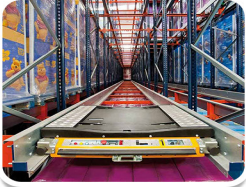




# Brushless DC (BLDC) Motor Controller 4Q.BDC.DRV.200S



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# WARNING

Date :24.05.2022

## TOPICS TO BE CONSIDERED

### WARNINGS

To avoid electrical shock and damage to the device, do not remove or install the device cover or control the input-output socket while it is energized.

Contact authorized personnel only for service.

The use of the device other than those specified here creates a hazard.

Please use the device by following the points stated in the user manual.

### SAFETY

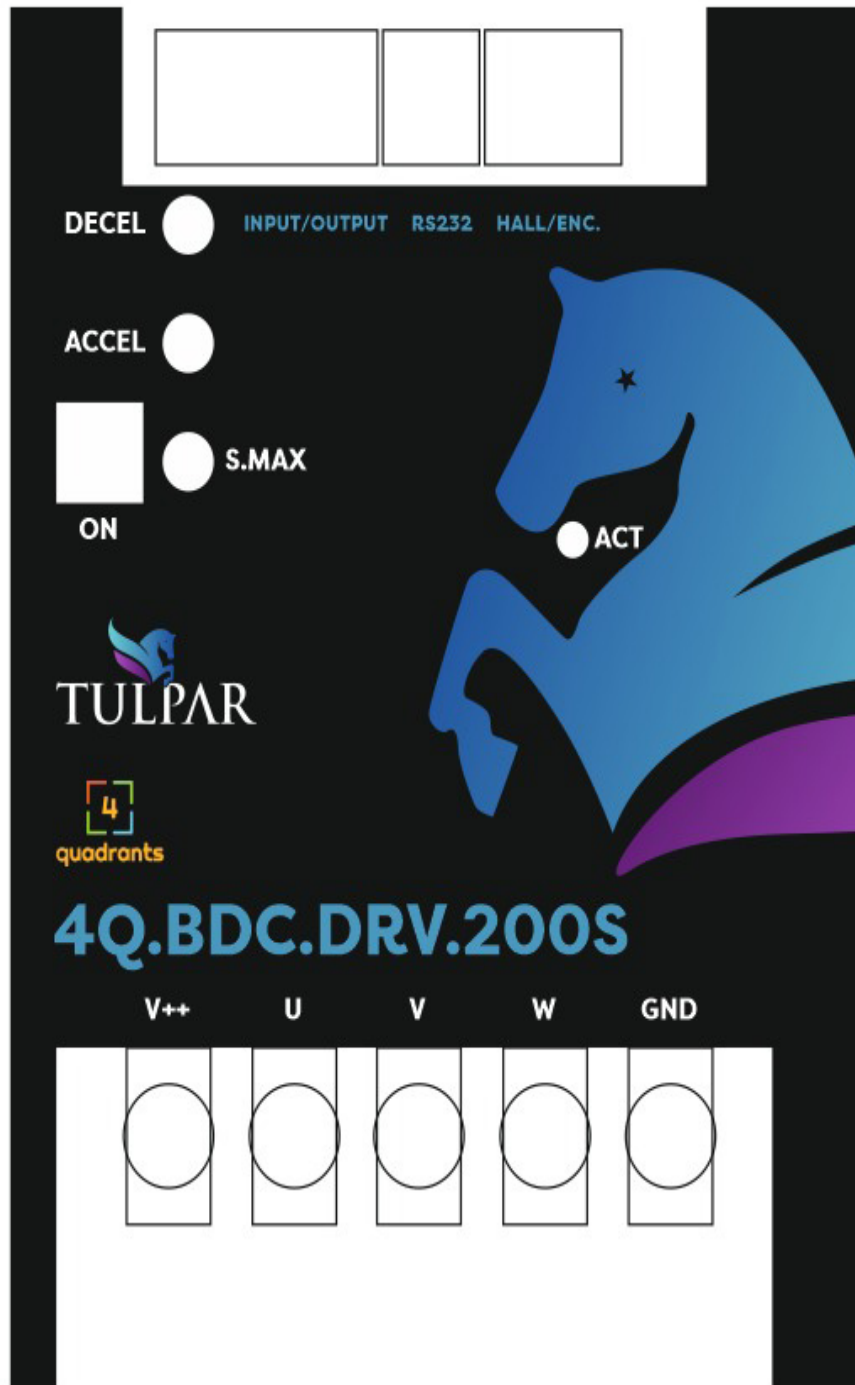
This product has been designed with high safety standards in mind. Any electrical device that is not used correctly can cause fire, electric shock, or personal injury.

For the accident-free operation of the device, follow the instructions below.

- Follow all warnings and instructions.
- The device is manufactured in IP54 Standard. Take necessary precautions without operating in excessively humid or hot places.
- Install the cooler of the device on a full metal surface.
- Use a fuse of sufficient value for the device supply input.
- When the device is energized, check the PWR LED lights up.
- Do not disconnect or plugin any cables while the drive is running.
- Regularly check the BATTERY, MOTOR, and CONTROL cables for damage.
- To run the engine efficiently, use the BATTERY and MOTOR cables according to current needs.
- If the device is operating abnormally, making unusual noises, or overheating stop immediately.
- Contact authorized service personnel or our company and ask for help.
- Using the device outside the specified conditions creates a hazard and in the event of a malfunction, the device will be out of warranty

Operating Voltage	10VDC - 72VDC
Start Current ( 2sn ) :	120 Amper
Continuous Output Current	15-30-50 A
Current Limit	3A - 50 A
Current Limit Resolution	0.1A
PWM Frequency	16 kHz
PWM Duty Rate:	% 0.1 ~ 99.0
Braking:	REGENERATIVE
MOSFET Resistance	< 0.5 mΩ
Productivity	> %96
Standby Current	< 50 mA
Speed Reference Input	Pot , 0 - 5V or 0 - 10V
	If SW1 On Pot or 0 - 5 V
	If SW1 Off 0 - 10V
Parameter Setting	4 Pot or Internal Parameters
	If SW2 is On External ( 3 Pot )
	If SW2 is Off Internal
Error Output ( IO )	Open Collector ( 80 Ω )
	External Pull-up Resistance: 2.4 kΩ - 10 kΩ
Motor Voltage Reference Output ( 0 - 5V )	Motor Voltage / 10
HALL Sensor Input	5VDC U , V , W ( Closed Loop )
Indicator LEDs	Constant red : Key Entry is passive , red flash optional : error
	Yellow : ready for forward or reverse motion
	Green: forward movement , blue: backward movement
Brake Relay	Motor magnetic brake opener
Drive temperature setting	adjustable 0..80° C
Parameter Setting	Operating ( -20 .+ 40 ) ° C Rs232 , Modbus RTU , Can bus ( optional )
Dimensions	134 x 89,50 x 39,30 mm

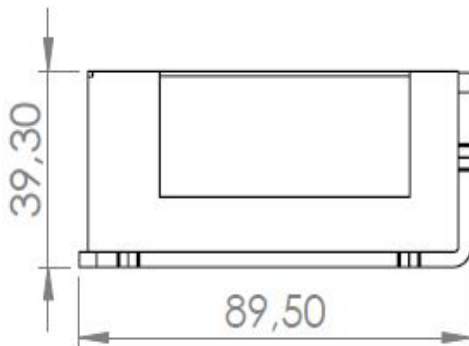
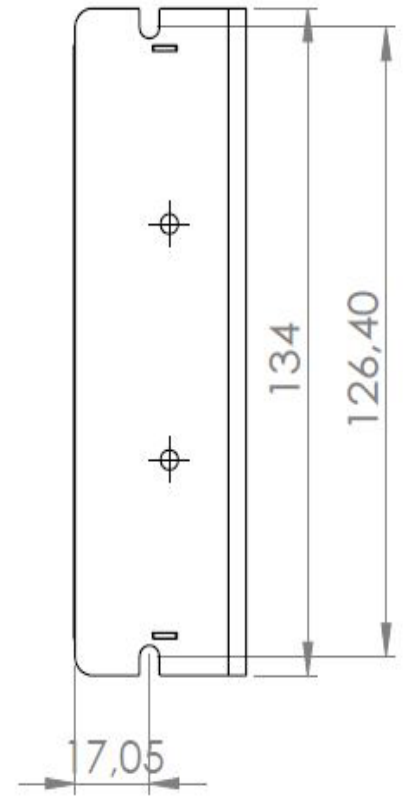
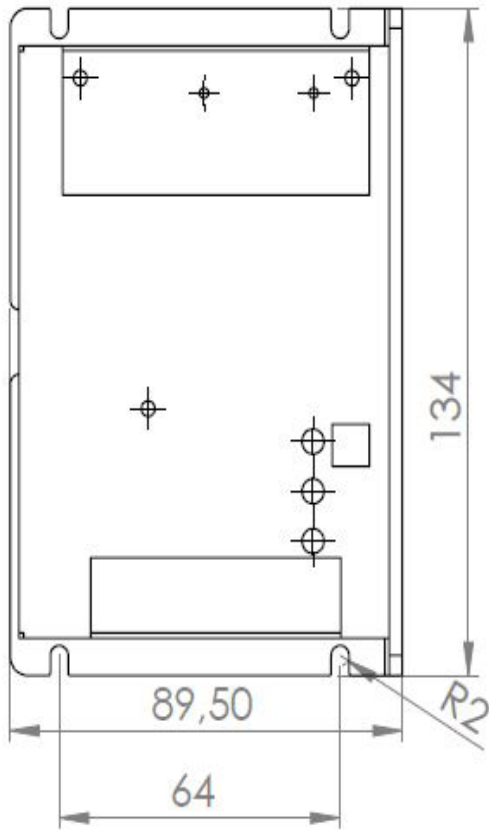
# DIMENSIONS



To protect the circuit from external EMC and physical effects and for optimum heat transfer, the PCB design 4 layers and Power / Logic layers are realized separately from each other.

