0.0	-99999.9 to 99999.9	Position loaded into the count when the axis activates and then releases the Homing sensor (master).

Parameter Name	Unit of Measure	Default	Range	Description
PB13: SLAVE PRESET POSITION	mm	0.0	-99999.9 to 99999.9	Position loaded into the count when the axis activates and then releases the Homing sensor (slave).
PB14: PRESET SPEED	%	5	1 to 100	Speed for the homing sensor search.
PB15: SLOW PRESET SPEED	%	2	1 to 100	Speed for releasing the homing sensor.
PB16: MASTER PRESET DIRECTION	-	BACKWARD	FORWARD, BACKWARD	Direction in which to search for the homing sensor (master).
PB17: SLAVE PRESET DIRECTION	-	BACKWARD	FORWARD, BACKWARD	Direction in which to search for the homing sensor (slave).
PB18: GANTRY HOMING MODE	-	2	1 to 2	Gantry homing mode only if 2 motors are used for bridge movement (one master and one slave) Homing mode 1: positioning will be done by disengaging the slave axis Homing mode 2: positioning will be done with master and slave axes always engaged Refer to the operator's manual for more information
PB19: MAX MISALIGNMENT	mm	1	0 to 999999.9	Maximum misalignment (mm) between master bridge axis and slave bridge axis before sending an alarm signal.
PB20: MAX HOMING MISALIGNMENT	mm	1	0 to 999999.9	Maximum misalignment (mm) between master bridge axis and slave bridge axis before sending an alarm signal during the homing phase.
PB21: SLAVE HOMING OFFSET	mm	0	-99999.9 to 99999.9	Displacement (mm) that the slave bridge axis must perform after homing.
PB22: MAX SLAVE POSITION	mm	99999.9	-99999.9 to 99999.9	Maximum position reachable by the slave bridge (slave).
PB23: MIN SLAVE POSITION	mm	99999.9	-99999.9 to 99999.9	Minimum position reachable by the slave bridge (slave).
PB24: MAX HOMING TIME	s	.	99999	Maximum time for performing homing.


2.5.1 Bridge Buttons / Settings

Calibration pages are divided into:

RESOLUTION 	setting the resolution of the master and slave axis
P. I. D. MASTER 	calibration procedure for the master axis to adjust feedback and set offset and maximum speed
P. I. D. SLAVE 	calibration procedure for the slave axis to adjust feedback and set offset and maximum speed Enabled only if parameter PG 07 = ON
JOG SLAVE 	manual jog procedure forward/backward for the slave axis Enabled only if parameter PG 07 = ON

Bridge Axis Resolution



Parameter Name	Unit of Measure	Default	Range	Description
MEASURE	mm	0.1	0 to 99999.9	Indicates the space, in units of measurement, traveled by the bridge to obtain the encoder pulses set in the <i>pulse</i> parameter.
PULSE	-	1	0 to 999999	Indicates the pulses multiplied by 4 provided by the bridge encoder to obtain the space set in the measure parameter. The ratio between measure and pulse is the encoder resolution and must have values between 1 and 0.000935.
 Gantry (master/slave connection) enable/disable button. Usable only if parameter PG 07 = ON				

