



Release Notes

ACE™ is free software for use in commissioning and setup of ADVANCED Motion Controls' FlexPro® servo drives.

ACE™ provides the ability to set drive limits, tune the current, velocity, and position control loops, and assign automated functions to drive events. The fully functional multi-channel oscilloscope eases system setup and assessment.

Documentation and support are available on the ADVANCED Motion Controls' web site (www.a-m-c.com) or contact Technical Support by phone at 805-389-1935.

Compatibility

- Gain definitions have been changed in the **ACE** 1.2022.4 GUI and 1-2022-4-0 firmware.
 - It is recommended to confirm that velocity and position loop gains still provide a stable response when first connecting using **ACE** 1.2022.4 and after upgrading to 1-2022-4-0 CANopen or Serial firmware from an older firmware version.
- The 1-2022-4-0 CANopen and Serial firmware utilizes an updated command set compared to the 1-2022-2-0 firmware. For customers using network commands, it is recommended to review the changes in the published communication manual.

New Features in ACE™ 1.2024.2

- Support for Hard Stop Homing is added for CANopen and Serial drives
- Autocomm can be initiated with the bridge disabled for customers who have a brake configured on the Motor Parameters page
- Position Feedback added as an available location for a biquad filter

Bug Fixes in ACE™ 1.2024.2 Patch 1.1

- Fixed a bug where Feedback Sensor Error faults would not clear in dual feedback configurations with an absolute encoder where the Position Feedback Source is different than the Velocity Feedback Source or Commutation Feedback Source for CANopen/Serial drives
- Fixed a bug where ACE would disconnect or a Drive Internal Error fault would occur when enabling the waveform generator in dual feedback configurations with an absolute encoder where the Position Feedback Source is different than the Velocity Feedback Source or Commutation Feedback Source for CANopen/Serial drives
- Fixed a bug where an error would occur when applying Autocomm results in halls only configurations for CANopen/Serial drives
- Fixed a bug where the initialization of the Position Measured to 0 on power up can cause unexpected movement with CANopen drives using an absolute encoder in Profile Position mode

- Fixed a bug where reserved bits could not be applied on the Loop Feedback page for CANopen/Serial drives

Known Issues in ACE™ 1.2024.2

Software

- Enabling Jerk Limiting in Velocity mode and setting a value of 0 prevents motion
- Second trigger does not function properly on the scope for CANopen and Serial drives
- Changing the IP Address for Ethernet/IP drives can cause ACE to crash
- Analog Input scaling does not function properly if both a deadband and offset are configured for EtherCAT drives
- Adding more than 5 active signals to the scope for CANopen and Serial drives causes the sampling resolution to drop

Firmware

- 1018.04h in EtherCAT does not display the correct serial number
- It is recommended to only use EoE for monitoring purposes. Storing to NVM in ACE while connected via EoE will cause a parameter restore error and project file reset if the drive is power cycled after storing parameters
- Tachometer feedback is not functioning in EtherCAT firmware
- Feedback Sensor Error faults occur when applying Endat 2.2 feedback parameters on CANopen and Serial drives. These are nuisance faults that should be clearable if the written parameters are correct
- Nuisance Motor Overspeed faults occur on power up with Endat 2.2 encoders on CANopen and Serial drives if the drive is not set to phase detect immediately in Power-up settings.