# DIMENSIONS

Fixing holes and all dimensions in millimeters.



# DEFINITIONS

## OPERATION OF THE TULPAR 200 CONTROLLER

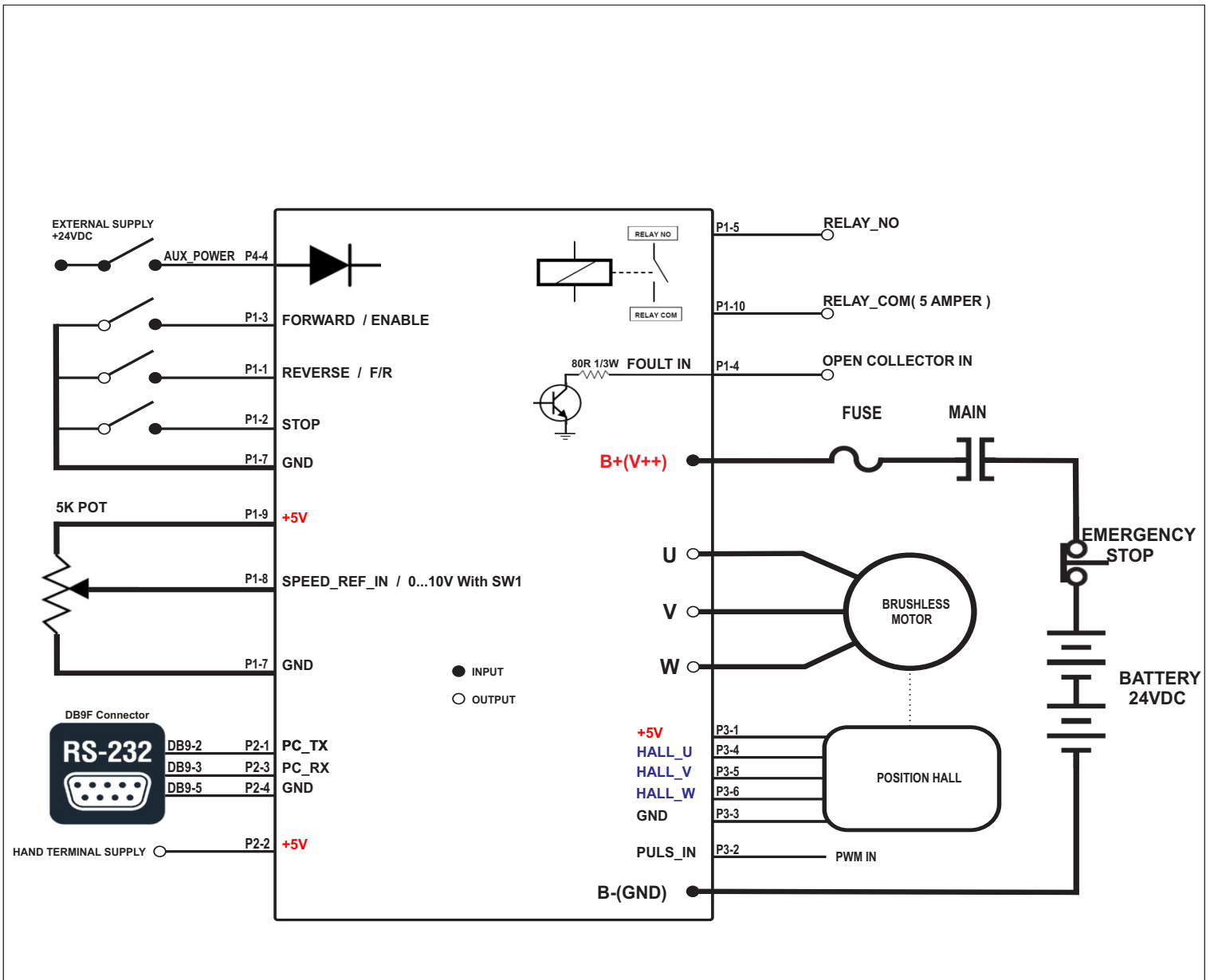
The control unit has bidirectional operation and REGENERATIVE braking feature. Microprocessor controlled, real time calculations to be provided to the engine. Fixed parameters can be loaded and read from the computer interface.

Design:

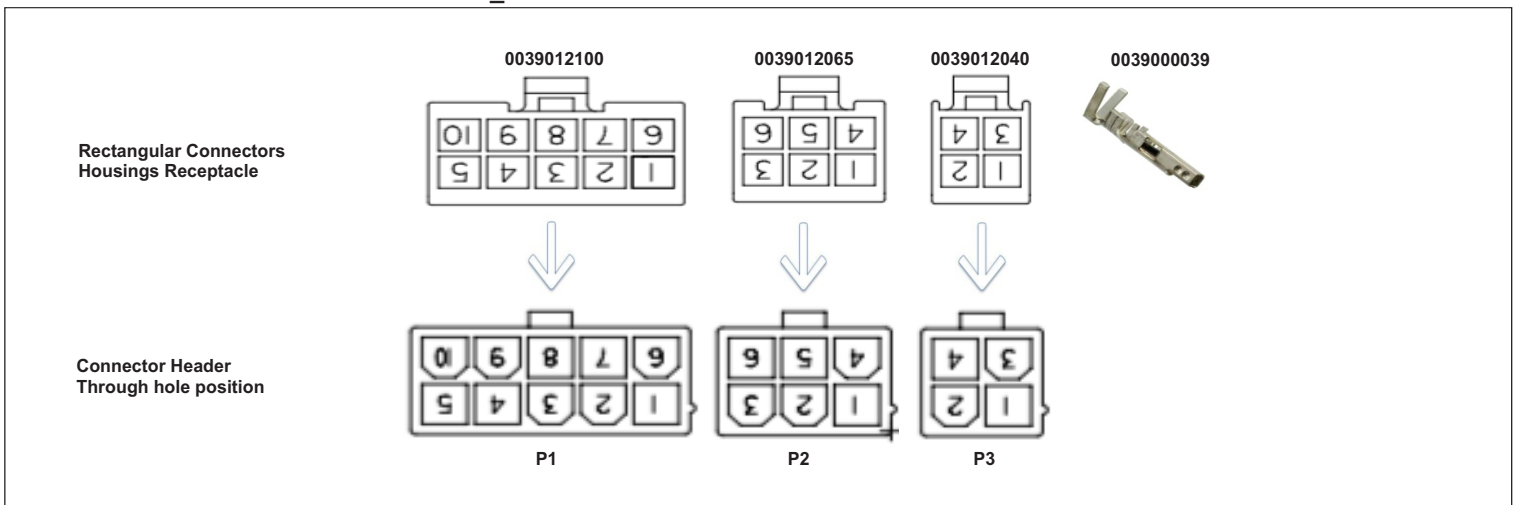
- 10VDC - 72VDC Supply Input
- Ability to work at current 120A starting
- 15A-30A-50A 1 Hour Operation
- Current Limit Resolution 0.1 Amper
- PWM Frequency 16kHz
- PWM Ratio 0.1 - 99.0%
- REGENERATIVE Braking Continuous
- Mosfet Resistance <0.5 mOhm
- Standby Current <50mA
- Forward - Reverse - Stop Digital Inputs
- Speed and ramp adjustment with internal or external S.Max , Accel , Decel Pot
- Low and High Voltage ALARM
- Ability to set or limit motor CURRENT
- EMERGENCY STOP
- FAULT Digital Inputs
- Braking Output and Control System
- Analog Output 0 - 5V Motor Voltage Reference
- Red Status Indicator LED
- Encoder or HALL Sensor Feedback
- Main board temperature measurement and monitoring
- General Purpose Dry Contact - RS232 Data cable sample Motor Voltage, Current monitoring and recording software

# CIRCUIT DIAGRAM

## TULPAR\_200 CONNECTOR WIRING STANDARD CONFIGURATION



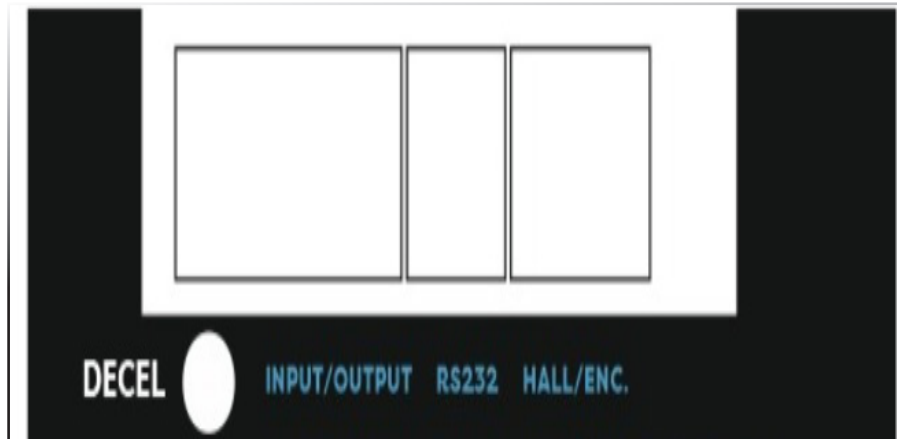
## TULPAR\_200 MOLEX CONNECTOR





# INPUT & OUTPUT P1-10

Figure - 5 P1 I/O CONNECTOR



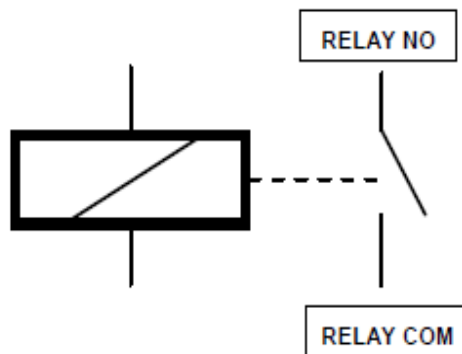
1	P1-1	REVERSE DIR / FR
2	P1-2	STOP
3	P1-3	FORWARD DIR / ENABLE
4	P1-4	FAULT ( IO )
5	P1-5	RELAY NO(Normally open contact - Motor magnetic brake opener )
6	P1-6	AUX POWER ( Digital Supply Input)
7	P1-7	GND
8	P1-8	SPEED LIMIT ANLG INPUT 5K POT , 0-5VDC INPUT, 0-10VDC
9	P1-9	5V ( 50mA ) ( HAND TERMINAL SUPPLY )
10	P1-10	RELAY COM ( Motor magnetic brake opener )

