SIMODRIVE 611 universal
SIMODRIVE 611 universal E

Control Components for Closed-Loop Speed Control and Positioning

Function Manual

Valid for

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05/2010 Edition
SIMODRIVE® documentation

Printing history
Brief details of this edition and previous editions are listed below.

The status of each edition is shown by the code in the “Remarks” column.

Status code in the “Remarks” column:

A.... New documentation
B.... Unrevised reprint with new Order No.
C.... Revised edition with new status

If factual changes have been made on the page since the last edition, this is indicated by a new edition coding in the header on that page.

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Foreword

Instructions when reading

The SIMODRIVE 611 documentation is structured in 2 levels:

- General Documentation
- Manufacturer/Service Documentation

Information on the following topics is available at http://www.siemens.com/motioncontrol/docu:

- Ordering documentation
  Here you can find an up-to-date overview of publications.
- Downloading documentation
  Links to more information for downloading files from Service & Support.
- Researching documentation online
  Information on DOConCD and direct access to the publications in DOConWEB.
- Individually compiling documentation on the basis of Siemens contents with the My Documentation Manager (MDM), refer to http://www.siemens.com/mdm
  My Documentation Manager provides you with a range of features for generating your own machine documentation.
- Training and FAQs
  Information on our range of training courses and FAQs (frequently asked questions) is available via the page navigation.

Target group

This document addresses engineers and technologists (employed with the machinery construction OEM), commissioning engineers (commissioning the system/machine), programmers.

Benefits

This publication describes the functions so that the target group understands these functions and can appropriately select them. It provides the target group with the information required to implement the appropriate functions.

Should you wish for additional information or should exceptional problems arise that are not addressed in sufficient detail in this manual, you can request the required information from your local Siemens office.

Standard version

The scope of the functionality described in this document can differ from the scope of the functionality of the drive system that is actually supplied. It may be possible for other functions not described in this documentation to be executed in the drive system. However, no claim can be made regarding the availability of these functions when the equipment is first supplied or in the event of servicing. Additions or revisions made by the machine manufacturer are documented by the machine manufacturer.

This document does not purport to cover all details or variations in equipment, nor to provide for every possible contingency to be met in connection with installation, operation or maintenance.
The contents of this document are not part of an earlier or existing contract or agreement nor do they change this. The sales contract contains the entire obligation of Siemens. The warranty conditions specified in the contract between the parties is the sole warranty of Siemens. Any statements contained herein neither create new warranties nor modify the existing warranty.

Technical Support

If you have any technical questions, please contact our hotline:

<table>
<thead>
<tr>
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<tbody>
<tr>
<td>Phone</td>
<td>+49 180 5050 222</td>
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<td>Fax</td>
<td>+49 180 5050 223</td>
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<tr>
<td>Internet</td>
<td><a href="http://www.siemens.com/automation/support-request">http://www.siemens.com/automation/support-request</a></td>
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<td>Fax</td>
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<tr>
<td>E-mail</td>
<td><a href="mailto:techsupport.sea@siemens.com">mailto:techsupport.sea@siemens.com</a></td>
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<tr>
<td>E-mail</td>
<td><a href="mailto:support.asia.automation@siemens.com">mailto:support.asia.automation@siemens.com</a></td>
</tr>
</tbody>
</table>

Note

National telephone numbers for technical support are provided under the following Internet address:


Calls are subject to charge, e.g. 0.14 €/min. on the German landline network. Tariffs of other phone providers may differ.

Questions regarding documentation

If you have any queries (suggestions, corrections) in relation to this documentation, please fax or e-mail us:

| Fax          | +49 9131 98 2176 |
| E-mail       | [mailto:docu.motioncontrol@siemens.com](mailto:docu.motioncontrol@siemens.com) |

Internet address

SIMODRIVE

Certificates

You will find the certificates for the products described in this documentation in the Internet: [http://www.support.automation.siemens.com](http://www.support.automation.siemens.com)

under the Product/Order No. 15257461

or at the relevant branch office of the IDT MC group of Siemens AG.
Information for using this Manual

The following should be observed when using this manual:

**Notice**

From Edition 10.99, this documentation includes information for "SIMODRIVE 611 universal" and "SIMODRIVE 611 universal E".
From Edition 02.02, this documentation includes information for "SIMODRIVE 611 universal HR" and "SIMODRIVE 611 universal E HR".
From Edition 09.05, this documentation includes information for "SIMODRIVE 611 universal HRS" and "SIMODRIVE 611 universal E HRS".

- Information for users of "SIMODRIVE 611 universal" and "SIMODRIVE 611 universal HR/HRS":
  --> For you, all of the Chapters are applicable with the exception of Chapter 1.4.
- Information for users of "SIMODRIVE 611 universal E" and "SIMODRIVE 611 universal E HRS":
  --> It is important that you read Chapter 1.4.5 first.

The Chapter and pages are coded for the reader as follows in the header line below the edition:

<table>
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<td>! not 611u!</td>
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<tr>
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<td>! 611ue diff!</td>
<td>Information differs between 611u and 611ue.</td>
</tr>
<tr>
<td></td>
<td>In addition, the list of differences in Chapter 1.4.5 must be carefully observed.</td>
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Board Abbreviation (only for this purpose)

<table>
<thead>
<tr>
<th>Board</th>
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</tr>
<tr>
<td>SIMODRIVE 611 universal E</td>
<td>611ue</td>
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</tbody>
</table>
The following should also be observed when using this manual:

1. Help: The following help is available for the reader:
   - Complete table of contents
   - Header line (as orientation):
     the main chapter is in the upper header line
     the sub-chapter is in the lower header line
   - Chapter list of contents is provided at the beginning of each Chapter
   - Appendix with
     - Abbreviations and List of References
     - Index

   If you require information regarding a specific term, then look for
   this in the Appendix under the Chapter "Index".
   The Chapter number as well as the page number is specified
   where information on this term can be found.

2. Parameter displays

   In this description, for the parameters, the following displays and
   significances are available:
   - P0660 Parameter 0660 without sub-parameter
   - P1451:8 P1451 with sub-parameters (P1451:0 to P1451:7)
     :8 Sub-parameters that are dependent on the parameter set
   - P0080:64 P0080 with sub-parameters (P0080:0 to P0080:63)
     :64 sub-parameters that are dependent on the traversing block

   The following applies: Colon (:) the parameter has the sub-parameter
   Number: these sub-parameters are available (from :0)

   - P1650.15 Parameter 1650 bit 15

3. Identifying "new" or "revised" information

   The documentation, Edition 01.99 is the first edition.
   How is the "new" or "revised" information identified for the other editions?
   - "from SW x.y" is provided with the information.

   The edition is in the header line on this page > 01.99.

   Exceptions:
   List of faults and warnings, parameter list

   The lists are completely updated at each edition, and a new edition
   can be entered in the header lines on all of the pages.
   For the individual faults and warnings, there is no software release-
   dependent coding regarding the parameters.
There is a fixed relationship between the edition of the documentation and the software release of the control board.

**The first edition 01.99 describes the functionality of SW 2.1.**

**Edition 04.99 describes the functionality of SW 2.x.**

What are the essential new functions that have been added for SW 2.x in comparison to SW 2.1?

- Rotary axis with modulo correction
- Motor changeover for induction motors
- Optional TERMINAL modules can now be used independent of the operating mode.
- Communications via the RS485 interface (HW dependent)
- SimoCom U Comparing parameter sets
- Example: Drive operated via PROFIBUS
  Reading/writing parameters via PROFIBUS

**Edition 10.99 describes the functionality of SW 2.x and SW 3.x.**

What are the essential new functions that have been added for SW 3.x in comparison to SW 2.x?

- Jerk limitation
- External block change
- Input signal "Suppress fault 608" (speed controller output limited)
- Optional PROFIBUS-DP module:
  PROFIBUS-DP2, Order No. (MLFB): 6SN1114–0NB00–0AA1
  PROFIBUS-DP3, Order No. (MLFB): 6SN1114–0NB01–0AA0
- PROFIBUS
  Process data configuring
  Motion Control with PROFIBUS-DP (clock synchronous operation)
  New control signals: NSOLL_B, DIG_OUT, Gx_STW
  New status signals: NIST_B, DIG_IN, XistP, IgGl, Gx_ZSW, Gx_XIST1, Gx_XIST2
  Override evaluation can be set (P0883)
  S7 blocks to read/write parameters
- Fixed speed setpoints for closed-loop speed controlled operation
- $i^2$t power module limitation
- SimoCom U Online operation via PROFIBUS possible
  Online operation via MPI interface possible
  PROFIBUS diagnostics screen
  Help topics for each parameter of the expert list
- Faults and warnings:
  The stop response (STOP I to STOP VII) is specified for each one
List of motors
1FE1 motors (PE spindle) new in the list
1FT6xxx–xWxxx–xxxx motors new in the list (water-cooled synchronous motors)

"SIMODRIVE 611 universal E" control board

First common software release for the "SIMODRIVE 611 universal" and "SIMODRIVE 611 universal E"

Edition 05.00 describes the functionality of SW 2.x and SW 3.x.

What are the essential new functions that have been added for SW 3.3 in comparison to SW 3.1/3.2?

- "External position reference value" operating mode
- Axis couplings
- Angular incremental encoder interface as input
- Direct measuring system (DM, encoder 2)
- Process data
  - Encoder interface (encoder 1, 2 and 3) is written into bitwise
  - Standard telegrams 4 and 103 have been supplemented
- The encoder interface is independent of clock-synchronous operation
- Traversing to fixed stop
- In order to execute traversing blocks, it is no longer necessary to supply the input signals "Operating condition/reject traversing task" and "Operating condition/intermediate stop".
- SimoCom U "Boot board" function
  "User parameter list" function
- Permanent–magnet synchronous motors with field weakening (1FE1 motors, PE spindle)
  - List of 1FE1 motors, expanded
  - Reluctance torque constant introduced
- Bandstop filter with bilinear transformation or Z transformation

Edition 08.01 describes the functionality of SW 2.x, SW 3.x and SW 4.x.

What are the essential new functions that have been added for SW 4.x in comparison to SW 2.x/3.x?

- "External position reference value" is now available in the "Positioning" mode
- Teach–in and incremental jogging
- Slave–to–slave communications, PROFIBUS–DP
- Dynamic Servo Control (DSC)
Edition 02.02 describes the functionality of SW 2.x, SW 3.x, SW 4.x and SW 5.1.

What are the essential new functions that have been added for SW 5.1?

- Spindle positioning
- Possibility of integrating into an external safety concept
  “Safe standstill”
- Expanded functionality of the “SimoCom U” start-up tool
  - Support, motor data optimization
  - Bit masking for the "Trace" function
- Passive homing
- Filter parameterization (current, speed setpoint)
- "SIMODRIVE 611 universal HR" control board
  (HR stands for high resolution)
- The functionality for "SIMODRIVE 611 universal” described in the
  Description of Functions, also applies to “SIMODRIVE 611 universal HR”

Edition 08.02 describes the functionality of SW 2.x, SW 3.x, SW 4.x, SW 5.x and SW 6.1.

What are the essential new functions that have been added for SW 6.1?

- PROFIdrive conformance

Edition 02.03 describes the functionality of SW 2.x, SW 3.x, SW 4.x, SW 5.x, SW 6.x and SW 7.1.

What are the essential new functions that have been added for SW 7.1?

- MDI (external block processing)

Edition 07.03 describes the functionality of SW 2.x, SW 3.x, SW 4.x, SW 5.x, SW 6.x and SW 7.

The 06.04 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x and SW 8.1

What are the essential new functions that have been added for SW 8.1?

- Electronic handwheel
- Password protection
- Any gearbox ratio
- Changes/modifications for the CAN bus
- Direction–dependent fast–stop using a hardware switch

The 10.04 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x and SW 8.x
The 04.05 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x and SW 8.x

What are the essential new functions that have been added for SW 8.3?

- Input signal "ON/OFF 1" at a digital input terminal
- Reading the DC link voltage via PROFIBUS-DP
- Referencing (homing) with distance-coded measuring system

The 09.05 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x and SW 9.x

What are the essential new functions that have been added for SW 9.1?

- Control board "SIMODRIVE 611 universal HRS" to compatibly replace the control board "SIMODRIVE 611 universal HR"
- Additional torque/force limiting at zero setpoint (P1096/P1097)
- Parameter P0900 (angular incremental encoder handwheel evaluation) is replaced by P0889
- Supplement to activate the function generator and the measuring function for "SimoCom U" with
  - PROFIBUS control signal in the pos mode (PosStw.15)
  - Digital input terminal function No. 41

The 04.06 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x and SW 9.x

What are the essential new functions that have been added for SW 9.2?

- New type, optional PROFIBUS-DP module:
  PROFIBUS-DP2, Order No. (MLFB): 6SN1114-0NB00-0AA2
  PROFIBUS-DP3, Order No. (MLFB): 6SN1114-0NB01-0AA1
- Active oscillation damping (APC, in preparation)
- Extension of positioning data sets (64 to 256, in preparation)
- Start-up Tool "SimoCom U" can run under WIN Server 2003

The 08.06 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x and SW 9.x

What are the essential new functions that have been added for SW 10.1?

- Active oscillation damping (APC)
- Extension of positioning data sets (64 to 256)
- Encoder plausibility monitoring

The 12.06 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x, SW 9.x and SW 10.x

What are the essential new functions that have been added for SW 10.2?

- Troubleshooting
The 07.07 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x, SW 9.x, SW 10.x and SW 11.x

What are the essential new functions that have been added for SW 11.1?
- Stationary minimum speed speed range exclusion (taken over from SIMODRIVE 611 analog)
- Improvement of the distance of the measuring probe edges (to 65 ms)
- PTC evaluation for ASM (taken over from SIMODRIVE 611 analog)
- Signal: Programmed velocity reached
- Monitoring of the direction of the axis motion
- Oscillation (taken over from SIMODRIVE 611 analog)
- Thermal motor model

The 02.08 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x, SW 9.x, SW 10.x and SW 11.x

What are the essential new functions that have been added for SW 11.2?
- PROFIBUS-DP expansion and optional module interfaces for parameters > 2000
- Oscillation function enabled via P 0878.6 = 1
- Troubleshooting

The 09.08 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x., SW 8.x, SW 9.x, SW 10.x SW 11.x and SW 12.1.x

What are the essential new functions that have been added for SW 12.1?
- Speed monitoring using a BERO for IM operation
- Adaptations for PROFIDRIVE Version 4
- Travel to fixed stop with velocity limiting
- P1172 “FD operation with field weakening” have been introduced
- Troubleshooting

The 06.09 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x., SW 8.x, SW 9.x, SW 10.x SW 11.x and SW 12.1.x

What are the essential new functions that have been added for SW 12.2?
- Pre-alarm threshold, thermal motor protection
- Troubleshooting

The 05.10 Edition describes the functionality of SW 3.6, SW 4.1, SW 5.x, SW 6.x, SW 7.x, SW 8.x, SW 9.x, SW 10.x SW 11.x, SW 12.1.x and SW 13.1.x

What are the essential new functions that have been added for SW 13.1?
- Equalization controller via Profibus
- Expansion of the power section derating
- Motor diagnostics, ground-fault test
- Dynamic energy management
- Online help “SimuComU start-up tool” changeover to HTML
Setup and operation of the device/equipment/system in question must only be performed using this documentation. Only qualified personnel should be allowed to commission and operate the device/system. Qualified personnel as referred to in the safety instructions in this documentation are persons authorized to start up, ground, and label devices, systems, and circuits in accordance with the relevant safety standards.

Safety information/instructions

This documentation contains information that must be observed to ensure your personal safety and to prevent material damage. The instructions for your personal safety are marked by a warning triangle. Instructions relating solely to material damage are not marked by a warning triangle. Depending on the degree of hazard, the warning information is shown as follows in decreasing sequence:

**Danger**

Indicates that death or severe personal injury **will** result if proper precautions are not taken.

**Warning**

Indicates that death or severe personal injury **may** result if proper precautions are not taken.

**Caution**

With a warning triangle indicates that minor personal injury **can** result if proper precautions are not taken.

**Caution**

Without warning triangle indicates that material damage **can** result if proper precautions are not taken.

**Notice**

Indicates that an undesirable result or state **may** arise if the relevant note is not observed.
Proper use

Note the following:

Warning
Siemens products must only be used for the applications specified in the catalog and in the technical documentation. If third-party products and components are used, they must be recommended or approved by Siemens. To ensure trouble-free and safe operation of the products, they must be appropriately transported, stored, assembled, installed, commissioned, operated and maintained. The permissible ambient conditions must be adhered to. The notes in the associated documentation must be complied with.

Further notes

Note
This symbol indicates important information about the product or part of the document, where the reader should take special note.

Reader’s note
This symbol is shown, if it relates to important information which the reader must observe.

Technical information

Warning
When electrical equipment is operated, certain parts of this equipment are inevitably under dangerous voltage.
Incorrect handling of these units, i.e. not observing the warning information, can therefore lead to death, severe bodily injury or significant material damage.

Only appropriately qualified personnel may commission/start up this equipment.

This personnel must have in-depth knowledge regarding all of the warning information and service measures according to this operating instructions.

Professional transport, storage, mounting, and installation, as well as careful operation and service, are essential for the error-free, safe and reliable operation of the equipment.

Hazardous axis motion can occur when working with the equipment.
Danger

"Protective separation" (PELV/SELV) in the drive can only be guaranteed when the following points are taken into consideration:

- Certified components are used.
- The degree of protection for all components is ensured.
- With the exception of the DC link and motor terminals, all of the circuits (e.g. digital inputs) must fulfill the requirements of PELV or SELV circuits.
- The braking cable shield must be connected to PE through the largest possible surface area.
- For unlisted motors, "protective separation" is required between the temperature sensor and motor winding.

Note

When handling cables, observe the following:

- They are not damaged,
- they may not be stressed,
- they may not come into contact with rotating components.

Warning

All of the SIMODRIVE unit connections must be withdrawn or disconnected when the electrical equipment on the machines is subject to a voltage test (EN 60204-1 (VDE 0113-1), Point 20.4). This is necessary, as the SIMODRIVE insulation has already been tested, and should not be subject to a new test (additional voltage stressing).

Warning

Start-up/commissioning is absolutely prohibited until it has been ensured that the machine in which the components described here are to be installed, fulfills the regulations/specifications of the Directive 89/392/EEC.

Warning

The information and instructions in all of the documentation supplied and any other instructions must always be observed to eliminate hazardous situations and damage.

- For special versions of the machines and equipment, the information in the associated catalogs and quotations applies.
- Further, all of the relevant national, local land plant/system-specific regulations and specifications must be taken into account.
- All work should be undertaken with the system in a no-voltage condition!
Caution
When using mobile radios (e.g. cellular phones, mobile phones, 2-way radios) with a transmission power of > 1 W close to the equipment (< 1.5 m) the function of the equipment can be disturbed.

ElectroStatic Discharge Sensitive Devices

Note
Components, which can be destroyed by electrostatic discharge are individual components, integrated circuits, or boards, which when handled, tested, or transported, could be destroyed by electrostatic fields or electrostatic discharge. These components are referred to as ESDS (ElectroStatic Discharge Sensitive Devices).

Handling ESDS modules:
• When handling devices which can be damaged by electrostatic discharge, personnel, workstations and packaging must be well grounded!
• Electronic components should only be touched when absolutely necessary.
• Personnel may only come into contact with the components, if
  - they are continuously grounded through ESDS wristlets,
  - they wear ESDS shoes, ESDS shoe grounding strips in conjunction with an ESDS floor surface.
• Boards/modules must only be placed on conductive surfaces (table with ESDS surface, conductive ESDS foam, ESDS packaging, ESDS transport container).
• Boards may not be brought close to data terminals, monitors or television sets (minimum clearance to the screen > 10 cm).
• Boards may not be brought into contact with highly insulating materials which can be statically charged, e.g. plastic foils, insulating desktops, clothing manufactured from man-made fibers.
• Measuring work may only be carried out on the components if
  - the measuring unit is grounded (e.g. via protective conductor), or
  - for floating measuring equipment, the probe is briefly discharged before making measurements (e.g. a bare-metal control housing is touched).
• Only touch control components, option modules and memory modules at the front panel or at the edge of the PC boards.
Space for your notes
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1.1 What can "SIMODRIVE 611 universal" do?

"SIMODRIVE 611 universal" is a control board, which can be universally used in the modular SIMODRIVE 611 converter system as a result of its communication interfaces, the motors and encoder systems and option modules which can be used.

Two independent drive controls are implemented on a 2-axis board. The closed-loop drive controls can be operated in the following operating modes with motor frequencies up to 1400 Hz:

- Operating mode, "speed/torque setpoint":
  In this case, the board is used for closed-loop speed control, open-loop torque control and/or torque reduction.

- "Positioning" mode:
  A maximum of 64 (256 from SW 10.1) traversing blocks can be selected and executed. Every traversing block can be freely parameterized, and in addition to the block number, it also contains additional data, e.g. target position, acceleration, velocity, command and block enable circuit.

The following interfaces are provided on the board:

- Two analog interfaces per drive (±10 V)
  Setpoints for speed, torque (current, torque reduction or a velocity override when positioning can be entered via these interfaces.

- Angular incremental encoder interface (WSG-SS)
  - Parameterized as input: (from SW 3.3)
    Incremental position reference values can be entered.
  - Parameterized as output:
    The position actual values are available for a higher-level control via the appropriately parameterized interface.

- Four digital inputs and four digital outputs per drive
  The digital inputs/outputs can be assigned the required control/message functions by appropriate parameterization.

- Two analog outputs per drive
1.1 What can "SIMODRIVE 611 universal" do?

Optional modules
The "SIMODRIVE 611 universal" control board can be expanded by one of the following option modules:

- Optional TERMINAL module
  This module provides an additional 8 digital inputs and 8 digital outputs (e.g. necessary to select and start a traversing block in the "positioning" mode).

Note
The input/output terminals of the optional TERMINAL module are:

- Before SW 4.1: permanently assigned to drive A or axis A
- From SW 4.1: can be freely assigned axes

- Optional PROFIBUS–DP module
  To integrate the system into distributed concepts, "SIMODRIVE 611 universal" can be operated as slave on PROFIBUS–DP using this option module (refer to Table 1-3).

Which motors can be used?
The following motors can be used with "SIMODRIVE 611 universal":

- 1FK6, 1FT6 servomotors up to 140 Nm
- 1FE1 permanent-magnet synchronous motors
- 1PH induction motors up to 100 kW (1PH6, 1PH4, 1PH2, 1PH7)
- Induction motors without encoder
- Standard 1LA induction motors up to 100 kW
- 1FN linear motors
- 1FW6 built-in torque motors

Note
- Two different motor types can be operated with a control board (e.g. 1FK6 synchronous motor and 1PH7 induction motor).
- Unlisted motors can also be connected.
- The motors which can be connected are listed in Chapter A.3.
1.1 What can "SIMODRIVE 611 universal" do?

The following encoders can be connected when using "SIMODRIVE 611 universal":
- Resolver with pole pair numbers 1, 2, 3, 4, 5 and 6
- Incremental encoder with sin/cos 1Vpp up to 65535 pulses, e.g. ERN 1387 from Heidenhain
- Absolute encoder with sin/cos 1Vpp and interface with EnDat protocol, e.g. EGN 1325 from Heidenhain (EnDat protocol)
- From SW 8.1 incremental encoders with TTL signals with control board, Order No. 6SN1118-VN01-0AA, only for induction motors

Note
- For a 2-axis control board, it is not possible to mix encoders with sin/cos 1Vpp and resolvers.
- Unlisted encoders can also be connected.
- The encoders which can be connected are listed in Chapter A.4.
- The following is valid for resolvers:
  The selected resolver must match the motor.
  For resolvers, pole pair number = 1 (P1018) or the pole pair number of the motor (P1112) is permissible.

Parameter assignment
The equipment is integrated and adapted to the machine/system by appropriately parameterizing it. The following possibilities are available for start-up and for service:
- "SimoCom U" parameterizing and start-up tool (SimoCom U under Windows, refer to Chapter 3.3)
- Display and operator unit (on the control board front panel)

Data save
The control board has an interchangeable memory module with a non-volatile data memory (FEPROM) to save the following data:
- Firmware (system software)
- User data

Where can "SIMODRIVE 611 universal" be used?
The "SIMODRIVE 611 universal" control board can be flexibly used in many applications as a result of its design.
Typical applications for this control board are, e.g.:
- Textile machines
- Packaging machines
- Machine tools
- Handling equipment
- Conveyor and transport equipment
- Machines to machine/handle wood, glass or ceramics, etc.
1.1 What can "SIMODRIVE 611 universal" do?

The subsequent diagram provides an overview of the features and functions of "SIMODRIVE 611 universal".

**Optional modules**
- Optional TERMINAL module
- Optional module PROFIBUS-DP1 (up to SW 3.5)
- PROFIBUS-DP2 (from SW 3.1)
- PROFIBUS-DP3 (from SW 3.1)

**Serial interface**
- RS232
- RS-485

2 analog interfaces (± 10 V) per drive

Angular incremental encoder interface
- Electronic handwheel (from SW 8.1)

4 digital inputs and 4 digital outputs per drive (can be freely parameterized)
2 test sockets (0 - 5 V)

Safe start inhibit (AS1/AS2)
2 analog outputs (± 10 V) per drive

Pushbuttons and LEDs for
- POWER-ON RESET
- FAULT

**Control units**
- 2-axis for encoders with sin/cos 1 Vpp
- 2-axis for resolvers
- 1-axis for resolvers

As an alternative, for each board, the following firmware can be used:
- n-set
- Positioning

**Operating modes**
- n-set (speed/torque setpoint)
- Speed control
- Open-loop torque control
- Torque reduction
- Dyn. Servo Control (DSC, from SW 4.1)
- Spindle positioning (from SW 5.1)
- Oscillation (from SW 11.1)
- Speed monitoring using a BERO (from SW 12.1)
- Positioning
- HW/SW limit switches
- 64 (256) traversing blocks (maximum)
- Position-related switching signals
- Rotary axis with modulo correction (from SW 2.4)
- Jerk limiting (from SW 3.1)
- External block change (from SW 3.1)
- Travel to fixed stop (from SW 3.3)
- Axis couplings (from SW 3.3)
- Position measuring system with distance-coded reference marks (from SW 4.1)
- Jogging via velocity and incremental (from SW 4.1)
- Teach-in (from SW 4.1)
- MDI operation (from SW 7.1)

**Memory module** (can be replaced)
- Firmware (system software)
- User data (parameter)
- Display and operator unit

**“SimoCom U” parameterizing and start-up tool**

**Communication**
- SimoCom U <-> drive
  - via serial interface
  - via PROFIBUS (from SW 3.1)
- PROFIBUS-DP

**Motors**
- 1FK, 1FT6 synchronous motors
- 1FE1 permanent-magnet synchronous motors
- 1PH induction motors
- 1LA standard induction motors
- 1FN linear motors
- 1FW6 built-in torque motors

**Encoder**
- Incremental encoder with sin/cos 1Vpp
- Absolute encoder with sin/cos 1Vpp and EnDat interface
- Resolver with pole pair numbers 1, 2, 3, 4, 5 and 6
- Incremental encoders with TTL signals (only induction motors) (from SW 8.1)

**Fig. 1-1  Function overview for “SIMODRIVE 611 universal”**
1.2 "SIMODRIVE 611 universal" in the SIMODRIVE 611 system

How is the SIMODRIVE 611 universal integrated into the SIMODRIVE 611 system?

"SIMODRIVE 611 universal" is implemented as digital control module for two drives for operation in the SIMODRIVE 611 system. A SIMODRIVE drive group is modular and comprises the following modules and boards:

- Commutating reactor(s)
- Supply infeed module (NE module)
- Power module(s) with control board
  - "SIMODRIVE 611 universal" or
  - "SIMODRIVE 611 universal HR" (from the middle of 2002 with SW 5.1)
  - "SIMODRIVE 611 universal HRS" (from the middle of 2005 with SW 9.1)

Note

In the following chapters of the Description of Functions, a differentiation is not made between "SIMODRIVE 611 universal" and "SIMODRIVE 611 universal HR/HRS". The functionality, specified under "SIMODRIVE 611 universal" also applies for "SIMODRIVE 611 universal HR/HRS".

and, when required

- Line filter
- Monitoring and pulsed resistor module
- Transformer

Reference: /PJU/, SIMODRIVE 611, Configuration Manual, Drive Converters

Configuration

Engineering a SIMODRIVE drive group is subdivided into the following phases as follows:

- Phase 1 (engineering)
  - The motor is selected
  - The power module and the supply infeed are selected
- Phase 2 (integration)
  - Create circuit diagrams
Note

The following documentation, SW Tools and Catalogs are available when engineering the system:

- **Reference:** /PJU/, SIMODRIVE 611, Configuration Manual, Drive Converters
- **Reference:** /PJM/, SIMODRIVE 611, Configuration Manual, Motors
  AC Motors for Feed and Main Spindle Drives
- **PC Tool:** /SP/, SIMOPRO, Program to engineer SIMODRIVE drives
  [http://www.ad.siemens.de/mc/html_00/info/projektier_tools/index.htm](http://www.ad.siemens.de/mc/html_00/info/projektier_tools/index.htm)
- **Reference:** /BU/, Catalog NC 60, Ordering Documentation
  /Z/, Catalog NC Z, Accessories and Equipment
- **CD:** Interactive Catalog CA01
- **CD:** /CD1/, DOC ON CD with all SINUMERIK 840D/810D/FM–NC and SIMODRIVE 611D documentation
System overview

The SIMODRIVE 611 drive converter system with the "SIMODRIVE 611 universal" control board can comprise the individual components and higher-level control components as shown in the following diagram.

![System overview diagram](image)

Fig. 1-2 System overview (schematic)
Components

The most important components and their function are listed in the following table.

Table 1-1 Components for the SIMODRIVE 611 system

<table>
<thead>
<tr>
<th>Component</th>
<th>Function</th>
</tr>
</thead>
</table>
| Line supply infeed module (NE module) | ... has the following functions:  
  - Interface from/to the 3-phase network  
  - Establishes the DC link voltage  
  - Equipment bus |
| Equipment bus | ... supplies the control boards with various voltages and enable signals. |
| DC link | ... the power modules draw the power required to control the motors from the DC link. |
| Power modules | ... control the motors. |
| "SIMODRIVE 611 universal" control board | ... is used as 1 or 2-axis board in the SIMODRIVE 611 system, and can be expanded using the optional TERMINALS or PROFIBUS-DP module. |
| Memory module | ... is integrated on the control board, can be replaced and has a non-volatile memory (EPROM) to save the firmware and the user data. |
| Optional modules | ... expands the interface functionality of the control board.  
  ... the optional TERMINAL module or the optional PROFIBUS-DP module can be used. |
| Motor | ... is connected to the power module. |
| Encoder | ... is the angular incremental encoder to sense the actual position. |
| Parameterizing and start-up tool (SimoCom U) for PG/PC | ... is a software running under Windows 95/98/NT2000/XP to parameterize, commission and test the "SIMODRIVE 611 universal" control board.  
Furthermore, using this tool, the following functions are possible:  
  - Parameterizing "SIMODRIVE 611 universal"  
  - Axes traversed  
  - Settings optimized  
  - Firmware downloaded  
  - Series machine startup  
  - Diagnostics (e.g. measuring function) |
1.3 "SIMODRIVE 611 universal" control board

Description
The "SIMODRIVE 611 universal" control board is used in the SIMODRIVE 611 system, and it can be expanded using the optional TERMINALS or PROFIBUS–DP module.

Features
The control board has the following features:

- Variants

Table 1-2 Control board, option modules, data medium

<table>
<thead>
<tr>
<th>Cons. No.</th>
<th>Description</th>
<th>Order No. (MLFB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Control unit</td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>2-axis(^1) for encoders with sin/cos 1 Vpp or TTL signals(^9)</td>
<td>6SN1118–0NH00–0AA(^2)(6)</td>
</tr>
<tr>
<td>3</td>
<td>2-axis(^1) for resolvers</td>
<td>Positioning</td>
</tr>
<tr>
<td>4</td>
<td>2-axis(^1) for resolvers</td>
<td>6SN1118–0NK00–0AA(^2)(6)</td>
</tr>
<tr>
<td>5</td>
<td>2-axis(^1) for resolvers</td>
<td>Positioning</td>
</tr>
<tr>
<td>6</td>
<td>1-axis for resolvers</td>
<td>6SN1118–0NJ00–0AA(^2)(6)</td>
</tr>
<tr>
<td>7</td>
<td>1-axis for resolvers</td>
<td>Positioning</td>
</tr>
<tr>
<td>8</td>
<td>Option module (can be alternatively used in the control board)</td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>TERMINALS</td>
<td>6SN1114–0NA00–0AA0</td>
</tr>
<tr>
<td>10</td>
<td>PROFIBUS–DP(^1)(3)</td>
<td>6SN1114–0NB00–0AA0</td>
</tr>
<tr>
<td>11</td>
<td>PROFIBUS–DP(^2)(4)</td>
<td>6SN1114–0NB00–0AA2</td>
</tr>
<tr>
<td>12</td>
<td>PROFIBUS–DP(^3)(4)</td>
<td>6SN1114–0NB01–0AA1</td>
</tr>
</tbody>
</table>

Data carrier

<table>
<thead>
<tr>
<th>Cons. No.</th>
<th>Description</th>
<th>Order No. (MLFB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>CD</td>
<td>SimoCom U, drive firmware, Toolbox, GSD file, readme file, etc.</td>
</tr>
</tbody>
</table>

\(^1\) For 2-axis control boards, 1-axis operation is also possible
\(^2\) □: Space retainer for the hardware and software version
\(^3\) Can no longer be used from SW 4.1
\(^4\) Prerequisites: Control board SW 3.1 and higher
\(^5\) 1: "SIMODRIVE 611 universal HRS" control board from SW 8.3
\(^6\) "SIMODRIVE 611 universal" control board
\(^7\) 0: "SIMODRIVE 611 universal HR" control board from SW 5.1
\(^8\) 0: "SIMODRIVE 611 universal HR" control board from SW 6.2
\(^9\) With control board, Order No. 6SN1118–□NH01–0AA□ from SW 8.1
Reader’s note
Please observe the information in the "readme.txt" file on the CD for "SIMODRIVE 611 universal".

• Settings
All drive-related settings of the control board can be made as follows:
- using the parameterizing and start-up tool SimoCom U on an external PG/PC (refer to Chapter 3.3)
- using the display and operator unit on the front panel (refer to Chapter 3.2)
- using PROFIBUS-DP (parameter area, PKW area, refer to Chapter 5.6.7)

• Software and data
The firmware and the user data are saved on a memory module which can be replaced.

• Terminals and operator control elements
- 2 analog inputs, 2 analog outputs per drive
- 4 digital inputs, 4 digital outputs per drive
- 2 test sockets
- POWER-ON RESET pushbutton with LED
- Display and operator unit

• Safe start inhibit
The start inhibit is addressed via terminal 663 and is signaled back using a relay with positively-driven signaling contacts (AS1/AS2). Using the start inhibit, the energy feed from the drive to the motor is interrupted.
When the “safe start inhibit” function is correctly used, the signaling contacts AS1/AS2 must be included in the line contactor circuit or the EMERGENCY OFF circuit.

Caution
When using the “safe start inhibit” function, it must be ensured that the velocity goes to zero.

The control board supports the “Safe standstill” function.
Detailed information about the “Safe Standstill” function is provided in

Reference: /PJU/, SIMODRIVE 611, Configuration Manual, Drive Converters
• Serial interface (RS232/RS485)

• Optional modules
  - Optional TERMINAL module,
    8 digital inputs and 8 digital outputs for drive A
  - Optional PROFIBUS–DP module

• Expanded functions SW 5.1 and higher
  The following expanded functionality is provided with the "SIMODRIVE 611 universal" control board for sin/cos 1Vpp encoders:
  - Higher internal resolution, interpolation factor 2048 (previously 128)
  - Pulse multiplication is possible (doubling) at the angular incremental encoder interface for absolute value encoders
  - Pulse multiplication (doubling) and division (1:2, 1:4, 1:8) are possible at the angular incremental encoder interface, also for incremental encoders
  - From SW 8.1
    It is possible to connect standard square-wave encoders (TTL) with differential signals according to RS422 and 5 V power supply voltage as pulse encoder for induction motors at the SIMODRIVE 611 universal HR" control board (Order No. 6SN1118--VNH01--0AA.).

• Expanded functions from SW 9.1
  "SIMODRIVE 611 universal HR" or "SIMODRIVE 611 universal" control boards can be replaced by the "SIMODRIVE 611 universal HRS" control board (higher computational performance) and this replacement is compatible.

  The "SIMODRIVE 611 universal HRS" control board is, at all interfaces, electrically compatible to its predecessor and as far as all of the functions are concerned.

  The mechanical dimensions, mounting/installation dimensions and connection interfaces of the "SIMODRIVE 611 universal HRS" control board are compatible to the previous types and are compatible from an installation perspective to the the SIMODRIVE 611 digital power modules.

  Exception: Connectors X461/X462.
  - 10-pin for "SIMODRIVE 611 universal".
  - 11-pin for "SIMODRIVE 611 universal HR" and "SIMODRIVE 611 universal HRS" as terminal 15 has been added.

  When the board has to be replaced, please refer to the attached installation instructions regarding the wiring changes that have to be made.
1.3.1 Control board for 2 or 1 axis

The following 2-axis control boards are available:

1. Mounting slot for
   - Optional TERMINAL module
   - Optional PROFIBUS-DP module
2. Interfaces
   - Terminals
   - Switches
3. Memory module
   - Firmware
   - User data
4. Display and operator unit
5. Pulse interface
6. Equipment bus

The following applies to retaining screws:
- Tighten (to establish a good shield contact) max. torque = 0.8 Nm
- For plug connections:
  - Plug connectors with the same number of pins must be appropriately coded so that they cannot be interchanged (refer under the index entry "Coding the mini connectors").

Fig. 1-3 Control boards for 2 axes
The following 1-axis control boards are available:

- Mounting slot for
  - Optional TERMINAL module
  - Optional PROFIBUS-DP module
- Interfaces
- Terminals
- Switches
- Memory module
  - Firmware
  - User data
- Display and operator unit
- Pulse interface
- Equipment bus

The following applies to retaining screws:
Tighten (to establish a good shield contact) max. torque = 0.8 Nm
For plug connections:
Plug connectors with the same number of pins must be appropriately coded so that they cannot be interchanged (refer under the index entry "Coding the mini connectors").
1.3.2 Elements on the control board front panel

- **Motor encoder, drive A**: X411
- **Motor encoder, drive B**: X412
- **Pushbutton for POWER-ON**: S1
- **Red FAULT LED**:
- **Mounting slot for**:
  - Optional TERMINAL module X422 (inputs)
  - X432 (outputs) (refer to Chapter 1.3.3)
  - Optional PROFIBUS-DP module X423 (interface) (refer to Chapter 1.3.3)
- **Terminals, drive B**:
  - P24
  - M24
  - 9
  - 19
- **Terminals for supply and pulse enable**:
  - X421
  - X431
- **Analog outputs**:
  - 75.A
  - 16.A
  - 75.B
  - 16.B
  - 15
- **Terminals, drive A**:
  - 56.A
  - 14.A
  - 24.A
  - 20.A
  - 65.A
  - 9
  - 10.A
  - 11.A
  - 12.A
  - 13.A
  - A+.A
  - A--.A
  - B+.A
  - B--.A
  - R+.A
  - R--.A
  - O0.A
  - O1.A
  - O2.A
  - O3.A
- **Switch S1**
- **Serial interface (RS232/RS485)**: X471
- **Display and operator unit**
- **Equipment bus**

1) for 6SN1118:...-0A#: Order No. [MLFB] refer to Table 1-2
2) for 6SN1118:...-0A#: Order No. [MLFB] refer to Table 1-2

Fig. 1-5 Front panel elements (dummy cover removed, no option module inserted)
Reader’s note

The display and operator control elements provided on the front panel are described in the following.

Additional information about

- Terminals (assignment, wiring, technical data, etc.)
- Interfaces (assignment, wiring, etc.)

are included in the Chapter 2.

Button for

POWER-ON-RESET, button

The button is recessed into the front panel (hole: \( \varnothing 3\) mm).

The processor runs up again when pressed.

When the pushbutton is pressed, an LED which may have been previously bright (lit), goes dark, i.e. this indicates the pushbutton was completely actuated (the pushbutton pressure point has been reached).

Warning

When the POWER-ON RESET button is pressed, this corresponds to a POWER ON and should only be executed when the motors are at a standstill.

In order to prevent the drive from undesirably starting after POWER ON, before carrying out a POWER ON–RESET, the controller enable must be withdrawn at terminals 65.A and 65.B.

- FAULT, LED red (refer to Chapter 7.2.2)

The LED is bright at run-up and when faults occur.

Display and operator unit

The 6-character 7-segment display with point is used to display and change parameter values and to display alarms.

The operator control PLUS, P and MINUS keys are used to select and change parameter values and/or for operator control when faults and warnings are displayed (e.g. to acknowledge these).

Reader’s note

Handling the display and operator unit

- How to parameterize "SIMODRIVE 611 universal" is described in Chapter 3.2.
- To remove faults and warnings refer to Chapter 7.2.
Switch S1

The terminating resistor can be switched-in/switched-out using switch S1 on the front panel of the control board for the angular incremental encoder interface and the serial RS485 interface (RS485-SS).

**Note:**
All of the associated switches (e.g. switches 7 and 8) must be in the same setting.

**Fig. 1-6** Location and settings of switch S1
1.3.3 Optional modules

Optional TERMINAL module

An additional 8 digital inputs and outputs can be realized using this optional module. The functionality of these inputs/outputs can be freely parameterized.

Note

- The input/output terminals of the optional TERMINAL module are
  - Before SW 4.1: permanently assigned to drive A or axis A
  - From SW 4.1: can be freely assigned axes
- The optional TERMINAL module can be used as follows, dependent on the software release:
  - The following applies before SW 2.4: The module can only be used in the "positioning" mode.
  - The following applies from SW 2.4: The module can be used independently of the operating mode.

Order No. [MLFB]: 6SN1114-0NA00-0AA0

Fig. 1-7 Optional TERMINAL module

Reader’s note

Information regarding
- Installing the option
- The input and output terminals (X422 and X432)
- The connection diagram and wiring/connecting the option module is included in Chapter 2.
Optional PROFIBUS-DP module

The "SIMODRIVE 611 universal" control board can be connected and operated as DP slave on the PROFIBUS-DP field bus when this optional module is used.

The following applies to retaining screws:
- Tighten (due to the shield contact)
- Max. torque = 0.8 Nm

**Fig. 1-8** Optional PROFIBUS-DP module

**Table 1-3** Which optional modules are available?

<table>
<thead>
<tr>
<th>Designation</th>
<th>Order No. (MLFB)</th>
<th>Features</th>
</tr>
</thead>
</table>
| PROFIBUS-DP1 (can no longer be used from SW 4.1) | 6SN1114-0NB00-0AA0 | • PROFIBUS-ASIC SPC3  
• Cyclic data transfer (PKW and PZD section) possible |
| PROFIBUS-DP2 | 6SN1114-0NB00-0AA2 | • PROFIBUS-ASIC DPC31 without PLL  
• For control boards SW 3.1, this module can replace the optional PROFIBUS-DP1 module |

Features that PROFIBUS-DP2 and DP3 have in common

- Requirement: Control board from SW 3.1 is required  
- Cyclic data transfer (PKW and PZD section) possible  
- FW module can be updated using SimoCom U  
- Non-cyclic data transfer (DP/V1)  
- "SimoCom U via PROFIBUS" possible

PROFIBUS DP3 | 6SN1114-0NB01-0AA1 | • PROFIBUS-ASIC DPC31 with PLL  
• "Motion Control with PROFIBUS-DP" function (clock-synchronous PROFIBUS operation) is possible |
Table 1-4  Which optional modules can be used for the various software releases?

<table>
<thead>
<tr>
<th>Situation</th>
<th>Firmware version</th>
<th>Optional module</th>
</tr>
</thead>
<tbody>
<tr>
<td>1. A master configured software, generated with GSD file siem808f.gsd, can be operated with</td>
<td>from SW 3.1</td>
<td>No</td>
</tr>
<tr>
<td>2. A master configured software, generated with a GSD file siem8055f.gsd and P0875 = 2, can be operated with</td>
<td>before SW 4.1</td>
<td>Yes</td>
</tr>
<tr>
<td>3. A master configured software, generated with a GSD file siem8055f.gsd and P0875 = 2, can be operated with</td>
<td>from SW 4.1</td>
<td>No</td>
</tr>
<tr>
<td>4. A master configured application, generated using gsd file si02808f.gsd and P0875 = 2 can be operated with</td>
<td>from SW 6.1</td>
<td>No</td>
</tr>
</tbody>
</table>

**Note**

Case 1 is for "new" applications with the DP2, DP3 module.

Cases 2 and 3 are for series commissioning of drives using DP1 modules and for replacing a defective DP1 module by a DP2 module. From SW 4.1, the DP1 module can no longer be used.

**Reader's note**

Information regarding
- Installing the optional module  --> refer to Chapter 2
- The interface (X423)       --> refer to Chapter 2
- The connection diagram and wiring/connection of the option module   --> refer to Chapter 2
- Communications via PROFIBUS-DP --> refer to Chapter 5
1.4 "SIMODRIVE 611 universal E" control board

Description
The "SIMODRIVE 611 universal E" control board is used with
SINUMERIK 802D with the "motion control with PROFIBUS--DP" func-
tion.
Using this function, it is possible to implement a clock-synchronous
drive coupling between a DP master (e.g. SINUMERIK 802D) and the
DP slave "SIMODRIVE 611 universal E".

Features
The control board has the following features:
• Control board (refer to Chapter 1.4.1)
  - Order No. (MLFB):
    before SW 5.1: 6SN1118--0NH10--0AA
    ("SIMODRIVE 611 universal E" control board)
    □: Space retainer for hardware function
    from SW 5.1: 6SN1118--0NH11--0AA0
    ("SIMODRIVE 611 universal E HR" control board)
    from SW 9.1: 6SN1118--0NH11--0AA1
    ("SIMODRIVE 611 universal E HRS" control board)
  - 2-axis for encoders with sin/cos 1Vpp
  - with memory module for n-set
• Optional PROFIBUS--DP3 module (refer to Chapters 1.3.3 and 1.4.1)
  - Order No. (MLFB): 6SN1114--0NB01--0AA0
• The parameters can be set as follows:
  - using the "SimoCom U" parameterizing and start-up tool on an
    external PG/PC (refer to Chapter 3.3)
  - using the display and operator unit on the front panel
    (refer to Chapter 3.2)
  - using PROFIBUS--DP
    (parameter area, PKW area, refer to Chapter 5.6.7)
• Software and data
  The software and the user data are saved on an interchangeable
  memory module.
• Terminals and operator control elements
  - 2 analog inputs and 2 analog outputs per drive
  - 2 digital inputs and 2 digital outputs per drive
  - 2 test sockets
  - POWER-ON RESET button with integrated LED
  - Display and operator unit
• Safe start inhibit
  Detailed information about this function is provided in
Reference: /PJU/, SIMODRIVE 611,
Configuration Manual, Drive Converters
• Serial interface (RS232, refer to Chapter 3.3.3)
1.4.1 Diagram of the board and optional module

The following applies to retaining screws:
Tighten (due to the shield contact)
Max. torque = 0.8 Nm

For plug connections:
Plug connectors with the same number of pins must be appropriately coded so that they cannot be interchanged (refer under the index entry "Coding the mini connectors").

Fig. 1-9 "SIMODRIVE 611 universal E" control board with optional PROFIBUS-DP3 module
1.4.2 Elements on the control board front panel

Fig. 1-10 Elements on the front panel of "SIMODRIVE 611 universal E"
### 1.4.3 Description of the terminals, interfaces and operator control elements

#### Board-specific terminals and interfaces

The board-specific terminals and interfaces are available, common for both drive A and B.

#### Table 1-5 Overview of the board-specific terminals and interfaces

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Signaling terminal, start inhibit (X421)</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>AS1 X421</td>
<td>Signaling contact</td>
<td>NC</td>
<td>Connector type: 2-pin conn. strip</td>
</tr>
<tr>
<td>AS2</td>
<td>Start inhibit</td>
<td></td>
<td>Max. cond. cross-sect.: 2.5 mm²</td>
</tr>
<tr>
<td></td>
<td>Feedback signal from terminal 663</td>
<td></td>
<td>Contact: Floating NC contact</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Contact load capability: at 250 VAC max. 1 A 2) at 30 VDC max. 2 A</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>AS1</td>
<td>Relay, safe start inhibit</td>
<td></td>
<td></td>
</tr>
<tr>
<td>AS2</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>T. 663</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Pulses not enabled (T. 663)</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>The gating pulses of the power transistors are inhibited.</td>
</tr>
<tr>
<td>AS1</td>
<td>Relay, safe start inhibit</td>
<td></td>
<td></td>
</tr>
<tr>
<td>AS2</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>T. 663</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Pulses enabled (T. 663)</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>The gating pulses of the power transistors are enabled.</td>
</tr>
</tbody>
</table>

**Terminals for supply and pulse enable (X431)**

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>X431</strong></td>
<td></td>
<td></td>
<td>Connector type: 5-pin conn. strip</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Max. cond. cross-sect.: 1.5 mm²</td>
</tr>
<tr>
<td><strong>P24 X431.1</strong></td>
<td>External power supply for digital outputs (+24 V)</td>
<td>S</td>
<td>Voltage tolerance (including ripple): 10 V to 30 V</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Max. aggregate current: 2.4 A</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• The external supply is required for the 4 digital outputs (O0.A, O1.A and O0.B, O1.B).</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• When dimensioning the external power supply, the total current of all of the digital outputs must be taken into account.</td>
</tr>
<tr>
<td><strong>M24 X431.2</strong></td>
<td>Reference for the external supply</td>
<td>S</td>
<td>Reference: Terminal 19</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Maximum current (for the total group): 500 mA</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>The enable voltage (terminal 9) can be used to supply the enable signals (e.g. pulse enable) at 24 V auxiliary voltage.</td>
</tr>
<tr>
<td><strong>9 X431.3</strong></td>
<td>Enable voltage (+24 V)</td>
<td>S</td>
<td>Reference:</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

1) NC: NC contact; S: Supply
2) Corresponding to EN 60204-1 (Safety of Machinery), control transformers should be used when using AC control voltages.
Table 1-5  Overview of the board-specific terminals and interfaces, continued

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Function &amp; Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>663</td>
<td>X431.4</td>
<td>Pulse enable (+24 V)</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Voltage tolerance</td>
</tr>
<tr>
<td></td>
<td></td>
<td>(including ripple): 21 V to 30 V</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Typ. current consumption: 25 mA at 24 V</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Note:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The pulse enable acts simultaneously on drive A and drive B. When this pulse enable is withdrawn, the drives &quot;coast down&quot; unbraked.</td>
</tr>
<tr>
<td>19</td>
<td>X431.5</td>
<td>Reference (Reference for all digital inputs)</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Note:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>If the enable signals are to be controlled from an external voltage and not from terminal 9, then the reference potential (ground) of the external source must be connected to this terminal.</td>
</tr>
<tr>
<td>X471</td>
<td>Serial interface for “SimoCom U”</td>
<td>Connector type: 9-pin D-sub socket connector</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Note:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• The interface can only be used as RS232 interface --&gt; refer to Chapter 3.3.3</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Pin assignment of the interface --&gt; refer to Chapter 2.4</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Cable diagram for RS232 --&gt; refer to Chapter 2.5</td>
</tr>
<tr>
<td>X423</td>
<td>Communications interface for PROFIBUS</td>
<td>Connector type: 9-pin D-sub socket connector</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Note:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Pin assignment of the interface --&gt; refer to Chapter 2.4</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Connecting diagram and connecting-up the optional PROFIBUS-DP module --&gt; refer to Chapter 2.3.4</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Communications via PROFIBUS-DP --&gt; refer to Chapter 5</td>
</tr>
<tr>
<td>X351</td>
<td>Equipment bus</td>
<td>Ribbon cable: 34-pole</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Voltages: various</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Signals: various</td>
</tr>
<tr>
<td>X34</td>
<td>Test socket 1&lt;sup&gt;2)&lt;/sup&gt;</td>
<td>Test socket: ☝ 2 mm</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Resolution: 8 bits</td>
</tr>
<tr>
<td></td>
<td>X34</td>
<td>Rated operating voltage: 0 V to 5 V</td>
</tr>
<tr>
<td></td>
<td>DAC2</td>
<td>Maximum current: 3 mA</td>
</tr>
</tbody>
</table>

1) I: Input; S: Supply; IO: Input/output; MA: Measuring signal, analog
2) Can be freely parameterized
The drive-specific terminals are available for both drive A and drive B.

Table 1-6  Overview of the drive-specific terminals

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>Drive A</td>
<td>Drive B</td>
<td></td>
<td></td>
</tr>
<tr>
<td>No.</td>
<td>Designation</td>
<td>No.</td>
<td>Designation</td>
</tr>
<tr>
<td>Encoder connection (X411, X412)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>-</td>
<td>X411</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>-</td>
<td></td>
<td>X412</td>
<td></td>
</tr>
<tr>
<td>Reference:</td>
<td></td>
<td>I</td>
<td></td>
</tr>
<tr>
<td>PJU/ SIMODRIVE 611, Configuration Manual, Drive Converters</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Chapter “Indirect and direct position sensing”</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Encoder limit frequencies:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Encoder with sin/cos 1Vpp: 350 kHz</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Resolver: 432 Hz</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Analog outputs (X441)

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>Drive A</td>
<td>Drive B</td>
<td></td>
<td></td>
</tr>
<tr>
<td>No.</td>
<td>Designation</td>
<td>No.</td>
<td>Designation</td>
</tr>
<tr>
<td>75.A</td>
<td>X441.1</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>16.A</td>
<td>X441.2</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>-</td>
<td>X441.3</td>
<td>75.B</td>
<td></td>
</tr>
<tr>
<td>-</td>
<td>X441.4</td>
<td>16.B</td>
<td></td>
</tr>
<tr>
<td>15</td>
<td>X441.5</td>
<td>15</td>
<td>X441.5</td>
</tr>
<tr>
<td>Reference</td>
<td></td>
<td>-</td>
<td></td>
</tr>
</tbody>
</table>

1) I: Input; AO: Analogausgang
2) Can be freely parameterized
3) The analog outputs (X441) should be connected through a terminal strip.
   A shielded cable should be used together for all of the analog outputs together between X441 and the terminal strip. For this cable, the shield must be connected at both cable ends. The 4 analog cables can be routed away from the terminal strip. The shield of the cables must be connected and the ground cables must be connected to a common ground terminal.
Table 1-6  Overview of the drive-specific terminals, continued

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Drive A</th>
<th>Drive B</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>No.</td>
<td>Desig-</td>
<td>No.</td>
<td>Desig-</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>nation</td>
<td></td>
<td>nation</td>
<td></td>
</tr>
<tr>
<td>Connectors for the analog inputs and digital inputs/outputs (X453, X454)</td>
<td>X453</td>
<td>X454</td>
<td>Connectortype: 10-pin conn. strip</td>
<td>I</td>
<td>Typ. current consumption: 6 mA at 24 V</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Max. cond. cross-section for finely-stranded or solid cond.: 0.5 mm²</td>
<td></td>
<td></td>
</tr>
<tr>
<td>56.A</td>
<td>X453.1</td>
<td>56.B</td>
<td>X454.1</td>
<td>None</td>
<td>-</td>
</tr>
<tr>
<td>14.A</td>
<td>X453.2</td>
<td>14.B</td>
<td>X454.2</td>
<td>None</td>
<td>-</td>
</tr>
<tr>
<td>24.A</td>
<td>X453.3</td>
<td>24.B</td>
<td>X454.3</td>
<td>None</td>
<td>-</td>
</tr>
<tr>
<td>20.A</td>
<td>X453.4</td>
<td>20.B</td>
<td>X454.4</td>
<td>None</td>
<td>-</td>
</tr>
<tr>
<td>65.A</td>
<td>X453.5</td>
<td>65.B</td>
<td>X454.5</td>
<td>Controller enable drive-specific</td>
<td>I</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Level (incl. ripple)</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>High level: 15 V to 30 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Low signal level: -3 V to 5 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Electrical isolation: Ref. is T. 19/T. M24</td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>X453.6</td>
<td>9</td>
<td>X454.6</td>
<td>Enable voltage (+24 V)</td>
<td>S</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Maximum current (for the total group): 500 mA</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Note: The enable voltage (terminal 9) can be used to supply the enable signals (e.g. controller enable).</td>
<td></td>
</tr>
<tr>
<td>I0.A</td>
<td>X453.7</td>
<td>I0.B</td>
<td>X454.7</td>
<td>Digital input 0²)</td>
<td>DI</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Fast input ³)</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Typ. current consumption: 6 mA at 24 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Level (incl. ripple)</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>High level: 15 V to 30 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Low signal level: -3 V to 5 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Electrical isolation: Ref. is T. 19/T. M24</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Note:</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• The parameterization of the input terminals and the standard assignment is described in Chapter 6.4.2.</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• An open-circuit input is interpreted as 0 signal.</td>
<td></td>
</tr>
<tr>
<td>I1.A</td>
<td>X453.8</td>
<td>I1.B</td>
<td>X454.8</td>
<td>Digital input 1³)</td>
<td>DI</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Fast input ³)</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Typ. current consumption: 6 mA at 24 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Level (incl. ripple)</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>High level: 15 V to 30 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Low signal level: -3 V to 5 V</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Electrical isolation: Ref. is T. 19/T. M24</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Note:</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• The parameterization of the input terminals and the standard assignment is described in Chapter 6.4.2.</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• An open-circuit input is interpreted as 0 signal.</td>
<td></td>
</tr>
</tbody>
</table>

1) I: Input; S: Supply; DI: Digital input
2) Can be freely parameterized
3) All of the digital inputs are de-bounced per software. For the signal detection, this results in a delay time of between 1 and 2 interpolation clock cycles (P1010).
4) I0.x is internally hard-wired to the position sensing function where it acts almost instantaneously.
Table 1-6  Overview of the drive-specific terminals, continued

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Drive A</th>
<th>Drive B</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>No.</td>
<td>Desig-</td>
<td>No.</td>
<td>Desig-</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>nation</td>
<td></td>
<td>nation</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
| O0.A     | X453.9   | O0.B     | X454.9       | DO    | Rated current per output: 500 mA
|          |          |          |              |       | Max. current per output: 600 mA
|          |          |          |              |       | Voltage drop, typical: 250 mV at 500 mA
|          |          |          |              |       | Short-circuit proof      |
|          |          |          |              |       | Parameterization of the output terminals as well as the standard assignment is described in Chapter 6.4.5. |
| O1.A     | X453.10  | O1.B     | X454.10      | DO    | Rated current per output: 500 mA
|          |          |          |              |       | Max. current per output: 600 mA
|          |          |          |              |       | Voltage drop, typical: 250 mV at 500 mA
|          |          |          |              |       | Short-circuit proof      |
|          |          |          |              |       | Parameterization of the output terminals as well as the standard assignment is described in Chapter 6.4.5. |

Note:
- The power switched via these outputs is supplied via terminals P24/M24 (X431). This must be taken into account when dimensioning the external supply.
- The digital outputs only "function" if an external power supply is available (+24 V, T. P24/M24).

1) DO: Digital output
2) Can be freely parameterized

The digital outputs are updated in the interpolation clock cycle (P1010). This is supplemented by a hardware-related delay time of approx. 200 µs.
### Encoder interface for TTL encoders (X472)

Table 1-7  Encoder interface for TTL encoders (X472)

<table>
<thead>
<tr>
<th>No.</th>
<th>Pin Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>P_Encoder</td>
<td></td>
<td>S</td>
<td>• Recommended for TTL encoders:</td>
</tr>
<tr>
<td>2</td>
<td>M_Encoder</td>
<td></td>
<td>S</td>
<td>Order No. (MLFB): 6FX2001-2□B02</td>
</tr>
<tr>
<td>3</td>
<td>A</td>
<td></td>
<td>I</td>
<td>Encoder pulse number = 1024</td>
</tr>
<tr>
<td>4</td>
<td>*A</td>
<td>Possibility of connecting a power supply for an additional measuring system (TTL encoders, encoder 3)</td>
<td>I</td>
<td>□ = Space retainer for conn. types A, C, E or G</td>
</tr>
<tr>
<td>5</td>
<td>Reserved</td>
<td></td>
<td>-</td>
<td>• Cabling</td>
</tr>
<tr>
<td>6</td>
<td>B</td>
<td></td>
<td>I</td>
<td>- Max. cable length: 15 m</td>
</tr>
<tr>
<td>7</td>
<td>*B</td>
<td></td>
<td>I</td>
<td>- Recommended encoder cable:</td>
</tr>
<tr>
<td>8</td>
<td>Reserved</td>
<td>The information is transferred to a higher-level control via PROFIBUS. See Chapter 5.6.4</td>
<td>-</td>
<td>Order No. (MLFB): 6FX2002-2CA11-1□□0</td>
</tr>
<tr>
<td>9</td>
<td>P_Encoder</td>
<td></td>
<td>S</td>
<td>□ = Space retainer for cable type (length, ...)</td>
</tr>
<tr>
<td>10</td>
<td>R</td>
<td></td>
<td>I</td>
<td>Reference:</td>
</tr>
<tr>
<td>11</td>
<td>M_Encoder</td>
<td></td>
<td>S</td>
<td><a href="#">Z/ Catalog NC Z, Accessories and Equipment</a></td>
</tr>
<tr>
<td>12</td>
<td>*R</td>
<td></td>
<td>I</td>
<td>• Encoder power supply</td>
</tr>
<tr>
<td>13</td>
<td>Reserved</td>
<td></td>
<td>-</td>
<td>- Voltage: 5.1 V ± 2%</td>
</tr>
<tr>
<td>14</td>
<td>Reserved</td>
<td></td>
<td>-</td>
<td>- Short-circuit proof</td>
</tr>
<tr>
<td>15</td>
<td>Reserved</td>
<td></td>
<td>-</td>
<td>- Max. current: 300 mA</td>
</tr>
</tbody>
</table>

1) I: Input; S: Supply

---

1.4 "SIMODRIVE 611 universal E" control board

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SIMODRIVE 611 universal Function Manual (FBU) - 05/2010 Edition
1.4 "SIMODRIVE 611 universal E" control board

Button for

**POWER ON-RESET,** button

The button is recessed into the front panel (hole: \( \varnothing 3 \) mm). The processor runs up again when pressed.

**FAULT, LED red**

When the pushbutton is pressed, an LED which may have been previously bright (lit), goes dark, i.e. this indicates the pushbutton was completely actuated (the pushbutton pressure point has been reached).

---

**Warning**

When the POWER-ON RESET button is pressed, this corresponds to a POWER ON and should only be executed when the motors are at a standstill.

In order to prevent the drive from undesirably starting after POWER ON, before carrying out a POWER ON-RESET, the controller enable must be withdrawn at terminals 65.A and 65.B.

---

**Display and operator unit**

The 6-character 7-segment display with point is used to display and change parameter values and to display alarms.

The operator control PLUS, P and MINUS keys are used to select and change parameter values and/or for operator control when faults and warnings are displayed (e.g. to acknowledge these).

---

**Reader’s note**

Handling the display and operator unit

- To parameterize the drive, refer to Chapter 3.2
- To remove faults and warnings, refer to Chapter 7.2.1
1.4.4 Commissioning the board with "SimoCom U"

Requirements

The following prerequisites must be fulfilled in order to be able to commission a drive using the "SimoCom U" parameterizing and start-up tool:

1. All of the prerequisites for commissioning are fulfilled, according to Chapter 4.1 this means that the system with "SIMODRIVE 611 universal E" can be commissioned.
2. The checklist for commissioning according to Chapter 4.1 has been checked.
3. The optional PROFIBUS-DP3 module is inserted into the control board (refer to Chapter 1.3.3).
4. The "SimoCom U" tool is installed on the PC/PG, which is to be used to commission the drive.
5. There is a connecting cable between the PG/PC and control board (RS232 connecting cable, refer to Chapter 2.5).
6. The PC/PG with "SimoCom U" is connected to the control board (X471).

Reader’s note

- Cable diagrams for the connecting cable refer to Chapter 2.5
- Everything about "SimoCom U" refer to Chapter 3.3
Procedure when commissioning the drive for the first time

Please proceed as follows when commissioning "SIMODRIVE 611 universal E" using the "SimoCom U" parameterizing and start-up tool for the first time:

1. Power-up the drive group
2. Start SimoCom U
3. Request online operation for drive A
   Operator action:
   Execute the "Search for online drives" function in the "Start-up" menu, and select drive A in the "Drive and dialog browser".
   Is the "start-up required" window displayed?
   - Yes: --> Start the drive configuration assistant
     --> This means you signal the drive the existing configuration (PROFIBUS node address, power module, motor, etc.).
   - No: --> Press "re-configure drive" button
     --> This means that you change the configuration on the control board (PROFIBUS node address, power module, motor, etc.).
4. Execute the drive configuration, and at the end, press the "Calculate controller data, save, reset" button.

Note
If drive B is to be commissioned, then the points must be executed for drive B from point 3 onwards.
### 1.4.5 What are the differences with respect to "SIMODRIVE 611 universal"?

Table 1-8 Differences with respect to "SIMODRIVE 611 universal"

<table>
<thead>
<tr>
<th>Difference</th>
<th>SIMODRIVE 611 universal</th>
<th>611 universal E</th>
<th>This should be observed for SIMODRIVE 611 universal E</th>
</tr>
</thead>
<tbody>
<tr>
<td>The informa-</td>
<td>The following chapter is of no significance:</td>
<td>Reader’s note:</td>
<td></td>
</tr>
<tr>
<td>tion in this doc-</td>
<td>• Chapter 1.4</td>
<td>Before the 10.99 Edition (SW 3.1) the following was valid:</td>
<td></td>
</tr>
<tr>
<td>ument</td>
<td></td>
<td>This documentation only contains information for &quot;SIMODRIVE 611 universal&quot;.</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>From the 10.99 Edition (SW 3.1) the following is valid:</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>This documentation contains information for &quot;SIMODRIVE 611 universal&quot; and &quot;SIMODRIVE 611 universal E&quot;.</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>The information for &quot;SIMODRIVE 611 universal E&quot; is provided in this Chapter.</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>The following abbreviations have been introduced to identify the information for both modules in the other chapters:</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>Board Abbreviation (only for this purpose)</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• SIMODRIVE 611 universal 611u</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• SIMODRIVE 611 universal E 611ue</td>
<td></td>
</tr>
<tr>
<td>The following applies for users of &quot;SIMODRIVE 611 universal E&quot;:</td>
<td>The following applies for users of &quot;SIMODRIVE 611 universal E&quot;:</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The Chapter and pages are coded for the reader as follows in the header line below the edition:</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Designation</td>
<td>Significance</td>
<td></td>
</tr>
<tr>
<td></td>
<td>none</td>
<td>Information is valid for 611u and 611ue</td>
<td></td>
</tr>
<tr>
<td></td>
<td>! not 611u !</td>
<td>Information is not valid for 611u</td>
<td></td>
</tr>
<tr>
<td></td>
<td>! not 611ue !</td>
<td>Information is not valid for 611ue</td>
<td></td>
</tr>
<tr>
<td></td>
<td>! 611ue diff !</td>
<td>Information differs between 611u and 611ue. In addition, this list of differences must be carefully observed.</td>
<td></td>
</tr>
<tr>
<td>Operating mode</td>
<td>• Speed/torque set-point</td>
<td>• Speed/torque set-point</td>
<td>• Permissible settings are:</td>
</tr>
<tr>
<td></td>
<td>• Positioning</td>
<td>• No</td>
<td>- P0700 = 0 (the drive is inactive, only drive B)</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Thus, a double-axis module can only be operated as single-axis module.</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Should communications be established with inactive drive B via PROFIBUS?</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>If yes, then communications must be disabled with P0875 = 0.</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>- P0700 = 1 (operating mode &quot;speed/torque setpoint&quot;)</td>
</tr>
<tr>
<td>Memory module</td>
<td>... for n-set</td>
<td>... for n-set</td>
<td>P0700 = 3 is not permissible</td>
</tr>
<tr>
<td></td>
<td>... for pos</td>
<td></td>
<td>The rear of the memory module is identified as follows:</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• URL.-SOFTWARE N_SOLL-611U (before SW 4.2)</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• SYS.-SOFTWARE N_SOLL-611U (from SW 4.2)</td>
</tr>
</tbody>
</table>
Table 1-8 Differences with respect to "SIMODRIVE 611 universal", continued

<table>
<thead>
<tr>
<th>Difference</th>
<th>SIMODRIVE 611 universal</th>
<th>SIMODRIVE 611 universal E</th>
<th>This should be observed for SIMODRIVE 611 universal E</th>
</tr>
</thead>
<tbody>
<tr>
<td>Software release</td>
<td>- SW 1.1</td>
<td>- No</td>
<td>Software release 3.1 is the first software release which is used for both modules.</td>
</tr>
<tr>
<td></td>
<td>- SW 2.1</td>
<td>- No</td>
<td>The following applies for &quot;SIMODRIVE 611 universal E&quot;:</td>
</tr>
<tr>
<td></td>
<td>- SW 2.4</td>
<td>- No</td>
<td>Software from SW 3.1 onwards must be used.</td>
</tr>
<tr>
<td></td>
<td>- SW 3.x</td>
<td>- SW 3.x</td>
<td>Note:</td>
</tr>
<tr>
<td></td>
<td>- SW 4.1</td>
<td>- SW 4.1</td>
<td>The SW version installed and supplied with the &quot;SIMODRIVE 611 universal E&quot; control board is that which has been approved for combination with SINUMERIK 802D!</td>
</tr>
<tr>
<td></td>
<td>- SW 5.x</td>
<td>- SW 5.x</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 6.x</td>
<td>- SW 6.x</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 7.x</td>
<td>- SW 7.x</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 8.x</td>
<td>- SW 8.x</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 9.x</td>
<td>- SW 8.3</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 10.x</td>
<td>- SW 8.3</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 11.x</td>
<td>- SW 8.3</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 12.x</td>
<td>- SW 8.3</td>
<td></td>
</tr>
<tr>
<td></td>
<td>- SW 13.x</td>
<td>- SW 8.3</td>
<td></td>
</tr>
<tr>
<td>Module type</td>
<td>The module is identified using P0870 (module type)</td>
<td>P0870 = 0004\textsubscript{hex}</td>
<td>-\rightarrow it involves a &quot;SIMODRIVE 611 universal E&quot; control board, 2-axes for encoders with sin/cos 1 Vpp</td>
</tr>
<tr>
<td>Analog inputs</td>
<td>- Term. 56.x/14.x</td>
<td>- No</td>
<td>The information in Chapter 6.6 is of no significance.</td>
</tr>
<tr>
<td></td>
<td>- Term. 24.x/20.x</td>
<td>- No</td>
<td></td>
</tr>
<tr>
<td>Digital inputs</td>
<td>- Term. I0.x</td>
<td>- Term. I0.x</td>
<td>Effective parameters are:</td>
</tr>
<tr>
<td></td>
<td>- Term. I1.x</td>
<td>- Term. I1.x</td>
<td>- P0660 (function, input terminal I0.x)</td>
</tr>
<tr>
<td></td>
<td>- Term. I2.x</td>
<td>- No</td>
<td>- P0661 (function, input terminal I1.x)</td>
</tr>
<tr>
<td></td>
<td>- Term. I3.x</td>
<td>- No</td>
<td>P0662 and P0663 are ineffective</td>
</tr>
<tr>
<td>Digital outputs</td>
<td>- Term. O0.x</td>
<td>- Term. O0.x</td>
<td>Effective parameters are:</td>
</tr>
<tr>
<td></td>
<td>- Term. O1.x</td>
<td>- Term. O1.x</td>
<td>- P0680 (signal function, output terminal O0.x)</td>
</tr>
<tr>
<td></td>
<td>- Term. O2.x</td>
<td>- No</td>
<td>- P0681 (signal function, output terminal O1.x)</td>
</tr>
<tr>
<td></td>
<td>- Term. O3.x</td>
<td>- No</td>
<td>P0682 and P0683 are ineffective</td>
</tr>
<tr>
<td>Optional TERMINAL module</td>
<td>Yes, can be used</td>
<td>No, cannot be used</td>
<td>P0664 to P0671 (function, input terminal I4 to I11) And</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>P0684 to P0691 (signaling function, output terminal O4 to O11) are of no significance</td>
</tr>
<tr>
<td>Optional PROFIBUS module</td>
<td>- PROFIBUS-DP1</td>
<td>- No</td>
<td>P0872 = 4</td>
</tr>
<tr>
<td></td>
<td>- PROFIBUS-DP2</td>
<td>- No</td>
<td>-\rightarrow The following option module was detected:</td>
</tr>
<tr>
<td></td>
<td>- PROFIBUS-DP3</td>
<td>- PROFIBUS DP3</td>
<td>Optional PROFIBUS-DP3 module (from SW 3.1) with PROFIBUS-ASIC DPC31 with PLL</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Order No. (MLFB): 6SN1114-0NB01-0AA0 or SN1114-0NB01-0AA1</td>
</tr>
</tbody>
</table>
Table 1-8 Differences with respect to “SIMODRIVE 611 universal”, continued

<table>
<thead>
<tr>
<th>Difference</th>
<th>SIMODRIVE 611 universal</th>
<th>SIMODRIVE 611 universal E</th>
<th>This should be observed for SIMODRIVE 611 universal E</th>
</tr>
</thead>
<tbody>
<tr>
<td>Serial interface</td>
<td>• RS232</td>
<td>• RS232</td>
<td>• Permissible settings</td>
</tr>
<tr>
<td></td>
<td>• RS485 (independent</td>
<td></td>
<td>- P0801 = 0 (RS232 interface, standard)</td>
</tr>
<tr>
<td></td>
<td>of the hardware)</td>
<td></td>
<td>- P0801 = 1 is interpreted just like P0801 = 0</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>P0802 and P0803 are of no significance</td>
</tr>
<tr>
<td>Angular incremental encoder interface</td>
<td>Yes</td>
<td>No</td>
<td>• Permissible settings, drive A</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>- P0890 = 0 Encoder interface, inactive</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>- P0890 = 4 Encoder interface, active</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• Permissible settings, drive B</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>- P0890 = 0 Encoder interface, inactive</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>For all other parameter values, a fault is signaled.</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>The encoder interface is not suitable to connect a</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>direct measuring system for the following reasons:</td>
</tr>
<tr>
<td>Encoder interface (TTL encoder)</td>
<td>No</td>
<td>Yes</td>
<td>• The encoder signals are not evaluated in the drive.</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• The drive transfers the information which is sensed</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>to a higher-level of control using the appropriate</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>process data.</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• The encoder interface is used for the &quot;Motion Control</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>with PROFIBUS–DP” function (clock cycle synchronous</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>operation, e.g. together with SINUMERIK 802D).</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• &quot;Motion Control with PROFIBUS” function</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>----&gt; refer to Chapter 5.8</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• Configuring telegrams ----&gt; refer to Chapter 5.6.5</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>• Encoder interface ----&gt; refer to Chapter 5.6.4</td>
</tr>
<tr>
<td>Encoder interface (process data)</td>
<td>• Sensor 1</td>
<td>• Sensor 1</td>
<td>Encoder 1 Motor measuring system (X411, X412)</td>
</tr>
<tr>
<td></td>
<td>• Encoder 2 (from SW 3.3)</td>
<td>• Encoder 2 (from SW 3.3)</td>
<td>Encoder 2 Direct measuring system (X412)</td>
</tr>
<tr>
<td></td>
<td>• No</td>
<td>• Sensor 3</td>
<td>Encoder 3 TTL encoder (X472)</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>Description of the process data ----&gt; refer to Chap. 5.6.4</td>
</tr>
<tr>
<td>Traversing to fixed stop</td>
<td>Yes from SW 3.3</td>
<td>No</td>
<td>This function is programmed using the FIXED STOP</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>command in the &quot;Positioning” mode. The operating mode</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>is not possible for SIMODRIVE 611 universal E ----&gt;</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>function not available</td>
</tr>
<tr>
<td>Axis couplings</td>
<td>Yes from SW 3.3</td>
<td>No</td>
<td>This function can be used in either the &quot;External position</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>reference value” mode or &quot;Positioning”. Operating</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>modes are not possible for SIMODRIVE 611 universal E</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>----&gt; function is not available</td>
</tr>
</tbody>
</table>
Space for your notes
## Installing and Connecting-Up

<table>
<thead>
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<th>Section</th>
<th>Page</th>
</tr>
</thead>
<tbody>
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<tr>
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<td>2-62</td>
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<td>2.1.4 Replacing a defective HR control board by a new one</td>
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</tr>
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<td>2-67</td>
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</tr>
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<td>2-73</td>
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<tr>
<td>2.2.3 Connecting-up the power module</td>
<td>2-74</td>
</tr>
<tr>
<td>2.3 Connection diagram and wiring</td>
<td>2-75</td>
</tr>
<tr>
<td>2.3.1 Connection diagram for the &quot;SIMODRIVE 611 universal&quot; board</td>
<td>2-75</td>
</tr>
<tr>
<td>2.3.2 Connecting-up the control board</td>
<td>2-76</td>
</tr>
<tr>
<td>2.3.3 Connection diagram, connecting-up the optional TERMINAL module</td>
<td>2-82</td>
</tr>
<tr>
<td>2.3.4 Connection diagram, connecting-up the optional PROFIBUS-DP module</td>
<td>2-84</td>
</tr>
<tr>
<td>2.4 Pin assignment of the interfaces</td>
<td>2-86</td>
</tr>
<tr>
<td>2.5 Cable diagrams</td>
<td>2-89</td>
</tr>
</tbody>
</table>
2.1 Installing/removing control boards and modules

Warning
It is only permissible to install/remove a control board or an option module when the system is in a no-voltage condition (powered down). If boards or option modules are inserted or withdrawn under voltage, this can result in data loss or destruction of components.

