

Npmbsar Glqrpsargml K_ls_j



1 1
2 3
2.1 3
2.2 4
2.3 5
2.4 6
2.5 7
3 8
3.1 8
3.2 8
3.3 13
4 14
4.1 14
4.2 14
4.3 15
4.4 16
5 20
5.1 20
5.2 20
5.3 24
6 28
7 29
7.1 29
7.2 29
7.3 29
8 30

1







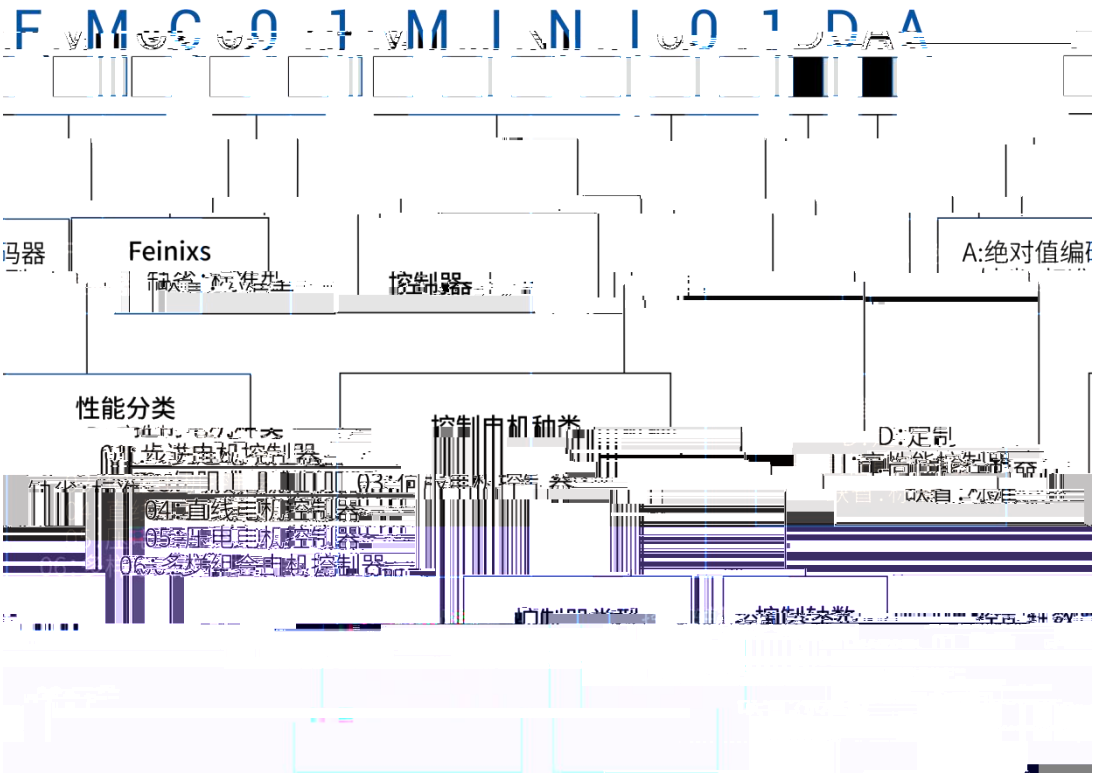
36VDC

DKA.2

2

FMC04-H /

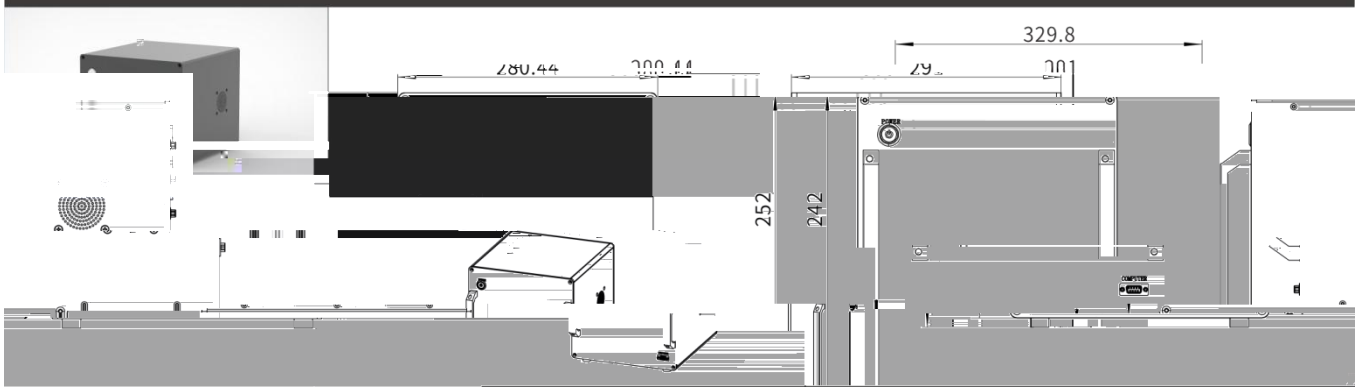
2.2