# OUTPUT P1-10 ( RELAY )

Figure -6 P1 RELAY CIRCUIT



TERMINAL NO	PCB NO	DESCRIPTION
5	P1-5	RELAY COM
10	P1-10	RELAY NO



## INPUT & P1-10 ( FAULT IO & SPEED LIMIT )

Figure - 8 P1 FAULT IO & SPEED LIMIT



TERMINAL NO	PCB NO	DESCRIPTION
8	P1-8	SPEED REF INPUT
4	P1-4	FAULT (IO)
7	P1-7	GND
9	P1-9	5V (50mA)
6	P1-6	AUX POWER ( Digital Supply Input)

# INPUT & P1-10 ( FORWARD , REVERSE & STOP )

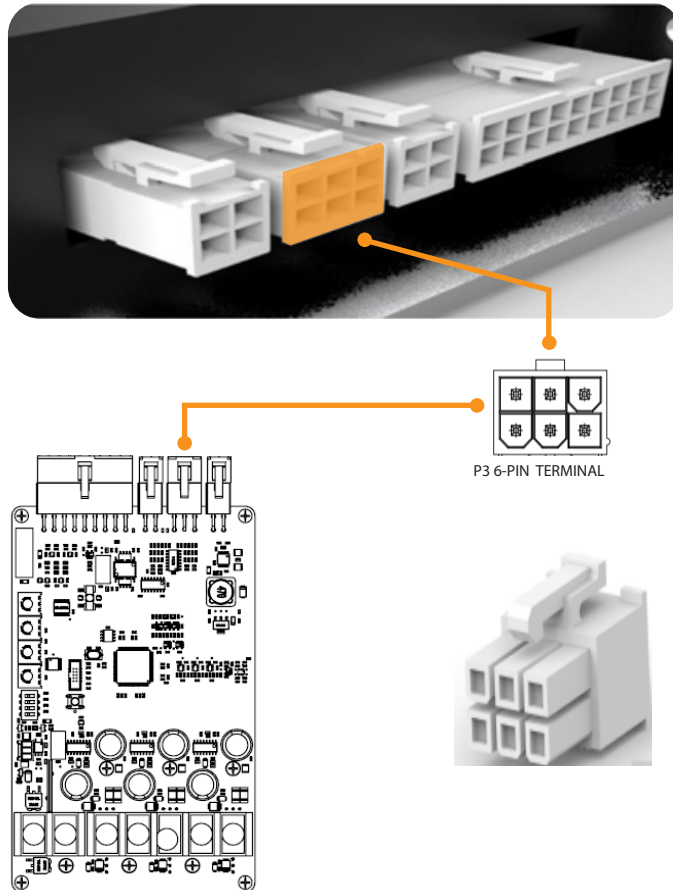
Figure - 11 P1 FORWARD , REVERSE & STOP INPUT CIRCUIT



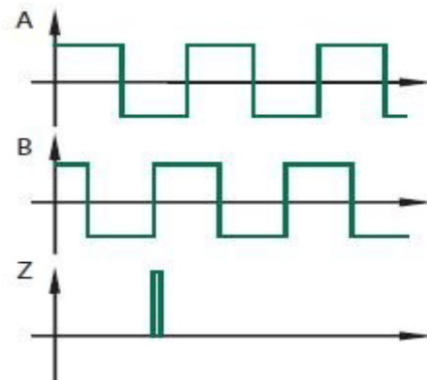
TERMINAL NO	PCB NO	DESCRIPTION
1	P1-1	REVERSE DIR / FR
2	P1-2	STOP
3	P1-3	FORWARD DIR / ENABLE
7	P1-7	GND

# INPUT & P3-6 ( HALL SENSOR & ENCODER )

Figure - 12 P3 HALL SENSOR & ENCODER CIRCUIT



TERMINAL NO	PCB NO	DESCRIPTION
1	P3-1	5V (0.1A) (HALL SENSOR & ENCODER SUPPLY)
2	P3-2	PULSE INPUT
3	P3-3	GND
4	P3-4	ENC Z / HALL-U
5	P3-5	ENC B / HALL-V
6	P3-6	ENC A / HALL-W



# ACT LED NOTIFICATIONS



## ACT LED NOTICES:

Periods 1-2 sec in normal condition

Drive Stop Status: Red 1s on, 1s off

On take-off ramp: Red (250msec on - 250msec off)

In forward and reverse speed control: Red (500msec on - 500msec off)

In case of error: (RED LIGHT)

Drive Stop Status	Red
Forward Active	Red(Proportional to Duty Cycle)
Reverse Active	Red(Proportional to Duty Cycle)
Drive Brake Active	Red(Constant)
In case of error	Red
<b>Periods 4sec in case of error</b>	
Key Entry Passive	Solid red
Low Voltage	(250mS on + 250mS off)x1 + 3.5sn passive
Over Current	(250mS on + 250mS off)x2 + 3.0sn passive
High Voltage	(250mS on + 250mS off)x3 + 2.5sn passive
Min> Max Speed	(250mS on + 250mS off)x4 + 2.0sn passive
High Drive Temperature	(250mS on + 250mS off)x5 + 1.5sn passive
High Motor Temperature	(250mS on + 250mS off)x6 + 1.0sn passive
External Fault Input Active	(250mS on + 250mS off)x7 + 0.5sn passive

# COMPUTER COMMUNICATION

The standard RS-232 connection is used for the hand terminal / PC connection. Thanks to this connection, read/write operations can be made for all parameters in the driver.

## Computer Interconnect Cable:

To read parameters from the driver, to see the motor current and voltage values, PC connection must be made first.

1 - Energy connections must be made to the driver first.

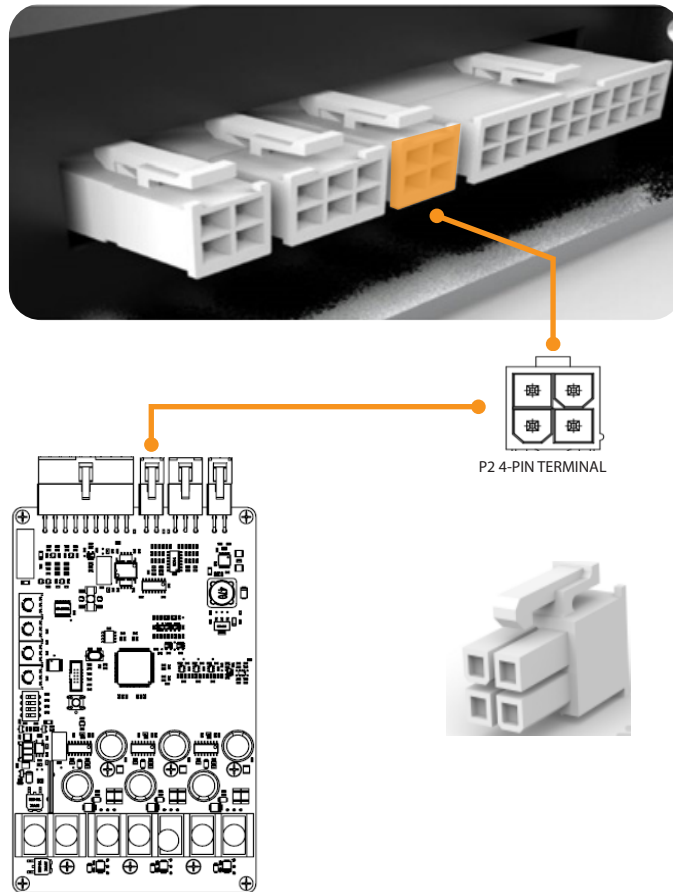
2 - Then, the computer coming out of the box should be plugged into the socket cable.