Note
The screws retaining electrical connections at the modules must be tightened with the following torque:

<table>
<thead>
<tr>
<th>Screw size</th>
<th>→→</th>
<th>Tightening torque</th>
</tr>
</thead>
<tbody>
<tr>
<td>M3</td>
<td>→→</td>
<td>0.5 Nm (for electrical connections)</td>
</tr>
<tr>
<td>M3</td>
<td>→→</td>
<td>0.8 Nm (for mechanical connections)</td>
</tr>
<tr>
<td>M4</td>
<td>→→</td>
<td>1.8 Nm</td>
</tr>
<tr>
<td>M5</td>
<td>→→</td>
<td>3.0 Nm</td>
</tr>
<tr>
<td>Tolerance</td>
<td>→→</td>
<td>0/+30 %</td>
</tr>
</tbody>
</table>

After transport, the screws should be tightened!

2.1.1 Installing the control board

The following points must be observed when installing the "SIMODRIVE 611 universal" control board into the power module (refer to Fig. 2-1):

Warning
The ESDS measures must be observed when installing/removing the control board.

1. Ensure that the power module is in a no-voltage condition.
2. Check that the memory module is inserted and locked into place in the control board.
   If it is not inserted, then refer to the point "installing/removing the memory module".
3. Insert the control board in the power module.
4. Tighten up the screws retaining the board
   (2 screws on the front panel, max. torque= 0.8 Nm).
5. Connect-up the front panel of the board corresponding to the connection diagram (refer to Chapter 2.3.1).
   The mating connectors are inserted at the appropriate interface.
2.1.2 Installing/removing an option module

An option module is installed/removed from the control board as follows (refer to Fig. 2-1):

Warning
When installing/removing an option module, observe the ESDS measures.

1. Ensure that the control board is in a no-voltage condition.
2. Removing (changing):
   Release the screws at the slot and withdraw the option module from the "old" control board.
   Installing:
   Remove the screws for the cover at the slot for the option module.
3. Insert the module through the front panel until it latches into place.
4. Tighten up the screws holding the module
   (2 screws in the front panel, max. torque = 0.8 Nm).
5. Connect–up the front panel of the option module corresponding to the connection diagram (refer to Chapter 2.3.3).
   The mating connectors are inserted at the appropriate interface.

Fig. 2-1 Installing the control board and an option module

Note
The PROFIBUS firmware, associated with the 611u firmware must be available on the PROFIBUS-DP option module. Otherwise the firmware must be upgraded. PROFIBUS-DP1 option modules from SW 4.1 - and also in this particular case - can no longer be used.
2.1.3 Installing/removing the memory module

General

The memory module can be replaced, and when supplied from the factory, a new control board is already installed.

When replacing the control board (service) with an identical one, a functioning memory module can be taken from the old control board and inserted in the new control board. This means that the system software can be transferred over with the user files without requiring any other resources.

When replacing with a type HR or HRS control board, Chapter 2.1.4 or 2.1.5 or the mounting instructions provided with the spare part must be carefully observed.

There are memory modules for n-set or positioning.

This is labeled at the rear of the memory module:

- Designation can be inserted in control board before SW 4.2
- URL.--SOFTWARE POS.--611U for positioning (refer to Chap. 1.3)
- URL.--SOFTWARE N_SOLL--611U for n-set (refer to Chapter 1.3)
- SYS.--SOFTWARE POS.--611U for positioning (refer to Chap. 1.3)
- SYS.--SOFTWARE N_SOLL--611U for n-set (refer to Chapter 1.3)

The software designation refers to the system software including the initial program loader.

A memory module is inserted/replaced as follows:

**Warning**

The ESDS measures must be observed when installing/removing the memory module.

1. Place the old and new control boards on an ESDS-compatible surface (to the left of the front panel).
2. Press the memory module latches downwards and outwards until they release (refer to Fig. 2-2).
3. Remove the memory from its connections (upwards).
4. Insert the old memory module into the new control board and the new memory module into the old control board. The latches must automatically engage.
5. Check that the latches are correctly engaged.
2.1 Installing/removing control boards and modules

Referencing

If a motor with absolute value encoder is mounted to the drive, then if the firmware release was < 9.1, and a *.par file was downloaded into the memory module, then the drive must always be re-reference (re-homed), even if the drive already appears as if it has been referenced (homed).

If the referencing (homing) of the axis is completed and takes a lot of time, then it is possible to save the reference point (home position). A description on this is provided in the product support in the Internet under FAQs ID21821692.
2.1.4 Replacing a defective HR control board by a new one

**General**

From delivery date 04.2002 onwards, there will be a new "SIMODRIVE 611 universal HR" or "SIMODRIVE 611 universal E HR" control board with a higher encoder resolution (refer to Chapter 1.3 or 1.4). This new hardware simultaneously replaces the previous types and is coupled to the new software \( \geq SW \ 5.1 \).

A control board is installed/removed as follows:

1. Ensure that the power module is in a no-voltage condition.
2. Release the screw connection and withdraw the "old" control board from the power module.
3. Remove the memory module from the defective ("old") and insert this into the "new" control board, refer to Chapter 2.1.3 "Installing/removing a memory module".
4. Insert the "new" control board and connect-up the equipment bus.

---

**Fig. 2-3** Replacing a defective HR control board by a new one
2.1 Installing/removing control boards and modules

5. Install the "SimoCom U" start-up tool with version 5.1 (or higher) or, when using an "older" version, observe the following information:
   - Exit SimoCom U.
   - Make a back-up copy of the test file "C:\siemens\lists\control.txt" in the main SimoCom U directory (generally under "C:\Program Files\Siemens\SimoComU").
   - Then open this file with Microsoft Wordpad (not with a text editor!).
   - Search for the following line under the Section "611U" or the last line of this section:
     - 6SN1118-1NJ00-0AAx 259 0x00000000 1 1 2 1 ;611U resolver 1-axis X_SOLL
   - Insert the following lines directly below:
     - 6SN1118-0NH01-0AA0 5 0x00000000 2 2 1 7 ;611U encoder HR 2-axis N_SOLL
     - 6SN1118-0NK01-0AA0 7 0x00000000 1 2 1 8 ;611U resolver HR 2-axis N_SOLL
     - 6SN1118-0NJ01-0AA0 8 0x00000000 1 1 1 8 ;611U resolver HR 1-axis N_SOLL
     - 6SN1118-1NH01-0AA0 261 0x00000000 2 2 2 7 ;611U encoder HR 2-axis X_SOLL
     - 6SN1118-1NK01-0AA0 263 0x00000000 1 2 2 8 ;611U resolver HR 2-axis X_SOLL
     - 6SN1118-1NJ01-0AA0 264 0x00000000 1 1 2 8 ;611U resolver HR 1-axis X_SOLL
   - As last line, insert under the Section "611UE":
     - 6SN1118-0NH11-0AA0 9 0x00000000 2 2 1 9 ;611UE encoder HR 2-axis N_SOLL
   - Save the "control.txt" file.
   - Restart SimoCom U and continue with Point 6.

6. Save your machine data from the "old" memory module (File: "*.par") using the "SimoCom U" start-up tool.

7. Again remove the "new" control board and replace the "old" memory module by the "new" memory module. Software release \( \geq \) SW 5.1 is already installed on the "new" memory module.

8. Insert the "new" control board back into the power module and tighten the retaining screws (2 screws at the front panel, torque = 0.8 Nm).
9. Re-connect the front panel of the module corresponding to the con-
nection diagram.
   Insert the mating connector at the appropriate interface.

**Notice**

For "SIMODRIVE 611 universal", connectors X461 and X462
have been extended to an 11-pole version. This means that the signal
conductors connected to this terminal block must be
re-connected to the new (11-pole) terminal block (terminal block
assignment, refer to Fig. 1-5).

10. Download your machine data, saved under 6., into the "new" control
    board using the "SimoCom U" start-up tool.

**Warning**

It is only permissible to install/remove a control board when the system
is in a no-voltage condition (i.e. powered-down).

If a control board is inserted or removed under voltage (with the
system powered-up), this can result in data being lost or components
being destroyed.

The ESDS measures must be observed when installing/removing the
control board.

**Note**

For spare control boards, a set of installation instructions are provided
which describes how the control board is replaced.
2.1.5 Replacing a defective HRS control board by a new one

General
From 10.2005 onwards, there will be a new "SIMODRIVE 611 universal HRS" or "SIMODRIVE 611 universal E HRS" control board with a higher computational performance (refer to Chapter 1.3 or 1.4). This new hardware simultaneously replaces the previous types and is coupled to the new software ≥ SW 8.3.

![Diagram showing replacement process](image)

**Fig. 2-4** Replacing a defective HRS control board by a new one
2 Installing and Connecting-Up

2.1 Installing/removing control boards and modules

How is a control board replaced?

A control board is installed/removed as follows:

1. The user data should be in a file that has been backed-up. This is because the "old" memory module does not always run in the new control board.

2. Ensure that the power module is in a no-voltage condition.

3. Release the screw connection and withdraw the "old" control board from the power module.

4. Remove the memory module from the defective ("old") and insert this into the "new" control board, refer to Chapter 2.1.3 "Installing/removing a memory module".

5. Insert the "new" control board, tighten the retaining screws (2 screws at the front panel, max. torque = 0.8 Nm) and connect the equipment bus.

6. Switch on the drive. If the drive system successfully boots, then the operation to replace the board has been completed and you can continue with Point 11. Otherwise, carry-out the following steps 7. to 10.

7. Install the "SimoCom U" start-up tool, Version 8.3 (or higher).

8. Power-down/power-up the drive again and start the "SimoCom U" commissioning tool.

9. Comply with the request in "SimoCom U" "necessary to upgrade the firmware" by installing firmware version 8.3 (or higher).

10. If communications are not established or the system does not boot after it has been upgraded, then the old memory module is either defective, and cannot be used and must be replaced by the memory module of the new control board. The appropriate user data should be downloaded from the archived file.

For a control board with motors with absolute value encoders and a firmware release <9.1, the axes must be re-referenced, even if they already appear to have been referenced. If referencing the axis is complicated and time consuming, then there is a possibility of saving the reference points. A description on this is provided in Product Support in the Internet under FAQs ID21821692.

11. Re-connect the front panel of the module corresponding to the connection diagram. Insert the mating connector at the appropriate interface.

Notice

Plug connectors X461 and X462 have been extended, for "HR and "HRS", to an 11-pin version. This means that the assigned signal conductors of the (10-pin) terminal block of the SIMODRIVE 611 universal must be re-connected to the new (11-pin) terminal block. (terminal block assignment, refer to Fig. 1-5).
Warning
It is only permissible to install/remove a control board when the system is in a no-voltage condition (i.e. powered-down).

If a control board is inserted or removed under voltage (with the system powered-up), this can result in data being lost or components being destroyed.

The ESDS measures must be observed when installing/removing the control board.

Note
For spare control boards, a set of installation instructions are provided which describes how the control board is replaced.
2.2 Wiring

2.2.1 General information on connecting-up

Reader’s note
Information on the subjects
- Cabinet design
- Basic rules regarding electromagnetic compatibility (basic EMC rules)
- Equipotential bonding
- Wiring and cabling
- EMC-compliant wiring
- Shielding and shield connections
- Handling modules that can be damaged by electrostatic discharge (ESDS measures), etc.

are included in

Warning
Cable shields and cores/conductors of power cables which are not used (e.g. brake conductors) must be connected to PE potential in order to discharge charges arising from capacitive coupling.

Non-observance can cause lethal shock voltages.
Mini connector MICRO-COMBICON

For the “SIMODRIVE 611 universal” control board, a compact connector is used (this is also known as mini connector).
The following information is required when handling this mini connector:

- **Introducing conductors (refer to Fig.2-5):**
  - for solid conductors with 0.2 – 0.5 mm² or stranded conductors with end sleeve
    
    The conductors can be introduced without having to use a tool.
    
    Procedure: Insert the conductor into the required terminal.
  
  - for solid conductors < 0.2 mm² or stranded conductors without end sleeve
    
    The lever-type opener must be pressed in order to introduce the conductor (e.g. using a screwdriver 0.4 • 2.0 • 20 mm).
    
    Procedure: Depress the lever-type opener below to the particular terminal. Insert the conductor into the opening provided and then release the lever-type opener.

- **Coding (refer to Fig. 2-5):**
  
  The connectors with the same number of pins should be coded so that the incorrect connector cannot be inserted. A star with 6 individual coding profile is supplied with each control board.
  
  Procedure: Insert the coding element into the required coding groove on the base housing. Now break-off the appropriate coding lug at the connector section (e.g. coding groove/lug 2).

<table>
<thead>
<tr>
<th>Test sockets</th>
<th>Connector part</th>
<th>Coding grooves</th>
</tr>
</thead>
<tbody>
<tr>
<td>To measure the voltage at a terminal, a measuring probe with max. Ø 1 mm diameter can be inserted in this socket.</td>
<td><strong>Base housing</strong></td>
<td>The coding elements are inserted here (red insulating material)</td>
</tr>
<tr>
<td><strong>Marking</strong></td>
<td>The self-adhesive labeling strips can then be attached.</td>
<td><strong>Coding lugs</strong></td>
</tr>
<tr>
<td><strong>Introducing the conductor (max. 0.5 mm²)</strong></td>
<td></td>
<td><strong>Introducing the conductor (max. 0.5 mm²)</strong></td>
</tr>
<tr>
<td>• Stranded conductor</td>
<td></td>
<td>• Stranded conductor or</td>
</tr>
<tr>
<td>• solid conductor</td>
<td></td>
<td>• solid conductor</td>
</tr>
</tbody>
</table>

**Lever-type opener**
The terminal contact to introduce the conductor or to release a conductor is opened using this element.

<table>
<thead>
<tr>
<th>pressed</th>
<th>not pressed</th>
</tr>
</thead>
<tbody>
<tr>
<td>--&gt; terminal contact opened</td>
<td>--&gt; terminal contact closed</td>
</tr>
</tbody>
</table>

**Fig. 2-5 Compact connector (Mini connector)**
The following cables are recommended when connecting-up the most important terminals on the control board:

Table 2-1  Recommended cable

<table>
<thead>
<tr>
<th>Cable for</th>
<th>Description</th>
<th>Order No. (MLFB)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Analog inputs</strong></td>
<td>Term. 56.A/14.A cond. 2 • 2 • 0.38 mm²</td>
<td>6FX2008-1BD21-VVVV</td>
</tr>
<tr>
<td></td>
<td>Term. 24.A/20.A cond. 2 • 2 • 0.38 mm²</td>
<td>Cable, sold by the meter, twisted pairs</td>
</tr>
<tr>
<td></td>
<td>Note: 4-conductor connection, e.g. at drive A</td>
<td>with overall shield</td>
</tr>
<tr>
<td></td>
<td>Term. 75.A/15 conductor 2 • 0.5 mm²</td>
<td>Conductors: 4 • 2 • 0.38 mm² +</td>
</tr>
<tr>
<td></td>
<td>Term. 16.A/15 conductor 2 • 0.5 mm²</td>
<td>4 • 0.5 mm²</td>
</tr>
<tr>
<td><strong>Analog outputs</strong></td>
<td>Term. A+.A cond. 1 • 0.38 mm²</td>
<td>6FX2008-1BD21-VVVV</td>
</tr>
<tr>
<td></td>
<td>Term. A-.A cond. 1 • 0.38 mm²</td>
<td>Cable, sold by the meter, twisted pairs</td>
</tr>
<tr>
<td></td>
<td>Term. B+.A cond. 1 • 0.38 mm²</td>
<td>with overall shield</td>
</tr>
<tr>
<td></td>
<td>Term. B-.A cond. 1 • 0.38 mm²</td>
<td>Conductors: 4 • 2 • 0.38 mm² +</td>
</tr>
<tr>
<td></td>
<td>Term. R+.A cond. 1 • 0.38 mm²</td>
<td>4 • 0.5 mm²</td>
</tr>
<tr>
<td></td>
<td>Term. R-.A cond. 1 • 0.38 mm²</td>
<td>Condition to maintain the burst strength:</td>
</tr>
<tr>
<td></td>
<td>T. 15 (from SW 5.1) cond. 1 • 0.38 mm²</td>
<td>Cable length &lt; 30 m</td>
</tr>
<tr>
<td></td>
<td>Remaining: Conductor 1 • 0.38 mm² + 4 • 0.5 mm²</td>
<td></td>
</tr>
<tr>
<td><strong>Input/ output terminals</strong></td>
<td>Term. I0.x to term. I3.x</td>
<td>50-conductor cable without overall shield</td>
</tr>
<tr>
<td></td>
<td>Term. O0.x to term. O3.x</td>
<td>Conductors: 50 • 0.38 mm²</td>
</tr>
<tr>
<td></td>
<td>Term. I4 to term. I11</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Term. O4 to term. O11</td>
<td></td>
</tr>
</tbody>
</table>

**Shield connection to the side of the power module**

To connect the shield to the side of the power module, the cable end must be prepared as illustrated in Fig. 2-6.

With the shield exposed, the cable is connected at the top of the power module using a shield connecting terminal (tapped holes are provided).

![Fig. 2-6 Preparing the cable end for the shield connection](image)
2.2 Wiring

**Note**
- The cable shield should be connected at both cable ends through the largest possible surface area.
- Recommendation for the end of the conductor:
  Remove 5 mm of insulation from the end of the conductor and attach the specified cable lug using the manual crimping tool.
  - Pin-type cable lug from the AMP company
    Type A, yellow, DIN cable cross-section range 0.14 - 0.35 mm², max. insulation diameter 2.1 mm, Order No.: 165514-1
  - Manual crimping tool from AMP
    CERTI-CRIMP, Order No.: 169485-0

### 2.2.2 Connecting-up and setting the line supply infeed module

#### Wiring
Connecting-up the line supply infeed module will not be described in any more detail in this documentation. The following applies:

**Reader’s note**
Information on connecting-up the supply infeed modules, technical data as well as an interface overview are included in:

**Reference:** /PJU/ SIMODRIVE 611, Configuration Manual, Drive Converters Chapter “Line infeed (NE)”

#### Setting switch S1
There is a 6-position switch S1 on the top or front of the line supply infeed module.
The setting of this switch is not described in any more detail in this documentation. The following applies:

**Reader’s note**
Information on setting switch S1 at the line supply infeed module is included in:

**Reference:** /PJU/ SIMODRIVE 611, Configuration Manual, Drive Converters Chapter “Line infeed (NE)”
2.2.3 Connecting-up the power module

Table 2-2 Overview of the interfaces

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>U1 V2 W2</td>
<td>A1</td>
<td>Motor connection for drive A</td>
<td>O</td>
<td>Note: Additional information on connecting-up the power module, technical data as well as interface overview are included in:</td>
</tr>
<tr>
<td>U2 V2 W2</td>
<td>A2</td>
<td>Motor connection for drive B (only for 2-axis power modules)</td>
<td>O</td>
<td>Reference: /PJU/ SIMODRIVE 611 Configuration Manual, Drive Converters Chapter &quot;Power module&quot;</td>
</tr>
<tr>
<td>PE</td>
<td></td>
<td>Protective conductor</td>
<td>I</td>
<td>0 V Bolt</td>
</tr>
<tr>
<td>DC link</td>
<td></td>
<td>DC link</td>
<td>IO</td>
<td>Conductor bar</td>
</tr>
<tr>
<td>Equipment bus</td>
<td>X151</td>
<td>Equipment bus</td>
<td>IO</td>
<td>Ribbon cable: 34-pole</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Voltages: various</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Signals: various</td>
</tr>
</tbody>
</table>

1) O: Output; I: Input; IO: Input/output

**Warning**

If a contactor is used between the motor and the power module, then it must be ensured that this contactor is only switched in a no-current condition (power circuit).

**Switch-off**

When terminal 663 (pulse cancellation) is simultaneously de-energized and the coil of the power contactor, this condition is maintained. The pulses are almost instantaneously canceled, the contactor contacts are then in a no-current condition, and switch somewhat later due to the contact delay.

**Switching on:**
Terminal 663 may only be energized if all of the main contacts of the power contactor are closed (e.g. terminal 663 is switched through an auxiliary contact of the power contactor).
2.3 Connection diagram and wiring

2.3.1 Connection diagram for the "SIMODRIVE 611 universal" board

Fig. 2-7 Connection diagram for the control board
2.3.2 Connecting-up the control board

**Board-specific terminals and interfaces**

The board-specific terminals and interfaces are available, common for both drive A and B.

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>AS1</td>
<td>X421</td>
<td>Signaling contact</td>
<td>NC</td>
<td>Connector type: 2-pin conn. strip</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Start inhibit</td>
<td></td>
<td>Max. cond. cross-sect.: 2.5 mm²</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Feedback signal</td>
<td></td>
<td>Contact: Floating NC contact</td>
</tr>
<tr>
<td></td>
<td></td>
<td>from terminal 663</td>
<td></td>
<td>Contact load capability:</td>
</tr>
<tr>
<td>AS2</td>
<td>AS1</td>
<td>Relay, safe start inhibit</td>
<td>AS2</td>
<td>at 250 VAC max. 1 A²)</td>
</tr>
<tr>
<td></td>
<td>AS2</td>
<td></td>
<td></td>
<td>at 30 VDC max. 2 A</td>
</tr>
</tbody>
</table>

1) NC: Normally closed contact
2) Corresponding to EN 60204-1 (Safety of Machinery), control transformers should be used when using AC control voltages.

Table 2-3 Overview of the board-specific terminals and interfaces
Table 2-3 Overview of the board-specific terminals and interfaces, continued

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>X431</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P24 X431.1</td>
<td>External power supply for digital outputs (+24 V)</td>
<td>S</td>
<td>Max. cond. cross-sect.: 1.5 mm²</td>
</tr>
<tr>
<td>M24 X431.2</td>
<td>Reference for the external supply</td>
<td>S</td>
<td>Voltage tolerance (including ripple): 10 V to 30 V</td>
</tr>
</tbody>
</table>

The external supply is required for the following digital outputs:
- 8 outputs of the drive-specific terminals (X461, O0.A - O3.A/X462, O0.B - O3.B)
- 8 outputs of the optional TERMINAL module (X432, O4 - O11)

When dimensioning the external power supply, the total current of all of the digital outputs must be taken into account.

Maximum total current:
- for the control board (all 8 outputs): 2.4 A
- for the optional TERMINAL module (all 8 outputs): 480 mA

Example:

<table>
<thead>
<tr>
<th>Board/module</th>
<th>Outputs</th>
<th>Dimensioning the external supply</th>
</tr>
</thead>
<tbody>
<tr>
<td>Control board</td>
<td>8</td>
<td>max. 1.5 A</td>
</tr>
<tr>
<td>Control module + optional TERMINAL module</td>
<td>8 + 8</td>
<td>max. (1.5 A + 280 mA)</td>
</tr>
</tbody>
</table>

9 X431.3 Enable voltage (+24 V) S Reference: Terminal 19
Maximum current (for the total group): 500 mA

Note:
The enable voltage (terminal 9) can be used to supply the enable signals (e.g. pulse enable) as 24 V auxiliary voltage.

663 X431.4 Pulse enable (+24 V) I Voltage tolerance (including ripple): 21 V to 30 V
Typ. current consumption: 25 mA at 24 V

Note:
The pulse enable acts simultaneously on drive A and drive B. When this pulse enable is withdrawn, the drives "coast down" unbraked.

19 X431.5 Reference (Reference for all digital inputs) S Note:
If the enable signals are to be controlled from an external voltage and not from terminal 9, then the reference potential (ground) of the external source must be connected to this terminal.

1) I: Input; S: Supply
<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>Serial interface (X471)</td>
<td>X471</td>
<td>Serial interface for &quot;SimoCom U&quot;</td>
<td>IO</td>
<td>Connector type: 9-pin D-sub socket connector</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• Online operation via the serial RS232/RS485 interface --&gt; refer to Chapter 3.3.3</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• Pin assignment of the interface --&gt; refer to Chapter 2.4</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>• Cable diagram --&gt; refer to Chapter 2.5</td>
</tr>
<tr>
<td>Equipment bus (X351)</td>
<td>X351</td>
<td>Equipment bus</td>
<td>IO</td>
<td>Ribbon cable: 34-pin</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Voltages: various</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Signals: various</td>
</tr>
<tr>
<td>Test sockets (X34)</td>
<td>X34</td>
<td>Test socket 1 2)</td>
<td>MA</td>
<td>Test socket: ⊙ 2 mm</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Resolution: 8 bits</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Rated operating voltage: 0 V to 5 V</td>
</tr>
<tr>
<td>DAC2</td>
<td></td>
<td>Test socket 2 2)</td>
<td>MA</td>
<td>Maximum current: 3 mA</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Reference</td>
</tr>
</tbody>
</table>

1) I: Input; S: Supply; IO: Input/output; MA: Measuring signal, analog
2) Can be freely parameterized
The drive-specific terminals are available for both drive A and drive B.

### Table 2-4 Overview of the drive-specific terminals

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Drive A</th>
<th>Drive B</th>
<th>Function</th>
<th>Type</th>
<th>Technical specifications</th>
</tr>
</thead>
</table>
| Encoder connection (X411, X412) | | | | I | Reference:  
/PU/ SIMODRIVE 611, Configuration Manual, Drive Converters  
Chapter “Indirect and direct position sensing”  
Encoder limit frequencies:  
- Enc. with sin/cos 1Vpp: 350 kHz  
- Resolver: 12 Bit 432 Hz  
14 Bit 108 Hz  
- Enc. with TTL signal4): 420 kHz |
| - | X411 | - | Motor encoder connection, drive A | I |  |
| - | - | X412 | Motor encoder connection, drive B or connection, direct measuring system (from SW 3.3) | I |  |
| Analog outputs (X441) | | | | | |
| 75.A | X441.1 | - | Analog output 12) | AO | Connector type: 5-pin conn. strip  
Wiring: refer to3)  
Max. conductor cross-section for finely-stranded or solid cond.: 0.5 mm²  
Rated oper. voltage: -10 V to +10 V  
Maximum current: 3 mA  
Resolution: 8 bits  
Update: In the speed-contr. clock cycle  
Short-circuit proof |
| 16.A | X441.2 | - | Analog output 22) | AO |  |
| - | 75.B | X441.3 | Analog output 12) | AO |  |
| - | 16.B | X441.4 | Analog output 22) | AO |  |
| 15 | X441.5 | 15 X441.5 | Reference (electronics ground) | - |  |

1) I: Input; AO: Analog output
2) Can be freely parameterized
3) The analog outputs (X441) should be connected through a terminal strip.  
A shielded cable should be used together for all of the analog outputs together between X441 and the terminal strip. For this cable, the shield must be connected at both cable ends.  
The 4 analog cables can be routed away from the terminal strip. The shield of the cables must be connected and the ground cables must be connected to a common ground terminal.
4) Only with control board, Order No. 6SN1118-□NH01-0AA, from SW 8.1
## 2.3 Connection diagram and wiring

**Table 2-4 Overview of the drive-specific terminals, continued**

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Drive A Designation</th>
<th>Drive B Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>X451.1</td>
<td>X452.1</td>
<td>Connectortype: 10-pin conn. strip</td>
<td>I</td>
<td>Al</td>
<td>Differential input</td>
</tr>
<tr>
<td>56.A</td>
<td>56.B</td>
<td>Max. cond. cross-section for finely-stranded or solid cond.: 0.5 mm²</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>65.A</td>
<td>65.B</td>
<td>Controller enable drive-specific</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>9</td>
<td>Enable voltage (+24 V)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>10.A</td>
<td>10.B</td>
<td>Digital input 0²)</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

1) I: Input; DI: Digital input; AI: Analog input; S: Supply, 2) Can be freely parameterized  
All of the digital inputs are de-bounced per software. For the signal detection, this results in a delay time of between 1 and 2 interpolation clock cycles (P1010).  
3) I0.x is internally hard-wired to the position sensing function where it acts almost instantaneously.
Table 2-4 Overview of the drive-specific terminals, continued

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Drive A Designation</th>
<th>Drive B Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>X461</td>
<td>A+.A</td>
<td>X462.1</td>
<td>Signal A+</td>
<td>IO</td>
<td>Connector type: 10-pin conn. strip</td>
</tr>
<tr>
<td>X461.1</td>
<td>A+.B</td>
<td>X462.1</td>
<td>Signal A+</td>
<td>IO</td>
<td>Max. cond. cross-section for finely-stranded or solid cond.: 0.5 mm²</td>
</tr>
<tr>
<td>A-.A</td>
<td>X461.2</td>
<td>A-.B</td>
<td>Signal A-</td>
<td>IO</td>
<td>Angular incremental encoder interface</td>
</tr>
<tr>
<td>B+.A</td>
<td>X461.3</td>
<td>B+.B</td>
<td>Signal B+</td>
<td>IO</td>
<td>Wiring:</td>
</tr>
<tr>
<td>B-.A</td>
<td>X461.4</td>
<td>B-.B</td>
<td>Signal B-</td>
<td>IO</td>
<td>• Cable with braided shield, connected at both ends.</td>
</tr>
<tr>
<td>R+.A</td>
<td>X461.5</td>
<td>R+.B</td>
<td>Signal R+</td>
<td>IO</td>
<td>• The reference ground of the connected node should be connected to terminal 15.</td>
</tr>
<tr>
<td>R-.A</td>
<td>X461.6</td>
<td>R-.B</td>
<td>Signal R-</td>
<td>IO</td>
<td>• Condition to maintain the burst strength: Cable length &lt; 30 m</td>
</tr>
<tr>
<td>15(3)</td>
<td>X461.7</td>
<td>15</td>
<td>Ground reference</td>
<td>-</td>
<td></td>
</tr>
</tbody>
</table>

Note:
- Devices (stations) that conform to the RS485/RS422 Standard must be connected.
- The permissible signal level lies between 0 V and +5 V. The module will be destroyed if higher voltages are connected, e.g. 24 V!
- The angular incremental encoder interface can be parameterized as either input or output (refer to Chapter 6.6).
  - Input (from SW 3.3) To enter incremental position reference values
  - Output To output incremental position actual values

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Drive A Designation</th>
<th>Drive B Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>O0.A</td>
<td>X461.8</td>
<td>O0.B</td>
<td>Digital output 0(2)</td>
<td>DO</td>
<td>Rated current per output: 500 mA</td>
</tr>
<tr>
<td>O1.A</td>
<td>X461.9</td>
<td>O1.B</td>
<td>Digital output 1(2)</td>
<td>DO</td>
<td>Max. current per output: 600 mA</td>
</tr>
<tr>
<td>O2.A</td>
<td>X461.10</td>
<td>O2.B</td>
<td>Digital output 2(2)</td>
<td>DO</td>
<td>Maximum total current: 2.4 A</td>
</tr>
<tr>
<td>O3.A</td>
<td>X461.11</td>
<td>O3.B</td>
<td>Digital output 3(2)</td>
<td>DO</td>
<td>(valid for these 8 outputs)</td>
</tr>
</tbody>
</table>

Note:
- The power switched via these outputs is supplied via terminals P24/M24 (X431). This must be taken into account when dimensioning the external supply.
- The digital outputs only “function” if there is an external supply (+24 V/0 V, terminals P24/M24).

1) DO: Digital output; IO: Input/output
2) Can be freely parameterized
3) "SIMODRIVE 611 universal HR/HRS" (Order No.[MLFB] 6SN1118---N:01---V18 (with SW 5.1 or higher)
2.3.3 Connection diagram, connecting-up the optional TERMINAL module

Connection diagram for the optional TERMINAL module

Fig. 2-8 Connection diagram for the optional TERMINAL module
Connecting-up the TERMINAL module

**Connectors:**
- 8-pin plug connector

**Max. conductor cross-section for finely-stranded or solid conductors:**
- 0.5 mm²

**Connector type:**
- 8-pin plug connector

**Max. conductor cross-section for finely-stranded or solid conductors:**
- 0.5 mm²

### Table 2-5 Interface overview for the optional TERMINAL module

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Function</th>
<th>Type 1)</th>
<th>Technical specifications</th>
</tr>
</thead>
<tbody>
<tr>
<td>Digital inputs (X422)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>I4</td>
<td>X422.1</td>
<td>Digital input 4</td>
<td>DI</td>
<td>Voltage: 24 V</td>
</tr>
<tr>
<td>I5</td>
<td>X422.2</td>
<td>Digital input 5</td>
<td>DI</td>
<td>Typ. current consumption: 6 mA at 24 V</td>
</tr>
<tr>
<td>I6</td>
<td>X422.3</td>
<td>Digital input 6</td>
<td>DI</td>
<td>Electrical isolation: Ref. is T. 19/T. M24</td>
</tr>
<tr>
<td>I7</td>
<td>X422.4</td>
<td>Digital input 7</td>
<td>DI</td>
<td>Signal level (incl. ripple)</td>
</tr>
<tr>
<td>I8</td>
<td>X422.5</td>
<td>Digital input 8</td>
<td>DI</td>
<td>High signal level: 15 V to 30 V</td>
</tr>
<tr>
<td>I9</td>
<td>X422.6</td>
<td>Digital input 9</td>
<td>DI</td>
<td>Low signal level: -3 V to 5 V</td>
</tr>
<tr>
<td>I10</td>
<td>X422.7</td>
<td>Digital input 10</td>
<td>DI</td>
<td>Note:</td>
</tr>
<tr>
<td>I11</td>
<td>X422.8</td>
<td>Digital input 11</td>
<td>DI</td>
<td>An open-circuit input is interpreted as 0 signal.</td>
</tr>
</tbody>
</table>

| Digital outputs (X432) |
| O4 | X432.1 | Digital output 4 | DO | Rated current per output: 100 mA |
| O5 | X432.2 | Digital output 5 | DO | Max. current per output: 120 mA |
| O6 | X432.3 | Digital output 6 | DO | Maximum total current: 480 mA |
| O7 | X432.4 | Digital output 7 | DO | (valid for these 8 outputs) |
| O8 | X432.5 | Digital output 8 | DO | Short-circuit proof |
| O9 | X432.6 | Digital output 9 | DO | Voltage drop, typical: 50 mV at 100 mA |
| O10 | X432.7 | Digital output 10 | DO | Electrical isolation: Ref. is T. 19/T. M24 |
| O11 | X432.8 | Digital output 11 | DO | Example: |

Note:
- The parameterization of the terminals and the standard assignment is described in Chap.6.5.
- The power switched via these outputs is supplied via the board-specific terminal 431 (external supply, P24, M24) from the control board.
- This must be taken into account when dimensioning the external supply.
- The digital outputs only “function” if an external power supply is available (+24 V, T. P24/M24).

1) DI: Digital input; DO: Digital output
2) Can be freely parameterized
   All of the digital inputs are de-bounced per software. For the signal detection, this results in a delay time of between 1 and 2 interpolation clock cycles (P1010).
3) Can be freely parameterized
   The digital outputs are updated in the interpolation clock cycle (P1010). This is supplemented by a hardware-related delay time of approx. 200 μs.

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SIMODRIVE 611 universal Function Manual (FBU) - 05/2010 Edition
2.3.4 Connection diagram, connecting-up the optional PROFIBUS-DP module

Connection diagram for the optional PROFIBUS-DP module

---

**Warning**

The serial interface (X471) and the PROFIBUS-DP interface (X423) use 9-pin D-SUB socket connectors.

If the cables are interchanged when connecting-up, this could destroy the module or board of the communications partner.

---
The following bus connectors can be connected to the optional PROFI-BUS-DP module:

- Bus connector for copper cable (e.g.: Cable 6XV1 830-0AH10)
  Order No. (MLFB): 6ES7 972-0BB40-0XA0 (with PG connection)
  Order No. (MLFB): 6ES7 972-0BA40-0XA0 (without PG connection)

The following bus connectors are permissible for copper cable:
  Order No. (MLFB): 6FX2 003-0AA03 (with PG connection)
  Order No. (MLFB): 6FX2 003-0AA02 (without PG connection)
  Order No. (MLFB): 6GK1 500-0EA00 (axial cable outlet)

- OLP (optical link plug)
  Bus connector for fiber-optic cables (baud rate: max. 1.5 Mbaud)
  Order No. (MLFB): 6GK1 502-1AA00

---

Note:
- The dimensions in brackets specify the total depth up to the rear cabinet panel.
- The external shield should be connected through the largest possible surface area (refer to Fig. 2-6).

Fig. 2-10 Mounting depth of the bus connector for the optional PROFIBUS-DP module

---

**Reader’s note**

Additional information on configuring a PROFIBUS-DP network is provided in:

**References:**

/IK10/ SIMATIC NET, Industrial communications, Catalog IK 10

/STPI/ PROFIBUS & AS Interface, Components Connected to the Field Bus, Catalog ST PI
2.4 Pin assignment of the interfaces

Connector designation:  
X411 --> Drive A  
X412 --> Drive B

Connector type: 25-pin, D-Sub, plug connector

Table 2-6 Assignment of X411/X412 for encoders with sin/cos 1Vpp

<table>
<thead>
<tr>
<th>Pin</th>
<th>Signal name</th>
<th>Pin</th>
<th>Signal name</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>P_Encoder</td>
<td>14</td>
<td>5 V sense</td>
</tr>
<tr>
<td>2</td>
<td>M_Encoder</td>
<td>15</td>
<td>EnDat_DAT</td>
</tr>
<tr>
<td>3</td>
<td>A</td>
<td>16</td>
<td>0 V sense</td>
</tr>
<tr>
<td>4</td>
<td>*A</td>
<td>17</td>
<td>R</td>
</tr>
<tr>
<td>5</td>
<td>Inner shield</td>
<td>18</td>
<td>*R</td>
</tr>
<tr>
<td>6</td>
<td>B</td>
<td>19</td>
<td>C</td>
</tr>
<tr>
<td>7</td>
<td>*B</td>
<td>20</td>
<td>*C</td>
</tr>
<tr>
<td>8</td>
<td>Inner shield</td>
<td>21</td>
<td>D</td>
</tr>
<tr>
<td>9</td>
<td>Reserved</td>
<td>22</td>
<td>*D</td>
</tr>
<tr>
<td>10</td>
<td>EnDat_CLK</td>
<td>23</td>
<td>*EnDat_DAT</td>
</tr>
<tr>
<td>11</td>
<td>Reserved</td>
<td>24</td>
<td>Inner shield</td>
</tr>
<tr>
<td>12</td>
<td>*EnDat_CLK</td>
<td>25</td>
<td>-Temp (KTY/PTC)</td>
</tr>
<tr>
<td>13</td>
<td>+Temp (KTY/PTC)</td>
<td>-</td>
<td>-</td>
</tr>
</tbody>
</table>

Motor encoder incremental 6FX\[002-2CA31-1\]
Motor encoder incremental (AH20) 6FX\[002-2CA20-1\]
Motor encoder absolute 6FX\[002-2EQ00-1\]
Motor encoder absolute (EnDat) 6FX\[002-2EQ10-1\]
Motor encoder absolute (AH20) 6FX\[002-2EQ20-1\]

□: Space retainer for the cable type (length, ...)

Motor encoder, TTL signal the user does not have to assemble a shielded connecting cable

(only with control board, Order No. 6SN1118-□NH01-0AA□, from SW 8.1)

References: /Z/ Catalog NC Z, Accessories and Equipment
2 Installing and Connecting-Up

2.4 Pin assignment of the interfaces

**Pin assignment of X411/X412 for the control board for resolvers**

Connector designation:
- X411 --> Drive A
- X412 --> Drive B

Connector type: 25-pin, D-Sub, plug connector

**Table 2-7 Assignment of X411/X412 for resolvers**

<table>
<thead>
<tr>
<th>Pin</th>
<th>Signal name</th>
<th>Pin</th>
<th>Signal name</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Reserved</td>
<td>14</td>
<td>Reserved</td>
</tr>
<tr>
<td>2</td>
<td>M_Encoder</td>
<td>15</td>
<td>Reserved</td>
</tr>
<tr>
<td>3</td>
<td>SIN_PLUS</td>
<td>16</td>
<td>Reserved</td>
</tr>
<tr>
<td>4</td>
<td>SIN_MINUS</td>
<td>17</td>
<td>Reserved</td>
</tr>
<tr>
<td>5</td>
<td>Inner shield</td>
<td>18</td>
<td>Reserved</td>
</tr>
<tr>
<td>6</td>
<td>COS_PLUS</td>
<td>19</td>
<td>Reserved</td>
</tr>
<tr>
<td>7</td>
<td>COS_MINUS</td>
<td>20</td>
<td>Reserved</td>
</tr>
<tr>
<td>8</td>
<td>Inner shield</td>
<td>21</td>
<td>Reserved</td>
</tr>
<tr>
<td>9</td>
<td>Excitation_Pos</td>
<td>22</td>
<td>Reserved</td>
</tr>
<tr>
<td>10</td>
<td>Reserved</td>
<td>23</td>
<td>Reserved</td>
</tr>
<tr>
<td>11</td>
<td>Excitation_Neg</td>
<td>24</td>
<td>Inner shield</td>
</tr>
<tr>
<td>12</td>
<td>Reserved</td>
<td>25</td>
<td>Temp- (KTY/PTC)</td>
</tr>
<tr>
<td>13</td>
<td>Temp+ (KTY/PTC)</td>
<td>-</td>
<td>-</td>
</tr>
</tbody>
</table>

Cable Order No. (MLFB)
- Resolver in the motor 6FX2 002-2CF01-1☐☐0
- Resolver in the motor (AH20) 6FX☐ 002-2CF20-1☐☐0
  ☐: Space retainer for the cable type (length, ...)

**References:** /Z/ Catalog NC Z, Accessories and Equipment

**Serial interface X471**

Connector type: 9-pin, D-Sub socket connector

**Table 2-8 Assignment of the serial interface**

<table>
<thead>
<tr>
<th>Pin</th>
<th>Signal name</th>
<th>Pin</th>
<th>Signal name</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>RS485 DATA+</td>
<td>6</td>
<td>Reserved</td>
</tr>
<tr>
<td>2</td>
<td>RS232 TxD</td>
<td>7</td>
<td>RS232 CTS</td>
</tr>
<tr>
<td>3</td>
<td>RS232 RxD</td>
<td>8</td>
<td>RS232 RTS</td>
</tr>
<tr>
<td>4</td>
<td>Reserved</td>
<td>9</td>
<td>RS485 DATA-</td>
</tr>
<tr>
<td>5</td>
<td>Ground 0 V</td>
<td>-</td>
<td>-</td>
</tr>
</tbody>
</table>

**Note:**
- The serial interface can be declared an RS232 or an RS485 interface by appropriate parameterization (refer to Chapter 3.3.3).
- When set as an RS485 interface, a terminating resistor can be switched in/out via switch S1 on the front panel.
- The cable diagrams for the serial interface are provided in Chapter 2.5.
## 2.4 Pin assignment of the interfaces

**Connector type:** 9-pin, D-Sub socket connector

**Table 2-9 Assignment of the PROFIBUS-DP interface**

<table>
<thead>
<tr>
<th>Pin</th>
<th>Signal name</th>
<th>Pin</th>
<th>Signal name</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Reserved</td>
<td>6</td>
<td>VP, Supply voltage plus (P5V)</td>
</tr>
<tr>
<td>2</td>
<td>Reserved</td>
<td>7</td>
<td>Reserved</td>
</tr>
<tr>
<td>3</td>
<td>RxD/TxD-P, Receive/send data P B cable</td>
<td>8</td>
<td>RxD/TxD-N, Receive/send data N A conductor</td>
</tr>
<tr>
<td>4</td>
<td>RTS, Request To Send</td>
<td>9</td>
<td>Reserved</td>
</tr>
<tr>
<td>5</td>
<td>DGND, Data reference potential (M5V)</td>
<td>-</td>
<td>-</td>
</tr>
</tbody>
</table>
2.5 Cable diagrams

Cable diagram for 
RS232

Cable diagram: 9/9 conductor

A commercially available 1:1 serial extension cable can be used to connect a PG/PC to "SIMODRIVE 611 universal".

**Fig. 2-11 RS232 connecting cable with RTS/CTS lines:**

PG/PC <-> SIMODRIVE 611 universal

**Fig. 2-12 RS232 connecting cable without RTS/CTS lines:**

PG/PC <-> SIMODRIVE 611 universal
Cable diagram: 25/9 conductor

<table>
<thead>
<tr>
<th>PG</th>
<th>SIMODRIVE 611 universal</th>
</tr>
</thead>
<tbody>
<tr>
<td>RxD</td>
<td>3</td>
</tr>
<tr>
<td>TxD</td>
<td>2</td>
</tr>
<tr>
<td>0 V</td>
<td>7</td>
</tr>
<tr>
<td>RTS</td>
<td>4</td>
</tr>
<tr>
<td>CTS</td>
<td>5</td>
</tr>
<tr>
<td>DSR</td>
<td>6</td>
</tr>
<tr>
<td>DTR</td>
<td>20</td>
</tr>
<tr>
<td>25-pin</td>
<td>D-Sub</td>
</tr>
<tr>
<td>D-Sub plug con.</td>
<td></td>
</tr>
<tr>
<td>1</td>
<td></td>
</tr>
</tbody>
</table>

Connection to a serial interface e.g. COM1 V24/AG for PG

Jumpered in the connector
Remove the latch interlock on the SIMODRIVE side

Connection at X471
Setting the interface to RS232 (P0801 = 0)

Setting the interface to RS485 (P0801 = 1)

Note:
Pins which are not used may not be assigned.

Fig. 2-13  RS232 connecting cable: PG <-> SIMODRIVE 611 universal

Order No.: 6FC9 348-2T□00  □ = B --> Length 5 m  □ = C --> Length 10 m

Cable diagram for RS485

Fig. 2-14  RS485 connecting cable:
PG/PC <-> RS232/RS485 interface converter <-> SIMODRIVE 611 universal
## Parameterizing the Board

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3.3.4 Online operation: SimoCom U via PROFIBUS-DP (from SW 3.1) ...... 3-114
3.1 Overview when parameterizing

You can parameterize “SIMODRIVE 611 universal” as follows:

- Using the display and operator unit on the front panel of “SIMODRIVE 611 universal”
- Using the parameterizing and start-up tool (SimoCom U) on a PG/PC
  - SimoCom U via serial interface (RS232/RS485)
    --> refer to Chapter 3.3.3
  - SimoCom U via PROFIBUS-DP (CP 5511/CP 5611/CP 5613)
    --> refer to Chapter 3.3.4

Fig. 3-1 Overview when parameterizing
3.2 Parameterizing using the display and operator unit

General

The display and operator unit is used to

- Select, display and change parameters, sub-parameters and parameter values (refer to Chapter 3.2.1)
- Display and control when faults and warnings occur (refer to Chapter 7.2)

Operating statuses of the display unit

The display unit on the front panel of the "SIMODRIVE 611 universal" control board can have the following operating statuses:

<table>
<thead>
<tr>
<th>Operating state</th>
<th>Selection</th>
<th>Description</th>
</tr>
</thead>
</table>
| Power-on mode            | Automatically after power-on                   | • Power-on before first commissioning: The following is displayed "A1106" or "b1106".  
                            | The parameterizing mode is selected by pressing any key on the operator unit (PLUS/MINUS/P key).    |     
                            |                                                | • Power-on after the first commissioning: After power-on and the system has successfully booted it goes into cyclic operation and "___ run" is displayed. |
| Parameterizing mode      | This mode can be selected from                 | The parameterizing mode is used to select parameters and sub-parameter numbers and to display and change parameter values. |
| (refer to Chapter 3.2.1) | • Power-on mode or                            | **Note:** You cannot change into another mode from the parameterizing mode. The other modes are automatically selected. |
|                          | • Alarm mode                                   |                                                                             |
| Alarm mode               | Automatically after at least one fault or warning occurs | The alarm mode is used to display faults and warnings.                       |
| (refer to Chapter 7.2)   |                                                |                                                                             |
### 3.2.1 Parameterizing mode

**Display types**

In the parameterizing mode, a differentiation is made between the following display types:

- Parameter display
- Sub-parameter display

**Note**

Only those parameters are displayed, which correspond to the selected authorization level. Parameter P0651 is used to define which parameters can be read and written into (refer to Chapter 4.5).

- Value display

**Parameters without sub-parameter and value display, max. 6 digits**

These parameters can be displayed and handled in the following ways (example with A1400: Parameter 1400 from drive A):

---

**Fig. 3-2 Handling parameters without sub-parameter and value display, max. 6 positions**
3.2 Parameterizing using the display and operator unit

Parameter with sub-parameter and value display, max. 6 digits

These parameters can be displayed and handled in the following ways (example with A1401: Parameter 1401 from drive A):

- **Parameter display**

- **Sub-parameter display**

- **Value display**

For these parameters, the following display and handling possibilities exist (example with A0160: Parameter 0160 from drive A):

- **Parameter display**

- **Sub-divided into H: High part L: Low part**

- **Value display** (e.g. the value 123 456.789)

Fig. 3-3 Handling parameters with sub-parameter and value display, max. 6 positions

Fig. 3-4 Handling parameters with sub-parameter and value display > 6 positions
Parameters with sub-parameter and value display
> 6 digits

These parameters can be displayed and handled in the following ways (example with A0081: Parameter 0081 from drive A):

**Parameter display**

- **Previous parameter**
- **Subsequent parameter**

+: Key +
-: Key -
P: Key P

Sub-divided into H: High part
L: Low part

**Value display**

-e.g. the value 123 456.789

Display from the 7th position
Display up to the 6th position

Fig. 3-5 Handling parameters with sub-parameter and value display > 6 positions

---

**Note**

**Examples:**

<table>
<thead>
<tr>
<th>Display in A081.0H</th>
<th>A081.0L</th>
</tr>
</thead>
<tbody>
<tr>
<td>123</td>
<td>456.789</td>
</tr>
<tr>
<td>-3</td>
<td>459.765</td>
</tr>
</tbody>
</table>
### Key combinations

The following key combinations are available to make operator entries in the display types:

<table>
<thead>
<tr>
<th>Display mode</th>
<th>Key combination</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Parameter display</td>
<td>+</td>
<td>Jump to the next higher existing parameter number</td>
</tr>
<tr>
<td></td>
<td>-</td>
<td>Jump to the next lower existing parameter number</td>
</tr>
<tr>
<td></td>
<td>+ P</td>
<td>Fast scrolling up$^1$ (jumps over five existing parameters)</td>
</tr>
<tr>
<td></td>
<td>P -</td>
<td>Fast scrolling down$^1$ (jumps over five existing parameters)</td>
</tr>
<tr>
<td></td>
<td>+</td>
<td>Jump to the same parameter of another drive</td>
</tr>
<tr>
<td></td>
<td>P</td>
<td>Jump to the sub-parameter display or to the value display</td>
</tr>
<tr>
<td>Sub-parameter display</td>
<td>+</td>
<td>Jump to the next sub-parameter number or back to the parameter display</td>
</tr>
<tr>
<td></td>
<td>-</td>
<td>Jump to the previous sub-parameter number or back to the parameter display</td>
</tr>
<tr>
<td></td>
<td>+ P</td>
<td>Fast scrolling up$^1$ (jumps over a maximum of five existing sub-parameters)</td>
</tr>
<tr>
<td></td>
<td>P -</td>
<td>Fast scrolling down$^1$ (jumps over a maximum of five existing sub-parameters)</td>
</tr>
<tr>
<td></td>
<td>+</td>
<td>Jump to the selected sub-parameter of the same parameter of the other drive</td>
</tr>
<tr>
<td></td>
<td>P</td>
<td>Jump to the value display</td>
</tr>
<tr>
<td>Value display</td>
<td>+</td>
<td>Parameter is incremented by 1 (at the least-significant position)</td>
</tr>
<tr>
<td></td>
<td>-</td>
<td>Parameter value is decremented by 1 (at the least significant position)</td>
</tr>
<tr>
<td></td>
<td>+ P</td>
<td>Fast scrolling up$^1$ accelerating</td>
</tr>
<tr>
<td></td>
<td>P -</td>
<td>Fast scrolling down$^1$ accelerating</td>
</tr>
<tr>
<td></td>
<td>P</td>
<td>Jump to the parameter or sub-parameter display</td>
</tr>
</tbody>
</table>

$^1$ Setting to the lower or the upper limit
3 Parameterizing the Board

3.2 Parameterizing using the display and operator unit

Parameters for drives A and B

The parameters of a drive are displayed in a numerical sequence. By simultaneously pressing the PLUS and MINUS keys in the parameter and sub-parameter display, it is possible to jump to the same parameter of the other drive. The parameters of drive A are designated with "A ..." and the parameters of drive B with "b ...".

Parameters of drive A

Parameters of drive B

Fig. 3-6 Parameter display for drive A and B

Representation of hexadecimal values

Hexadecimal numbers are displayed in the following form:

__ __ __ __ 0. to F.F.F.F.F.

Displaying parameter numbers

While a parameter value is being displayed, the associated parameter or sub-parameter number is cyclically displayed every 10 seconds for one second. This function can be enabled/disabled using P1650 bit 15.

P1650.15 = 0 Cyclic display is active (standard)

= 1 Cyclic display is inactive

Designating parameters which are effective after POWER ON

The parameters, which are effective after POWER ON, are designated in the parameter display by a point after the drive letters.

Fig. 3-7 Designating parameters which are effective after POWER ON
3.2.2 Example: Changing a parameter value

Task description:
The analog setpoint is to be inverted via terminal 56.B/14.B. In this case, in drive B, parameter P0608 must be set to 1.

Assumptions:
- The drive was already commissioned once.
- Presently "__ run" is being displayed.

Operating sequence:
1. Select the parameterizing mode
   --> press any key on the operator unit (e.g. "P")
2. Select drive B
   --> Simultaneously press the PLUS and MINUS keys
3. Remove write protection
   --> Set P0651 to 4
   --> Set P0608 to 1
5. Save the parameters in the FEPROM
   --> Set P0652 to 1
6. Re-activate write protection
   --> Set P0651 to 0

Note
The analog setpoint via terminal 56.B/14.B is now processed inverted. At the next power-on and after the system has successfully booted "__ run" is displayed again.

When reading/writing parameters using the display and operator unit, the following generally applies:
The read and write protection (P0651) should be taken into account.
3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

3.3.1 Installing SimoCom U

Note
"SimoCom U" is a tool that is used for commissioning, diagnostics and parameterization. It is not permissible to use this tool as operator interface for continuous operation of drives!

Prerequisite
A PG/PC is required to install the tool; it must fulfill the following minimum requirements:

- Operating system:
  - Windows 98® or Windows NT® or
  - from SW 4.1 also Windows ME® or Windows 2000® or
  - from SW 6.1, also Window XP®
  - from SW 9.1, also WIN Server 2003®
  - from SW 9.2, only Windows XP®, WIN Server 2003®
  - from SW 12.1, only Windows XP®, WIN Server 2003® or Windows Vista®

- 32 MB RAM memory

- Free memory required on the hard disk
  - Installing with one language --> 30 MB
  - Installing each additional language --> plus approx. 10 MB

- 1 free serial interface (RS232 interface)

Note
Note: If the PG/PC does not have a serial interface, then a commercially available USB/RS232 interface adapter can be connected!

Software supply
The various software versions are supplied on a CD-ROM. Further, the software is available in the Internet under the following address:
http://www.ad.siemens.de/
--> Products & Solutions --> Drive systems --> Drive converters --> SIMODRIVE 611 --> 611 universal --> Downloads
3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

Which SimoCom U version is the optimum one?

The "SimoCom U" parameterizing and start-up tool can be used for various drives.

The functional scope of "SimoCom U" tool will be continually adapted to the functional expansion of these drives.

In order to parameterize and handle all of the functions of a drive using "SimoCom U", the optimum matching "SimoCom U" must be used, depending on the drive software release.

Reader’s note
Which version of SimoCom U optimally matches which drive and which drive software release?
refer to SimoCom U as follows:
Help ----> Info about "SimoCom U" ... ----> Versions

Installing "SimoCom U"

This is how you install the "SimoCom U" tool on your PG/PC:

Reader’s note
The "readme.txt" file is provided on the software CD.
Please observe the information, tips and tricks provided in this file.

1. Insert the software CD into the appropriate drive of your PG/PC.
2. Run the "setup.exe" file in the "disk1" directory of the required version of "SimoCom U".
   --> START --> RUB --> OPEN SETUP.EXE --> OK
3. Follow the instructions which the installation program displays step-by-step.

Result:
- The "SimoCom U" tool has now been installed in the target directory which you selected.
- The tool can e.g. be started as follows:
  --> START --> PROGRAMS --> SIMOCOMU
  -> SimoComU -> click on selection

Note
The firmware on the CD can be loaded into the appropriate module using the "SimoCom U" tool.
3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

Un-installing SimoCom U

You can un-install the "SimoCom U" parameterizing and start-up tool from your PG/PC:

- Using the SimoCom U program
  The "SimoCom U" tool can, e.g. be uninstalled as follows:
  -> START --> PROGRAMS --> SIMOCOMU
  -> Un-install SimoComU --> click

- Using the Control Panel just like any other Windows program
  - Select the "control panel"
    -> START --> SETTINGS --> CONTROL PANEL
  - Double-click on the "Software" symbol
  - Select the "SimoCom U" program in the selection field
  - Press the "add/remove..." button and then follow the instructions
3.3.2 Entry into SimoCom U

Prerequisite

The SimoCom U parameterizing and start-up tool is installed and started on the PG/PC acc. to Chapter 3.3.1.

The following basic screen is displayed after the first start:

![Basic screen of SimoCom U for the latest version](image)

---

Note

When using SimoCom U, please be aware of the following:

The program attempts to “think with you”:

- If you select a command, which is presently not available for a specific reason (e.g. you are offline and wish to “move an axis”), then the program does what you would probably wish it to do:
  It goes “online”, and offers you a list of drives and after the required drive has been selected, it opens the traversing window. However, if you do not wish to do this, then you can exit and continue as required.

- Only the information is provided in the dialog boxes which must be available as a result of the selected configuration.

Example:
If a synchronous motor is set, then a ramp-function generator is not made available in the dialog boxes for parameterization.
3 Parameterizing the Board

3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

The information listed in Table 3-3 provides basic information and instructions on how to handle the SimoCom U parameterizing and start-up tool.

Table 3-3 Information on SimoCom U

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
</table>
| Tasks, which can be executed using SimoCom U | • Check the wiring (go into the Online Help: connection diagrams)  
• Establish a connection to the drive to be parameterized  
• Change the parameters  
  - The essential parameters are changed in interactive dialog  
  - All of the parameters can be changed using the list parameterization  
• Upgrade firmware  
• Optimize the controller parameters  
• Traverse the axis  
• Diagnose the drive status  
  - Obtain an overview of all of the connected drives and their status  
  - Identify the connected hardware  
  - Obtain a display of the terminal status  
  - Obtain a display of the alarms and information on how they can be removed  
• Carry-out diagnostics  
  - Parameterize the test sockets (DAC1, DAC2)  
  This means that selected signals in the drive can be routed to the test sockets for measurement with an oscilloscope.  
  - Execute the measuring function  
  It is possible to measure the most important quantities in the closed-loop current and speed control loop in the time and frequency domains without having to use external measuring equipment; these can then also be graphically displayed.  
  - Execute the trace function  
  Selected measuring quantities in the drive can be measured corresponding to the specified measuring parameters, and graphically displayed using SimoCom U.  
• Simulate terminal signals  
• Save the results  
  - Save the parameters in the drive FEPROM  
  - Save the parameters in a file/open a file  
  - Print the parameters  
• Comparing parameter sets (from version 02.04)  
  This allows the differences between 2 parameter sets to be identified.  
• Boot the board (from version 03.03)  
  The board status when originally shipped can be re-established using this function.  
• User-parameter list (from version 03.03)  
  The user can include a parameter in this list. This list has the same functionality as the expert list.  
• Password protection (from version 08.01)  
  Using this function, access protection can be provided for SimoCom U and the drive firmware so that the drive configuration cannot be changed. To set the password protection, refer to Chapter 4.3.3. |
### 3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

Table 3-3 Information on SimoCom U, continued

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
</table>
| **Working offline**           | ... this means that you are only working at the computer and you do not have a connection to a “SIMODRIVE 611 universal” drive.  
The opened files are now included in the drive selection box of the toolbar.                                                                                       |
| **Working online**            | ... this means that you are connected with one or several SIMODRIVE 611 universal drives and SimoCom U also knows these drives.  
This is the case, if SimoCom U has already searched for the interface.  
You go online, if  
- You default setting in the menu “Options/Settings/Communications” is set to “connect via COMx”  
  (this is realized when starting SimoCom U)  
- You make the selection with the operator action "Search for online drives"  
In the online mode, the toolbars of the opened files are included in the drive selection box together with all of the drives available at the interface.  
Recommended interface setting:  
If you are starting SimoCom U for the first time, then you will be prompted about the default setting of the interface:  
- If you predominantly work in the office, then select “work offline”.  
- If you predominantly work at the machine, then select “connect via” and the serial interface at your computer.  
**Note:**  
The parameters, displayed via SimoCom U, are not cyclically read.  
Examples:  
- If a parameter of an open dialog box is changed in online operation using the display and operator unit, then this parameter remains “frozen” in the open dialog box.  
- If a first commissioning is executed using the display and operator unit while SimoCom U is in the online mode with the drive, then SimoCom U cannot identify that the drive has been started up (commissioned).  
Remedy:  
After changing parameters using the display and operator unit or via PROFI-BUS-DP, you should first go offline with SimoCom U, in order to go back online with updated data. |
| **Working in the drive or in the file** | You can work in a file directly in the drive or only at the PC - however, only with one data set at any one time.  
For instance, you can be connected with a double axis module (and therefore have access to the parameter sets in the two drives A and B) and at the same time, have several files open. All of these parameter sets are then displayed in the selection box in the toolbar, and also in the “file” menu.  
When you select “Drive A”, you will see the status and the parameters which are active directly in Drive A – otherwise none. When changing over to a “my.par” file, then you will only see the parameters of this file.  
Opened parameter files can also be re-closed:  
Menu “File/Close file”. |
3 Parameterizing the Board

3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

Table 3-3 Information on SimoCom U, continued

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Expert list</td>
<td>... displays all of the &quot;SIMODRIVE 611 universal&quot; parameters. You can individually change any parameter via the expert list. The operator has no additional support here. This list parameterization should only be used in exceptional cases.</td>
</tr>
<tr>
<td></td>
<td>• Operating Instructions</td>
</tr>
<tr>
<td></td>
<td>- Call: Menu &quot;Start-up/Additional parameters/Expert list&quot;</td>
</tr>
<tr>
<td></td>
<td>- If you open the list, you will additionally obtain the menu, which can also be reached using the right-hand mouse key.</td>
</tr>
<tr>
<td></td>
<td>- It is especially interesting that the standard value and value limits for the actual parameters are displayed in the status line.</td>
</tr>
<tr>
<td></td>
<td>- Modified values only become effective after pressing the Enter key or if another parameter was selected. Values which are inactive have a red background.</td>
</tr>
<tr>
<td></td>
<td>- In the &quot;List&quot; menu, you can select which data should appear in the list: All, or only the controller data, or only the sub-parameter set 0 or .... Furthermore, you can search for specific terms with F3 (or list/search menu), e.g. you can search for &quot;temp&quot; if you wish to change the temperature warning threshold value.</td>
</tr>
<tr>
<td></td>
<td>- Bit-coded values: Go with the cursor to the line and press F4 (or menu, List/bit values). You then obtain a plain text display of the individual bits and can select these at a click of the mouse.</td>
</tr>
<tr>
<td>Assign the PC the master control</td>
<td>... means that the terminal signals are ignored at the terminals and instead, the drive evaluates signals set by the PC.</td>
</tr>
<tr>
<td></td>
<td>This means that the enable signals to traverse the drive can be output from the PC.</td>
</tr>
<tr>
<td></td>
<td>Exceptions:</td>
</tr>
<tr>
<td></td>
<td>• The pulse enable (terminal 663) and the controller enable (terminal 65.x) must be provided, as before, via the input terminals.</td>
</tr>
<tr>
<td></td>
<td>This is for safety: You can withdraw these enable signals at any time, using a switch in order to switch the drive into a no-current condition or shut it down.</td>
</tr>
<tr>
<td></td>
<td>• During PC-control, digital input 10 with the &quot;external block exchange&quot; parameter assignment is not active even if set via the PC (Diagnostics &gt; Diagnostics Views &gt; CTRL L).</td>
</tr>
<tr>
<td>Transfer the master control from</td>
<td>... you then obtain a display of the voltage level available at the terminals compared to the signals set by the PC. The master control is only transferred back to the terminals after acknowledgement.</td>
</tr>
<tr>
<td>the PC back to the terminals</td>
<td></td>
</tr>
</tbody>
</table>
### 3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

#### Table 3-3 Information on SimoCom U, continued

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Commissioning required</td>
<td>A drive that has still not been commissioned, logs-on with: &quot;Commissioning required!&quot; You have 5 possibilities:</td>
</tr>
<tr>
<td></td>
<td>1. Open the Start-up Assistant - if you have not already created a file, which you wish to load into the drive.</td>
</tr>
<tr>
<td></td>
<td>2. Load an existing file into the drive.</td>
</tr>
<tr>
<td></td>
<td>3. Optionally, you can switch the drive, which logs-on, into the passive state (this is only possible for drive B).</td>
</tr>
<tr>
<td></td>
<td>4. Work offline - this means that you disconnect the link to the drive without start up the drive.</td>
</tr>
<tr>
<td></td>
<td>5. Emergency exit - in this case, you remain online without carrying out any commissioning (e.g. in order to upgrade the firmware before commissioning)</td>
</tr>
<tr>
<td>Procedure when commissioning</td>
<td>Recommendation: Go through the &quot;Start-up&quot; menu, from the top to the bottom.</td>
</tr>
<tr>
<td>1.) Drive configuration</td>
<td>The parameters are arranged according to importance:</td>
</tr>
<tr>
<td></td>
<td>... here, enter which power modules, which motors, which encoders are used with this drive, and in which operating mode the drive is used.</td>
</tr>
<tr>
<td></td>
<td>If this data is changed, the controller data is re-calculated, i.e. previous changes made to the relevant parameters will be overwritten.</td>
</tr>
<tr>
<td>2.) Basic commissioning</td>
<td>... here, you will find the data, which is in most cases necessary and also sufficient for the motor and the operating mode that has been entered.</td>
</tr>
<tr>
<td></td>
<td>You can access all of the parameters in the expert list.</td>
</tr>
<tr>
<td>Traverse the drive</td>
<td>After the drive has been configured, you can already operate the drive from the PC.</td>
</tr>
<tr>
<td></td>
<td>Call: &quot;Operator control/Traverse/ ...” menu</td>
</tr>
<tr>
<td>Data transfer</td>
<td>Also here, the program attempts to &quot;think with you&quot;:</td>
</tr>
<tr>
<td></td>
<td>If you are working with drive A and select &quot;File/Load into drive&quot;, then the program assumes that you wish to download a file, still to be selected, into this drive A.</td>
</tr>
<tr>
<td></td>
<td>If a file is presently open, then the program assumes that using the same command, you wish to download this open data set into a drive still to be selected.</td>
</tr>
<tr>
<td></td>
<td>If these assumptions are not applicable, then you can always undo by canceling.</td>
</tr>
</tbody>
</table>
Integrated help

The "SimoCom U" tool has an integrated Help function, which helps you to use the tool and the "SIMODRIVE 611 universal" drive. This is how you call up the integrated help function:

- Using the menu command Help > Help contents...
  or
- By pressing the Help button
  or
- By pressing key F1

Printing

Data for the following dialog boxes can be printed using the print symbol in the symbol bar:

- Traversing blocks
- Teach In
- User parameter list
- Operating conditions
- Status parameters
- Trace function
- Measurement function
- Expert List

3.3.3 Online operation: SimoCom U via a serial interface

General

The serial interface (X471) can be used as RS232 interface or as RS485 interface.

- Used as RS232 interface
  --> refer under the index entry, "Communications via RS232"
- Used as RS485 interface
  --> refer under the index entry "Communications via RS485"
The following parameters are available for the serial interface (X471):

### Table 3-4 Overview of the serial interface

<table>
<thead>
<tr>
<th>Interface</th>
<th>Parameter</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0801</td>
<td>Toggling between RS232/RS485</td>
<td></td>
<td></td>
<td>-1</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The serial interface (X471) is either set to</td>
<td></td>
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<tr>
<td></td>
<td>RS232 or RS485 using this parameter.</td>
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</tr>
<tr>
<td></td>
<td>= 1 Interface is set to RS485</td>
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<tr>
<td></td>
<td>= 0 Interface is set to RS232</td>
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<td></td>
<td>= -1 Reserved</td>
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<tr>
<td></td>
<td>The interface can be changed over from both</td>
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<td></td>
<td>drives. As the interface can either be set</td>
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<td></td>
<td>to RS232 or to RS485, when changing the</td>
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<tr>
<td></td>
<td>parameter in a drive, the parameter in the</td>
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<td></td>
<td>other drive is automatically changed.</td>
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<tr>
<td></td>
<td><strong>Note:</strong></td>
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<tr>
<td></td>
<td>The RS485 interface can only function for</td>
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<td></td>
<td>control boards from a certain hardware version</td>
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<td></td>
<td>onwards.</td>
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<tr>
<td></td>
<td>--- refer under the index entry &quot;RS485 (from HW ...1)&quot;</td>
<td></td>
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</tr>
<tr>
<td>0802</td>
<td>Drive number for RS485</td>
<td></td>
<td></td>
<td>0</td>
<td>0</td>
<td>31</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>In an RS485 group, using this parameter, each</td>
<td></td>
<td></td>
<td></td>
<td></td>
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<tr>
<td></td>
<td>drive must be assigned a unique drive number</td>
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<tr>
<td></td>
<td>that is used for addressing.</td>
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<td></td>
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<tr>
<td></td>
<td>= 0 The drive is not available in the RS485</td>
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<tr>
<td></td>
<td>group</td>
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<td></td>
<td>= 1 to 31 The drive has this valid drive</td>
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<td><strong>Note:</strong></td>
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<tr>
<td></td>
<td>The drive number must be unique in the</td>
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<tr>
<td></td>
<td>complete group.</td>
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<tr>
<td></td>
<td>The terminating resistor is switched in/out</td>
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</tr>
<tr>
<td></td>
<td>using switch S1 (on: Switch 7 and 8 = ON).</td>
<td></td>
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<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
Before changing over the serial interface, it must be checked that the appropriate "correct" connecting cable is connected at X471.