: FMC04-02H / +2 +

2.3

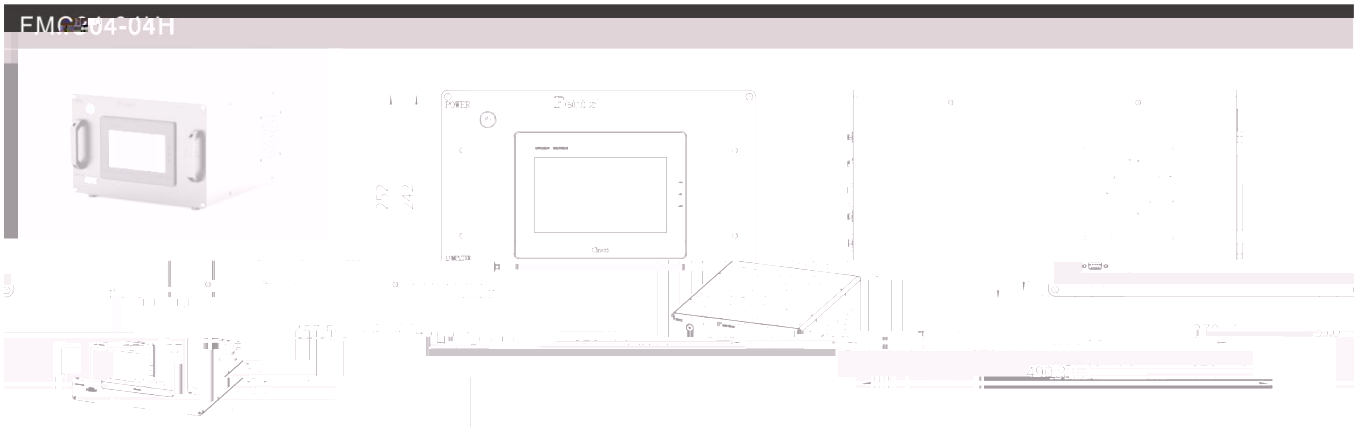
FMC04-01H



FMC04-02H



FMC04-04H



2.4



Feinixs
FMC04-03H
SN KB20201201001

“ ”

2.5

Model	FMC04-01H

3

3.1

1

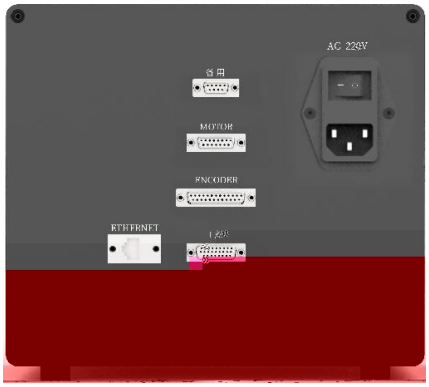
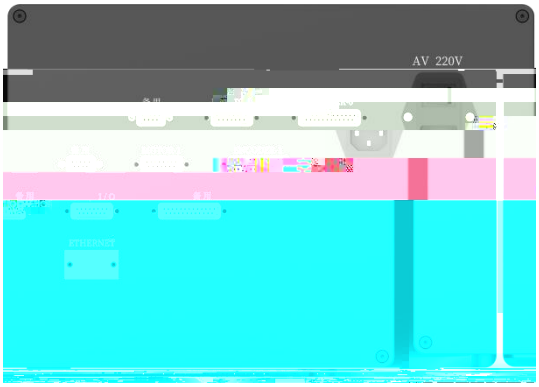
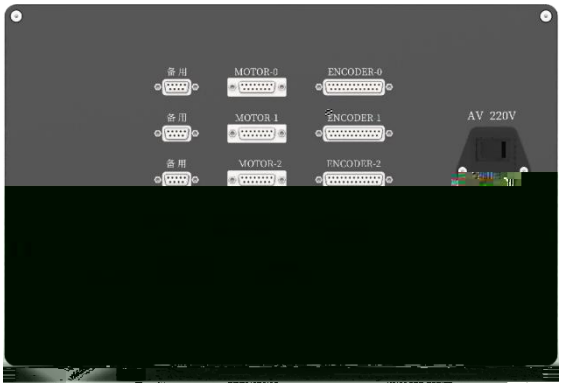
2