(P2 - 4)

**IF YOU DO NOT HAVE RS232 PORT ON YOUR COMPUTER, YOU CAN USE USB TO RS232 CONVERTER.**

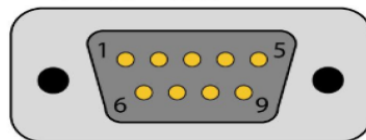
# INPUT & P2-4 ( RS232 COMMUNICATION )

Figure - 14 P2 RS232 & HAND TERMINAL CIRCUIT



TERMINAL NO	PCB NO	DESCRIPTION
1	X21	RS232 RX
2	X22	5V (0.1A) (HAND TERMINAL SUPPLY)
3	X23	RS232 TX
4	X24	GND

DB9M Connector



RS232 Pin Out

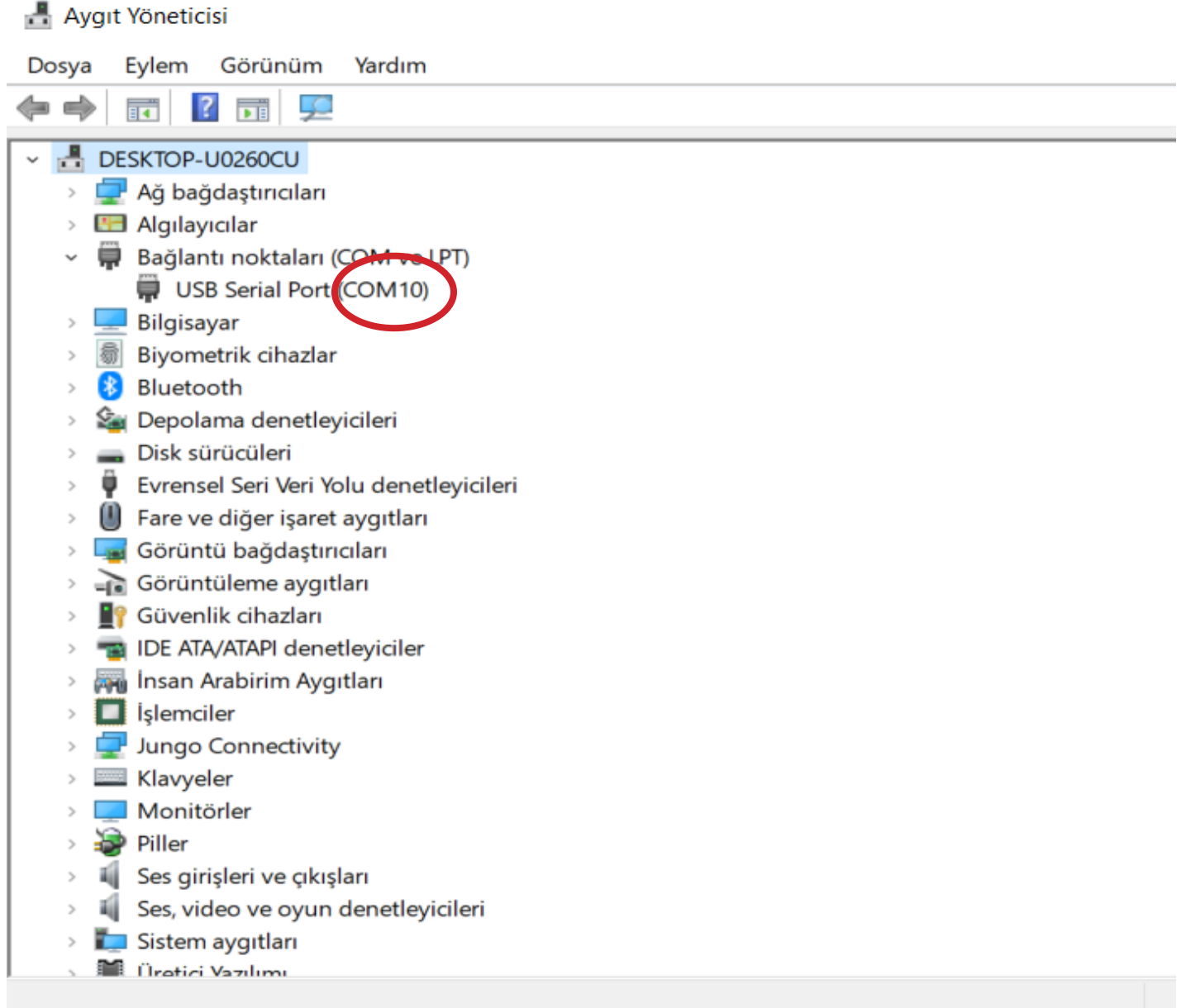
Pin #	Signal
1	DCD
2	RX
3	TX
4	DTR
5	GND
6	DSR
7	RTS
8	CTS
9	RI



# COM PORT IDENTIFICATION

The number of the USB or RS232 Port is determined by looking at the computer device manager.

Figure - 15 COM PORT IDENTIFICATION



Then the NES\_DRIVE\_STUDIO program is installed and run.

# Nes Drive Studio COM PORT SELECTION

Figure - 16 P4 COM PORT SELECTION



The motor driver to be used is selected.

It is then opened by selecting the com port. Program menus can be viewed by selecting the virtual port.

## P2-4 ( RS232 COMMUNICATION & RS485 Modbus RTU )

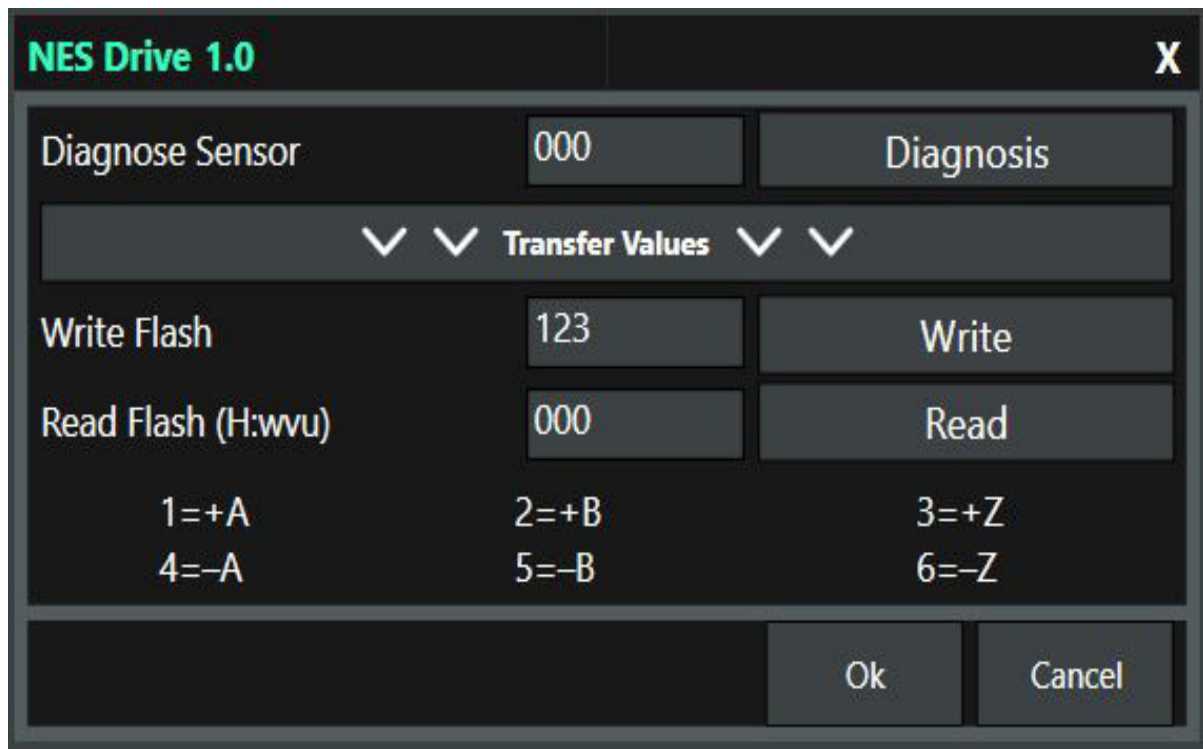
Tag Name	Address	Data Type	Scaling	Raw Low	Raw High	Scaled Low	Scaled High	Scaled Data Type	R/W
1-Maksimum Speed Rate [%]	40001	Word	0,100	0	1000	0	100	%	R/W
2-Minimum Speed Rate [%]	40002	Word	0,100	0	1000	0	100	%	R/W
3-Acceleration Time[s]	40003	Word	0,001	250	99000	0,25	99	Second	R/W
4-Deceleration Time[s]	40004	Word	0,001	250	99000	0,25	99	Second	R/W
5-Maksimum Battery Voltage[V]	40005	DWord	0,001	10000	100000	10	100	Voltage	R/W
6-Minimum Battery Voltage[V]	40007	DWord	0,001	10000	100000	10	100	Voltage	R/W
7-Current Protection Limit[A]	40009	DWord	0,001	1000	500000	1	500	Ampere	R/W
8-Time Witout Protection Time[s]	40011	Word	0,001	10	3000	0,01	3	Second	R/W
9-Dijital Input Type [0-Sev 1-Ken]	40012	Word	1,000	0	1	0	1	Level	R/W
10-Driver Ptection Limit[°C]	40013	Word	0,010	0	8500	0	85	Temperature	R/W
11-Driver Protection Limit[°C]	40014	Word	0,010	0	10000	0	100	Temperature	R/W
12-Torque Reference In [%]	40015	Word	0,100	0	1000	0	100	%	R
13-Motor Voltage [V]	40016	Long	0,001	-100000	100000	-100	100	Voltage	R
14-Drive Temperature [°C]	40018	Short	0,010	-100000	10000	-1000	100	Temperature	R
15-Motor Temperature [°C]	40019	Short	0,010	-100000	10000	-1000	100	Temperature	R
16-Speed Referance Input[%]	40020	Word	0,100	0	1000	0	100	%	R
17-Supply Voltage[V]	40021	DWord	0,001	0	100000	0	100	Voltage	R
18-Motor Current [A]	40023	Long	0,001	-500000	500000	-500	500	Ampere	R
19-Aktif PWM Duty [%]	40025	Word	0,100	-1000	1000	-100	100	%	R
20-Aktif Motor rpm [RPM]	40026	Long	1,000	-30000	30000	-30000	30000	RPM	R
21-Aktif Speed Pilot [RPM]	40028	Long	1,000	-30000	30000	-30000	30000	RPM	R
22-Closed Loop Control [0-Pas 1-Akt]	40029	Word	1,000	0	1	0	1	Select	R
23-00_BUS_VOLTAGE_MIN_ER-ROR	40030,0	Boolean	1,000	0	1	0	1	Error Message	R
23-01_CURRENT_MAX_ERROR	40030,1	Boolean	1,000	0	1	0	1	Error Message	R
23-02_BUS_VOLTAGE_MAX_ER-ROR	40030,2	Boolean	1,000	0	1	0	1	Error Message	R
23-03_MIN_MAX_SPEED_ER-ROR	40030,3	Boolean	1,000	0	1	0	1	Error Message	R
23-04_BOARD_TEMP_MAX_ER-ROR	40030,4	Boolean	1,000	0	1	0	1	Error Message	R
23-05_MOTOR_TEMP_MAX_ER-ROR	40030,5	Boolean	1,000	0	1	0	1	Error Message	R
23-06_EXT_ERROR_INP_ERROR	40030,6	Boolean	1,000	0	1	0	1	Error Message	R
23-07_UNDEFINED_ERROR	40030,7	Boolean	1,000	0	1	0	1	Error Message	R
23-08_HALL_SENSOR_ERROR	40030,8	Boolean	1	0	1	0	1	Error Message	R
23-09_MB_TIME_OUT_ERROR	40030,9	Boolean	1	0	1	0	1	Error Message	R/W
24-00_Digital Input SW_1	40031,0	Boolean	1,000	0	1	0	1	Notification bit	R
24-01_Digital Input SW_2	40031,1	Boolean	1,000	0	1	0	1	Notification bit	R
24-02_Digital Input SW_3	40031,2	Boolean	1,000	0	1	0	1	Notification bit	R
24-03_Digital Input SW_4	40031,3	Boolean	1,000	0	1	0	1	Notification bit	R
24-04_Digital Input FORWARD / ENABLE	40031,4	Boolean	1,000	0	1	0	1	Notification bit	R
24-05_Digital Input STOP	40031,5	Boolean	1,000	0	1	0	1	Notification bit	R
24-06_Digital Input REVERSE /FR	40031,6	Boolean	1,000	0	1	0	1	Notification bit	R
24-07_Digital Input Hold	40031,7	Boolean	1,000	0	1	0	1	Notification bit	R
24-08_Digital Input Fault	40031,8	Boolean	1,000	0	1	0	1	Notification bit	R
24-09_Digital Input KewSW	40031,9	Boolean	1,000	0	1	0	1	Notification bit	R