### Interface parameters

For "SIMODRIVE 611 universal", the interface parameters for the serial interface are permanently assigned and cannot be changed.
Communications via RS232

The serial RS232 interface is used to connect the "SIMODRIVE 611 universal" control board to a PG/PC. The parameterizing and start-up tool SimoCom U communicates via this interface in the online mode (refer to Fig. 3-9).

Note

When changing the drive (changing-over the serial connecting cable) while there is an open connection to SimoCom U, first wait until the SimoCom U has recognized that the connection has been interrupted (a dialog box opens within a few seconds). You can then insert the cable into the new drive. In the dialog box, you can then select whether you wish to re-connect or cancel.

The following should be observed when establishing a communications link:

1. Parameter P0801 "toggling between RS232/RS485":
   The parameter must be set to RS485 (P0801 = 0).
   Recommendation:
   Set or check this parameter using the display and operator panel (refer to Chapter 3.2).

2. RS232 connecting cable between PG/PC and "SIMODRIVE 611 universal"
   (cable diagram: refer to Chapter 2.5).

Fig. 3-9  Communications via RS232
Communications via RS485

The serial RS485 interface is used to connect several "SIMODRIVE 611 universal" control boards in an RS485 group. The SimoCom U parameterizing and start-up tool communicates, in the online mode, via an RS232/RS485 interface converter and the selected drive in the RS485 group (refer to Fig. 3-10).

Notice

The RS485 interface can only function with control boards from the appropriate hardware version (refer to Order No., MLFB).

Control board (Order No.) RS485?

- 6SN1118-VN00-0AA0 RS485 cannot be used
- from 6SN1118-VN00-0AA1 RS485 can be used

□: Space retainer for the Order No.

For communications via RS485, the following should be observed:

1. Parameter

   - P0801 (toggling between RS232/RS485)
     The parameter must be set to RS485 (P0801 = 1).
     Recommendation:
     Set or check this parameter using the display and operator panel (refer to Chapter 3.2).

   - P0802 (drive number for RS485)
     The drive number for each drive is selected via this parameter.

2. Interface converter RS232/RS485

   For operation via RS485, a commercially available RS232/RS485 converter is required between the PC and RS485 bus.

   The interface converter must have the following features:

   - The converter itself must automatically change over the data flow direction.

   - It is not permissible that the converter sends an "echo" back to the PC.

   Recommended RS232/RS485 interface converter name:

   - Name: PC/PPI cable (RS232/RS485 converter)
   - Order No.: 6ES7 901-3BF20-0XA0
   - Cable length: 5 m
   - Connector: on the RS232 side: 9-pin socket connector
     on the RS485 side: 9-pin plug connector
   - Power supply: via the connector on the RS485 side
     RS485 side (+24 V/0.5 W)
   - Data transfer rate: set to 38.4 kbaud
3. Cable

- RS232 connecting cable
  Cable between the PG/PC and interface converter
  (cable diagram: refer to Chapter 2.5)

- RS485 connecting cable
  Cable between the RS232/RS485 interface converter and the
  nodes to establish an RS485 link
  (cable diagram: refer to Chapter 2.5 or Fig. 3-10)

4. Terminating resistor for the RS485 bus

Generally applies:
First and last node --> terminating resistor switched--in
Other nodes on the bus --> terminating resistor switched--out
(switch S1, refer to Chapter 1.3.2)

Example:
Communications from a PG/PC to 3 "SIMODRIVE 611 universal" con-
control boards (2-axis versions) should be possible via the serial interface.
Online operation between a PG/PC and the individual control boards
must be realized via an RS232/RS485 converter and the appropriate
abling on the RS485 side, so that the drive can go online at any time.
Assumptions for the example:

- The recommended RS232/RS485 converter is used (PC/PPI cable).
  Set all of the switches at the converter to "0".
- The serial interface must be set to RS485 for all drives (P0801 = 1).
- Setting the drive number (P0802)
  - 1st board  Drive A: Drive number for RS485 = 4
                Drive B: Drive number for RS485 = 2
  - 2nd board  Drive A: Drive number for RS485 = 7
                Drive B: Drive number for RS485 = 8
  - 3rd board  Drive A: Drive number for RS485 = 5
                Drive B: Drive number for RS485 = 3
- Terminating resistor for the RS485 bus
  - Interface converter:       First node
    --> Switch--in the terminating resistor
        or solder into the socket (refer to Fig. 3-10)
  - 1st and 2nd board:        No first or last node
    --> Switch--out the terminating resistor
  - 3rd board:                Last node
    --> Switch--in the terminating resistor
Basic solution for the example:

Fig. 3-10 Communications via RS485 (example with 3 nodes)

Note
Essentially the same as when specifying the possible node addresses (drive numbers), up to 31 drives can be connected to an RS232/RS485 interface converter (PC/PPI cable).
3.3.4 Online operation: SimoCom U via PROFIBUS-DP (from SW 3.1)

Description

The “SimoCom U” parameterizing and start-up tool can communicate with the drives via the serial interfaces and also via the PROFIBUS-DP field bus.

The following online modes are possible:

- Online operation via the CP 5511/CP 5611/CP 5613 directly with the field bus
  
  \[ \text{PG/PC} \leftrightarrow \text{CP 5511 / CP 5611 / CP 5613} \leftrightarrow \text{PROFIBUS} \leftrightarrow \text{drives} \]

- Online operation via the MPI interface of SIMATIC S7
  
  \[ \text{PG/PC} \leftrightarrow \text{MPI} \leftrightarrow \text{PROFIBUS} \leftrightarrow \text{drives} \]

If the subsequently listed prerequisites are fulfilled, then online operation can be established between SimoCom U, and all of the drives connected to the bus (“DP slaves 611U”).

Note

When displaying drive-internal values (e.g. position setpoint...) deviations can occur at the last position of the value. This is due to the different rounding-off techniques employed by the conversion programs in the drive and in the “SimoCom U” parameterizing and commissioning tool. However, this has no effect on the computational accuracy in the drive.

Settings for SimoCom U

For SimoCom U, communications via PROFIBUS-DP can be set as follows:

- Options - Settings - Communications --> “Interface” dialog
- For “Go online” connect via set the following:
  --> “PROFIBUS” and
    --> “Direct connection”
      --> if the coupling is directly with the field bus or
    --> “MPI -> PROFIBUS Routing”
      --> if the coupling is via the MPI interface or
    --> “Communication via OPC server” (from SW 6.1)
      --> if the coupling is via OPC server

Then, online operation can be established directly to the drive via the field bus using the “Search for online drives” function.
### Conditions

In order to go online with a drive via the PROFIBUS-DP field bus using "SimoCom U", the following prerequisites must be fulfilled:

1. "SIMODRIVE 611 universal" control board from SW 3.1 with the following option module:
   - Optional PROFIBUS-DP2 module (with ASIC DPC31 without PLL)
     Order No. (MLFB): 6SN1114-0NB00-0Axx
   - or
   - Optional PROFIBUS-DP3 module (with ASIC DPC31 with PLL)
     Order No. (MLFB): 6SN1114-0NB01-0Axx

2. "SimoCom U" parameterizing and start-up tool from version 3.1

3. Communication boards, if connected via PROFIBUS
   - CP 5511 (PROFIBUS connection via PCMCIA card)
     Setup:
     PCMCIA card, type 2 + adapter with 9-pin SUB-D socket connector to connect to PROFIBUS.
     Order No. (MLFB): 6GK1551-1AA00
   - or
   - CP 5611 (PROFIBUS connection through a short PCI card)
     Setup:
     Short PCI card with 9-pin SUB-D socket to connect to PROFIBUS.
     Order No. (MLFB): 6GK1561-1AA00
   - CP 5613 (PROFIBUS coupling via short PCI card)
     (from SW 4.1)
     Setup:
     Short PCI card with 9-pin SUB-D socket to connect to PROFIBUS.
     Diagnostic LEDs,
     PROFIBUS controller ASPC2 StepE
     Order No. (MLFB): 6GK1561-3AA00

4. SIMATIC-CPU, if connected via an MPI interface
   A routing-capable SIMATIC-CPU is required for a coupling via MPI interface.

5. S7-DOS from V5.0
   This software is supplied on the CD for "SIMODRIVE 611 universal" (refer to Chapter 1.3).

6. Cables
   - between CP 5511 or CP 5611 and the PROFIBUS field bus
   - or
   - between the MPI interface from the PG and SIMATIC CPU
3 Parameterizing the Board

3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

**Note**

Going online/offline in cyclic operation via PROFIBUS:

While PROFIBUS is in cyclic operation, SimoCom U with CPxx can be attached or disconnected from the field bus via the following plug-in cable without creating a fault.

Order No. (MLFB): 6ES7901-4BD00-0XA0 (plug-in cable)

---

**Prerequisites with the OPC server (from SW 6.1)**

In order to go online with a drive using "SimoCom U" via an OPC server PROFIBUS-DP, the OPC server must first be installed according to the manufacturers instructions and the following prerequisites must be fulfilled:

- **Hardware**
  - PROFIBUS card must be installed in the PC – cards from third-party manufacturers can also be used
  - Connecting cable
- **Software**
  - Driver software and the associated OPC server for the installed Profibus card
  - Configuring software for the OPC server

Most OPC server/Profibus cards require a bus setting (e.g. baud rate, protocol) – several also require that the existing drives are configured on the bus.

---

**Reader’s note**

Please refer to the documentation of the appropriate manufacturer regarding information on how to configure a PROFIBUS card and OPC server. These procedures depend on the particular manufacturer.

- The OPC server, provided by the manufacturer, offers a possibility of accessing MSAC2 services according to DPV1 (EN50170) including the DataTransport service.

OPC servers that have registered themselves with the system under the Category "Profibus–DPV1–OPC server Version 1.0" fulfill this requirement.

When selecting the interface, SimoCom U offers this OPC server in a separate selection box.
3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

- SimoCom U from Version 6.1

After this configuration of the OPC server has been activated, the access route to "Communications via OPC server" can be set in SimoCom U under "Options/Settings/Communication".

The OPC server to be used should then be selected using the "OPC Configuration" button:

- We recommend that the option "Display all DPV1-OPC-Server" is selected and an OPC server selected from the selection box located below. The OPC servers, which are displayed for this particular selection, guarantee that the utilities (services), required by SimComU, as described in the software prerequisites, are provided.

- If the required OPC server is not listed, but the required utilities (services) are however available, then the button "Display all OPC servers" should be selected, whereby, all of the utilities, installed in the PC which support the OPC, are listed.

- Alternatively, the so-called ClassID of the OPC server can be directly entered under the "Specify OPC server name (only for experts!)".
3 Parameterizing the Board

3.3 Parameterizing using the parameterizing and start-up tool SimoCom U

Example:
SimoCom U via PROFIBUS-DP

\[X423\]

Parameterizing and start-up tool "SimoCom U"

SIMATIC S7-300 (CPU: S7-315-2-DP)

"DP slave 611U"
Assumptions:
2-axis board
P0918 (node address) = 15

"DP slave 611U"
Assumptions:
1-axis board
P0918 (node address) = 16

"DP slave 611U"
Assumptions:
2-axis board
P0918 (node address) = 17

Fig. 3-11 SimoCom U via PROFIBUS (example with 3 control boards)
# Commissioning

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<th>Page</th>
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</tr>
</tbody>
</table>
4.1 General commissioning information

The following differentiation is made when commissioning the "SIMODRIVE 611 universal" control board:

- **First commissioning**
  
  If there is still not a matching parameter set for the drive, then the drive must be commissioned for the first time.

  The drive can be commissioned for the first time using
  
  - the SimoCom U tool (refer to Chapter 4.3.1)
  - the display and operator unit (refer to Chapter 3.2.1)

- **Series commissioning**
  
  An existing data set can be transferred to the control board via the SimoCom U tool (refer to Chapter 4.3.2).

  Examples:
  
  - Several systems having the same configuration and functions are to be commissioned.
    
    For the first system, a first commissioning must be executed, and for additional systems, a series commissioning.
  
  - Replacing a control board.

---

**Note**

- SimoCom U is a start-up tool for "qualified commissioning personnel"

- **SimoCom U has neither been designed nor is suitable for operational control of the system!**

- When called via several PCs, only that PC displays modified data, from which the changes were also made!

---

**Note**

The original status of the board when shipped can always be re-established as follows:

- **via P0649 = 1 (from SW 3.1)**

- **via the SimoCom U tool using the "boot board" function (from version 03.03)**
Prerequisites for commissioning

The SIMODRIVE 611 universal control board can be commissioned the fastest if the following prerequisites are checked and fulfilled before commissioning is started:

Table 4-1 Prerequisites for commissioning

<table>
<thead>
<tr>
<th>The following conditions must be fulfilled before commissioning!</th>
<th>OK</th>
</tr>
</thead>
<tbody>
<tr>
<td>The SIMODRIVE drive group has been configured.</td>
<td></td>
</tr>
<tr>
<td>The wiring has been completed.</td>
<td></td>
</tr>
<tr>
<td>The Order numbers (MLFBs) of the power module, motor and encoder are known.</td>
<td></td>
</tr>
<tr>
<td>Checks for the supply infeed module (NE module)</td>
<td></td>
</tr>
<tr>
<td>Switch S1: Check the settings of this switch at the NE and monitoring module (e.g.: Has the line supply voltage been set to 400 V or 480 V?)</td>
<td></td>
</tr>
<tr>
<td>Reference: /PJU/, SIMODRIVE 611 Configuration Manual, Drive Converters</td>
<td></td>
</tr>
<tr>
<td>The system has been prepared so that it can be powered-up.</td>
<td></td>
</tr>
</tbody>
</table>

Check list for commissioning

The following checklist should help you to simply commission the components that we supplied, and to also guarantee a high availability when used in conjunction with your product:

- Observe all of the ESD measures when handling components.
- All screws are tightened to the correct torque. Pay special attention to the DC link bolt connections (1.8 Nm torque).
- All connectors are correctly attached and locked/screwed in place.
- Screw the control components into the power module.
- Observe the power-on sequence in the Configuration Manual.
- If the equipment is powered up and down too frequently, the DC link pre-charging circuit will be inhibited. This can only be re-charged again after a cooling time of several minutes (e.g. 4 minutes) with the line supply disconnected (powered down).
- Are there line supply/motor contactors connected to the drive converter? It is only permissible to switch these when they are in a no-current condition.
- All components are grounded and correctly shielded.
- Connection X131 is grounded.
- The load capability of the central power supply system is not exceeded.
- Only discharge the unit at the DC link buses through a minimum of 20 Ω.
4 Commissioning

4.1 General commissioning information

- The units are designed for the specified mechanical, climatic and electrical ambient conditions. None of the limit values may be exceeded in operation nor during transport. Please pay special attention to the following:
  - Line supply conditions
  - Pollutants
  - Damaging gases
  - Ambient climatic conditions
  - Storage/transport
  - Shock load
  - Vibratory load
  - Ambient temperature
  - Total (summed) current of the digital outputs (refer to Chapter 2.3)

Reader's note
More detailed information on the drive group and the ambient conditions is provided in:

Reference: /PJU/ SIMODRIVE 611 Configuration Manual, Drive Converters

Caution
General rule: Before powering up or down using the main switch or a line contactor, terminal 63 (pulse enable) and/or terminal 48 (start terminal, contactor control) must be de-energized or disconnected at the supply infeed module (NE module!)

Otherwise, there is a danger that the line supply infeed module will be destroyed.

Upgrading the firmware of the optional PROFIBUS module
In order that the optional PROFIBUS module can be upgraded error-free, the cyclic PROFIBUS connection must interrupted. In this case, the physical connection must also be interrupted, i.e. the PROFIBUS connector must be withdrawn.

The firmware cannot be upgraded while data is being transferred via the PROFIBUS.

Note
If the firmware is updated via PROFIBUS-DP and is then interrupted, the firmware can only be downloaded via the serial link. This is the case for the existing software releases < SW 4.1 or ≥ SW 7.2.
4.2 Booting "SIMODRIVE 611 universal"

General

When booting, a differentiation is made as to whether the drive was already commissioned.

- Still not commissioned
  ⇒ The drive requests a commissioning routine
  → refer to Chapter 4.3.1 or 3.2.1

- Already commissioned
  ⇒ When in an error-free condition, the drive runs up until the following is displayed

\[ \_\_\_\_\_\_\_\_run \]

Reader’s note

Information regarding fault/error handling and diagnostics is provided in Chapter 7.

---

**Fig. 4-1** Booting "SIMODRIVE 611 universal"

---

**Note:**

Faults/errors which occur when booting are displayed flashing in the display unit.

---

**Display unit**

START

Power-up the "SIMODRIVE 611 universal"
Run-up starts

<table>
<thead>
<tr>
<th>Already commissioned?</th>
</tr>
</thead>
<tbody>
<tr>
<td>No</td>
</tr>
</tbody>
</table>

- Carry-out commissioning (e.g. specify the power module, motor, encoder, etc. refer to Chapter 4.3.1 or Chapter 3.2.1)

- The red LED is bright approx. 2 s

- "\_\_\_\_\_\_\_\_run" is displayed
  The red LED is dark

- The system has been successfully booted. The drive is now in cyclic operation

END
4.3 Commissioning via SimoCom U

Requirements

The following prerequisites must be fulfilled in order to be able to commission a drive using the "SimoCom U" parameterizing and start-up tool:

1. All of the prerequisites for commissioning, according to Chapter 4.1, have been fulfilled, i.e. the system with "SIMODRIVE 611 universal" can be commissioned.

2. The checklist for commissioning according to Chapter 4.1 has been checked.

3. The "SimoCom U" tool is installed on the PC/PG, which is to be used to commission the drive.

4. There is a connecting cable between the PG/PC and the control board (e.g. RS232 connecting cable, refer to Chapter 2.5).

5. The PC/PG with "SimoCom U" is connected to the control board (X471).

Reader’s note

- Cable diagrams for the connecting cable refer to Chapter 2.5
- Installing "SimoCom U", Introduction to "SimoCom U" and establishing online operation refer to Chapter 3.3
4.3.1 First commissioning with SimoCom U

When “SIMODRIVE 611 universal” is first commissioned using the "SimoCom U" parameterizing and start-up tool, proceed as follows:

1. Power-up the drive group
2. Start SimoCom U
3. Request online operation for drive A
   Operator action:
   Execute the "Search for online drives" function in the "Start-up" menu, and select drive A in the "Drive and dialog browser".
   Is the "start-up required" window displayed?
   - Yes: --> Start the drive configuration assistant
     --> This signals the drive the existing configuration (power module, motor, etc.).
   - No: --> Press "re-configure drive" button
     --> This adapts the control board to the present configuration (power module, motor, etc.).

4. Execute the drive configuration, and at the end, press the "Calculate controller data, save, reset" button.

5. Carry-out basic commissioning
   Set the "Drive and dialog browser" (left-hand window) to "Parameter". To do this, press the "P Par" button below the browser.
   The commissioning is now executed by working through the remaining dialog boxes for this drive in the "Drive and dialog browser" from the top to the bottom. The required settings are made in the selected dialog boxes.

Note
If drive B is to be commissioned, then the points must be executed for drive B from point 3 onwards.
4.3 Commissioning via SimoCom U

4.3.2 Series commissioning with SimoCom U

Procedure for series commissioning

For series commissioning of "SIMODRIVE 611 universal" with the "SimoCom U" parameterizing and start-up tool, proceed as follows:

1. Power-up the drive group
2. Start SimoCom U
3. Request online operation for drive A

Operator action:
Click on the "Search for online drives" in the "Start-up" menu, and select "Drive A" in the selection box.

Is the "start-up required" window displayed?
- Yes:
  --> Click on the "Load parameter file into the drive..." button
  --> After you have selected the required parameter file for drive A and have pressed "open", the file is downloaded into drive A.
- No:
  --> Click on the menu "File --> Load into drive --> Load and save in the drive"
  --> After you have selected the required parameter file for drive A and have pressed "open", the file is downloaded into drive A.

Note
If drive B is to be commissioned, then the points must be executed for drive B from point 3 onwards.
4.3.3 Password protection with SimoCom U (from SW 8.1)

**General information**

Access protection using a password is possible in order to ensure that when service is carried-out the drive configuration is not changed.

The "SimoCom U" parameterizing and start-up tool has a password input and change view in order to carry-out the following on a connected drive:

- Activate/de-activate the password protection
- Define the password
- Define the functions that are to be protected using the password

For a series commissioning, the password and the password configuration are transferred to the drive just like any other parameter assignment.

The password is not necessary to do the following:

- Open files
- Downloading files into a drive

The password must only be entered if the protected functions are to be accessed in the file or in the drive.

SimoCom U allows the password function to be copied between several drives.

**Note**

The function "Password protection" only functions with a "SimoCom U" parameterizing and start-up tool version ≥ 8.1.

**Procedure when setting-up the password**

Proceed as follows when setting-up a password using the "SimoCom U" parameterizing and start-up tool:

1. Power-up the drive group
2. Start SimoCom U
3. Request that the required drive either goes into the offline or online mode
4. In the "drive and dialog browser" (left-hand window), select the "password" folder
5. Access to enter a PIN and browser to enter the functions to be protected is activated by a "check" in the "Activate password protection" field (right-hand window)
6. Enter a PIN (4-digit number from 1000...9999) and acknowledge
7. Define the functions to be protected
   --> The safety-relevant functions are displayed in
   the "right-hand" display window (browser) with a "check" in
   the particular field (default setting).
   --> Further, additional functions can be assigned password
   protection by activating the button "Activate all functions"
   or by entering a "check" in the field of the function to be
   protected.

8. Press the "Accept password configuration" button
9. Save the changes

---

**Note**
The "Activate safety-relevant functions" and "Activate all functions"
buttons should only be pressed when actually required.

---

**Access protection**
Individual functions (operator masks, menu items, ...) can be protected
or enabled.

The following safety-relevant functions are set as default values:
- Expert List
- Load to drive
- Reconfigure drive
- Establish the standard values of the current drive configuration
- Upgrade firmware
- User parameter list

**Access with SimoCom U <Version 8.1**
The drive inhibits write access operations via SimoCom U <Version 8.1
and outputs a warning.

In order to be able to change the drive in any way, a
SimoCom U ≥Version SW 8.1 must be used.

**Access via the 7-segment display**
The drive inhibits all access operations via the 7-segment display. The
7-segment display is then only used to display " _ _ _ run" or warnings
and alarms that are present.

**Access via data bus**
Access operations via PROFIBUS-DP, CAN bus and other unlisted
modules are not prevented, as in the normal operating state of the ma-
chine, these channels cannot be manipulated by the operator.
Enable the access  You can access a password-protected function via SimoCom U as follows:

1. In the online mode, SimoCom U prompts for the password.  
   --> Enter password

2. All of the protected functions in the "right-hand" browser of the menu screen can now be changed.

3. After entry, the password remains valid up to the next time that SimoCom U goes online.

4. The protected functions cannot be accessed if the password was not entered.

5. If the password was incorrectly entered five times in a row, then SimoCom U must be re-started before the password can be re-entered.

Password forgotten?  The drive must be deleted using "delete drive configuration" or "boot board". This deletes the complete parameterization.

Note

Before activating password protection using SimoCom U, we recommend that the functioning configuration of the drive is saved in a file.

There is no generally-valid password!

Password protection and other programs with SimoCom U

When using A&D Data Management (ADDM) and other programs, that SimoCom U uses, then password protection may not be activated.
4.3.4 Upgrading the firmware

Runtime behavior

In order to take into account technical advances, the drive firmware is continually being further developed with each software release.

In spite of the fact that the firmware is optimized regarding its runtime behavior, it cannot be excluded that more recent firmware releases will have a different runtime behavior. This must be especially taken into account if functions are used that require a high level of runtime.

When upgrading control boards to a new firmware release, it must therefore be carefully checked as to whether the runtime behavior is satisfactory. If required, re-optimize the drive parameterization or do not upgrade the firmware!

In order to be able to optimally use new firmware releases with respect to the runtime behavior, we recommend that the latest hardware is always used.

4.3.5 Firmware download

Firmware can be downloaded using the “SimoCom U” parameterizing and commissioning tool.

Procedure:

Under the menu item: Options / Service / .... select required firmware upgrade item...., then follow the user prompting.

For a connection via PROFIBUS-DP, e.g. PC as Master Class 2 on the bus, only an update or download is possible to any status of the drive firmware (e.g. SW 7.2).

For a connection via the RS 232 interface, it is also possible to download the firmware of the Profibus module.

Notice

Under no circumstances interrupt or exit the update as otherwise it is possible that the module will no longer be able to be identified and addressed!
4.3.6 Automated firmware download (from SW 8.1)

General
Automated firmware download is possible using the "SimoCom U" parameterizing and start-up tool.

This means that both the actual firmware as well as also the previous version releases (e.g. SW 7.2) can be downloaded.

"SimoCom U" is configured for the appropriate drive using registry files.

Data can be downloaded via the data bus (e.g. PROFIBUS-DP) or the serial interface.

Condition

- When downloading via PROFIBUS-DP, the correct PROFIBUS node address must be parameterized for the appropriate drive.
- The registry files must be edited so that they match a specified drive configuration.
- It is necessary that "SimoCom U" was installed – however, the application may not run while changing or running the registry file.

Proceed as follows

1. Edit the .reg file and carry-out the settings (refer to Fig. 4-2).
   If you wish to only change the file names, the path or the PROFIBUS address, then the settings are also possible via SimoCom U without using the .reg files.
   - Using the dialog menu “Service” --> "Automated firmware download" --> "Define file" or "Options" --> "Settings" --> "Communications"

2. Run the .reg file if you have not carried-out the settings via SimoCom U.
   - The Windows registry editor prompts after the settings have been transferred into the registry.
   - Acknowledge with "Enter".
   - The Windows registry editor signals that the settings have been successfully transferred into the registry
   - Again acknowledge this message with "Enter".
4.3 Commissioning via SimoCom U

3. Go online with SimoCom U
   --> Press CTRL+H to download the firmware
   --> SimoComU prompts you as to whether you wish to download
       the firmware into your drive.
   --> Acknowledge this using the "Enter" key

4. A "display window" shows the firmware being downloaded
   --> A drive reset is requested once the download has been
       successfully completed.
   --> Acknowledge this using the "Enter" key

5. Wait until the drive is again online and then check that the system is
   correctly operating.
   --> Then close SimoCom U
       (key combination CTRL+ALT+Shift+F12).

Note
• In order to upgrade or downgrade several drives, you will require
  ."reg" files for each drive with the matching
  PROFIBUS address. Repeat all of the steps from the beginning to
  the end for each drive for which you wish to download the matching
  firmware.
• In order to download via the serial interface, an appropriate
  connection must be established and the line
  "PortType"=dword:00000004
  changes into
  "PortType"=dword:00000001,
  --> refer to the text example in the diagram 4-2.
  The information in the ProfibusAdresse" line is ignored.
• When retrograding the drive to an older firmware release, it must be
  noted that after downloading the system firmware and running-up
  the module, it may be necessary to re-commission the drive.
4.4 Commissioning using the display and operator unit

1. Axxxx, bxxxx: Parameters, drive A, B
2. Only set, if there is no automatic power module identification available (refer to Chapter 4.6)
3. The parameter value is changed using these keys
4. If drive B is not used, then b0700 = 0 (drive B inactive) and b0659 = 0 -> 1 (boot)
5. Set the PROFIBUS node address --> refer to Chapter 5.7.2

Fig. 4-3 Commissioning using the display and operator unit (Part 1 of 3)
4.4 Commissioning using the display and operator unit

Fig. 4-4 Commissioning using the display and operator unit (Part 2 of 3)
4.4 Commissioning using the display and operator unit

![Flowchart](image)

**Reader’s note**

What is an unlisted motor?

A motor, which is not defined using a motor code number, and is therefore also not in the Attachment (refer to Chapter A.3.1, A.3.4 and A.3.5) is classified as an unlisted motor.

The motor can be supplied from Siemens or from another motor manufacturer.

To commission an unlisted motor, the associated parameters are required (refer under the index entry “Unlisted motor – parameters for...”).
### 4.5 Function-initiating and diagnostic parameters

#### Function-initiating parameters

<table>
<thead>
<tr>
<th>Parameter</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Delete parameters, drive A and B</td>
<td>0649</td>
<td>(from SW 3.1)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>–</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td></td>
<td>... all of the parameters can be deleted in the memory module FEPROM (user data). After these parameters have been deleted, the status of the control board when it was first supplied is re-established.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>0 Standard value</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>1 All of the parameters should be deleted (establish the status when first supplied)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Procedure when deleting all parameters:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Switch-out the pulse and controller enable (e.g. via terminal 663, 65.A and 65.B)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Remove write protection (P0651 = 10\text{Hex}, only for the display and operator unit)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Activate that all parameters are deleted in the FEPROM (P0649 = 1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Write into the FEPROM (P0652 = 1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Carry-out a HW power-on reset</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>After booting, the board status when originally supplied is re-established.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Read and write protection</th>
<th>0651</th>
<th>0</th>
<th>0</th>
<th>10</th>
<th>Hex</th>
<th>immediately</th>
</tr>
</thead>
<tbody>
<tr>
<td>This defines which parameters can be read (visible) or can be written into.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 Parameters for standard commissioning (operator prompting) can be read</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 Parameters for standard commissioning (operating prompting) can be read and written into</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>2 All parameters can be read</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>4 All parameters can be read and written into</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(Exception: Motor data parameters cannot be written into)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>8 Motor data parameters can be read and written into</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>10 All parameters (including motor data parameters) can be read and written into</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Note: Read and write protection is only of significance when parameterizing the display and operator unit.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Transfer into the FEPROM</th>
<th>0652</th>
<th>0</th>
<th>0</th>
<th>1</th>
<th>–</th>
<th>immediately</th>
</tr>
</thead>
<tbody>
<tr>
<td>This means that parameter values can be transferred from the RAM into the FEPROM.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 --&gt; 1 The parameter values in the RAM are written into the FEPROM</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The parameter is automatically set to 0 at the end of the data save operation.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 Data is being saved - other parameters cannot be selected</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Note: Writing to the FEPROM memory depends on the particular manufacturer and is physically limited to between (10^5) and (10^6). In order that the maximum number of write operations is not exceeded in the operational period, automatic, cyclic back-up operations are only permissible at time intervals that are adequately long enough.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### 4.5 Function-initiating and diagnostic parameters

#### Table 4-2  Function-initiating parameters, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0659</td>
<td>Boot</td>
<td>0</td>
<td>0</td>
<td>4</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>

... it is possible to toggle between the boot and standard state.

0 Establish the boot state
Sequence:
- Remove write protection (P0651 = 4), establish the boot state (P0659 = 0), write into the FEPROM (P0652 = 1), hardware POWER-ON RESET
- Only the following parameters can be selected and changed in the boot state (first commissioning):
  - P1106 (power module code number), if it was not automatically identified
  - P1102 (motor code number)
  - P1006 (IM encoder code number)
  - P0700 (operating mode)
  - P0918 (PROFIBUS node address)
  - P0659 (boot), execute in the sense of a boot

0 → 1 Boot
All of the parameters, which are not listed above, are appropriately pre-set (default) standard values or are preset as a result of internal "calculate controller data" routine.

1 Standard state
The standard values are loaded. The motor code and power module code are write-protected. The boot state can be re-established (with P0659 = 0).

2, 3, 4 Internal Siemens

| 1080| Calculate controller data  | 0    | 0        | 1    | -    | immediately |

Using this function, suitable settings for the control parameters are calculated from the motor parameters and several other parameters.

0 → 1 The controller data is being calculated, the function is active
0 Function inactive or exited error-free

**Note:**
- Recommendation: Execute this function with SimoCom U, as the calculated parameters are then displayed, and are only transferred and overwritten after acknowledgment.
- At the end of the calculation, the parameter is automatically reset to 0 or a fault code is written into it.
- If there is an error condition, the parameters for current, flux and speed controller were not able to be optimally pre-assigned. Standard values were entered.

The function can be re-started after the error cause has been removed.

**Fault code:**
- -15 Magnetizing reactance (P1141) = 0
- -16 Leakage reactance (P1139/P1140) = 0
- -17 Rated motor frequency (P1134) = 0
- -18 Rotor resistance (P1138) = 0
- -19 Motor moment of inertia (P1117) = 0
- -21 Speed at the start of field weakening (P1142) = 0
- -22 Motor standstill current (P1118) = 0
- -23 The ratio between the maximum motor current (P1104) and the motor standstill (stall) current (P1118) is greater than the maximum value for the torque limit (P1230) and the power limit (P1235)
- -24 The ratio between the rated motor frequency (P1134) and the rated motor speed (P1400) is not permissible (pole pair number)
4.5 Function-initiating and diagnostic parameters

Table 4-2  Function-initiating parameters, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1081</td>
<td>Calculate the equivalent circuit diagram data (ARM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>–</td>
<td>immediately</td>
</tr>
</tbody>
</table>

1  Equivalent circuit diagram data is calculated, the function is active
0  Inactive or exited fault-free

Procedure for unlisted motors:
- Select "unlisted motor" when commissioning the system for the first time (refer to Chap. A.3)
- Enter all rating plate data
- Calculate the equivalent circuit diagram data via P1081 = 1
- Calculate the unlisted motor via P1082 = 1

Note:
- At the end of the calculation, the parameter is automatically reset to 0 or a fault code is written into it.
- Under fault conditions, the equivalent circuit diagram data are not changed (exception: Coding -56).
  The function can be re-started after the cause of the fault has been removed.

Fault code:
-51  Rated motor power (P1130) = 0
-52  Rated motor voltage (P1132) = 0
-53  Rated motor current (P1103) = 0
-54  \( \cos \varphi \) (P1129 = 0 or > 0.996)
-55  The ratio between the rated motor frequency (P1134) and the rated motor speed (P1400) is not permissible (pole pair number)
-56  Warning: Speed at the start of field weakening (P1142) < Rated motor speed (P1400)
-57  The function is only only permissible for unlisted motors (P1102 = 99)

| 1082| Calculate unlisted motor | 0 | 0 | 1 | – | immediately |

... the "Calculate unlisted motor" function is started. Parameters P1105 (only SRM), P1147, P1241, P1401 are pre-assigned, the "Calculate controller data" function executed and the appropriate unlisted motor code entered into P1102.

By entering the unlisted motor code in P1102, at the next POWER ON, motor data which were possibly changed, are no longer overwritten by the catalog motor data (previous motor code).

0  Inactive
1  Calculate unlisted motor

Procedure:
Are all equivalent circuit diagram data known?
- if no: Calculate the equivalent circuit diagram data via P1081 and set P1082 to 1
- if yes: Enter all of the equivalent circuit diagram data and set P1082 to 1

Note:
At the end of the calculation, the parameter is automatically set to 0, or an error code is written into it (refer to the "calculate controller data" function, P1080).

| 1083| Function selection, motor data optimization (ARM) | 1 | 1 | 4 | – | immediately |

... specifies the function number for the motor data optimization.
1  Determine the leakage inductance and rotor resistance
2  Determine the no-load current and magnetizing reactance
3  Determine the speed at field weakening
4  Determine the moment of inertia
4.5 Function-initiating and diagnostic parameters

Table 4-2  Function-initiating parameters, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1084</td>
<td>Start motor data optimization (ARM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... starts the "motor data optimization" function, which is set in P1083.

0  Inactive or exited fault-free
1  Start motor data optimization

**Note:**
At the end, 0 or a fault code is automatically written into the parameter.

**Fault code:**
- 2  A pulse frequency (P1100) of 4 kHz or 8 kHz is required
- 3  Controller/pulse enable missing
- 4  Speed setpoint <> 0
- 5  Motor is presently being changed-over
- 6  Error when determining the leakage inductance (result) < 0
- 7  V/f mode is active
- 8  The incorrect motor was selected because of the motor changeover
- 9  Parameterized maximum speed is too low for the measurement
-11  Changeover speed, open-loop/closed-loop control is too high (P1466)
-12  Speed range too low (P1466 or P1160 too high)
-13  Ramp-function generator enable missing
-14  Open-loop torque controlled mode is selected
-15  Motor data optimization for the listed motor not permissible (from SW 3.3)
-16  Excessively high current results in limiting by the i2t power module model

---

**Diagnostic parameters**
Diagnostic parameters are display parameters, i.e. they can only be read.

The following parameters are used for diagnostics:

Table 4-3  Diagnostic parameters

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0599</td>
<td>Active motor data set (from SW 2.4)</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates whether the motor changeover has been enabled, or which motor data set is active.

0  Motor changeover inhibited (P1013 = 0)
1  Motor data set 1 (P1xxx) active
2  Motor data set 2 (P2xxx) active
3  Motor data set 3 (P3xxx) active
4  Motor data set 4 (P4xxx) active

**Note:**
Motor changeover is described in Chapter 6.11.
### 4.5 Function-initiating and diagnostic parameters

#### Table 4-3 Diagnostic parameters, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0600</td>
<td>Operating display</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the actual operating status of the unit.

#### Motor type
- Synch. motor, standard
- Induction mot., standard
- Induction motor, no encoder, open-loop contr.
- Induction motor, no encoder, closed-loop contr.
- Synchronous motor, field-weakening operation
- Synchronous motor, linear

#### Operating state
- Drive not enabled
- Speed-controlled operation
- Open-loop torque controlled operation
- V/f mode
- Positioning mode
- Point lit "PROFIBUS has the master function"
- Point flashes "clock-synchronous operation active"

#### Equipment status
- All enable signals present, motoring
- All enable signals present, generating
- Setpoint enable missing (STW1.6)
- Ramp-function generator enable missing
- Controller enable (terminal 64 or 65.x) missing
- Module-specific, pulse enable (terminal 633) missing
- Central enable (terminal 63 or 46) missing or a fault is present
- Power-on inhibit present
- Inverter enable missing (STW1.3)
- ON/OFF 1 missing (STW1.0)
- Enable/Off 2 missing (STW1.1)
- Operating condition/Off 3 missing (STW1.2) or no control requested (STW1.10)
- Drive is inactive or the parking axis has been selected
- Point is lit "wait for the signal edge, "motor changed over" (STW2.11)

#### Parameter set 0 ... 7
- Parameterized speed setpoint source
  - F: Fixed setpoint
  - A: Analog
  - O: Digital
- n-set operating mode pos
  - Trav. block
  - Permanent running coupling
- Activate traversing task (edge)
- Intermediate stop
- Reject traversing task
- Referencing running
- Reference point still not approached
- Follow-up mode
- Jogging 1/2
- Override is zero
- Traversing to fixed stop
- MDI active
- Point lit "wait for an external block change"

#### Freely parameterizable output terminals (standard assignment for n-set)
- O3.x: Motor temperature pre-warning
- O1.x: Ramp-up completed
- O0.x: Ready or no fault
- O2.x: \(|n_{act}| < n_{min}\)

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Additional parameters for diagnostics (refer to Chapter A.1)

The following additional parameters are available for diagnostics:

- P0653 Image, input signals, Part 1
- P0654 Image, input signals, Part 2
- P0655 Image, input signals, Part 3 (from SW 3.3)
- P0656 Image, output signals, Part 1
- P0657 Image, output signals, Part 2
- P0658 Image, output signals, Part 3
- P0678 Image of the input terminals
- P0698 Image of the output terminals
4.6 Parameters for hardware, operating mode and clock cycles

The drive must identify the hardware used (motor, power module and encoder) so that it can behave appropriately. The hardware can only be identified when the drive is in the booted state.

- Specifying the hardware with the display and operator unit
  In order to specify the motor, power module and encoder used, the appropriate code must be determined from the tables, using the Order No. (MLFB) and entered in the parameter.

- Specifying the hardware with SimoCom U
  The motor, power module and encoder are selected from a list using the relevant Order numbers (MLFB). The appropriate code is then automatically entered.

Caution

A power module could be destroyed for the following reasons:

- Incorrect power module code or motor code
- Incorrect motor data
- Inverter clock frequency or current controller gain too high

Procedure when first commissioning an unlisted motor (also refer to Chapter 3.2.1):

- Select "unlisted motor", e.g. synchronous or induction motor
- Enter all of the rating plate data, and if known, all of the equivalent circuit diagram data. The equivalent circuit diagram data can also be calculated using parameter P1081.
- Set parameter P1082 "Calculate unlisted motor". This means that the controller data is internally calculated and the motor code number corresponding to the motor type is saved.

Which power modules have an automatic identification function?

Only power modules from a specific hardware version have the automatic power module identification function (refer to Order No.).
4.6 Parameters for hardware, operating mode and clock cycles

Power module (Order No.) Automatic identification?

- 6SN112—□—□—□—□—□—□  No automatic identification
- from 6SN112—□—□—□—□—□—□  Automatic identification

☐ Space retainer for the Order No.

After the first commissioning, a value is in P1106 (power module code No.) which corresponds to the particular power module.

An automatic power module identification routine is executed each time that the control board boots. In this case, the value in P1106 is compared with the value of the power module identified in P1110.

If the values are not the same, there is an error condition, and an appropriate fault message is signaled.

---

### Table 4-4 Hardware parameters

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1102</td>
<td>Motor code number</td>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The motor code number defines the connected motor.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The motor code of the existing motor is located in the following lists:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- for rotating synchronous motors (SRM) --&gt; refer to Chapter A.3.1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- for permanent-magnet synchronous motors with field-weakening (1FE1 motor, PE spindle, from SW 3.1) --&gt; refer to Chapter A.3.2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- for linear synchronous motors (SLM) --&gt; refer to Chapter A.3.4</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- for induction motors (ARM) --&gt; refer to Chapter A.3.5</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- At the first commissioning and at each POWER ON, the motor data are pre-assigned according to the entered motor code (Exception: unlisted motor).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- For unlisted motors, the parameters must be manually assigned (refer to Chapter A.3).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1106</td>
<td>Power module code number</td>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The power module code number defines the power module used.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The power module code can be determined from a list (refer to Chapter A.2).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- It is not necessary to select power modules with automatic identification.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1006</td>
<td>IM encoder code number</td>
<td>0</td>
<td>0</td>
<td>65 535</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The encoder code number describes the connected encoders.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The encoder code number can be determined from a list (refer to Chapter A.4).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- At the first commissioning and at each POWER ON the encoder data are pre-assigned corresponding to the entered encoder code number (Exception: Unlisted encoder).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- For unlisted encoders, the parameters must be manually assigned (refer to Chapter A.4).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
4.6 Parameters for hardware, operating mode and clock cycles

Parameters for the operating mode

The operating mode of “SIMODRIVE 611 universal” is set using P0700 (operating mode).

It is not possible to change over the operating mode in the powered-on status, as the parameter only becomes effective after POWER ON.

Table 4-5 Parameters for the operating mode

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0700</td>
<td>Operating mode</td>
<td>0</td>
<td>1</td>
<td>3</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>

- 0: Drive inactive only drive B)
  This means that a double-axis module can only be operated in the single-axis mode. Should there be no communications with the inactive drive B via PROFIBUS? If yes, then communications must be disabled using P0875 = 0.

- 1: Speed/torque setpoint (refer to Chapter 6.1)
  In this mode, the drive can be operated in the following operating states:
  - closed-loop speed controlled mode ($n_{set}$ mode)
  - open-loop torque controlled mode ($M_{set}$ mode)
  - torque reduction ($M_{Red}$)

- 2: External position reference value (from SW 3.3)
  No longer available from SW 4.1. Select the positioning mode.

- 3: Positioning (from SW 2.1, refer to Chapter 6.2)
  Traversing blocks can be selected and executed in this operating mode.
  Every traversing block can be freely parameterized, and in addition to the block number, it also contains additional data, e.g. target position, acceleration, velocity, command and block enable circuit.

Note:
- The drive can be operated in the "speed/torque setpoint" mode and "positioning" modes via terminals or via PROFIBUS-DP or mixed (refer to Chapter 5.4).
- For operation with PROFIBUS-DP:
  - Operating mode: Overview of process data
  - Speed/torque setpoint: (refer to Chapter 5.6.1)
  - Positioning (from SW 2.1): refer to Chapter 5.6.1
For "SIMODRIVE 611 universal", the clock cycles (current controller, speed controller, position controller and interpolation clock cycles) are set as standard, and generally do not have to be changed.

However, the speed controller dynamic performance can be further enhanced by reducing the clock cycle times (current controller and speed controller clock cycles).

**Note**

In standard operation, use the standard clock cycle settings.

After the clock cycles have been changed, the "calculate controller data" function (P1080 = 1) should be executed.

### Table 4-6 Parameters for clock cycles

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>Current controller clock cycle</td>
<td>2</td>
<td>4</td>
<td>4</td>
<td>31.25 µs</td>
<td>PO</td>
</tr>
<tr>
<td>1001</td>
<td>Speed controller clock cycle</td>
<td>2</td>
<td>4</td>
<td>16</td>
<td>31.25 µs</td>
<td>PO</td>
</tr>
<tr>
<td>1009</td>
<td>Position control cycle</td>
<td>32</td>
<td>32</td>
<td>128</td>
<td>31.25 µs</td>
<td>PO</td>
</tr>
<tr>
<td>1010</td>
<td>Interpolation cycle</td>
<td>64</td>
<td>128</td>
<td>640</td>
<td>31.25 µs</td>
<td>PO</td>
</tr>
</tbody>
</table>

The clock cycles are derived from the basic hardware clock cycle (31.25 µs). When changing the clock cycles, the data in the following tables and the associated limitations must be observed.

<table>
<thead>
<tr>
<th>Current ctr clk cycle P1000</th>
<th>Speed ctr clk cycle P1001</th>
<th>Position ctr clk cycle P1009</th>
<th>Interpolation clk cycle P1010</th>
<th>Clock cycles Values</th>
</tr>
</thead>
<tbody>
<tr>
<td>4 (125 µs)</td>
<td>4 (125 µs)</td>
<td>32 (1 ms)</td>
<td>128 (4 ms)</td>
<td>Standard</td>
</tr>
<tr>
<td>2 (62.5 µs)</td>
<td>2 (62.5 µs)</td>
<td></td>
<td></td>
<td>Possible values</td>
</tr>
<tr>
<td>4 (125 µs)</td>
<td>4 (125 µs)</td>
<td></td>
<td></td>
<td>(also refer to</td>
</tr>
<tr>
<td>8 (250 µs)</td>
<td>4 (125 µs)</td>
<td></td>
<td></td>
<td>Limitations)</td>
</tr>
<tr>
<td>12 (500 µs)</td>
<td>4 (125 µs)</td>
<td></td>
<td></td>
<td>Tip: 31.25 µs • 32 = 1 ms</td>
</tr>
</tbody>
</table>

**Limitations:**

- The clock cycles for both active axes must be set the same on a control board.
- **Curr. ctr clk cycle:** for 2 active axes and positioning, 62.5 µs is not permissible
  - From SW 8.3: for "SIMODRIVE universal HRS" control board, 62.5 µs for 2 active axes and positioning, permissible
- **Speed ctr clk cycle:** Speed controller clock cycle ≥ Current controller clock cycle for 2 active axes, 62.5 µs is not permissible
- **Pos. ctr clk cycle:** must be an integer multiple of the speed contr. clock cycle
- **Interpolation cycle:** must be an integer multiple of the position contr. clock cycle
4.7 Induction motor operation with induction motor

4.7.1 Description

**IM operation**

The IM function permits pure encoderless operation (IM operation) or mixed operation (encoderless operation/operation with encoder), $P1465 = 0$.

The induction motor operation for a "SIMODRIVE 611 universal" drive is used for 4-quadrant closed-loop speed control of induction motors without speed or rotor position encoder.

Induction motor operation permits higher demands to be fulfilled regarding the dynamic control performance and the stall immunity of conventional converter drives with V/Hz characteristic control. Compared to drives with rotor position encoder, the speed accuracy is somewhat lower and therefore it must be taken into account, that in the lower speed range, the dynamic response and smooth running characteristics will deteriorate.

**Applications**

IM (Induction Motor) operation is used, e.g. in the area of special high-speed motors, for grinding applications and for drives for punches and presses.

MSD mode:

MSD mode with encoder is for high speed accuracy, dynamics and positioning, $P1465 > n_{max}$.

Application: Spindles, spindle positioning

**Closed-loop control**

As the dynamic performance in IM operation is less than MSD operation with encoder, a speed-torque-frequency pre-control is implemented to improve the control dynamic performance.

This pre-control is only active in induction motor operation. It pre-controls, with information about the drive torque, taking into account the existing torque and current limits and the load (motor – $P1117 + load – P1123:8$ (from SW 2.4)), the torque required for a particular speed change, in the fastest possible time.

This means, that when correctly parameterized, overshoot is prevented and the controlled dynamic performance is enhanced.

For the torque pre-control, a smoothing time can be parameterized via $P1459$.

The speed controller is parameterized for induction motor operation using $P1451$ and $P1453$ due to the low dynamic performance.

In the low speed range, for pure induction motor operation, the actual speed, the orientation and the actual flux can no longer be calculated. This is due to the accuracy of the measured values and the parameter sensitivity of the technique. Thus, an open-loop current/frequency control is selected.

The changeover threshold is parameterized using $P1466$, whereby a 5 % hysteresis is implemented.

In order to be able to accept a high load torque, even in the open-loop controlled range, the motor current can be increased via $P1458$. 

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Note
The value in MD 1458 should be taken into account when
dimensioning the power section, particularly in those cases where the
controlled operational state lasts for a long time. The maximum current
specified with MD 1458 is also used with low speeds and torques; this
can lead to long-term damage or to a power section whose
dimensions are too small being destroyed.

Behavior after pulse cancellation
When the pulses are canceled and in pure induction motor operation,
the drive converter has no information about the actual motor speed.
When the pulses are re-enabled, the speed actual value must first be
searched for.
Parameter P1012.7 can be used to define whether the search should
start at the setpoint speed or at speed = 0.

\[
P1012.7 = 0 \quad \text{Search starts at the setpoint speed} \\
= 1 \quad \text{Search starts at speed } = 0
\]

When the motor is stationary and P1012.7 = 0, you should avoid applying
a high setpoint before the pulses have been enabled.

Warning
When deleting the gating pulses for the motor (terminal 663, terminal
63 or internally canceling the pulses when faults are present), there is
no motor speed data. The computed actual speed value is then set to
zero, Thus, all of the speed actual value signals, speed actual value
messages and output signals (\(|n_{\text{act}}| < n_{\text{min}}, \text{ramp-function generator}
ended, |n_{\text{act}}| < n_x, n_{\text{set}} = n_{\text{act}}\) are no longer reliable.

MSD/IM operation
The MSD/AM function enables the control response to be switched during
operation from MSD to AM control for high speeds, depending on
the speed. Parameter P1465 > 0, < n_{max}.
The switchover takes place automatically, depending on the setting of
the speed threshold in P1465.
A switchover via a digital input, for example, is not possible.
4 Commissioning

4.7 Induction motor operation with induction motor

<table>
<thead>
<tr>
<th>IM, open-loop controlled</th>
<th>IM, closed-loop controlled</th>
</tr>
</thead>
<tbody>
<tr>
<td>P1465</td>
<td>P1466 n_max</td>
</tr>
</tbody>
</table>

Pure IM operation:  
P1465 = 0

Pure MSD operation:  
P1465 > n_max

Mixed operation:  
0 < P1465 < n_max

MSD -> ARM with encoder signal evaluation
IM -> ARM without encoder signal evaluation

Fig. 4-6 Operating ranges, MSD/IM

Note

For pure IM operation, a rotor position encoder is not necessarily required. A fixed temperature must be selected in P1608, as in this case, generally temperature sensing is not connected.

When IM operation is selected, only drive converter frequencies (P1100) of 4 or 8 kHz are permissible.

Reference:  
/PJU/ SIMODRIVE 611, Configuration Manual, Drive Converters Chapter "Power modules"

Operating display

The actual operating status of the drive is displayed in P0600 (operating display) (refer to Chapter 4.5).

Series reactor

When high-speed special motors are used, or other low leakage induction motors, a series reactor may be required to ensure stable operation of the current controller. This reactor is taken into account in the current model using P1119.
4.7.2 Commissioning induction motors (ARM) without encoder

Danger
The EMERGENCY STOP functions must always be functioning when commissioning the drive. The relevant safety regulations must be observed to exclude danger for man and machine.

When optimizing the motor data, motor movements are initiated, which can reach the maximum motor speed.

Motor data optimization
The use of unlisted induction motors with "SIMODRIVE 611 universal" is supported with the motor data optimization.

Often, the commissioning engineer only knows the rating plate data (manufacturer’s data according to DIN VDE 0530, Part 1) of the motor.

The “Calculate equivalent circuit diagram data” function can be used to calculate other motor data.
The result of the calculation is merely an approximate estimate. The motor data optimization is used to improve the result.

When optimizing the motor data, voltage, current and speed setpoint patterns are output to the motor, and information regarding the equivalent circuit diagram data is taken from the motor response.

Prerequisites for commissioning
The following prerequisites are necessary when commissioning the drive system:

- Pulses, controller, and ramp–function generator must be enabled.
- Motor data optimization is possible in the MSD and IM modes.
- For MSD operation, it is not necessary to determine the moment of inertia.

Note
As a result of the many motors available in the market, it cannot always be guaranteed that the motor data optimization routine supplies results for all motor types. This is especially true for motors with a low power rating.

In this case, in addition to using the data on the motor rating plate, an attempt can also be made to only execute those steps 1...4 for motor data optimization (Chapter 4.7.3) that can be executed without any problems being encountered. If step 2 results in problems, then only the data on the motor rating plate should be used. So, after the motor data optimization has been completed, an attempt can be made to increase the flux gain (P1150). If this is also not successful, then unfortunately, the motor cannot be used together with SIMODRIVE 611 universal!
Commissioning, induction motors without encoder

START

- Connect-up the unit
- Check the connections

Power-up the unit (power ON)

Already commissioned?

Yes

Is "run" displayed?

Yes

No

Request a new commissioning?

No

End (cyclic operation)

Yes

Commissioning, induction motors without encoder

Is the "E- ..." displayed flashing or is the display inactive?

Remove the cause! (refer to Chapter 7.3)

Is either A1106 or b1106 displayed?

No

Yes

Carry-out the hardware configuration
(parameter list, refer to Chapter A.1)

- Enter the power module code number\(^1\) (P1106)
- Enter the motor code number (P1102 = 99)
- Enter the encoder code number (P1006 = 98, no encoder)
- Define the operating mode (P0700)
- Boot (set P0659 to 1)

Establish the boot state

- Remove write protection (P0651 = 4)
- Boot, set P0659 to 0
- Start to write into the FEPROM (P0652 = 1) and then wait until the write operation has been completed (P0652 = 0)
- Carry-out a HW power-on reset or POWER OFF → ON

Fault message "E-x683" is displayed. Using the - key, change from the alarm mode into the operating mode (repeat often, as the system automatically changes over into the alarm mode after 1 minute).

1) only if not automatically identified

2

continue on the next page

Fig. 4-7 Commissioning induction motors without encoder (Part 1)
4.7 Induction motor operation with induction motor

from the previous page

Remove write protection (P0651 = 8)

Enter the rating plate data

Yes

Are the equivalent circuit diagram data known?

No

Enter the equivalent diagram data

P1117: Motor moment of inertia
P1135: Motor no-load voltage
P1136: Motor no-load current
P1137: Stator resistance, cold
P1138: Rotor resistance, cold
P1139: Stator leakage reactance
P1140: Rotor leakage reactance
P1141: Magnetizing reactance
P1142: Speed at the start of field weakening

Calculate the equivalent circuit diagram data (P1081 = 1)

Motor data optimization required?

Yes

Calculate unlisted motor (P1082 = 1)

Save to FEPROM (P0652 = 1)
Execute POWER-ON RESET

Optimize the motor data, steps 1 to 4 (refer to Chapter 4.7.3)

Calculate unlisted motor (P1082 = 1)

Save to FEPROM (P0652 = 1)
Execute POWER-ON RESET

No

continue on the next page

Fig. 4-8 Commissioning induction motors without encoder (Part 2)
Check the following parameters, and if required, change:

- P1401:8  Speed for the max. useful motor speed
- P0610/0615  Drift/offset correction, terminal 56.x/14.x/terminal 24.x/20.x
- P0618  Normalization voltage
- P1451:8/1453:8  P gain, speed controller IM/integral action time
- P1256:8/1257:8  Ramp-function generator, ramp-up/ramp-down time
- P1147  Speed limiting
- P1123:8  Load moment of inertia (from SW 2.4)
- P1417:8  nx for "nact < nx" signal
- P1418:8  nmin for "nact < nmin" signal
- P1426:8  Tolerance bandwidth for "nset = nact" signal
- P1427  Delay time "nset = nact" signal
- P1428  Threshold torque Md
- P1429  Delay time "Md < Md" signal
- P1230:8  1st torque limit
- P1235:8  1st power limit
- P1458  Current setpoint, open-loop controlled range IM
- P1459  Torque smoothing time constant IM
- P1465  Changeover speed IM
- P1466  Changeover speed, open-loop/closed-loop control IM
- P0660 - 0663  Function, input terminal I0.x/I1.x/I2.x/I3.x
- P0680 - 0683  Signaling function, output terminal O0.x/O1.x/O2.x/O3.x

Start to write into the FEPRM (P0652 = 1) and then wait until the write operation has been completed (P0652 = 0)

Enable write protection (P0651 = 0)

Save parameters in the file and document

End

Fig. 4-9  Commissioning induction motors without encoder (Part 3)
4.7.3 Motor data optimization, steps 1 to 4

Reader’s note

What happens to the faults occurring during motor data optimization?

Faults, which occur during the commissioning steps, are written into P1084 as fault code (refer to the parameter list in Chapter A.1).

Prerequisites for the commissioning steps 1 to 4:

- Switch in the pulse, controller and ramp-function generator enable signal
- Remove write protection (P0651 = 8)
- Set the converter switching frequency (P1100) to 4 or 8 kHz

Note

The motor is immediately braked if a motor data optimization routine is interrupted while it is running.

Optimizing using "SimoCom U"

From SW 5.1, the “SimoCom U” start-up tool supports motor data optimization.

After "motor data optimization" has been selected, a menu is displayed in which, the following optimization steps can be selected one after another from the "Settings" selection box. These optimizing steps can be started using the "Start" button:

1. Step 1: Determining the resistances and reactances
2. Step 2: Finely defining the no-load current, magnetizing field reactance
3. Step 3: Determining the speed at the start of field weakening
4. Step 4: Determining the moment of inertia

For the listed parameters, the results of the optimization steps are displayed, up-to-date, in the menu screen.

Optimizing with the parameter settings

The motor can also be optimized as follows using parameter settings.

Commissioning step 1

Determine the resistance and reactance values of the motor and an improved no-load current value.

Note

- The motor does not move and may not move during this measurement.
- Monitoring is not possible, as the induction motor does not have an encoder.
4 Commissioning

4.7 Induction motor operation with induction motor

Carrying-out step 1

The step is executed as follows:

1. Select the step: P1083 = 1
2. Start the step: P1084 = 1
   - P1084 = 1 The step was started and is running - it can be exited with P1084 = 0.
   - P1084 = 1/0 The step was successfully completed
   - P1084 = -x The step was cancelled with fault-x (refer to P1084 in Chapter A.1)
     Start again after the fault has been removed.

Changed parameters

The following parameters are calculated/written into:

- P1136, P1137, P1138, P1139, P1140, P1141

Commissioning step 2

Determine the no-load current and magnetizing reactance.

The no-load current is set, so that at rated speed, the no-load voltage is present at the motor terminals.

Danger

The motor is accelerated, with a positive rotating field, up to the rated speed.

Note

If the speed actual value is not steady (resolver, toothed-wheel encoder), it cannot be guaranteed that this commissioning step is correctly executed (the setting takes too long).

Remedy: Set the speed actual value smoothing (P1522) to min. 1 ms.

Carrying-out step 2

The step is executed as follows:

1. Select the step: P1083 = 2
2. Start the step: P1084 = 1
   - P1084 = 1 The step was started and is running - it can be exited with P1084 = 0.
   - P1084 = 1/0 The step was successfully completed
   - P1084 = -x The step was cancelled with fault-x (refer to P1084 in Chapter A.1)
     Start again after the fault has been removed.

Changed parameters

The following parameters are calculated/written into:

- P1136, P1141
**Commissioning step 3**

Determine the speed at the start of field weakening.

When traveling at the threshold speed for the start of field weakening and a DC link voltage $V_{\text{DC link}}$, the converter output voltage is set to 380 V. If $V_{\text{DC link}} < 600$ V, the converter output voltage is reduced by the factor $V_{\text{DC link}}/600$ V.

---

**Danger**

The motor is accelerated up to the speed at the start of field weakening with a positive rotating field; the speed is limited to the currently effective limit.

---

**Note**

If the speed actual value is not steady (resolver, toothed-wheel encoder), it cannot be guaranteed that this commissioning step is correctly executed (the setting takes too long).

Remedy: Set the speed actual value smoothing (P1522) to min. 1 ms.

---

**Carrying out step 3**

The step is executed as follows:

1. Select the step: $P1083 = 3$
2. Start the step: $P1084 = 1$
   - $P1084 = 1$ The step was started and is running - it can be exited with $P1084 = 0$.
   - $P1084 = 1/0$ The step was successfully completed
   - $P1084 = -x$ The step was cancelled with fault-$x$

   (refer to $P1084$ in Chapter A.1)

   Start again after the fault has been removed.

**Changed parameters**

The following parameters are calculated/written into:

- $P1142$

---

**Note**

If an asynchronous motor with a rated voltage $> 400$ V is configured, the message is displayed that the speed at the start of field weakening lies under the rated speed. This configured rated voltage cannot be provided by the DC link voltage $U_{\text{ZK}}$. 

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4.7 Induction motor operation with induction motor

Commissioning step 4

(Not required when carrying-out self-commissioning in the MSD mode)

Determine the moment of inertia.

The moment of inertia is set, so that when the motor accelerates to the maximum speed, no I component is set in the speed controller.

Note

If there is a significant load moment of inertia in actual operation, this step should be executed with a coupled load.

For identification runs, the total moment of inertia (P1117 + P1123:8 (from SW 2.4)) is taken into account and corrected in P1117. The commissioning engineer must make the appropriate distribution between P1117 and P1123:8 (parameter set independent and dependent).

Danger

The motor is accelerated with a positive field direction of rotation up to the maximum speed along the torque limit.

Carrying-out step 4

The step is executed as follows:

1. Select the step: P1083 = 4
2. Start the step: P1084 = 1
   - P1084 = 1 The step was started and is running - it can be exited with P1084 = 0.
   - P1084 = 1/0 The step was successfully completed
   - P1084 = -x The step was cancelled with fault-x (refer to P1084 in Chapter A.1)

Start again after the fault has been removed.

Changed parameters

The following parameters are calculated/written into:

- P1117

Parameter overview

For IM operation (encoderless operation), the following parameters are available:
### Table 4-7 Parameter overview for IM operation (encoderless operation)

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1451:8</td>
<td>P gain, speed controller IM (ARM)</td>
<td>0.0</td>
<td>0.3</td>
<td>9999.999</td>
<td>Nms/rad</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... the P gain of the speed controller in IM operation is set (operation without encoder).

**Note:**
The parameter is preset when executing the “calculate controller data”/“calculate unlisted motor” function.

| 1453:8 | Integral action time, speed controller IM (ARM)   | 0.0  | 140.0    | 6000.0  | ms          | immediately|

... the integral action time of the speed controller is set in IM operation (operation without encoder).

**Note:**
The parameter is preset when executing the “calculate controller data”/“calculate unlisted motor” function.

| 1458   | Current setpoint open-loop controlled range IM (ARM) | 0.0  | 90.0     | 150.0    | %           | immediately|

For pure IM operation (P1465 = 0), the drive is open-loop, current–frequency controlled below the changeover speed (P1466).

In order to be able to accept a higher load torque, the motor current in this range can be increased using P1458.

**Note:**
This is entered as a percentage of the rated motor current (P1103). The current is limited to 90% of the current limit value (P1238).

| 1459   | Torque smoothing time constant AM (ARM)            | 0.0  | 4.0      | 100.0    | ms          | immediately|

... the pre-control value for the torque is smoothed (initial rounding-off).

**Note:**
In IM operation, a speed–torque–frequency pre-control is implemented due to the low dynamic performance.

| 1465   | Changeover speed MSD/IM (ARM)                     | 0.0  | 100 000.0| 100 000.0| RPM         | immediately|

Above this, the drive runs, in IM operation with the speed set in this parameter.

- P1465 = 0 pure IM operation
- P1466 < P1465 < n\text{max} mixed operation, MSD/IM
- P1465 > n\text{max} only MSD operation

**Note:**
- When IM operation is selected, only pulse frequencies (P1100) of 4 and 8 kHz are permissible.
- The parameter is preset to 0 when first commissioning, if there is no motor measuring system (P1006 = 98, P1027.5 = 1).

| 1466   | Changeover speed, closed-loop/open-loop control IM (ARM) | 150.0 | 300.0   | 100 000.0| RPM         | immediately|

For pure IM operation (P1465 = 0), the drive is open-loop, current–frequency controlled below the speed set using this parameter.

**Note:**
The parameter is preset when executing the “calculate controller data”/“calculate unlisted motor” function.
4.7 Induction motor operation with induction motor

4.7.4 Speed monitoring using a BERO (from SW 12.1)

**Description**

With the "Speed monitoring using a BERO" function, this function can be emulated for IM operation the same as for the "SIMODRIVE 611 analog" drive that has already been implemented for all configured induction motors.

An adapter for the BERO is required to use this function.

**Commissioning**

The angular incremental encoder interface must be used as input for the "Speed monitoring using BERO" for "SIMODRIVE 611 universal" (refer to Chapter 6.8.2). This means that in the speed/torque setpoint mode, the angular incremental encoder interface can no longer be used as output if a BERO is connected.

The angular incremental encoder interface is correctly configured with P0890 = 2, the angular incremental encoder interface switched-in as input and P0894 = 1, pulse/direction signal.

Commercially available BEROs function with a 24 V output. This is the reason that the signal level must be adapted to the angular incremental encoder interface (5 V input). This can be realized by connecting a DTI (Digital Tacho Interface, Order No. [MLFB] 6SE7090-0XX84-3DB0) at the existing angular incremental encoder interface input.

---

**Note**

If the angular incremental encoder interface has already been defined as an output for another function, when a BERO is connected, fault message 750 (from SW 12.1 and higher) is output – "Angular incremental encoder interface incorrectly configured".
DTI connection

Fig. 4-10  Example: Digital Tacho Interface connection, Order No. [MLFB] 6SE7090-0XX84-3DB0

- Supply voltage connection:
  - DTI 24 V via X404.1 and X404.2
  - BERO 24 V is possible via X404.3 and X404.4
  - DTI 5 V is possible via X402.14 to X403.6 and X402.13 to X403.1
4 Commissioning

4.7 Induction motor operation with induction motor

- Connection, BERO output signal:
  - BERO at X402.2 and M24 via X404.3 to X402.3

- Connection, DTI output signal:
  - DTI pulse track A from X405.2 to SIMODRIVE 611 universal X461/X462 A+
  - DTI inverse pulse track A from X405.3 to SIMODRIVE 611 universal X461/X462 A-
  - DTI pulse track B from X405.4 to SIMODRIVE 611 universal X461/X462 B+
  - DTI inverse pulse track B from X405.5 to SIMODRIVE 611 universal X461/X462 B-
  - DTI ground reference from X405.1 to SIMODRIVE 611 universal X461/X462.7 (15)

Activation

The “Speed monitoring using a BERO” function is activated with P1467 ≥ 1. P1467 = 1 allows a BERO signal to be transferred to the angular incremental encoder interface. P1467 is set > 1 if the BERO detects the number of fan blades.

Parameter overview

The following parameters are used for the “Speed monitoring using a BERO”:

- P1467 BERO pulse number
- P1468 BERO shutdown threshold, speed monitoring
- P1469 BERO speed actual value

Fault case

Fault message 718 “BERO shutdown threshold exceeded” is output, if,

- The speed threshold parameterized in P1468 was exceeded or
- BERO pulses are no longer being received for a calculated speed of > 1200 RPM.
4.8 Permanent-magnet synchronous motor with and without field-weakening (PE spindle)

4.8.1 Description

What is a permanent-magnet synchronous motor with field weakening?

The permanent-magnet synchronous motors with field weakening (1FE1 motor series) are liquid-cooled synchronous motors, which are supplied as components. After the components have been assembled on the spindle, a complete motor spindle unit is formed.

The rotors of 1FE1 motors are equipped with permanent magnets. The high speeds for spindle operation are achieved by a current which opposes the field. This is similar to field weakening for induction motors.

Advantages

The advantages of permanent-magnet spindles in comparison to induction motors are:

- Extremely low power loss in the rotor ---> low bearing temperature
- Higher torque for the same active part dimensions ---> more compact machine design
- Shorter accelerating times with the same moment of inertia
- Improved efficiency
- Favorable Cos $\varphi$ ---> it may be possible to use a smaller power module
- More favorable speed/power characteristic ---> no power reduction in the upper speed range

Reader's note

Detailed information on 1FE1 motors, configuring and mounting built-in motors are provided in:

Reference: /PJFE/ AC Motors for Main Spindle Drives
Synchronous Built-in Motors 1FE1
Configuration Manual
Manufacturer Documentation
4.8 Permanent-magnet synchronous motor with and without field-weakening (PE spindle)

Motor spindle components

A motor spindle generally consists of the following components:

- Spindle box
- Spindle with bearings
- Cooling system

The spindle manufacturer is responsible for designing the bearings, lubrication and cooling.

- Built-in motor
  - 4-pole series (especially suitable for high speeds)
  - 6-pole series (especially suitable for high torque)
  - A VP module (VPM) is required, depending on the EMF (rotor voltage) (VPM: Voltage Protection Module)
  - Maximum speed: up to 16 000 RPM
  - Maximum torque: up to 310 Nm
    (depending on the frame size)

- Encoder system (integrated encoder)
  - Hollow shaft measuring systems with sin/cos 1 Vpp
    (e.g. SIZAG 2 or SIMAG H)

System prerequisites

The prerequisites are as follows:

- Control board
  SIMODRIVE 611 universal for encoders with sin/cos 1 Vpp
- Maximum motor cable length = 50 m
4.8.2 Commissioning synchronous motors

The following questions must be positively answered before commissioning synchronous motors:

- Are all of the prerequisites for commissioning checked and were the points in the checklist for commissioning checked (refer to Chapter 4.1)?

- Is the motor used a standard or an unlisted motor?
  - Standard motor?
    In the Catalog, the motor is listed as a permanent-magnet synchronous motor and has an assigned motor code (refer to Chapter A.3.2)?
    When commissioning, the motor used is selected from a list.
  - Unlisted motor?
    The motor is not included in the list of permanent-magnet synchronous motor without field weakening and also does not have a motor code (refer to Chapter A.3.2)?
    When commissioning, the data of the motor used must be available and must be manually entered.
    The data required with field weakening can be found in the table under the index entry "Unlisted motor - parameters for PE spindle".

- Are the motor and encoder already mounted and ready to be powered up?

Commissioning synchronous motors with SimoCom U

The synchronous motors are commissioned as follows using the SimoCom U parameterizing and start-up tool:

1. Establish online operation
   Operation: e.g. with "Commissioning - search for online drives"

2. Configure the drive
   General rule:
   You can reach the next or the previous dialog box by pressing "next" or "back".
   - "Drive name" dialog box
   - "Power module" dialog box (only if it is not automatically identified)
   - "Motor selection" dialog box for standard motors:
     "Motor" field "Motor type" field
     -> Standard motor -> 1FT6, 1FK6, 1FE1, 1FW6 (synchronous)
     --- select the motor used
     --- continue with the "measuring system/encoder" dialog box
4.8 Permanent-magnet synchronous motor with and without field-weakening (PE spindle)

- "Motor selection" dialog box for unlisted motor:

  "Motor" field  "Motor type" field
  --> Enter data  --> Synchronous motor (SRM)

After "continue", the motor data and the pre-setting for the current controller adaptation must be entered:

<table>
<thead>
<tr>
<th>P No.</th>
<th>Name</th>
<th>Value</th>
<th>Unit</th>
</tr>
</thead>
<tbody>
<tr>
<td>1103</td>
<td>Rated motor current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1104</td>
<td>Maximum motor current (as for P1122)</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1112</td>
<td>Motor pole pair number</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>1113</td>
<td>Torque constant</td>
<td>Nm/A</td>
<td></td>
</tr>
<tr>
<td>1114</td>
<td>Voltage constant</td>
<td>V(rms)</td>
<td></td>
</tr>
<tr>
<td>1115</td>
<td>Armature resistance</td>
<td>Ohms</td>
<td></td>
</tr>
<tr>
<td>1116</td>
<td>Armature inductance</td>
<td>mH</td>
<td></td>
</tr>
<tr>
<td>1117</td>
<td>Motor moment of inertia</td>
<td>kgm²</td>
<td></td>
</tr>
<tr>
<td>1118</td>
<td>Motor standstill current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1122</td>
<td>Motor limiting current (as for P1104)</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1128</td>
<td>Optimum load angle (from SW 3.3)</td>
<td>Degrees</td>
<td></td>
</tr>
<tr>
<td>1146</td>
<td>Maximum motor speed</td>
<td>RPM</td>
<td></td>
</tr>
<tr>
<td>1149</td>
<td>Reluctance torque constant (from SW 3.3)</td>
<td>mH</td>
<td></td>
</tr>
<tr>
<td>1180</td>
<td>Lower current limit adaptation</td>
<td>0 %</td>
<td></td>
</tr>
<tr>
<td>1181</td>
<td>Upper current limit adaptation</td>
<td>30 %</td>
<td></td>
</tr>
<tr>
<td>1182</td>
<td>Current controller data factor</td>
<td>30 %</td>
<td></td>
</tr>
<tr>
<td>1400</td>
<td>Rated motor speed</td>
<td>RPM</td>
<td></td>
</tr>
</tbody>
</table>

- "Measuring system/encoder" dialog box

  Field
  "Which motor measuring system are you using?"  --> Enter data

  The encoder data should be entered after "continue":

  Incremental - without zero mark     yes
  Rotor position identification       yes

  Note: This results in, P1011 = 3XXX\text{Hex}

  Speed actual value inversion   first remains like this
  P1005 (encoder pulse number)     

- "Operating mode" dialog box

- "Complete the drive configuration" dialog box

  After the data that has been set has been carefully checked, the drive configuration is completed by pressing
  "Accept this drive configuration".
3. With field weakening, PE specific parameters must be set and the PE spindle activated (only for unlisted motors).
   - Enter or change the following parameters via the expert list.