Bridge Calibration

MASTER BRIDGE TUNING

CALIBRATION **OFF**

VOLTAGE OUTPUT 99999999 V

OFFSET 99999999 V

A **-** **+**
OFF

VELOCITY 99999999 mm/s
99999999 Hz

MAX VELOCITY 99999999 mm/s

POSITION **= 0** 99999999 mm
999999999999

SLAVE POSITION 99999999 mm

DISALIGNMENT 99999999 mm

POSITIONER **STOP**

DELTA 99999999 mm

SET VELOCITY 99999999 mm/s

ACC. TIME 99999999 s

DEC. TIME 99999999 s

FEEDFORWARD 99999999 %

PROP. GAIN 99999999

INTEGRAL TIME 99999999 s

MAX FOLL. ERROR 99999999 mm

INVERSION TIME 99999999 s

PROP. GAIN SLAVE 99999999

PROP. GAIN JOG M 99999999

PROP. GAIN JOG S 99999999


FOLLOW ERROR 99999999 mm

MAX. ERR. AXIS + 9999999 mm

MAX. ERR. AXIS - 9999999 mm

B1 B2 **RESET FOLLERR.**

Parameter Name	Unit of Measure	Default	Range	Description
OUT VOLTAGE	V	0.0	-10.0 to 10.0	Inverter/Driver control voltage
OFFSET	V	0.0000	-99.9999 to 99.9999	Voltage value to obtain 0 Volts from the analog output
SPEED	mm/'	-	-	Bridge speed
MAX SPEED	mm/'	5000	0 to 9999999	Bridge speed with 10 Volt command
POSITION	mm	-	-	Master bridge position
MASTER POSITION	mm	-	-	Master bridge position
MISALIGNMENT	mm	-	-	Current misalignment between master and slave
DELTA	mm	0.0	-	Bridge pendulum space
SET SPEED	mm/'	0	-	Bridge speed
ACCELERATION TIME	s	0.00	-	Acceleration time
DECELERATION TIME	s	0.00	-	Deceleration time
FEEDFORWARD	%	100.0	0.0 to 200.0	The percentage coefficient that, multiplied by the speed, generates the feed-forward part of the control output.
PROP. GAIN	-	0.000	0.000 to 9.999	The coefficient that, multiplied by the tracking error, generates the proportional part of the control output during automatic master movement.
INTEGRAL TIME	s	0.000	0.000 to 9.999	The time that produces the integral coefficient of tracking error. The integration of this error multiplied by this coefficient generates the integral part of the control output.
MAX TRACKING ERROR	mm	99.9	0.0 to 99999.9	Defines the maximum acceptable deviation between the theoretical position and the actual position of the axis, beyond which an alarm is generated.
REVERSAL TIME	s	1.0	1.0	Defines the axis reversal time during calibration.
TRACKING ERROR	mm	-	-	The instantaneous value of the tracking error.
MAX AXIS ERROR +	Not-modifiable. Indicates in mm the maximum tracking error of the axis during positive movement.			

Parameter Name	Unit of Measure	Default	Range	Description
MAX AXIS ERROR -	Not-modifiable. Indicates in mm the maximum tracking error of the axis during negative movement.			
	Gantry (master/slave connection) enable/disable button. Usable only if parameter PG 07 = ON			



SLAVE BRIDGE TUNING



CALIBRATION

OFF

VOLTAGE OUTPUT 99999999 U

OFFSET 99999999 U

A
OFF

-

+

VELOCITY 99999999 mm/s
99999999 Hz

MAX VELOCITY 99999999 mm/s

POSITION = 0 99999999 mm
9999999999

MASTER POSITION 99999999 mm

DISALIGNMENT 99999999 mm

POSITIONER

STOP

DELTA 99999999 mm

SET VELOCITY 99999999 mm/s

ACC. TIME 99999999 s

DEC. TIME 99999999 s

FEEDFORWARD 99999999 %

PROP. GAIN 99999999

INTEGRAL TIME 99999999 s

MAX FOLL. ERROR 99999999 mm

INVERSION TIME 99999999 s

FOLLOW ERROR 99999999 mm

MAX. ERR. AXIS + 99999999 mm

MAX. ERR. AXIS - 99999999 mm


▶▶



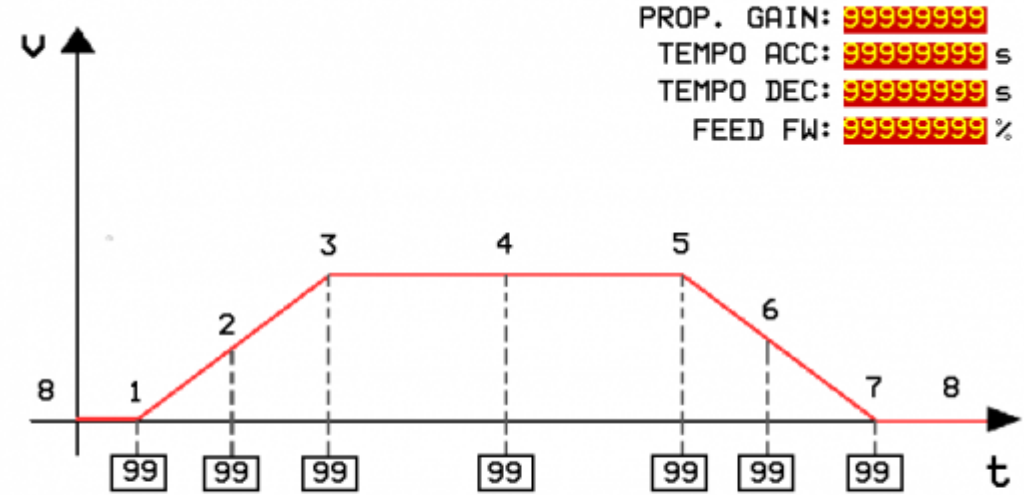
RESET
FOLL.ERR.