## P2-4 ( RS232 COMMUNICATION & RS485 Modbus RTU )

Tag Name	Address	Data Type	Scaling	Raw Low	Raw High	Scaled Low	Scaled High	Scaled Data Type	R/W
25-Motor Torque [Nm]	40032	Long	0,100	-10000	10000	-1000	1000	Nm(Torque)	R
30-Proportional Coefficient [P]	40034	DWord	0,001	1	99999	0,001	99,999	Proportional Coefficient	R/W
31-Integral Coefficient [I]	40036	DWord	0,001	1	99999	0,001	99,999	Proportional Coefficient	R/W
32-Derivative Coefficient[D]	40038	DWord	0,001	1	99999	0,001	99,999	Proportional Coefficient	R/W
33-Encoder Pals (Number of poles in Tulpar series)	40040	DWord	1,000	6	2048	6	2048	ppr	R/W
34-Motor %100 Rpm[rpm]	40042	DWord	1,000	1	30000	1	30000	RPM	R
35-Number of Poles(Tulpar) [pole]	40044	Word	1,000	1	100	1	100	pole	R/W
36-hall sensor adjustment [wvu]	40045	Word	1,000	123	654	123	654	wvu	R/W
37-Hall Sensor Calibration [wvu]	40046	Word	1,000	123	654	123	654	wvu	R/W
38-Spd Cal Volt L [100mV] Calibration	40047	Word	0,001	75	125	0,075	0,125	Voltage	R/W
39-Spd Cal Volt H [5V0] Calibration	40048	Word	0,001	4925	5075	4,925	5,075	Voltage	R/W
40-Spd Cal Adc L [2066] Calibration	40049	Word	1,000	2029	2103	2029	2103	Voltage	R/W
41-Spd Cal Adc H [2978] Calibration	40050	Word	1,000	2922	3034	2922	3034	Voltage	R/W
42-Spd Cal Volt In [V] Calibration	40051	Short	0,001	-10250	10250	-10,25	10,25	Voltage	R/W
43-R01-Remote Mode Timeout	41001	DWord	0,001	1	4294967295	0,001	4294967,295	Second	R/W
44-R02-Remote Mode Enable	41003	Word	1,000	0	10	0	10	Active - Pasive	R/W
45-R03-Remote Digital Input Enable	41004	Word	1,000	0	10	0	10	Active - Pasive	R/W
46-R04-Remote Digital Input FORWARD	41005	Word	1,000	0	10	0	10	Active - Pasive	R/W
47-R05-Remote Digital Input STOP	41006	Word	1,000	0	10	0	10	Active - Pasive	R/W
48-R06-Remote Digital Input REVERSE	41007	Word	1,000	0	10	0	10	Active - Pasive	R/W
49-R07-Remote Digital Input Hold	41008	Word	1,000	0	10	0	10	Active - Pasive	R/W
50-R08-Remote Analog Input Enable	41009	Word	1,000	0	10	0	10	Active - Pasive	R/W
51-R09-Remote Analog Torque Referans Input [%]	41010	Word	0,100	0	1000	0	100	%	R/W
52-R10-Remote Analog Speed Referans Input [%]	41011	Word	0,100	0	1000	0	100	%	R/W
53-DP01-Driver Password 1	41071	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
54-DP02-Driver Password 2	41072	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
55-DP03-Driver Password 3	41073	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
56-DP04-Driver Password 4	41074	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
57-DP05-Driver Password 5	41075	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
58-DP06-Driver Password 6	41076	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
59-DP07-Driver Password 7	41077	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
60-DP08-Driver Password 8	41078	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
61-DP09-Driver Password 9	41079	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
62-DP10-Driver Password 10	41080	Word	1,000	0	65535	0	65535	Data Storage Addresses	R/W
63-M01-Modbus Slave Adres	42001	Word	1,000	1	247	1	247	ModbusRTU Addresses	R/W
64-M02-Modbus Baud Rate	42002	DWord	1,000	9600	115200	9600	115200	ModbusRTU Addresses	R/W
65-M03-Modbus Stop Bits	42004	Word	1,000	1	2	1	2	ModbusRTU Addresses	R/W
66-M04-Modbus Parity	42005	Word	1,000	0	2	0	2	ModbusRTU Addresses	R/W
67-M05-Modbus Reset	42006	Word	1,000	0	10	0	10	ModbusRTU Addresses	R/W

# HALL SENSOR RECOGNITION

Figure - 17 HALL SENSOR RECOGNITION



## The first introduction of the hall sensor

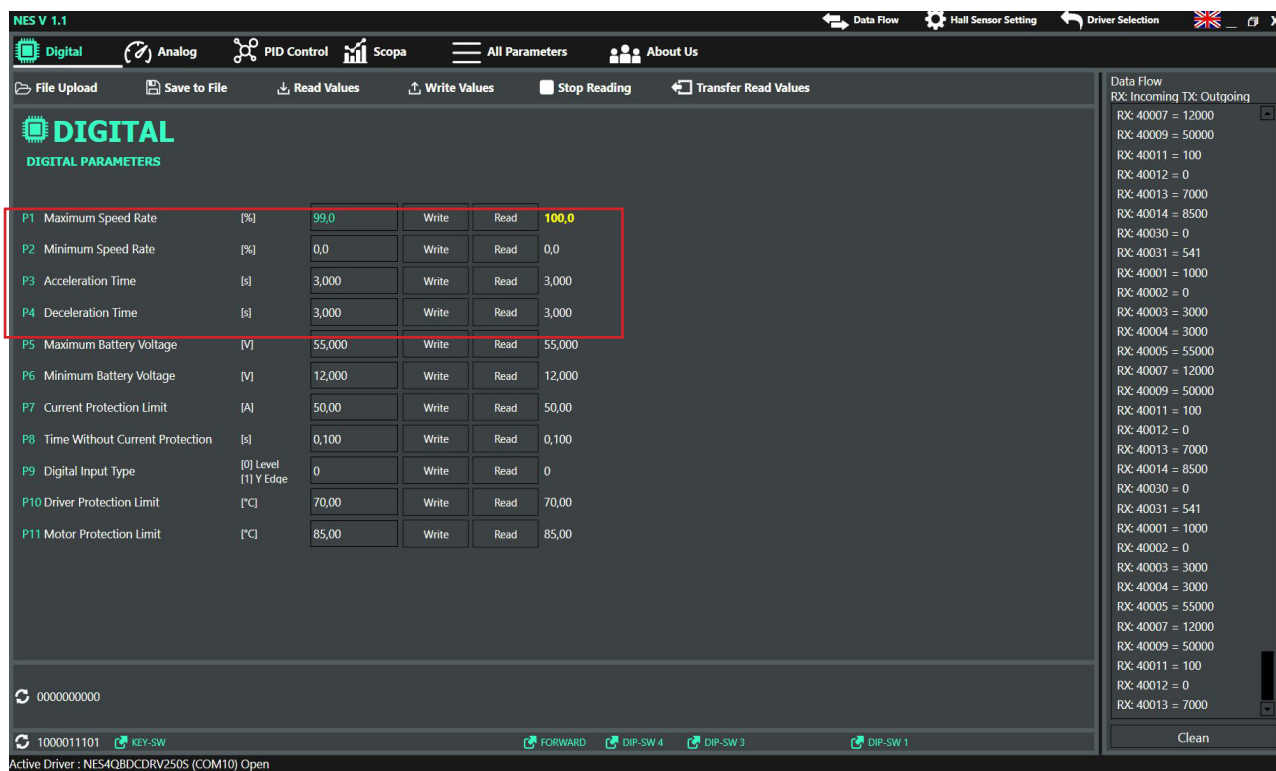
- 1-After the motor U, V, W power cables and hall sensor cables are correctly connected, it is expected to recognize the motor by pressing the recognition button.
- 2-By turning the motor a little, the driver tries to detect the hall sensors.
- 3-He writes the code in the recognition section.
- 4-The detected values are transferred to the flash writing section by pressing the transfer button.
- 5-Clicking the write button will be taken to the flash memory.
- 6-By clicking the flash read button, the hall sensor code in the memory can be read.
- 7-If the same connection will always be established, there is no need to re-introduce it.
- 8-It can start working by writing the code directly into memory.