<table>
<thead>
<tr>
<th>P No.</th>
<th>Name</th>
<th>Value</th>
<th>Unit</th>
</tr>
</thead>
<tbody>
<tr>
<td>1136</td>
<td>Motor locked–rotor current</td>
<td></td>
<td>A(rms)</td>
</tr>
<tr>
<td>1142</td>
<td>Speed at the start of field weakening</td>
<td></td>
<td>RPM</td>
</tr>
<tr>
<td>1015</td>
<td>Activate PE–MSD</td>
<td>1: Activated</td>
<td>-</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0: Deactivated</td>
<td></td>
</tr>
</tbody>
</table>

**Note**

From SW 12.01, P1172 must be = 0!

- Execute the "calculate controller data" function
  After this, the controller data is pre-assigned, PE-specific.
- Save the parameters in the FEPROM
- Carry-out a POWER-ON RESET

**Note**

This completes the basic commissioning.
The motor can be operated with these settings.

After this first commissioning, for reasons of accuracy, the rotor position identification run must be executed with zero mark and the angular commutation offset determined.

**Reader’s note**

Additional commissioning instructions/information regarding motor optimization are provided in the following.
Additional commissioning information/instructions to optimize the motor

1. Check the control sense of the speed control loop
   - P1146 = _ _ _ _ _ _
   P1147 = _ _ _ _ _ _ Note values so that they can be written back into the system
   - P1146 (maximum motor speed) --> enter a low value P1147 (speed limiting) --> enter a low value
   - Enable the drive and operate the drive with a low speed setpoint

<table>
<thead>
<tr>
<th>If</th>
<th>Then</th>
</tr>
</thead>
<tbody>
<tr>
<td>No error</td>
<td>Control sense OK</td>
</tr>
<tr>
<td>Fault (e.g. the drive oscillates at (n_{set} = 0))</td>
<td>If the control sense is incorrect, e.g. due to incorrect phase sequence (counter-clockwise rotating field) or interchanged encoder tracks --&gt; correct the phase sequence or change the inversion of the speed actual value (P1011.0) and carry out POWER ON-RESET</td>
</tr>
<tr>
<td>Fault (e.g. fault 608)</td>
<td>If the control sense or encoder pulse number (P1005) is incorrect --&gt; correct P1005 and execute a POWER-ON RESET</td>
</tr>
</tbody>
</table>

- P1146 and P1147: Re-enter the old parameter values

2. Motor pole position identification is described in Chapter 6.16.

3. Set the current controller adaptation (refer to Chapter 4.8.3)
   - P1120 is pre-set with "Calculate controller data"
   - Check the pre-setting for the current controller adaptation (the values were already entered together with the motor data):
     \(P1180 = 0\%\), \(P1181 = 30\%\), \(P1182 = 30\%\)
4.8.3 Current controller adaptation

Pre-setting of the current controller adaptation

The current controller adaptation must be pre-set as follows before subsequently setting and checking:

\[
P1182 = 30\% \\
\]

\[
P1180 = 0\% \\
P1181 = 30\% \\
\]

Proportional gain \( K_p \)

\[
P1120 = \text{calculated value [V/A]} \\
\]

Fig. 4-11 Pre-setting of the current controller adaptation for 1FE1 motors

Setting the current controller adaptation

To check and set the current controller adaptation, different current set-point steps are entered via the SimoCom U parameterizing and start-up tool using the measuring function. The appropriate step response is then evaluated (current actual value = torque actual value).

Goal when setting the P gain \( K_p \)

The adaptation characteristic for the P gain \( K_p \) of the current controller should be set over the complete current \( I_q \), so that the controller is optimally set at each current, and does not overshoot.

\[
\begin{align*}
K_p \text{ is optimum} & \quad \rightarrow \quad \text{OK} \\
K_p \text{ is too high, overshoots} & \quad \rightarrow \quad \text{not OK} \\
K_p \text{ is too low, dampened transient response} & \quad \rightarrow \quad \text{OK, not optimum}
\end{align*}
\]

Fig. 4-12 How should the step response be evaluated?
The pre-setting (default) of the adaptation characteristic can, e.g. be checked and set as follows:

1. Current setpoint input (amplitude = 2 % + offset = 0 %)
   Check the start of the adaptation characteristic for \( I_q = 0 \) %.
   Step response?
   OK: \( P_{1120} \) is correct
   Not OK: Increase/decrease \( P_{1120} \)
   \( --> \) Target: Optimum transient response
   (refer to Fig. 4-12, left)

2. Current setpoint input (amplitude = 2 % + offset = 100 %)
   Check the constant adaptation characteristic range at \( I_q = 100 \) %.
   Step response?
   OK: \( P_{1182} \) is correct
   Not OK: Increase/decrease \( P_{1182} \)
   \( --> \) Objective: Optimum transient response
   (refer to Fig. 4-12, left)

3. Current setpoint input (2 % amplitude + 30, 20, 10, 5 % offset)
   Check the transition point and the gradient of the adaptation characteristic at \( I_q = 30 \), 20, 10, 5 %.
   Step response?
   OK: \( P_{1181} \) is correct
   Not OK: Increase/decrease \( P_{1181} \)
   \( --> \) Objective: Well dampened transient response
   (refer to Fig. 4-12, right)

---

**Note**

The reference for the current setpoint (amplitude and offset) refer to the power module transistor current (\( P_{1107} \), units: A(pk), peak value).

Example:
\( P_{1107} = 50 \) A(pk) \( --> \) \( 50 \sqrt{2} \approx 36 \) A(rms) \( --> \) \( 50 \% \approx 18 \) A
\( --> \) \( 10 \% \approx 3.6 \) A, etc.
The following parameters are used for the current controller adaptation:

Table 4-8 Parameter overview for the current controller adaptation

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1180</td>
<td>Lower current limit adaptation (SRM, SLM)</td>
<td>0.0</td>
<td>0.0</td>
<td>100.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td>1181</td>
<td>Upper current limit adaptation (SRM, SLM)</td>
<td>0.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td>1182</td>
<td>Factor, current controller adaptation (SRM, SLM)</td>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The P gain of the current control (\(K_p\), P1120) can be reduced, depending on the current, using the controller adaptation.

The adaptation characteristic is defined using P1180, P1181 and P1182. The following value pairs are obtained:

- First value pair: P1180/100%
- Second value pair: P1181/P1182

The following applies: P1180 (lower current limit adaptation) < P1181 (upper current limit adaptation)
4.8.4 Parameters for PE spindles

The following parameters are used for permanent-magnet spindles (PE spindles):

Table 4-9 Parameter overview for PE spindles

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1015</td>
<td>Activate PE-MSD (SRM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>PO</td>
<td></td>
</tr>
</tbody>
</table>

...the permanent-magnet spindle (PE spindle, 1FE1 motor) is activated/deactivated for this drive.

= 1 Permanent-magnet spindle is activated
= 0 Permanent-magnet spindle is de-activated

1128 Optimum load angle (SRM) 90.0 90.0 135.0 Degrees. immediately

For synchronous motors that have rotors that are not symmetrical around the rotational axis, the additional reluctance torque can be used to increase the torque.

The optimum load angle specifies at which load angle the torque reaches a maximum value at 150 % rated current.

Note:
Refer to P1149 (reluctance torque constant)
Synchronous motors without rotors that are symmetrical around their rotational axis: e.g. 1FE motors
  • Operation with reluctance torque: P1128 and P1149 not equal to the standard value
  • Operation without reluctance torque: P1128 and P1149 equal to the standard value

1136 Motor locked-rotor current 0.0 0.0 500.0 A(rms) immediately

The parameter is set by selecting the motor from the motor list or according to the data sheet of the motor manufacturer.

If the motor manufacturer has no data, then the motor locked-rotor current can be calculated according to the following formula:

\[ P1136 = \left( \frac{P1114 \times 60 \, [\text{sec}]}{\sqrt{3} \times P1112 \times P1116 \times 2\pi} \right) \]

Note:
P1112 Motor pole pair number
P1114 Voltage constant (Vrms/1000 rev/min)
P1116 Armature inductance (in mH)

Note:
For PE spindles, the maximum motor short-circuit current (no-load current) influences the high motor speeds. This means that if the power module rating is too low, the maximum speed will not be reached. Otherwise, the functionality is not restricted.
### 4.8 Permanent-magnet synchronous motor with and without field-weakening (PE spindle)

#### Table 4-9 Parameter overview for PE spindles, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1142</td>
<td>Speed at the start of field weakening (SRM, ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>RPM</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The speed at the start of field weakening is assigned when selecting the motor from the motor list, or according to the motor manufacturer's data sheet. If the motor manufacturer has no data, then the speed at the start of field weakening can be calculated according to the following formula:

**For SRM:**

\[ P_{1142} \text{ [RPM]} = \frac{425 \text{ [V] } \times 1000 \text{ [RPM]}}{P_{1114} \text{ [V]}} \]

- \( P_{1114} \) Voltage constant
- \( I_d \) Field--generating current
- \( P_{1136} \) Motor locked--rotor current

Depending on the load, the field current can change between the speed - \( I_d \) - characteristic and the motor short-circuit current.

**For ARM:**

\[ P_{1142} \text{ [RPM]} = \frac{P_{1400} \text{ [RPM]} \times 400 \text{ [V]}}{\sqrt{3} \times 2\pi \times P_{1134} \text{ [s}^{-1}] \times P_{1119} \text{ [mH]} \times P_{1103} \text{ [A]}} \]

\[ P_{1132} \text{ [V]} + \frac{1000}{\psi} \]

Note:

When commissioning the system, parameter \( P_{1142} \) is calculated using the motor equivalent circuit diagram.

<table>
<thead>
<tr>
<th>No.</th>
<th>Stall torque reduction factor</th>
<th>5.0</th>
<th>100.0</th>
<th>1000.0</th>
<th>%</th>
<th>immed.</th>
</tr>
</thead>
<tbody>
<tr>
<td>1149</td>
<td>Reluctance torque constant (SRM)</td>
<td>0.0</td>
<td>0.0</td>
<td>300.0</td>
<td>mH</td>
<td>immed.</td>
</tr>
</tbody>
</table>

For synchronous motors that have rotors that are not symmetrical around the rotational axis, the additional reluctance torque can be used to increase the torque. The reluctance torque constant multiplied by the torque and field--generating current provides the torque increased as a result of the reluctance torque.

Note:

Refer to \( P_{1128} \) (optimum load angle)

Synchronous motors that have rotors that are not symmetrical around the rotational axis: e.g. 1FE motors

- Operation with reluctance torque: \( P_{1128} \) and \( P_{1149} \) not equal to the standard value
- Operation without reluctance torque: \( P_{1128} \) and \( P_{1149} \) equal to the standard value
4.9 1FW6 built-in torque motors (from SW 6.1)

4.9.1 Description

Built-in torque motors are liquid-cooled, slow-speed (high pole number), permanent-magnet three-phase synchronous motors with hollow-shaft rotors. The motors are supplied as built-in components which are kept together, when shipped, using an assembly unit. In addition, a bearing and a rotary encoder are required for a complete drive unit.

The stator and the rotor have flanges at both ends with centering surfaces and tapped holes which allow them to be integrated into a machine.

Advantages

The motors distinguish themselves as follows:

- Extremely high power density
- High torque with a compact design and low envelope dimensions
- Wide range of types
- High overload capability (factor 1.8 ... 2.0)
- Low moment of inertia
- High degree of availability as there are no gearbox components in the mechanical drive transmission line which are subject to wear
- Cable and cooling connections, either radial or axial
- Water cooling to increase the rated power
- Directly flanged to the machine

Reader’s note

Detailed information on 1FW6 motors and to engineer and mount built-in torque motors is provided in:

Reference: /PJTM/ Configuration Manual
1FW6 Built-in Torque Motors
Manufacturer Documentation
Components of built-in torque motors

Generally, a built-in torque motor comprises the following components:

- **Stator**
  This comprises an iron core and a three-phase winding. The winding is cast in polyurethane in order to better dissipate the power losses. The motor can be force-cooled using a liquid heat exchanger (main heat exchanger) around its circumference.

- **Rotor**
  This is the reaction part of the motor. It comprises a cylindrical hollow steel shaft which has permanent magnets around its circumference.

- **Cooling**
  The cooling version depends on the outer diameter.

- **Encoder system**
  - Absolute incremental encoder with EnDat (e.g. RCN 723, Heidenhain)
  - Incremental encoder (1Vpp) (e.g. RON 786, Heidenhain)
  - Min. encoder pulse number \( z_{\text{min}} = 2048 \)
  - Max. encoder pulse number \( z_{\text{max}} = 65535 \)

System prerequisites

The prerequisites are as follows:

- **Control board**
  SIMODRIVE 611 universal (encoder interpolation depends on the number of pulses of the incremental encoder)

- **Built-in torque motors should be set-up as feed motors**

- **Maximum motor cable length = 50 m**

Note

When built-in torque motors (direct drives) are connected to controlled infeeds, an HFD commutating reactor with the appropriate resistance must be used as otherwise electrical system oscillations could occur.

When engineering the HFD commutating reactor with resistor, refer to:

**Reference:** /PJU/ SIMODRIVE 611 Configuration Manual Manufacturer Documentation
4.9.2 Commissioning 1FW6 motors

The following questions must be positively answered before commissioning 1FE1 motors:

- Are all of the prerequisites for commissioning checked and were the points in the checklist for commissioning checked (refer to Chapter 4.1)?
- Is the motor used a standard or an unlisted motor?
  - Standard motor?
    In the Catalog, the motor is listed as a permanent-magnet synchronous motor without field weakening and has an assigned motor code (refer to Chapter A.3.3)?
    When commissioning, the motor used is selected from a list.
  - Unlisted motor?
    The motor is not included in the list of permanent-magnet synchronous motor without field weakening and also does not have a motor code (refer to Chapter A.3.3)?
    When commissioning, the data of the motor used must be available and must be manually entered.
    The necessary data is listed in the table under the index entry "Unlisted motor - parameters for 1FW6 motor".
- Are the motor and encoder already mounted and ready to be powered up?

1FW6 motors are commissioned as follows using the SimoCom U parameterizing and start-up tool:

Reader’s note
Also refer to commissioning 1FE1 motors with SimoCom U in Chapter 4.8.2.
For 1FW6 torque motors, the commutation required for synchronous motors can be automatically set using the software-based rotor position identification technique.

The following two techniques can be applied for all frame sizes of 1FW6 torque motors:

- **Saturation-based technique (from SW 5.1)**
  - This technique can also be used to determine the angular commutation offset once in conjunction with an absolute measuring system (e.g. RCN 723 from Heidenhain).
  - This technique does not cause the rotor to move which means that it can also be used for axes which are locked (e.g. using a brake).
  - Depending on the actual mechanical design, this can result in a higher noise level when the axis is powered-up during the identification routine.

- **Motion-based technique (from SW 6.1)**
  - This technique may only be used for horizontal axes that are free to move and are not braked (static friction < 10 % of the rated motor torque).
  - When this technique is applied, under worst case condition, the rotor can move in the range of ±5 degrees.
  - The measuring system must be very stiffly mounted if this technique is used.

### 4.9.3 Thermal motor protection

1FW6 stators are equipped with the two following temperature monitoring circuits to protect the stator against inadmissibly high thermal stressing as well as to monitor the temperature during the commissioning phase and in operation:

- 2 x Temp-S (one switching threshold at 130°C and another at 150°C)
- 1 x Temp-F

---

**Reader's note**

Detailed information on how to connect and evaluate the temperature monitoring circuits is provided in:

**Reference:** /PJTM/ Configuration Manual
1FW6 Built-in Torque Motors
Manufacturer Documentation
4.10 Linear motors (1FN1, 1FN3 motors)

4.10.1 General information on commissioning linear motors

Before commissioning motors, the following questions must be answered:

- Are all of the prerequisites for commissioning checked and were the points in the checklist for commissioning checked (refer to Chapter 4.1)?
- Is there a control board with sin/cos 1 Vpp (refer to Chapter 1.3)?

Reader’s note
Detailed information on linear motors, encoders and power connection, configuring and mounting are provided in:

Reference: Configuration Manual
Linear Motors of the Product Family 1FN1 or Linear Motors 1FN Peak-Load Motors of the Product Family 1FN3

Checks in the no-current state
The following checks can be made:

1. Linear motor
   - Which linear motor is being used?
   - Is the motor in the list (refer to Chapter A.3.4)?

   Yes: Which? 1FN ___ ___ ___ ___ ___ ___ ___ ___ ___
   No: Is the data of the "unlisted" linear motor available? (refer under the index entry "Unlisted motor - Parameters for SLM")
   - Is the motor already mounted and ready to be powered up?
   - If a cooling circuit is being used, is it functional?
2. Mechanical system
   - Is the axis easy to move over the complete traversing range?
   - Does the air gap between the primary and secondary section and the mounting dimensions correspond to the motor manufacturer’s data (refer to Chapter 4.10.4)?
   - Suspended/hanging axis:
     If weight equalization is being used for the axis, is this functional?
   - Brake:
     If a brake is being used, is it correctly controlled?
   - Traversing range limiting:
     Are the mechanical end stops available and tightly bolted to both ends of the traversing path?
   - Are the moving feeder cables correctly routed in a cable drag assembly?

3. Measuring system (refer to Chapter 4.10.6)
   - Which measuring system is being used? ______________
     Absolute or incremental: abs □ incr □
     Grid spacing: ______________________ μm
     Zero marks (number and position): ______________________
   - Which is the positive drive direction? (refer to Chapter 4.10.6)
     Which is the positive counting direction of the measuring system?
     Invert (P1011.0)? yes □ no □

4. Wiring
   - Power module (connect UVW, phase sequence, clockwise rotating field)
   - Protective conductor connected?
   - Screen connected?
   - Temperature monitoring circuits:
     Are the cables connected to the terminal block of the screen connecting plate?
     --> Temperature sensor (Temp–F):
       The average absolute winding temperature can be measured using the temperature sensor (Temp–F).
     --> Overtemperature switch (Temp–S)
       The over temperature shutdown circuit (Temp–S) allows each individual motor phase winding to be digitally monitored for an overtemperature condition.
Danger

The circuits of Temp--F and Temp--S neither have "protective separation" between each other nor to the power circuits in accordance with VDE 0160/EN 50178 (EN 61800-5-1).

Thus, they may not be used as SELV/PELV circuits, or connected with these. Also refer to

Reference: Configuration Manual
Linear Motors of the Product Family 1FN1 or
Peak-Load Motors of the Product Family 1FN3

- Temperature sensor evaluation (refer to Chapter 4.10.5)

5. Measuring system cable
Is the measuring system cable inserted at X411/X412 or at the adapter connector of the temperature sensor coupling cable?

Danger

Presently, the connection does not correspond to "protective separation" according to VDE 0160/EN 50178 (EN 61800-5-1).

Thus, they may not be used as SELV/PELV circuits, or connected with these. Also refer to

Reference: Configuration Manual
Linear Motors of the Product Family 1FN1 or
Peak-Load Motors of the Product Family 1FN3
4.10.2 Commissioning: Linear motor with one primary section

Procedure when commissioning using SimoCom U

Linear motors with a primary section (single motor) should be commissioned as follows using the parameterizing and start-up tool:

Warning
The pulse enable (terminal 663) must be switched-out (de-energized) for safety reasons before the drive is powered-up.

1. Establish online operation
   Operation: e.g. with "Commissioning – search for online drives"

2. Configure the drive
   General rule:
   You can reach the next or the previous dialog box by pressing "next" or "back".
   - "Drive name" dialog box
   - "Power module" dialog box (only if it is not automatically identified)
   - "Motor selection" dialog box:
     Is the linear motor included in the list of linear motors?
     "Motor" field "Motor type" field
     -> Standard motor -> 1FNx (linear)
     The linear motor is not included in the list of linear motors?
     --> Unlisted motor
     "Motor" field "Motor type" field
     -> Enter data -> Linear motor (SLM)
     The motor data should be entered after "continue".
"Measuring system/encoder" dialog box

Field
"Which motor measuring system are you using?" -> Enter data

The encoder data should be entered after "continue".

"Linear measuring system" field

Incremental - a zero mark
There is an incremental measuring system with 1 zero mark in the traversing range.

Incremental - several zero marks
An incremental measuring system is used with several zero marks in the traversing range.

Incremental - no zero mark
An incremental measuring system is used without any zero marks in the traversing range.

Absolute (EnDat)
An absolute measuring system (EnDat) is used.

Speed actual value inversion
The inversion must be set, as was already determined under "Check in the no--current status".

Grid spacing
The grid spacing should be set as was already entered in the "check in the no--current status" point.

Rotor position identification yes
(only for incremental measuring systems)

- "Operating mode" dialog box

- "Complete the drive configuration" dialog box

After the data that has been set has been carefully checked, the drive configuration is completed by pressing "Accept this drive configuration".
3. Fixed temperature?
   If the temperature monitoring is realized through a PLC and not through the drive (refer to case c), then for the temperature sensor evaluation, refer to Chapter 4.10.5), the monitoring function must be disabled by specifying a fixed temperature > 0.
   - P1608 (fixed temperature) = e.g. 80 °C  Monitoring off
   - P1608 (fixed temperature) = 0 °C  Monitoring on

4. Reduce the maximum motor current for safety reasons
   - P1105 (maximum motor current) = e.g. enter 20 %

---

**Danger**
Linear drives can achieve significantly higher rates of acceleration and velocities than conventional drives.
The traversing range must always be kept clear in order to avoid any potential danger for man or machine.

5. Determine the angular commutation offset
   The angular commutation offset is determined as follows:
   a) Select the identification technique using P1075. Possibly adapt other machine data for the rotor position identification routine.
   b) Save the parameters and carry-out a POWER ON RESET.
   c) Depending on the measuring system used, proceed as follows:
For an incremental measuring system:

At power-on, the rough synch is retrieved from the Hall sensor signals (C/D track)

Zeromarks?

Onezeromark
Set P1017 ("commissioning") to 1

Movetheaxis over the zeromark, "jogging"

When the zeromark is passed, the angular commutation offset is automatically entered into P1016

Alarm 799 is displayed

Saveparameters and carry-out a POWER-ONRESET

Azeromark is not selected and an angular commutation offset is not transferred

No zeromark, several zeromarks or distance-coded reference marks

Secondary conditions fulfilled?

Yes

No

Mount Hall sensor

When the enable signals are present, a rotor position identification routine is immediately carried-out. If the rotor position identification was not successful, the appropriate fault message is output. If the causes of the fault are removed and the fault message acknowledged, a new identification attempt is made

1FN3
Motor type 1FN1 or 1FN3?

1FN1

4.10 Linear motors (1FN1, 1FN3 motors)
For an absolute measuring system:

1FN1 linear motor

If the EnDat serial number read from the measuring system is not equal to P1025, then P1017 is automatically set to 1.

Yes, limitations fulfilled (P1075 must be set to 3)

- Set P1017 to 1
- acknowledge alarm 604

When the enable signals are present, a rotor position identification routine is immediately carried out. If the rotor position identification was not successful, the appropriate fault message is output. If the causes of the fault are removed and the fault message acknowledged, a new identification attempt is made.

- The angular commutation offset is automatically entered into P1016

END

1FN3 linear motor

If the EnDat serial number read from the measuring system is not equal to P1025, then P1017 is not set and alarm 604 is displayed ("motor encoder is not adjusted").

Set P1017 to 1

acknowledge alarm 604

Limitations for motion-based rotor position identification fulfilled?

- Yes, limitations fulfilled
- (P1075 must be set to 3!)

- No, limitations not fulfilled

The angular commutation offset is automatically entered into P1016 (refer to Chapter 4.10.8) and manually saved parameters and carry-out a POWER-ON RESET.

The correct value in P1016 is mandatory

Set P1017 to -1

The EnDat serial number is read-out of the measuring system and automatically entered into P1025

Alarm 799 is displayed

Fig. 4-14 Absolute measuring system
For a distance-coded measuring system:

"SIMODRIVE 611 universal" from SW 8.3 supports this measuring system. Just the same as for incremental measuring systems, several zero marks must be selected.

**Note**

For unlisted motors, a rotor position identification routine to determine the angular commutation offset cannot be guaranteed. Depending on the motor design, the following can be possibly used for both measuring systems:

- The technique based on saturation,
- The technique based on motion,
- For an absolute measuring system: The angular commutation offset is determined by making the appropriate measurements (refer to Chapter 4.10.8).

When commissioning has been completed, it is absolutely necessary that the angular commutation offset is carefully checked again by making the appropriate measurements. This is independent of whether it involves an unlisted or SIEMENS motor!

6. Traverse the axis and check that it is functioning correctly

- Traversing in the closed-loop speed controlled mode
  
  When a speed setpoint is entered, does the axis traverse correctly?
  
  Yes  Set the rotor position identification (Point 10.)
  
  No longer reduce the maximum current
  
  (set P1105 to 100 %)
  
  Optimize the current and speed controllers
  
  (refer to Chapter 6.1.4)

  If a higher-level closed-loop position control is used, after these points have been executed, the linear motor has been commissioned, otherwise after "yes" immediately proceed with the next point.

  No  Resolve the problem (refer to Chapter 7.3.2)
  
  If fault 608 (speed controller output limited)
  
  is displayed
  
  --> Invert the speed actual value (change P1011.0)

- Traversing in the positioning mode
  
  Does the axis traverse with a positive velocity setpoint in the required direction?
  
  Yes  OK
  
  No  Change P0232 (position reference value inversion)

  Is the traversing path OK (10 mm is specified --> 10 mm traversing path)?

7. Set or carry-out referencing/adjusting

- Incremental measuring system:  Referencing (refer to Chap. 6.2.5)

- Absolute measuring system:  Adjust (refer to Chapter 6.2.7)
8. Set the setpoint limit switch
   - P0314, P0315 and P0316
     (refer under the index entry "Software limit switch")

9. Optimizing the axis controller settings

   Note:
   Generally, the automatic controller setting for linear motors does not
   provide adequate results, as the measuring system mounting plays
   a significant role in the closed-loop control characteristics.
   - Current and speed controllers  (refer to Chapter 6.1.4)
   - Position controller  (refer under the index entry
     "Kv factor")

10. Check and set the rotor position identification

    To check the rotor position identification, using a test function,
    you can determine the difference between the calculated rotor
    angle position and that actually used by the closed-loop control.
    Proceed as follows:

    - Start the test function several times and evaluate the difference
      Start  Set P1736 (test rotor position identification) to 1
      Difference  P1737 (difference, rotor position identification)

      = ____, ____, ____, ____, ____

    - Is the spread of the measured values less than 10 degrees electrical?
      Yes:  OK
      No:  Increase P1019 (e.g. by 10 %)
           and repeat the measurements

      If OK after having repeated the measurements, then the
      angular commutation offset can be re-determined:

      For an incremental measuring system
      (incremental - one zero mark):
      as for Point 5. (determining the angular commutation off-
      set)

      For an absolute measuring system:
      Power-down the drive (POWER ON-RESET)
      Power-up the drive with the pulse or controller enable
      signals switched-out
      Set P1017.0 to 1
      Switch-in the pulse and enable signals
      -->  The angular offset is automatically
            entered into P1016
      -->  Fault 799
            (Save to FEPROM and HW-RESET required)
            is displayed
      Save to FEPROM and carry-out a HW-RESET

      For incremental measuring system
      (incremental - no or several zero marks):
      Save to FEPROM and carry-out a HW RESET
4.10 Linear motors (1FN1, 1FN3 motors)

4.10.3 Commissioning: Linear motor with two identical primary sections

General information

If it is certain that the EMF of both motors have the same relative phase position to one another, the connecting cables can be connected in parallel and operated from one drive.

Linear motors, which are connected in parallel, are commissioned, based on the commissioning of a single linear motor.

First, only one linear motor (motor 1) is connected to the drive, and is commissioned as individual motor (1FNx ...). The angular commutation offset is automatically determined and noted.

Instead of motor 1, motor 2 is connected and is commissioned as individual motor. Also here, the angular commutation offset is automatically determined and noted.

If the difference between the angular commutation offset of motor 1 and motor 2 is less than 10 degrees electrical, both motors can be connected in parallel to the drive and commissioned as a parallel circuit configuration of 2 linear motors (e.g. 2 • 1FN1xxx).

Procedure for commissioning linear motors connected in parallel

Linear motors connected in parallel are commissioned as follows:

1. Disconnect the parallel circuit
   Only connect motor 1 to the power module.

2. Commission motor 1 as a single motor
   --> Observe the information/data in Chapter 4.10.1
   --> Commission as described in Chapter 4.10.2 (up to and including Point 5.)
   --> Check and set the rotor position identification (refer to Chapter 4.10.2, Point 10.)

3. Traverse the axis and check that it is functioning correctly

4. Note the angular commutation offset of motor 1
   \[ P1016 \text{ (motor 1)} = _ _ _ _ _ _ \text{ degrees electrical} \]

5. Power-down and wait until the DC link has been discharged

6. Instead of motor 1, connect motor 2 to the power module
   Caution:
   For a Janus configuration (refer to Chapter 4.10.7) interchange phases U and V.

7. Power-up with the pulse and controller enable signals switched out
8. Determine the angular commutation offset of motor 2

For an incremental measuring system:
as for Chapter 4.10.2, Point 5. (determining the angular commutation offset)

For an absolute measuring system:
Power-down the drive (POWER ON–RESET)
Power-up the drive with the pulse or controller enable signals switched-out
Set P1017.0 to 1
Switch-in the pulse and enable signals
--> The angular offset is automatically entered into P1016
--> Fault 799
(Save to FEPROM and HW–RESET required)
is displayed

9. Traverse the axis and check that it is functioning correctly

10. Note the angular commutation offset of motor 2
- P1016 (motor 2) = __ __ __ __ __ __ degrees electrical

11. Deviation between Point 4. (motor 1) and Point 10. (motor 2)
if ≤ 10 degrees --> OK
If > 10 degrees
--> Check and correct the mechanical arrangement
(refer to Chapter 4.10.4 and 4.10.7)
or
--> Carry-out a check by making the appropriate measurements
(refer to Chapter 4.10.8)

12. Delete the drive configuration
Operator action: "Options - Service - Delete drive configuration"

13. Power-down and wait until the DC link has been discharged

14. Connect the 2 linear motors in parallel again
Connect both of the motors back to the power module.

15. Power-up with the pulse and controller enable signals switched out

16. Commission the linear motors connected in parallel
- Work completely through Chapter 4.10.2
- In the "motor selection" dialog box, select the motor connected in parallel (2 • 1FNx ...)
or
enter the data of the unlisted motor connected in parallel (refer under the index entry "unlisted motor - parameters for SLM")
17. Compare the angular commutation offset between motors 1 and 2

P1016 (motor 1, refer to Point 4.) = __________
P1016 (motor 2, refer to Point 10.) = __________

if the difference ≤ 10 degrees  OK
if the difference > 10 degrees not OK

Check and correct the motor cable connection at the power module and determine the angular commutation offset.

For an incremental measuring system:
as for Chapter 4.10.2, Point 5. (determining the angular commutation offset)

For an absolute measuring system:
Power-down the drive (POWER ON–RESET)
Power-up the drive with the pulse or controller enable signals switched-out
Set P1017.0 to 1
Switch-in the pulse and enable signals
---> The angular offset is automatically entered into P1016
---> Fault 799
(Save to FEPROM and HW-RESET required) is displayed
Save to FEPROM and carry-out a HW-RESET
4.10.4 Mechanical system

The mounting dimensions can be checked before mounting the motor, e.g. using the final dimensions and feeler gauges.

The mounting dimensions must lie within the specified tolerance bandwidth over the complete traversing distance.

**Note**

The valid mounting dimensions can be taken from the following references:

- **Reference:** Configuration Manual
  Linear Motors of the Product Family 1FN1 or
  Linear Motors 1FN Peak-Load Motors of the
  Product Family 1FN3

- The data sheet of the appropriate motor

For mounting dimension and air gap, the following applies:

Only the mounting dimension is decisive and not the air gap which can be measured, when it comes to maintaining the electrical and system-related characteristics of the linear motor. The air gap must be large enough so that the motor can freely move.

---

**Table 4-10 Important mounting dimensions and air gap for 1FN1 motors**

<table>
<thead>
<tr>
<th>Important dimension to be checked</th>
<th>Linear motors</th>
<th>1FN1 ...</th>
</tr>
</thead>
<tbody>
<tr>
<td>Mounting dimension $e_1$ [mm]</td>
<td>1FN1 07</td>
<td>1FN1 12</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1FN1 18</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1FN1 24</td>
</tr>
<tr>
<td>Mounting dimension $e_2$ [mm] (without thermal insulating strips)</td>
<td>80.7 ± 0.3</td>
<td>106.7 ± 0.3</td>
</tr>
<tr>
<td>Measurable air gap $l$ [mm] (without taking into account the mounting dimension tolerance)</td>
<td>76.7 ± 0.3</td>
<td>101.7 ± 0.3</td>
</tr>
<tr>
<td>Clearance $b$ [mm] (without taking into account the mounting dimension tolerance)</td>
<td>1.1 ±0.3/-0.45</td>
<td>1.1 ±0.3/-0.45</td>
</tr>
<tr>
<td></td>
<td>13 ± 1</td>
<td>13 ± 1</td>
</tr>
</tbody>
</table>
4.10 Linear motors (1FN1, 1FN3 motors)

Checking the mounting dimensions 1FN3

Fig. 4-16 Important dimensions when mounting the motor

<table>
<thead>
<tr>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>1FN3 050– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td>63.4</td>
<td>60.4</td>
<td>48.5</td>
<td>51.5</td>
</tr>
<tr>
<td>1FN3 100– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td>65.4</td>
<td>62.4</td>
<td>50.5</td>
<td>53.5</td>
</tr>
<tr>
<td>1FN3 150– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td>79.0</td>
<td>76.0</td>
<td>64.1</td>
<td>67.1</td>
</tr>
<tr>
<td>1FN3 300– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td>81.0</td>
<td>78.0</td>
<td>66.1</td>
<td>69.1</td>
</tr>
<tr>
<td>1FN3 450– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td>86.0</td>
<td>76.0</td>
<td>64.1</td>
<td>67.1</td>
</tr>
<tr>
<td>1FN3 600– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td>88.0</td>
<td>78.0</td>
<td>66.1</td>
<td>69.1</td>
</tr>
<tr>
<td>1FN3 900– ...</td>
<td>±0.3</td>
<td>0.9</td>
<td>1.3</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Check the air gap

After mounting the motor components, the air gap between the primary and secondary sections can be optionally checked. Generally, this is not necessary. If the mounting dimensions are correct, the correct air gap is automatically obtained. If, after mounting, the air gap does not match the data in Table 4-11, either the motor has been incorrectly mounted, or the specified motor dimensions were not maintained when the motor was produced.
4.10.5 Thermal motor protection

Description

Two independent monitoring circuits are available for the 1FN1, 1FN3 primary sections for thermal motor protection.

The absolute, average winding temperature can be measured using the temperature sensor (Temp–F) comprising a temperature sensor (KTY 84).

The overtemperature shutdown circuit (Temp–S) allows each individual motor phase winding to be digitally monitored for an overtemperature condition.

The two independent temperature circuits Temp–F and Temp–S can be used for motor protection, either individually or together. At least one Temp–S must be used for the motor overtemperature protection.

The circuit and connection system for Temp–F and Temp–S are described in detail in:

---

Reader’s note

Reference: Configuration Manual of the Product Family 1FN1 or 1FN3

---

Danger

The circuits of Temp–F and Temp–S neither have "protective separation" between each other nor to the power circuits in accordance with VDE 0160/EN 50178.

Thus, they may not be used as SELV/PELV circuits, or connected with these. Also refer to the literature reference mentioned above!

---

Note

Temp–S must be connected for thermal motor protection; it is not permissible not to connect Temp–S!

Temp–F can be optionally connected to a measuring device for commissioning and testing.

For regular operation, the Temp–F connections should be short-circuited and connected to PE.
4 Commissioning 08.01

4.10 Linear motors (1FN1, 1FN3 motors)

**Temperature sensor Temp-F**

The resistance change is proportional to the winding temperature change.

- Resistance when cold (20 °C): approx. 580 Ohm
- Resistance when hot (100 °C): approx. 1000 Ohm

**Response temp.:**

1FN1:
- Pre-warning at 120 °C
- Trip at 155 °C ± 5 °C (standard setting)

1FN3:
- Pre-warning at 100...110 °C (depending on the machine type)
- Trip at 120 °C ± 5 °C

---

**Warning**

- If the user carries out an additional high-voltage check, the cable ends of the Temp-F should be short-circuited before the check! If the test voltage is connected to the temperature sensors, it will destroy them.

- When connecting-up Temp-F, please observe the polarity!

---

**Fig. 4-17 Characteristic, temperature sensor (Temp-F)**

**Note**

The temperature sensor (Temp-F) only evaluates the winding temperature of one phase in the primary section. However, the phases in the synchronous motor are loaded to different degrees depending on the particular load, so that in the worst case, the phases, not measured, have the higher temperatures.
4.10 Linear motors (1FN1, 1FN3 motors)

Note
For protective separation, it is not permissible to connect Temp–F at the encoder connector X411/X412 of the SIMODRIVE power module without using a suitable protective module.

When handling and connecting Temp–F, it must be assumed, that when the drive is powered up, there are hazardous voltages at the terminals on the motor side and at the Temp–F connecting cable – this means that the drive must always be disconnected so that it is ensured that it really is in a no-voltage condition.

The overtemperature shutdown circuit Temp–S has an NC contact for each motor phase winding. The NC contacts are connected in series.

Table 4-12 Shutdown and switch-in temperatures for the overtemperature shutdown circuit

<table>
<thead>
<tr>
<th></th>
<th>1FN1 07, 12</th>
<th>1FN1 18, 24</th>
</tr>
</thead>
<tbody>
<tr>
<td>Shutdown temperature</td>
<td>130 °C</td>
<td>140 °C</td>
</tr>
<tr>
<td>Switch-on temperature</td>
<td>approx. 70 °C</td>
<td>approx. 70 °C</td>
</tr>
<tr>
<td>Tolerance, switch-in temperature</td>
<td>± 20 °C</td>
<td>± 20 °C</td>
</tr>
<tr>
<td>Tolerance, shutdown temperature</td>
<td>± 5 °C</td>
<td>± 5 °C</td>
</tr>
</tbody>
</table>

Temp–S can be connected to the PLC through a series resistor 20 Ω < $R_V$ ≤ 100 Ω via a 3RN1013–1BW10 thermistor motor protection device.

The series resistor is required in the sensor circuit due to the short-circuit detection function which is integrated in the 3RN1013–1BW10 thermistor motor protection device. Several Temp–S circuits can be connected in series for each 3RN1013–1BW10 thermistor motor device. However, only one series resistor should be used for each 3RN1013–1BW10 thermistor motor protection device $R_V$.

Temperature shutdown circuit comprising PTC temperature sensors (PTC elements).

There is one PTC temperature sensor (PTC element) in each of the three phase windings (U, V and W). The PTC elements are connected in series. The characteristics of the PTC elements are in compliance with DIN VDE 0660 Part 303, DIN 44081 and DIN 44082.
Type: PTC temperature resistor

Nominal response temp. ($\Theta_{\text{NAT}}$)

<table>
<thead>
<tr>
<th>Temperature Range</th>
<th>Resistance Range</th>
</tr>
</thead>
<tbody>
<tr>
<td>$T &lt; \Theta_{\text{NAT}} - 20$°C</td>
<td>Min. 60 $\Omega$ (3 x 20 $\Omega$)</td>
</tr>
<tr>
<td>$T = \Theta_{\text{NAT}} - 5$°C</td>
<td>Min. 590 $\Omega$ (550 $\Omega$ + 2 x 20 $\Omega$)</td>
</tr>
<tr>
<td>$T = \Theta_{\text{NAT}} + 5$°C</td>
<td>Min. 1370 $\Omega$ (1330 $\Omega$ + 2 x 20 $\Omega$)</td>
</tr>
<tr>
<td>$T = \Theta_{\text{NAT}} + 15$°C</td>
<td>Min. 4100 $\Omega$ (4000 $\Omega$ + 2 x 20 $\Omega$)</td>
</tr>
</tbody>
</table>

Minimum triplet resistance when hot

Temp-S can be connected to a PLC via a 3RN1013-1BW10 thermistor motor protection device. A max. of two Temp-S circuits can be connected in series for each 3RN1013-1BW10 thermistor motor protection device (total resistance when cold $\leq$ 1.5 k$\Omega$).

**Note**

For protective separation, it is not permissible to connect Temp-S to the PLC or at the encoder connector X411/X412 of the SIMODRIVE power module without using a 3RN1013-1BW10 thermistor motor protective device.

When handling and connecting Temp-F, it must be assumed, that when the drive is powered up, there are hazardous voltages at the terminals on the motor side and at the Temp-F connecting cable - this means that the drive must always be disconnected so that it is ensured that it really is in a no-voltage condition.

How are the temperature sensors evaluated?

Please refer to the following note for the reader:

**Reader’s note**

Reference: Configuration Manual of the Product Family 1FN1 or 1FN3
4.10.6 Measuring system

Determining the control sense

The control sense of an axis is correct if the positive direction of the drive (= clockwise rotating field U, V, W) coincides with the positive counting direction of the measuring system.

Note

The data to determine the drive direction is only valid for Siemens motors (1FNx motors).

If the positive direction of the drive and positive counting direction of the measuring system do not coincide, then when commissioning, the speed actual value (P1011.0) must be inverted in the "measuring system/encoder" dialog box.

The control sense can also be checked by first parameterizing the drive, and then manually moving it, with the enable signals inhibited (switched out).

If the axis is pushed in the positive direction (refer to the definition in Fig. 4-18), then the velocity actual value must also count in the positive direction.

Determining the drive direction

The direction of the drive is positive if the primary section moves relative to the secondary section in the opposite direction to the cable outlet direction.

Determining the counting direction of the measuring system

The counting direction is determined depending on the measuring system itself.

- Measuring systems from the Heidenhain Company

Note

The counting direction of the measuring system is positive, if the distance between the sensor head and rating plate increases.
• Measuring systems from Renishaw (e.g. RGH22B)

The RGH22B measuring system from Renishaw (grid division = 20 μm) only has connections which are compatible to Heidenhain from serial number G69289 onwards. For earlier sensor heads, the zero mark cannot be evaluated.

As the reference mark for the Renishaw RGH22B has a direction-dependent position, with control cables BID and DIR, the encoder must be parameterized, so that the reference mark is only output in one direction. The direction (positive/negative) depends on the geometrical arrangement at the machine and the reference point approach direction.

Table 4-13  Signal and pin assignments, signal marshaling

<table>
<thead>
<tr>
<th>Signal</th>
<th>Cable color</th>
<th>Round connector, 12-pin</th>
<th>Connected to</th>
</tr>
</thead>
<tbody>
<tr>
<td>BID</td>
<td>Black</td>
<td>Pin 9</td>
<td>+5 V</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>0 V</td>
</tr>
<tr>
<td>DIR</td>
<td>Orange</td>
<td>Pin 7</td>
<td>+5 V</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>0 V</td>
</tr>
<tr>
<td>+5 V</td>
<td>Brown</td>
<td>Pin 12</td>
<td>Reference mark in both directions</td>
</tr>
<tr>
<td>0 V</td>
<td>White</td>
<td>Pin 10</td>
<td>Reference mark in one direction</td>
</tr>
</tbody>
</table>

The counting direction of the measuring system is positive if the sensor head moves relative to the gold band in the cable outlet direction.

Fig. 4-20  Determining the counting direction for measuring systems from Renishaw

Note

If the sensor head is mechanically connected to the primary section, the cable outlet direction must be different. Otherwise, invert the actual value!

• Measuring systems from Zeiss (e.g. LIE 5)

Note

The positive counting direction of the linear measuring system from the Zeiss company should be determined just like the measuring system RGH22B from Renishaw (refer to Fig. 4-20).
**Temperature sensor coupling cable**

The temperature sensor coupling cable is used to couple the temperature sensor circuit Temp--F into the encoder cable using connector boxes. The transition from the power cable to encoder cable can be realized at the machine as well as in the cabinet.

How are the temperature sensor coupling cable and length measuring system connected?

Please refer to the following note for the reader:

---

**Reader’s note**

Section “General information on the connection system (CON)” in:

**Reference:** /PJLM/ Configuration Manual, 1FN1, 1FN3 Linear Motors

---

If an incremental measuring system is used, the drive is roughly synchronized using the rotor position identification.

---

**Warning**

When connecting–up the temperature monitoring circuits, carefully observe the specifications relating to protective separation DIN EN 50178.

Information on protective separation can be taken from:

**Reference:** /PJLM/ Configuration Manual, 1FN1, 1FN3 Linear Motors
4.10.7 Parallel and double-cam arrangement of linear motors

**Note**

Only identical linear motors (the same forces, winding types, secondary section types and air gap) may be connected in parallel. (Order designation or Order No. [[MLFB] of the primary sections to be connected in parallel must be identical up to the winding sense and/or primary section length.)

If linear motors in an axis are connected in parallel, the position of the primary sections with respect to one another and to the secondary sections must exhibit a specific grid, in order to achieve a matching electrical phase position.

Additional data, refer to:

**References:**

- PJLM/ SIMODRIVE Configuration Manual, 1FN1, 1FN3 Linear Motors

---

**Temperature sensor and electrical wiring (refer to Chapter 4.10.5)**

The temperature sensors can be evaluated, for example, as follows:

- **Temperature sensor**
  - Motor 1: Evaluated by the drive
  - Motor 2: Not connected (short-circuited and connected with PE)

- **Temperature switch**
  - Motor 1 and 2: Evaluated by a PLC

---

**Reader’s note**

Section “General information on the connection system (CON)” in:

**Reference:**

/PJLM/ Configuration Manual, 1FN1, 1FN3 Linear Motors

---

**Warning**

When connecting-up the temperature monitoring circuits, carefully observe the specifications relating to protective separation DIN EN 50178.

Information on protective separation can be taken from:

**Reference:**

/PJLM/ Configuration Manual, 1FN1, 1FN3 Linear Motors
4.10.8 Checking the linear motor by making measurements

Why make measurements? If the linear motor was commissioned according to the relevant instructions, and unexplained fault/error messages still occur, then all of the signals must be checked using an oscilloscope.

Checking the phase sequence U-V-W

For primary sections connected in parallel, the EMF_U from motor 1 must be in phase with the EMF_U from motor 2. The same applies to EMF_V and EMF_W. These must be checked using the appropriate measurements.

Procedure for making the necessary measurements:
- De-energize terminal 48 (NE module) and terminal 663 (drive).
- Caution: Wait until the DC link has been discharged!
- Disconnect the power cables at the drive. If primary sections are connected in parallel, please disconnect.
- Form an artificial neutral point using 1 kOhm resistors.

For a positive traversing direction, the phase sequence must be U-V-W. The direction of the drive is then positive if the primary section moves relative to the secondary section in the opposite direction to the cable outlet direction.

![Configuration for making the measurements](image)

![The positive direction of the drive (clockwise rotating field)](image)
4.11 Direct measuring system for position control (from SW 3.3)

Description

Alternative to the motor encoder (indirect measuring system, IM) in the "positioning" operating mode, a direct measuring system (DM) can be used for closed-loop position control.

The direct measuring system for drive A, for a 2-axis control board, is connected to X412 (motor encoder, drive B). In this case, drive B must be de-activated.

After the direct measuring system has been activated, the drive evaluates both measuring systems as follows:

- Motor encoder, drive A (IM) at X411:
  --> for the closed-loop speed control of the axis
  --> for the coarse synchronization of the axis rotor position

- Direct measuring system (DM) for drive A at X412:
  --> for the closed-loop position control and "precise" position sensing of axis A

Advantage:

The "actual" position of the axis is sensed using a direct measuring system. Any play between the motor and table is corrected.

![Diagram of indirect and direct measuring system for drive A](image-url)
Limitations and rules for a direct measuring system

The following limitations and rules apply:

1. The direct measuring system may only be directly connected at the load side without measuring gearbox.

2. Which combinations of power module and control board are possible for a direct measuring system?
   - 1-axis power module with 2-axis control board
     In this case, drive B is not available.
   - 2-axis power module with 2-axis control board
     Drive B is available.
     The following applies: Switch drive B into a passive state (P0700 (B) = 0)

3. Which encoder systems are available for the direct measuring system?
   Dependent on the 2-axis board with encoder for sin/cos 1 Vpp or for resolver, the following rotary or linear measuring systems can be connected at X412:
   - Incremental encoder with sin/cos 1 Vpp
   - Absolute value encoder with EnDat protocol
   - Resolver with any pole pair number

4. Process data for the direct measuring system
   The actual values of the position controller can be read via status word XistP.

5. The "direct measuring system" function is activated with P0250 (A) = 1.
   The following applies:
   - This activation becomes effective after POWER ON
   - The direct measuring system must have been commissioned
     --> refer to "commissioning the direct measuring system"
   - It is not permissible to operate drive A without a motor measuring system.
     --> The following must be valid: P1027.5 (A) = 0
   - The input terminal I0.B (fast input from drive B) can be assigned a function for the direct measuring system from drive A via P0672.
     e.g. the "Equivalent zero mark" function (P0672=79) or "flying measurement" (P0672=80)
6. Output the direct measuring system via the angular incremental encoder interface
   - Before SW 4.1 the following applies:
     The direct measuring system signals cannot be output via the angular incremental encoder interface.

     If the angular incremental encoder interface is switched as output (P0890 = 1), then the following is valid, independent of activating the direct measuring system (P0250 (A) = 0 or 1):

     Interface | Output signals
     Ang. incr. enc. interf. (A) | Signals of the motor meas. system
     Ang. incr. enc. interf. (B) | No signals

   - From SW 4.1, the following applies:
     The direct measuring system signals can be output via the angular incremental encoder interface. The angular incremental encoder interface as output becomes automatically active if P0890 is set to 1 for the motor measuring system AND the direct measuring system is activated (P0250 = 1). However, parameters P0892 and P0893 are not effective for the angular incremental encoder interface (B).

     Interface | Output signals
     Ang. incr. enc. interf. (A) | Signals of the motor meas. system
     Ang. incr. enc. interf. (B) | Signals of the direct

7. Direction adaptation for direct measuring systems
   - P0231  Position act. value inversion
   - P0232  Position ref. value inversion

8. You can toggle between the indirect measuring system (IM) and the direct measuring system (DM) by changing P0250 and executing a POWER–ON RESET.
   - The parameters for the closed–loop position control are only available once and must also be appropriately adapted, e.g.:
     P0231  Position act. value inversion
     P0332  Position ref. value inversion
     P0201  Backlash compensation

   - The parameters for the gearbox and spindle pitch are only available once and must be set for the indirect measuring system, e.g.:
     P0236  Spindle pitch
     P0237:8  Encoder revolutions
     P0238:8  Load revolutions

   - The adjustment status for absolute value encoders is changed after changeover, i.e. P0175 is set to 0. A re–adjustment is required.

9. Which measuring system does the drive control use?
   --> refer to P1792 (active measuring system)
Commissioning the direct measuring system

The following should be observed when commissioning:

Requirements:
1. The direct measuring system must have been installed, connected at X412 and the system must be ready to be powered up.
2. The specified rules and limitations have been maintained.

Procedure:
1. Enter an encoder code for the direct measuring system
   The encoder code number is requested when first commissioning the system in the "Positioning" mode via P1036.
   
   if No DM then
   P1036 = 0
   DM available then
   P1036 = 99 (unlisted encoder) and enter data (refer to Chapter A.4)

2. Activate the direct measuring system
   Set P0250 (A) to 1

3. Execute a POWER-ON RESET and check the function

Parameter overview (refer to Chapter A.1)

The following parameters are available for the indirect and direct measuring systems:

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter Name</th>
<th>No.</th>
<th>Parameter Name</th>
</tr>
</thead>
<tbody>
<tr>
<td>0250</td>
<td>Activates the direct measuring system (only possible for drive A)</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>1005</td>
<td>IM encoder pulse number</td>
<td>1007</td>
<td>DM encoder pulse number</td>
</tr>
<tr>
<td>1006</td>
<td>IM encoder code number</td>
<td>1036</td>
<td>DM encoder code number</td>
</tr>
<tr>
<td>1008</td>
<td>IM encoder phase error correction</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>1011</td>
<td>IM configuration, actual value sensing</td>
<td>1030</td>
<td>DM configuration, actual value sensing</td>
</tr>
<tr>
<td>1018</td>
<td>IM pole pair number resolver</td>
<td>1040</td>
<td>DM pole pair number resolver</td>
</tr>
<tr>
<td>1021</td>
<td>IM multi-turn resolution, absolute value encoder</td>
<td>1031</td>
<td>DM multi-turn resolution, absolute value encoder</td>
</tr>
<tr>
<td>1022</td>
<td>IM single-turn resolution, absolute value encoder</td>
<td>1032</td>
<td>DM single-turn resolution, absolute value encoder</td>
</tr>
<tr>
<td>1023</td>
<td>IM diagnostics</td>
<td>1033</td>
<td>DM diagnostics</td>
</tr>
<tr>
<td>1024</td>
<td>IM grid division</td>
<td>1034</td>
<td>DM grid division</td>
</tr>
<tr>
<td>1025</td>
<td>IM serial number, low component</td>
<td>1038</td>
<td>DM serial number, low component</td>
</tr>
<tr>
<td>1026</td>
<td>IM serial number, high component</td>
<td>1039</td>
<td>DM serial number, high component</td>
</tr>
<tr>
<td>1027</td>
<td>IM configuration, encoder</td>
<td>1037</td>
<td>DM configuration, encoder</td>
</tr>
</tbody>
</table>

1) IM --> indirect measuring system (motor encoder)
2) DM --> direct measuring system (encoder 2)
4.12 Connecting induction motors with TTL encoder (from SW 8.1)

Description
Standard square-wave encoders (TTL) with differential signals according to RS422 and 5 V power supply voltage can be connected as pulse encoder for induction motors to the control board “SIMODRIVE 611 universal HR/HRS” (Order No. 6SN1118-□NH01-0AA□).

The maximum encoder limiting frequency is 420 kHz.

Connection
Encoder connection: X411/X412
Pin assignment of the interface: refer to Chapter 2.4
Encoder cable: Users must assemble these themselves
Max. cable length: 50 m

Note
If an induction motor with TTL encoder is connected to “SIMODRIVE 611 universal HR/HRS”, then it is not permissible that the angular incremental encoder interface is used as output.

Warning
If individual or several signals of the encoder are short-circuited or interrupted - under certain circumstances - it is possible that the encoder signal monitoring does not respond and the motor can move in an uncontrolled fashion.

Parameter overview (refer to Chapter A.1)
The following parameters are available for connecting an induction motor with TTL encoder:
- P1011 IM configuration, actual value sensing
- P1005 IM encoder pulse number
- P1027 IM configuration, encoder
4.13 FD operation with field weakening (from SW 12.1)

Description
In order to be able to use field weakening – also with the FD machine data assignments, e.g. for 1FT7 motors, then this can be activated by setting P1172 = 1 in addition to P1015 = 1.

Closed-loop control parameters
If P1015 and P1172 were enabled and a motor selected using the list diagram, then the following machine data are additionally pre-assigned using the “Calculate controller data” function:

- P1121: Current controller reset time
- P1147: Speed limitation (ARM SRM)
- P1401: Velocity for max. useful motor velocity (ARM SRM)
- P1403: Creep speed, pulse suppression (ARM SRM)
- P1404: Timer pulse suppression
- P1405: Monitoring speed, motor (ARM SRM)
- P1606: Threshold n controller at stop
- P1610: Diagnostic functions
- P1612: Shutdown response, faults 1
- P1613: Shutdown response, faults 2

Note
For synchronous motors, field-weakening operation can be switched-in using P1015.

“Calculate controller data” must be initiated after changing the machine data setting!

The speed at the start of field weakening is assigned by selecting the motor from the motor list or set according to the data sheet of the motor manufacturer.

If the motor manufacturer does not specify any data, then the speed at the start of field weakening can be calculated using the following formula:

\[ P1142 = 380 \text{ V} \times 1000 \text{ [RPM]} / P1114 \]

P1114: EMF_VOLTAGE
4.13 FD operation with field weakening (from SW 12.1)

Note

P1172 is only effective, if P1015 = 1 was set – “Activate PE-MSD”.

“Calculate controller data” must be initiated after changing the machine data setting!

The following parameters are used for FD operation with field weakening:
- P1015 Activate PE-MSD (SRM)
- P1114 Voltage constant (SRM SLM)
- P1142 Threshold speed field weakening (ARM SRM)
- P1172 FD operation with field weakening (SRM) (→ 12.1)
# Communications via PROFIBUS DP

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<th>Title</th>
<th>Page</th>
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5.1 General information about PROFIBUS-DP for "SIMODRIVE 611 universal"

**General**

PROFIBUS DP is an international, open fieldbus standard, which is specified in the European Fieldbus Standard EN 50170 Part 2. PROFIBUS DP is optimized for fast, data transmission at the field level for time-critical applications.

The fieldbus is used for cyclic and non-cyclic data transfer between a master and the slaves assigned to this master.

The following communication possibilities are available:

- **Cyclic communication**
  - Setpoint, actual value transfer using process data (PZD communications)
  - According to the DP standard functionality
    - For standard DP operation, a new cycle is started after the old cycle has been completed.
      - refer to Chapter 5.2
  - Clock-cycle synchronous functionality
    - For clock-cycle synchronous operation a new cycle is started with the set Tp clock cycle.
      - refer to Chapter 5.2
  - Slave-to-slave communications
    - Fast, distributed data transfer between drives (slaves) is possible using the "slave-to-slave" communications function without involving the master.
      - refer to Chapter 5.10

- **Noncyclic communication**
  - Access to the drive parameters
    - Parameterization using the "SimoCom U" tool
      - refer to Chapter 3.3
    - Data transfer using the SIMATIC Operation Panel (SIMATIC OP)
      - refer to Chapter 5.3
    - PKW area in the net data structure according to PPOs
      - refer to Chapter 5.6.7
    - Data exchange with the master (e.g. SIMATIC S7) and other control devices, utilizing the DPV1 utility (service) "read data set/write data set" corresponding to the PROFIdrive Profile
      - refer to Chapter 5.3

- **Configuration**
  - Configuring defines the data, which the master transfers to the "DP slaves" at every bus run-up via the parameterizing telegram and the configuration telegram.

The system can be configured in the following ways (refer to Chapter 5.7):

- using the GSD file (SIEM808F.GSD/SI02808F.GSD)
- using the "Slave object manager" (Drive ES)
5.1 General information about PROFIBUS-DP for "SIMODRIVE 611 universal"

The profile defines, among other things, how setpoints and actual values are transferred and how drive parameters can be accessed.

- The profile includes the necessary definitions for the operating mode "Speed setpoint" and "Positioning".
- It defines the basic drive functions and leaves sufficient freedom for application-specific expanded functionality and ongoing developments.
- The profile includes an image of the application functions on PROFIBUS-DP.
- The PROFIdrive Profile provides a total of 6 different application classes.
- "SIMODRIVE 611 universal" is in conformance with the profile for application Class 1 and from SW 6.1, application Class 4.

The following functional scope has been implemented corresponding to the directive PROFIdrive V3.1 – 2002. From SW 12.1, operation according to the PROFIdrive profile version V4.1 – 2006 is possible:

- Isochronous mode
- Configuring a telegram
- Encoder interface
- Non-cyclic parameter access using DPV1 utilities
- Profile parameters

The following parameters should be set in order, for this functionality, to achieve the precise compatibility to profile version 3.1:

- P0878 bit 0 = 1, bit 1 = 1, bit 2 = 1 (from SW 8.2)
- P0879 bit 0 = 1, bit 1 = 0, bit 2 = 0, bit 9 = 1
- P1012 bit 12 = 1, bit 13 = 1, bit 14 = 0, bit 15 = 1 (from SW 9.1)

In order to achieve compatibility to profile version 4.1, the following parameters must also be set:

- P0878 bit 3 = 1 (from SW 12.1)

---

Reader's note

Standard telegrams are defined to simplify configuring PROFIBUS-DP.

Telegrams 1, 2 ..., 6 are designated as standard telegrams corresponding to PROFIdrive definitions and telegrams 102...110 from Siemens are designated as standard telegram.
5 Communications via PROFIBUS DP

5.1 General information about PROFIBUS-DP for "SIMODRIVE 611 universal"

**Master and slaves**

For PROFIBUS, a differentiation is made between master and slave units.

- **Master (active bus device)**

  Devices, which represent a master on the bus, define data transfer along the bus, and are therefore known as active bus nodes.

  A differentiation is made between two classes of master:

  - **DP Master class 1 (DPMC1):**
    These are central master systems that exchange data with the slaves in defined message cycles.
    Examples: SIMATIC S5, SIMATIC S7, etc.

  - **DP Master class 2 (DPMC2):**
    These are devices for configuring, commissioning, operator control and monitoring in bus operations.
    Examples: Programming units, operator control and visualization devices

- **Slaves (passive bus nodes)**

  These devices may only receive, acknowledge and transfer messages to a master when so requested.

**Reader’s note**

The "SIMODRIVE 611 universal" control board with the optional PROFIBUS-DP module is a slave on the fieldbus.
In the following text, this slave is designated the "DP slave 611U".

**Data transfer technology, baud rate**

PROFIBUS supports data transfer according to RS485 and also data transfer using fiber-optic cable.

The "DP-Slave 611U" automatically detects the baud rate set at the bus at power-on.
The following baud rates are possible:
9.6 kbaud, 19.2 kbaud, 93.75 kbaud, 187.5 kbaud,
500 kbaud, 1.5 Mbaud, 3.0 Mbaud, 6.0 Mbaud and 12 Mbaud

**Note**

- When using Optical Link Plugs (OLPs), the baud rate is limited to 1.5 Mbaud.
- When several slaves are connected to a master, for practical and sensible operation with SimoCom U, a baud rate \( \geq 187.5 \text{ kbaud} \) should be set.

When commissioning the fieldbus, the baud rate is defined the **same for all devices** starting from the master.
5.1 General information about PROFIBUS-DP for “SIMODRIVE 611 universal”

Data transfer via PROFIBUS

Data is transferred between the master and slaves according to the master/slave principle. The drives are always the slaves. This permits extremely fast cyclic data transfer.

In addition, non-cyclic communications functions are also used for parameterization, diagnostics and fault/error handling during cyclic data transfer with drives.

![Data transfer via PROFIBUS](image)

Fig. 5-1 Data transfer via PROFIBUS

Transferring words and double words

All of the word and double word formats used are transferred in the Big Endian format, i.e. the high byte or high word is transferred before the low byte or low word.

Protocols

The communications type corresponds to the protocol shown in Fig. 5-2 for the “DP slave 611U”.
Parameters can be read and written into according to the protocol, defined in the PROFIdrive Profile via the DPV1 parameter channel.

Fig. 5-2 Protocol for "DP slave 611U"
The "SIMODRIVE 611 universal" control board together with the optional PROFIBUS-DP module is used to connect drives to higher-level automation systems via PROFIBUS-DP.

"SIMODRIVE 611 universal" identifies the installed optional PROFIBUS-DP module at power-on.

If an optional module is used, the input/output functions can be selected via PROFIBUS-DP, or also entered as setpoints. The compatibility between the terminal and PROFIBUS signals is described in Chapter 5.4.

Fig. 5-3 "SIMODRIVE 611 universal" with optional PROFIBUS-DP module

Reader’s note
- Which modules are available? refer to Chapter 1.3.3
- Installing the optional module refer to Chapter 2.1
- Connecting-up diagram and connecting-up the optional module refer to Chapter 2.3.4
5.2 Basic functions of the cyclic data transfer

Net data structure according to PPOs

The structure of the net data for cyclic operation, is designated as parameter-process data-object (PPO) in the "PROFIBUS profile, variable-speed drives".

The net data structure for cyclic data transfer is sub-divided into two areas, which are transferred in each telegram.

- Parameter area (PKW, parameter identification value)
  This telegram section is used to read and/or write parameters and to read out faults. The data transfer is optional and can be defined by appropriately configuring the system.
  The mechanisms, used to apply the PKW part, are described in Chapter 5.6.7.

- Process data area (PZD, process data)
  This area contains the control words, setpoints and status information and actual values.

  The following data is transferred with the process data:
  - Control words and setpoints (task: master --> drive) and
  - Status words and actual values (responses: drive --> master)

When the bus system is commissioned, the master defines which PPO type is used to address a drive. The "DP slave 611U" is automatically signaled the selected PPO-TYPE using the configuration telegram when the system boots.

Telegram structure for cyclic data transfer

With cyclic data transfer, setpoints and actual values are transferred one after the other between the master and its associated slaves in a cycle.

For standard DP operation, a new cycle is started after the old cycle has been completed.

For clock-synchronous operation, a new cycle is started with the selected TDP clock cycle.

The telegrams of the cyclic data transfer have, in both cases, the following basic structure:

<table>
<thead>
<tr>
<th>Drive A</th>
<th>Drive B</th>
</tr>
</thead>
<tbody>
<tr>
<td>Net data (PPO)</td>
<td>Net data (PPO)</td>
</tr>
<tr>
<td>Parameter ID value (PKW)</td>
<td>Parameter ID value (PKW)</td>
</tr>
<tr>
<td>Process data (PZD)</td>
<td>Process data (PZD)</td>
</tr>
</tbody>
</table>

Note:
Net data for drive B is only transferred, if the "DP slave 611U" operates as double-axis module.
---> refer to Chapter 5.9 under P0875
1) Transfer is optional and is defined by appropriately configuring the system.

Fig. 5-4 Telegram structure for cyclic data transfer
The PPO selection can be subdivided into:

- **Net data without** parameter area
  with 2 to 16 words for the process data.
  and
- **Net data with** parameter area
  with 2 to 16 words for the process data.
  These are the PPO types 1, 2 and 5.

A different number of process data is permissible for the setpoints and actual values (from SW 3.1).

In addition to being able to freely set the number of process data, the configuring allows standard settings to be selected. This includes, in addition to the PPO types PPO1 to PPO5 (refer to Table 5-1) a whole series of configured functions (GSD file, Drive ES), which are suitable for the various standard telegrams.

### Table 5-1 Parameter process data objects (PPO types)

<table>
<thead>
<tr>
<th>PPO</th>
<th>PIV</th>
<th>PD</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>• See Chapter 5.6.7</td>
<td>• In closed-loop speed controlled operation, refer to Chapter 5.6.6</td>
</tr>
<tr>
<td></td>
<td>• In the positioning mode, refer to Chapter 5.6.6</td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>PKE</th>
<th>IND</th>
<th>PWE</th>
<th>PZD 1</th>
<th>PZD 2</th>
<th>PZD 3</th>
<th>PZD 4</th>
<th>PZD 5</th>
<th>PZD 6</th>
<th>PZD 7</th>
<th>PZD 8</th>
<th>PZD 9</th>
<th>PZD 10</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st word</td>
<td>2nd word</td>
<td>3rd word</td>
<td>4th word</td>
<td>1st word</td>
<td>2nd word</td>
<td>3rd word</td>
<td>4th word</td>
<td>5th word</td>
<td>6th word</td>
<td>7th word</td>
<td>8th word</td>
<td>9th word</td>
</tr>
</tbody>
</table>

**Abbreviations:**
- **PPO** Parameter Process data Object
- **PKW** Parameter ID value
- **PKE** Parameter ID
- **IND** Sub-index, sub-parameter number, array index
- **PWE** Parameter value
- **PZD** Process data

**Notice**

The five various PPOs are selected with different data length depending on the task that the drive has to fulfill in the automation environment.

**Configuring process data (from SW 3.1)**

The process data structure of the telegram can be defined and configured as follows from SW 3.1:

- By selecting a standard telegram
- By freely configuring a telegram
  --> Refer to Chapter 5.6.5
5.3 Basic functions of the non-cyclic data transfer

There are three non-cyclic channels which can be accessed on the drive parameters from "SIMODRIVE 611 universal" via PROFIBUS-DP. An overview of how parameters can be accessed for "SIMODRIVE 611 universal" is shown in the following diagram.

![Diagram](image)

**Note**

Every parameter is allocated a parameter number. Profile-specific parameters are defined for the ranges decimal 900 to 999 and are reserved from decimal 60000 to 65535.

In order to remain compatible to previous parameter assignments, when accessing via the DPV1 parameter channel (reading/writing) in the drive firmware, the index is output starting with 1 and on the PROFIBUS side reduced by 1 (n-1).

**PKW (cyclic)**

"SIMODRIVE 611 universal" is compatible to the PKW mechanism in the PROFIdrive Profile, Version 2 and P0879.11; this allows a non-cyclic parameter access to be carried-out within the cyclic data exchange.
### Parameter access via DPV1

Using PROFIdrive, it is possible to transfer parameters via DPV1 using non-cyclic communications. The parameter definition and parameter access via the DPV1 mechanism is defined in the PROFIdrive parameter model, which is part of the PROFIdrive Profile Version 3 and 4 (from SW 12.1).

The function blocks and project examples for SIMATIC S7 can be used to transfer drive parameters in a non-cyclic fashion:

<table>
<thead>
<tr>
<th>Product</th>
<th>Order No. (MLFB):</th>
</tr>
</thead>
<tbody>
<tr>
<td>Drive ES SIMATIC</td>
<td>6SW1700–5JC00–2AA0</td>
</tr>
</tbody>
</table>

### Reader’s note

**Reference:**
- /PPA/, PROFIdrive–Profile Drive Technology, Version 3.1.2 Sept. 2004 (Chapter 3.4)
- From SW 12.1:
  - Version 4.1 May 2006 (Chapter 6.2)

### Parameters, reading/writing DPV1 (from SW 6.1)

A protocol has been defined for accessing parameters which comprises tasks and the associated responses. The tasks are non-cyclically transferred using the DPV1 utility “write data” and the responses with “read data”. Several drive parameters (e.g. traversing block) can be simultaneously accessed using a task/response.

A DPV1 parameter task and a DPV1 parameter response with individual fields is defined and documented in the PROFIdrive profile.

When reading and writing parameters, that, depending on the current configuring of the drive, are not valid - e.g. P1083 is only valid for induction motors, however, a synchronous motor is configured - then the Siemens-specific DPV1 error code 0x65 (parameter presently de-activated) is output.

Values of signal parameters (50000-type parameters) can only be read if this was configured in the PROFIBUS telegram (P0915, P0916). A negative acknowledgement (DPV1 error code 0x65) is output when reading signal parameters using non-cyclic data transfer that were not configured in the Profibus Telegram.

### Read the parameter description DPV1 (from SW 6.1)

The parameters, defined by the profile, are documented in a list form in the PROFIdrive profile.

This includes both parameters with the implementation rule “mandatory”, i.e. parameters that are absolutely necessary in order to be in conformance with the profile as well as parameters with the implementation rule “optional”.

Parameter descriptions can be read so that now a master knows which parameters a drive knows and the properties which each of these parameters has.
5.3 Basic functions of the non-cyclic data transfer

Reader’s note

Reference: PROFIdrive–Profile Drive Technology, Version 3.1.2 Sept. 2004 (Chapter 3.4)
From SW 12.1: Version 4.1 May 2006 (Chapter 6.2)

S7 protocol DPV1
It is possible to non-cyclically transfer parameters via the S7 protocol. For this type of communication, the S7 protocols link to DPV1.

Communications with SIMATIC OP (from SW 4.1)
From SW 4.1, data can be transferred, using the SIMATIC Operator Panel (SIMATIC OP) to “SIMODRIVE 611 universal” via the PROFIBUS–DP.

Fig. 5-6 Communications, SIMATIC OP – “SIMODRIVE 611 universal”
5 Communications via PROFIBUS DP

5.3 Basic functions of the non-cyclic data transfer

- Technical details
  - Communications are established directly between the SIMATIC OP (e.g. TP170B) as Master Class 2 and the "SIMODRIVE 611 universal" as slave using the S7 protocol and the non-cyclic DPV1 utilities.
  - SIMATIC OP can read and write into drive parameters.
  - A Class 1 master is not required.