▶▶▶

Parameter Name	Unit of Measure	Default	Range	Description
OUT VOLTAGE	V	0.0	-10.0 to 10.0	Inverter/Driver control voltage
OFFSET	V	0.0000	-99.9999 to 99.9999	Voltage value to obtain 0 Volts from the analog output
SPEED	mm/'	-	-	Bridge speed
MAX SPEED	mm/'	5000	0 to 9999999	Bridge speed with 10 Volt command
POSITION	mm	-	-	Master bridge position
SLAVE POSITION	mm	-	-	Slave bridge position
MISALIGNMENT	mm	-	-	Current misalignment between master and slave
DELTA	mm	0.0	-	Bridge pendulum space
SET SPEED	mm/'	0	-	Bridge speed
ACCELERATION TIME	s	0.00	-	Acceleration time
DECELERATION TIME	s	0.00	-	Deceleration time
FEEDFORWARD	%	100.0	0.0 to 200.0	The percentage coefficient that, multiplied by the speed, generates the feed-forward part of the control output.
PROP. GAIN	-	0.000	0.000 to 9.999	The coefficient that, multiplied by the tracking error, generates the proportional part of the control output during automatic master movement.
INTEGRAL TIME	s	0.000	0.000 to 9.999	The time that produces the integral coefficient of tracking error. The integration of this error multiplied by this coefficient generates the integral part of the control output.
MAX TRACKING ERROR	mm	99.9	0.0 to 99999.9	Defines the maximum acceptable deviation between the theoretical position and the actual position of the axis, beyond which an alarm is generated.
REVERSAL TIME	s	1.0	1.0	Defines the axis reversal time during calibration.

Parameter Name	Unit of Measure	Default	Range	Description
PROP.GAIN SLAVE	-			The coefficient that, multiplied by the tracking error, generates the proportional part of the control output during automatic slave movement.
PROP.GAIN JOG M	-			The coefficient that, multiplied by the tracking error, generates the proportional part of the control output during master jog movement.
PROP. GAIN JOG S	-			The coefficient that, multiplied by the tracking error, generates the proportional part of the control output during slave jog movement.
TRACKING ERROR	mm	-	-	The instantaneous value of the tracking error.
MAX AXIS ERROR +	Not-modifiable. Indicates in mm the maximum tracking error of the axis during positive movement.			
MAX AXIS ERROR -	Not-modifiable. Indicates in mm the maximum tracking error of the axis during negative movement.			
	Gantry (master/slave connection) enable/disable button. Usable only if parameter PG 07 = ON			