Recognition should be done again when the connection changes.

If the hall sensor code is known, the working process can be started by writing it directly to flash.

# DIGITAL PARAMETER SHEET & P1 , P2 , P3 , P4 Parameter

Figure - 18 DIGITAL PARAMETERS 1



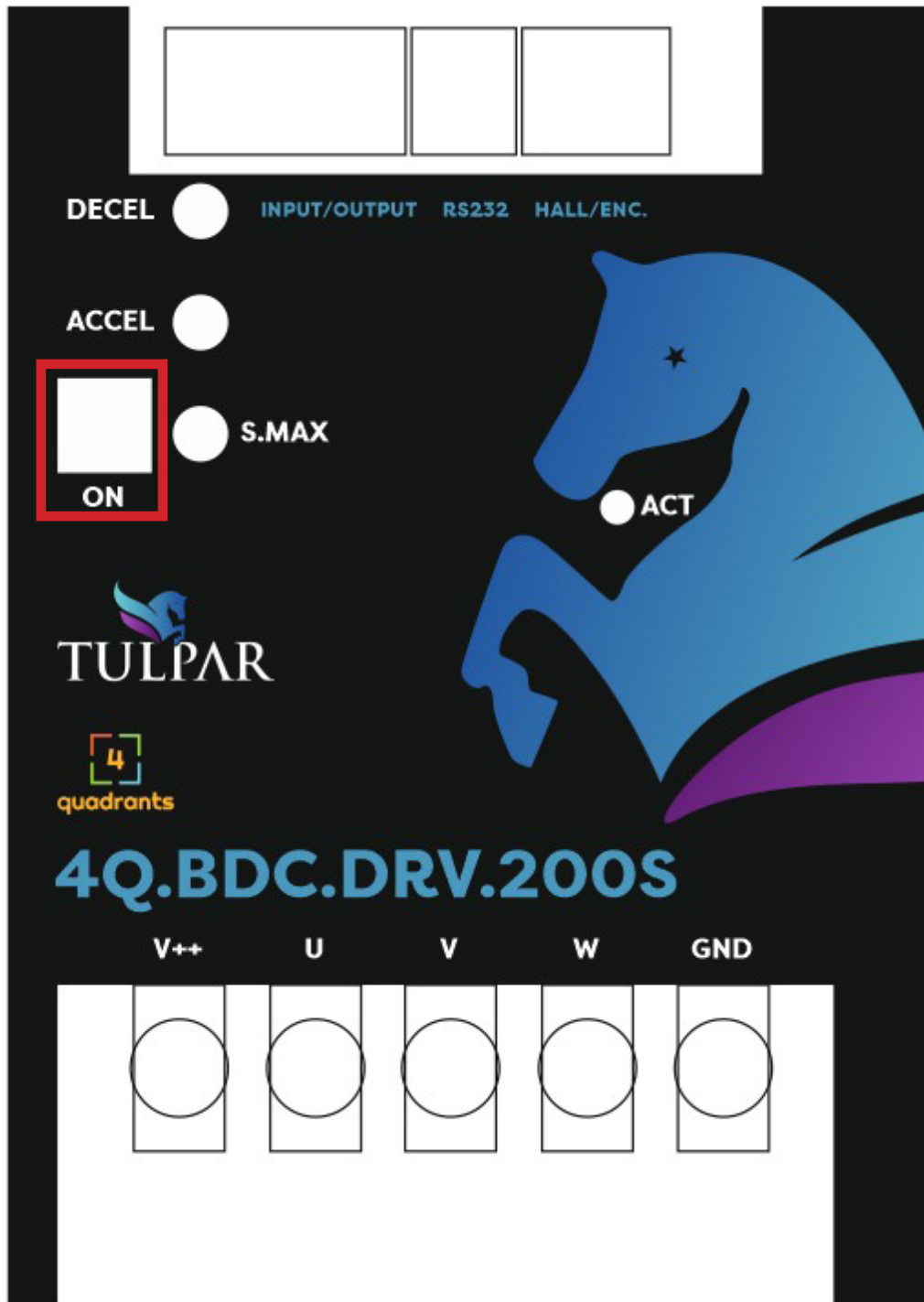
The parameters in the digital page can be read and written individually or with continuous reading buttons.

- P1 With the Maximum Speed Limit ratio, the motor speed can be limited in %.  
drive supply voltage is upper limit.
- P2 Motor speed in% with minimum speed limit ratio  
It can be kept at a certain value above 0 provided it is not greater than 99%.
- P3 The time to climb the motor reference point can be given by the acceleration ramp.  
reference movements can also work with ramps.  
The unit is in seconds.
- P4 A deceleration ramp can be given from the motor reference point to the zero point.  
reference movements can also work with ramps.  
the unit is in seconds.

Parameter Setting	4 Pot or Internal parameters
	If SW2 is on external (4 Pot)
	If SW2 is off internal

# DIGITAL PARAMETER SHEET & P1 , P2 , P3 , P4 Parameter

Figure - 19 P4 DIGITAL PARAMETERS 2



See. Page 3.

# DIGITAL PARAMETER SHEET & P5 .. P11 Parameter

Figure - 20 DIGITAL PARAMETERS 3

Parameter	Unit	Value	Write	Read	Value
P1 Maximum Speed Rate	[%]	99,0	Write	Read	100,0
P2 Minimum Speed Rate	[%]	0,0	Write	Read	0,0
P3 Acceleration Time	[s]	3,000	Write	Read	3,000
P4 Deceleration Time	[s]	3,000	Write	Read	3,000
P5 Maximum Battery Voltage	[V]	55,000	Write	Read	55,000
P6 Minimum Battery Voltage	[V]	12,000	Write	Read	12,000
P7 Current Protection Limit	[A]	50,00	Write	Read	50,00
P8 Time Without Current Protection	[s]	0,100	Write	Read	0,100
P9 Digital Input Type	[0] Level [1] Y Edge	0	Write	Read	0
P10 Driver Protection Limit	[°C]	70,00	Write	Read	70,00
P11 Motor Protection Limit	[°C]	85,00	Write	Read	85,00

P5- Maximum battery voltage upper alarm value can be entered. If the voltage is above this value, it will give the driver an alarm and stop after 3 seconds. It is not affected by instant increases. Its duration is 3 seconds. If the braking resistor is connected, any voltage above the limit is dissipated across the resistor.(See. Page 7).

P6- Minimum battery voltage alarm value can be entered. When the battery falls below this value, the driver stops.

Works smoothly between Maximum battery voltage and Minimum battery voltage.

P7- Motor current protection limit value. It is not affected by instant increases. It does not give more in constant flow. It allows up to P8 time over the limit. will give.

P8- When the motor wants to draw current above the P7 current limit,P8 seconds are allowed.

P9- Digital input type =0 (Momentary)

As long as the inputs are active, the motor is active.

Digital input type =1 (Toggle)

As long as the inputs are active once, the motor is active.

It does not change its position without pressing the stop or change direction button, it continues.