- Configured in SIMATIC OP
  - The drive parameters are addressed using the data block and data word.
    --> Axis A:
    Data block number_{OP} = parameter number_{611U}
    Data word_{OP} = sub-parameter_{611U}
    --> Axis B:
    Data block number_{OP} = parameter number_{611U} + 10000
    Data word_{OP} = sub-parameter_{611U}

- Parameterization in the "SIMODRIVE 611 universal"
  - A DP2 or DP3 module with a correctly entered DP address (P0918) must be inserted.
  - Parameterize from where the drive is to be operated
    --> PROFIBUS–DP Master Class 1:
    Set P0875 = P872
    --> HW terminals
    Set P0875 to 0

- Setpoint input
  - it is not possible to directly enter setpoints from the SIMATIC OP.
  - Setpoints can be indirectly entered using the SIMATIC OP by changing parameters, e.g. P0641 (fixed setpoint)
    --> Enter the setpoint via HW terminals (P0875 = 0)

Danger
For applications where the setpoint is entered using the SIMATIC OP, in addition, an enable or EMERGENCY STOP signal should be connected to SIMATIC OP, as an interrupted connection between SIMATIC OP and "SIMODRIVE universal" does not result in a drive fault.
5.4 Terminal signals and PROFIBUS signals

**Standard case**

When first commissioning the system with the optional PROFIBUS–DP module inserted (standard case), the control board terminals are automatically pre-assigned as follows:

- Digital input terminals: Terminals I0.x, I1.x, I2.x, I3.x = inactive
- Analog input terminals: Terminals 56.x/14.x, 24.x/20.x = switched-out

Table 5-2 Input terminals for the standard case

<table>
<thead>
<tr>
<th>If</th>
<th>Then</th>
</tr>
</thead>
<tbody>
<tr>
<td>at the first commissioning in the booted state, an optional PROFIBUS–DP module was identified,</td>
<td>these parameters are pre-assigned as follows:</td>
</tr>
<tr>
<td></td>
<td>• P0660 = 0 (function, input terminal I0.x)</td>
</tr>
<tr>
<td></td>
<td>• P0661 = 0 (function, input terminal I1.x)</td>
</tr>
<tr>
<td></td>
<td>• P0662 = 0 (function, input terminal I2.x)</td>
</tr>
<tr>
<td></td>
<td>• P0663 = 0 (function, input terminal I3.x)</td>
</tr>
<tr>
<td></td>
<td>• P0607 = 0 (analog setpoint, terminal 56.x/14.x)</td>
</tr>
<tr>
<td></td>
<td>• P0612 = 0 (analog setpoint, terminal 24.x/20.x)</td>
</tr>
</tbody>
</table>

**Note:**
- Parameter value 0 signifies: the terminal is inactive
- x signifies: Space retainer for drive A or B

**Mixed operation**

The terminal which is inactive or switched out as standard, can be re-assigned a function by appropriately parameterizing the terminal.

**Note**
- Rule for input signals:
  - A HW terminal has priority over a PROFIBUS signal.
- Rule for output signals:
  - The signal is output via the hardware terminal and PROFIBUS

**Example**

There is an optional PROFIBUS–DP module, but in spite of this, an analog speed setpoint is to be input via input, terminal 56.x/14.x.

Solution:

P0607 = 1  --> n_{set}/M_{set} mode possible via terminal 56.x/14.x

The analog speed setpoint via 56.x/14.x is used. The speed setpoint transferred via PROFIBUS–DP is ignored.
5.5 Internal effect of PROFIBUS signal and hardware terminals

Central enable signals

Fig. 5-7 indicates which input terminal signals and PROFIBUS control signals have an effect on the central internal enable signals.

Note:
- e.g.: STW1.1: Control word 1, bit 1

Fig. 5-7 Central enable signals and their dependency on the hardware terminals and PROFIBUS signals
Fig. 5-8 shows which input terminal signals and PROFIBUS control signals have a significant effect on the most important status signals and how they are formed.

**Fig. 5-8 Statuses dependent on the hardware terminals and PROFIBUS signals**

- T.663
- T.63
- STW1.1: OC/OFF 2
- STW1.2: OC/OFF 3
- Fault present (pulse enable)
- Power-on inhibit (refer to Fig. 5-9)
- T.663
- T.63
- T.64
- T.65.x
- STW1.0: ON/OFF 1
- STW1.1: OC/OFF 2
- STW1.2: OC/OFF 3
- Fault present (pulse enable)
- Power-on inhibit (refer to Fig. 5-9)
- Internal speed controller enable
- Regenerative braking
- Brake opening time running
- T.663
- T.63
- STW1.1: OC/OFF 2
- STW1.2: OC/OFF 3

ZSW1.0: Ready to be powered-up/not ready to be powered-up

ZSW1.1: P1012.2
= 1 --> Ready or
= 0 --> No fault

ZSW1.2: Status, controller enable

ZSW1.4: No OFF 2 present

ZSW1.5: No OFF 3 present
Power-on inhibit

If the power-on inhibit is activated (P1012.12 = 1), the drive can no longer move by itself after the "power-on inhibit" has been reached. The "power-on inhibit" status must be removed in order to traverse the drive.

In order to activate the behavior/response in conformance with the PROFIdrive from SW 6.1, bit 13 (power-on inhibit according to the PROFIdrive Profile) is pre-assigned a value of 1 in parameter P1012 (function switch). This means that the behavior/response, in conformance with PROFIdrive, is activated as standard.

Fig. 5-9 indicates which signals and parameters affect the power-on inhibit.

![Diagram of power-on inhibit](image)

**Note**

If, in addition to P1012.13 = 1 also P1012.14 = 1 is set to 1, if the status of signals STW1.1 (OC/OFF 2), STW1.2 (OC/OFF 3 and STW1.0 (ON/OFF 1) simultaneously change from 0 --> 1, this does not result in the "power-on inhibit" state.

Removing the power-on inhibit?

If there is no longer a setting condition for the power-on inhibit, then it can be removed as follows:

- Withdraw the controller enable, terminal 65.x, or
- Reset control signal STW1.0

Switching out the power-on inhibit?

The power-on inhibit can be switched-out with P1012.12 = 0.
5.6 Net data (PKW and PZD area)

5.6.1 Overview of the process data (PZD area)

---

Reader’s note

In the index, for each process data (control/status word), it is specified on which page information can be found on this word.

- refer to "Process data in the n-set mode – control words …"
- refer to "Process data in the n-set mode – status words …"
- refer to "Process data in the pos mode control words …"
- refer to the "Process data in the pos mode – status words - …"
Overview of the control words (setpoints)

From the perspective of the DP master, control words are setpoints. The "DP slave 611U" provides an image of the received process data P1788:17 (control words, setpoints) in P1788:17 (received process data, PROFIBUS).

Table 5-3 Overview of the control words (setpoints)

<table>
<thead>
<tr>
<th>Abbreviation</th>
<th>Description</th>
<th>Data type</th>
<th>Signal number</th>
<th>Operating mode n-set</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>STW1</td>
<td>Control word 1</td>
<td>U16</td>
<td>50001</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>STW1</td>
<td>Control word 1</td>
<td>U16</td>
<td>50001</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>STW2</td>
<td>Control word 2</td>
<td>U16</td>
<td>50003</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>NSET_A</td>
<td>Speed setpoint, most significant word (nset-h)</td>
<td>I16</td>
<td>50005</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>NSET_B</td>
<td>Speed setpoint, most significant and least significant word (nset-h+l)</td>
<td>I32</td>
<td>50007</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>G1_STW</td>
<td>Encoder 1, control word2)</td>
<td>U16</td>
<td>50009</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>G2_STW</td>
<td>Encoder 2, control word3)</td>
<td>U16</td>
<td>50013</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>G3_STW</td>
<td>Encoder 3, control word2)</td>
<td>U16</td>
<td>50017</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>XERR</td>
<td>System deviation (DSC)</td>
<td>I32</td>
<td>50025</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>KPC</td>
<td>Position controller gain factor (DSC)</td>
<td>U32</td>
<td>50026</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>MomRed</td>
<td>Torque reduction</td>
<td>U16</td>
<td>50101</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>DAU1</td>
<td>Analog output, terminal 75.x/15</td>
<td>I16</td>
<td>50103</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>DAU2</td>
<td>Analog output, terminal 16.x/15</td>
<td>I16</td>
<td>50105</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>DIG_OUT</td>
<td>Digital outputs, terminals 00.x to 03.x</td>
<td>U16</td>
<td>50107</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>XSP</td>
<td>Target position for &quot;spindle positioning&quot;</td>
<td>I32</td>
<td>50109</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>DezEing</td>
<td>Distributed inputs</td>
<td>U16</td>
<td>50111</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>MsollExt</td>
<td>External torque setpoint</td>
<td>I16</td>
<td>50113</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>QStw</td>
<td>Control word, slave-to-slave communication</td>
<td>U16</td>
<td>50117</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>SatzAnw</td>
<td>Block selection</td>
<td>U16</td>
<td>50201</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>PosStw</td>
<td>Position control word</td>
<td>U16</td>
<td>50203</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Over</td>
<td>Override</td>
<td>U16</td>
<td>50205</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Xext</td>
<td>External position reference value</td>
<td>I32</td>
<td>50207</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>dXcorExt</td>
<td>Correction, external position reference value</td>
<td>I32</td>
<td>50209</td>
<td>-</td>
<td>x</td>
</tr>
</tbody>
</table>
Table 5-3  Overview of the control words (setpoints), continued

<table>
<thead>
<tr>
<th>Abbreviation</th>
<th>Control word</th>
<th>Description</th>
<th>Data type&lt;sup&gt;4)&lt;/sup&gt;</th>
<th>Signal number&lt;sup&gt;1)&lt;/sup&gt;</th>
<th>Operating mode n-set</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>MDIPos</td>
<td>MDI position</td>
<td>I32</td>
<td>50221</td>
<td>-</td>
<td>x</td>
<td>from SW 7.1</td>
</tr>
<tr>
<td>MDIVel</td>
<td>MDI velocity</td>
<td>U32</td>
<td>50223</td>
<td>-</td>
<td>x</td>
<td>from SW 7.1</td>
</tr>
<tr>
<td>MDIAcc</td>
<td>MDI acceleration override</td>
<td>U16</td>
<td>50225</td>
<td>-</td>
<td>x</td>
<td>from SW 7.1</td>
</tr>
<tr>
<td>MDIDec</td>
<td>MDI deceleration override</td>
<td>U16</td>
<td>50227</td>
<td>-</td>
<td>x</td>
<td>from SW 7.1</td>
</tr>
<tr>
<td>MDIMode</td>
<td>MDI mode</td>
<td>U16</td>
<td>50229</td>
<td>-</td>
<td>x</td>
<td>from SW 7.1</td>
</tr>
</tbody>
</table>

1) From SW 3.1 the following applies:
   The signals are assigned to the process data in the setpoint telegram using P0915:17 (PZD setpoint assignment, PROFIBUS) (refer under the index entry "Process data, configuring").

2) Before SW 3.3, the following applies:
   This process data is only available if clock-synchronous operation is also running.

3) The process data for encoder 2 must be activated via P0879.12.

4) Data type: U16/U 32 --> unsigned integer 16/32 bit; I16/I 32 --> integer 16/32 bit
From the perspective of the DP master, status words are actual values. The "DP slave 611U" indicates an image of the sent process data (status words, actual values) in P1789:17 (sent process data, PROFIBUS).

### Overview of the status words (actual values)

Table 5-4  Overview of the status words (actual values)

<table>
<thead>
<tr>
<th>Abbreviation</th>
<th>Status word</th>
<th>Description</th>
<th>Data type</th>
<th>Signal number</th>
<th>Operating mode</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>ZSW1</td>
<td>Status word 1</td>
<td></td>
<td>U16</td>
<td>50002</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>ZSW1</td>
<td>Status word 1</td>
<td></td>
<td>U16</td>
<td>50002</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>ZSW2</td>
<td>Status word 2</td>
<td></td>
<td>U16</td>
<td>50004</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>NIST_A</td>
<td>Speed actual value, most significant word (nist--h)</td>
<td>I16</td>
<td>50006</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>NIST_B</td>
<td>Speed actual value, most significant and least significant word (nist--(h+l))</td>
<td>I32</td>
<td>50008</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>G1_ZSW</td>
<td>Encoder 1, status word</td>
<td>U16</td>
<td>50010</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G1_XIST1</td>
<td>Encoder 1, pos. actual value</td>
<td>U32</td>
<td>50011</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G1_XIST2</td>
<td>Encoder 1, pos. actual value</td>
<td>U32</td>
<td>50012</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G2_ZSW</td>
<td>Encoder 2, status word</td>
<td>U16</td>
<td>50014</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G2_XIST1</td>
<td>Encoder 2, pos. actual value</td>
<td>U32</td>
<td>50015</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G2_XIST2</td>
<td>Encoder 2, pos. actual value</td>
<td>U32</td>
<td>50016</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G3_ZSW</td>
<td>Encoder 3, status word</td>
<td>U16</td>
<td>50018</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G3_XIST1</td>
<td>Encoder 3, pos. actual value</td>
<td>U32</td>
<td>50019</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>G3_XIST2</td>
<td>Encoder 3, pos. actual value</td>
<td>U32</td>
<td>50020</td>
<td>x</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>MeldW</td>
<td>Message word</td>
<td></td>
<td>U16</td>
<td>50102</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>ADU1</td>
<td>Analog input, terminal 56.x/14</td>
<td>I16</td>
<td>50104</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>ADU2</td>
<td>Analog input, terminal 24.x/20</td>
<td>I16</td>
<td>50106</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>DIG_IN</td>
<td>Digital inputs, terminals I0.x to I3.x</td>
<td>U16</td>
<td>50108</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>Ausl</td>
<td>Utilization</td>
<td></td>
<td>U16</td>
<td>50110</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Pwirk</td>
<td>Active power</td>
<td></td>
<td>U16</td>
<td>50112</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Msoll</td>
<td>Smoothed torque setpoint</td>
<td>I16</td>
<td>50114</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>IgGI</td>
<td>Smoothed, torque-generating current</td>
<td>I16</td>
<td>50116</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>QZsw</td>
<td>Status word, slave-to-slave communications</td>
<td>U16</td>
<td>50118</td>
<td>-</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>UZK1</td>
<td>DC-link voltage</td>
<td></td>
<td>U16</td>
<td>50119</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>AktSatz</td>
<td>Currently selected block</td>
<td>U16</td>
<td>50202</td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>PosZsw</td>
<td>Positioning status word</td>
<td>U16</td>
<td>50204</td>
<td>-</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>XistP</td>
<td>Position actual value (pos. mode)</td>
<td>I32</td>
<td>50206</td>
<td>-</td>
<td>x</td>
<td></td>
</tr>
</tbody>
</table>
Table 5-4 Overview of the status words (actual values), continued

<table>
<thead>
<tr>
<th>Abbreviation</th>
<th>Status word Description</th>
<th>Data type</th>
<th>Signal number</th>
<th>Operating mode n-set</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>XsollP</td>
<td>Position reference value (positioning mode)</td>
<td>I32</td>
<td>50208</td>
<td>x</td>
<td>from SW 4.1</td>
</tr>
<tr>
<td>dXcor</td>
<td>Correction, position reference value</td>
<td>I32</td>
<td>50210</td>
<td>x</td>
<td>from SW 4.1</td>
</tr>
</tbody>
</table>

1) From SW 3.1 the following applies:
The signals are assigned to the process data in the actual value telegram using P0916:17 (PZD actual value assignment, PROFIBUS) (refer under the index entry "Process data, configuring").

2) Before SW 3.3, the following applies:
This process data is only available if clock-synchronous operation is also running.

3) The process data for encoder 2 must be activated via P0879.12.

4) Data type: U16/U32 --> Unsigned integer 16/32 bit; I16/I32 --> integer 16/32 bit

5.6.2 Description of the control words (setpoints)

Control word STW1 (n-set mode)

Table 5-5 Control word STW1 for the n-set mode

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Spindle positioning on (from SW 5.1)
Open-loop torque controlled mode
Accelerating time zero for controller enable (from SW 3.1)
Opening the holding brake for test purposes (from SW 4.1)
Reserved
Control requested/no control requested
Activate function generator immed. (from SW 11.02.06)1
Activate the function generator (edge) (from SW 8.1)

Reset the fault memory
Enable setpoint/inhibit setpoint
Ramp-function generator start/ramp-function generator stop
Ramp-up generator enabled
Enable inverter/pulse inhibit
Operating condition/OFF 3
Operating condition/OFF 2
ON/OFF 1

Note:
1) The signal is only effective for P0878.6 = 1 and, for SW 11.01.03, is connected to bit 11!
- The control signals, from the perspective of "SIMODRIVE 611 universal", are input signals and are described in Chapter 6.4.3.
  Also refer in the index under "Input signal, digital ...".
- The signals designated like this must have at least a 1-signal in order to be able to operate a motor with the speed setpoint NSET_A or NSET_B.
Control word
STW1
(pos mode)

Table 5-6  Control word STW1 for positioning

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<td></td>
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</tr>
</tbody>
</table>

- Request passive referencing (from SW 5.1)\(^1\)
- Reserved
- External block change (from SW 3.1)
- Opening the holding brake for test purposes (from SW 4.1)
- Start referencing/cancel referencing
- Control requested/no control requested
- Jogging 2 ON/jogging 2 OFF
- Jogging 1 ON/jogging 1 OFF

Note:

- The control signals, from the perspective of "SIMODRIVE 611 universal", are input signals and are described in Chapter 6.4.3.
  Also refer in the index under "Input signal, digital ...".
- The signals which have been identified in this way, must have at least a 1 signal in order to be able to start a traversing block using the control signal "activate traversing task (edge)".

1) QStw.1 is OR’d.
## Control word

**STW2**

Table 5-7  Control word STW2

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
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</tr>
</tbody>
</table>

- **Master sign-of-life** (from SW 3.1)
- **Motor changed over** (from SW 2.4)
- **Motor data changeover 1st input** (from SW 2.4)
- **Motor data changeover 1st input** (from SW 2.4)
- **Suppress fault 608** (from SW 3.1)

### Bit Description

- **Bit 15**: Parameters set changeover
- **Bit 14**: Reserved
- **Bit 13**: Ramp-up time zero
- **Bit 12**: First speed setpoint filter off
- **Bit 11**: Selection, parking axis
- **Bit 10**: Integrator inhibit, speed controller
- **Bit 9**: Note:

  The control signals, from the perspective of "SIMODRIVE 611 universal", are input signals and are described in Chapter 6.4.3.

  Also refer in the index under "Input signal, digital ...")

1) Only available in the n-set mode
Control word

NSET_A

NSET_B

(n-set mode)

The speed setpoint can be entered as follows:

via NSET_A (nset-h) ----> lower resolution

via NSET_B (nset-h + nset-l) ----> higher resolution

Table 5-8 Speed setpoint via NSET_A or via NSET_B

<table>
<thead>
<tr>
<th>NSET_B</th>
<th>NSET_A (nset-h)</th>
<th>nset-l</th>
<th>Decimal value for</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 31</td>
<td>24 23 16 15 8</td>
<td>7 3</td>
<td>nset-h + nset-l</td>
<td></td>
</tr>
<tr>
<td>7</td>
<td>F F F F</td>
<td>F F</td>
<td>+32 767</td>
<td>Highest value</td>
</tr>
<tr>
<td>4</td>
<td>0 0 0 0</td>
<td>0 0</td>
<td>+16 384</td>
<td>Positive normalization value (P0880)</td>
</tr>
<tr>
<td>0</td>
<td>0 0 0 0</td>
<td>0 0</td>
<td>0</td>
<td>nset = 0</td>
</tr>
<tr>
<td>C</td>
<td>0 0 0 0</td>
<td>0 0</td>
<td>-16 384</td>
<td>Negative normalization value (P0880)</td>
</tr>
<tr>
<td>8</td>
<td>0 0 0 0</td>
<td>0 0</td>
<td>-32 768</td>
<td>Lowest value</td>
</tr>
</tbody>
</table>

1) The speed setpoint resolution is increased with nset-l.
   The control word nset-l is only transferred for the PPO types PPO2, PPO4 and PPO5.
2) Sign bit: Bit = 0 ----> positive value, bit = 1 ----> negative value
3) The drive does not evaluate these values (low byte from nset-l)
4) The speed is limited by the lowest setting in P1401/P1405/P1146 or P1147.

Speed normalization

P0880 is used to define which speed is obtained for

NSET_A = 4000_Hex or NSET_B = 4000 0000_Hex.

Example:
Assumptions: The speed setpoint is entered via nset-h and P0880 = 16384
---> resolution = 1, i.e. 1 digit = 1 RPM
5.6  Net data (PKW and PZD area)

Control word XERR
(n-set mode)
(from SW 4.1)

The system deviation for the dynamic servo control (DSC) is transferred via this control word.

The format of XERR is identical with the format of G1_XIST1 (refer to Chapter 5.6.4)

Control word KPC
(n-set mode)
(from SW 4.1)

For dynamic servo control (DSC) the position controller gain factor is transferred via this control word.

Transfer format: KPC is transmitted in the units 0.001 1/s

Example:
A2C2AH ≡ 666666D ≡ KPC = 666.666 1/s ≡ KPC = 40 1000/min

Value range: 0 to 4000.0

Special case:
For KPC = 0, the dynamic servo control is de-activated.

Control word MomRed

The torque limit presently valid in the drive can be reduced using this control word.

Normalization of MomRed (P0881)

The normalization of MomRed is defined using P0881 (evaluation, torque reduction PROFIBUS). All 16 bits in the PROFIBUS process data are evaluated and interpreted as positive number. The result of the conversion is a percentage factor k which is applied to P1230 (torque limit) and P1235 (power limit).

\[
k = \text{maximum } (0; 1 - \frac{P0881/100 \%}{16384} \cdot \text{MomRed})
\]

Example:
Assumption: Best possible resolution for the full limiting range
Input: P0881 = 25 %
It then means:

- **Full torque**
  
  \[
  \text{MomRed} = 0000 \\
  \rightarrow k = 1 \text{ (i.e.} 1 \cdot P1230 \text{ and } 1 \cdot P1235 \text{ are effective)}
  \]

- **No torque**
  
  \[
  \text{MomRed} = FFFF \\
  \rightarrow k = 1 - 65535 / 65536 = 0.0000153 \text{ or almost } 0
  \]

with a total of 65536 intermediate steps.

When P0881 is parameterized > 25 %, then it is possible to reduce to precisely 0.

**Control word**

DAU1

DAU2

The 2 analog outputs of a drive can be controlled using these control words.

<table>
<thead>
<tr>
<th>Control word</th>
<th>Terminal/ analog output</th>
<th>Parameter/Signal No.</th>
</tr>
</thead>
<tbody>
<tr>
<td>DAU1 (PROFIBUS)</td>
<td>X441 Terminal 75.x/15</td>
<td>P0626 = 38 (Signal DAU1 from PROFIBUS-PPO)</td>
</tr>
<tr>
<td>DAU2 (PROFIBUS)</td>
<td>X441 Terminal 16.x/15</td>
<td>P0633 = 39 (Signal DAU2 from PROFIBUS-PPO)</td>
</tr>
</tbody>
</table>

**Note:**

- It is only possible to control the analog outputs via PROFIBUS-DP if the appropriate signal number is specified in P0626 or P0633.
- The parameters available to parameterize the analog outputs, are still valid (refer to Chapter 6.7).

**Transfer format:**

\[
4000_{\text{Hex}} \equiv 5 \text{ V, if the shift factor = 0 and the offset = 0} \\
4000_{\text{Hex}} \equiv 10 \text{ V, if the shift factor = 1 and the offset = 0}
\]
The digital outputs at the drive can be controlled, using this control word from the master side via PROFIBUS.

This terminal must be assigned function number 38 so that an output terminal can be controlled.

Control word
DIG_OUT
(from SW 3.1)

For the "Spindle positioning" function, the target position is entered via this control word.

Data transfer format: \[1000 \div 1 \text{ degree}\]

Example: \[\text{XSP} = 145500 \rightarrow 145.5 \text{ degrees}\]
Control signals can be directly read in from another slave (publisher) using this control word without the signals having first to be routed via the master.

The individual bits in the control word must then be assigned functions using P0888, for example, "ramp-function generator enable" or "hardware limit switch".

Table 5-10 Control word DezEing

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
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</tbody>
</table>

Note:
The control signals, from the perspective of "SIMODRIVE 611 universal", are input signals and are described in Chapter 6.4.3. Also refer in the index under "Input signal, digital ...".

For two rigidly connected drives, the actual torque setpoint of the master drive (ZSW Msoll) can be read into the slave drive using this control word.

Normalization of MsollExt (P0882)

Normalization of MsollExt is defined using P0882 (evaluation, torque setpoint PROFIBUS).

The polarity of the torque setpoint can be inverted by entering negative values.

Actual torque setpoint for
- Synchronous motors:
  Torque setpoint [Nm] = \( P1118 \cdot P1113 \cdot \frac{P0882}{4000_{\text{Hex}}} \cdot \text{MsollExt} \)
- Asynchronous motors:
  Torque setpoint [Nm] = \( \frac{60 \cdot P1130 \cdot 1000}{2 \pi \cdot P1400} \cdot \frac{P0882}{4000_{\text{Hex}}} \cdot \text{MsollExt} \)
Note
The slave drive must be changed over into the open-loop torque controlled mode using STW1.14.

Control word
QStw
(pos mode)
(from SW 4.1)

Table 5-11 Control word QStw

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
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</thead>
<tbody>
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</tr>
</tbody>
</table>

Note:
The control signals, from the perspective of "SIMODRIVE 611 universal", are input signals and are described in Chapter 6.4.3.
Also refer in the index under "Input signal, digital ...".

1) STW1.15 is OR'd.
**Control word**

**SatzAnw**

Table 5-12  Control word SatzAnw for positioning

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>27 (from SW 10.1)</td>
<td>26 (from SW 10.1)</td>
<td>25</td>
<td>24</td>
<td>23</td>
<td>22</td>
<td>21</td>
<td>20</td>
<td></td>
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<td></td>
</tr>
</tbody>
</table>

Block selection
(traversing blocks 0 to 63; from SW 10.1: 255 through 0)

**Note:**
The control signals, from the perspective of "SIMODRIVE 611 universal", are input signals and are described in Chapter 6.4.3.
Also refer in the index under "Input signal, digital ...").
Control word
PosStw
(pos mode)

Table 5-13  Control word (PosStw) for positioning

| Bit | 15 | 14 | 13 | 12 | 11 | 10 | 9  | 8  | 7  | 6  | 5  | 4  | 3  | 2  | 1  | 0 |
|-----|----|----|----|----|----|----|----|----|----|----|----|----|----|----|----|
|     |    |    |    |    |    |    |    |    |    |    |    |    |    |    |    |

- Activate function generator (edge) (from SW 9.1)
- Reserved
- Invert the ang. incr. encoder input (from SW 3.5)
- Activate teach-in (edge) (from SW 4.1)
- Incremental jogging (from SW 4.1)
- Activate coupling (from SW 3.3)
- Fixed stop, sensor (from SW 3.3)
- Reference
- Setting the home position
- Follow-up mode

Note:
The control signals, from the perspective of SIMODRIVE 611 universal are input signals and are described in Chapter 6.4.3 (also refer to the index entry under Input signal, digital ...).

Control word
Over
(pos mode)
The percentage value for the velocity override is specified using this control word.

Normalization of the override (P0883)
The override normalization is defined using P0883 (override evaluation PROFIBUS).

\[
\text{Actual override} = \frac{\text{P0883}}{16384} \cdot \text{Over}
\]

Notice
As the drive cannot rotate with Over = 0 %, then it is important for PPO types 2, 4 and 5, that a practical value (greater than 0%) is in this control word.

Negative values are interpreted as maximum value, as this control word is viewed unsigned.
5.6 Net data (PKW and PZD area)

Using this control word, a master drive can control a slave drive with a position reference value. Xext can be connected with the XsollP or XistP quantities from the master drive.

When using a SIMODRIVE 611 universal in the n-set mode as master drive, a connection can be made with the actual value Gx_XIST1 from the encoder interface.

Data transfer format: P0895 and P0896 define the input format

\[
\text{Position in MSR} = \text{input value} \cdot \frac{\text{P0896}}{\text{P0895}}
\]

**Note**

An input evaluation of the setpoints received via the source is only made for a coupling via the angular incremental encoder (P0891 = 0 or 1) and via PROFIBUS-DP (P0891 = 4).

The correction value, by which the position reference value jumps, e.g. when referencing in the master drive (publisher) can also be read-in and taken into account in the slave drive (subscriber) using this control word.

Data transfer format: P0895 and P0896 define the input format

\[
\text{Position in MSR} = \text{input value} \cdot \frac{\text{P0896}}{\text{P0895}}
\]

For MDI blocks, the position is transferred via this control word.

Data transfer format: Units as for parameter P0081:64/256 in MSR

Limits: min: -200000000 MSR
max: 200000000 MSR
For MDI blocks, the speed is transferred via this control word.

**Control word**

**MDIVel**

(pos mode)

(from SW 7.1)

Transfer format: Units as for parameter P0082:64/256 in c*MSR/min

Limits: min: 1000 c*MSR/min

max: 2000000000 c*MSR/min

For MDI blocks, the acceleration override is transferred via this control word.

**Control word**

**MDIAcc**

(pos mode)

(from SW 7.1)

Data transfer format: Units as for parameter P0083:64/256 in %

Limits: min: 1 %

max: 100 %

For MDI blocks, the deceleration override is transferred via this control word.

**Control word**

**MDIDec**

(pos mode)

(from SW 7.1)

Data transfer format: Units as for parameter P0084:64/256 in %

Limits: min: 1 %

max: 100 %

For MDI blocks, the mode is transferred via this control word.

**Control word**

**MDIMode**

(pos mode)

(from SW 7.1)

Data transfer format: Units as for parameter P0087:64/256 in Hex

The following ID is only active for MDI:

- x0x = ABSOLUTE
- x1x = RELATIVE
- x2x = ABS_POS
- x3x = ABS_NEG
- 0xx = END
- 3xx = CONTINUE EXTERNAL
### 5.6.3 Description of the status words (actual values)

**Status word ZSW1**  
(n-set mode)

#### Table 5-14 Status word ZSW1 for the n-set mode

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
<td>Spindle positioning on (from SW 5.1)</td>
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<tr>
<td>Open-loop torque controlled mode</td>
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<tr>
<td>Function generator active (from SW 6.1)</td>
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<tr>
<td>Reserved</td>
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<tr>
<td>Reserved</td>
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<td>Comparison value reached/comparison value not reached</td>
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<tr>
<td>Control requested/no control possible</td>
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<tr>
<td>$n_{\text{set}} = n_{\text{act}}$</td>
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<tr>
<td>Warning present/no warning present</td>
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<tr>
<td>Power-on inhibit/no power-on inhibit</td>
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<tr>
<td>No OFF 3 present/OFF 3 present</td>
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<tr>
<td>No OFF 2 present/OFF 2 present</td>
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<tr>
<td>Fault present/no fault present</td>
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<tr>
<td>Status, controller enable</td>
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<tr>
<td>Ready or no fault</td>
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<tr>
<td>Ready to be powered-up/not ready to be powered-up</td>
<td></td>
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</tr>
</tbody>
</table>

**Note:**  
From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6.  
Also refer in the index under "Output signal, digital ...".)
### Status word ZSW1 (pos mode)

Table 5-15   Status word ZSW1 for positioning

<table>
<thead>
<tr>
<th>Bit</th>
<th>0</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>6</th>
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<th>12</th>
<th>13</th>
<th>14</th>
<th>15</th>
</tr>
</thead>
<tbody>
<tr>
<td>ZSW 1</td>
<td>Pos Anw</td>
<td>Pos Zsw</td>
<td>ZSW 2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<td></td>
</tr>
</tbody>
</table>

- **Request passive referencing (from SW 5.1)**
- **Torque-controlled operation (from SW 3.3)**
- **Drive stationary/drive moving**
- **Setpoint acknowledge (edge)**
  - Reference point set/no reference point set
  - Reference position reached/outside reference position
  - Control requested/no control possible
  - No following error/following error
- **Warning present/no warning present**
- **Power-on inhibit/no power-on inhibit**
  - No OFF 3 present/OFF 3 present
  - No OFF 2 present/OFF 2 present
  - Fault present/no fault present
  - Status, controller enable
  - Ready or no fault
  - Ready to be powered-up/not ready to be powered-up

**Note:**
From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6.

Also refer in the index under "Output signal, digital ...".)
### Status word ZSW2

#### Table 5-16 Status word ZSW2

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
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</tr>
</tbody>
</table>

- **Suppress fault 608 active (from SW 3.1)**
- **Motor being changed over (from SW 3.3)**
- **Actual motor 1st signal (from SW 2.4)**
- **Actual motor 1st signal (from SW 2.4)**
- **Slave sign-of-life (from SW 3.1)**
- **Parking axis selected**
- **Integrator inhibit, speed controller**
- **Open holding brake**
- **Ramp-function gen. inactive**
- **First speed setpoint filter inactive**
- **Parameter set**

#### Bit 2 Bit 1 Bit 0

**Note:**
From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6.
Also refer in the index under "Output signal, digital ...".

1) Only available in the n-set mode

### Status word

#### NIST_A

#### NIST_B

For closed-loop speed controlled operation, the speed actual value is displayed as follows:

- **ZSW 1**
- **NIST_B**
- **ZSW 2**
- **NIST_A**

- **nist-h**
- **nist-l**

**Note**

The speed actual value is signaled in the same format as the speed setpoint is specified (refer to control word NSET_A (nset-h) and NSET_B (nset-(h+l))).

The speed actual value to be transferred via PROFIBUS-DP can be smoothed using a PT1 filter (from SW 13.1). The smoothing time constant of the PT1 filter is set using P0887 (P0887 = 0 smoothing is not active).
### Status word MeldW

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
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<td></td>
<td></td>
</tr>
</tbody>
</table>

- Spindle position reached (spindle position 2, from SW 5.1)
- Position reached (spindle position 1, from SW 5.1)
- Pulses enabled (from SW 3.1)
- Reserved
- Reserved
- Power module current not limited (from SW 3.1)
- Reserved
- $n_{\text{set}} = n_{\text{act}}$
- Heatsink temperature pre-warning
- Motor overtemperature pre-warning
- Variable signaling function
- DC link monitoring $V_{\text{DC link}} > V_x$
  - $|n_{\text{acq}}| < n_x$
  - $|n_{\text{act}}| < n_{\text{min}}$
  - $|M| < M_x$
- Run-up process completed (n-set)
- Programmed velocity reached (pos, from SW 11.1)

**Note:**
From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6.
Also refer in the index under "Output signal, digital ...".

### Status word ADU1 ADU2

The actually converted values of the 2 analog inputs of a drive are displayed using these status words.

- **Status word ADU1**
  - Analog input
  - ADU1: X451 terminal 56.x/14.x
  - ADU2: X451 terminal 24.x/20.x

**Note**
The parameters available to parameterize the analog inputs are still valid (refer to Chapter 6.6).

- Data transfer format: $4000_{\text{hex}} = 10\ \text{V}$
- Update rate at which this signal is provided:
  - Isochronous PROFIBUS-DP
    - --> generally: DP clock cycle, sensed at instant in time $T_i$
  - non-clock-cycle synchronous PROFIBUS-DP
    - --> n-set mode: Position controller clock cycle (P1009)
    - --> pos mode: Interpolation clock cycle (P1010)
Status word
DIG_IN
(from SW 3.1)

The digital inputs at the drive can be read via the PROFIBUS and evaluated on the master side using this status word.

![Diagram of DIG_IN status word](image)

**Fig. 5-12 Status word DIG_IN (from SW 3.1)**

Status word
Ausl

This status word is used to display the ratio between the actual torque and torque limit or between the actual power and the power limit.

![Diagram of Ausl status word](image)

**Note**

The utilization value is smoothed using P1251 (time constant (smoothing) motor utilization).

Data transfer format: $7FF_{\text{hex}} \approx 100\%$

Update rate at which this signal is provided:

- **Isochronous PROFIBUS-DP**
  - $n$-set mode: Position controller clock cycle ($T_{\text{MAPC}}$) of the master
  - pos mode: Position controller clock cycle (P1009)
- **Non-clock-cycle synchronous PROFIBUS-DP**
  - $n$-set mode: Position controller clock cycle (P1009)
  - pos mode: Interpolation clock cycle (P1010)
Status word Pwirk

The actual drive active power is displayed using this status word.

The active power is calculated from the speed actual value and the actual torque setpoint. Contrary to the torque and power limits, in this case, the current limiting is not taken into account.

Data transfer format: 100 = 1 kW

Update rate at which this signal is provided:
- Isochronous PROFIBUS–DP
  --> n-set mode: Position controller clock cycle ($T_{MAPC}$) of the master
  --> pos mode: Position controller clock cycle (P1009)
- non-clock-cycle synchronous PROFIBUS–DP
  --> n-set mode: Position controller clock cycle (P1009)
  --> pos mode: Interpolation clock cycle (P1010)

Status word Msoll

The drive torque is displayed using this status word.

Normalization of Msoll (P0882)

The normalization of Msoll is defined (from SW 4.1) using P0882 (evaluation, torque setpoint PROFIBUS).

Actual torque setpoint for
- Synchronous motors:
  Torque setpoint [Nm] = $P_{1118} \cdot P_{1113} \cdot \frac{P0882}{4000_{\text{Hex}}} \cdot Msoll$
- Asynchronous motors:
  Torque setpoint [Nm] = $\frac{60 \cdot P_{1130} \cdot 1000 \cdot P0882}{2\pi \cdot P1400} \cdot 4000_{\text{Hex}} \cdot Msoll$

Note

The reference torque is displayed in P1725 (normalization, torque setpoint).

The torque value is smoothed via P1252 (transition frequency, torque setpoint smoothing).

Transfer format: $4000_{\text{Hex}} = 16384 = \text{reference torque (in P1725)}$

Update rate at which this signal is provided:
- Isochronous PROFIBUS–DP
  --> generally: DP clock cycle, sensed at instant in time $T_i$
- non-clock-cycle synchronous PROFIBUS–DP
  --> n-set mode: Position controller clock cycle (P1009)
  --> pos mode: Interpolation clock cycle (P1010)
Status word IqGl (from SW 3.1)

The actual smoothed torque-generating current Iq of the drive is displayed using this status word.

The smoothing can be set using P1250 (transition frequency, current actual value smoothing).

Transfer format: \(4000_{\text{Hex}} = 16384 \Rightarrow P1107 \) (transistor limit current)

Update rate at which this signal is provided:
- Isochronous PROFIBUS-DP
  \(\rightarrow\) generally: DP clock cycle, sensed at instant in time \(T_i\)
- non-clock-cycle synchronous PROFIBUS-DP
  \(\rightarrow\) n-set mode: Position controller clock cycle (P1009)
  \(\rightarrow\) pos mode: Interpolation clock cycle (P1010)

Status word QZsw (pos mode) (from SW 4.1)

Table 5-18 Status word QZsw

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
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<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
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</thead>
<tbody>
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</tr>
</tbody>
</table>

Reserved

Request passive referencing (from SW 5.1)
Correction, external reference value via dXcor (from SW 4.1)

Note:
From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6.
Also refer in the index under "Output signal, digital ...".)
**Status word**

**AktSatz**

Table 5-19  Status word AktSatz

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
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<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>ZSW 1</td>
<td>Akt Satz</td>
<td>Pos Zsw</td>
<td>ZSW 2</td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
</tbody>
</table>

- MDI active (from SW 7.1)
- External block change (from SW 7.1)
- Angular incremental encoder handwheel active (from SW 8.1)
- Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1)
- Angular incr. encoder handwheel evaluation, bit 0 (from SW 8.1)
- Block processing inactive (from SW 8.1)
- Reserved
- Reserved

**Status, block selection**

(traversing blocks 0 to 63; from SW 10.1: 255 through 0)

- \(2^7\) (from SW 10.1)
- \(2^6\) (from SW 10.1)
- \(2^5\)
- \(2^4\)
- \(2^3\)
- \(2^2\)
- \(2^1\)
- \(2^0\)

**Note:**

As long as the block is not active, a -1 is displayed. The actual block number is displayed with the input signal "activate traversing task".

From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6.

Also refer in the index under "Output signal, digital ...".

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SIMODRIVE 611 universal Function Manual (FBU) - 05/2010 Edition
5.6 Net data (PKW and PZD area)

Status word
PosZsw
(pos mode)

Table 5-20 Status word PosZsw for positioning

<table>
<thead>
<tr>
<th>Bit</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
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<td>Pos</td>
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<td></td>
<td></td>
</tr>
<tr>
<td>Satz</td>
<td></td>
<td></td>
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<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Akt</td>
<td></td>
<td></td>
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<td></td>
<td></td>
</tr>
<tr>
<td>ZSW</td>
<td>1</td>
<td></td>
<td></td>
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<td></td>
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<td></td>
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<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

- Teach-in executed (from SW 4.1)
- Travel to fixed stop active (from SW 3.3)
- Fixed stop clamping torque reached (from SW 3.3)
- Fixed stop reached (from SW 3.3)
- Direct output 2 via the traversing block
- Direct output 1 via the traversing block
- Cam switching signal 2
- Cam switching signal 1

Note:
From the perspective of SIMODRIVE 611 universal, status signals are output signals and are described in Chapter 6.4.6. Also refer in the index under "Output signal, digital ...").

Status word
UZK1
(from SW 8.3)

The actual DC link voltage in the drive is displayed using this status word.

Data transfer format: hexadecimal, non-normalized
e.g.: 258\text{hex} = 600\text{dec} = 600 V

Reading the status word UZK1 must be configured in the standard telegram (P0922 = 0; refer to Chapter 5.6.5).
Status word \textit{XistP} (pos mode) (from SW 3.1)

Position actual value (positioning)

- P1792 = 1 \(\rightarrow\) \text{XistP} is received from the motor meas. system
- P1792 = 2 \(\rightarrow\) \text{XistP} is received from the direct measuring system

Table 5-21 Status word \textit{XistP} (from SW 3.1)

<table>
<thead>
<tr>
<th>Bit \textit{31})</th>
<th>24</th>
<th>23</th>
<th>16</th>
<th>15</th>
<th>8</th>
<th>7</th>
<th>0</th>
<th>Decimal values</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>7</td>
<td>F</td>
<td>F</td>
<td>F</td>
<td>F</td>
<td>F</td>
<td>F</td>
<td>F</td>
<td>2 147 483 647</td>
<td>Highest value</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>XistP = 0 (^2)</td>
</tr>
<tr>
<td>8</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>-2 147 483 648</td>
<td>Lowest value</td>
</tr>
</tbody>
</table>

1) Sign bit: \(\text{Bit} = 0 \rightarrow\) positive value, \(\text{bit} = 1 \rightarrow\) negative value
2) Resolution: 1 digit = 1 measuring system grid (MSR)

Transfer format: \(\text{P0884 and P0896 define the position output format}\)

The following applies: \(\text{Output value} = \text{position in MSR} \cdot \frac{\text{P0884}}{\text{P0896}}\)

Status word \textit{XsollP} (pos mode) (from SW 4.1)

The actual position reference value at the output of the interpolator or at the input of the fine interpolator is displayed in the drive using this status word.

Transfer format: \(\text{P0884 and P0896 define the position output format}\)

The following applies: \(\text{Output value} = \text{position in MSR} \cdot \frac{\text{P0884}}{\text{P0896}}\)

Status word \textit{dXcor} (pos mode) (from SW 4.1)

The correction value by which the position reference value jumps, e.g. when referencing in the master drive (publisher) is displayed in the drive using this status word.

Transfer format: \(\text{P0884 and P0896 define the position output format}\)

The following applies: \(\text{Output value} = \text{position in MSR} \cdot \frac{\text{P0884}}{\text{P0896}}\)
5.6.4 Encoder interface (n-set mode, from SW 3.1)

The encoder interface comprises the following process data:

- **G1_STW**
- **G2_STW**
- **G3_STW**
- **G1_ZSW**
- **G1_XIST1**
- **G1_XIST2**
- **G2_ZSW**
- **G2_XIST1**
- **G2_XIST2**
- **G3_ZSW**
- **G3_XIST1**
- **G3_XIST2**

**Note:**
- **G1_...** Enc. 1  ---> Motor encoder  Drives A, B: X411, X412
- **G2_...** Enc. 2  ---> Direct meas. system  Only drive A: X412 (from SW 3.3)
- **G3_...** Enc. 3  ---> Addit. meas. system  X472 (only for "SIMODRIVE 611 universal E")
  If P0890 = 4 a TTL signal can be entered via the angular incremental encoder interface.

**Note**
- The process data of the encoder interface can be included in the telegram when configuring the process data.
  --> Refer to Chapter 5.6.5
- **Encoder 1:** Standard telegram 3 or 102 (refer to P0922)
- **Encoder 2:** Standard telegram 4 or 103 (refer to P0922)
- **Enc. 1 and 3:** Standard telegram 104 (refer to P0922)

- The process data for encoder 2 must be activated via P0879.12.
- The description of this process data can be taken from the following literature:
  **Reference:** /PPA/, PROFIdrive Profile Drive Technology
- **Encoder 3 for "SIMODRIVE 611 universal":**
  For P0890 = 4, a TTL signal can be entered via the incremental angular encoder interface (refer to Chapter 6.8) and re-output via PROFIBUS–DP (encoder 3, e.g. standard telegram 104).
### Encoder x control word

**x:** Space retainer for encoder 1, 2 or 3

---

#### Table 5-22 Description of the individual signals in the encoder control word (Gx_STW)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Name</th>
<th>Signal status, description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td></td>
<td>If bit 7 = 0, then find reference mark request applies:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Bit Meaning</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0 Function 1 Reference mark 1</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1 Function 2 Reference mark 2</td>
</tr>
<tr>
<td></td>
<td></td>
<td>2 Function 3 Reference mark 3</td>
</tr>
<tr>
<td></td>
<td></td>
<td>3 Function 4 Reference mark 4</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>If bit 7 = 1, then flying measurement request applies:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Bit Meaning</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0 Function 1 Measuring probe, positive edge</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1 Function 2 Measuring probe, negative edge</td>
</tr>
</tbody>
</table>

**Note:**
- Bit x = 1 Request function
- Bit x = 0 Do not request function
- The following applies if more than 1 function is activated:
  - The values for all functions cannot be read until each activated function has been terminated and this has been confirmed in the corresponding status bit (ZSW.0/.1/.2/.3 "0" signal again).
  - Find reference mark
  - Up to 4 reference marks can be found. Reference marks can also be skipped (e.g. find reference marks 1 and 3).
  - Equivalent zero mark
    - Input terminal I0.x with function number 79 (refer to Chapter 6.4.2)
    - P0879.13/.14 (refer to Chapter A.1)
  - Measurement on-the-fly
    - The positive and negative edge can be activated simultaneously.
    - The measuring probe signal is recognized depending on the direction.
    - The values are read out in succession.
    - Input terminal I0.x with function number 80 (refer to Chapter 6.4.2)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td>0</td>
</tr>
<tr>
<td>5</td>
<td>010</td>
</tr>
<tr>
<td>6</td>
<td>011</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Mode</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>7</td>
<td>1 Measurement on-the-fly</td>
</tr>
<tr>
<td>0</td>
<td>0 Find reference mark (zero mark or BERO)</td>
</tr>
</tbody>
</table>
### Table 5-22  Description of the individual signals in the encoder control word (Gx_STW), continued

<table>
<thead>
<tr>
<th>Bit</th>
<th>Name</th>
<th>Signal status, description</th>
</tr>
</thead>
<tbody>
<tr>
<td>8</td>
<td>-</td>
<td>Reserved</td>
</tr>
<tr>
<td></td>
<td>...</td>
<td></td>
</tr>
<tr>
<td>12</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
| 13  | Request cyclic absolute value | 1 Request to cyclically transfer the absolute track of the absolute value encoder (EnDat encoder) via Gx_XIST2 
    |                                          | Used for (e.g.):  
    |                                          | - Additional measuring system monitoring  
    |                                          | - Synchronization during ramp-up          |
|     | 0                        | No request                                                                                 |
| 14  | Activate parking encoder | 1 Request to disable the measuring system monitoring and the actual value sensing         |
|     | 0                        | No request                                                                                 |
|     | 0/1                      | Request to reset encoder faults                                                            |
| 15  | Acknowledge encoder error | 1) Signal must be reset by user                                                            |
|     |                          |                                                                                           |
|     | 0                        | No request                                                                                 |
Example 1: Find reference mark

Assumptions for the example:
- Distance-coded reference mark
- Two reference marks (function 1/function 2)
- Closed-loop position control with encoder 1

Fig. 5-14 Flowchart for “find reference mark”
Example 2: Flying measurement

Assumptions for the example:

- Measuring probe with a positive edge (function 1)
- Closed-loop position control with encoder 1

**Assumptions**

- **Mode**
  - G1_STW.7 = 1

- **Function 1**
  - G1_STW.0 = 1

- **Command**
  - G1_STW.4 = 1 (activate function)
  - G1_STW.5 = 1 (read value)

- **Function active**
  - G1_ZSW.0 = 1

- **Value available**
  - G1_ZSW.4 = 1

- **Measuring probe deflected**
  - G1_ZSW.8

- **Measuring probe edge**
  - Actual value transfer

1) Signal must be reset by user

**Fig. 5-15** Flowchart for "flying measurement"
**Gx_ZSW**

Encoder x status word

x: Space retainer for encoder 1, 2 or 3

--> to display statuses, acknowledgments, faults/errors etc.

### Table 5-23 Description of the individual signals in the encoder status word (Gx_ZSW)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Name</th>
<th>Signal status, description</th>
</tr>
</thead>
</table>
| 0   | Valid for find reference mark and flying measurement | Bit Meaning
|     | 0  | Function 1 Reference mark 1 Measuring probe, positive edge |
|     | 1  | Function 2 Reference mark 2 Measuring probe, negative edge |
| 1   | 2  | Function 3 Reference mark 3 |
|     | 3  | Function 4 Reference mark 4 |
|     | Status: Function 1 - 4 active Note:
|     | Bit x = 1 Function active |
|     | Bit x = 0 Function inactive |
| 2   | Find reference mark or Measurement on-the-fly Value 1 - 4 available Note:
|     | Bit x = 1 Value available |
|     | Bit x = 0 Value not available |
|     | Only one value can be fetched at a time. Reason: Only one shared status word Gx_XIST2 is available for reading the values. |
| 3   | Measuring probe deflected 1 Measuring probe deflected |
|     | 0 Measuring probe is not deflected |
| 4   | Status: Value 1 - 4 available |
| 5   | Value 1 Reference mark 1 Measuring probe, positive edge |
|     | Value 2 Reference mark 2 Measuring probe, negative edge |
| 6   | Value 3 Reference mark 3 |
| 7   | Value 4 Reference mark 4 |
| 8   | Measuring probe deflected |
| 9   | Reserved |
| 10  | - |
| 11  | Encoder fault acknowledgement active 1 Encoder fault acknowledge active Note:
|     | Refer under STW.15 (acknowledge encoder error) |
|     | 0 No acknowledgement active |
| 12  | - | Reserved |
### Table 5-23 Description of the individual signals in the encoder status word (Gx_ZSW), continued

<table>
<thead>
<tr>
<th>Bit</th>
<th>Name</th>
<th>Signal status, description</th>
</tr>
</thead>
<tbody>
<tr>
<td>13</td>
<td>Transmit cyclic absolute value</td>
<td>1 Acknowledgement for Gx_STW.13 (request cyclic absolute value)</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>Cyclic transmission of the absolute value can be interrupted by a function with higher priority.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The bit remains set although no absolute value is transmitted via Gx_XIST2.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>--&gt; refer to Fig. 5-17</td>
</tr>
<tr>
<td></td>
<td></td>
<td>--&gt; refer to Gx_XIST2</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0 No acknowledgement</td>
</tr>
<tr>
<td>14</td>
<td>Parking encoder active</td>
<td>1 Acknowledgment for Gx_STW.14 (activate parking encoder)</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0 No acknowledgement</td>
</tr>
<tr>
<td>15</td>
<td>Encoder error</td>
<td>1 Encoder or actual value sensing fault present</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>The error code is stored in Gx_XIST2. If several errors occur, then only the first error is displayed.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0 No fault present</td>
</tr>
</tbody>
</table>
**Gx_XIST1**

Encoder x position actual value 1 --> position actual value

- Resolution: Encoder pulses * 2^n
  
  n: Fine resolution
  
  Number of bits for the internal multiplication

  The fine resolution is defined via P1042/P1044.

  P1042 Encoder 1, fine resolution G1_XIST1
  
  P1044 Encoder 2 fine resolution G2_XIST1

---

**Fig. 5-16 Partitioning and settings for Gx_XIST1**

- Encoder pulses
  - The following applies for encoders with sin/cos 1Vpp:
    
    Encoder pulses = No. of sinusoidal signal periods
  
  - The following applies for resolvers with 12-bit resolution:
    
    Encoder pulses = 1024 * No. of pole pairs of resolver
  
  - The following applies for resolvers with 14-bit resolution:
    
    Encoder pulses = 4096 * No. of pole pairs of resolver

- After power-up: Gx_XIST1 = 0

- An overflow Gx_XIST1 must be viewed from the higher-level control

- In the drive there is no modulo view of Gx_XIST1
Gx_XIST2

Encoder x position actual value 2 --> Additional position actual value

Different values are entered in Gx_XIST2 depending on the function (refer to Fig. 5-17).

- Priorities for Gx_XIST2

The following priorities should be considered for values in Gx_XIST2:

![Flowchart showing priorities for Gx_XIST2](image)

- Resolution: Encoder pulses • $2^n$
  
  n: Fine resolution
  Number of bits for the internal multiplication

The fine resolution is defined via P1043/P1045 or P1042/P1044 for the "requested value" or the "absolute value" in Gx_XIST2.

- P1043 Encoder 1, fine resolution, absolute track G1_XIST2
- P1045 Encoder 2, fine resolution, absolute track G2_XIST2
- P1042 Encoder 1, fine resolution G1_XIST1
- P1044 Encoder 2 fine resolution G2_XIST1
5.6 Net data (PKW and PZD area)

![Diagram of Encoder Pulses and Fine Information]

- Encoder pulses
  - The following applies for encoders with sin/cos 1Vpp:
    
    \[ \text{Encoder pulses} = \text{No. of sinusoidal signal periods} \]
  - The following applies for resolvers with 12-bit resolution:
    
    \[ \text{Encoder pulses} = 1024 \times \text{No. of pole pairs of resolver} \]
  - The following applies for resolvers with 14-bit resolution:
    
    \[ \text{Encoder pulses} = 4096 \times \text{No. of pole pairs of resolver} \]
### Error code

Table 5-24  Fault code in Gx_XIST2

<table>
<thead>
<tr>
<th>Gx_XIST2</th>
<th>Description</th>
<th>Possible causes/description</th>
</tr>
</thead>
</table>
| 1<sub>Hex</sub> | Encoder sum error | The fault description should be taken from the following faults (refer to Chapter 7.3.2):
- Fault 514 Motor measuring system (encoder 1)
- Fault 609 Encoder limiting frequency exceeded
- Fault 512 Direct measuring system (encoder 2)
- Fault 615 DM encoder limiting frequency exceeded |
| 2<sub>Hex</sub> | Zero mark monitoring | The fault description should be taken from the following faults (refer to Chapter 7.3.2):
- Fault 508 Motor measuring system (encoder 1)
- Fault 514 Direct measuring system (encoder 2) |
| 3<sub>Hex</sub> | Abort parking encoder | The "parking axis" was already selected.
From PROFIdrive profile version 4.1, the fault “Abort parking encoder” is also initiated if the motor measuring system may not be parked as the motor is still turning. |
| 4<sub>Hex</sub> | Abort find reference marker | A fault is present (Gx_ZSW.15 = 1)
- Parking encoder/axis active
- "Flying measurement" function already active
- Change of function type
- No reference mark programmed
- Hardware already busy with another function
- Only BERO: BERO not at terminal I0.x
- Not BERO: EnDat encoder used
- Invalid combination of reference marks for distance-coded encoder (1-2, 3-4, 1-2-3-4 are supported) |
| 5<sub>Hex</sub> | Retrieve reference value interrupted | A fault is present (Gx_ZSW.15 = 1)
- Parking encoder/axis active
- No reference mark programmed
- Requested value not available
- Change of function type |
| 6<sub>Hex</sub> | Abort flying measurement | A fault is present (Gx_ZSW.15 = 1)
- Parking encoder/axis active
- Change of function type
- Reference point approach still active
- Measuring probe not at terminal I0.x and measuring probe 1 not used
- Hardware already busy with another function
- Spindle positioning active (P0125=1, from SW 5.1) |
| 7<sub>Hex</sub> | Abort, retrieve measured value | A fault is present (Gx_ZSW.15 = 1)
- Parking encoder/axis active
- Change of function type
- Requested value not available
- Not exactly 1 value to be retrieved |
| 8<sub>Hex</sub> | Abort absolute value transmission on | EnDat encoder not used |
### Table 5-24 Fault code in Gx_XIST2, continued

<table>
<thead>
<tr>
<th>Gx_XIST2</th>
<th>Description</th>
<th>Possible causes/description</th>
</tr>
</thead>
</table>
| AHex             | Fault when reading the absolute track of the absolute value encoder (EnDat encoder) | For further diagnostics:  
  - - - - refer to P1023 IM diagnostics  
  - - - - refer to P1033 DM diagnostics |
| F01Hex (from SW 8.2) | Command is not supported | Encoder x control word Gx_STW.6 = 1 |

### Limitations and rules when connecting-up encoder 2 (direct measuring system)

The following limitations and rules apply:

1. Which combinations of power module and control board are possible?
   - 1-axis power module with 2-axis control board  
     In this case, drive B is not available.
   - 2-axis power module with 2-axis control board  
     Drive B is available.
     The following applies: Switch drive B into a passive state (P0700 (B) = 0)

2. Which encoder systems are available for encoder 2?
   Dependent on the 2-axis board with encoder for sin/cos 1 Vpp or for resolver, the following rotary or linear measuring systems can be connected at X412:
   - Incremental encoder with sin/cos 1 Vpp  
   - Absolute value encoder with EnDat protocol  
   - Resolver

3. Process data for encoder 2
   - Control word: G2_STW  
   - Status words: G2_ZSW, G2_XIST1 and G2_XIST2

4. Encoder 2 is activated with P0879.12 (A) = 1.
   The following applies:
   - This activation becomes effective after POWER ON  
   - Encoder 2 must be commissioned  
     - - - - refer to the Start-up Assistant of SimoCom U  
   - It is not permissible to operate drive A without a motor measuring system.
     - - - - The following must be valid: P1027.5 (A) = 0  
   - Input terminal I0.B (fast input from drive B) can be assigned a function for encoder 2 from drive A via P0672.
     e.g. the "equivalent zero mark" or "flying measurement" function
5.6.5 Configuring process data (from SW 3.1)

**Description**

The process data structure of the telegram can be defined and configured as follows:

1. By selecting a standard telegram (P0922 > 0)

   Examples:
   - P0922 = 1 standard telegram for nset interface 16 bit
   - P0922 = 101 telegram is as for SW 2.4
     (dependent on the operating mode)

2. By freely-configuring the telegram (P0922 = 0)

   Example:
   - P0922 = 0 **Before SW 4.1:**
     PZD1 to PZD4 are defined as standard
     PZD5 to PZD16 can be freely configured
   
   **From SW 4.1:**
   PZD1 remains defined as standard
   PZD2 to PZD16 can be freely configured

   **Setpoint direction**
   (refer to the parameter overview for P0915:17)
   e.g.:
   P0915:5 = xxxx (required signal ID)
   P0915:6 = yyyy ...
   or
   
   **Actual value direction**
   (refer to the parameter overview for P0916:17)
   e.g.:
   P0916:5 = uuuu (requested signal ID)
   P0916:6 = vvvv ...

---

**Note**

Standard signals, defined in the PROFIdrive Profile as well as special signals only defined for the "DP slave 611U" can be configured as setpoints/actual values.

For double-word signals (32 bits) the appropriate signal ID must be configured twice on adjacent process data.

Example:

P0916:7 = 50011 --- G1_XIST1 is assigned to PZD7
P0916:8 = 50011 --- G1_XIST1 is assigned to PZD8
--- as G1_XIST1 is a double word (32 bits), it must be assigned two PZDs.
Parameter overview

The following parameters are available for the process data configuring:

Table 5-25 Parameters for configuring the process data

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0915:17</td>
<td>PZD setpoint assignment PROFIBUS</td>
<td>0</td>
<td>0</td>
<td>65535</td>
<td></td>
<td>immediately</td>
</tr>
</tbody>
</table>

... is used to assign the signals to the process data in the setpoint telegram.
Permissible signals for the setpoint direction (control words) are:

<table>
<thead>
<tr>
<th>ID</th>
<th>Significance</th>
<th>Abbrev.</th>
<th>Length</th>
<th>Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>No signal</td>
<td>NIL</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50001</td>
<td>Control word 1</td>
<td>STW1</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50003</td>
<td>Control word 2</td>
<td>STW2</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50005</td>
<td>Speed setpoint A (nset-h)</td>
<td>NSET_A</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50007</td>
<td>Speed setpoint B (n-set (h + l))</td>
<td>NSET_B</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50009</td>
<td>Encoder 1 control word</td>
<td>G1_STW</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50013</td>
<td>Encoder 2 control word (from SW 3.3)</td>
<td>G2_STW</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50017</td>
<td>Encoder 3 control word</td>
<td>G3_STW</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50025</td>
<td>System deviation (DSC) (from SW 4.1)</td>
<td>XERR</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50026</td>
<td>Pos. contr. gain factor (DSC) (from SW 4.1)</td>
<td>KPC</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50101</td>
<td>Torque reduction</td>
<td>MomRed</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50103</td>
<td>Analog output, terminals 75.x/15</td>
<td>DAU1</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50105</td>
<td>Analog output, terminals 16.x/15</td>
<td>DAU2</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50107</td>
<td>Digital outputs, terminals 00.x to 03.x</td>
<td>DIG_OUT</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50109</td>
<td>Target pos. for “Spindle positioning” (from SW 5.1)</td>
<td>XSP</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50111</td>
<td>Distributed inputs</td>
<td>DezEng</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50113</td>
<td>Torque setpoint external (read-in, subscriber) (from SW 4.1)</td>
<td>MsollExt</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50117</td>
<td>Ctrl word slave-to-slave traffic (from SW 4.1)</td>
<td>QStw</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50201</td>
<td>Block selection</td>
<td>SatzAnw</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50203</td>
<td>Position control word</td>
<td>PosStw</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50205</td>
<td>Override</td>
<td>Over</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50207</td>
<td>Ext. position reference value (from SW 4.1)</td>
<td>Xext</td>
<td>32 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50209</td>
<td>Correction, ext. pos. ref. val. (from SW 4.1)</td>
<td>XcorExt</td>
<td>32 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50221</td>
<td>MDI position (from SW 7.1)</td>
<td>MDIPos</td>
<td>32 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50223</td>
<td>MDI velocity (from SW 7.1)</td>
<td>MDIVel</td>
<td>32 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50225</td>
<td>MDI acceleration override (from SW 7.1)</td>
<td>MDIAcc</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50227</td>
<td>MDI deceleration override (from SW 7.1)</td>
<td>MDIDec</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50229</td>
<td>MDI mode (from SW 7.1)</td>
<td>MDIMode</td>
<td>16 bit</td>
<td>pos</td>
</tr>
</tbody>
</table>
Table 5-25  Parameters for configuring the process data, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Note:

- For P0922 > 0, the following is valid:
  - P0915:17 is pre-assigned when booting corresponding to the selected standard telegram in P0922.
  - A change made to P0915:2 to P0915:16 is overwritten again when the system re-boots corresponding to the selected standard telegram.
- Operating mode not specified --> possible in every operating mode
- The following applies for P0922 = 0:
  - **Before SW 4.1** --> From P0915:5 (assignment for PZD5), process data can be freely configured. This means from P0915:5, the signal ID of the requested signal can be entered.
  - **From SW 4.1** --> From P0915:2 (assignment for PZD2), process data can be freely configured, i.e. from P0915:2, the signal ID of the required signal can be entered.

- P0915:0  No significance
- P0915:1  PZD1  Configuring not possible (standard setting)
- P0915:2  PZD2  Free configuring possible (from SW 4.1, before SW 4.1 from PZD5), i.e. enter the required signal ID
  ...
- P0915:16 PZD16  Free configuring possible, i.e. enter the required signal ID

- An overview of the control words is available in Chapter 5.6.1.
- The process data for encoder 2 must be activated via P0879.12.
<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0916:17</td>
<td>PZD actual value assignment, PROFIBUS</td>
<td>0</td>
<td>0</td>
<td>65535</td>
<td></td>
<td>immediately</td>
</tr>
</tbody>
</table>

... is used to assign the signals to the process data in the actual value telegram.

Permissible signals for the actual value direction (status words) are:

<table>
<thead>
<tr>
<th>ID</th>
<th>Significance</th>
<th>Abbrev.</th>
<th>Length</th>
<th>Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>50000</td>
<td>No signal</td>
<td>NIL</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50002</td>
<td>Status word 1</td>
<td>ZSW1</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50004</td>
<td>Status word 2</td>
<td>ZSW2</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50006</td>
<td>Speed actual value A (nist-h)</td>
<td>NIST_A</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50008</td>
<td>Speed actual value B (n-ist (h + l))</td>
<td>NIST_B</td>
<td>32 bit</td>
<td></td>
</tr>
<tr>
<td>50010</td>
<td>Encoder 1 status word</td>
<td>G1_ZSW</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50011</td>
<td>Encoder 1 position actual value 1</td>
<td>G1_XIST1</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50012</td>
<td>Encoder 1 position actual value 2</td>
<td>G1_XIST2</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50014</td>
<td>Encoder 2, status word (from SW 3.3)</td>
<td>G2_ZSW</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50015</td>
<td>Encoder 2, pos. act. value 1 (from SW 3.3)</td>
<td>G2_XIST1</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50016</td>
<td>Encoder 2, pos. act. value 2 (from SW 3.3)</td>
<td>G2_XIST2</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50018</td>
<td>Encoder 3 status word</td>
<td>G3_ZSW</td>
<td>16 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50019</td>
<td>Encoder 3 position actual value 1</td>
<td>G3_XIST1</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
<tr>
<td>50020</td>
<td>Encoder 3 position actual value 2</td>
<td>G3_XIST2</td>
<td>32 bit</td>
<td>n-set</td>
</tr>
</tbody>
</table>

Equipment-specific signals, especially for "SIMODRIVE 611 universal"

<table>
<thead>
<tr>
<th>ID</th>
<th>Significance</th>
<th>Abbrev.</th>
<th>Length</th>
<th>Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>50102</td>
<td>Message word</td>
<td>MeldW</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50104</td>
<td>Analog input, terminals 56.x/14</td>
<td>ADU1</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50106</td>
<td>Analog input, terminal 24.x/20</td>
<td>ADU2</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50108</td>
<td>Digital inputs, terminals I0. to I3.x</td>
<td>DIG_IN</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50110</td>
<td>Utilization</td>
<td>Ausl</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50112</td>
<td>Active power</td>
<td>Pwirk</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50114</td>
<td>Smoothed torque setpoint</td>
<td>Msoll</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50116</td>
<td>Smoothed, torque-generating current Iq</td>
<td>IgGl</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50118</td>
<td>Cntrl word slave-to-slave traffic (from SW 4.1)</td>
<td>QZsw</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50119</td>
<td>DC link voltage (from SW 8.3)</td>
<td>UZK1</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50202</td>
<td>Currently selected block</td>
<td>AktSatz</td>
<td>16 bit</td>
<td></td>
</tr>
<tr>
<td>50204</td>
<td>Positioning status word</td>
<td>PosZsw</td>
<td>16 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50206</td>
<td>Position actual value (positioning mode)</td>
<td>XistP</td>
<td>32 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50208</td>
<td>Position reference value (from SW 4.1)</td>
<td>XsollP</td>
<td>32 bit</td>
<td>pos</td>
</tr>
<tr>
<td>50210</td>
<td>Correction, pos. ref. value (from SW 4.1)</td>
<td>Xcor</td>
<td>32 bit</td>
<td>pos</td>
</tr>
</tbody>
</table>
Table 5-25  Parameters for configuring the process data, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
</table>

**Note:**
- The following applies for P0922 > 0:
  - P0916:17 is pre-assigned when the system boots corresponding to the selected standard telegram in P0922. A change made to P0916:2 to P0916:16 is again overwritten corresponding to the selected standard telegram when the system re-boots.
  - Operating mode not specified --> possible in every operating mode
  - The following applies for P0922 = 0:
    - before SW 4.1 --> From P0916:5 (assignment for PZD5), process data can be freely configured. This means from P0916:5, the signal ID of the requested signal can be entered.
    - From SW 4.1 --> From P0916:2 (assignment for PZD2), process data can be freely configured, i.e. from P0916:2, the signal ID of the required signal can be entered.

- P0916:0 No significance
- P0916:1 PZD1 Configuring not possible (standard setting)
- P0916:2 PZD2 Free configuring possible (from SW 4.1, before SW 4.1 from PZD5), i.e. enter the required signal ID
- ...
- P0916:16 PZD16 Free configuring possible, i.e. enter the required signal ID

- An overview of the status words is provided in Chapter 5.6.1.
- The process data for encoder 2 must be activated via P0879.12.
### Table 5-25 Parameters for configuring the process data, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0922</td>
<td>Telegram selection PROFIBUS</td>
<td>0</td>
<td>101</td>
<td>104</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>

... is used to set the free configurability or to select a standard telegram.

**Note:**
The signal IDs of the process data can be entered into P0915:17 and P0916:17 and pre-assigned default values corresponding to the selection when the drive boots.

**P0922 = 0**

**The telegram can be freely configured**
i.e. PZD1 is pre-assigned default values as standard, dependent on the selected operating mode and PZD2 to PZD16 can be configured using P0915:2 to P0915:16 or P0916:2 to P0916:16 by entering the required signal ID.