PROP. GAIN & FEEDFORWARD



PROP. GAIN: 99999999

TEMPO ACC: 99999999 s

TEMPO DEC: 99999999 s


FEED FW: 99999999 %

GAIN 1:	99999999
GAIN 2:	99999999
GAIN 3:	99999999
GAIN 4:	99999999

GAIN 5:	99999999
GAIN 6:	99999999
GAIN 7:	99999999
GAIN 8:	99999999

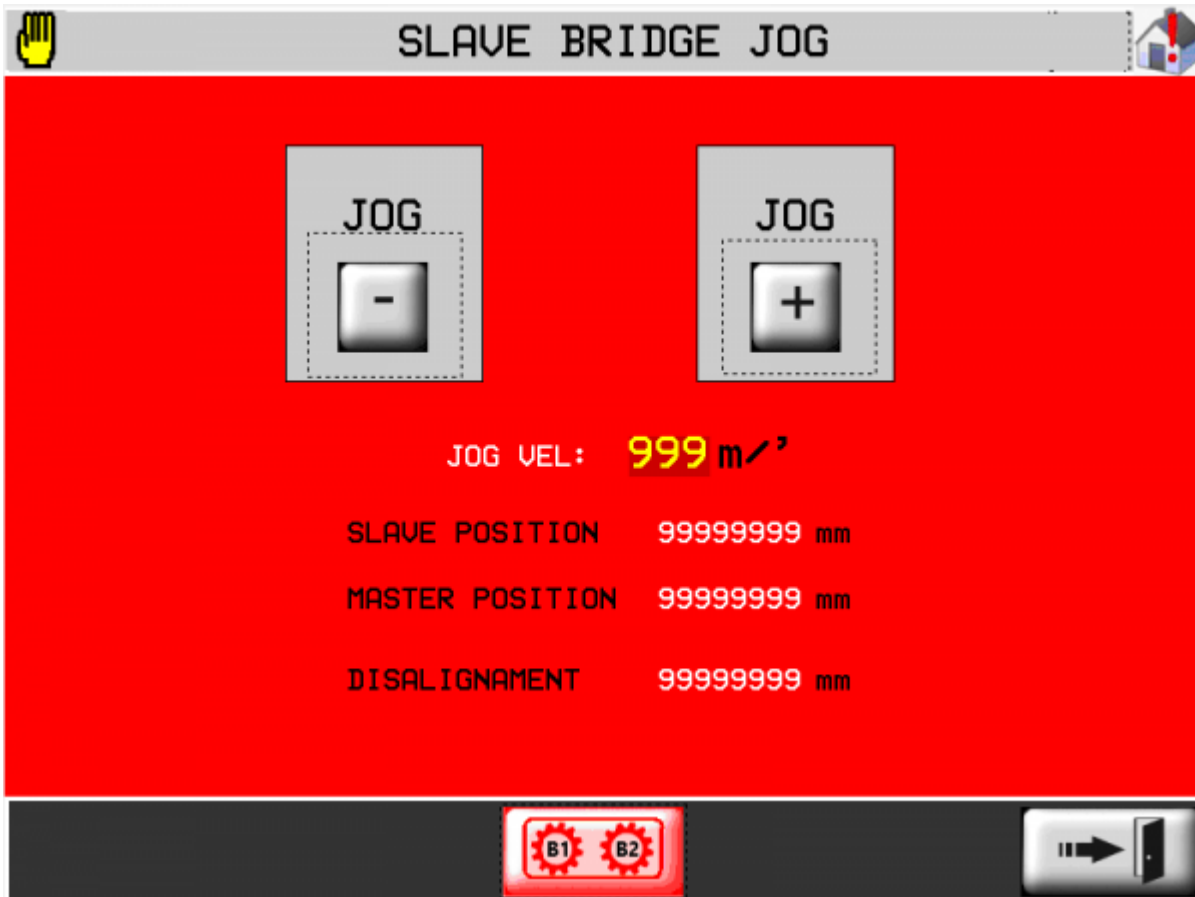
FFW 1:	99999999
FFW 2:	99999999
FFW 3:	99999999
FFW 4:	99999999


FFW 5:	99999999
FFW 6:	99999999
FFW 7:	99999999
FFW 8:	99999999



The following page is for **exclusive** use by technical support. On this page, you can adjust the gain and feedforward at different points along the axis position.
 Default values at 0.

Jog bridge slave



Parameter name	Unit of measure	Default value	Range	Description
VEL JOG	%	0.0	0 to 100	Jog command speed in percentage
SLAVE POSITION	mm	-	-	Position of the slave bridge
MASTER POSITION	mm	-	-	Position of the master bridge
DISALIGNMENT	mm	-	-	Current misalignment between master and slave
	Enable/disable gantry button (master/slave connection). Usable only if parameter PG 07 = ON			

2.6 Setup Heads

TOOLS

DIAMETER		ORTHOGONAL OFFSET	
1	PT01: 9999999 mm	1	PT23: 9999999 mm
2	PT02: 9999999 mm	2	PT24: 9999999 mm
3	PT03: 9999999 mm	3	PT25: 9999999 mm
4	PT04: 9999999 mm	4	PT26: 9999999 mm
5	PT05: 9999999 mm	5	PT27: 9999999 mm
6	PT06: 9999999 mm	6	PT28: 9999999 mm
7	PT07: 9999999 mm	7	PT29: 9999999 mm
8	PT08: 9999999 mm	8	PT30: 9999999 mm
9	PT09: 9999999 mm	9	PT31: 9999999 mm
10	PT10: 9999999 mm	10	PT32: 9999999 mm
11	PT11: 9999999 mm	11	PT33: 9999999 mm
12	PT12: 9999999 mm	12	PT34: 9999999 mm
13	PT13: 9999999 mm	13	PT35: 9999999 mm
14	PT14: 9999999 mm	14	PT36: 9999999 mm
15	PT15: 9999999 mm	15	PT37: 9999999 mm
16	PT16: 9999999 mm	16	PT38: 9999999 mm
17	PT17: 9999999 mm	17	PT39: 9999999 mm
18	PT18: 9999999 mm	18	PT40: 9999999 mm
19	PT19: 9999999 mm	19	PT41: 9999999 mm
20	PT20: 9999999 mm	20	PT42: 9999999 mm
21	PT21: 9999999 mm	21	PT43: 9999999 mm
22	PT22: 9999999 mm	22	PT44: 9999999 mm