Digital input type =2

Forward = Enable

Reverse = FR

Forward = if active

FR = Passive

Motor Direction CC

FR = Active

Motor Direction CCW

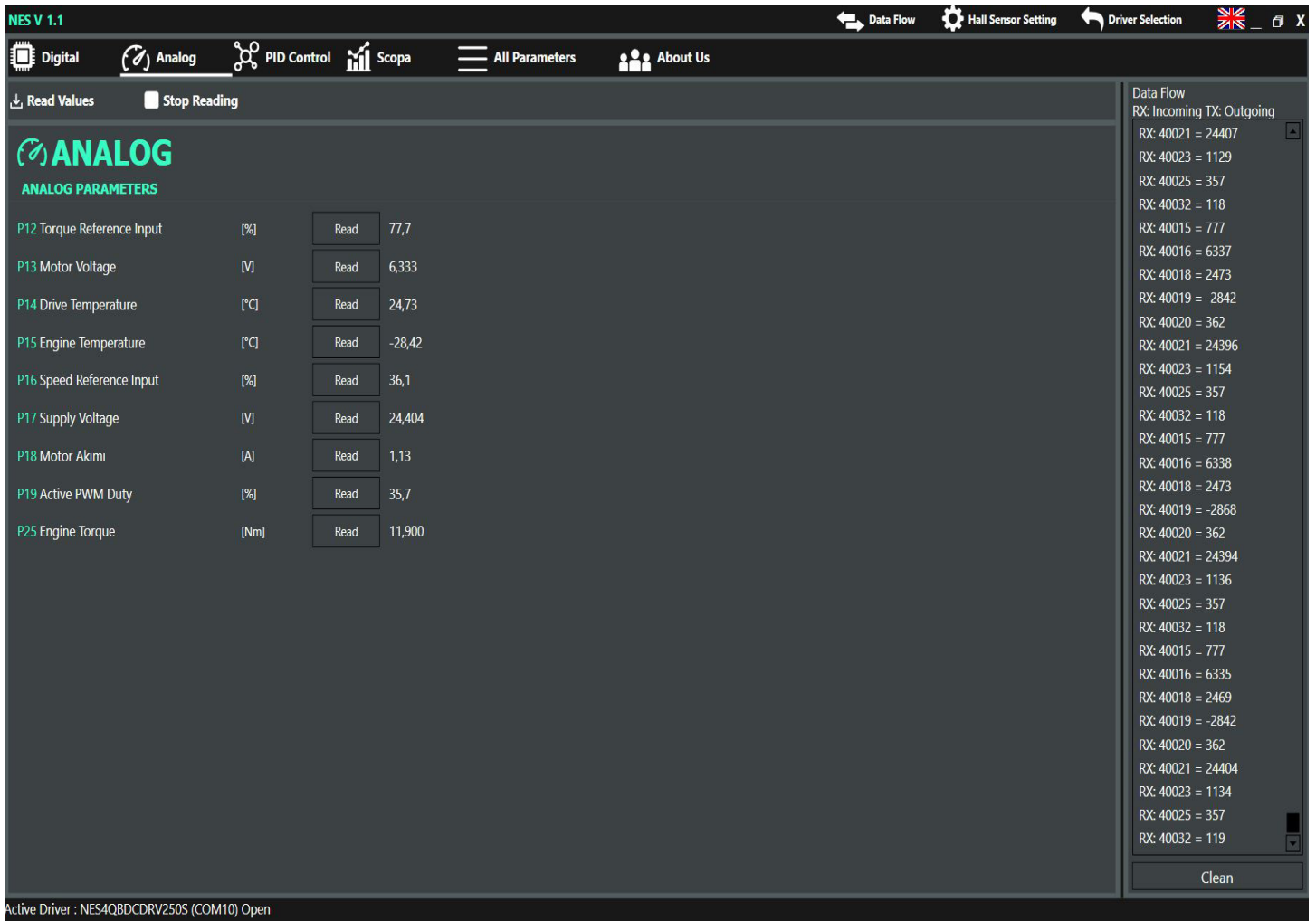
P10- Drive protection temperature. There is a sensor that measures the drive case temperature. It gives an alarm when the temperature value is exceeded. 45 degrees stage 1(Low) , 55 degrees stage 2(Middle). 65 degrees stage 3.(High) It works in stages.

P11- Motor protection limit & Battery protection are used together. If the motor or battery sensor is connected, a heat alarm can be assigned.



# ANALOG PARAMETER SHEET & P12 .. P25 Parameter

Figure - 22 ANALOG PARAMETERS

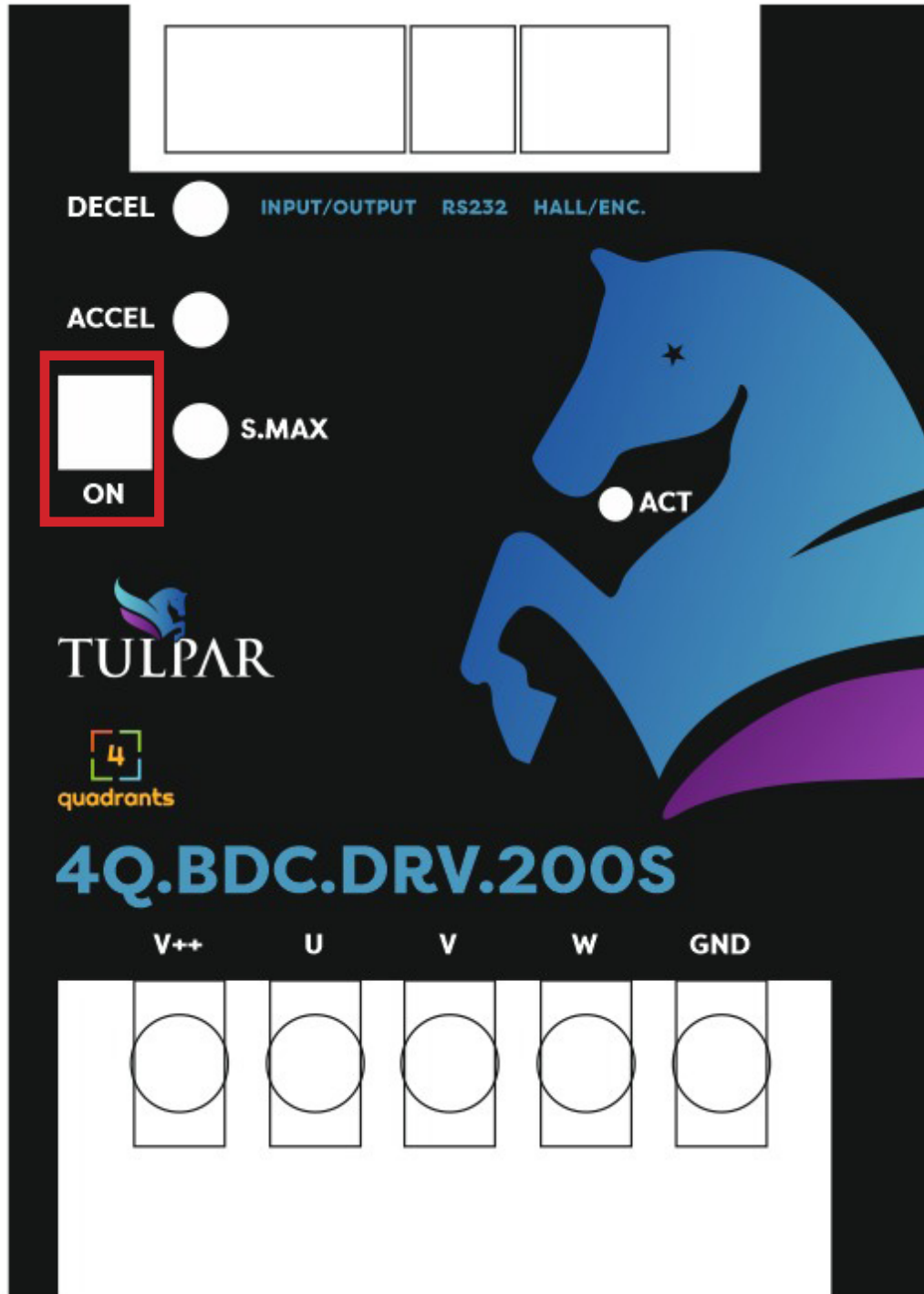


- P12-P16 0-5vdc and 0-10vdc can be selected by SW1. PORT(P1-15, P1-6), (See. Page 17).
- P13 Instantaneous Motor voltage. Motor voltage reference output (0-5V), PORT(P1-16 , P1-5), (See. Page 11).
- P14 Instantaneous driving temperature(Degres).
- P15 Instantaneous motor temperature PORT(P1-8, P1-5), (See. Page 11).
- P17 Instantaneous Battery Voltage
- P18 Instantaneous Motor current.
- P19 Instantaneous active PWM
- P25 Instantaneous engine torque

The parameters in the digital page can be read individually or continuously.

# TORQUE & SPEED REFERENCE INPUT 0-5VDC or 0-10VDC SELECT

Figure - 23 SPEED REFERENCE SELECT



See. Page 3.

# PID PARAMETER SHEET

## P20 , 21 , 22 - P30 .. 34 Parameter

Figure - 24 PID PARAMETERS

**PID CONTROL PARAMETERS**

Parameter	Unit	Value
P20 Active Motor Speed		720
P21 Active Speed Pilot		724
P22 Closed Loop Control		[0] Passive
P30 Proportional Coefficient	[P]	1,000
P31 Integral Coefficient	[I]	0,010
P32 Derivative Coefficient	[D]	0,010
P33 Encoder Pulse / D	[ppr]	0
P34 Motor 100% Speed	[RPM]	0

Active Driver : NES4QBDCDRV250S (COM10) Open

- P20 Shows the instant engine speed value.
- P21 It is the pilot value that the engine should output.
- P22 It works with SW3 and SW4. The drive is a closed loop or open loop operating option.
- P30 Proportional Coefficient , It can be adjusted according to the reaction of the engine.
- P31 Integral Coefficient , It can be adjusted according to the reaction of the engine.
- P32 derivative Coefficient , It can be adjusted according to the reaction of the engine.
- P33 Motor pole number value can be entered in Tulpar series drives. For Bamsı series drives, the encoder pulse value is entered in closed loop operation.
- P34 The engine is factory (Label) rpm.This value must be entered exactly.

The parameters in the digital page can be read individually or continuously.