**Operating mode:**
P0700 = 1 (speed/torque setpoint)

<table>
<thead>
<tr>
<th>Setpoint</th>
<th>Actual value</th>
</tr>
</thead>
<tbody>
<tr>
<td>PZD1</td>
<td>PZD2</td>
</tr>
<tr>
<td>STW1</td>
<td>NSET_B</td>
</tr>
<tr>
<td>P0915 :1</td>
<td>50001</td>
</tr>
<tr>
<td>P0915 :2</td>
<td>50001</td>
</tr>
<tr>
<td>...........</td>
<td>..............</td>
</tr>
</tbody>
</table>

**before SW 4.1:**
from here can be freely configured

<table>
<thead>
<tr>
<th>xxx: Signal name</th>
<th>yyyy: Signal ID</th>
</tr>
</thead>
</table>

**Operating mode:**
P0700 = 3 (positioning)

<table>
<thead>
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<th>Setpoint</th>
<th>Actual value</th>
</tr>
</thead>
<tbody>
<tr>
<td>PZD1</td>
<td>PZD2</td>
</tr>
<tr>
<td>STW1</td>
<td>SatzAnw</td>
</tr>
<tr>
<td>P0915 :1</td>
<td>50001</td>
</tr>
<tr>
<td>P0915 :2</td>
<td>50001</td>
</tr>
<tr>
<td>...........</td>
<td>..............</td>
</tr>
</tbody>
</table>

**before SW 4.1:**
from here can be freely configured

<table>
<thead>
<tr>
<th>xxx: Signal name</th>
<th>yyyy: Signal ID</th>
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</thead>
</table>
Table 5-25 Parameters for configuring the process data, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0922</td>
<td>Standard telegram 1, ( n_{\text{set}} ) interface 16 bit</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>PZD1 PZD2 STW1 NSET_A</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0915 P0915 :1 :2</td>
<td>50001</td>
<td>50005</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>PZD1 PZD2 ZSW1 NIST_A</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0916 P0916 :1 :2</td>
<td>50002</td>
<td>50006</td>
<td></td>
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<tr>
<td>P0922</td>
<td>Standard telegram 2, ( n_{\text{set}} ) interface 32 bit without encoder</td>
<td></td>
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<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>PZD1 PZD2 PZD3 PZD4 STW1 NSET_B STW2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<tr>
<td></td>
<td>P0915 P0915 P0915 :1 :2 :3 :4</td>
<td>50001</td>
<td>50007</td>
<td>50007</td>
<td>50003</td>
<td></td>
</tr>
<tr>
<td></td>
<td>PZD1 PZD2 ZSW1 NIST_B ZSW2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0916 P0916 P0916 :1 :2 :3 :4</td>
<td>50002</td>
<td>50008</td>
<td>50008</td>
<td>50004</td>
<td></td>
</tr>
<tr>
<td>P0922</td>
<td>Standard telegram 3, ( n_{\text{set}} ) interface 32 bit with encoder 1</td>
<td></td>
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</tr>
<tr>
<td></td>
<td>PZD1 PZD2 PZD3 PZD4 PZD5 STW1 NSET_B STW2 G1_STW</td>
<td></td>
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<td></td>
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<tr>
<td></td>
<td>P0915 P0915 P0915 P0915 P0915 :1 :2 :3 :4 :5</td>
<td>50001</td>
<td>50007</td>
<td>50007</td>
<td>50003</td>
<td>50009</td>
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<tr>
<td></td>
<td>PZD1 PZD2 ZSW1 NIST_B ZSW2 G1_ZSW G1_XIST1 G1_XIST2</td>
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<tr>
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<td>P0916 P0916 P0916 P0916 P0916 :1 :2 :3 :4 :5 :6 :7 :8 :9</td>
<td>50002</td>
<td>50008</td>
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<td>50004</td>
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</table>

This process data is associated with the encoder interface (refer to Chapter 5.6.4)
### Table 5-25 Parameters for configuring the process data, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
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<tbody>
<tr>
<td>P0922</td>
<td>4</td>
<td><strong>Standard telegram 4, ( n_{\text{set}} ) interface, 32-bit with encoder 1 and encoder 2</strong></td>
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<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
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<td>50003</td>
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<td>P0916</td>
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<td>50010</td>
<td>50011</td>
<td>50012</td>
</tr>
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</table>

This process data is associated with the encoder interface (refer to Chapter 5.6.4)

| P0922 | 5  | **Standard telegram 5, \( n_{\text{set}} \) interface with KPC (DSC) and encoder 1** | | | | |
| P0915 | P0915 | P0915 | P0915 | P0915 | P0915 | P0915 |
| 50001 | 50007 | 50007 | 50003 | 50009 | 50025 | 50025 |

This process data is associated with the encoder interface (refer to Chapter 5.6.4)
Table 5-25  Parameters for configuring the process data, continued

<table>
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<tr>
<th>No.</th>
<th>Name</th>
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<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
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<td>Standard telegram 6, nset interface with KPC (DSC) and encoder 1 and encoder 2</td>
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</tr>
<tr>
<td></td>
<td></td>
<td>PZD1</td>
<td>PZD2</td>
<td>PZD3</td>
<td>PZD4</td>
<td>PZD5</td>
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<tr>
<td>STW1</td>
<td>NSET_B</td>
<td>STW2</td>
<td>G1_STW</td>
<td>G2_STW</td>
<td>XERR</td>
<td>KPC</td>
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<td>PZD2</td>
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<td>PZD4</td>
<td>PZD5</td>
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<td>NIST_B</td>
<td>ZSW2</td>
<td>G1_ZSW</td>
<td>G1_XIST1</td>
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</tbody>
</table>

This process data is associated with the encoder interface (refer to Chapter 5.6.4)
Table 5-25  Parameters for configuring the process data, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
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<tbody>
<tr>
<td>P0922</td>
<td>101 The telegram has the same structure as in SW 2.4</td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td><strong>Operating mode: P0700 = 1 (speed/torque setpoint)</strong></td>
<td></td>
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<tr>
<td></td>
<td>PZD1</td>
<td>PZD2</td>
<td>PZD3</td>
<td>PZD4</td>
<td>PZD5</td>
<td>PZD6</td>
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<td>STW1</td>
<td>NSET_B</td>
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<td>PZD4</td>
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<td>ZSW1</td>
<td>NIST_B</td>
<td>ZSW2</td>
<td>MeldW</td>
<td>ADC1</td>
<td>ADC2</td>
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<td>50104</td>
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<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Operating mode: P0700 = 3 (positioning)</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>PZD1</td>
<td>PZD2</td>
<td>PZD3</td>
<td>PZD4</td>
<td>PZD5</td>
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<td>STW1</td>
<td>SatzAnw</td>
<td>PosStw</td>
<td>STW2</td>
<td>Over</td>
<td>DAC1</td>
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<td>ZSW1</td>
<td>AktSatz</td>
<td>PosZsw</td>
<td>ZSW2</td>
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<td>ADC1</td>
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<td>P0922 = 102 Standard telegram 102, n_set interface with encoder 1</td>
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<td>PZD4</td>
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This process data is associated with the encoder interface (refer to Chapter 5.6.4)
### Table 5-25  Parameters for configuring the process data, continued

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##### This process data is associated with the encoder interface (refer to Chapter 5.6.4)

### Table 5-25  Parameters for configuring the process data, continued

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### Table 5-25 Parameters for configuring the process data, continued

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This process data is associated with the encoder interface (refer to Chapter 5.6.4)
Table 5-25  Parameters for configuring the process data, continued

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This process data is associated with the encoder interface (refer to Chapter 5.6.4)
Table 5-25  Parameters for configuring the process data, continued

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This process data is associated with the encoder interface (refer to Chapter 5.6.4)

| P0922 | 108  Standard telegram 108, positioning, master drive for the position reference value coupling (publisher) |      |          |      |      |           |
|      | Setpoint                                                           |      |          |      |      |           |
|      | **PZD1** | **PZD2** | **PZD3** | **PZD4** | **PZD5** | **PZD6** | **PZD7** | **PZD8** | **PZD9** | **PZD10** |      |      |      |      |
| P0915 | :1          | :2          | :3          | :4          | :5          | :6          | :7            | :8          | :9            | 50001        | 50201        | 50203        | 50003        | 50205        | 50018        | 50015        | 50015        | 50016        | 50016        |

Actual value

**G3_ZSW** | **G3_XIST1** | **G3_XIST2** | **XERR** | **KPC** | **Xcor** |
| P0916 | :11          | :12          | :13          | :14          | :15            | 50018        | 50015        | 50015        | 50016        | 50016        |
Table 5-25  Parameters for configuring the process data, continued

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<td>PZD25</td>
<td>P0916</td>
<td>50201</td>
<td>50202</td>
<td>50203</td>
<td>50003</td>
<td>50205</td>
</tr>
<tr>
<td>PZD26</td>
<td>P0916</td>
<td>50201</td>
<td>50202</td>
<td>50203</td>
<td>50003</td>
<td>50205</td>
</tr>
<tr>
<td>PZD27</td>
<td>P0916</td>
<td>50201</td>
<td>50202</td>
<td>50203</td>
<td>50003</td>
<td>50205</td>
</tr>
<tr>
<td>PZD28</td>
<td>P0916</td>
<td>50201</td>
<td>50202</td>
<td>50203</td>
<td>50003</td>
<td>50205</td>
</tr>
<tr>
<td>PZD29</td>
<td>P0916</td>
<td>50201</td>
<td>50202</td>
<td>50203</td>
<td>50003</td>
<td>50205</td>
</tr>
<tr>
<td>PZD30</td>
<td>P0916</td>
<td>50201</td>
<td>50202</td>
<td>50203</td>
<td>50003</td>
<td>50205</td>
</tr>
</tbody>
</table>

5.6 Net data (PKW and PZD area)

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5-277
5.6.6 Defining the process data according to the PPO type

The following process data is transferred in the speed-controlled mode when using standard telegram 101, depending on the particular PPO type:

Table 5-26 Process data in the closed-loop speed controlled mode

<table>
<thead>
<tr>
<th>PPO</th>
<th>PPO1</th>
<th>PPO2</th>
<th>PPO3</th>
<th>PPO4</th>
<th>PPO5</th>
</tr>
</thead>
<tbody>
<tr>
<td>Master</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Control words (setpoints)</td>
<td>STW 1</td>
<td>n-soll-1</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
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<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Slave</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

The control words are described in Chapter 5.6.2.
The status words are described in Chapter 5.6.3.

### Abbreviations:
- **PPO**: Parameter Process data Object
- **PZD**: Process data
- **STW1**: Control word 1
- **n-soll**: Speed setpoint
- **MomRed**: Torque reduction
- **STW2**: Control word 2
- **ADU1**: Analog input, terminal 56.x/14.x
- **ADU2**: Analog input, terminal 24.x/20.x
- **DAU1**: Analog output, terminal 75.x/15
- **DAU2**: Analog output, terminal 16.x/15
- **ZSW1**: Status word 1
- **ZSW2**: Status word 2
- **n-ist**: Speed actual value
- **MeldW**: Message word
- **ADU1**: Analog input, terminal 56.x/14.x
- **Mset**: Smoothed torque setpoint
- **Ausl**: Utilization
- **Pwirk**: Active power

**Note**
Operation is also possible with the PPO types which cannot transfer all process data (e.g. PPO1 and PPO3).
PPO type 3 is sufficient for closed-loop speed controlled operation with a simple basic functionality (2 control and 2 status words).
The "SIMODRIVE 611 universal" drive should be operated in the mode "speed/torque setpoint" with a speed of 1500 RPM via PROFIBUS-DP.

Assumptions for the slave:

- The drive has been completely commissioned is connected to PROFIBUS-DP and is ready to run.
- P0918 (PROFIBUS node address) = 12

Assumptions for the master:

- The DP master is a SIMATIC S7 (CPU: S7-315-2-DP)
- Hardware configuration
  - 1-axis, PPO type 1, node address = 12
  - Part I address O address
    - PKW 272 – 279 272 – 279 (not shown in the example)
    - PZD 280 – 283 280 – 283

---

**Fig. 5-19 Example: Operate the drive via PROFIBUS**
Process data in the positioning mode

Dependent on the PPO type, in the positioning mode, the following process data is transferred when using standard telegram 101:

Table 5-27  Process data in the positioning mode

<table>
<thead>
<tr>
<th></th>
<th>PZD 1</th>
<th>PZD 2</th>
<th>PZD 3</th>
<th>PZD 4</th>
<th>PZD 5</th>
<th>PZD 6</th>
<th>PZD 7</th>
<th>PZD 8</th>
<th>PZD 9</th>
<th>PZD 10</th>
</tr>
</thead>
<tbody>
<tr>
<td>PD</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>1st</td>
<td>2nd</td>
<td>3rd</td>
<td>4th</td>
<td>5th</td>
<td>6th</td>
<td>7th</td>
<td>8th</td>
<td>9th</td>
<td>10th</td>
</tr>
<tr>
<td>Master</td>
<td>STW</td>
<td>Satz</td>
<td>Pos</td>
<td>STW</td>
<td>Over</td>
<td>DAU</td>
<td>DAU</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Slave</td>
<td>1</td>
<td>2</td>
<td>3</td>
<td>4</td>
<td>5</td>
<td>6</td>
<td>7</td>
<td>8</td>
<td>9</td>
<td>10</td>
</tr>
</tbody>
</table>

The control words are described in Chapter 5.6.2.
The status words are described in Chapter 5.6.3.

Abbreviations:
- PPO Parameter Process Object
- ZSW Status word
- STW Control word
- Satz Block selection
- Pos Position control
- STW2 Control word
- Over Override
- ADU Analog input
- DAU Analog output
- Akt Currently selected block
- Anw Positioning status word
- Zsw Status word
- Meld Message word
- ADU1 Analog input, terminal 56.x/14.x
- ADU2 Analog input, terminal 24.x/20.x
- Pwirk Active power
- Msoll Smoothed torque setpoint

Note

Operation is also possible with the PPO types which cannot transfer all process data (e.g. PPO1 and PPO3).

For the positioning mode with a basic functionality, PPO type 3 is sufficient (2 control and 2 status words).
5.6.7 Parameter area (PKW area)

Tasks

For PPO types 1, 2 and 5 for the net data (useful data), a parameter range with 4 words is also transferred. The following tasks are possible using the parameter range:

- Request parameter value (read parameters)
- Change parameter value (write parameters)
- Request number of array elements

Structure of the PKW area

The PKW area comprises the parameter ID (PKE), the sub-index (IND) and the parameter value (PWE).

Table 5-28 Structure of the parameter area (PKW)

<table>
<thead>
<tr>
<th>Word</th>
<th>PKE</th>
<th>IND</th>
<th>PWE</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>3</td>
<td>4</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>PPO1</th>
</tr>
</thead>
<tbody>
<tr>
<td>PPO2</td>
</tr>
<tr>
<td>PPO5</td>
</tr>
</tbody>
</table>

Note:

- Bit 15 = 1: PNU of PKE + 2000
- Bit 12 = 1: PNU of PKE + 4000
- Reserved bits 8 to 11, 13, 14

Sub-parameter number

Bits 15 to 12

- Bit 15: PNU of PKE + 2000
- Bit 12: PNU of PKE + 4000

Reserved bits 8 to 11, 13, 14

16-bit parameters: Value = 0
32-bit parameters: High component Low component

From SW 11.2:

AK: Value range 0 ... 15
Res: Reserved
PNU: Value range 1 ... 1999
Value range > 1999 refer to IND bits 12 and 15

Note:

- refer to P0879.11

(Sub-index in the high/low byte of IND)

Abbreviations:

- PPO: Parameter Process data Object
- PKW: Parameter ID value
- PZD: Process data
- PKE: Parameter ID
- IND: Sub-index, sub-parameter number, array index
- PWE: Parameter value
- AK: Task and response ID
- PNU: Parameter number
### Task telegram, IDs

The IDs for the task telegram (master --> slave) should be taken from the following table:

Table 5-29  Task IDs (master --> slave)

<table>
<thead>
<tr>
<th>Request ID</th>
<th>Function</th>
<th>Response ID (positive)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>No task</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>Request parameter value</td>
<td>1, 2</td>
</tr>
<tr>
<td>2</td>
<td>Change parameter value (word)</td>
<td>1</td>
</tr>
<tr>
<td>3</td>
<td>Change parameter value (double word)</td>
<td>2</td>
</tr>
<tr>
<td>4, 5</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>6</td>
<td>Request parameter value (array)</td>
<td>4, 5</td>
</tr>
<tr>
<td>7</td>
<td>Change parameter value (array word)</td>
<td>4</td>
</tr>
<tr>
<td>8</td>
<td>Change parameter value (array double word)</td>
<td>5</td>
</tr>
<tr>
<td>9</td>
<td>Request number of array elements</td>
<td>6</td>
</tr>
<tr>
<td>10 (from SW 3.5)</td>
<td>Quickly change the parameter value (array, double word)</td>
<td>5</td>
</tr>
</tbody>
</table>

**Note:**

- All of the "SIMODRIVE 611 universal" parameters can be read and written into the using the task IDs 6, 8 and 10.
- The negative response ID is 7.
- The IDs are defined so that they indicate which fields of the PK interface must also be evaluated.
- Task 8  Data is first calculated into the control and then a response telegram is sent
- Task 10  Data is calculated into the control and a response telegram is sent at the same time

For example, in order to be able to issue a start task immediately after a traversing block has been completely transferred, the last write task should have the ID 8.

### Response telegram, IDs

The IDs for the response telegram (slave --> master) can be taken from the following table:

Table 5-30  Response IDs (slave --> master)

<table>
<thead>
<tr>
<th>Response ID</th>
<th>Function</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>No response</td>
</tr>
<tr>
<td>1</td>
<td>Transfer parameter value (word)</td>
</tr>
<tr>
<td>2</td>
<td>Transfer parameter value (double word)</td>
</tr>
<tr>
<td>3</td>
<td>-</td>
</tr>
<tr>
<td>4</td>
<td>Transfer parameter value (array word)</td>
</tr>
<tr>
<td>5</td>
<td>Transfer parameter value (array double word)</td>
</tr>
<tr>
<td>6</td>
<td>Transfer number of array elements</td>
</tr>
<tr>
<td>7</td>
<td>Task cannot be executed (with error number)</td>
</tr>
<tr>
<td>8, 9 and 10</td>
<td>-</td>
</tr>
</tbody>
</table>
How is a task executed?
The master transfers a task to a slave and repeats this task for at least as long as the associated response is received from the slave.
The slave provides the response until the master has formulated a new task.
For responses, which include parameter values, the slave always cyclically responds with an updated value. This involves all responses to the tasks "request parameter value" and "request parameter value (array)".

Fault evaluation
If tasks cannot be executed, the slave responds as follows:
- Outputs a response ID = 7
- Outputs an error number in word 4 of the parameter area

Table 5-31  Error IDs for "DP slave 611U"

<table>
<thead>
<tr>
<th>Fault ID</th>
<th>Error cause</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Illegal parameter number (the parameter does not exist)</td>
</tr>
<tr>
<td>1</td>
<td>Parameter value cannot be changed (Parameter can only be read or is write protected)</td>
</tr>
<tr>
<td>2</td>
<td>Upper or lower value limit exceeded</td>
</tr>
<tr>
<td>3</td>
<td>Incorrect sub-index</td>
</tr>
<tr>
<td>4</td>
<td>No array (parameter does not have any sub-parameter)</td>
</tr>
<tr>
<td>5</td>
<td>Incorrect data type (is not required for the type conversion)</td>
</tr>
<tr>
<td>6 to 19</td>
<td>not required</td>
</tr>
<tr>
<td>20 to 100</td>
<td>Reserved</td>
</tr>
</tbody>
</table>

Data types
The data type, assigned to the parameter must be written into the parameter value via the PKW mechanism (refer under data type in the parameter list in Chapter A.1).

Table 5-32  Data types

<table>
<thead>
<tr>
<th>Data type for &quot;DP slave 611U&quot;</th>
<th>Explanation</th>
<th>Data type for SIMATIC S7</th>
</tr>
</thead>
<tbody>
<tr>
<td>Integer16</td>
<td>Integer number, 16 bit</td>
<td>INT</td>
</tr>
<tr>
<td>Integer32</td>
<td>Integer number, 32 bit</td>
<td>DINT</td>
</tr>
<tr>
<td>Unsigned16</td>
<td>Integer number without sign (unsigned) 16 bit</td>
<td>WORD</td>
</tr>
<tr>
<td>Unsigned32</td>
<td>Integer number without sign (unsigned) 32 bit</td>
<td>DWORD</td>
</tr>
<tr>
<td>Floating point</td>
<td>Floating-point number</td>
<td>REAL</td>
</tr>
</tbody>
</table>
Transferring traversing blocks

For "SIMODRIVE 611 universal", the traversing blocks in the "positioning" operating mode are saved in parameters, and can therefore be read and changed using the PKW mechanism.

Reader’s note

The parameters for the traversing blocks are described in Chapter 6.2.10.

When mapping the traversing blocks to the parameters, the parameter number defines the block components (position, velocity, etc.) and the sub-parameter number of the traversing block number.

Example: P0081:17 Position for traversing block 17

Addressing in the PKW mechanism:

- The parameter ID (PKE) addresses the block components.
- The sub-index (IND) addresses the traversing block number

This means that a complete set can only be read or changed one after the other via the individual components.

From SW 7.1, during positioning, a new position or a new traversing block can be accepted and executed (flying block change) using the function "MDI" (refer to Chapter 6.2.12).

Rules for processing tasks/responses

1. A task or a response can always only be referred to one parameter.
2. The master must repeat a task until it has received the appropriate response from the slave.
3. The slave provides the response until the master has formulated a new task.
4. The master recognize the response to a task which it issued:
   - by evaluating the response ID
   - by evaluating the parameter number (PNU)
   - also, if required, by evaluating the parameter index (IND)
5. For response telegrams, which include parameter values, the slave always cyclically responds with an updated value.
   This involves all responses to the tasks "request parameter value" and "request parameter value (array)".
Example: **Reading parameters via PROFIBUS**

When there is at least one fault, the drive fault buffer (P0945:1 to P0945:8) should be read out via PROFIBUS, and buffered on the master side.

Assumptions for the slave:

- The drive has been completely commissioned is connected to PROFIBUS–DP and is ready to run.
- P0918 = 12 (PROFIBUS node address) has been set

Assumptions for the master:

- The DP master is a SIMATIC S7 (CPU: S7-315–2–DP)
- Hardware configuration
  - 1-axis, PPO type 1, node address = 12
  - Part I address O address
    - PKW 272 – 279 272 – 279
    - PZD 280 – 283 280 – 283 (not shown in the example)

What has to be programmed on the master side?

If the input signal from the peripheral (I/O) area E281.3 (ZSW1.3, fault present/no fault present) = "1" signal, then the following must be executed on the master side (refer to Fig. 5-20):

1. Programming SFC14 and SFC15
   - The standard functions SFC14 "Read slave data" and SFC15 "write slave data" are required in order to consistently transfer more than 4 bytes.

2. Request parameter value
   - Write into the PKW output signals (PAB 272 –279) with
     - AK = 6, PNU = 945, IND = 1, PWE = no significance

3. Read parameter value and save
   - Evaluate the PKW input signals (PEB 272 –279)
     - If AK = 4 or 5, PNU = 945, IND = 1 and PWE = xx then OK
     - Read and save P945:1 = xx
     - If AK = 7, then evaluate the fault number in PEW 278 (refer to Table 5-31)

4. Repeat points 1 and 2 to read the other sub-parameters of the fault condition
   - P945:2 --> PNU = 945, IND = 2
   - P945:8 --> PNU = 945, IND = 8

This repetitive procedure can be exited if a "0" is in one of the sub-parameters. All of the faults of the last fault situation are then detected.
5.6 Net data (PKW and PZD area)

Fig. 5-20 Example: Reading parameters via PROFIBUS

**Note**

The "FC 92" SIMATIC S7 block can be used for "read parameters via PROFIBUS". This block is included in the toolbox of the CD for "SIMODRIVE 611 universal" in the file "s7_Baust.arj" and is documented using its block comments.

There are additional application examples in the toolbox with the "read/write parameter" function (e.g. interface 611u <--> S7 in the file "611u39.arj").
Depending on a condition, the position in traversing block 4 (P0081:3) should be adapted as required via PROFIBUS.

In this particular example, P0081:3 = 14 586 is written.

Assumptions for the slave:

- The drive has been completely commissioned is connected to PROFIBUS-DP and is ready to run.
- P0700 = 3 ("positioning" mode) has been set
- P0918 = 12 (PROFIBUS node address) has been set

Assumptions for the master:

- The DP master is a SIMATIC S7 (CPU: S7–315-2–DP)
- Hardware configuration
  - 1-axis, PPO type 1, node address = 12
  - Part I address O address
    - PKW 272 – 279 272 – 279
    - PZD 280 – 283 280 – 283 (not shown in the example)

If the condition to write the position in traversing block 4 is available, then the following must occur on the master side (refer to Fig. 5-21):

1. Write the parameter value (define task)
   - PKW output signals (PAB 272 – 279) written into
     with
     AK = 8, PNU = 81, IND = 3, PWE2 = 14586

2. Check the task
   - Evaluate the PKW input signals (PEB 272 –279)
   - If AK = 5, PNU = 81, IND = 3 and PWE2 = 14586 then OK
   - If AK = 7,
     then evaluate the fault number in PEW 278 (refer to Table 5-31)
5.6 Net data (PKW and PZD area)

**Fig. 5-21 Example: Writing parameters via PROFIBUS**

---

**Note**

The "FC 93" SIMATIC S7 block can be used to "write parameters via PROFIBUS". This block is included in the toolbox of the CD for "SIMODRIVE 611 universal" in the file "s7_Baust.arj" and is documented using its block comments.

There are additional application examples in the toolbox with the "read/write parameter" function (e.g. interface 611u <--> S7 in the file "611u39.arj").
5.7 Settings at the PROFIBUS-DP master

5.7.1 Master device file and configuring

Performance features of the PROFIBUS devices

PROFIBUS devices have different performance features. In order that all of the master systems can correctly address the "DP slave 611U", the characteristic features of the slave are combined in a standardized master device file (GSD).

The "DP slave 611U" is exclusively operated as DP slave.

Master device file for "DP slave 611U"

The following master device files (GSDs) are available for the "DP slave 611U":

Before SW 4.1:
- SIEM8055.GSD for the optional PROFIBUS-DP1 module
- SIEM808F.GSD for the optional PROFIBUS-DP2 and DP3 modules

From SW 4.1:
- SIEM808F.GSD for the optional PROFIBUS-DP2 and DP3 modules

From SW 6.1:
- SIEM808F.GSD for the optional PROFIBUS DP2 and DP3 modules (PROFIdrive application Class 1)
- SI02808F.GSD for the optional PROFIBUS DP2 and DP3 modules (PROFIdrive application Class 4)

Using the GSD file SI02808F.GSD, it is no longer necessary to enter the block for clock-cycle synchronism into the parameterizing telegram manually byte-for-byte.

In order to use the GSD file SI02808F.GSD, a configuring tool is required which supports the GSD Revision 4 (e.g. Step7 HW-Config Version x.xx)

Reader’s note

From SW 4.1, the optional PROFIBUS-DP1 module can no longer be used.

Compatibility conditions, GSD file and optional modules are described in Chapter 1.3.3 in Table 1-4.

The GSDs are available as ASCII files on the data medium (e.g. CD) for "SIMODRIVE 611 universal".

These files uniquely describe the features and properties of the "DP slave 611U" in a precisely defined format.

The GSD file must be inserted into the configuring tool of the master.
If this is not possible, then the appropriate information must be derived for the "DP slave 611U" from the GSD file.

---

**Reader's note**

Information on the PROFIBUS--DP master settings should be taken from the literature of the master used.

---

**Configuration**

Configuring defines the data, which the master transfers to the "DP slaves" at every bus run-up via the parameterizing telegram and the configuration telegram.

Configuring can be realized in the following ways:

1. Using the GSD "SIEM808F.GSD" or "SI02808F.GSD"

2. Using the "Slave Object Manager (Drive ES Slave--OM)", which is included in the following products:

<table>
<thead>
<tr>
<th>Product</th>
<th>Order No. (MLFB):</th>
</tr>
</thead>
<tbody>
<tr>
<td>Drive ES Basic V5.1 SP2</td>
<td>6SW1700–5JA00–1AA0 (single license)</td>
</tr>
<tr>
<td></td>
<td>6SW1700–5JA00–1AA1 (company license)</td>
</tr>
<tr>
<td></td>
<td>6SW1700–5JA00–1AA4 (upgrade)</td>
</tr>
<tr>
<td>Drive ES SIMATIC V5.2</td>
<td>6SW1700–5JC00–2AA0</td>
</tr>
<tr>
<td></td>
<td>6SW1700–5JC00–2AA4 (upgrade)</td>
</tr>
</tbody>
</table>

   The products, require as basis, the basic SIMATIC--STEP 7 software.

   Compared to the GSD file, Drive ES offers a higher degree of user friendliness regarding the telegram structure and clock cycle-synchronous operation.

   Slave-to-slave communications does not function without Drive ES.

   The following is valid from SW 3.1:

   The parameterizing and configuration data, received from the "DP slave 611U" are displayed in the following parameters:

   - P1783:64 Received PROFIBUS parameterizing data
   - P1784:64 Received PROFIBUS configuration data
Parameterizing telegram

For the parameterizing data, the following should be noted:

- for DP slaves with SIEM8055.GSD
  The drive only expects the 6-byte standard DP parameterizing telegram.
- for DP slaves with SIEM808F.GSD (from SW 3.1)
  - If there is no clock-synchronous operation
    The standard setting from the GSD can be used for the parameterizing data.
  - If there is clock-synchronous operation
    The parameterizing data must, in some cases, be modified (refer to Chapter 5.8.5).

Configuration telegram

The following must be observed for the configuration data:

- for DP slaves with SIEM8055.GSD
  Using the configuration telegram, the "DP slave 611U" is signaled the PPO type, the axis number and consistent or inconsistent data transfer mode.
  A consistent data transfer is selected as standard via the GSD file. The "DP slave 611U" also accepts an inconsistent data transfer (refer to Table 5-33).
  Consistent and inconsistent entries can also be mixed (e.g. the PKW area with consistent and the PZD area with inconsistent data transfer).

Table 5-33 Permissible configuration telegrams

<table>
<thead>
<tr>
<th>PPO</th>
<th>Consistent (over the complete length)</th>
<th>Inconsistent (consistent over 1 word)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>1-axis</td>
<td>2-axis</td>
</tr>
<tr>
<td>1</td>
<td>F3F1</td>
<td>F3F1F3F1</td>
</tr>
<tr>
<td>2</td>
<td>F3F5</td>
<td>F3F5F3F5</td>
</tr>
<tr>
<td>3</td>
<td>F1</td>
<td>F1F1</td>
</tr>
<tr>
<td>4</td>
<td>F5</td>
<td>F5F5</td>
</tr>
<tr>
<td>5</td>
<td>F3F9</td>
<td>F3F9F3F9</td>
</tr>
</tbody>
</table>
• for DP slaves with SIEM808F.GSD (from SW 3.1)

Using the configuration telegram, the "DP slave 611U" is signaled the length of the I/O data, the axis number and consistent or inconsistent data transfer mode.

Net data - maximum length
The maximum length of the net data is 20 words for each drive (PKW section = 4 words, PZD section = max. 16 words).

PZD - minimum length
if no clock--synchronous operation: I/O = min. 2/2 words
for clock--synchronous operation: I/O = min. 4/4 words

Any combination of I/O data is possible, whereby the length for the data must be specified as either word or double--word resolution (one word = 16 bits).

The 2-byte ID 01FEhex is used to differentiate between the two configuration data of the two drives.

A PKW section is present, if the first entry for an axis is F3hex.

Table 5-34  IDs in the configuration telegram

<table>
<thead>
<tr>
<th>Entry</th>
<th>Description</th>
<th>Data transfer</th>
<th>Consistent</th>
<th>Inconsistent</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>PIV</td>
<td></td>
<td>F3</td>
<td>00 or ≠ F3</td>
</tr>
<tr>
<td></td>
<td>No PKW</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 or 2 ... last</td>
<td>n words I/O</td>
<td>F(n-1) with the exception F3</td>
<td>7(n-1)</td>
<td></td>
</tr>
<tr>
<td>1 or 2 ... last</td>
<td>n words I</td>
<td>D(n-1)</td>
<td>5(n-1)</td>
<td></td>
</tr>
<tr>
<td>1 or 2 ... last</td>
<td>n words O</td>
<td>E(n-1)</td>
<td>6(n-1)</td>
<td></td>
</tr>
</tbody>
</table>

Table 5-35  Examples: Configuration data for SIEM808F.GSD

<table>
<thead>
<tr>
<th>Example</th>
<th>Data transfer</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>Consistent (complete length)</td>
</tr>
<tr>
<td></td>
<td>1-axis</td>
</tr>
<tr>
<td>With PKW with PZD = 10/10 words (I/O), = PPO 5</td>
<td>F3F9</td>
</tr>
<tr>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
</tr>
<tr>
<td>Without PKW with PZD = 8/15 words (I/O)</td>
<td>D7EE</td>
</tr>
<tr>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
</tr>
</tbody>
</table>
5.7.2 Commissioning

Prerequisites for a slave

In order to commission the "DP slave 611U" the slave must fulfill the following prerequisites or these prerequisites must be clarified:

- What is the node address of the DP slave?
  
  The node address must be set in P0918.

- In which mode is the DP slave operated?
  
  This mode is set in P0700.
  
  The selected mode is significant when defining the functional scope of the DP slave and the function of the control and status signals.

  - "Speed/torque setpoint" mode
    
    The closed-loop speed controlled mode represents a functional subset of the positioning mode.
    
    The functional scope is defined by the control and status words specified in Chapter 5.6.1.

  - "Positioning" mode
    
    In the positioning mode, the functional scope is defined by the control and status words, specified in Chapter 5.6.1.

---

**Note**

In order to commission all of the nodes connected to PROFIBUS, it now may be necessary to temporarily disable the "disturbing" DP slaves (also refer to the Chapter 5.9 under P0875).

---

**Caution**

With the "DP slave 611U" powered-up, the enable terminals and PROFIBUS enable signals are required in order to enable the drive and to operate it.

If the "DP slave 611U" is switched out via P0875 = 0, then the drive is already enabled using the local enable terminals (e.g. terminal 663, 65.x). Thus, the enable signals via the PROFIBUS control word are no longer necessary.
When starting-up the "DP slave 611U" the following must be taken into consideration on the master side:

- Node address (station address)
  What is the node address (P0918) of the "DP slave 611U" which is to be commissioned?

- Master device file (GSD file)
  Is there a GSD file for the "DP-Slave 611U" for the master? If not, then the GSD file must be inserted into the configuring tool of the master for the "DP-Slave 611U".

- Data transfer (consistent/non-consistent)
  The following applies when programming the data transfer (consistent/inconsistent) in the user program of the master:
  (e.g. for the SIMATIC S7, CPU 315-2DP)
  - PKW part
    --> with SFC 14/15
  - PZD part
    consistent data transfer (consistent over the complete length):
    --> with SFC 14/15
    non-consistent data transfer (consistent over 1 word):
    --> An SFC14/15 cannot be used. Instead, a direct peripheral access must be used (PAW/PEW).
5.7 Settings at the PROFIBUS-DP master

Communications must be possible between the master and slave when parameterizing a DP slave via PROFIBUS. To realize this, for "DP slave 611U", the PROFIBUS node address must be set in P0918. This can be done as follows:

1st possibility: Commission the system for the first time using the display and operator panel and then set the PROFIBUS address

Procedure:
- Fully commission the system using the display and operator panel (refer to Chapter 4.4)
- Set the PROFIBUS node address P0918 = required address
- Save the parameters in the FEPROM: set A0652 to 1
- Carry-out a POWER-ON RESET

2nd possibility: Only set the PROFIBUS address using the display and operator unit

There are the following possibilities:

Setting the PROFIBUS node address via operator action (from SW 3.1)

Requirements:
- Neither faults nor warnings are displayed (if required, press the MINUS key, refer to Chapter 7.2.1).

Proceed as follows:
1. Set the PROFIBUS node address
   - Press the "P" key for longer than 3 seconds
     --> The actual value of P0918 (PROFIBUS node address) is displayed
   - Press the "+" or "-" key to set the required address
   - Press the "P" key again to exit the entry field
2. Save the PROFIBUS node address in the FEPROM
   - Press the "+" or "-" key
     --> P0652 (transfer into the FEPROM) is displayed
   - Press the "P" key to change the parameter
   - Press the "+" key to set P0652 to 1 and wait until P0652 = 0
3. Execute a POWER-ON RESET
   - Press the "POWER-ON RESET" button on the front panel of the board
     --> the selected PROFIBUS node address is effective after run-up
5 Communications via PROFIBUS DP

5.7 Settings at the PROFIBUS-DP master

Setting the PROFIBUS node address using the dialog box for the first start-up

1. Carry out the first commissioning (start-up) using the display and operator unit and for the hardware configuration, do not enter the configuration data up to the node address (refer to Chapter 4.4).

   A1106 (power module code number) do not set
   ... (other parameters) do not set
   A0918 (PROFIBUS node address) set
   A0652 (write into the FEPROM) = 1 set

2. Carry-out a POWER-ON RESET

3. --> cyclic operation between
   "DP slave 611U" <----> PROFIBUS-DP master is possible

Note

The system can be commissioned and parameterized as follows:

- With "SimoCom U via PROFIBUS-DP" (from SW 3.1)
  - Establish online operation (refer to Chapter 3.3.4)
  - Carry-out the first or series commissioning (start-up) using SimoCom U (refer to Chapter 4.3.1 or 4.3.2, P0918 (PROFIBUS node address) may not be overwritten).

- Using "read/write parameter " via PKW section
  The parameters of the "DP slaves 611U" can be read/written into via the PKW section from the PROFIBUS-DP master.
5.7.3 Diagnostics and troubleshooting

There is a two-color LED with the following significance on the front of the optional PROFIBUS DP module:

<table>
<thead>
<tr>
<th>LED Display</th>
<th>Significance</th>
</tr>
</thead>
<tbody>
<tr>
<td>Off</td>
<td>The module has still not been started from the control board or it has not been enabled (P0875)</td>
</tr>
<tr>
<td>Red, Continuous</td>
<td>The module has been enabled (P0875) and started from the control board, there are no cyclic communications (MSCY_C1, Data Exchange, net data transport) between the master and this module as PROFIBUS slave or there was a communications failure (watchdog)</td>
</tr>
<tr>
<td>Red, Flashing</td>
<td>The module has an internal, fatal error</td>
</tr>
<tr>
<td>Green</td>
<td>The module is enabled (P0875) and has been started from the control board, cyclic communications has been established (MSCY_C1, Data Exchange, net data transport) between the master and this module as PROFIBUS slave</td>
</tr>
<tr>
<td>Yellow/green, Alternating flashing light</td>
<td>The firmware is upgraded on the optional module via the serial interface</td>
</tr>
</tbody>
</table>

Check! (if cyclic communications was previously active):  
- is the DP slave node address correct (P0918 ≠ 0)?  
- is the bus connection OK?  
- terminating resistor?  
- are all of the bus cables inserted?  

Counter-measure: Execute POWER-ON RESET  
Replace the option module

Fault display on the control board

Faults and warnings are displayed on the display unit located on the front panel of the control board.

Display and operator control unit for faults and warnings (refer to Chapter 7.2)
Faults which occur are entered into a fault buffer. The fault code, fault number, fault time and fault value for each fault are specified using the appropriate parameters.

The "SIMODRIVE 611 universal" drive signals as to whether there is at least one fault using the status bit or output signal ZSW1.3 "Fault present/no fault present".

The fault buffer comprises 8 fault cases, each of which can include 8 fault entries.

For fault case 1, the faults which have occurred are saved and they remain there until the fault case has been removed, i.e. all of the faults have been removed and also acknowledged.

In fault cases 2 to 8, the acknowledged fault cases since the last POWER ON are saved. The number of fault cases since POWER ON can be read from P0952.

<table>
<thead>
<tr>
<th>Index</th>
<th>Fault code</th>
<th>Fault number</th>
<th>Fault time</th>
<th>Fault value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>101</td>
<td>2</td>
<td>t_{101}</td>
<td>w_{101}</td>
</tr>
<tr>
<td>2</td>
<td>114</td>
<td>10</td>
<td>t_{114}</td>
<td>w_{114}</td>
</tr>
<tr>
<td>3</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>4</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>5</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>6</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>7</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>8</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>9</td>
<td>90</td>
<td>3</td>
<td>t_{90}</td>
<td>w_{90}</td>
</tr>
<tr>
<td>10</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>11</td>
<td>to</td>
<td>to</td>
<td></td>
<td></td>
</tr>
<tr>
<td>16</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

Fig. 5-24  Fault buffer structure
Rules regarding the fault buffer

The following rules apply to the fault buffer:

- At POWER ON, the complete fault buffer is deleted.
- The faults are entered in the sequence that they occur, in the parameter of fault case 1, i.e.
  - 1. fault that has occurred \(\rightarrow\) parameter with index 1
  - 2. fault that has occurred \(\rightarrow\) parameter with index 2, etc.
  
  If more than 8 faults occur, then these are not displayed.
- Fault case 1 is considered to have been resolved, if, the following is valid for all of the entered faults:
  - the cause has been removed and
  - the fault has been acknowledged

The fault buffer is then re-arranged so that the faults of fault case 1 go into fault case 2 and those from fault case 2 into fault case 3 etc. This means that the parameters of fault case 1 are again free for additional entries.

If more than 8 fault cases have occurred since the last POWER ON, then fault case 8 is overwritten, the oldest fault case is eliminated.
- If, in fault case 1, there is at least one fault, which must be acknowledged with POWER ON, then this is valid for the complete fault case.

Reader’s note

A description of the faults, the way in which they can be acknowledged as well as a list of all the faults, is provided in Chapter 7.

Evaluating warnings via PROFIBUS-DP

The warnings which occurred, are displayed, bit-coded in P0953 to P0960.

Status signal for warnings

The "SIMODRIVE 611 universal" drive signals as to whether there is at least one message present via the status bit or output signal ZSW1.7 "Warning present/no warning present".

Reader’s note

A description of the warnings as well as a list of all of the warnings is provided in Chapter 7.
The sent and received process data of the "DP slaves 611U" are displayed using the following parameters:
- P1788:17 Received process data PROFIBUS
- P1789:17 Sent process data PROFIBUS

The sent and received PKW data of the "DP slave 611U" are displayed using the following parameters:
- P1786:5 Received PKW data PROFIBUS
- P1787:5 Sent PKW data PROFIBUS

The parameterizing and configuration data, received from the DP master, are displayed using the following parameters:
- P1783:64 Received PROFIBUS parameterizing data
- P1784:64 Received PROFIBUS configuration data
5.8 Motion Control with PROFIBUS-DP (from SW 3.1)

General

Using the “Motion Control with PROFIBUS DP” function, a clock-cycle synchronous drive coupling can be established between a DP master and one or several slaves via the PROFIBUS fieldbus.

Reader’s note

The clock-synchronous drive coupling is defined in the following documentation:

Reference: /PPA/, PROFIdrive Profile Drive Technology, Version 3.1.2 Sept. 2004 (Chapter 3.4)

From SW 12.1:
Version 4.1 May 2006 (Chapter 6.2)

Which clock-synchronous masters are there?

Clock-synchronous operation can be implemented using the following DP masters:

Table 5-36 Examples for clock-synchronous masters

<table>
<thead>
<tr>
<th>DP-MASTER</th>
<th>DP slave 611U</th>
</tr>
</thead>
<tbody>
<tr>
<td>SINUMERIK 802D</td>
<td>In the &quot;speed/torque setpoint&quot; mode (n-set mode)</td>
</tr>
<tr>
<td>SINUMERIK 840Di</td>
<td></td>
</tr>
<tr>
<td>Positioning and path control board FM 357-2</td>
<td></td>
</tr>
<tr>
<td>SIMATIC S7-300 6ES7315-2AF03-xxxx</td>
<td>In the &quot;positioning&quot; operating mode (pos mode)</td>
</tr>
</tbody>
</table>

Activating

The clock-cycle synchronous drive coupling can be activated if all of the prerequisites of the DP master and DP slave have been fulfilled and the function has been selected in the DP master by appropriately parameterizing/configuring it.

Parameterizing equidistant operation

The parameters for equidistant operation are included in the slave-specific master device file SIEM808F.GSD. Parameterization is also possible via Drive ES.

The master configuring ensures, that all of the DP slaves in the application use the same clock cycle times and processing instants.

When PROFIBUS boots, the information required by the DP slaves, is transferred from the master to all of the slaves via the parameterizing telegram.
Every DP cycle starts with a Global Control Telegram (GC), which is then followed, one after the other, with the data transfer with the individual slaves (S1, S2, ...).

The GC telegram is a broadcast telegram, sent from the master, and which is received simultaneously by all slaves.

The internal clock cycles of the "DP slave 611U" are synchronized to the DP clock cycle using this GC telegram and the PLL used for the optional PROFIBUS–DP3 module.

The clock-synchronous coupling has the following prerequisites and features:

- Prerequisites for the DP slave (refer to Chapter 1.3.3)
  - "SIMODRIVE 611 universal" control board from SW 3.1
  - Optional PROFIBUS–DP3 module with ASIC DPC31 and PLL (Order No.: 6SN1114–0NB01–0AA0)

- Prerequisites for the DP master
  - "Motion Control with PROFIBUS–DP" function
  - Using a DP interface in the DP master, which can realize clock-cycle synchronous operation
  - Transmission rate: Can be set between 1.5 and 12 Mbaud

- Telegram data transfer between a DP master and slave in equidistant cycles.

- Post synchronization of the slave clock cycles to the equidistant DP cycle via the Global Control Telegram at the start of a DP cycle.

- The maximum permissible fluctuations when recognizing a Global Control Telegram (Jitter) via the optional PROFIBUS DP module is dependent on the data transfer rate as follows:

<table>
<thead>
<tr>
<th>Data transfer rate</th>
<th>Max. permissible jitter</th>
</tr>
</thead>
<tbody>
<tr>
<td>12 Mbaud</td>
<td>1.0 µs</td>
</tr>
<tr>
<td>3 or 6 Mbaud</td>
<td>0.9 µs</td>
</tr>
<tr>
<td>1.5 Mbaud</td>
<td>0.8 µs</td>
</tr>
</tbody>
</table>

Clock-synchronous operation with the "DP slave 611U" is only guaranteed when the maximum permissible jitter is maintained.

When configuring the bus system, it should be ensured, that especially when, e.g. repeaters or optical bus components are used, the maximum permissible jitter is not exceeded.
5.8.1 Equidistant DP cycle operation in the n-set mode

Overview

With the function, the closed-position control loop is closed through PROFIBUS. The position controller is in the DP master, the closed-loop current and speed control as well as the position actual value sensing (encoder interface) are in the DP slave.

The position controller clock cycle is transferred to the DP slaves via the fieldbus, and the slaves synchronize their speed/current controller clock cycle to the position controller clock cycle of the DP master.

The DP master enters the speed setpoint.

The motor encoder or another measuring system can be used for the position actual value sensing in the DP slave.

- Direct measuring system at X412 ----> Encoder 2 (from SW 3.3)
- Additional measuring system at X472 ----> Encoder 3
  TTL encoder, P0890 = 4, only SIMODRIVE 611 universal E

The encoder interface must be configured in the process data.

--> Refer to Chapter 5.6.5

Fig. 5-25 Overview for "motion control with PROFIBUS-DP": Example with DP master and 3 DP slaves
**Time sequence**

The position actual value $x_{\text{act}}$ is read in to the telegram image at time $T_I$ before the start of each DP clock cycle, and is transferred to the DP master at the next DP cycle.

The closed-loop DP master control starts at the time $T_M$ after each position controller clock cycle, and uses the slave actual values which were previously read. The master transfers the calculated setpoints to the telegram image of the slave in the next DP cycle. The speed setpoint $n_{\text{set}}$ is input into the control at instant $T_O$ after the start of the DP cycle.

By minimizing the times $T_O$ and $T_I$ the dead time is also minimized in the higher-level position control loop.

![Diagram of PROFIBUS DP communication cycle](image)

**Fig. 5-26 Example: optimized DP cycle with $T_{\text{MAPC}} = 2 \times T_{\text{DP}}$**

- $T_{\text{MAPC}}$: Master Application Cycle: Position control cycle
- $T_{\text{DP}}$: DP cycle time
- $T_{\text{DX}}$: Data Exchange Time: Sum of the data transfer times of all of the slaves
- $T_M$: Master time: Start of the closed-loop master control
- $T_I$: Input time: Instant in time for the actual value sensing
- $T_O$: Output time: Time of setpoint transfer
- GC: Global Control Telegram (Broadcast Telegram)
- R: Computation time, speed/position controller
- Dx: Slaves: Net data transfer between master and slave 1 - n
- MSG: Acyclic utilities (for example, DP/V1, token passing)
- RES: Reserve: "Active pause" until the isochronous (equidistant) cycle has expired
5.8 Motion Control with PROFIBUS-DP (from SW 3.1)

### Average value generation for \( n_{set} \)

In the "DP slave 611U", the speed setpoint is transferred at instant \( T_0 \) in each \( n \)th DP clock cycle \( (n = T_{MAPC}/T_{DP}) \).

In order to eliminate having to trace the setpoint steps, the speed setpoint can be averaged using an average value filter \( (P1012.8) \).

#### 5.8.2 Equidistant DP cycle operation in the positioning mode

**Overview**

The traversing movements can be simultaneously started for several drives via the clock-synchronous PROFIBUS.

If the traversing blocks have been parameterized the same (travel, velocity, acceleration) in the various drives, then the axes can also move in synchronism.

Traversing blocks are simultaneously started and synchronous movements of the motion profile are realized precisely in the IPO clock cycle.

In this case, position differences only result in different following errors in the axes.

![Diagram of traversing motion](image)

Fig. 5-27 Example: Simultaneously starting the traversing motion

**Note**

For the equidistant DP cycle sequence in the pos mode a setpoint transfer instant \( (T_0) \) of at least 750 \( \mu \)s must be configured (refer to Fig. 5-26). If the configured time is <750 \( \mu \)s then it is possible that either inconsistent or "old" actual values are transferred, e.g. \( X_{istP}, X_{sollP}, dX_{cor} \).
**Timing**

The clock-cycle synchronous PROFIBUS ensures that the IPO clock cycles run in synchronism in all of the axes involved which means that the traversing enable signals are effective at precisely the same time.

The SYNC telegram from the DP master guarantees that the axes start in the same DP clock cycle.

---

**Diagram Description**

- **TMAPC**: Master Application Cycle: Master application clock cycle
- **TD_P**: DP cycle time
- **TD_X**: Data Exchange Time: Sum of the data transfer times of all of the slaves
- **TI**: Input time: Instant in time for the actual value sensing
- **TO**: Output time: Time of setpoint transfer
- **GC**: Global Control Telegram (Broadcast Telegram)
- **Dx**: Slaves: Net data transfer between master and slave 1 – n
- **MSG**: Acyclic utilities (for example, DP/V1, token passing)
- **RES**: Reserve: "Active pause" until the isochronous (equidistant) cycle has expired

---

**Figure 5-28** Example: \( T_{IP0} = 4 \text{ ms} \) and \( T_{DP} = 8 \text{ ms} \)
**General prerequisites:**

- The interpolation clock cycle (P1010) must be parameterized the same for all axes.
- The master application clock cycle $T_{MAPC}$ must be an integer multiple of the interpolation clock cycle.
- $T_I$ and $T_O$ must be the same for all axes.
- $T_{DP}$ must be less than or equal to 16 ms.
- For masters, which cannot generate a master sign of life (e.g. SIMATIC S7), $T_{MAPC}$ must be $T_{DP}$ and the sign-of-life monitoring in operation must be disabled using $P0879.8 = 1$.

**Additional prerequisites for SIMATIC S7:**

- Presently, there is no run level that is in synchronism with DP cycle in S7 user programs. This means, that if axes are to be simultaneously started, in addition to the clock-synchronous PROFIBUS operation, the "classic" SYNC mechanism must be used.

**SYNC mechanism**

--- refer to the documentation of the DP master SIMATIC S7 (SFC 11 "DPSYNC_FR")

The SYNC mechanism may only be activated after the drive has set the status bit ZSW1.9 "control requested".
5.8.3 Times in the equidistant DP cycle

General information

The "DP slave 611U" requires the following time information for equidistant operation, clock cycles and signal processing instants:

Table 5-37  Time settings for "DP slave 611U"

<table>
<thead>
<tr>
<th>Name</th>
<th>Value(^1)</th>
<th>Limit value</th>
<th>Description</th>
</tr>
</thead>
</table>
| T\(\text{BASE}_{\text{DP}}\) | \(5\text{DChex}\) \(\approx 1\text{500}_{\text{dec}}\) | - | Time base for \(T_{\text{DP}}\)
  Calculation: \(T_{\text{BASE}_{\text{DP}}} = 1500 \times T_{\text{Bit}} = 125 \mu\text{s}\)
  \(T_{\text{Bit}} = 1/12 \mu\text{s} \text{ at } 12\text{ Mbaud}\) |
| \(T_{\text{DP}}\) | 8 | \(T_{\text{DP}} \geq T_{\text{DP}_{\text{MIN}}}\)  
  \(T_{\text{DP}_{\text{MIN}}} = 8\) | DP cycle time
  \(T_{\text{DP}} = \text{integer multiple of } T_{\text{BASE}_{\text{DP}}}\)
  Calculation: \(T_{\text{DP}} = 8 \times T_{\text{BASE}_{\text{DP}}} = 1\text{ ms}\)
  Minimum DP cycle time
  Calculation: \(T_{\text{DP}_{\text{MIN}}} = 8 \times T_{\text{BASE}_{\text{DP}}} = 1\text{ ms}\) |
| \(T_{\text{MAPC}}\) | 1  
  \(n = 1 - 14\) | \(n \times T_{\text{DP}}\) | Master application cycle time
  This is the time frame in which the master application generates new setpoints (e.g. in the position controller cycle).
  Calculation: \(T_{\text{MAPC}} = 1 \times T_{\text{DP}} = 1\text{ ms}\) |
| \(T_{\text{BASE}_{\text{IO}}}\) | \(5\text{DChex}\) \(\approx 1\text{500}_{\text{dec}}\) | - | Time base for \(T_{\text{I}, T_{\text{O}}}\)
  Calculation: \(T_{\text{BASE}_{\text{IO}}} = 1500 \times T_{\text{Bit}} = 125 \mu\text{s}\)
  \(T_{\text{Bit}} = 1/12 \mu\text{s} \text{ at } 12\text{ Mbaud}\) |
| \(T_{\text{I}}\) | 2 | \(T_{\text{I}_{\text{MIN}}} \leq T_{\text{I}} < T_{\text{DP}}\)  
  \(T_{\text{I}_{\text{MIN}}} = 1\) | Time of actual value acquisition
  Is the time, where the position actual value is sensed before the start of a DP cycle.
  \(T_{\text{I}} = \text{integer multiple of } T_{\text{BASE}_{\text{IO}}}\)
  Calculation: \(T_{\text{I}} = 2 \times 125 \mu\text{s} = 250 \mu\text{s}\)
  For \(T_{\text{I}} = 0\), the following is valid: \(T_{\text{I}} = T_{\text{DP}}\)
  Minimum \(T_{\text{I}}\)
  Calculation: \(T_{\text{I}_{\text{MIN}}} = 1 \times T_{\text{BASE}_{\text{IO}}} = 125 \mu\text{s}\) |
| \(T_{\text{O}}\) | 4 | \(T_{\text{DX}} + T_{\text{O}_{\text{MIN}}} \leq T_{\text{O}} \leq T_{\text{DP}}\)  
  \(T_{\text{O}_{\text{MIN}}} = 1\) | Time of setpoint transfer
  This is the time that the setpoints (speed setpoint) are transferred to the closed-loop control after the start of DP cycle.
  \(T_{\text{O}} = \text{integer multiple of } T_{\text{BASE}_{\text{IO}}}\)
  Calculation: \(T_{\text{O}} = 4 \times 125 \mu\text{s} = 500 \mu\text{s}\)
  For \(T_{\text{O}} = 0\), the following is valid: \(T_{\text{O}} = T_{\text{DP}}\)
  Minimum time interval between \(T_{\text{O}}\) and \(T_{\text{DX}}\)
  Calculation: \(T_{\text{O}_{\text{MIN}}} = 1 \times T_{\text{BASE}_{\text{IO}}} = 125 \mu\text{s}\) |
### Table 5-37: Time settings for "DP slave 611U", continued

<table>
<thead>
<tr>
<th>Name</th>
<th>Value(^1)</th>
<th>Limit value</th>
<th>Description</th>
</tr>
</thead>
</table>
| T\(_{DX}\) | E\(_{10\text{hex}}\) \(\pm\) 3600\(_{\text{dec}}\) | T\(_{DX}\) < T\(_{DP}\) | Data exchange time  
This is the time which is required to transfer, within one DP cycle, the process data to all of the slaves.  
T\(_{DX}\) = integer multiple of T\(_{\text{Bit}}\)  
T\(_{\text{Bit}}\) = 1/12 \(\mu\)s at 12 Mbaud  
Calculation: T\(_{DX}\) = 3600 \(\times\) T\(_{\text{Bit}}\) = 300 \(\mu\)s |
| T\(_{PLL\_W}\) | 0                       | -           | PLL window  
(half the window width of the GC synchronizing window)  
The following applies to the setting:  
- Small window \(\rightarrow\) minimization of synchronization fluctuations on the drive  
- Large window \(\rightarrow\) larger tolerance with respect to GC fluctuations  
Calculation (assumption: T\(_{PLL\_W}\) = A\(_{\text{Hex}}\) \(\approx\) 10\(_{\text{Dec}}\))  
T\(_{PLL\_W}\) = 10 \(\times\) T\(_{\text{Bit}}\) = 0.833 \(\mu\)s  
T\(_{\text{Bit}}\) = 1/12 \(\mu\)s at 12 Mbaud  
Recommendation: Set T\(_{PLL\_W}\) to 0 (standard value)  
\(\rightarrow\) the "DP slave 611U" then automatically uses the standard value of 0.81 \(\mu\)s |
| T\(_{PLL\_D}\) | 0                       | -           | PLL dead time  
The PLL deadtime can be used to compensate for different data transfer times to the slaves (e.g. due to the use of repeaters).  
The slaves with faster transfer times are delayed by a corresponding PLL dead time.  
Calculation: T\(_{PLL\_D}\) = 0 \(\times\) T\(_{\text{Bit}}\) = 0 \(\mu\)s  
T\(_{\text{Bit}}\) = 1/12 \(\mu\)s at 12 Mbaud |

\(^1\) The values correspond to the master device file SIEM808F.GSD
5.8 Motion Control with PROFIBUS-DP (from SW 3.1)

Setting criteria

The following criteria must be taken into account when setting the times:

- **DP cycle (T\textsubscript{DP})**
  - Time T\textsubscript{DP} must be set the same for all bus nodes.
  - The following must be valid: T\textsubscript{DP} > T\textsubscript{DX} and T\textsubscript{DP} \geq T\textsubscript{O}
    - Time T\textsubscript{DP} is therefore long enough to permit communications with all of the bus nodes.
  - Specific reserves must be available
    - This means that additional masters can be connected and non-cyclic communications can be realized.

- **T\textsubscript{I} and T\textsubscript{O}**
  - n-set mode: Setting the times in T\textsubscript{I} and T\textsubscript{O} as short as possible reduces the dead time in the position control loop.
  - The following must be valid: T\textsubscript{O} > T\textsubscript{DX} + T\textsubscript{Omin}

- The following is valid for interpolating axes:
  - T\textsubscript{I} of the interpolating axes should be the same
  - T\textsubscript{O} of the interpolating axes should be the same

5.8.4 Bus run-up, synchronization and net data save

Bus run-up and synchronization

When running-up, the DP master checks the DP slave by requesting diagnostic information.

The following faults/errors are identified:

- Parameterizing and configuring errors
- The DP slave has been assigned to another master
- Static user diagnostics
- Operational readiness of the DP slave

If a fault has not been detected, then the DP master, with this DP slave, goes into cyclic net data operation, i.e. input and output data are exchanged.

With the transition into cyclic net data transfer, the DP slave is synchronized to the master sign-of-life.

The DP slave runs in synchronism with the master, if

- The status signal ZSW1.9 (control requested/no control possible) = "1"
  and
- The slave sign-of-life (ZSW2.12 to ZSW2.15, value = 1 to 15) is counted
Net data save

The net data save is realized in both data transfer directions (master <-> slave) using a sign-of-life that comprises a 4-bit counter. The sign-of-life counter is always incremented from 1 to 15, and then starts again with the value 1.

- **Master sign-of-life (M-SoL)**
  - The control signals STW2.12 to STW2.15 are used as master sign-of-life.
  - The master sign-of-life counter is incremented in each master application cycle (TMAPC).
  - P0879.2 to .0 Permissible sign-of-life error
  - P0879.8 Operation with/without Master sign-of-life monitoring
  - Monitoring
    - The master sign-of-life is monitored in the DP slave. If the master sign-of-life does not consecutively correspond to the expected value or more often than is permitted in P0879 bit 2 to bit 0, then the following occurs:
      - --> fault 597 (PROFIBUS: synchronization error) is output
      - --> zero is output as slave sign-of-life
      - --> the status signal ZSW1.9 (control requested/control not possible) is set to "0"
      - --> the system re-synchronizes to the master sign-of-life

- **Slave sign-of-life (S-SoL)**
  - The status signals ZSW2.12 to ZSW2.15 are used as slave sign-of-life.
  - The slave sign-of-life counter is incremented in every DP cycle (TDP).
### 5.8.5 Parameterization using the parameterizing telegram

For parameterization, the "DP slave 611U" is supplied with the following equidistant parameters within a parameterizing telegram (Set_Prm):

<table>
<thead>
<tr>
<th>Byte</th>
<th>Parameter</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Parameter header</td>
</tr>
<tr>
<td>1-12</td>
<td>Standard DP parameters</td>
</tr>
<tr>
<td>13-25</td>
<td>DP/V1 parameters</td>
</tr>
</tbody>
</table>

#### State 1
- Bit 6: Fail_safe

#### State 3
- Bit 3: PRM_Structure
- Bit 4: IsoM_Req

**Block length, incl. header**

**ID isochronous**
- \( \text{E1}_{\text{hex}} \) no PROFIBUS standard
- \( \text{04}_{\text{hex}} \) PROFIBUS standard

**Isochron_Mode_Supported**
- \( \text{00}_{\text{hex}} \) not isochronous
- \( \text{01}_{\text{hex}} \) isochronous
- \( \text{E1}_{\text{hex}} \) isochronous

**5DC_{\text{hex}} = 1500_{\text{dec}}**
- \( T_{\text{BASE}} = 1500 \cdot 1/12 \mu s = 125 \mu s \)
- \( T_{\text{DP}} = 8 \cdot T_{\text{BASE}} = 1 \text{ ms} \)
- \( T_{\text{MAPC}} = 1 \cdot T_{\text{DP}} = 1 \text{ ms} \)
- \( T_{\text{BASE}, \text{IO}} = 1500 \cdot 1/12 \mu s = 125 \mu s \)

**T_{\text{I}} = 2 \cdot T_{\text{BASE}, \text{IO}} = 250 \mu s**

**T_{\text{O}} = 4 \cdot T_{\text{BASE}, \text{IO}} = 500 \mu s**

**E1_{\text{hex}} = 3600_{\text{dec}}**
- \( T_{\text{DX}} = 3600 \cdot 1/12 \mu s = 300 \mu s \)
- \( T_{\text{PLL}, \text{W}} = 0 \)
- \( T_{\text{PLL}, \text{D}} = 0 \mu s \)

**Note:**

- P1783:64 is used for diagnostics, parameterizing data.
- P1783:0 No. of valid bytes
- P1783:1 1st byte of the received parameterizing data, etc.

*Fig. 5-29 Parameterizing telegram Set_Prm*
5.9 Parameter overview of PROFIBUS-DP

The following parameters are available for PROFIBUS-DP:

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Std.</th>
<th>Max.</th>
<th>Unit</th>
<th>Effec-</th>
<th>RO</th>
</tr>
</thead>
<tbody>
<tr>
<td>0872</td>
<td>Optional module type</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... indicates which optional module was identified when the control board was powered-up.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0</td>
<td>No option module</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
<td></td>
</tr>
<tr>
<td>1</td>
<td>Optional TERMINAL module, Order No. (MLFB): 6SN1114-0NA00-0AA0</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>Optional PROFIBUS-DP1 module with PROFIBUS-ASIC SPC3, Order No. (MLFB): 6SN1114-0NB00-0AA0</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>3</td>
<td>Optional PROFIBUS-DP2 module (from SW 3.1) with PROFIBUS-ASIC DPC31 without PLL, Order No. (MLFB): 6SN1114-0NB00-0AA1/-0AA2</td>
<td></td>
<td></td>
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<td></td>
</tr>
<tr>
<td>4</td>
<td>Optional PROFIBUS-DP3 module (from SW 3.1) with PROFIBUS-ASIC DPC31 with PLL, Order No. (MLFB): 6SN1114-0NB01-0AA0/-0AA1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0873</td>
<td>Option module version</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... displays the version of the particular option module.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0875</td>
<td>Expected optional module type</td>
<td>0</td>
<td>0</td>
<td>4</td>
<td>-</td>
<td>PO</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... indicates which option module was expected as a result of the parameterization.</td>
<td></td>
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</tr>
<tr>
<td></td>
<td>The parameters are automatically set at the first start-up corresponding to P0872 (option module type).</td>
<td></td>
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</tr>
<tr>
<td></td>
<td>Examples:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• P0875 = P0872</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>--&gt; normal situation after first commissioning</td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>--&gt; no error is signaled when booting</td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>• P0875 = 3 and P0872 = 0</td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>--&gt; the optional PROFIBUS-DP2 module has been parameterized but was not detected</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>--&gt; a fault was signaled when the system ran up</td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>Note: Switch-out the communications or the &quot;DP slaves 611U&quot; when the module is inserted:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• 1-axis module</td>
<td></td>
<td></td>
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<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>--&gt; the &quot;DP slave 611U&quot; is switched-out from drive A with P0875 = 0</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• 2-axis module</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>--&gt; with P0875 = 0, the communications with drive B is switched-out from drive B</td>
<td></td>
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</tr>
<tr>
<td></td>
<td>--&gt; with P0875 = 0 in both drives, the &quot;DP slave 611U&quot; is switched-out</td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>This means, that e.g. &quot;disturbing&quot; slaves can be temporarily disabled when commissioning the other nodes (refer under the index entry &quot;Start-up PROFIBUS-DP&quot;).</td>
<td></td>
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<tr>
<td></td>
<td>After disabling the communications or the module, P0875 must be again set to P0872.</td>
<td></td>
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</tr>
</tbody>
</table>
### 5.9 Parameter overview of PROFIBUS-DP

#### Table 5-38 Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective Unit</th>
<th>PO</th>
</tr>
</thead>
<tbody>
<tr>
<td>0879</td>
<td>PROFIBUS configuration (from SW 3.1)</td>
<td>0</td>
<td>1</td>
<td>FFFF</td>
<td>Hex</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 2, 1, 0 Permissible sign-of-life error</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 8 Operation with/without master sign-of-life monitoring</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 11 PKW area: Sub-index in the high/low byte of IND (from SW 3.3)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 12 Activates the direct measuring system (encoder 2) for the encoder interface (from SW 3.3)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 13 Incremental motor measuring system with/without equivalent zero mark</td>
<td></td>
<td></td>
<td></td>
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<td></td>
</tr>
<tr>
<td></td>
<td>Bit 14 Incremental, direct meas. system with/without equivalent zero mark (from SW 3.3)</td>
<td></td>
<td></td>
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<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0880</td>
<td>Speed evaluation PROFIBUS (SRM, ARM)</td>
<td>0.0</td>
<td>16384.0</td>
<td>100000.0</td>
<td>RPM m/min</td>
<td>immediately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Motor velocity evaluation PROFIBUS (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the normalization of the speed or velocity when using PROFIBUS-DP.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>4000Hex or 16384Dec = of the speed or velocity in P0880</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0881</td>
<td>Evaluation, torque/power reduction PROFIBUS (SRM, ARM)</td>
<td>0.0</td>
<td>16384.0</td>
<td>16384.0</td>
<td>%</td>
<td>immediately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Evaluation, force/power reduction PROFIBUS (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
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<td></td>
</tr>
<tr>
<td></td>
<td>... defines the normalization of the torque/power reduction or force/power reduction when using PROFIBUS-DP.</td>
<td></td>
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<td></td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
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<td></td>
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<td></td>
</tr>
<tr>
<td></td>
<td>4000 hex or 16384 dec in the control word MomRed corresponds to a reduction by the percentage specified in P0881.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0882</td>
<td>Torque setpoint evaluation PROFIBUS (SRM, ARM)</td>
<td>-16384.0</td>
<td>800.0</td>
<td>16384.0</td>
<td>%</td>
<td>immediately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Force setpoint evaluation PROFIBUS (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the normalization of the torque or force setpoint when entered via PROFIBUS-DP.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
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<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0882 is a percentage value referred to the rated motor torque. The parameter acts on the process data MsollExt (torque setpoint external in the input direction) and Msoll (torque setpoint in the output direction).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>4000 hex or 16384 dec in the control word corresponds to the percentage entered into P0882.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0883</td>
<td>Override evaluation, PROFIBUS (from SW 3.1)</td>
<td>0.0</td>
<td>16384.0</td>
<td>16384.0</td>
<td>%</td>
<td>immediately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the normalization of the override when entered via PROFIBUS DP.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>4000Hex or 16384Dec = the override in P0883</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0884</td>
<td>PROFIBUS position output evaluation number of increments</td>
<td>1</td>
<td>2048</td>
<td>8388607</td>
<td>-</td>
<td>PO</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the normalization of the override when entered via PROFIBUS.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>4000Hex or 16384Dec = the override in P0883</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 5-38  Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0888:16</td>
<td>Function, distributed input (PROFIBUS)</td>
<td>0</td>
<td>0</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>
|           | ... defines which function a signal has which was read in via the PROFIBUS-PZD for distributed inputs (DezEing).
|           | The function number from the "list of input signals" is entered. The following applies for the individual indices of P0888:
|           | :0 Function DezEing bit 0
|           | :1 Function DezEing bit 1
|           | :2 etc.                                          |

| 0891      | Source, external position reference value       | -1   | -1       | 4    | -    | PO        |
|          | ... defines the source for the external position reference value.
|          | - 1 No external position reference value
|          | 0 Angular incremental encoder interface
|          | 1 Motor encoder, drive A (only drive B in double-axis modules)
|          | (only for compatibility, recommended value = 2)
|          | 2 Pos. act. value drive A (only drive B in double-axis modules, from SW 4.1)
|          | 3 Pos. ref. value, drive A (only drive B in double-axis modules, from SW 4.1)
|          | 4 PROFIBUS-DP (from SW 4.1)                      |

| 0895      | External position reference value - number of increments | 1    | 2048     | 8388607 | -    | PO        |
|          | ... defines, together with P0896 for couplings, the ratio between input increments and the dimension system grids.
|          | **Note:**
|          | -> P0895 input pulses at the angular incremental encoder correspond to P0896 MSR
|          | -> Setpoint input from P0895 corresponds to P0896 MSR refer to P0896 |

| 0896      | External position reference value - number of dimension system grids | 1    | 10000    | 8388607 | MSC  | PO        |
|          | ... defines, together with P0895, for couplings, the ratio between the input pulse periods (or input bit) and the dimension system grids. |

| 0915      | PZD setpoint assignment, PROFIBUS (from SW 3.1) | 0    | 0        | 65 535 | -    | immediately |
|          | ... is used to assign the signals to the process data in the setpoint telegram.
|          | -> Refer to Chapter 5.6.5 |

| 0916      | PZD actual value assignment, PROFIBUS (from SW 3.1) | 0    | 0        | 65 535 | -    | immediately |
|          | ... is used to assign the signals to the process data in the actual value telegram.
|          | -> Refer to Chapter 5.6.5 |
Table 5-38 Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0918</td>
<td>PROFIBUS node address</td>
<td>0</td>
<td>0</td>
<td>126</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>... specifies the address of the drives as DP slave on PROFIBUS.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• There is <strong>one</strong> node address for the control board, although it is designed for two drives.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• When changing the parameter in one drive, the parameter in the other drive is automatically adapted.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• Every node connected to PROFIBUS must have a unique address.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0922</td>
<td>Telegram selection PROFIBUS (from SW 3.1)</td>
<td>0</td>
<td>101</td>
<td>104</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>... is used to set the free configurability or to select a standard telegram.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>-- &gt; Refer to Chapter 5.6.5</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0945:65</td>
<td>Fault code</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... the fault code, i.e. the number of the fault which occurred, is entered. The faults which occurred, are entered as follows into the fault buffer:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- first fault which occurred -- &gt; parameter with index 1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- eight faults which occurred -- &gt; parameter with index 8</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The following belongs to a fault:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Fault code (P0945:65), fault number (P0947:65), fault time (P0948:65) and fault value (P0949:65)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• A description of the faults, the way in which they can be acknowledged as well as a list of all the faults, is provided in Chapter 7.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• This parameter is reset at POWER ON.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0947:65</td>
<td>Fault number</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>This parameter is of no significance.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0948:65</td>
<td>Fault time</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>ms</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>This parameter specifies at which relative system time, the fault occurred.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>This parameter is set to zero at POWER ON, and the time is then started.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0949:65</td>
<td>F value</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>The supplementary information associated with a fault which occurred, is entered in this parameter.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• A description of the faults, the way in which they can be acknowledged as well as a list of all the faults, is provided in Chapter 7.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• This parameter is reset at POWER ON.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 5-38  Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0952</td>
<td>Number of faults</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>The parameter specifies the faults which occurred after POWER ON an. Note: This parameter is reset at POWER ON.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0953</td>
<td>Warnings 800 – 815</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0954</td>
<td>Warnings 816 – 831</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0955</td>
<td>Warnings 832 – 847</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0956</td>
<td>Warnings 848 – 863</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0957</td>
<td>Warnings 864 – 879</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0958</td>
<td>Warnings 880 – 895</td>
<td>-</td>
<td>-</td>
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<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0959</td>
<td>Warnings 896 – 911</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>0960</td>
<td>Warnings 912 – 927</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates which warning(s) is(are) present.
Bit x = 1  warning yyy present
Bit x = 0  a warning is not present

**Example:**
P0955 = 0110  --> bits 8 and 4 are set  --> warnings 840 and 836 are present

<table>
<thead>
<tr>
<th>Parameter</th>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>9</th>
<th>8</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
<th>Bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0953</td>
<td>815</td>
<td>814</td>
<td>813</td>
<td>812</td>
<td>811</td>
<td>810</td>
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</tr>
<tr>
<td>P0954</td>
<td>831</td>
<td>830</td>
<td>829</td>
<td>828</td>
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<td>826</td>
<td>825</td>
<td>824</td>
<td>823</td>
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<td>820</td>
<td>819</td>
<td>818</td>
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<td></td>
</tr>
<tr>
<td>P0955</td>
<td>847</td>
<td>846</td>
<td>845</td>
<td>844</td>
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<td>842</td>
<td>841</td>
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<td>838</td>
<td>837</td>
<td>836</td>
<td>835</td>
<td>834</td>
<td>833</td>
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<td>P0956</td>
<td>863</td>
<td>862</td>
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<td>850</td>
<td>849</td>
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</tr>
<tr>
<td>P0957</td>
<td>879</td>
<td>878</td>
<td>877</td>
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<td>867</td>
<td>866</td>
<td>865</td>
<td>864</td>
<td></td>
</tr>
<tr>
<td>P0958</td>
<td>895</td>
<td>894</td>
<td>893</td>
<td>892</td>
<td>891</td>
<td>890</td>
<td>889</td>
<td>888</td>
<td>887</td>
<td>886</td>
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<td>882</td>
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<tr>
<td>P0959</td>
<td>911</td>
<td>910</td>
<td>909</td>
<td>908</td>
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<td>900</td>
<td>899</td>
<td>898</td>
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</tr>
<tr>
<td>P0960</td>
<td>927</td>
<td>926</td>
<td>925</td>
<td>924</td>
<td>923</td>
<td>922</td>
<td>921</td>
<td>920</td>
<td>919</td>
<td>918</td>
<td>917</td>
<td>916</td>
<td>915</td>
<td>914</td>
<td>913</td>
<td>912</td>
<td></td>
</tr>
</tbody>
</table>

0963 (from SW 4.1) Baud rate PROFIBUS

... contains the actual baud rate of the PROFIBUS.

0 9.6 kbit/s
1 19.2 kbit/s
2 93.75 kbit/s
3 187.5 kbit/s
4 500 kbit/s
6 1500 kbit/s
7 3000 kbit/s
8 6000 bit/s
9 12000 bit/s
10 31.25 kbit/s
11 45.45 kbit/s
### Table 5-38 Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0967</td>
<td>PROFIBUS control word</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... is the image of control word STW1.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The bit assignment can be found as follows:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>under the index entry &quot;Process data in the n-set mode - control words - STW1&quot;</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>under the index entry &quot;Process data in the pos mode - control words - STW1&quot; (from SW 2.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>under the index entry &quot;Process data in the x-set mode - control words - STW1&quot; (from SW 3.3)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0968</td>
<td>PROFIBUS status word</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... is the image of status word ZSW1.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The bit assignment can be found as follows:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>under the index entry &quot;Process data in the n-set mode - status words - ZSW1&quot;</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>under the index entry &quot;Process data in the pos mode - status words - ZSW1&quot; (from SW 2.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>under the index entry &quot;Process data in the x-set mode - status words - ZSW1&quot; (from SW 3.3)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0969</td>
<td>Actual time difference</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>ms</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... contains the relative system time since the last time that the drive was powered-up or since the last counter overflow</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1781:17 (from SW 4.1)</td>
<td>Setpoint source, PROFIBUS process data</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... indicates the source of the process data received via PROFIBUS</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The high byte includes a reference to the source device (0xFF for the master, DP address for a Publisher) and the lower byte includes the offset within the received telegram (counted in bytes starting with 1).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The following applies:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1781:0</td>
<td>Number of valid entries</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1781:1</td>
<td>Source of process data 1 (STW1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1781:2</td>
<td>Source of process data 2 (PZD2), etc.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1782:17 (from SW 4.1)</td>
<td>Target offset, PROFIBUS process data</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... indicates which offset process data, sent to the master or the subscribers via PROFIBUS, have in the sent telegram (counted in bytes starting with 1).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The following applies:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1782:0</td>
<td>Number of valid entries</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1782:1</td>
<td>Target offset of process data 1 (ZSW1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1782:2</td>
<td>Target offset of process data 2 (PZD2), etc.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 5-38 Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1783:64</td>
<td>Received parameterizing data PROFIBUS (from SW 3.1)</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>1784:64</td>
<td>Received configuration data PROFIBUS (from SW 3.1)</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
</tbody>
</table>

P1783:64 ... is an image of the parameterizing data received from the DP slave (refer to Chapter 5.8.5).
P1784:64 ... is an image of the configuration data received from the DP slave (refer to Chapter 5.7.1).