3

4

3.2

3.2.1

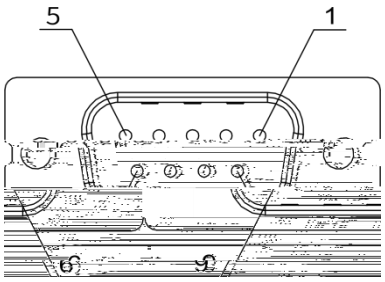
FMC04-01H	FMC04-02H
	
FMC04-04H	
	

MOTOR-0 0 ENCODER-0 0
MOTOR-1 1 ENCODER-1 1
MOTOR-2 2 ENCODER-2 2
MOTOR-3 3 ENCODER-3 3
MOTOR-4 4 ENCODER-4 4
MOTOR-5 5 ENCODER-5 5
ETHERNET I/O IO
AC 220V

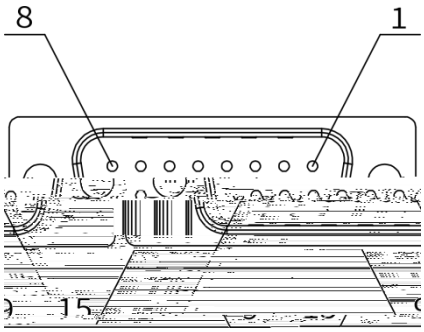
FMC04-01H	FMC04-02H
	
FMC04-04H	
	

COMPUTER RS232
POWER

3.2.2

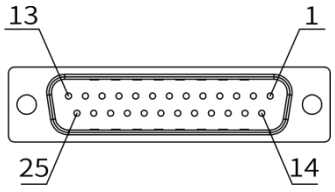
Debug wiring diagram		
 DB9		
	1	/
	2	/
	3	/
	4	/
	5	/
	6	5V+
	7	DATA-
	8	DATA+
	9	GND

3.2.3

 DB15			
	1	U	U
	2	/	/
	3	V	V
	4	/	/
	5	W	W
	6	/	/
	7	PE	
	8-15	/	/

3.2.4

Encoder wiring diagram



DB25

1	5V+	5V
2	0V	0V
3	SD+/PS+	
4	SD-/PS-	
5	A+ CLK+/MA+	A+ +
6	A- CLK-/MA-	A- -
7	B+ DATA+/SLO+	B+ +
8	B- DATA-/SLO-	B- -
9	Z+	Z+
10	Z-	Z-
11	HA	HA
12	HB	HB
13	HC	HC
14	5V+	5V
15	0V	0V
16	SIN+	SIN+
17	SIN-	SIN-
18	COS+	COS+
19	COS-	COS-
20	REF+	Ref+
21	REF-	Ref-
22	24V+	24V+
23	Limit-	
24	limit+	
25	24V-	24V-

3.3

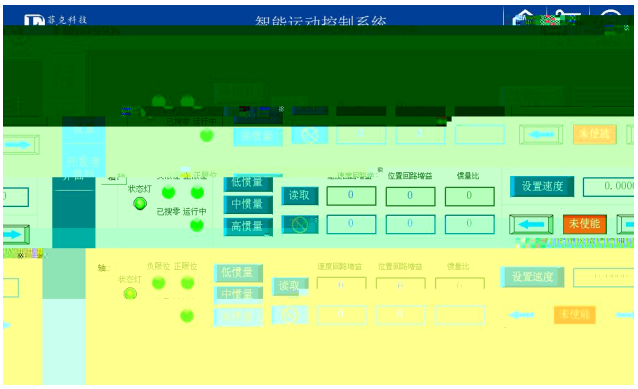
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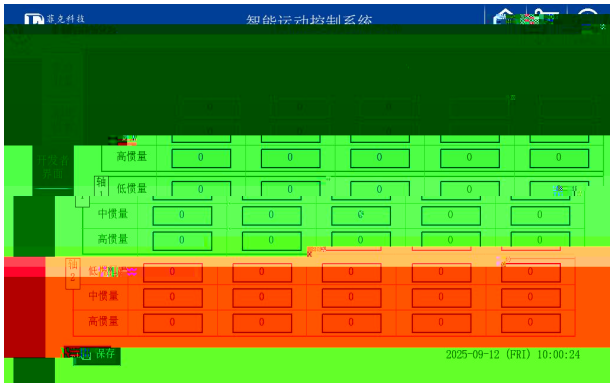
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“ ” “ ”