TOOLS

TIME TO PARTIAL LIFT	MIN ASCENT
PT45: 9999999 ms	1 PT89: 9999999 mm
	2 PT90: 9999999 mm
	3 PT91: 9999999 mm
	4 PT92: 9999999 mm
	5 PT93: 9999999 mm
	6 PT94: 9999999 mm
	7 PT95: 9999999 mm
	8 PT96: 9999999 mm
	9 PT97: 9999999 mm
	10 PT98: 9999999 mm
	11 PT99: 9999999 mm
	12 PT100: 9999999 mm
	13 PT101: 9999999 mm
	14 PT102: 9999999 mm
	15 PT103: 9999999 mm
	16 PT104: 9999999 mm
	17 PT105: 9999999 mm
	18 PT106: 9999999 mm
	19 PT107: 9999999 mm
	20 PT108: 9999999 mm
	21 PT109: 9999999 mm
	22 PT110: 9999999 mm

Parameter Name	Unit of Measure	Default Value	Range	Description
PT01 / PT22 : DIAMETER	mm	0.0	0 to 99999.9	Diameter of the head.
PT23 / PT44 : ORTHOGONAL OFFSET	mm	0.0	0 to 99999.9	It is the distance between the working head and the bridge's centerline.

Parameter Name	Unit of Measure	Default Value	Range	Description
PT45 : PARTIAL RISE TIME	s	0.500	0 to 999.999	It is the excitation time of the output for partial rise. Valid for all heads.
PT89 / PT110 : MINIMUM RISE	s	0.000	0 to 999.999	Minimum rise value. Generates an alarm if the head performs a partial rise below the set value.

2.7 Sensor Setup

SENSORS

01 02 03 04 05 06 07 08 09 10 11 12 13 14 15 16 17 18 19 20 21 22 23 24 25 26 27 28 29 30 31 32 33 34 35 36 37 38 39 40 41 42 43 44 45 46 47 48 49 50 51 52 53 54 55 56 57 58 59 60 61 62 63 64

= SENSOR ENABLE
 = SENSOR NOT READING
 = SENSOR ALWAYS READING

PS01: BAR SENSORS NUMBER 99999
 PS02: TYPE SENSORS N.O
 PS03: ERRORS TOLERANCE: FALSE POSITIVE 99999
 PS04: ERRORS TOLERANCE: FALSE NEGATIVE 99999