# ALL PARAMETER SHEET & P1 ... P34 Parameter

Figure - 26 ALL PARAMETERS

**ALL PARAMETERS**

Parameter ID	Parameter Name	Unit	Value	Action	Value
P1	Maximum Speed Rate	[%]	99,0	Write	100,0
P2	Minimum Speed Rate	[%]	0,0	Write	0,0
P3	Acceleration Time	[s]	3,000	Write	3,000
P4	Deceleration Time	[s]	3,000	Write	3,000
P5	Maximum Battery Voltage	[V]	55,000	Write	55,000
P6	Minimum Battery Voltage	[V]	12,000	Write	12,000
P7	Current Protection Limit	[A]	50,00	Write	50,00
P8	Time Without Current Protection	[s]	0,100	Write	0,100
P9	Digital Input Type	[0] Level [1] Y Edge	0	Write	0
P10	Driver Protection Limit	[°C]	70,00	Write	70,00
P11	Motor Protection Limit	[°C]	85,00	Write	85,00
P12	Torque Reference Input	[%]	Read		77,7
P13	Motor Voltage	[V]	Read		5,221
P14	Drive Temperature	[°C]	Read		24,88
P15	Engine Temperature	[°C]	Read		-28,42

0000000000

1000011101 KEY-SW

FORWARD DIP-SW 4 DIP-SW 3 DIP-SW 1

Active Driver : NES4QBDCDRV250S (COM10) Open

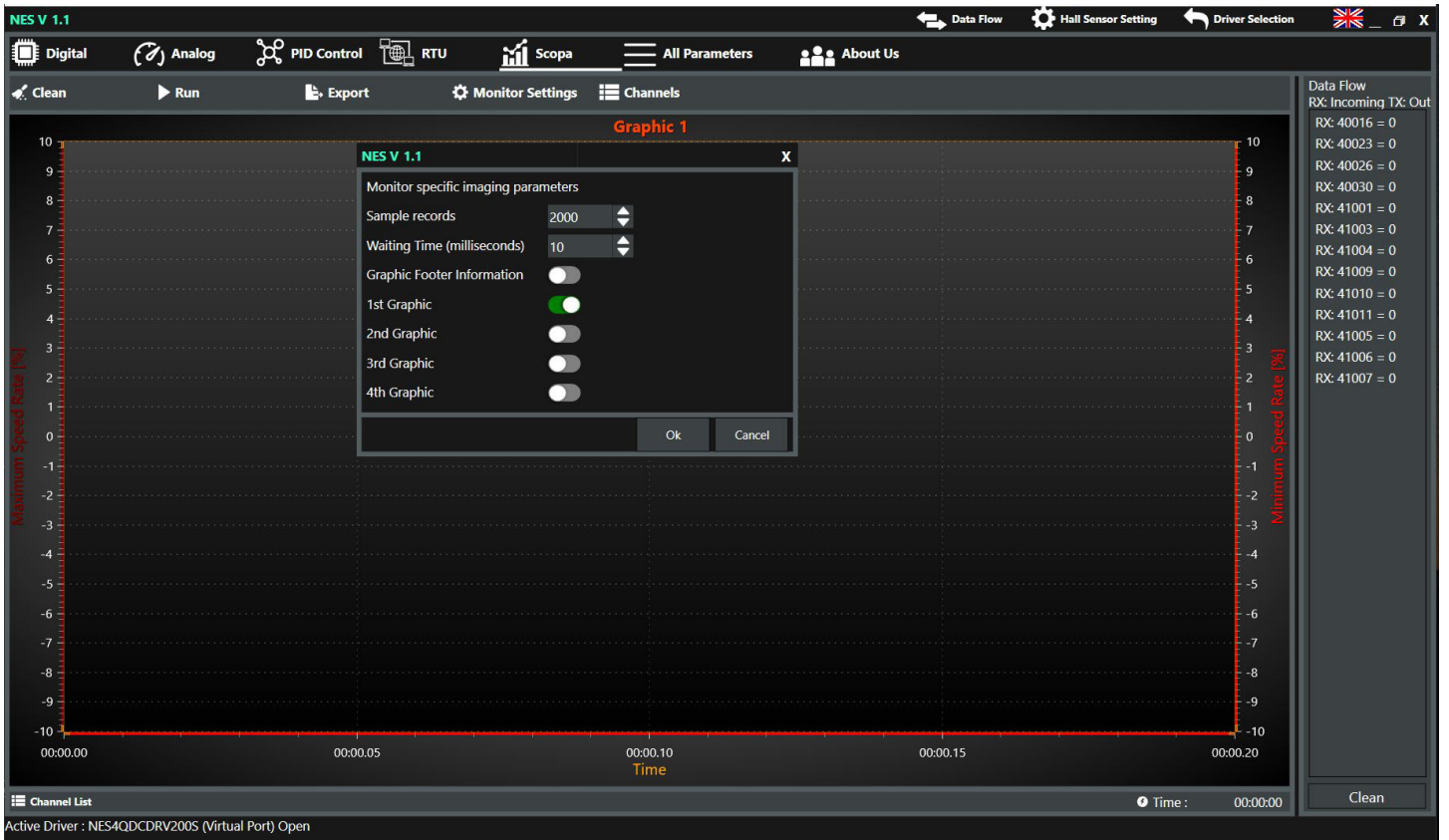
Data Flow  
RX: Incoming TX: Outgoing  
RX: 40013 = 7000  
RX: 40014 = 8500  
RX: 40015 = 777  
RX: 40016 = 5221  
RX: 40018 = 2488  
RX: 40019 = -2842  
RX: 40020 = 286  
RX: 40021 = 24404  
RX: 40023 = 977  
RX: 40025 = 294  
RX: 40026 = 576  
RX: 40028 = 572  
RX: 40029 = 0  
RX: 40030 = 0  
RX: 40031 = 541  
RX: 40032 = 100  
RX: 40034 = 2000  
RX: 40036 = 30  
RX: 40038 = 1000  
RX: 40040 = 24  
RX: 40042 = 2000  
RX: 40001 = 1000  
RX: 40002 = 0  
RX: 40003 = 3000  
RX: 40004 = 3000  
RX: 40005 = 55000  
RX: 40007 = 12000  
RX: 40009 = 50000  
RX: 40011 = 100  
RX: 40012 = 0  
RX: 40013 = 7000

Clean

In this parameter page, all parameters within the drive can be viewed in a single page. parameters can be saved and saved and recalled.

The parameters in the digital page can be read individually or continuously or the written ones can be changed.

Figure - 27 SCOPE CHART TRACKING PAGE 1



4 graphic pages can be displayed on the scope screen.

Sampling times can be selected.

It can be selected which data will be watched live on the graphic screens.

Figure - 28 SCOPE CHART TRACKING PAGE 2



Figure - 29 REMOTE MANAGEMENT UNIT PAGE



Device IO can be canceled and taken completely to the Remote control unit.

Speed reference and torque control can be done with the mouse thanks to the dial on the screen.

Motor motion can be given with forward stop buttons.

Analog or digital inputs can be operated in RTU mode.

### Working order

1- R08 = ON if speed reference or torque will be RTU Mode

2- R03 = ON if digital inputs will be in IO RTU mode

3-Time must be written for R01. If there is no movement, the time counts down and becomes 0.

Time is renewed with the flow of information. When there is no information flow, the time will be 0 and an error occurs. The time error is reset with P23.

Otherwise, RTU will not switch to mode.

4-RTU mode is activated with R02.

RTU Mode works actively through RS232 and RS485.

# WHO ARE WE

Nes Yazilim Sanayi ve Ticaret Ltd. Şti, we started our work on electronic card design and embedded software. Our Company Headquarters carries out its activities within the Erciyes Technopark. At the same time, we have an R&D center under the same roof with our company partner Name Elektronik, which operates in electronic card repair and component sales, in order to provide better service to companies operating in the Kayseri OSB region. We have liaison offices in Aksaray and Istanbul. We carry out our activities professionally with our expert staff with 20 years of R&D and market experience.

## OUR WAY TO WORK DIFFERENT

First, we listen to you, and we work so that you can afford the right solution. We are aware that your time is precious and we start our business at the time we promise, and deliver your products at the time we promise. He stands behind what we do, guides etc. We deliver the documents to you, answer all your questions, and continue our after-sales technical support 24/7. We know that success; It is only possible with the appropriate content, quality and delivery of the work.

Erciyes Üniversitesi Teknoloji Geliştirme Bölgesi  
Tekno-3 No: 67/31 Pk: 38039  
Melikgazi/KAYSERİ/TÜRKİYE  
Telefon: +90 352 311 55 57  
www.nesdrive.com - info@nesdrive.com

## Design and software Our areas of expertise

- DC Motor drivers
- STEP Motor drivers
- LINEAR Actuators
- (Piston Motor) drivers
- BLDC (Brushless) Motor Drivers
- SRM (Switched Reluctance Motor) drivers
- AC-DC Converters
- DC-DC Converters
- LINEAR Actuator
- M-BUS Converters
- PELET Stove Control Systems
- Intersection Control Devices
- Mechanical Calorimeters
- Ultrasonic Calorimeters
- Wireless Data Collection Systems
- Wireless Vehicle Detection Systems
- Electrostatic Powder Coating Control Systems
- Tram and Trambus On Vehicle  
Communication and Control Systems
- LED Panel Control Systems
- Analog, Digital, Hybrid, RF,
- Power circuit design and software
- Magnetic, Ultrasonic, Temperature,
- Humidity, Pressure etc. sensor interfaces
- Every brand RISC, DSP, ARM etc.