3

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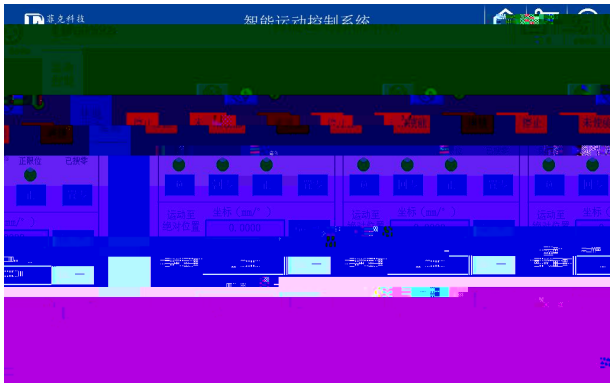

智能运动控制系统
状态灯
已探零 运行中
低惯量
中惯量
高惯量
读取
设置速度
未使能

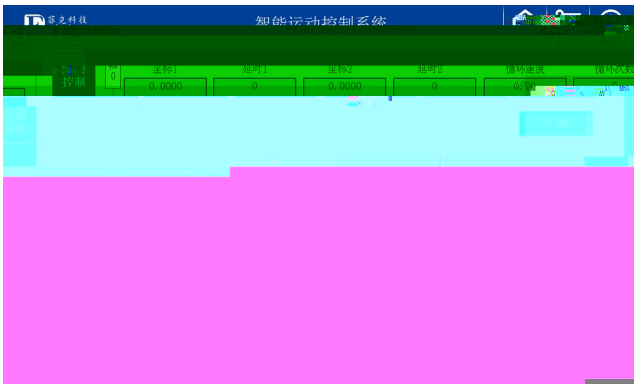

智能运动控制系统
高惯量
低惯量
中惯量
高惯量
中惯量
高惯量
保存
2025-09-12 (FRI) 10:00:24

4.3

“ ”

4.4







未使能 已使能	
清错	


停止


搜零


回零


实时坐标:
0.0000


循环次数
0
延时1
0
延时2
0
已完成次数
0
循环速度
0.00
开 始
停 止
加速度
(mm/s²&° /s²)
0
减速度
(mm/s²&° /s²)
0
保存
低惯量
中惯量