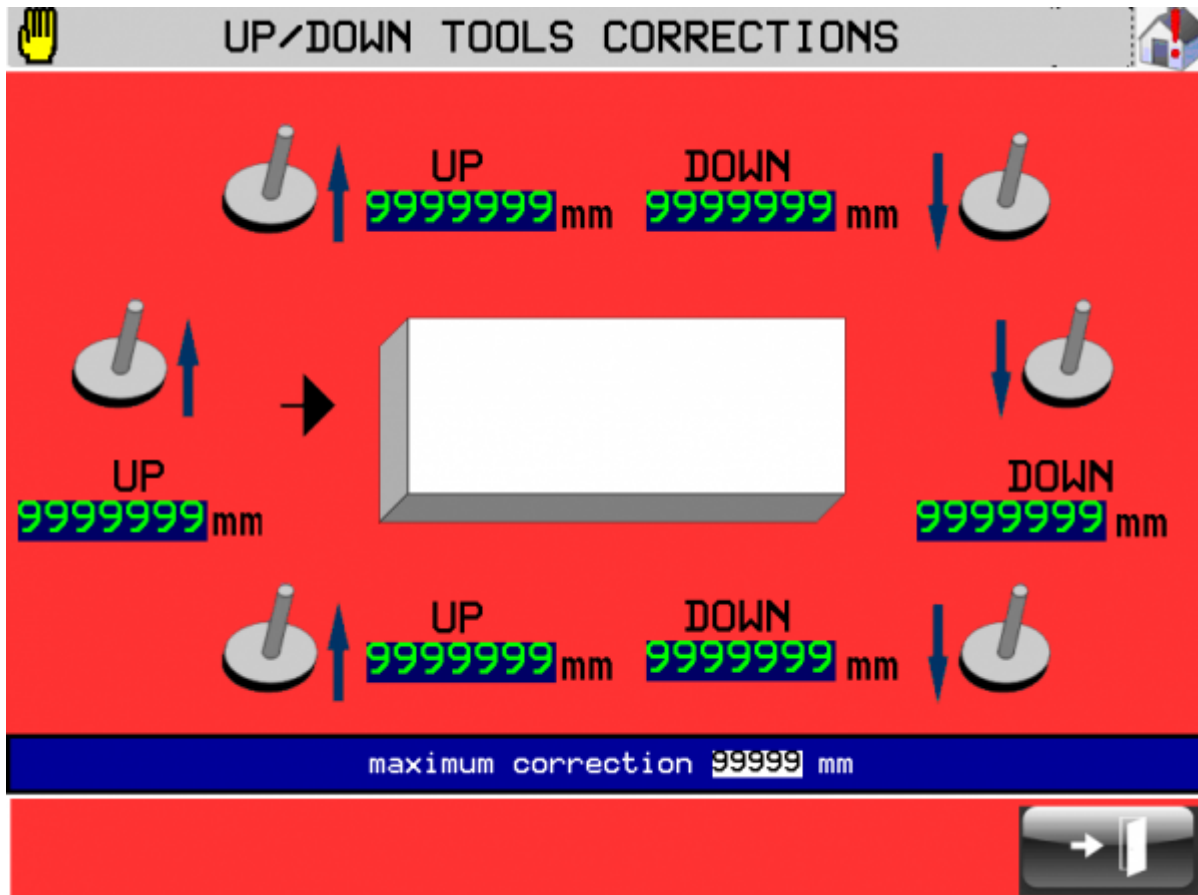
- Enabled sensor
- Faulty sensor, reads 0 while the two adjacent sensors read 1
- Faulty sensor, reads 1 while the two adjacent sensors read 0

On this page, you can disable a sensor by clicking on it. A sensor should be disabled (green LED off) if it reads 1 instead of 0 (always active).

Caution: During each machine startup after a shutdown, all sensors are automatically enabled. Faulty sensors should be fixed as soon as possible.

Parameter Name	Unit of Measure	Default Value	Range	Description
PS01 : NUMBER OF SENSORS	-	32	8 to 64	Number of sensors on the acquisition bar.
PS02 : SENSOR TYPE	-	NO	NO to NC	Logic of the slab acquisition inputs. NO = Normally Open NC = Normally Closed
PS03 : FALSE POSITIVE ERROR TOLERANCE	-	0	0 to 1000	Indicates the number of steps or scans required in the case of a serious error (sensor reads 1 instead of 0) before an alarm is triggered. Zero tolerance is a special value indicating that error checking is not performed, so with a value = 0, there will never be an alarm.
PS04 : FALSE NEGATIVE ERROR TOLERANCE	-	0	0 to 1000	Indicates the number of steps or scans required in the case of a solvable error (sensor reads 0 instead of 1) before a warning is triggered. Zero tolerance is a special value indicating that error checking is not performed, so with a value = 0, a warning will never occur.

2.8 Corrections Setup





On this page, you can input permanent corrections for the rise(UP)/fall(DOWN) of the heads. Corrections can be horizontal or vertical, affecting all edges of the material.

Positive values for rise	the head will rise later to polish the material
Negative values for rise	the head will rise earlier to polish the material
Positive values for fall	the head will descend earlier to polish the material
Negative values for fall	the head will descend later to polish the material
Maximum correction	value to input to determine the maximum achievable correction

3. Support

For supplying you fast service, at the lowest cost, we need your support.




	
<p>Follow all instructions provided in the MIMAT manual</p>	<p>If the problem remains, fill out the "Request Form for assistance" on the page Contacts at www.qem.it site. Our technicians will get elements essential for the understanding of your problem.</p>

Repair

To provide you with an efficient service, please read and adhere to the instructions given [here](#)

Shipping

It is recommended to pack the instrument with materials that are able to cushion any falls.

		
<p>Use the original package: it must protect the instrument during transport.</p>	<p>Attach:</p> <ol style="list-style-type: none"> 1. A description of the anomaly; 2. A part of the electric scheme where the equipment is inserted 3. The planning of the equipment (set up, quotas of job, parameters...). 4. Request a quote for repair; if not required, the cost will be calculated in the final balance. 	<p>A full description of the problem, will help identify and resolve your problems fast. A careful packaging will avoid further inconveniences.</p>

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