<table>
<thead>
<tr>
<th>Index</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>:0</td>
<td>Error master sign-of-life since POWER ON</td>
</tr>
<tr>
<td>:1</td>
<td>Clock-cycle synchronous operation selected</td>
</tr>
<tr>
<td>:2</td>
<td>Interpolation clock cycle (Tipo) in us</td>
</tr>
<tr>
<td>:3</td>
<td>Position controller clock cycle (Tlr) in us</td>
</tr>
<tr>
<td>:4</td>
<td>Master application cycle type (Tmapc) in us</td>
</tr>
<tr>
<td>:5</td>
<td>DP cycle time (Tdpc) in us</td>
</tr>
<tr>
<td>:6</td>
<td>Data exchange time (Tdx) in us</td>
</tr>
<tr>
<td>:7</td>
<td>Instant in time of the setpoint sensing (To) in us</td>
</tr>
<tr>
<td>:8</td>
<td>Instant in time of the actual value sensing (Ti) in us</td>
</tr>
<tr>
<td>:9</td>
<td>PLL window (Tpllw) in 1/12us</td>
</tr>
<tr>
<td>:10</td>
<td>PLL delay time (Tplld) in 1/12us</td>
</tr>
<tr>
<td>:11</td>
<td>External slave-to-slave communication connections</td>
</tr>
<tr>
<td>:12</td>
<td>Internal slave-to-slave communication connections</td>
</tr>
</tbody>
</table>

= 0 -> Neither parameterizing nor configuration data available
### Table 5-38 Parameters for PROFIBUS-DP, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1786:5</td>
<td>Received PKW data, PROFIBUS (from SW 2.4)</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
<tr>
<td>1787:5</td>
<td>Sent PKW data, PROFIBUS    (from SW 2.4)</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>RO</td>
</tr>
</tbody>
</table>

P1786:5 ... is an image of the PKW data received from the DP slave.
P1787:5 ... is an image of the PKW data sent to the DP master.

<table>
<thead>
<tr>
<th>Index</th>
<th>:0</th>
<th>:1</th>
<th>:2</th>
<th>:3</th>
<th>:4</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of valid words</td>
<td>PKE</td>
<td>IND</td>
<td>PWE</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Image of the PKW data</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Index</th>
<th>:0</th>
<th>:1</th>
<th>:2</th>
<th>:3</th>
<th>...</th>
<th>:14</th>
<th>:15</th>
<th>:16</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of valid words</td>
<td>PZD 1</td>
<td>PZD 2</td>
<td>PZD 3</td>
<td>...</td>
<td>PZD 14</td>
<td>PZD 15</td>
<td>PZD 16</td>
<td></td>
</tr>
<tr>
<td>Image of the process data (PZD)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**

- The parameter range (PKW range) is described in Chapter 5.6.7.

1788:17 Received process data PROFIBUS - - - Hex RO
1789:17 Sent process data PROFIBUS - - - Hex RO

P1788:17 ... is an image of the process data received from the DP slave (control words).
P1789:17 ... is an image of the process data sent to the DP master (status words).

**Note:**

- The number of valid words in P1788:0 and P1789:0 depends on the selected PPO type.
- Invalid words (are contained in parameters with an index greater than the number) have the value 0.
- Example:
  - P1788:0 = 2 2 words are valid, i.e. it involves either a PPO1 or PPO3 P1788:1 contains the process data 1 (PZD1) P1788:2 contains the process data 2 (PZD2) P1788:3 to P1788:10 have the value 0
- An overview of the process data in the speed-controlled mode and in the positioning mode is included in Chapter 5.6.1.
5.9 Parameter overview of PROFIBUS-DP

Additional parameters relevant for PROFIBUS-DP (refer to Chapter A.1)

- P0600 Operating display
- P0607 Analog setpoint, terminal 56.x/14.x
- P0612 Analog setpoint, terminal 24.x/20.x
- P0653 Image, input signals, Part 1
- P0654 Image, input signals, Part 2
- P0656 Image, output signals, Part 1
- P0657 Image, output signals, Part 2
- P0658 Image, output signals, Part 3
- P0660 Function, input terminal I0.x
- P0661 Function, input terminal I1.x
- P0662 Function, input terminal I2.x
- P0663 Function, input terminal I3.x
- P0680 Function, output terminal O0.x
- P0681 Function, output terminal O1.x
- P0682 Function, output terminal O2.x
- P0683 Function, output terminal O3.x
- P0972 Request POWER-ON RESET (from SW 3.3)
- P1012.2 Function switch
  Bit 2 "Ready or no fault"
- P1012.12 Function switch
  Bit 12 "power-on inhibit"
- P1795 Optional module (PROFIBUS): Firmware version
5.10 Slave-to-slave communications (from SW 4.1)

5.10.1 General information

Description

For PROFIBUS-DP, the master addresses all of the slaves one after
the other in a DP cycle. In this case, the master transfers its output
data (setpoints) to the particular slave and receives as response the
input data (actual values).

Fast, distributed data transfer between drives (slaves) is possible using
the "slave-to-slave" communications function without involving the
master.

The following terms are used for the functions described here:

- Slave-to-slave communications
- Data exchange broadcast (DXB.req)
- Slave-to-slave communications (is used in the following)

Publisher

For the "slave-to-slave communications" function, at least one slave
must accept the role of publisher.

The master addresses the publisher, when transferring the output data,
with a modified Layer 2 function code (DXB.req). The publisher then
sends its input data to the master with a broadcast telegram to all bus
nodes.
Subscriber

The subscribers evaluate the broadcast telegrams, sent from the publishers, and use the data which has been received as setpoints.

The setpoints are used, in addition to the setpoints received from the master, corresponding to the configured telegram structure (P0915:17).

Links and taps

The links configured in the subscriber (connection to publisher) contain the following information:

- From which publishers may input data be received?
- Which input data is there?
- Which location should the input data be used as setpoints?

Several taps are possible within a link. Several input data or input data areas, which are not associated with one another, can be used as setpoint via a tap.

Links are possible to the device itself. This means, e.g. that for a two-axis module, data can be transferred from drive A to B. This internal link corresponds, as far as the timing is concerned, to a link via PROFIBUS.

Requirements and boundary conditions

The following limitations should be observed for the "slave-to-slave" communications function:

- Drive ES Basic V5.1 SP1
- Optional PROFIBUS-DP2 module \( \geq \) SW 4.1
- Optional PROFIBUS-DP3 module \( \geq \) SW 4.1
- SIMODRIVE 611 universal \( \geq \) SW 4.1
- Number of process data max. of 16 per drive
- Number of links to publishers max. 3 and 1 internal
- Number of taps per link max. 8

Applications

For example, the following applications can be implemented using the "slave-to-slave communications" function:

- Axis couplings (this is practical for clock cycle synchronous operation) (refer to Chapter 6.3)
  - Angular synchronism where the position reference value or position actual value is entered
  - Torque setpoint coupling (master/slave operation)
    Master drive \( \leftarrow \rightarrow \) Slave drive
    Closed-loop speed controlled \( \rightarrow \rightarrow \) Open-loop torque controlled

- Entering digital input signals from another slave (refer to Chapter 5.10.4)
### Parameter overview (refer to Chapter A.1)

The following parameters are available for the "slave-to-slave communications" function:

- **P0032** External position reference value
- **P0400** Reference point coordinate, master drive
- **P0401** Coupling factor, revolutions master drive
- **P0402** Coupling factor, revolutions slave drive
- **P0410** Configuration, coupling that can be switched-in
- **P0412** Synchronous offset position
- **P0413** Offset, synchronous velocity
- **P0420** Position difference, measuring probe to the zero point, slave drive
- **P0425:16** Coupling positions
- **P0879** PROFIBUS configuration
- **P0882** Evaluation, torque setpoint PROFIBUS
- **P0884** PROFIBUS position output evaluation
  Number of increments
- **P0888** Function, distributed inputs (PROFIBUS)
- **P0891** Source, external position reference value
- **P0895** External position reference value - No. of increments
- **P0896** Ext. position reference value - No. of dimension system grids
- **P0897** Inversion, external position reference value
- **P0898** Modulo range, master drive
- **P1781:17** Setpoint source, PROFIBUS process data
- **P1782:17** Target offset, PROFIBUS process data
- **P1785:13** Extended PROFIBUS diagnostics

### Input/output signals (refer to Chapter 5.6)

The following signals are available for the "slave-to-slave communications" function:

- **Input signals**
  - "Correction, external position reference value via dXcor (from SW 4.1)"
    --> via the PROFIBUS control signal "QStw.0"
  - "Request passive referencing (from SW 5.1)"
    --> via the PROFIBUS control signal QStw.1 or STW1.15"

- **Output signals**
  - "Correction, external position reference value via dXcor (from SW 4.1)"
    --> via PROFIBUS control signal "QZsw.0"
  - "Request passive referencing (from SW 5.1)"
    --> via the PROFIBUS control signal QZsw.1 or ZSW1.15"
5.10.2 Setpoint assignment in the subscriber

Setpoints

The following statements can be made about the setpoint/reference values:

- Number of setpoint
  When bus communications is being established, the master signals the slave the number of setpoints (process data) to be transferred e.g. using the STEP 7 HW-Config configuring tool.

- Contents of the setpoints
  The structure and contents of the data are defined for the "DP slave 611U" using the local process data configuring (P0915, P0922).

- Operation as "standard" DP slave
  The drive (slave) only receives its setpoints and output data from the DP master.

- Operation as subscriber
  When operating a slave subscriber, some of the setpoints are entered from one or several publishers instead of from the master.
  The slave is signaled the assignment when bus communications are being established, using the parameterizing and configuring telegram.

Example, setpoint assignment

The slave in Fig. 5-31 receives its process data as follows:

- STW1 and STW2 from the master
- NSET_B and MomRed as tap from a publisher

![Setpoint assignment diagram](image-url)
5.10 Slave-to-slave communications (from SW 4.1)

5.10.3 Activating/parameterizing slave-to-slave communications

The activation of the function "slave-to-slave communication" must be activated in the subscribers.

**Activation in the publisher**

By configuring the links with Drive ES Basic, the master can identify which slaves are to be addressed as publisher with a modified layer 2 function code (DDB—Distributed Data Base). The publisher then does not send its input data to the master, but to all bus nodes as broadcast telegram.

**Activation in the subscriber**

The slave, which is to be used as subscriber, requires a filter table. The slave must know which setpoints are received from the master and which are received from a publisher.

The filter table contains the following information:

- From which publisher is data to be retrieved?
- The length of the publisher input data (test purposes)?
- From which position (offset) in the input data is data to be taken?
- How much data is to be taken?
- To which position in the setpoints is the data, which has been taken, to be copied?

**Parameterizing telegram (SetPrm)**

The filter table is transferred, as dedicated block from the master to the slave with the parameterizing telegram when bus communications are established.

If: The block for the filter table is not available or element "number of links" = 0

Then: -- > no subscriber functionality

The precise structure of this block, together with the permissible setting values is shown in Fig. 5-32.

**Configuration telegram (ChkCfg)**

Using the configuration telegram, a slave knows how many setpoints are to be received from the master and how many actual values are to be sent to the master.

For slave-to-slave communications, a special empty ID is required for each data access, which is then transferred with the ChkCfg.

Structure of the empty ID for Drive ES Basic (S7 ID format):

\[ \text{0x04 0x00 0x00 0xD3 0x40} \]
### Filter Table (Block Table)

<table>
<thead>
<tr>
<th>Field</th>
<th>Content</th>
</tr>
</thead>
<tbody>
<tr>
<td>Block header</td>
<td>Block-Len 12 - 244</td>
</tr>
<tr>
<td>Command</td>
<td>0xE2</td>
</tr>
<tr>
<td>Slot</td>
<td>0x00</td>
</tr>
<tr>
<td>Specifier</td>
<td>0x00</td>
</tr>
<tr>
<td>Version ID</td>
<td>0xE2</td>
</tr>
<tr>
<td>Number of links</td>
<td>0 - 3</td>
</tr>
<tr>
<td>Offset Link 1</td>
<td></td>
</tr>
<tr>
<td>...</td>
<td></td>
</tr>
<tr>
<td>Offset Link n</td>
<td></td>
</tr>
<tr>
<td>Link 1</td>
<td>Publisher DP address</td>
</tr>
<tr>
<td>Tap 1</td>
<td>Publisher input length</td>
</tr>
<tr>
<td>Tap 2</td>
<td>Offset in the publisher data</td>
</tr>
<tr>
<td>Link 2</td>
<td>Target offset in the subscriber</td>
</tr>
<tr>
<td>Tap 2</td>
<td>Length of the data access</td>
</tr>
<tr>
<td>...</td>
<td></td>
</tr>
<tr>
<td>Link 2</td>
<td>Publisher DP address</td>
</tr>
<tr>
<td>...</td>
<td></td>
</tr>
</tbody>
</table>

1) Data in bytes  
2) Calculated from the version ID

---

**Fig. 5-32** Filter block in the parameterizing telegram (SetPrm)
5.10.4 Message format

Configuring a telegram

In order to be able to use the process data for slave-to-slave communications, the appropriate signal IDs must be entered into P0915 and P0916 for the telegram configuration.

Synchronous operation

For synchronous operation, where position reference values or actual values are entered for the axis couplings (refer to Chapter 6.3), the following process data is required for data transfer via PROFIBUS-DP:

- Signals for synchronous operation in the actual value direction (publisher)
  - Position actual value --> Signal ID 50206
  - Position reference value --> Signal ID 50208
  - Correction, position reference value --> Signal ID 50210
  - Status word, slave-to-slave comm. --> Signal ID 50118

- Signals for synchronous operation in the setpoint direction (subscriber)
  - External position reference value --> Signal ID 50207
  - Correction, ext. position ref. value --> Signal ID 50209
  - Control word, slave-to-slave comm. --> Signal ID 50117

For a description of this process data, refer to Chapter 5.6.

Example, synchronous operation

An example of a synchronous application, from the perspective of the slave drive, is shown in Fig. 5-33. Most of the control words are entered from the PROFIBUS-DP master; whereas, the actual setpoints/reference values are sent from a "SIMODRIVE 611 universal" as master drive.

![Diagram of process data](image-url)
Distributed input signals

When distributed input signals are read in, a "SIMODRIVE 611 universal" can directly read in control signals from another slave (publisher) without the signals first having to be routed via the master.

Either an input module, which is capable of slave-to-slave communications (e.g. ET200) can be used as publisher, or another drive, whose status signals can be used as control signals.

The following process data is required for the telegram configuring to read in these input signals:

Distributed inputs ---> Signal ID 50111

For a description of the process data, refer to Chapter 5.6.

The individual bits in the process data must be assigned functions using parameter P0888. The same function IDs are used as when parameterizing the input terminals via P0660 to P0671 (function numbers from the "List of input signals", refer to Chapter 6.4.2).

Using this function assignment, signal sources can be mixed. The following hierarchy applies (1. = highest priority):

1. The signal comes from the local digital input on the "SIMODRIVE 611 universal" hardware.
2. The signal comes from a publisher via the process data "DezEing".
3. Signal comes from the PROFIBUS master via "STW1", "STW2", etc.

Example, mixed operation

For the example from Fig. 5-34, all setpoints, with the exception of the hardware limit switch, are entered from the PROFIBUS-DP master.

The hardware limit switches are read in via an ET200 module and entered into the process data "DezEing" (bit 0 and bit1).

In this case, it is necessary that the appropriate telegram is configured using P0915:17 and P0888:16 is assigned the function numbers for the hardware limit switch.
###Slave-to-slave communications (from SW 4.1)

<table>
<thead>
<tr>
<th>Setpoint telegram from the master (S7)</th>
<th>Setpoints in the &quot;SIMODRIVE 611 universal&quot; (subscriber)</th>
<th>Control signals in &quot;SIMODRIVE 611 universal&quot;</th>
</tr>
</thead>
<tbody>
<tr>
<td><em>STW1</em></td>
<td><em>ON/OFF 1</em></td>
<td></td>
</tr>
<tr>
<td><em>SatzAnw</em></td>
<td><em>Block selection, bit 0</em></td>
<td></td>
</tr>
<tr>
<td><em>PosStw</em></td>
<td><em>Setting the home position</em></td>
<td></td>
</tr>
<tr>
<td><em>STW2</em></td>
<td><em>Parameter set, bit 0</em></td>
<td></td>
</tr>
<tr>
<td><em>DezEing</em></td>
<td><em>Hardware limit switch plus</em></td>
<td></td>
</tr>
<tr>
<td><em>P0915:5 = 50111</em></td>
<td></td>
<td></td>
</tr>
<tr>
<td><em>P0888:0 = 81</em></td>
<td></td>
<td></td>
</tr>
<tr>
<td><em>P0888:1 = 82</em></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Fig. 5-34 Example, mixed operation for the control signals
5.10 Slave-to-slave communications (from SW 4.1)

5.10.5 Example: Coupling two drives (master, slave drive)

General information

The following example is based on the functionality of slave-to-slave communications via PROFIBUS-DP. It shows the steps which are necessary, using SimoCom U, to parameterize the master and slave drive.

We recommend the following sequence when parameterizing:

1. Parameterizing the master, e.g. SIMATIC S7
2. Parameterizing the master drive
3. Parameterizing the slave drive

Assumptions for the example

- Standard telegram 108 for the master drive (publisher)
- Standard telegram 109 for the slave drive (subscriber)
- Default ±5 m, sufficient for the traversing range
- An SFC14/15 cannot be used
- P1009 = 4 ms

Parameterizing DP master

The steps when configuring an S7 are shown in the following Figs.:

The following data should be parameterized in the DP master (S7):

- Configuration, master drive matching telegram 108
  - number of process data
    - 4 words, PKW
    - 10 words, actual values to the DP master (inconsistent)
    - 10 words, setpoints from the DP master (inconsistent)

Fig. 5-35  Example, configuring the master drive for S7
5.10 Slave-to-slave communications (from SW 4.1)

- Configuring the slave drive matching telegram 109
  - Definition of the slave-to-slave communications link
  - 4 words, PKW
  - 10 words, actual values to the DP master (inconsistent)
  - 5 words, setpoints from the DP master (inconsistent)
  - 5 words, setpoints via slave-to-slave communications

Fig. 5-36 Example, configuring the slave drive for S7

- Clock cycle synchronization --> applicable for the master and slave drives

Fig. 5-37 Example, clock cycle synchronization for configuring S7
  DP cycle 4 ms
5.10 Slave-to-slave communications (from SW 4.1)

Note
When transferring data via the clock-cycle synchronous PROFIBUS-DP, a setpoint transfer instant in time of (T₀) of at least 750 µs must be configured. If the configured time is <750 µs then it is possible that either inconsistent or "old" actual values are transferred, e.g. XistP, XsollP, dXcor.

Parameterizing the master drive
The following parameters have been set:

- P0922 = 108
  --> Standard telegram 108: Master drive for the position reference value coupling

- Normalization via P0884 and P0896
  Setting for the best possible resolution:
  \[ P0884 = 2048 \text{ increments} = P0896 = 5 \text{ MSR} \]
  The default setting can be changed according to the following formula:
  \[ \text{Max. traversing distance which can be represented: } \pm \frac{2^{31}}{P0884} \cdot P0896 \]

- Optional: Inverting the external position reference value using P0897

Fig. 5-38 Parameterizing the master drive
Note

In order to ensure that the process data is correctly assigned between the publisher and subscriber, the offsets of the sent and received data must match.

For example, actual values (sent data) for PZD 18 (XsollP_H) in the master drive (Fig. 5-38) must match the setpoint/reference value (received data) for PZD 18 (Xext_H) in the slave drive (Fig. 5-39).

Parameterizing the slave drive

The following parameters have been set:

- \( \text{P0922} = 109 \)
  \( \rightarrow \) Standard telegram 109: Slave drive for the position reference value coupling

- \( \text{P0891} = 4 \)
  \( \rightarrow \) Source for "External position reference value": PROFIBUS DP

- Normalization using P0895 and P0896

Setting for the best possible resolution:

\[ \text{P0895} = 2048 \text{ increments} \quad \text{and} \quad \text{P0896} = 5 \text{ MSR} \]

Max. traversing distance which can be represented:

\[ \pm \left( \frac{2^{31}}{\text{P0895}} \right) \cdot \text{P0896} \]

- Optional: Inverting the external position reference value using P0897

Fig. 5-39  Parameterizing the slave drive
5.10 Slave-to-slave communications (from SW 4.1)

 Configuring the coupling

The following parameters should be set at the slave drive:

- Source for the "external position reference value"
  --> e.g. P0891 = 4: PROFIBUS DP

- Select the coupling type using P0410
  --> e.g. P0410 = 7: Coupling to the absolute position + P0412 via the digital input signal

- Define the optional coupling factor for revolutions, master and slave drive
  --> P0401 and P0402 (e.g. 1)

Fig. 5-40 Parameterizing the couplings

The DP master must set control word PosStw.4 in order to activate the coupling.
Space for your notes
6

Description of the Functions

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6.1.1 Application examples

**Fig. 6-1** Variable-speed drive

**Fig. 6-2** Positioning drive using a higher-level open-loop control, position actual value generation via angular incremental encoder

**Fig. 6-3** Positioning drive using a higher-level open-loop control, position actual value generation via a direct measuring system
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

6.1.2 Current and speed control

General

For "SIMODRIVE 611 universal", in the "speed/torque setpoint" mode, a setpoint can be entered as follows via analog inputs 1 and 2:

- Terminal 56.x/14.x (refer to Chapter 6.6)
  - Speed setpoint n_{set} analog/torque setpoint M_{set} analog
- Terminal 24.x/20.x (refer to Chapter 6.6)
  - Speed setpoint n_{set} analog/torque setpoint M_{set} analog/setpoint for torque reduction M_{red} analog

![Diagram of current and speed control](image)

Fig. 6-4 Current and speed control
Reader’s note

Described in the following:

- Ramp-function Generator
- Optimizing the closed-loop current and speed controller
- Speed controller adaptation

All additional parameters to optimize the current and speed control loop can be adapted using the expert list.

Detailed information regarding the current and speed control loop are included in:

Reference: /FBA/ SIMODRIVE 611D/SINUMERIK 840D/810D Description of Functions, Drive Functions
6.1.3 Ramp-function generator

**General information**

The ramp-function generator is used to limit the acceleration when the analog setpoint voltage has step changes. Various parameter set-dependent ramps can be entered for ramp-up and ramp-down.

**Parameter overview**

The following parameters are available for the ramp-function generator:

<table>
<thead>
<tr>
<th>Parameter overview for the ramp-function generator</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Table 6-1</strong> Parameter overview for the ramp-function generator</td>
</tr>
<tr>
<td><strong>Parameter</strong></td>
</tr>
<tr>
<td>----------------</td>
</tr>
<tr>
<td></td>
</tr>
<tr>
<td></td>
</tr>
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<td></td>
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<td></td>
</tr>
<tr>
<td></td>
</tr>
<tr>
<td></td>
</tr>
</tbody>
</table>

The setpoint is increased from zero up to the maximum permissible actual speed within this time.

- Max. permissible actual speed for synchronous motors: Minimum from 1.1 \* P1400 and P1147 (from SW 7.1 1.05 \* P1400 and P1147 with "SIMODRIVE 611 universal HR/HRS" resolver)
- Max. permissible actual speed for induction motors: Minimum from P1146 and P1147
- Max. permissible actual speed for linear motors: from P1147

The setpoint is changed from the maximum permissible actual speed to zero within this time.

- Max. permissible actual speed for synchronous motors: Minimum from 1.2 \* P1400 and P1147
- Max. permissible actual speed for induction motors: Minimum from P1146 and P1147

The ramp-function generator tracking can be activated/de-activated using P1012 bit 0. 

= 1 Ramp-function generator tracking active (standard)  
= 0 Not active

**Note:**

1) For example, from the PROFIBUS control word NSOLL or P0641 (fixed speed setpoint).  
2) Ramp-function generator output corresponds to the speed setpoint trace parameter.
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

For the ramp-function generator, the following signals are used:

- **Input signal**
  - Ramp-function generator enable
  - Ramp-up time zero
  - Ramp-up time zero for controller enable (from SW 3.1)

- **Output signal**
  - Ramp-up completed

---

**Reader’s note**

The signals can be entered or output as follows:

- via terminals -- refer to Chapter 6.4.2 or 6.4.5
- via PROFIBUS-DP -- refer to Chapter 5.6.1

All of the input/output signals are shown and described in Chapter 6.4.3 and 6.4.6 and can be found in the Index under "Input signal..." or "Output signal...".

---

![Diagram of ramp-function generation](image-url)

1) For an active average-value filter for the speed setpoint (P1012.8=1), a setpoint step somewhat greater than P1426 must be used in order to clearly identify the start of a new ramp-up operation.

Fig. 6-5 Signal characteristics for the ramp-function generator
6.1.4 Optimizing the closed-loop current and speed controller

When optimizing the cascaded control structure (current, speed controller), you generally proceed from the inside to the outside.

**Optimizing the current controller**

At the first commissioning or later, the current controller is pre-set using the "Calculate controller data" function, and generally no longer has to be optimized. However, all parameters for the current control loop can be adapted via the expert list of the "SimoCom U" tool.

**Optimization speed controller**

At the first start-up (first commissioning) or later, the speed controller is pre-set using the "Calculate controller data". This speed controller setting is calculated for a motor operating under no-load conditions, and corresponds to a "safe" setting.

In order to be able to fully utilize the dynamic performance of the drive including the mechanical system, some post-optimization will be necessary.

- Optimizing using the "SimoCom U" tool
  
  The controller setting for "SIMODRIVE 611 universal" can be automatically executed using the "SimoCom U" tool (only in online operation).

  Call:
  
  Press the "Execute automatic controller setting" button under "Controller" and execute the steps offered.

---

**Reader's note**

Recommendation when optimizing the controller:

Optimize the control loop with "SimoCom U" and the "Execute automatic controller setting" function.

- Optimization using the display and operator control unit:
  
  - Remove write protection --> set P0651 to 4
  
  - Increase the proportional gain Kp (P1407:8) until the motor makes a whistling sound
  
  - Reduce the proportional gain Kp (P1407:8) until this whistling sound disappears
  
  - The integral action time T_N (P1409:8) can be retained
Table 6-2 Parameters for the speed controller optimization

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1407:8</td>
<td>P gain, speed controller (SRM, ARM) P gain, velocity controller (SLM)</td>
<td>0.0</td>
<td>0.3</td>
<td>999.999</td>
<td>Nm*s/rad, Ns/m</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... specifies the magnitude of the proportional (gain $K_p$, proportional component) of the control loop.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1409:8</td>
<td>Integral action time, speed controller (SRM, ARM) Integral action time, velocity controller (SLM)</td>
<td>0.0</td>
<td>10.0</td>
<td>500.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... specifies the integral action time ($T_N$, integral component) of the control loop.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Reader’s note

When optimizing, e.g. linear drives, it may be necessary to set the current and speed setpoint filters.
This procedure is described in:

Reference: /FBA/ SIMODRIVE 611D/SINUMERIK 840D/810D
Description of Functions, Drive Functions
6.1.5 Speed controller adaptation

**Description**

The speed controller can be adapted, depending on the speed or velocity, using the speed/velocity controller adaptation.

For example, in order to better overcome static friction at lower speeds, a higher proportional gain can be set than for higher speeds.

**Enabling/disabling adaptation**

Adaptation is enabled/disabled with P1413.

- The following is valid with the adaptation enabled (P1413 = 1):
  - **Proportional gain** \((K_p)\):
    - The settings in P1407:8 and P1408:8 are effective as a function of the lower (P1411) and upper thresholds (P1412).
    - The values are linearly interpolated in the adaptation range.
  - **Integral action time** \((T_N)\):
    - The settings in P1409:8 and P1410:8 are effective as a function of the lower (P1411) and upper thresholds (P1412).

- With adaptation disabled (P1413 = 0) the following is valid:
  - The proportional gain \((K_p, P1407:8)\) and the integral action time \((T_N, P1409)\) are effective over the complete range.

![Proportional gain \(K_p\) and integral action time \(T_N\)](image)

**Fig. 6-6 Adaptation of the speed controller parameters using the characteristic**

**Note**

Only the position controller output is taken into account for limit sensing (upper and lower adaptation speed).
### Parameter overview

The following parameters are available for the speed controller adaptation:

#### Table 6-3 Parameters for the speed controller adaptation

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter</th>
<th>Min.</th>
<th>Std.</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1413</td>
<td>Select adaptation, speed controller (SRM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Select adaptation, speed controller (ARM)</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Select adaptation, velocity controller (SLM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... the adaptation can be activated/de-activated immediately.

1 The adaptation is active
0 The adaptation is not active

**Note:**
For induction motors (ARM), the speed controller adaptation is switched-in as standard.

| 1408:8| P gain, upper adaptation speed (SRM, ARM)                                 | 0.0  | 0.3  | 999 999.0 | Nm*s/rad   | immediately |
|       | P gain, upper adaptation velocity (SLM)                                   | 2 000.0 | 999 999.0 | Ns/m       | immediately |

... defines the P gain in the constant, upper range (\( \text{n or } v > P1412 \)).

**Note:**
When a value of 0 is entered, the associated integral component (P1410) is automatically de-activated.

| 1410:8| Integral action time, upper adaptation speed (SRM, ARM)                   | 0.0  | 10.0 | 500.0 | ms         | immediately |
|       | Integral action time, upper adaptation velocity (SLM)                     |      |      |       |            |            |

... defines the integral action time in the constant, upper range (\( \text{n or } v > P1412 \)).

**Important:**
With the adaptation activated, you should avoid de-activating the integral component for only one range (P1409 = 0 and P1410 = 0 or vice versa).

**Problem:** Torque jumps when resetting the integral value at the transition from the adaptation range to the constant range.

**Note:**
If a value of 0 is entered, this de-activates the integral component for the range greater than set in P1412.

| 1411 | Lower adaptation speed (SRM, ARM)                                       | 0.0  | 0.0  | 100 000.0 | RPM m/min  | immediately |
|      | Lower adaptation velocity, motor (SLM)                                  |      |      |         |            |            |

... defines the lower threshold for adaptation.

| 1412 | Upper adaptation speed (SRM, ARM)                                       | 0.0  | 0.0  | 100 000.0 | RPM m/min  | immediately |
|      | Upper adaptation velocity, motor (SLM)                                  |      |      |         |            |            |

... defines the upper threshold for adaptation.
6.1.6 Fixed speed setpoint (from SW 3.1)

Description

Speed setpoints can be defined in parameters using this function. The required fixed setpoint for the speed setpoint input is selected via input signals. The currently selected fixed setpoint can be displayed via output signals.

Advantage:

An analog voltage is not required for the speed setpoint input, and the setpoint can be precisely set.

Input/output signals

The following signals are used for the "fixed speed setpoint" function:

- Input signals
  (refer under index entry "Input signal, digital - ...")
  - Fixed speed setpoint 1st input (function number = 15)
  - Fixed speed setpoint 2nd input (function number = 16)
  - Fixed speed setpoint 3rd input (function number = 17)
  - Fixed speed setpoint 4th input (function number = 18)

- Output signals
  (refer under the index entry, "Output signal, digital - ...")
  - Status, fixed speed setpoint 1st output (function number = 15)
  - Status, fixed speed setpoint 2nd output (function number = 16)
  - Status, fixed speed setpoint 3rd output (function number = 17)
  - Status, fixed speed setpoint 4th output (function number = 18)

Parameter overview

The following parameters are available for the "fixed speed setpoint" function:

- P0641:16 Fixed speed setpoint (SRM, ARM)
  Fixed velocity setpoint (SLM)

Commissioning the function

The following sequence is practical when commissioning:

1. Enter the required fixed speed setpoints (refer to Chapter A.1)
   - P0641:0 = no significance
   - P0641:1 = required fixed setpoint 1
   - P0641:2 = required fixed setpoint 2, etc.

2. Parameterize the input terminals (refer to Chapters 6.4.2 and 6.4.3)

3. Parameterize the output terminals (refer to Chapters 6.4.5 and 6.4.6)

4. Check the function
6.1.7 Monitoring functions

Motor temperature monitoring

The temperature limit values are pre-assigned, corresponding to the selected motor when the motor code is specified; the user should not change these.

The following motor temperature monitoring functions are available:

- Temperature monitoring with pre-warning (P1602 + P1603)

  If the temperature warning threshold (P1602) is exceeded, the result is as follows:
  - Warning 814 is output
  - Timer (P1603) is started
  - Motor overtemperature is signaled via terminal 5.x at the NE module

  **Note:**
  This signal is saved, if it is still present after the time in P1603 has expired.
  - The "motor temperature pre-warning" (MeldW.6) output signal is set

  If the overtemperature condition still remains after the time set in P1603, then this results in fault 614 and the drive is powered down.

  The monitoring function can be enabled/disabled using P1601.14.

- Temperature monitoring without pre-warning (P1607)

  If the temperature threshold in P1607 is exceeded, this immediately results in fault 613 and the drive is powered down.

  The monitoring function can be enabled/disabled using P1601.13.

**Note**

The temperature monitoring functions (warning P1602 + timer P1603 or P1607) are not subject to any mutual restrictions, i.e. it is permissible that P1607 < P1602.

- Specifying a fixed temperature (P1608)

  When a fixed temperature is specified, the temperature-dependent adaptation of the rotor resistance is executed with this fixed temperature.

**Note**

The temperature monitoring functions of the motor, set using P1602 or P1607, are then no longer effective.
Temperature sensor

The following motor temperature sensor types can be connected to X411/X412:

- KTY temperature sensor (standard)
  The measured resistance is converted to a temperature. The maximum permissible temperature can be parameterized (P1602).

- PTC temperature sensor
  The PTC temperature sensor has a switching behavior:
  - Measured resistance < 1330 Ohm (temperature display 0°C) => Motor temperature is permissible
  - Measured resistance > 1330 Ohm (temperature display 200°C) => Excessive motor temperature
  - Measured resistance < 30 Ohm => Short circuit

Warning 814 is signaled when the motor temperature reaches the warning threshold for excessive motor temperature, in P1602 at the KTY temperature sensor or the specific switching temperature at the PTC temperature sensor.

When the resistance drops below the resistance threshold 1330 Ohm at the PTC temperature sensor, the warning goes away again, provided the excessive motor temperature does not exist longer than the timer parameterized in P1603.

If the drive is to switch off immediately at an excessive temperature, P1603 = 0 (timer for motor temperature alarm) is to be parameterized.

In the case of a short circuit recognition with a PTC temperature sensor both Alarms 613 and 614 as well as Warning 814 are displayed simultaneously. In this case Parameters 1602 and 1607 are ineffective.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0603</td>
<td>Motor temperature</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>°C</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... displays the motor temperature measured using the temperature sensor.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>This display is not valid, if a fixed temperature was entered in P1608.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1602</td>
<td>Warning threshold, motor overtemperature</td>
<td>0</td>
<td>120</td>
<td>200</td>
<td>°C</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>The parameter specifies the permissible thermal steady-state motor temperature, and is appropriately pre-assigned when the motor code is specified.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>If the temperature warning threshold is exceeded, initially, &quot;only&quot; warning 814 is output, which is withdrawn when the temperature threshold is fallen below.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>If the overtemperature condition remains for a time longer than that set in P1603, then this results in fault 614.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Monitoring can be enabled/disabled via P1601.14.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 6-4  Parameters for the motor temperature monitoring function, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1603</td>
<td>Timer for motor temperature alarm</td>
<td>0</td>
<td>240</td>
<td>600</td>
<td>s</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>The parameter defines the time, which is started when the temperature warning threshold is exceeded (P1602).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1607</td>
<td>Shutdown limit, motor temperature</td>
<td>0</td>
<td>155</td>
<td>200</td>
<td>°C</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>The temperature defines the shutdown limit for the temperature monitoring without pre-warn-</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>ing. If the shutdown limit is exceeded, this results in fault 613.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1608</td>
<td>Fixed temperature</td>
<td>0</td>
<td>0</td>
<td>200</td>
<td>°C</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>If a value &gt; 0 is entered, the rotor resistance is adapted depending on the temperature using this fixed temperature.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• This can be necessary, e.g. if a motor does not have any temperature sensor.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• This means, that, e.g. the temperature monitoring for linear motors is switched-out if the monitoring is realized using an external PLC.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The temperature monitoring functions of the motor, set using P1602 and P1603 or P1607, are then no longer effective.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1609</td>
<td>PTC temperature sensor (from SW 11.1)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>Hex</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>The temperature defines the sensor type for measuring the motor temperature.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 0 = 0: KTY temperature sensor (standard)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 0 = 1: PTC temperature sensor</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Thermal motor model (only for rotating motors) (from SW 11.1)**

This monitoring protects the motor from constant thermal overload so that the motor is not overloaded beyond the permissible temperature. It represents an expansion of the known temperature measurement (temperature sensors).

With the thermal motor model, a model temperature of the motor is calculated internally in accordance with the motor type, the measured motor current, the KTY motor temperature sensor, if present, and the shutdown temperature threshold.

If the KTY motor temperature sensor is incorporated, the motor can no longer be overloaded when powered on in the warmed-up state. The calculated model temperature refers to the permissible shutdown temperature of the motor from P1607 (up to SW 12.1) and P1288 (from SW 12.2).

**Note**

The thermal motor model cannot be activated if P1268 = 0 (winding time constant).

If a PTC temperature sensor is connected, the "Thermal motor model" function acts as if no temperature sensor were connected.
In case of a thermal motor load (P1266) greater than that configure in the response threshold P1269, the following happens, as when the temperature threshold in P1602 is exceeded:

- Warning 814 is output
- Timer in P1603 is started
- Excessive motor temperature is signaled via terminal 5.x of the NE module
- The "motor temperature pre-warning" (Fct. No. 5, MeldW.6) output signal is set

If the thermal motor load still exceeds the value in P1269 after the time set in P1603, this results in Fault 614 and the drive being powered down (can be parameterized).

If the motor load rises up to 100%, this results in Fault 614 and the drive being powered down (can be parameterized).

These monitoring functions can be activated/deactivated with P1601 or by switching off the drive with P1613.

### Table 6-5 Parameters at thermal motor model

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P1265</td>
<td>Configuration of thermal motor model</td>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>... Specifies the configuration for the thermal motor model. Bit 0: Activation of the thermal motor model Bit 0 = 0: Thermal motor model not activated Bit 0 = 1: Thermal motor model activated Bit 1: Evaluation of thermal motor model Bit 1 = 0: Evaluation with KTY temperature sensor activated Bit 1 = 1: No evaluation (purely current monitoring)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P1266</td>
<td>Thermal motor load</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... Is used to diagnose the thermal motor load The parameter indicates the thermal load of the motor as a percentage. The mathematical model references the maximum permissible motor temperature from P1288. A default value is assigned to P1288 motor-specifically during commissioning. If this value is changed, the triggering of the thermal motor model also changes. <strong>Note:</strong> In case of a thermal motor load &gt; 100% Fault 613 is signaled.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P1268</td>
<td>Winding time constant</td>
<td>0</td>
<td>0</td>
<td>5000</td>
<td>s</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... Is used to enter the winding time constant. The motor-specific parameter has to be specified by the motor manufacturer. It is required for thermal model model (P1265).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Table 6-5  Parameters at thermal motor model, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1269</td>
<td>Thermal motor load warning threshold</td>
<td>0</td>
<td>80</td>
<td>100</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... Outputs a message to the PLC (NST &quot;Motor temperature pre-warning&quot;, DB 31, to DBX 94.0), if the thermal motor load (P1266) is greater than the response threshold in P1269 and the time monitoring in P1603 is started. If the timer expires without the value of the thermal motor load dropping below the threshold, the drive generates a configurable reset alarm (P1601, Bit 14). <strong>Note:</strong> Also refer to P1603 and P1288.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1288</td>
<td>Shutdown threshold, thermal motor model</td>
<td>0</td>
<td>180</td>
<td>220</td>
<td>°C</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... defines the shutdown threshold of the thermal motor model (up to SW 12.1, P1607 applies). When commissioning, the value in P1288 is pre-assigned depending on the specific motor. <strong>Note:</strong> Also refer to P1265, P1266, P1268 and P1269.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Torque setpoint monitoring (speed controller output limited, speed controller at its endstop)**

The following is monitored:

- Is the speed controller output (torque setpoint) at its limit for longer than the time in P1605 (torque, power, stall or current limit)? and
- Is the absolute actual speed less than that in P1606?

When the monitoring function responds, fault 608 (speed controller output limited) is output and the pulse enable is withdrawn.

**Note**

Fault 608 (speed controller output limited) can be suppressed using the input signal "suppress fault 608 (from SW 3.1)".
### Table 6-6 Parameters for the torque setpoint monitoring

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1605</td>
<td>Timer stage, n controller at its limit</td>
<td>20.0</td>
<td>200.0</td>
<td>10 000.0</td>
<td>ms</td>
<td>immedi- ately</td>
</tr>
</tbody>
</table>

... specifies how long the speed controller output may be at its limit, without a fault condition being generated.

**Important:**
If P1605 < P1404, then regenerative braking can be canceled with fault 608, whereby the drive then coasts down.

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1606</td>
<td>Threshold, speed controller at its limit</td>
<td>0.0</td>
<td>90 000.0</td>
<td>100 000.0</td>
<td>RPM</td>
<td>RPM m/min</td>
</tr>
</tbody>
</table>

... specifies up to which speed the torque setpoint monitoring is active, i.e. up to this value, fault 608 (speed controller output limited) can be output.

**Note:**
For PE spindles (P1015 = 1), the standard assignment is the same as for ARM (30.0 RPM).

### DC link monitoring

The DC link of the drive system is monitored for an undervoltage condition.

The set DC link undervoltage warning threshold in P1604 is monitored and the monitoring result is displayed via the "DC link monitoring V_{DC link} > V_x" output signal.

The DC link voltage is generally monitored in the NE modules. If the fixed monitoring limits are exceeded or fallen below, then the NE module automatically carries out shutdown operations.

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1604</td>
<td>DC link undervoltage warning threshold</td>
<td>0</td>
<td>200</td>
<td>680</td>
<td>V(pk)</td>
<td>immedi- ately</td>
</tr>
</tbody>
</table>

... specifies the DC link undervoltage warning threshold V_x to output the signal "DC link monitoring V_{DC link} > V_x".

**Note:**
The DC link voltage is sensed by the NE module or a monitoring module, and can also be output as analog signal (0 - 10 V) via an analog output.
From SW 4.1, the following monitoring functions/warnings are available for the DC link voltage, which result in the drive being powered down (tripped):

- Monitoring the DC link for an overvoltage condition
  
  **Threshold:** P1163 "Max. DC link voltage"
  
  Fault 617, if the DC link voltage, when the pulses are enabled, is greater than the threshold. The shutdown response can be configured using P1613 bit 16 or 17.

- Monitoring for a DC link undervoltage condition
  
  **Threshold:** P1162 "Minimum DC link voltage"
  
  Defines the permissible lower limit for the DC link voltage.
  
  Fault 616 is generated if the DC link voltage when setting the enable signals is less than the threshold. The monitoring only becomes active if $V_{DC\,\text{link}}$ (P1701) has fallen below the value in P1162 at least once and the drive is ready to be moved.
  
  The shutdown response to fault 616 can be configured using P1613 bit 16 or 17.

If the standard value is entered in P1162/P1163, then the appropriate monitoring is inactive.
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

| Hardware limit switch (HW limit switch) (from SW 8.1) | When using “SIMODRIVE 611 universal” with a higher-level control, it can occur that for coordinate transformation, e.g. shifting and rotating the tool, that the software limit switches cannot be activated/evaluated in the higher-level control. An axis fast stop is possible using a hardware limit switch monitoring function. The HW limit switches must be connected to an input terminal with the following function numbers:
  - “Plus hardware limit switch” function --> function number 81
  - “Minus hardware limit switch” function --> function number 82
    --> Refer to Chapter 6.4.2 |

| Traverse to a hardware limit switch? | When traversing to a hardware limit switch, the associated input signal is set to “0” and the following response is automatically initiated:
  - A setpoint of zero is entered in the selecting speed direction - the axis is braked and comes to a standstill. The drive remains in the closed-loop controlled mode.
    If it is switched-in, the ramp-function generator remains active. The braking that is initiated runs with or without braking ramp.
  - One of the following warnings is output:
    - Warning 800 Minus hardware limit switch
    - Warning 801 Plus hardware limit switch
    The hardware limit switch signal must always remain at a “0 signal” outside the permitted traversing range. A brief change from “0 signal” to “1 signal” is not permitted.
    As a result of the zero speed input when reaching the hardware limit switch, alarms, e.g. "following error too high" or similar faults must be detected in the higher-level control. |

| How do you move away from a hardware limit switch? | If an axis is at a hardware limit switch, then it can be moved away as follows:
  - Enter a setpoint in the opposite direction to the approach direction or
  - Withdraw the controller enable and move the drive away manually
    After moving away from the hardware limit switch, warning 800 or 801 is automatically deleted. |
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

Other monitoring functions

Reader's note
For "SIMODRIVE 611 universal", additional monitoring functions can be parameterized, and processed via output signals (terminals, PROFIBUS) (refer to Chapter 6.4.6 and 6.20).

6.1.8 Limits

Limiting the speed setpoint
The speed setpoint is limited to the maximum value which is set.

How is the speed setpoint limiting calculated?

Motor type Interdependencies
- SRM, SLM: P1405:8 • P1401:8
- ARM: Minimum
  (P1405:8 • P1401:8, 1.02 • P1147, 1.02 • P1146)

Note
The maximum useful motor speed, set via P1401:8, is taken into account when calculating the speed setpoint, i.e. P1401:8 acts as speed limiting. This is valid, independent of whether the setpoint is entered via a terminal or PROFIBUS-DP.

Speed limiting
If the speed actual value exceeds the selected limit value by more than 2%, then the torque, when motoring, is set to 0. Thus, further acceleration is not possible. If the speed actual value drops below the limit value, the torque limiting is withdrawn again.

How is the speed limiting calculated?

Motor type Interdependencies
- SRM: Minimum (P1147, 1.2 • P1400)
- ARM, SLM, PE spindle: Minimum (P1147, P1146)
### 6.1 Operating mode, speed/torque setpoint (P0700 = 1)

#### Table 6-8 Parameters for speed limiting

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1146</td>
<td>Maximum motor speed (SRM)</td>
<td>0.0</td>
<td>0.0</td>
<td>100 000.0</td>
<td>RPM</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>Maximum motor speed (ARM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Maximum motor velocity (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... specifies the maximum motor speed or maximum motor velocity defined by the motor manufacturer.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong> This is only included in the speed limiting for rotary induction motors (ARM).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1147</td>
<td>Speed limit (SRM)</td>
<td>0.0</td>
<td>7 000.0</td>
<td>100 000.0</td>
<td>RPM</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Speed limit (ARM)</td>
<td></td>
<td>8 000.0</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Velocity limit, motor (SLM)</td>
<td></td>
<td>120.0</td>
<td></td>
<td>m/min</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... specifies the maximum permissible motor speed or motor velocity.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>When commissioning the system for the first time and for &quot;calculate unlisted motors&quot;, the parameter is pre-assigned as follows:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• SRM 1.1 • P1400</td>
<td></td>
<td></td>
<td></td>
<td>RPM</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>1.05 • P1400 (from SW 7.1 with &quot;SIMODRIVE 611 universal HR/HRS&quot; resolver)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• ARM, SLM, PE spindle</td>
<td></td>
<td></td>
<td></td>
<td>m/min</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Speed actual value &gt; Speed limit</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• Exceeded by more than 2 %:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The torque limit when motoring is internally set to zero, the drive is prevented from accelerating any further.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>With the appropriate setting, the &quot;speed controller at its limit&quot; monitoring can respond.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1401:8</td>
<td>Speed for max. useful motor speed (SRM, ARM)</td>
<td>-100 000.0</td>
<td>0.0</td>
<td>100 000.0</td>
<td>RPM</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Velocity for max. motor useful velocity (SLM)</td>
<td></td>
<td></td>
<td></td>
<td>m/min</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... limits the speed to the maximum useful motor speed.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The parameter is pre-set at the first start-up and for &quot;Calculate unlisted motor&quot;:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• SRM P1400</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• ARM, SLM, PE spindle</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong> P1401:8 is used for normalization for speed setpoints entered via analog inputs (refer to Chapter 6.6).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1405:8</td>
<td>Monitoring speed, motor (SRM, ARM)</td>
<td>100.0</td>
<td>110.0</td>
<td>110.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Monitoring velocity, motor (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... specifies the maximum permissible setpoint as a percentage referred to P1401:8.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The parameter is pre-assigned as follows when the system is commissioned for the first time and for &quot;calculate unlisted motor&quot;:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• SRM 110 %</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>105 % (from SW 7.1 with &quot;SIMODRIVE 611 universal HR/HRS&quot;, resolver)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

Limiting the torque setpoint

The following limits all effect the torque setpoint at the speed controller output. The "lowest" (minimum) is used if different limits are available.

- Torque limiting
  The value specifies the maximum permissible torque, whereby different limits can be parameterized for motoring and generating operation.

- Power limiting
  The value specifies the maximum permissible power, whereby different limits can be parameterized for motoring and generating operation.

- Stall limiting (only for ARM and PE spindle)
  The stall limiting is internally calculated in the drive from the motor data. The internally calculated limit can be changed using the torque reduction factor.

**Warning**

If the stall limit has been set too high, this can cause the motor to "stall".

As the current limiting additionally limits the maximum torque which the motor can provide, if the torque limit is increased, more torque will only be available if a higher current can also flow. It may be necessary to also adapt the current limit.

![Fig. 6-7 Limiting the torque setpoint](image-url)
The torque/power can be reduced continuously by reducing the currently effective torque limit using "MomRed" control word (refer to Chapter 5.6.6). The result of the conversion is a percentage factor $k$ which is applied to $P1230$ (torque limit) and $P1235$ (power limit). For the specified $k$ factor, $P1230$ is replaced by $k\times P1230$ and $P1235$, by $k\times P1235$ in Fig. 6-7.

Table 6-9 Parameters for limits

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1145</td>
<td>Stall torque reduction factor</td>
<td>5.0</td>
<td>100.0</td>
<td>1 000.0</td>
<td>%</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... the start of stall torque limiting can be changed (refer to Fig. 6-7).
For a setting greater than 100%, the intervention point is increased.
For a setting of less than 100%, the intervention point is decreased.

1230:8
1. torque limit value (SRM, ARM)
2. Force limit value (SLM)

... specifies the maximum torque referred to the pull-out torque (SRM), rated motor torque (ARM) or stall force (SLM) of the motor.

**SRM/SLM:**
Stall torque/stall force = $P1118 \times P1113$
$P1118$: Motor standstill (stall) current
$P1113$: Torque constant

**ARM:**
Rated motor torque
$= ((P1130 \times 1000) / (2\pi \times P1400 / 60))$
$= 9549.3 \times (P1130 / P1400)$
$P1130$: Rated motor power
$P1400$: Rated motor speed

The minimum of the torque, power and stall torque limits are always effective as limit (refer to Fig. 6-7). The standard pre-assignment for ARM is 100%.
For SRM/SLM, this is realized with the following operator action **Calculate controller data**, whereby the value is obtained from the following formula:

**SRM/SLM:**
$P1230:8 = (P1104/P1118) \times 100\%$

The following is especially true for ARM:
In order to achieve significantly shorter accelerating times up to the maximum speed, the power and current limits must also be increased.

**Important:**
If the motor is overloaded for a longer period of time, this can result in an impermissible temperature rise (the drive is shutdown as a result of a motor overtemperature condition); the motor can also be destroyed.
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

Table 6-9  Parameters for limits, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1235:8</td>
<td>1. power limit value</td>
<td>5.0</td>
<td>100.0</td>
<td>900.0</td>
<td>%</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... specifies the maximum permissible power referred to the motor power (SRM) or the rated motor power (ARM - P1130: Rated motor power).
Motor power for SRM [kW] = 1/9549.3 \( \cdot (P1118 \cdot P1113) \cdot P1400 
P1118: Motor standstill (stall) current  
P1113: Torque constant  
P1400: Rated motor speed

As shown in Fig. 6-7, using the power limiting (constant power), the torque is limited  
\( P = 2\pi \cdot M \cdot n ; \) with \( P = \text{constant} \rightarrow M = \frac{1}{n} \).

The minimum of the torque, power and stall torque limits are always effective as limit (refer to Fig.6-7).
SRM/SLM: \( P1235:8 = (P1104/P1118) \cdot 100 \% \)
For SRM/SLM, this parameter is automatically pre-assigned using the operator action calculate controller data, whereby the value is obtained from the formula above:

ARM: The standard default is 100 %.
The following is especially true for ARM:
If the speed at the start of field weakening is greater than the rated speed, then the ramp-up times can already be shortened and the power yield increased if only the power limit is increased (with the same current limit). As the current limit (P1238) can also limit the maximum torque which can be specified, if the output limit (power limit) is increased further, more torque can only be obtained if the current limit is also increased.

Important:
If the motor is overloaded for a longer period of time, this can result in an impermissible temperature rise (the drive is shut down as a result of a motor overtemperature condition); the motor can also be destroyed.
Corresponding parameters are: P1104, P1145 and P1233:8 to P1238

1233:8 Regenerative limiting 5.0 100.0 100.0 % immediately

... specifies the regenerative limiting.
The setting refers to the parameter value in P1230.

1237 Maximum regenerative power 0.1 100.0 500.0 kW immediately

... allows the regenerative power to be limited for the input/regenerative feedback module.
An appropriately lower value should be entered here, especially when using an uncontrolled NE module.

---

Note
Torque/power reduction
It is possible to continuously reduce the torque/power by reducing the effective torque limit.
- for terminals:
  via analog input 2 (terminal 24.x/20, refer to Chapter 6.6.4).
- for PROFIBUS-DP:
  using the "MomRed" control word (refer to Chapter 5.6.6).
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

Drives, for which a stop was initiated as a result of one of the following measures, are braked with the maximum possible motor current (P1104) taking into account the reduction in P1105:

- Terminal 64 de-energized at the SIMODRIVE line infeed module.
- Generating an alarm, which initiates a Stop II, and therefore withdraws the internal controller enable.
- Controller enable (ON/OFF1) withdrawn or terminal 65 de-energized (X451.5/X452.5).

This may possible cause the plant/machine to be mechanically damaged. For this case, a torque reduction can be parameterized for a setpoint of zero.

The following definitions apply:

- P1096: Used to configured the torque reduction at nset = 0.
  - Bit 0 = 1: Reduces the torque limit for a regenerative stop with a speed setpoint of zero.
  - Bit 1 = 0: Monitors the speed controller at its endstop for torque reduction.

If the motor brakes with a low torque, then fault 608 can be initiated. If it is not desirable that this fault is initiated, then the fault can be suppressed using bit 1 = 1.

- P1097: Specifies the torque reduction at nset = 0.

Note

The percentage value from P1097 only refers to the torque obtained at the maximum motor current if P1105 = 100%.

- The braking behavior is influenced by:
  - P1403: Shutdown speed/velocity, pulse cancellation
    - If the absolute speed actual value or velocity actual value falls below the specified shutdown speed in P1403 while braking, then the pulse enable is withdrawn and the drive coasts down.
  - P1404: Timer for pulse suppression
    - The pulses are cancelled before this if the timer set in P1404 has expired.
  - P1605: Timer stage, n controller at its limit
    - After the set time has expired, then drive coasts down after braking.
  - P1613: Shutdown response, faults
    - If the torque reduction is to be initiated by a fault at nset = 0, then this must be parameterized using the shutdown response STOP II.
6.1 Operating mode, speed/torque setpoint (P0700 = 1)

**Current limiting**

The motor current is limited to a maximum value. The maximum value is obtained from the minimum between the parameterization according to Table 6-10 and the limiting as a result of the power module.

<table>
<thead>
<tr>
<th>Table 6-10</th>
<th>Parameters for the current limiting</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>No.</strong></td>
<td><strong>Description</strong></td>
</tr>
<tr>
<td>1238</td>
<td>Current limit (ARM)</td>
</tr>
<tr>
<td>1105</td>
<td>Reducing the maximum motor current (SRM, SLM)</td>
</tr>
</tbody>
</table>

... specifies the maximum permissible motor current referred to the rated motor current (P1103). In order to shorten the ramp-up (accelerating) times, it may make sense to set the current limit to values > 100%, and additionally increase the power and torque limit.

If the motor current is at its limit due to high torque/power limits, the monitoring function intervenes with P1605 and P1606 (speed controller at its limit).

Stationary minimum speed (from SW 11.1)

No stationary operation in the speed range around zero.

Activation of the function "Stationary minimum speed":

\[ \Rightarrow P1255 \neq 0 \]

If the value of the speed setpoint is smaller than the parameterized minimum speed, the minimum speed is used as the setpoint with the sign of the speed setpoint.

In the case of a speed setpoint near zero a hysteresis prevents an unwanted change in the sign. The width of the hysteresis is equal to the minimum speed, however at the most 200 RPM.

A setpoint equal to zero can only be achieved when the minimum speed is not equal to zero by removing the controller or ramp-function generator enable.

![Fig. 6-8 Method of operation of the minimum speed](image_url)
6 Description of the Functions

6.1 Operating mode, speed/torque setpoint (P0700 = 1)

Speed range exclusion (from SW 11.1)

No stationary operation in the excluded speed rate

Activation of the function "Speed range exclusion":

⇒ P1271 ≠ 0 and P1271 > P1270

Special case: P1271 > 0 and P1270 = 0

⇒ The "Speed range exclusion" function acts like the "Stationary minimum speed" function.

The "Speed range exclusion" makes it possible to prohibit the stationary running of speeds in a range that can be parameterized.

This range can only be traveled through, whereby the set motor-specific ramp-up or ramp-down times of the ramp function generator are effective.

If the speed setpoint lies between the lower speed (P1270) and the upper speed (P1271) of the "Speed range exclusion", coming from the smaller value, the lower speed (P1270) continues to be effective as the setpoint until the specified setpoint has reached the upper speed.

If the speed setpoint is dropping, the upper speed (P1271) is initially retained until the setpoint has reached the lower speed (P1270).

![Fig. 6-9 Method of operation of the speed range exclusion](image)

**Note**

If spindle positioning is selected with the "Spindle positioning on" signal (PROFIBUS STW1.15 or input terminal with Fct. No. 28), the "Minimum speed" and "Speed range exclusion" functions remain deactivated until the "Spindle positioning on" signal is canceled again.
6.1.9 Position measuring system with distance-coded reference marks (from SW 4.1)

**General**

In order that large distances do not have to be traversed for reference point approach, for indirect and direct measuring systems, it is possible to use a position measuring system with distance-coded reference marks.

This guarantees that the measuring system has already been referenced after a short traversing distance (e.g. 20 mm).

---

**Note**

Referencing with distance-coded reference marks is only possible using PROFIBUS-DP in an external control (refer to Chapter 5.6.4). It is not possible to evaluate the coding in the board itself!

From SW 8.3 for rotary encoder systems and from SW 9.2 for linear encoder systems:

The SIMODRIVE module is, in the pos mode, in the position to autonomously reference (home) without an external control.

---

**Proceed as follows**

The procedure is the same as when referencing with normal incremental measuring systems.

The following conditions are to be observed:

- **Indirect measuring system (motor measuring system, IM)**
  - $P_{1027.7} = 1$ (IM configuration, encoder)
  - $\rightarrow$ distance-coded reference scale
  - $P_{1050}$ or $P_{1051}$
  - $\rightarrow$ basic distance between two fixed reference marks

- **Direct measuring system (DM)**
  - $P_{1037.7} = 1$ (DM configuration, encoder)
  - $\rightarrow$ distance-coded reference scale
  - $P_{1052}$ or $P_{1053}$
  - $\rightarrow$ distance-coded reference scale

- **Modulo operation (from SW 10.2)**

  Distance-coded referencing in modulo operation is only possible if the following practical, integer number modulo range values apply: $n \cdot 360$ degrees with $n = 1, 2, ...$

  Any modulo range values are not permitted and would result in fault 139 being output.
6.2 Positioning mode (P0700 = 3, from SW 2.1)

The following functions are available in the "positioning" mode:

- Referencing or adjusting
  - Referencing for incremental positioning measuring systems
  - Adjusting absolute position measuring systems
  - Setting the home position

- Programming and selecting traversing blocks
  The max. 64 (256, from SW 10.1) traversing blocks per drive can be freely programmed and are saved in the parameters.
  - How many blocks can be individually selected via terminals?
    Drive A + optional TERMINAL module: all 64/256 blocks
    Drive B: Block 0 or 1 can be selected (1 input terminal)
  - How many blocks can be individually selected via PROFIBUS-DP?
    Drives A and B: all 64/256 blocks

A block contains the following information:
- Block number
- Position
- Velocity
- Acceleration override
- Deceleration override
- Command
- Command parameters
- Mode: Block change enable - positioning mode - IDs

When programming a traversing block, the block enable condition is specified. This means that when starting a block, precisely one block can be executed (for a block enable condition END) or automatic, even for several blocks (if the block enable condition CONTINUE FLYING, CONTINUE WITH STOP, CONTINUE EXTERNAL).
The blocks are executed according to the consecutive block number up to the block with the block enable condition END.

- Position-related switching signals (cams)
  Signals are generated and output as a function of the actual position actual value and parameter setting.

- Jogging
  This operating mode allows speed-controlled traversing in the "positioning" mode. From SW 4.1, the drive can be jogged in the closed-loop position controlled mode (incremental) (refer to Chapter 6.2.9).

- Monitoring functions
  Dynamic following error monitoring, positioning monitoring, standstill monitoring, hardware/software limit switches
6.2.1 Encoder adaptation

Normalization of the encoder signals

The mechanical characteristics of the axis must be specified using the appropriate parameters to adapt the encoder.

The "SIMODRIVE 611 universal" drive calculates the ratio between the travel and the encoder increments from this data, which means that motion on the load side can be determined.

Linear axis with rotary motor encoder

The following parameters are supplied using this configuration:

- P1027.4 = 0: Rotary motor encoder
- P1005 Encoder pulses per revolution (only encoders with sin/cos 1Vpp)
- P0236 Spindle pitch or fictitious spindle pitch
- P0237:8 Encoder revolutions
- P0238:8 Load revolutions

![Diagram of Linear axis with rotary motor encoder (ball screw)](image)

![Diagram of Linear axis with rotary motor encoder (rack/pinion)](image)
6 Description of the Functions

6.2 Positioning mode (P0700 = 3, from SW 2.1)

Linear axis with linear motor encoder

The following parameters are supplied using this configuration:
- P1027.4 = 1: Linear motor encoder
- P1024: Grid divisions, linear measuring system

![Diagram of Linear axis with linear motor encoder](image)

Fig. 6-12 Linear axis with linear motor encoder

Rotary axis with rotary motor encoder

The following parameters are supplied using this configuration:
- P1027.4 = 0: Rotary motor encoder
- P1005: Encoder pulses per revolution
  (only encoders with sin/cos 1Vpp)
- P0237: Encoder revolutions
- P0238: Load revolutions

![Diagram of Rotary axis with rotary motor encoder](image)

Fig. 6-13 Rotary axis with rotary motor encoder

Rotary axis without/with modulo correction (from SW 2.4)

A modular rotary axis is set via the following parameters:
- P0241: Activates the modulo conversion, rotary axis
- P0242: Modulo range, rotary axis
The following secondary conditions must be observed, dependent on the axis type:

### Table 6-11 Restrictions for axis/encoder

<table>
<thead>
<tr>
<th>Axis/encoder</th>
<th>Restrictions</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Linear axis</strong></td>
<td></td>
</tr>
<tr>
<td>Rotary incremental encoder</td>
<td>The axis must be referenced after power-up.</td>
</tr>
<tr>
<td>Linear absolute value encoder (e.g. LC 181)</td>
<td>None</td>
</tr>
<tr>
<td>Rotary absolute value encoder (e.g. EQN 1325, P1021 = 4096)</td>
<td>Overflow after the number of revolutions entered in P1021 (multiturn resolution, motor absolute value encoder). For linear axis with encoder connected to the motor, the following is valid: --&gt; The maximum traversing travel is: P1021 • effective spindle pitch Example: EQN 1325, 10 mm spindle pitch --&gt; max. traversing distance = -20.48 m to 20.48 m • The machine zero can be completely freely selected in the range from -20.48 m to +20.48 m.</td>
</tr>
<tr>
<td><strong>Rotary axis endlessly rotating</strong></td>
<td></td>
</tr>
<tr>
<td>Incremental encoder</td>
<td>The axis must be referenced after power-up.</td>
</tr>
<tr>
<td>Absolute encoder</td>
<td>Motor encoder --&gt; max. revolutions in P1021 (e.g. 4096)&lt;br&gt;Note: The same restrictions apply as for linear axes and rotary absolute value encoders.</td>
</tr>
<tr>
<td>The encoder must be mounted onto the motor. <strong>Caution: Before SW 8.1:</strong>&lt;br&gt;The gear ratio cannot be freely selected.&lt;br&gt;The ratio between the encoder and load must be selected so that the full range of encoder is an integer multiple of the modulo range.&lt;br&gt;The following condition must be fulfilled:&lt;br&gt;P1021 • P0238:8 • 360000 = integer multiple&lt;br&gt;P1021 Multi-turn resolution, absolute value encoder motor&lt;br&gt;P0238:8 Load revolutions&lt;br&gt;P0237:8 Encoder revolutions&lt;br&gt;P0242 Modulo range, rotary axis in MSR&lt;br&gt;Example: P1021 = 4096&lt;br&gt;P0237:0 = 64, P0238:0 = 72&lt;br&gt;P0242 = 360 000&lt;br&gt;are permitted, because 4096 • 72/64 • 360/360 = 4608 is an integer number.&lt;br&gt;Note: When a fault develops, fault 139 is signaled (modulo range and ratio do not match).</td>
<td></td>
</tr>
</tbody>
</table>
### Table 6-11 Restrictions for axis/encoder, continued

<table>
<thead>
<tr>
<th>Axis/encoder</th>
<th>Restrictions</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Rotary axis endlessly rotating (modulo rotary axis)</strong></td>
<td><strong>Absolute encoder</strong></td>
</tr>
<tr>
<td>From SW 8.1: Any gearbox ratio can be selected. (Fault 139 is no longer output.) The following condition applies:</td>
<td></td>
</tr>
<tr>
<td>- Modulo range, Endat enc. (traversing range) ( \geq ) modulo range, load</td>
<td></td>
</tr>
<tr>
<td>[ P1021 \cdot \frac{P0238:8}{P0237:8} \geq 1 ]</td>
<td></td>
</tr>
<tr>
<td>- Practical modulo range values include: ( n \cdot 360 \text{ degr.} ) with ( n = 1, 2, ... )</td>
<td></td>
</tr>
<tr>
<td>- For uneven gearbox factors, ( n ) must be ( 1, 2, ... )</td>
<td></td>
</tr>
<tr>
<td>- From SW 10.2, this will be monitored and if a fault develops, fault 149 is signaled (Incorrect data for modulo axis with absolute encoder).</td>
<td></td>
</tr>
<tr>
<td>If the selected gear ratio results in an uneven gear factor, when the control module is shut down, the actual position is automatically saved.</td>
<td></td>
</tr>
<tr>
<td>This is triggered when the DC link voltage decreases. When engineering the system it must be ensured that the time is sufficient to save the value.</td>
<td></td>
</tr>
<tr>
<td>Configuring:</td>
<td></td>
</tr>
<tr>
<td>- DC link has been connected</td>
<td></td>
</tr>
<tr>
<td>- P1161 = 0 (DC link fixed voltage deactived)</td>
<td></td>
</tr>
<tr>
<td>- P1162 &gt; 0 , e.g. 500 V for a controlled infeed</td>
<td></td>
</tr>
<tr>
<td>- Line supply infeed, terminal 112: Setting-up operation not permitted</td>
<td></td>
</tr>
<tr>
<td>- DC link voltage ( V_{DC \text{link}} &gt; (P1162 + P1164) )</td>
<td></td>
</tr>
<tr>
<td>In order to supply the control board from the DC link, at the infeed/regenerative feedback module, the DC link must be connected to terminals M500 and P500 of terminal strip X181 (refer to Reference /PJU/ Configuration Manual, Drive Converters). This means that when the DC link voltage is either removed or decreases, the energy saved in the DC link can be used to maintain the closed-loop control for a specific time.</td>
<td></td>
</tr>
<tr>
<td>When powering-down or when the DC link voltage decreases, the supply for the closed-loop control must still be maintained until the data save operation has been completed.</td>
<td></td>
</tr>
<tr>
<td>The thresholds to save the absolute value encoder data as a function of the DC link voltage are shown in the following diagram. For reasons of simplicity, the DC link charging and the decrease in the DC link voltage are shown as linear characteristics.</td>
<td></td>
</tr>
<tr>
<td>The DC link voltage starts to increase after powering-up. It is only possible to save the value when powering-down after the value ( P1162 + P1164 ) is exceeded.</td>
<td></td>
</tr>
<tr>
<td>The value is saved if the DC link voltage drops below the value ( P1162 ). However, if the system is not to be shut down and the DC link voltage starts to increase again and operation continues, then the voltage threshold ( P1162 + P1164 ) must be again exceeded in order to activate that the value is saved.</td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong> The voltage thresholds should be configured so that in operation, no unnecessary data save operations are triggered if the DC link fluctuates.</td>
<td></td>
</tr>
</tbody>
</table>

![Diagram](image-url)
Table 6-11 Restrictions for axis/encoder, continued

<table>
<thead>
<tr>
<th>Axis/encoder</th>
<th>Restrictions</th>
</tr>
</thead>
<tbody>
<tr>
<td>VDC link</td>
<td>Saving both drives A and B.</td>
</tr>
<tr>
<td>P1162 (B)</td>
<td>The gear ratio can be freely selected. Example: P0237:0 = 3 P0238:0 = 1</td>
</tr>
<tr>
<td>P1162 (A)</td>
<td>After the measuring system has been adjusted, the position of the load is determined from the absolute position of the motor measuring system by means of the gear ratio (R=P0239:8/P0237:8). Caution: For the functionality “any gear factors”, in parameters P0237[8] and P0238[8] the ratios must be identical in all parameter sets. This means that a gear changeover is not possible. The gear ratio has to be the same in all the parameter sets since the position can otherwise not be determined when parameter sets are changed. In order to determine the clear position of the load, then it must be guaranteed that after being powered-down, the motor can only move within half of the absolute encoder range that can be represented (coast down or manual motion). This is the reason that it is not permissible to use single-turn absolute value encoders. Exceptions are possible if the user can ensure that the drive does not move by more than half of an encoder revolution. Caution: If half of the absolute encoder range that can be represented is exceeded after powering-down, then the assumed actual position is incorrect and after powering-up again no fault or warning is generated! Note: When the DC link voltage starts to ramp-up, the DC link coupling must be maintained in order to supply the electronics. If a fault condition develops, fault 149 is signaled (incorrect data for modulo drive with absolute value encoder and any gearbox factor). In this case, P1162 and P1164 should be checked, as the position value is only saved if the corresponding thresholds have been exceeded or fallen below. The axis must be re-adjusted after fault 149 occurs. Fault 149 is signaled, if the R button (RESET) on the control board is pressed. The axis must be re-adjusted after fault 149 occurs. The DC link must be charged and the enable signals issued. If, during the commissioning, position reference value (setpoint) inversion is selected, then the next step is to carry-out a power on. Only then can the reference point be set. Caution: If the drive goes into regenerative operation after power-down, then this can also cause problems when saving data if the control board is re-activated by the energy fed back. From SW 8.2: As long as the signals were still not available at terminals 48 and 63 of the NE module, the electronics power supply of the control board can be shut down again after the system boots. If Alarm 149 is signaled in cyclic operation while traversing, the cause can be a data transmission error of the absolute encoder. In this case, the encoder including the cable and connectors should be checked.</td>
</tr>
</tbody>
</table>
Table 6-11 Restrictions for axis/encoder, continued

<table>
<thead>
<tr>
<th>Axis/encoder</th>
<th>Restrictions</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rotary axis end-</td>
<td>For incremental encoders, the above condition is not checked. If the mechanical machine design does not fulfill the condition above, then the rotary axis must be re-referenced after each endless operation and when being powered up.</td>
</tr>
</tbody>
</table>
| endlessly rotating (modulo       | The following is valid when evaluating the zero mark:  
| rotary axis)                      |   • The evaluated zero mark must always be located at the same load side position of the modulo range (the ratio is taken into account).                                                                              |
|                                   |   • For several zero marks, one must be defined for evaluation (e.g. set via cams).                                                                                                                     |
| Incremental encoder               |   • If it is not possible to reference the system using the encoder zero mark, then the equivalent zero mark must be used (e.g. BERO at the input with the "equivalent zero mark" function).                 |

Parameter overview

Table 6-12 Parameters for the encoder adaptation

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1027.4</td>
<td>IM configuration, encoder</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The motor encoder type is specified using P1027, bit 4.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 4  Linear measuring system</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 Linear motor encoder</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 0 Rotary motor encoder</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1005</td>
<td>IM encoder pulse number (SRM, ARM)</td>
<td>0</td>
<td>2048</td>
<td>65535</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The parameter is only relevant for rotary motor encoders.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• For encoders with voltage signals sin/cos 1 Vpp (rotary motor encoder)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The encoder pulses per revolution are specified using this parameter.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• for resolvers</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The parameter has no significance.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The &quot;fictitious&quot; encoder pulses are internally calculated from the pole pair number (P1018) of the resolver.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0236</td>
<td>Leadscrew pitch</td>
<td>1</td>
<td>10 000</td>
<td>8 388 607</td>
<td>MSR/rev</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>The spindle pitch is specified in this parameter (e.g. ballscrew spindle with 10 mm/revolution and metric dimension system --&gt; P0236 = 10 000 MSR/rev).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0237:8</td>
<td>Encoder revolutions</td>
<td>1</td>
<td>1</td>
<td>8 388 607</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>
### Table 6-12 Parameters for the encoder adaptation, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0238:8</td>
<td>Load revolutions</td>
<td>1</td>
<td>1</td>
<td>8 388 607</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>
|       | The gearbox ratio between the motor encoder and load is specified using these parameters. \[
\hat{\xi} = \frac{\text{Encoder revolutions}}{\text{Load revolutions}} = \frac{\text{P0237:8}}{\text{P0238:8}} \quad \hat{\xi}: \text{Ratio} \]
|       | **Note:** The parameters are dependent on the parameter set. The effective parameter set can be selected via the “parameter set changeover” input signals. |
| 0241  | Activates the modulo conversion, rotary axis (SRM, ARM) (from SW 2.4) | 0    | 0        | 1    | -    | PO        |
|       | ... activates/de-activates the modulo conversion for a rotary axis.  
1 Modulo conversion activated, the modulo correction is executed according to P0242  
0 Modulo conversion de-activated |
| 0242  | Modulo range, rotary axis (SRM, ARM) (from SW 2.4) | 1    | 360 000  | 100 000 000 | MSC | PO        |
|       | ... defines the modulo range of the rotary axis.  
Practical modulo range values include: \( n \cdot 360 \) degrees with \( n = 1, 2, ... \) |
| 1162  | Minimum DC link voltage                   | 0    | 0        | 800  | V(pk) | immediately |
|       | ... defines the permissible lower limit for the DC link voltage.  
If the DC link voltage falls below the parameterized value, then the stop response, parameterized in P1613, bit 16 is initiated and the encoder data is saved in the FEPROM. |
| 1164  | Hysteresis, DC link voltage (from SW 8.1) | 0    | 50       | 600  | V(pk) | immediately |
|       | ... defines the hysteresis for the DC link voltage.  
This parameter refers to P1162. For absolute value encoders with freely selectable gear ratio, when voltage fluctuations occur, several data save operations of the absolute value encoder data can, to a certain extent, be suppressed. These fluctuations can occur, e.g. when the drive regenerates into the DC link. |
6.2.2 Units for travel, velocity and acceleration

When setting the dimension system (mm, inch or degrees) for a drive configuration in the "Position mode", then the dimension system grid (MSR) is also defined:

Table 6-13 Dimension system and dimension system grid (MSR)

<table>
<thead>
<tr>
<th>Dimension system</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0100 = 1</td>
<td>mm</td>
</tr>
<tr>
<td>P0100 = 2</td>
<td>inch</td>
</tr>
<tr>
<td>P0100 = 3</td>
<td>Degrees</td>
</tr>
</tbody>
</table>

Reader's note

The units of the physical quantities are displayed differently or must be interpreted differently.