Ω 6

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5

5.1

win10 win11

.NET 6.0

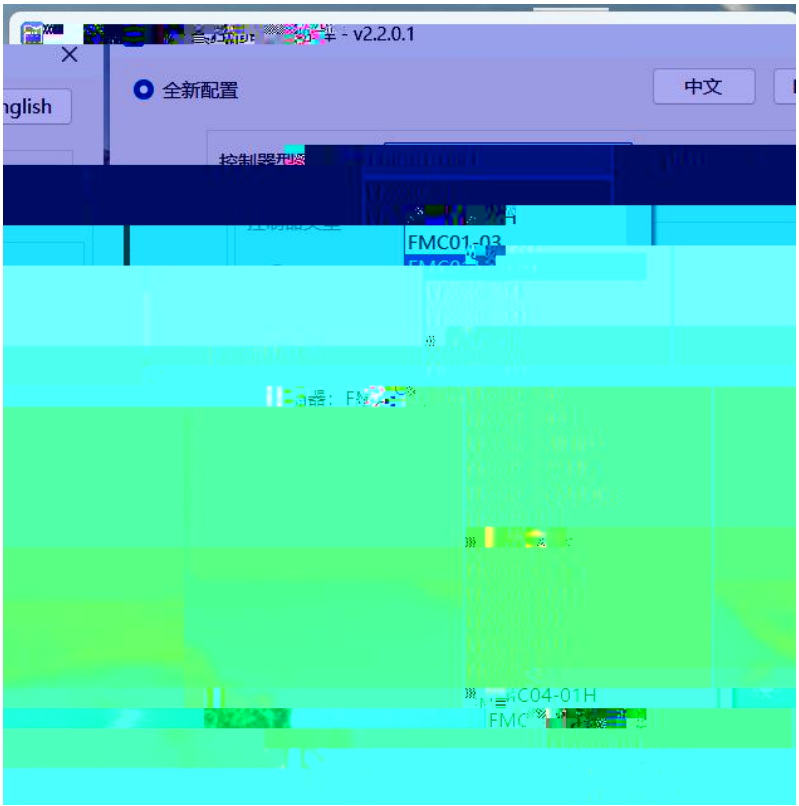
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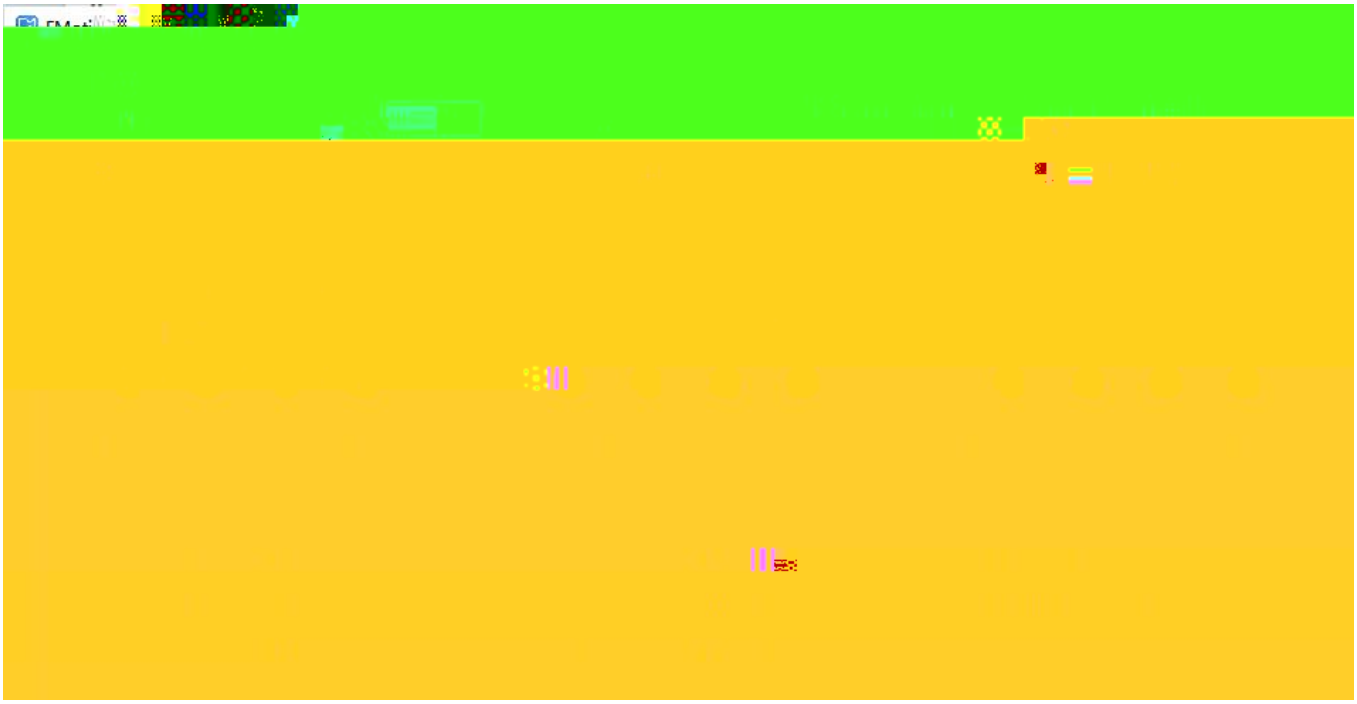
FMotion_win-x64

FMotion.exe



5.2





“ ”

“ FMC01-03H ” “ ”

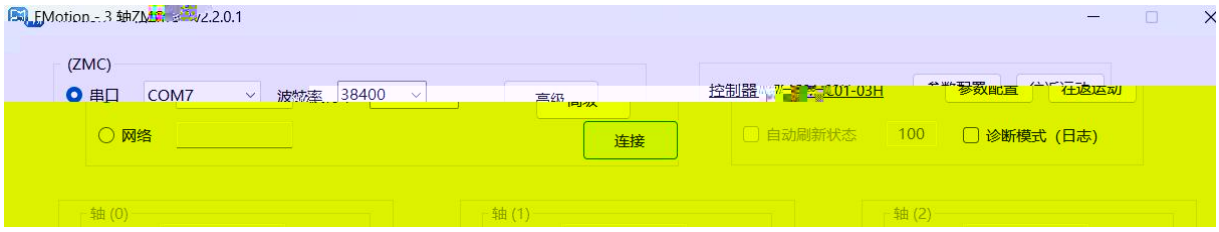
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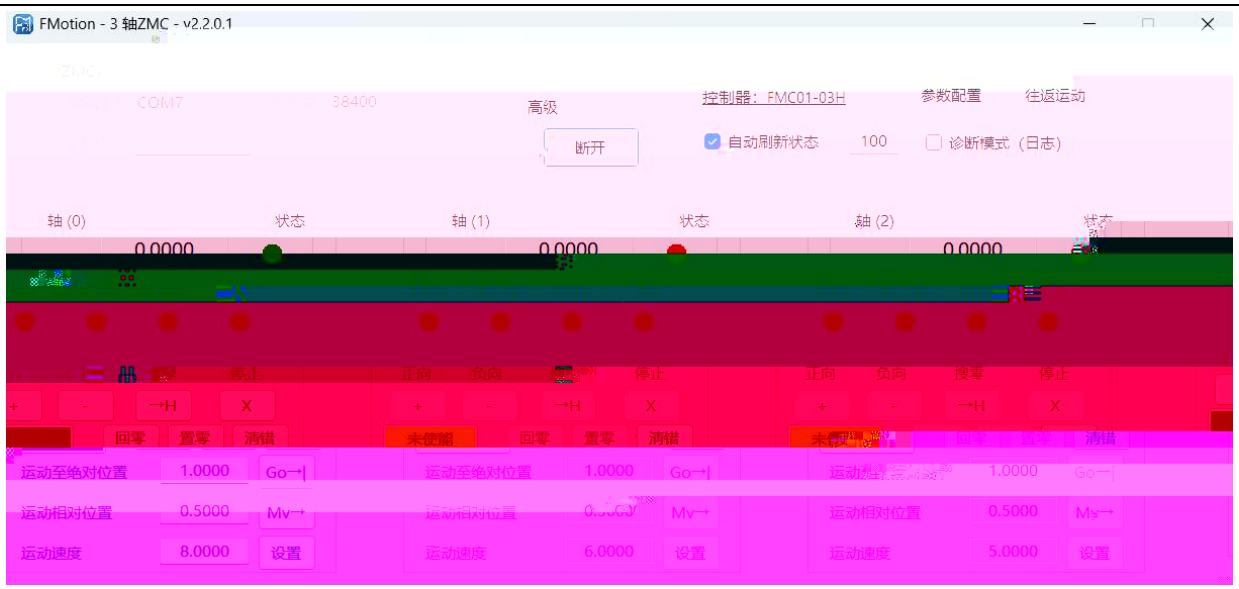
”

5.2.1

“ ” FMC04-H

38400





FMC04-H IP

192.168.0.11

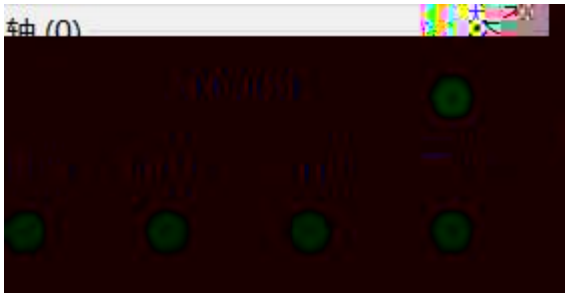
192.168.0.XXX





DKA.2+./-.0-.2F

5.2.3



/

- - -

5.3


正向
负向
搜零
停止
+
-
→H
X
已使能
回零
置零
清错
运动至绝对位置
1.0000
Go→
运动相对位置
Mv→
运动速度
8.0000
设置

5.3.1

(


搜零
→0

0

“ ”

0

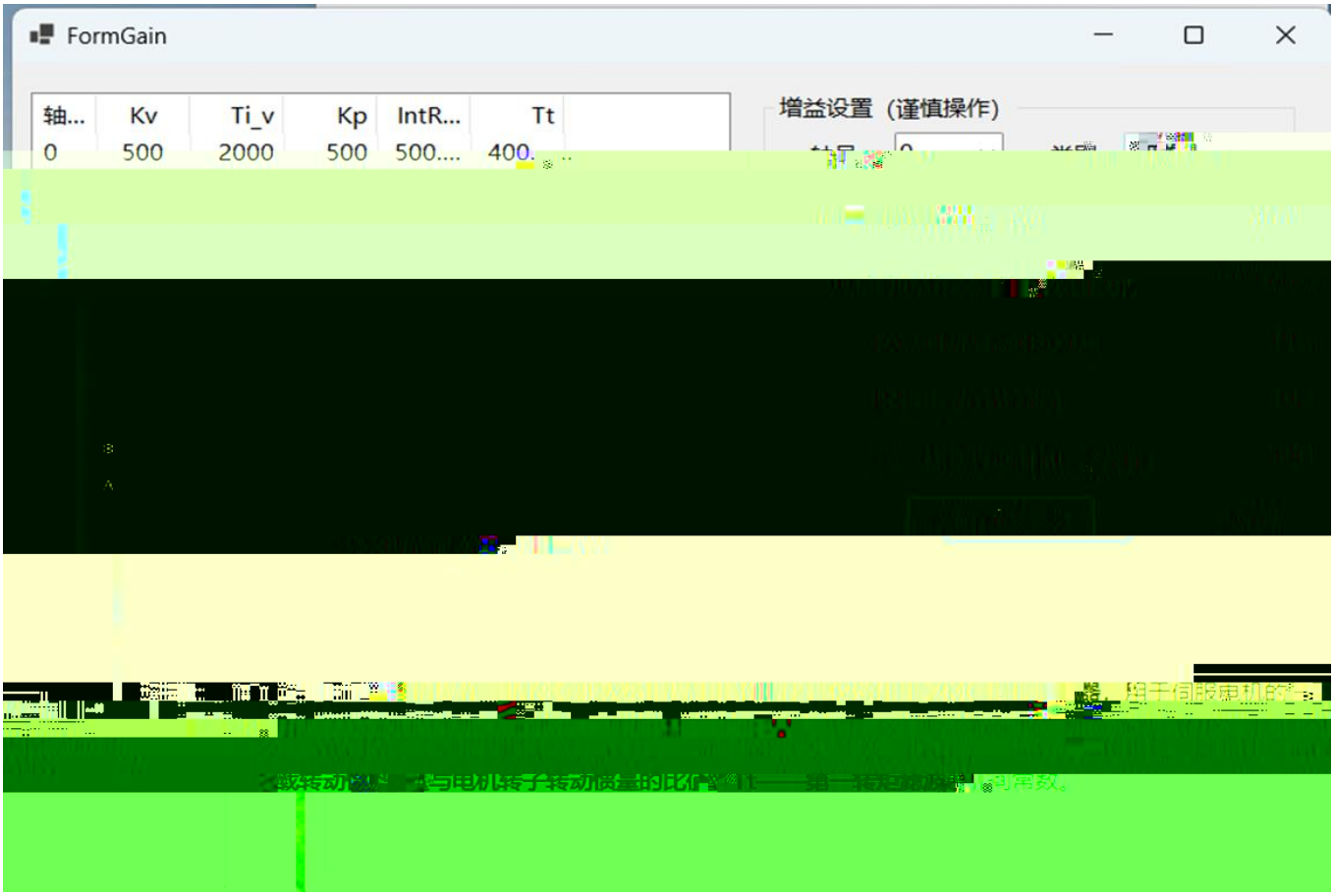
0

ms

5.3.6

FMC04-H 31

5.3.7



Kv Ti_v Kp_p

Int.ratio Tt

6

01 0x01

38400 8 1

IP 192.168.0.11

1

7

7.1

7.1.1 3 1

7.1.2

7.2

7.2.1

7.2.2

7.2.3

7.2.4

7.2.5

7.2.6

7.3

		0

8

8.1

A

B

C

D

E

F

8.2

8.3

8.4

8.5

8.6

8.7

: 111
:0086-28-85864663 :173 0280 5818
:610000 :info@feinixs.com
:http://www.feinixs.com