- In the parameter list (refer to Chapter A.1) and when reading and writing into parameters via PROFIBUS-DP, there is the dimension system grid (MSR) or a multiple (constant) of the MSR.
  Examples in the mm dimension system:
  - Distance (travel) has the units [MSR]
  - Velocity has the units [c*MSR/min], c = 1
  - Acceleration has the units [1000 MSR/s²]

- For the display unit on the front panel of the control board and for SimoCom U (for the dialog boxes and the expert list), there are converted units.
  Examples in the mm dimension system:
  - Travel (distance) has the units [mm]
  - Velocity has the units [mm/min]
  - Acceleration has the units [mm/s²]

The units for the various dimension systems (mm, inch or degrees) can be listed in the following tables using specific examples.
6.2 Positioning mode (P0700 = 3, from SW 2.1)

In the metric dimension system (P0100 = 1), the following units are used for distance, velocity and acceleration:

<table>
<thead>
<tr>
<th>Physical quantity</th>
<th>Parameter list (A.1)</th>
<th>PROFIBUS-DP (5.6.7)</th>
<th>Display unit (3.2)</th>
<th>SimoCom U (3.3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Distance</td>
<td></td>
<td>µm</td>
<td>mm</td>
<td></td>
</tr>
<tr>
<td>Example: 123.456 mm</td>
<td>123456 [MSR]</td>
<td>123.456 mm</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Example: 4766.176 mm/min</td>
<td>4766176 [c * MSR/min]</td>
<td>4766.176 mm/min</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Example: 4.378 m/s²</td>
<td>4378 [1000 MSR/s²]</td>
<td>4378 mm/s²</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

1) The units are specified as follows in the parameter list (refer to Chapter A.1): [c * MSR/min], c = 1

In the inch dimension system (P0100 = 2) the following units are used for distance, velocity and acceleration:

<table>
<thead>
<tr>
<th>Physical quantity</th>
<th>Parameter list (A.1)</th>
<th>PROFIBUS-DP (5.6.7)</th>
<th>Display unit (3.2)</th>
<th>SimoCom U (3.3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Distance</td>
<td></td>
<td>10⁻⁴ inch</td>
<td>inch</td>
<td></td>
</tr>
<tr>
<td>Example: 123.456 inch</td>
<td>1234567 inch</td>
<td>123.456 inch</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Example: 476.176 inch/min</td>
<td>4761765 [c * MSR/min]</td>
<td>476.176 inch/min</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Example: 243.7 inch/s²</td>
<td>2437 [1000 MSR/s²]</td>
<td>243.7 inch/s²</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

1) The units are specified as follows in the parameter list (refer to Chapter A.1): [c * MSR/min], c = 1
### Units in the degree dimension system

In the degrees dimension system (P0100 = 3) the following units are used for distance, velocity and acceleration:

#### Table 6-16 Units in the degree dimension system

<table>
<thead>
<tr>
<th>Physical quantity</th>
<th>Parameter list (A.1)</th>
<th>PROFIBUS- DP (5.6.7)</th>
<th>Display unit (3.2)</th>
<th>SimoCom U (3.3)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Distance</strong></td>
<td></td>
<td>mdegrees</td>
<td>Degrees</td>
<td></td>
</tr>
<tr>
<td>Example: 123.456 degrees</td>
<td></td>
<td>123456 [MSR]</td>
<td>123.456 degrees</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Velocity</strong></td>
<td></td>
<td>10 mdegrees/min</td>
<td>degrees/min</td>
<td></td>
</tr>
<tr>
<td>Example: 4766.17 degr./min</td>
<td></td>
<td>476617 [c * MSR/min]$^1$</td>
<td>4766.17 degr./min</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Acceleration</strong></td>
<td></td>
<td>degrees/s$^2$</td>
<td>degrees/s$^2$</td>
<td></td>
</tr>
<tr>
<td>Example: 24 degrees/s$^2$</td>
<td></td>
<td>24 [1000 MSR/s$^2$]</td>
<td>24 degrees/s$^2$</td>
<td></td>
</tr>
</tbody>
</table>

1) The units are specified as follows in the parameter list (refer to Chapter A.1): [c * MSR/min], c = 10
6.2.3 Closed-loop position control components

**General**

The closed-loop control of an axis consists of the current and speed control loop and a higher-level position control loop.

The closed-loop position control fulfills the following tasks:

- Controls the velocity of the drive during movement
- The axis is precisely moved to the programmed target position
- Holds the axis at a target position even when disturbances are present

The closed-loop position controller is a P controller. Various function units are provided in its environment, which provide support for special tasks in the motion control, and which can be adapted to the axis characteristics using numerous parameters.

![Diagram of closed-loop position control components](image_url)

**Fig. 6-14** Closed-loop position control components
6.2 Positioning mode (P0700 = 3, from SW 2.1)

The units of an axis are defined using the dimension system setting.

**Note**

- In the following text, the dimension system grid (MSR) term is used as unit of the selected dimension system.
  - The following is valid depending on P0100:
    - 1 MSR = 10^-3 mm or 10^-4 inch or 10^-3 degrees
    - Example: Assumption P0100 = 1 --> 10^3 MSR = 1 mm
  - The dimension system is selected depending on the axis type (linear axis, rotary axis), i.e. for a rotary axis, the dimension system 10^-3 degrees must be parameterized.
  - The dimension system setting must be specified when “SIMODRIVE 611 universal” is commissioned for the first time.

**Recommendation:**

Carry-out the first start-up using the “correct” dimension system, so that it isn’t necessary to later changeover (refer to the following warning information).

If, after “SIMODRIVE 611 universal” has been first commissioned, it is still necessary to changeover the dimension system setting from mm to inch, then the following steps must be executed:

1. Enter the required dimension system into P0100
2. Carry out a POWER ON

During run-up, it is identified, that P0100 ≠ P0101 and automatically, all of the parameters, dependent on the dimension system (refer to Chapter A.1) are converted corresponding to the setting in P0100.

Parameters that are dependent on the dimension system have the following units:

- MSC
- k * MSR/min
- 1 000 MSR/s
- 1 000 MSR/s^2
- 1 000 MSR/s^3
- MSR/rev

Example:

If 254 [mm] is located in P0081:4 and a changeover is made from metric to inch (imperial units), then afterwards, 10 [inch] is located in P0081:4.
### Warning

Although it is possible to subsequently change over the dimension system, we recommend that you do not do this:

When subsequently changing over the dimension system from mm to inch, data, dependent on the dimension system, is converted, whereby rounding-off errors can occur and value limits can be violated.

The conversion is not made when changing between a rotary axis (degrees) and linear axis (mm/inch).

---

**Table 6-17 Parameters for the dimension system setting and changeover**

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0100</td>
<td>Dimension system</td>
<td>1</td>
<td>1</td>
<td>3</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>... specifies the dimension system grid (MSR) which is being used.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 --&gt; 1 MSR = 10^{-3} mm used for linear axes in the metric system</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 2 --&gt; 1 MSR = 10^{-4} mm used for linear axes in the inch (imperial) system</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 3 --&gt; 1 MSR = 10^{-3} degrees used for rotary axes</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Example:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0100 = 1 --&gt; 345 123 MSR = 345.123 mm</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0101</td>
<td>Actual dimension system</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... indicates the currently active dimension system.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>If it is identified at POWER ON that P0100 ≠ P0101, then a dimension system changeover is automatically made.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
The maximum velocity of an axis is defined using this parameter. The drive is limited to this velocity if a higher velocity is specified or programmed via the override for the reference point approach or is programmed in the traversing block. The maximum velocity limit is effective for reference point approach, when executing a traversing block and in the jogging mode.

Maximum acceleration P0103

Maximum deceleration P0104

The maximum acceleration when approaching and the maximum deceleration when braking an axis can be specified, independently of one another, using these two parameters. The selected acceleration and deceleration are effective for reference point approach, when executing a traversing block, and when jogging (jog mode).

Table 6-18 Parameters for the maximum velocity, acceleration and deceleration

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0102</td>
<td>Maximum velocity</td>
<td>1 000</td>
<td>30 000 000</td>
<td>2 000 000 000</td>
<td>c*MSR/min</td>
<td>immediately</td>
</tr>
<tr>
<td>0103</td>
<td>Maximum acceleration</td>
<td>1</td>
<td>100</td>
<td>999 999</td>
<td>1 000 MSR/s²</td>
<td>Vset_0</td>
</tr>
<tr>
<td>0104</td>
<td>Maximum delay</td>
<td>1</td>
<td>100</td>
<td>999 999</td>
<td>1 000 MSR/s²</td>
<td>Vset_0</td>
</tr>
</tbody>
</table>

... defines the maximum velocity of the axis in the "Positioning" mode.

... defines the maximum acceleration/deceleration of the axis when approaching/braking.

v: Velocity  
a : Acceleration  
t: Time

Maximum velocity (P0102)

Actual velocity

Maximum acceleration (P0103)

Maximum deceleration (P0104)

Note:
- The maximum acceleration/deceleration is a step function.
- The effective acceleration or deceleration can be set in the traversing block using an override (P0083:64/256 or P0084:64/256).
Jerk limiting
P0107 (from SW 3.1)

Acceleration and deceleration are step-like if jerk limiting is not used.
Using jerk limiting, a ramp-type increase can be parameterized for both quantities, so that approach and braking are "smooth" (jerk-limited).

Applications
Jerk limiting can be used, e.g. for positioning tasks using liquids or generally to reduce the mechanical stressing on an axis.

Table 6-19  Jerk limiting parameters

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0107</td>
<td>Jerk limitation</td>
<td>0</td>
<td>0</td>
<td>10 000</td>
<td>1 000 MSR/s^3</td>
<td>Vset_0</td>
</tr>
</tbody>
</table>

The duration of the acceleration ramp (jerk time TR) is calculated from the higher value of the maximum acceleration (P0103), the maximum deceleration (P0104) and the selected jerk limiting (P0107).

\[
TR [s] = \frac{a_{\text{max}} [10^3 \text{ MSR/s}^2]}{r [10^3 \text{ MSR/s}^3]},
\]

where:
- \( v \): Velocity
- \( a_{\text{max}} \): Acceleration (higher value from P0103 and P0104)
- \( r \): Jerk
- \( TR \): Jerk time (calculated jerk time: refer to P1726)

0  Jerk limiting off
> 0 Jerk limiting on, the selected value is effective (refer to P1726)

Note:
The jerk is internally limited to the appropriate jerk time of 200 ms.
### Table 6-19  Jerk limiting parameters, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- The following is valid for this diagram: Acceleration and deceleration have been set the same.
- If, when setting the jerk limiting, the warning 870 "Jerk: Jerk time is limited" is displayed, then the actual motion is "harder" than that set in P0107.
- For traversing motion with a direct transition between acceleration and deceleration (i.e. jerk time \( T_R \) is greater than the constant velocity phase), jerk \( r \) can increase up to twice the parameterized jerk.

<table>
<thead>
<tr>
<th>1726</th>
<th>Calculated jerk time</th>
<th>-</th>
<th>-</th>
<th>-</th>
<th>ms</th>
<th>RO</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>... indicates the calculated, current effective jerk time.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- The jerk time is internally limited to 200 ms.
- From SW 13.1 and higher, the jerk time is no longer permanently limited to 200 ms, but depends on the interpolation sampling time.
- The jerk time is calculated with: interpolation time \([\text{ms}]\) \( \div 200 \)
- Therefore, for example, a maximum jerk time of 4 seconds is obtained with an interpolation sampling time of 20 ms. The maximum standard value is 800 ms (interpolation sampling time 4 ms).

### Table 6-20  Examples for acceleration, deceleration and jerk limiting

<table>
<thead>
<tr>
<th>( P0103 )^1) (Maximum acceleration) [1000 ( \text{MSR/s}^2 )]</th>
<th>( P0104 )^1) (Maximum deceleration) [1000 ( \text{MSR/s}^2 )]</th>
<th>( P0107 )^1) (Jerk limiting) [1000 ( \text{MSR/s}^3 )]</th>
<th>Which jerk time is effective for acceleration and deceleration?</th>
</tr>
</thead>
<tbody>
<tr>
<td>( = 2 000 ) ( \rightarrow 2 \text{ m/s}^2 )</td>
<td>( = 2 000 ) ( \rightarrow 2 \text{ m/s}^2 )</td>
<td>( = 100 000 ) ( \rightarrow 100 \text{ m/s}^3 )</td>
<td>( a_{\text{max}} = 2 \text{ m/s}^2 ) ( \rightarrow \text{Jerk time} = 20 \text{ ms} )</td>
</tr>
<tr>
<td>( = 8 000 ) ( \rightarrow 8 \text{ m/s}^2 )</td>
<td>( = 2 000 ) ( \rightarrow 2 \text{ m/s}^2 )</td>
<td>( = 100 000 ) ( \rightarrow 100 \text{ m/s}^3 )</td>
<td>( a_{\text{max}} = 8 \text{ m/s}^2 ) ( \rightarrow \text{Jerk time} = 80 \text{ ms} )</td>
</tr>
<tr>
<td>( \text{The jerk time of} 80 \text{ ms is effective for acceleration and deceleration.} )</td>
<td>( \text{The jerk time of} 80 \text{ ms is effective for acceleration and deceleration.} )</td>
<td>( \text{The jerk time of} 80 \text{ ms is effective for acceleration and deceleration.} )</td>
<td></td>
</tr>
<tr>
<td>( = 2 000 ) ( \rightarrow 2 \text{ m/s}^2 )</td>
<td>( = 8 000 ) ( \rightarrow 8 \text{ m/s}^2 )</td>
<td>( = 100 000 ) ( \rightarrow 100 \text{ m/s}^3 )</td>
<td>( a_{\text{max}} = 8 \text{ m/s}^2 ) ( \rightarrow \text{Jerk time} = 80 \text{ ms} )</td>
</tr>
<tr>
<td>( \text{The jerk time of} 80 \text{ ms is effective for acceleration and deceleration.} )</td>
<td>( \text{The jerk time of} 80 \text{ ms is effective for acceleration and deceleration.} )</td>
<td>( \text{The jerk time of} 80 \text{ ms is effective for acceleration and deceleration.} )</td>
<td></td>
</tr>
<tr>
<td>( = 30 000 ) ( \rightarrow 30 \text{ m/s}^2 )</td>
<td>( = 25 000 ) ( \rightarrow 25 \text{ m/s}^2 )</td>
<td>( = 100 000 ) ( \rightarrow 100 \text{ m/s}^3 )</td>
<td>( a_{\text{max}} = 30 \text{ m/s}^2 ) ( \rightarrow \text{Jerk time} = 300 \text{ ms} )</td>
</tr>
<tr>
<td>( \text{A warning is output, and the jerk is limited corresponding to the jerk time of} 200 \text{ ms for acceleration and deceleration.} )</td>
<td>( \text{A warning is output, and the jerk is limited corresponding to the jerk time of} 200 \text{ ms for acceleration and deceleration.} )</td>
<td>( \text{A warning is output, and the jerk is limited corresponding to the jerk time of} 200 \text{ ms for acceleration and deceleration.} )</td>
<td></td>
</tr>
<tr>
<td>P0103(^1) (Maximum acceleration) [1000 MSR/s(^2)]</td>
<td>P0104(^1) (Maximum deceleration) [1000 MSR/s(^2)]</td>
<td>P0107(^1) (Jerk limiting) [1000 MSR/s(^3)]</td>
<td>Which jerk time is effective for acceleration and deceleration?</td>
</tr>
<tr>
<td>-----------------------------------------------------</td>
<td>-----------------------------------------------------</td>
<td>-----------------------------------------------------</td>
<td>---------------------------------------------------------------</td>
</tr>
<tr>
<td>(= 8 \ 000) (-\rightarrow) 8 m/s(^2)</td>
<td>(= 2 \ 000) (-\rightarrow) 2 m/s(^2)</td>
<td>(= 200 \ 000) (-\rightarrow) 200 m/s(^3)</td>
<td>(a_{max} = 8 \text{ m/s}^2) (-\rightarrow) Jerk time = 40 ms. The jerk time of 40 ms is effective for acceleration and deceleration.</td>
</tr>
</tbody>
</table>

1) Prerequisites:
There is a metric linear axis (dimension system P0100 = 1 \(-\rightarrow\) 1000 MSR = 1 mm)
Velocity override

P0111

The velocity of an axis can be influenced using the velocity override or also known as just override.

**Note**

The maximum traversing velocity is limited by the maximum velocity set in P0102.

The override has no effect on the acceleration/deceleration, i.e. when the override is doubled, the axis velocity is doubled, but the positioning time is not halved.

How can the override be entered?

The override can be entered as follows:

- Analog input, terminals 56.x/14.x
  
  The following prerequisites must be fulfilled to enter an override via the analog input:
  
  - Set P0607 to 2 (refer to Chapter 6.6):
    
    The analog input is declared as override input.
  
  - Set P0111 and P0112:
    
    The reference voltage and normalization is defined.
  
  - SimoCom U may not have the master control.

- PROFIBUS-DP
  
  The override is entered via the "Over" control word.

- SimoCom U
  
  SimoCom U must have the master control to set an override.

Table 6-21 Parameter for override via analog input, terminal 56.x/14.x

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0111</td>
<td>Normalization voltage, override</td>
<td>5.0</td>
<td>10.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td>0112</td>
<td>Normalization, override</td>
<td>0</td>
<td>100</td>
<td>255</td>
<td>%</td>
<td>immediately</td>
</tr>
</tbody>
</table>

P0111: ... defines at which input voltage the override, specified in P0112 is valid.

P0112: ... defines which override is valid when applying the voltage specified in P0111.

 Override [\%]  
 P0112  
 Max.  

\[\text{Override} = \frac{\text{V terminal 56.x/14.x}}{12.5\text{ V}} \times 100\%\]

Standard values:

- P0111 = 10.0 V
- P0112 = 100%

\[\Rightarrow 10\text{ V at term. 56.x/14.x} \triangleq 100\%\ \text{override}\]

\[0\text{ V at term. 56.x/14.x} \triangleq 0\%\ \text{override}\]

**Note:**

For analog input, terminal 56.x/14.x, in addition the following parameters are effective (refer to Chapter 6.6):

- P0608 Inversion, terminal 56.x/14.x
- P0609 Smoothing time, terminal 56.x/14.x
- P0610 Offset correction, terminal 56.x/14.x
Limit switch monitoring functions

For "SIMODRIVE 611 universal", the following limit switch monitoring functions can be used:

- Hardware limit switches (HW limit switch)
- Software limit switches (SW limit switches)

The limit switch monitoring functions can be used to limit the operating range or to protect the machine.

![Diagram of limit switch monitoring functions](image)

Fig. 6-15 Overview of the limit switch monitoring functions

Hardware limit switch (HW limit switch)

There is a hardware limit switch for every axis and every approach direction.

The HW limit switches must be connected to an input terminal with the following function numbers:

- "Plus hardware limit switch" function --> function number 81
- "Minus hardware limit switch" function --> function number 82

--> Refer to Chapter 6.4.2

Traverse to a hardware limit switch?

When traversing to a hardware limit switch, the associated input signal is set and the following response is automatically initiated:

- The axis is braked with the deceleration level set in P0104 (maximum deceleration) and therefore comes to a standstill after the limit switch. The drive remains in the closed-loop controlled mode.
- One of the following faults is signaled:
  - Fault 140 Minus hardware limit switch
  - Fault 141 Plus hardware limit switch
- The jogging key is inhibited in the direction of motion
- The traversing block is exited
How do you move away from a hardware limit switch?

If an axis is located at a hardware limit switch, then it can be moved away again as follows:

- Return the axis to the valid traversing range
  - Move away jogging in the opposite direction to the approach direction or
  - Withdraw the controller enable and move the drive away manually
- Withdraw controller enable (terminal 65.x)
- Acknowledge the fault

The minus software limit switch (P0315) and the plus software limit switch (P0316) must be appropriately set to limit the working range or to protect the machine.

Notice

The software limit switches only become active if the following conditions exist:

- The function is activated via P0314
- The axis is referenced ("reference point set" output signal)

Only then is it certain that the axis will be immediately stopped if it attempts to move out of the permissible range.

Note

The SW limit switch monitoring is dependent on the axis type as follows:

- For a linear axis or rotary axis with modulo correction, the following is valid:
  The software limit switches can be activated via P0314 and set via P0315 and P0316.
- For rotary axis with modulo correction (from SW 2.4), the following is valid:
  The software limit switches are automatically de-activated. If monitoring is parameterized, it has no effect.

Output signals

The status of a software limit switch is displayed using the following signals (refer to Chapter 6.4.5):

- "Minus software limit switch actuated" output signal or
- "Plus software limit switch actuated" output signal
When traversing to a software limit switch, the following response is automatically initiated:

- **Behavior in the jog mode (via velocity)**
  - When the axis reaches the software limit switch, it is braked with the deceleration level set in P0104 (maximum deceleration) and therefore comes to a standstill after the limit switch.
  - One of the following faults is signaled:
    - Fault 132 (drive is located after the minus software limit switch)
    - Fault 133 (drive is located after the plus software limit switch)
  - The jog button is inhibited in the approach direction.

- **Behavior in the positioning mode (traversing blocks) and for incremental jogging operation (from SW 4.1)**
  - The axis comes to a standstill directly at the software limit switch.
  - The traversing block or jogging operation is interrupted.
  - One of the following faults/warnings is signaled:
    - P0118.0 = 0 (standard, before SW 4.1)
    - Fault 119 (PLUS software limit switch actuated)
    - Fault 120 (MINUS software limit switch actuated)
    - P0118.0 = 1 (from SW 4.1)
    - Warning 849 (PLUS software limit switch actuated)
    - Warning 850 (MINUS software limit switch actuated)
  - When a target position is parameterized after a software limit switch, the traversing block is not started and fault 101 or 102 is output.

If an axis is at a software limit switch, then it can be returned to the valid traversing range as follows:

- **P0118.0 = 0 (standard, before SW 4.1)**
  - Return the axis to the valid traversing range
    - In the jogging mode (via velocity), move away in the direction opposite to the approach direction
    - Withdraw the controller enable and move the drive away manually
    - Withdraw controller enable (terminal 65.x)
    - Acknowledge the fault

- **P0118.0 = 1 (from SW 4.1)**
  - In the jogging mode (incremental or via velocity), move away in the direction opposite to the approach direction
    - Move away, with the traversing block in the opposite direction to the approach direction
If an axis is located after a software limit switch, then it is only possible to move away in the opposite direction to the approach direction in the jog mode via velocity.

Table 6-22 Parameters for software limit switch

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0118</td>
<td>Software limit switch</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>configuration</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The configuration for software limit switch reached is defined using these parameters.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 0 = 1 Software limit switch reached with warning 849/850 (from SW 4.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Bit 0 = 0 Software limit switch reached with fault 119/120 (before SW 4.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0314</td>
<td>Activate software limit switch</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PrgE</td>
</tr>
<tr>
<td></td>
<td>The software limit switches can be activated/de-activated using these parameters.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 Software limit switch active</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 0 Software limit switch inactive (e.g. this is necessary for a rotary axis)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0315</td>
<td>Minus software limit switch</td>
<td>-200 000 000</td>
<td>-200 000 000</td>
<td>200 000 000</td>
<td>MSC</td>
<td>PrgE</td>
</tr>
<tr>
<td>0316</td>
<td>Plus software limit switch</td>
<td>-200 000 000</td>
<td>200 000 000</td>
<td>200 000 000</td>
<td>MSC</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

The minus and plus positions for the software limit switches are set using these parameters. **Note:** The following applies: P0315 (minus software limit switch) < P0316 (plus software limit switch)
Position-related switching signals (cams)
P0310
P0311

Using the position-dependent switching signals 1 and 2, cams can be simulated without any mechanical equipment (e.g. at inaccessible positions), dependent on the actual position value.

The absolute cam switching positions are entered via parameter, and the associated cam switching signals are output as output signal.

Notice

Only after the axis has been referenced, is it guaranteed that the cam switching signals really do have a "true" position reference when output.

This means that an AND logic operation must be externally established between the "Reference point set/reference point not set" output signal and the "Cam switching signals 1, 2" output signals (e.g. using an external PLC).

Table 6-23 Parameters for position-related switching signals (cams)

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0310</td>
<td>Cam switching position 1</td>
<td>-200 000 000</td>
<td>0</td>
<td>200 000 000</td>
<td>MSC</td>
<td>immediately</td>
</tr>
<tr>
<td>0311</td>
<td>Cam switching position 2</td>
<td>-200 000 000</td>
<td>0</td>
<td>200 000 000</td>
<td>MSC</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The cam switching positions 1 and 2 are set using these parameters.

The following assignment applies:
P0310 (cam switching position 1) --> cam switching signal 1
P0311 (cam switching position 2) --> cam switching signal 2

Note:
Also refer under the index entry "Output signal, cam switching signals 1 and 2"
When mechanical force is transferred between a machine part and its drive, generally backlash occurs. If the mechanical system was to be adjusted/designed so that there was absolutely no play, this would result in high wear. Thus, backlash (play) can occur between the machine component and the encoder.

For axes with indirect position sensing, mechanical backlash results in a falsification of the traversing distance, as, at direction reversal, the axis travels either too far or not far enough corresponding to the absolute value of the backlash.

**Note**

The backlash compensation is active, after
- The axis has been referenced for incremental measuring systems
- The axis has been adjusted for absolute measuring systems

When backlash compensation is switched--in and there is a negative traversing direction, then a direction of reversal can occur - however the correct position is approached. Remedy: Delete bit 8 in parameter P1004.

In order to compensate the backlash, the determined backlash must be specified in P0201 with the correct polarity.

At each direction of rotation reversal, the axis actual value is corrected dependent on the actual traversing direction.

**Backlash compensation P0201**

The encoder actual value leads the actual value (table) at direction reversal.
- -> the table doesn’t travel far enough  
- -> **positive backlash** (standard case)

The actual value (table) leads the encoder actual value at a direction of rotation reversal.
- -> the table travels too far  
- -> **negative backlash**

---

Fig. 6-16  Positive and negative backlash compensation
### Table 6-24 Parameters for backlash compensation

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0201</td>
<td>Backlash compensation</td>
<td>-20 000</td>
<td>0</td>
<td>20 000</td>
<td>MSC</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... switches the backlash compensation in/out, and defines the absolute backlash amount for a positive or negative backlash.

- 0: The backlash (play) compensation is disabled
- > 0: Positive play (standard situation) For a direction of rotation reversal, the encoder actual value leads the actual value (table). The table does not travel far enough.
- < 0: Negative play The actual value (table) leads the encoder actual value at direction reversal. The table travels too far.

**Note:**
- **Search for reference:** When is the compensation value switched-in?
  When the zero mark is detected, backlash compensation is activated, only for P0173 = 1 (no reference cams).
  - If the axis continues to move: in the same direction after the reference point approach \(\rightarrow\) then a compensation value is not entered
  - in the opposite direction \(\rightarrow\) the compensation value is entered when the velocity set-point reverses

- **Reference point setting:** When is the compensation value switched-in?
  The behavior when first traversing after the "Set reference point" in the positive or negative direction depends on the setting "Reference point approach - plus/minus" (P0166).

<table>
<thead>
<tr>
<th>P0166</th>
<th>Behavior</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0 Traversing in the pos. direction (\rightarrow) a comp. value is not entered\n</td>
</tr>
<tr>
<td>1</td>
<td>Traversing in the pos. direction (\rightarrow) a comp. value is immediately entered\n</td>
</tr>
</tbody>
</table>

- = 1 \(\rightarrow\) Negative direction
- = 0 \(\rightarrow\) Positive direction

If the reference point is simply set again (new command, with and without withdrawing the bit "axis is referenced"), then for backlash compensation, the system acts as if the reference point was not set again.

The behavior mentioned above is only seen after power-on or POWER-ON RESET!

- **Absolute value encoder adjusted:** When is the compensation value switched-in?
  The behavior when first traversing after power-on, depends on the setting for "referencecams - with/without" (P0173) and "Direction reference point approach - positive/negative" (P0166).
  The following applies:

<table>
<thead>
<tr>
<th>P0173</th>
<th>P0166</th>
<th>Behavior</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>Traversing in the pos. direction (\rightarrow) a comp. value is immediately entered\n</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>Traversing in the pos. direction (\rightarrow) a comp. value is not entered\n</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>Traversing in the pos. direction (\rightarrow) a comp. value is not entered\n</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>Traversing in the pos. direction (\rightarrow) a comp. value is immediately entered\n</td>
</tr>
</tbody>
</table>

- = 1 \(\rightarrow\) Negative direction
- = 0 \(\rightarrow\) Positive direction
- = 1 \(\rightarrow\) No reference cams used
- = 0 \(\rightarrow\) Reference cams used
The position loop gain (Kv factor) defines which following error is obtained at which axis traversing velocity. The mathematical (proportional) equation is as follows:

\[ \text{Kv factor} = \frac{\text{Speed} \times 1000 \text{[min]}}{\text{Following error} \times 1000 \text{[mm]}} = \frac{1 \text{[m/min]}}{1 \text{[mm]}} = 1000 \text{[min]} \]

The Kv factor influences the following important characteristic quantities of the axis:
- Positioning accuracy and holding control
- Uniformity of the motion
- Positioning time

The better the axis design (high degree of stiffness), then the higher is the achievable Kv factor, and therefore the better the axis parameters from the technological perspective (lower following error).

**Note**

The stable position loop gain which can actually be set for the complete position control loop is influenced by time constants as well as backlash (play) and spring elements in the control loop.

The required Kv factor is entered in P0200:8. The actual (measured) Kv factor is displayed in P0031.

Table 6-25 Parameters for the position loop gain

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0200:8</td>
<td>Kv factor (position loop gain)</td>
<td>0.0</td>
<td>1.0</td>
<td>300.0</td>
<td>1000\text{[min]}</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The Kv factor defines at which traversing velocity of the axis which following error is obtained.

Low Kv factor: Slow response to setpoint–actual value difference ∆s is high
High Kv factor: Fast response to setpoint–actual value difference, ∆s is small

Examples:Kv factor Significance
- = 0.5 at v = 1 m/min an ∆s of 2 mm
- = 1 is obtained at v = 1 m/min an ∆s of 1 mm
- = 2 is obtained at v = 1 m/min an ∆s of 0.5 mm is obtained

**Note:**

The following parameters are available for position loop gain diagnostics:
- P0029 Following error
- P0030 System deviation, position controller input
- P0031 Actual Kv factor (position loop gain)

Refer under the index entry "Diagnostics of the motion status"
For speed pre-control, in addition a speed/velocity setpoint can be directly entered at the speed controller input. This additional setpoint can be weighed with a factor.

The speed pre-control improves the control characteristics of the position control loop in so much that for a constant velocity, the following error is almost completely reduced, i.e. to almost zero.

### Setting the speed pre-control

The following prerequisites must be fulfilled to set the speed pre-control:

- The current, speed and position control loop must be optimized.

After that, the speed pre-control can be set as follows:

1. Set P0203 = 1 ---> this activates speed pre-control
2. Set P0204:8 to 100 % (this is the standard value)
3. P0206:8 = Set the approximate value from the sum of P1502:8 (time constant, speed setpoint filter 1) and P1503:8 (time constant, speed setpoint filter 2)
4. P0205:8 = determine the value

Setting goal is: Positioning without undershoot or overshoot

Recommendation:

- Traverse the axis using the traversing blocks, and evaluate positioning by plotting the position actual value using the trace function (refer to Chapter 7.4.2).

With the trace function, the approach characteristics of the axis can be zoomed in using the appropriate scaling and then evaluated.
Table 6-26 Parameters for speed pre-control

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0203</td>
<td>Speed pre-control mode</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... the speed pre-control can be activated/de-activated.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>1 Speed pre-control active</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>0 Pre-control not active</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0204:8</td>
<td>Factor, speed pre-control</td>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... the supplementary speed setpoint which was entered is weighted.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>When the axis control loop has been optimally set as well as an equivalent time constant of the speed control loop (P0205, P0206) precisely determined, the pre-control factor has the value 100%.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0205:8</td>
<td>Balancing filter, speed pre-control</td>
<td>0.0</td>
<td>0.0</td>
<td>10.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>(dead time)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... allows the performance of the speed control loop to be simulated with a dead time.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong> The entered value is limited to two position controller clock cycles (P1009) (1 position controller clock cycle is, as standard = 2 ms, refer to Chapter 4.6).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0206:8</td>
<td>Balancing filter, speed pre-control</td>
<td>0.0</td>
<td>0.0</td>
<td>100.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>(PT1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... allows, in addition to P0205:8 the performance of the speed control loop to be simulated using a PT1 filter (low-pass filter).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... allows a possibly active speed setpoint smoothing to be better emulated (PT1).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0210:8</td>
<td>Time constant, position reference value</td>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>filter</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... is the time constant of the PT1 position reference value filter.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The effective Kv factor is reduced using the filter (position loop gain).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Applications:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• To reduce the pre-control dynamic performance</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Example: Kv factor = 3 * 1000/min -- &gt; P0210:8 = 20.0 ms</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• Jerk limiting</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>This makes it possible to achieve smoother control characteristics with improved response to disturbances.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1012.8</td>
<td>Average value filter, speed setpoint</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... selects whether the speed setpoint steps from the position controller output (position controller clock cycle) are interpolated in the speed controller clock cycle (adapted).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 Average value filter, speed setpoint filter on (standard)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Disadvantage: Delay in the position control loop by half a position controller clock cycle.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 0 Average value filter, speed setpoint off</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Direction adaptation
P0231
P0232

The position actual value and the position reference value can be adapted using these parameters.

The direction adaptation should be made as follows:

1. The position control sense is not correct?
   Effect:
   A fault is immediately signaled when moving the axis (e.g.: 131 (following error too high) or 135 (standstill monitoring has responded).
   Remedy:
   Invert the position actual value in P0231; POWER ON and check the control sense.

2. The direction of motion is not correct?
   Effect:
   The axis does not move in the required direction.
   Remedy:
   Invert the position reference value in P0232; POWER ON, and check the direction of motion.

Table 6-27 Parameters for direction adaptation

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0231</td>
<td>Position actual value inversion</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>

... the control sense of the position controller is established.

= 1 Position actual value inversion
= 0 No position actual value inversion

Note:
If the control sense of the position controller is not correct, then the position actual value must be inverted. The direction of motion is set using P0232.

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0232</td>
<td>Position reference value inversion</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>

... the required motion direction is selected.

= 1 Position reference value inversion
Positive motor speed --> the position is decreased (negative position count direction)
= 0 No position reference value inversion
Positive motor speed --> the position is increased (positive position count direction)

Note:
The position controller control sense is not influenced, i.e. it is internally taken into consideration.
Dynamic following error monitoring

When traversing an axis, a difference is obtained between the position reference value and position actual value, dependent on the following quantities (following error):

- The instantaneous traversing velocity
- The stabilizing characteristics of the position control loop, i.e. of the selected position control loop gain (Kv factor, P0200:8)

Fluctuations of the following error for a traversing axis signify inaccurate positioning.

In order to be able to check these fluctuations, the following error monitoring must be appropriately set.

Mode of operation

The dynamic following error monitoring is activated/de-activated with P0318:8, and is based on the continuous comparison between the measured and a calculated position actual value.

To calculate the following error, a model is used, which simulates the dynamic performance of the position control loop.

A tolerance bandwidth (P0318:8) for the maximum following error deviation is permitted so that the monitoring does not respond incorrectly as a result of slight speed fluctuations (caused by load changes or by a control loop model error).

![Fig. 6-18 Following error](image)

Fault

When the monitoring function responds, the drive is braked down to standstill with the deceleration set in P0104 (max. deceleration) and fault 131 (following error too high) is output.

A changeover is made into the follow-up mode.

Table 6-28 Parameters for the dynamic following error monitoring

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0318:8</td>
<td>Dynamic following error monitoring tolerance</td>
<td>0</td>
<td>1 000</td>
<td>200 000 000</td>
<td>MSC</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The parameter defines the maximum deviation between the measured and the calculated position actual value before an error is signaled.

The tolerance bandwidth is intended to prevent the dynamic following error monitoring incorrectly responding caused by slight speed fluctuations resulting from operational control sequences (e.g. load surges).

0 Dynamic following error monitoring is de-activated

≥ 1 The dynamic following error monitoring is active with this value
Standstill monitoring

Using the standstill monitoring function, it can be detected when the axis leaves the target position (under load, for hanging axes, etc.).

Mode of operation

The standstill monitoring time (P0325) is started after a motion block has been completed (position reference value = target reference value).

After the delay time has expired, it is cyclically monitored as to whether the position actual value remains within the defined standstill window (P0326).

Fault

When the standstill monitoring function responds, the drive is braked down to standstill with the deceleration level set in P0104 (maximum deceleration) and fault 135 (standstill monitoring) is signaled. A changeover is made into the follow-up mode.

Switching-off

The standstill monitoring function is disabled, if

- a new traversing block is started
- Follow-up mode is selected
- The standstill window has the value zero (P0326 = 0)
### Table 6-29 Parameters for the standstill monitoring function

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0325</td>
<td>Standstill monitoring time</td>
<td>0</td>
<td>400</td>
<td>100 000</td>
<td>ms</td>
<td>immediately</td>
</tr>
</tbody>
</table>

This parameter defines the time after which, when approaching the position, the following error must be within the standstill window (P0326).

**Note:**
- The standstill monitoring time is rounded-off in the drive to an integer multiple of the position controller clock cycle (P1009).
- If a larger value is entered in P0325 than in P0320, this is limited internally in the drive to P0320.

| 0326| Standstill window                | 0    | 200      | 20 000 | MSC  | immediately |

This parameter defines the standstill window, within which the position actual value must be located after the standstill monitoring time has expired (P0325).

0 Standstill monitoring is de-activated

≥ 1 Standstill monitoring is active with this value

There are the following differences between the standstill and positioning monitoring:

- **Standstill monitoring**
  - After the standstill monitoring time has expired, the system *cyclically* checks whether the axis remains within the standstill window around the target position.
  - **Objective:** Continually checks that the position is maintained

- **Position monitoring**
  - For this monitoring function, after the position monitoring time has expired, it is checked *once* whether the actual position lies within the positioning window around the target position.
  - **Objective:** Single check as to whether the position has been reached with sufficient accuracy

**Note**

The following is valid when setting the standstill and position monitoring:

- Standstill monitoring time ≤ position monitoring time (P0325 ≤ P0320)
- Standstill window ≥ positioning window (P0326 ≥ P0321)
The position monitoring can be used to identify when the target position is precisely approached.

In order to ensure that an axis is positioned within a specific time, after a motion block has been completed (partial position reference value = 0, \( \approx \) time \( t_1 \) in Fig. 6-20) the position monitoring time (P0320) is started. After this time has expired, it is checked once as to whether the position actual value lies within the positioning window (P0321).

![Position monitoring diagram](image_url)

**Fig. 6-20  Position monitoring**

**Table 6-30 Explanation of curves a, b and c**

<table>
<thead>
<tr>
<th>Curve</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>a</td>
<td>After the target position has been reached in ( t_1 ) the interpolator starts the positioning monitoring time.</td>
</tr>
<tr>
<td>b</td>
<td>From time ( t_2 ) the position actual value is within the positioning window. Positioning is considered as having been completed.</td>
</tr>
<tr>
<td>c</td>
<td>After the positioning monitoring time has expired in ( t_3 ), the position actual value lies outside the positioning window. This results in an error.</td>
</tr>
</tbody>
</table>

The following output signals are available (description, refer under the index entry "Output signal..."):
- Output signal, "setpoint static"
- Output signal, "reference position reached"
6.2 Positioning mode (P0700 = 3, from SW 2.1)

Fault

When the monitoring function responds, the drive is shutdown and fault 134 is issued (positioning monitoring). A changeover is made into the follow-up mode.

Table 6-31 Parameters for the positioning monitoring function

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0320</td>
<td>Positioning monitoring time</td>
<td>0</td>
<td>1 000</td>
<td>100 000</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>This parameter defines the time when approaching the position, after which the following error must be within positioning window (P0321).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Note: The following applies when setting the positioning and standstill monitoring: Positioning monitoring time (P0320) ≥ Standstill monitoring time (P0325)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0321</td>
<td>Positioning window</td>
<td>0</td>
<td>40</td>
<td>20 000</td>
<td>MSC</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>This parameter defines the positioning window within which the position actual value must be located after the positioning monitoring time has expired (P0320).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>0  Positioning monitoring is de-activated</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>≥ 1  Positioning monitoring is active with this value</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The following applies when setting the positioning and standstill monitoring: Positioning window (P0321) ≤ Standstill window (P0326)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The following is valid if the specified positioning window is not reached:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The motion block has not been completed</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- It is not possible to traverse the axis any further</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- After the time in P0320 has expired, fault 134 is issued (positioning monitoring)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The size of the positioning window influences the block change time. The lower that this tolerance is selected, the longer positioning takes. It also takes that much longer until the next traversing block can be executed.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Follow-up mode

If an axis is in the follow-up mode, then the control is disabled and its position reference value tracks the actual position actual value.

The actual position of the axis is still being sensed - this means that it is not necessary to re-home (re-reference) the axis when the follow-up mode (correcting mode) is cancelled.

Selection, signals

In the follow-up mode, there are various selection possibilities and signals:

- The follow-up mode is selected, if
  - controller enable terminal 65.x is withdrawn
  - the "follow-up mode" input signal is set to "1"
  - Jogging operation (jogging 1, 2) is active (when jogging via the velocity, not for incremental jogging)
  - When a fault develops, automatically using "SIMODRIVE 611 universal" (only for a STOP 0, I or II stop response)

- In all cases, the checkback signal is realized using the output signal "follow-up mode active".

Effect

The "follow-up mode" input signal is only relevant if the controller enable (terminal 65.x) of the drive is withdrawn or if the controller is re-enabled.

- Follow-up mode = 1 (so-called tracking)  
  When the axis-specific controller enable is withdrawn (terminal 65.x), the position reference value of the associated axis continually tracks the position actual value. In this status, the "follow-up mode active" output signal = "1".

  If the controller is re-enabled, all additional axis movements start at the actual position which may have changed.

- Follow-up mode = 0 (stopping)  
  No follow-up operation is activated when the controller enable is withdrawn and the following error, positioning and standstill monitoring are disabled. This means that the old position reference value is kept. If the axis is pushed out of its position, a following error occurs between the position reference value and the position actual value, which is compensated when the controller enable is set. In this status, the "follow-up mode active" output signal = "0". However, when the monitoring function is enabled, follow-up mode is activated and the position reference value follows the position actual value.

  All additional axis movements start at the reference position, which was available before the controller enable was withdrawn.
6.2 Positioning mode (P0700 = 3, from SW 2.1)

Note
If the follow-up mode is active and the input signal "follow-up mode" is set, then the dynamic following error monitoring, the position monitoring and the standstill monitoring are not effective.

Diagnostics: Motion status of the axis
The following parameters provide information about the actual motion status of an axis:

- P0020 Position reference value
- P0021 Position actual value
- P0022 Distance to go
- P0023 Velocity setpoint
- P0024 Velocity actual value
- P0025 Effective override
- P0026 Position act. value, ext. block change (from SW 3.1)
- P0029 Following error
- P0030 System deviation, position controller input
- P0031 Actual Kv factor (position loop gain)

Reader's note
The parameters are displayed and described in the parameter list is Chapter A.1.
6.2.4 Referencing and adjusting

Definitions
In order that the “SIMODRIVE 611 universal” drive precisely identifies the machine zero point after power-on, the axis measuring system must be synchronized with the machine.

This synchronization is realized when referencing incremental measuring systems or adjusting absolute measuring systems.

Notice
The following functions are ineffective for axes which are either not referenced not adjusted:

- Software limit switches
- Backlash compensation
- Start the traversing blocks

6.2.5 Referencing for incremental measuring systems

General
For axes with incremental measuring systems, each time the system is powered-up, the position reference to the machine zero point must be established.

Synchronization is realized for a reference point approach by accepting a specific position value at a known point of the axis.

Note
- Before SW 4.1:
  The encoder must be re-referenced if, for a referenced incremental measuring system, a parameter set was changed over.
- From SW 4.1:
  Using P0239, the behavior for a parameter set changeover can be set for a motor measuring system.
  P0239 = 0: Behavior as before SW 4.1 (standard)
  P0239 = 1: For a parameter set changeover, it is only necessary to re-reference the encoder, if the ratio P0237/P0238 has changed.
### Starting the reference point approach

The reference point approach can be started in the "positioning" mode via the "start referencing" input signal.

The signal can be entered via an input terminal or via PROFIBUS-DP, and must remain set until the end of the reference point approach travel via the "reference point set" output signal.

If the "start referencing" signal is reset during referencing, then referencing is exited and the drive stops.

For a 2-axis control board, the reference point approach for both axes can be started and executed, either one after the other or simultaneously.

The approach direction for reference point approach is defined using P0166.

### Axis with reference cams (P0173 = 0)

Axes, which have several zero marks over their complete traversing range (e.g. incremental, rotary measuring system), require a reference cam to select the "correct" zero mark when referencing.

The reference point approach for these axes is executed in 3 phases:

### Phase 1: Traverse to the reference cams

When starting the reference point approach, the following statuses are available:

- Axis is located in front of the reference cam
  - After the reference point approach is started, the axis moves with the reference point approach velocity (P0163) in the direction specified by P0166.
  - The drive detects the reference cam using the input signal "reference cam" and for a "1" signal brakes down to standstill.
  - It continues with the "synchronization with the zero pulse".

### Note

The maximum permissible distance from the starting position up to the reference cams can be monitored using P0170 (maximum distance to the reference cams).

The override influences the reference point approach velocity.

- The axis is located at the reference cam
  - After the reference point approach has started, it is considered as having been completed with "travel to the reference cam".
  - It continues with the "synchronization with the zero pulse".
Phase 2: Synchronization using the zero pulse

The axis traverses with the reference point shutdown velocity (P0164) in the opposite direction to that specified in P0166. After the reference cam has been left (input signal, "reference cam" = "0" signal), the axis synchronizes with the first zero pulse. The axis brakes down to standstill. The system continues with "traverse to reference point".

Note

The maximum permissible travel from the reference cams to the zero pulse can be monitored using P0171 (max. distance between the reference cam/zero pulse).

The override is not effective.

Phase 3: Traversing to the reference point

The axis traverses with the reference point approach velocity (P0165), the reference point offset (P0162) in a positive or negative direction referred to the zero pulse.

The following is achieved when the axis reaches the reference point:

- The reference point coordinate (P0160 = 0) is transferred as the new reference position.
- The "reference point set" output signal is set to a "1" signal.
- From SW 8.3, the reference point approach (homing) can be terminated after the zero mark has been detected, refer to Table 6-34 (P0160 = 1).

Note

If the reference point offset is less than the braking travel of the axis from the reference point shutdown velocity to standstill, then the reference point is approached from the other direction.

The override is not effective.

Mounting a reference cam

The reference cam signal must be connected to an input terminal with function number 78 (reference cam). Parameter P0167 can be used to adapt the signal characteristics of the reference cam (NO/NC characteristics).

Table 6-32 Adapting the reference cam signal

<table>
<thead>
<tr>
<th>If</th>
<th>then, when approaching/exiting the reference cam</th>
<th>P0167</th>
</tr>
</thead>
<tbody>
<tr>
<td>Normally open contact</td>
<td>a 0/1 edge or 1/0 edge -&gt;</td>
<td>P0167 = 0 (no inversion)</td>
</tr>
<tr>
<td></td>
<td></td>
<td>(standard)</td>
</tr>
<tr>
<td>Normally closed contact</td>
<td>a 0/1 edge or 1/0 edge -&gt;</td>
<td>P0167 = 1 (inversion)</td>
</tr>
</tbody>
</table>
The following factors influence how the drive identifies the reference cam from a time perspective:

- Accuracy or time delay when detecting a reference cam
- Delay at the input, position controller clock cycle, interpolation clock cycle, ...

**Warning**

If the reference cam is not adjusted, so that at each reference point approach, the same zero pulse is recognized for synchronization, then an "incorrect" machine zero point is obtained.

Recommendation:
Experience has shown that it is best to adjust the reference cam edge, required for synchronization, at the center between two zero pulses.

Example when adjusting the reference cam

After the reference point approach, the distance between the reference cams and the zero pulse can be read in P0172. This means that when the distance between 2 zero pulses is known, the reference cam offset travel can be calculated.
What is the minimum length of a reference cam?

The reference cam must be long enough, so that when the cam is approached with the reference point approach velocity, the braking travel ends right at the cam (the axis comes to a standstill at the cam), and the cam is exited with the reference point shutdown velocity.

The minimum length of the reference cam is calculated as follows:

$$\text{Min. length} = \frac{(\text{reference point approach velocity})^2}{2 \cdot \text{deceleration}} = \frac{\text{P0163}^2}{2 \cdot \text{P0104}}$$

Note:
This only applies if the jerk limiting is not active (P0107 = 0), otherwise longer.

Table 6-33 Reference cam up to the end of the traversing range?

<table>
<thead>
<tr>
<th>If...,</th>
<th>then...</th>
</tr>
</thead>
<tbody>
<tr>
<td>the cam extends up to the end of the traversing range,</td>
<td>the reference point approach can be started from every point of the axis.</td>
</tr>
<tr>
<td><strong>Recommendation</strong></td>
<td><strong>Reason:</strong> There are 2 conditions in this case (in front of and actually at the cam). The axis behaves appropriately at the start of the reference point approach, and traverses correctly for the reference point approach.</td>
</tr>
<tr>
<td>the reference cam does not extend up to the end of the traversing range,</td>
<td>The axis must be traversed into the range, determined at start-up, before the reference point approach is started.</td>
</tr>
<tr>
<td><strong>Reason:</strong> In this case, there are 3 initial conditions (in front of, at or behind the cam). The drive cannot differentiate between in front of and behind the cam, and for the reference point approach, for a specific initial condition it does not reach the reference cam.</td>
<td></td>
</tr>
</tbody>
</table>

Axis without reference cams (P0173 = 1)

Axes, which only have one zero mark over their complete traversing range (e.g. rotary axes), do not require any reference cams when referencing.

A reference point approach for these axes is executed as follows:

1. Synchronization with the zero pulse (phase 2, refer to "axis with reference cams" (P0173 = 0)"
2. Travel to the reference point (phase 3, refer to "axis with reference cam (P0173 = 0)"

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The referencing motion is shown in the following table as a function of the reference cams.

Table 6-34 Sequence when referencing (homing) for an incremental measuring system

<table>
<thead>
<tr>
<th>With/without</th>
<th>In front of/at Reference cams</th>
<th>Motion sequence</th>
</tr>
</thead>
<tbody>
<tr>
<td>Axis with reference cams (P0173 = 0)</td>
<td>Axis is in front of the reference cam</td>
<td><img src="image" alt="Diagram" /></td>
</tr>
<tr>
<td></td>
<td>Axis is at the reference cam</td>
<td><img src="image" alt="Diagram" /></td>
</tr>
<tr>
<td>Axis with reference cams (P0173 = 1)</td>
<td>Axis traverses up to the reference point (P0161 = 0)¹</td>
<td><img src="image" alt="Diagram" /></td>
</tr>
<tr>
<td></td>
<td>Axis traverses up to after the zero mark (P0161 = 1)¹ (from SW 8.3)</td>
<td><img src="image" alt="Diagram" /></td>
</tr>
</tbody>
</table>

Abbreviations:
- $V_{\text{appr.}}$ P0163 (reference point approach velocity)
- $V_{\text{shutd.}}$ P0164 (reference point shutdown velocity)
- $V_{\text{entry}}$ P0165 (reference point entry velocity)
- $R_V$ P0162 (reference point offset)
- $R_K$ P0160 (reference point coordinate)
- $H_M$ P0161 (stop at marks)

¹) When referencing (homing), the act. position is not displayed in SimoCom U.
6.2.6 Referencing with a distance-coded measuring system (from SW 8.3)

General
In the case of measurement systems with distance-coded reference marks, it is not necessary to evaluate a reference cam or approach a defined reference point in order to reference the machine axis.

Measuring systems of this type consist of a line grid and a reference mark track running parallel to this. The distance between two consecutive reference marks is defined variably, so that the absolute position of the machine axis can be determined from the distance.

For axes with incremental measuring systems, each time the system is powered-up, the position reference to the machine zero point must be established.

Synchronization is realized at reference point approach by accepting a specific position value at a known point of the axis.

Note
The distance between the zero marks is continually monitored.

Only encoders are monitored whose pulse number can be divide by either 16 or 10!

Starting the reference point approach
The reference point approach can be started in the "positioning" mode via the "start referencing" input signal.

The input signal is entered using an input terminal with function number 65, and must remain set until the end of the reference point approach is signaled using the output signal "reference point set" (function number 61).

If the "start referencing" signal is reset during referencing, then referencing is exited and the drive stops.

During the reference point approach (homing), at least two reference marks (zero marks) are passed. The reference point approach (homing) is completed when these zero marks have been passed and the drive has been braked.

For a 2-axis control board, the reference point approach for both axes can be started and executed, either one after the other or simultaneously.

The approach direction for reference point approach is defined using P0166.

The reference point approach (homing) is executed in 2 phases (refer to Table 6-35):
The axis traverses with the reference point shutdown velocity (P0164) in the direction specified in P0166. The system is synchronized when passing two zero pulses (position of two zero marks). The axis brakes down to standstill after the second zero pulse. The system continues with "traverse to reference point".

**Note**
The maximum permissible distance from the start up to the second zero pulse is monitored using P0171 (max. distance between the reference cams or start/zero pulse). For distance-coded measuring systems, it is practical to set the basic distance. The override is not effective.

---

The axis traverses with the reference point approach velocity (P0165), the reference point offset (P0162) in a positive or negative direction referred to the zero pulse of the encoder.

The following is achieved when the axis reaches the reference point:

- The reference point coordinate (P0160) is transferred as the new reference position.
- The "reference point set" output signal is set to a "1" signal.

**Note**
If, after the second zero point, a reference point approach is not required (P0161 = 1), then the absolute position of the current position is calculated and accepted in the drive.

The "reference point set" output signal is then set to a "1". Parameter P0162 and P0160 act the same as for a reference point approach with one zero mark. The reference point offset does not refer to the zero mark passed, but to the encoder zero.

---

For a machine with distance-coded reference marks, there is no requirement to reference using cams.

Standard setting when referencing with distance-coded measuring systems:

---

P0173 = 1: "Referencing without cams"
Motion sequence when referencing

The referencing motion is shown in the following table as a function of the zero marks.

Table 6-35 Sequence when referencing with distance-coded measuring systems

<table>
<thead>
<tr>
<th>With/without Reference cams</th>
<th>In front of/at Motion sequence</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
</tr>
<tr>
<td>Axis traverses up to the reference point (P0161 = 0)(^1)</td>
<td><img src="image" alt="Diagram" /></td>
</tr>
<tr>
<td>Axis traverses up to after the zero mark (P0161 = 1)(^1) (from SW 8.3)</td>
<td><img src="image" alt="Diagram" /></td>
</tr>
</tbody>
</table>

Abbreviations:

- \(V_{\text{shutd.}}\): P0164 (reference point shutdown velocity)
- \(V_{\text{entry}}\): P0165 (reference point entry velocity)
- \(R_v\): P0162 (reference point offset)
- \(R_K\): P0160 (reference point coordinate)
- \(H_M\): P0161 (stop at marks)

\(^1\) When referencing (homing), the act. abs. pos. is not displayed in SimoCom U.

Input/output signals (refer to Chapter 6.4)

The following signals are used for the function "referencing with distance-coded measuring system:

- **Input signals**
  - Refer under the index entry, "Input signal, digital - ..."
    - Input signal "Start referencing/cancel referencing"
      - \(\rightarrow\) using an input terminal with function number 65

- **Output signal**
  - Refer under the index entry "Output signal, digital - ...
    - Output signal, "Reference point set/no reference point set"
      - \(\rightarrow\) using an output terminal with function number 61
The following parameters are used for referencing with distance-coded measuring systems:

- **P0161** Stopping at marks (from SW 8.3)
- **P0173** Reference point approach (homing) without reference cams
- **P1027** IM configuration, encoder
- **P1037** DM configuration, encoder
- **P1050** IM reference mark distance for distance-coded scales
- **P1051** IM reference mark distance for distance-coded rotary encoders
- **P1052** DM reference mark distance for distance-coded scales
- **P1053** DM reference mark distance for distance-coded rotary encoders
- **P1054** IM difference for distance-coded rotary encoders (from SW 8.3)
- **P1055** DM difference for distance-coded rotary encoders (from SW 8.3)

### Supplementary condition

- **Modulo operation** (from SW 10.2)

  Distance-coded referencing in modulo operation is only possible if the following practical, integer number modulo range values apply:
  
  \[ n \cdot 360 \text{ degrees with } n = 1, 2, \ldots \]

  Any modulo range values are not permitted and would result in fault 139 being output.
6.2.7 Adjusting absolute measuring systems

**General information**
Aaxes with absolute value encoders automatically obtain their reference position without any axis motion after power-on.

Requirements:

- There is an absolute value encoder (single-turn/multi-turn absolute value encoder) ($P0175 = 0$)
- Absolute value encoder is considered to have been adjusted ($P0175 = 3$ for indirect measuring system $P0175 = 4$ for direct measuring system)

**Adjusting the absolute value encoder**
An absolute value encoder should be adjusted once when commissioning the axis or after opening the mechanical coupling between the measuring system and mechanical system, for example, after:

- Replacing the measuring system and/or motor
- Changing the gearbox ratio (when changing the gearbox factors)
- Selection, "parking axis" (if another EnDat encoder was connected)

**Note**

- "SIMODRIVE 611 universal" can only identify if the mechanical coupling between the measuring system and mechanical system is released, if it is powered up.
- When a parameter set is changed-over in operation (e.g. a gear ratio is changed), the "not adjusted" information is lost at power-down if "save to Feprom" is not explicitly initiated.
- Before SW 4.1:
  If a parameter set changeover was carried out with an adjusted absolute encoder for a particular motor measuring system, then the encoder must be re-adjusted.
- From SW 4.1:
  Using $P0239$, the behavior for a parameter set changeover can be set for a motor measuring system.
  $P0239 = 0$: Behavior as before SW 4.1 (standard)
  $P0239 = 1$: For a parameter set changeover, it is only necessary to adjust the encoder if the mechanical ratio of $P0237/P0238$ has been changed.
Procedure to adjust an absolute value encoder using the display and operator control unit

The following sequence is practical when adjusting absolute value encoders:

1. Traverse the axis to a known or measured position (this is the required actual value). The axis can be traversed, e.g. using "Jogging 1" or "Jogging 2".

2. Set P0160 to "required actual value"

3. Set P0175 = 1
   The "SIMODRIVE 611 universal" drive determines the difference between the required actual value in P0160 and the encoder actual value and enters it into an internal parameter.
   If a fault occurs, then P0175 is set to -1.
   If the operation was error-free, then P0175 is set to 2, 3 or 4 (refer to Chapter 6.2.8) and Fault 799 (save to FEPROM and HW RESET required) is signaled.
   - Save parameters in the FEPROM (P0652 = 1)
   - Carry-out a HW-RESET (press the POWER-ON RESET button on the front panel of the control board)

4. Check: Is the actual value correctly displayed after power-on?

Procedure when adjusting an absolute value encoder using SimoCom U

The absolute value encoder is adjusted, supported by the operator. The following sequence is practical:

1. Establish online operation between SimoCom U and the drive

2. Traverse the axis to a known or measured position (this is the required actual value). The axis can be traversed, e.g. using "Jogging 1" or "Jogging 2".

3. Select the "referencing" dialog box
   - Enter the "required actual value" into the appropriate field.
   - Press the "Set absolute value" button.
     The "SIMODRIVE 611 universal" drive determines the difference between the required actual value in P0160 and the encoder actual value and enters it into an internal parameter.
     If this operation is error-free, fault 799 is then signaled (save to FEPROM and HW RESET) and the operator is prompted to:
     - Save parameters by carrying out a "save to FEPROM"
       and
       carry out a "HW-RESET"

4. Check: Is the actual value correctly displayed after power-on?
### 6.2.8 Parameter overview when referencing/adjusting

#### Table 6-36 Parameter overview when referencing/adjusting

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0160</td>
<td>Reference point coordinate</td>
<td>-200 000 000</td>
<td>0</td>
<td>200 000 000</td>
<td>MSC</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The parameter defines the position value which is set, as actual axis position, after referencing or adjusting.

- Incremental measuring system
  - After the reference point has been reached, the drive accepts the position value in this parameter as the current axis position.
- Absolute encoder
  - When adjusting the encoder, the position value in this parameter is set as the actual axis position.

| No.  | Stopping at marks (from SW 8.3) | 0 | 0 | 1 | - | immediately |

...defines the behavior when stopping at marks.

- 0 Reference point approach (homing) is not interrupted at marks (standard)
- 1 Reference point approach (homing) remains stationary, if the first zero mark, or for distance-coded measuring systems, the second zero mark was found.

| No.  | Reference point offset            | -200 000 000 | -2 000  | 200 000 000 | MSC  | PrgE       |

Incremental measuring system

After the reference zero pulse has been identified, the axis is moved through this distance. The axis has reached the reference point of this position, and accepts the reference point coordinate (P0160) as new actual value.

| No.  | Reference point approach velocity | 1 000 | 5 000 000 | 2 000 000 000 | c*MSR/min | PrgE |

The axis moves with this velocity towards the reference cam after the reference point approach has been started.

The velocity must be set, so that after the reference cam has been reached, and braking, the following conditions must be fulfilled:

- The axis must come to a standstill at the reference cam
- It is not permissible that the hardware limit switch is reached when braking

| No.  | Reference point shutdown velocity | 1 000 | 300 000 | 2 000 000 000 | c*MSR/min | PrgE |

The axis moves with this velocity between identifying the reference cam and synchronizing with the first zero pulse (reference zero pulse).

| No.  | Reference point entry velocity    | 1 000 | 300 000 | 2 000 000 000 | c*MSR/min | PrgE |

The axis traverses with this velocity between synchronizing with the first zero pulse (reference zero pulse) and reaching the reference point.
Table 6-36  Parameter overview when referencing/adjusting, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0166</td>
<td>Reference cam approach direction</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

This parameter defines the approach direction/search direction of the reference cam. At power–on, the axis can be located in front of or at the reference cam.

- Assumption: The axis is located in front of the reference cam.
  When starting reference point approach, the reference cam is searched for in the direction specified in this parameter.
- Assumption: The axis is located at the reference cam
  When starting the reference point approach, the reference cam is already known. The axis now moves away from the reference cam in the direction opposite to that entered in this parameter and continues the reference point approach.

| 0    | The reference cam is in the negative direction |
| 0    | The reference cam is in the positive direction |

Note:
For an axis without reference cam (P0173 = 1), referencing is started with phase 2 (synchronizing with the zero reference pulse).
The approach direction when searching for the zero pulse is defined using P0166.

<table>
<thead>
<tr>
<th>0167</th>
<th>Inverting reference cams</th>
<th>0</th>
<th>0</th>
<th>1</th>
<th>-</th>
<th>immediately</th>
</tr>
</thead>
</table>

... the switching behavior of the reference cam signal (input terminal with function number 78) is adapted.

| 1    | Inversion                        | --> necessary for an NC contact |
| 0    | No inversion                      | --> necessary for a NO contact, standard |

| 0170 | Maximum distance to the reference cam | 0 | 10 000 000 | 200 000 000 | MSC | PrgE |

... specifies the maximum distance the axis can traverse from starting the reference point approach in order to find the reference cams.

Note:
When a fault condition occurs, the axis remains stationary and fault 160 is signaled (reference cam not reached).
Table 6-36  Parameter overview when referencing/adjusting, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Ef- fective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0171</td>
<td>Max. distance up to the zero pulse</td>
<td>0</td>
<td>20 000</td>
<td>200 000 000</td>
<td>MSC</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the maximum distance the axis can move when leaving the reference cam or from the start in order to find the zero pulse.

**Note:**
- If a fault condition occurs, the axis remains stationary and fault 162 is signaled (no reference zero pulse available).
- If P0171 is entered and it is insignificantly higher than P0172, a fault can occur due to a degree of uncertainty when determining the actual value travel.

<table>
<thead>
<tr>
<th>No.</th>
<th>Distance up to the zero pulse</th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>0172</td>
<td></td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>MSC</td>
<td>RO</td>
</tr>
</tbody>
</table>

The travel between leaving the reference cam or from the start up to reaching the zero pulse is entered in this parameter.

**Note:**
- This parameter helps to adjust the reference cam during start-up.
- There is some uncertainty in the actual distance between the reference cam and reference zero pulse. This is caused by the switching behavior (timing) of the reference cam switch and the sampling of the reference cam switching signals in the interpolation clock cycle.
- The measured distance in P0172 can therefore be different at each reference point approach.

<table>
<thead>
<tr>
<th>No.</th>
<th>Reference point approach without reference cams</th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>0173</td>
<td></td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... identifies the type of axes, which do not require reference cams for referencing. These are the following axes:
- Axes that have only one zero mark over the complete traversing range
- Rotary axes that only have one zero mark per revolution
  1  No reference cam available
     For these axes, the reference point approach starts with phase 2 (synchronization with the reference zero pulse).
     The approach direction is defined using P0166 (reference cam approach direction).
  0  Reference cams available
     For these axes, the reference point approach starts with phase 1 (travel to the reference cams).

<table>
<thead>
<tr>
<th>No.</th>
<th>Referencing mode - position measuring system</th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>0174</td>
<td></td>
<td>1</td>
<td>1</td>
<td>2</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

The parameter defines the referencing mode.
- 1  Incremental measuring system available
   The zero pulse on the encoder track is evaluated.
- 2  There is an incremental measuring system with equivalent zero mark
   Instead of the zero mark from the encoder, an "equivalent zero mark" (e.g. a BER0 pulse) is expected at the input terminal I0.x.

**Note:**
The equivalent zero mark is identified, depending on the direction (refer under the index entry "Input signal - equivalent zero mark").
### 6.2 Positioning mode (P0700 = 3, from SW 2.1)

#### Table 6-36 Parameter overview when referencing/adjusting, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0175</td>
<td>Adjustment status - absolute position measuring system</td>
<td>0</td>
<td>0</td>
<td>4</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

- ... indicates the status when adjusting the absolute value encoder
- -1 Error/fault occurred when adjusting the encoder
- 0 Absolute value encoder has not been adjusted. Pre-setting when commissioning the system for the first time.
- 1 Absolute value encoder has still not been adjusted. Adjustment has been initiated. The parameter is set to 2 for an error-free adjustment. If an error occurs when making the adjustment, the parameter is set to -1.
- 2 The absolute value encoder has been adjusted (before SW 3.1)
- 3 The absolute value encoder IM has been adjusted (from SW 3.1)
- 4 The absolute value encoder DM has been adjusted (from SW 3.3)

**Note:**
- If a valid adjustment becomes invalid, then P0175 is set from 2 to 0. This can be realized by manually changing the parameter as well as from "SIMODRIVE 611 universal" itself (e.g. for a parameter set changeover, as this signifies that the mechanical coupling between the measuring system and mechanical system has been opened - gear-box changeover.
- If a series start-up is executed (copying the parameters from drive x to drive y), then the adjustment value is also reset due to the "serial number motor measuring system" (P1025/P1026) (P0175 = 0).

| 0239 | Re-referencing or re-adjustment only when required (SRM ARM) (from SW 4.1) | 0 | 0 | 1 | - | immediately |

- 0 Referencing or adjustment is withdrawn when a parameter set is changed (standard)
- 1 Referencing or adjustment is only withdrawn when a parameter set is changed if the mechanical ratio (U = P0237:8/P0238:8) has changed.

| 1050 | IM reference mark distance for distance-coded measuring scales (from SW 4.1) | 0 | 20 000 | 4294967295 | µm | PO |

- ... specifies the basic distance between two fixed reference marks. If the control detects that the distance between each two reference marks is different and therefore incorrect, then the axis remains stationary. Fault 508 (zero mark monitoring, motor measuring system) is signaled.

**Note:**
- This monitoring is only activated if P1050/P1024*1000 can either be divided by 16 or by 10.
### Table 6-36  Parameter overview when referencing/adjusting, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Ef- fective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1051</td>
<td>IM reference mark distance for distance-coded rotary encoders (from SW 4.1)</td>
<td>0</td>
<td>20 000</td>
<td>4294967295</td>
<td>mdegrees</td>
<td>PO</td>
</tr>
</tbody>
</table>

...specifies the basic distance between two fixed reference marks. If the control detects that the distance between each two reference marks is different and therefore incorrect, then the axis remains stationary. Fault 508 (zero mark monitoring, motor measuring system) is signaled.

**Note:**
This monitoring is only activated if P1051/1000*P1005/360 can either be divided by 16 or by 10.

| 1052 | DM reference mark distance for distance-coded measuring scales (from SW 4.1) | 0    | 20 000   | 4294967295 | μm            | PO         |

...specifies the basic distance between two fixed reference marks. If the control detects that the distance between each two reference marks is different and therefore incorrect, then the axis remains stationary. Fault 514 (zero mark monitoring, direct measuring system) is signaled.

**Note:**
This monitoring is only activated if P1052/P1034*1000 can either be divided by 16 or by 10.

| 1053 | DM reference mark distance for distance-coded rotary encoders (from SW 4.1) | 0    | 20 000   | 4294967295 | mdegrees       | PO         |

...specifies the basic distance between two fixed reference marks. If the control detects that the distance between each two reference marks is different and therefore incorrect, then the axis remains stationary. Fault 514 (zero mark monitoring, direct measuring system) is signaled.

**Note:**
This monitoring is only activated if P1053/1000*P1007/360 can either be divided by 16 or by 10.

| 1054 | IM difference for distance-coded rotary encoders (from SW 8.3) | 0    | 20 | 450 000 | 500 000 | mdegrees | PO |

...specifies the differential distance between two reference marks for distance-coded encoders, indirect measuring system (motor measuring system).

| 1055 | DM difference for distance-coded rotary encoders (from SW 8.3) | 0    | 20 | 450 000 | 500 000 | mdegrees | PO |

...specifies the differential distance between two zero marks for distance-coded encoders, direct measuring system.
6.2.9 Jogging operation

Description
Closed-loop speed controlled traversing is made possible when jogging in the “positioning” mode. Jogging is executed using the input signal “Jogging 1, 2 ON”.

Changing over into the jogging mode
The jogging mode can be selected using the input signal “jogging incremental” (refer to Fig. 6-24):
- Jogging via velocity (standard)
- Jogging via velocity and increments (from SW 4.1)

![Fig. 6-24 Jogging: Via velocity or incrementally](image)

![Fig. 6-25 Accelerating and braking when jogging](image)
**Note**

The following is valid when jogging:

- The traversing direction is defined by the sign of P0108 or P0109.
- When the jogging signal is withdrawn, the axis comes to an immediate stop and, at the next "1" signal is re-started with the same task.
- It is not possible to continue after incremental jogging has been interrupted.
- The software limit switches are effective if they have been activated and set for this axis, and the axis has been referenced. Contrary to operation in the positioning mode, the axis only starts to brake when the software limit switch is reached. The travel beyond the software limit switch depends on the active velocity setpoint for jogging 1/2 (P0108/P0109, override) and the selected maximum deceleration (P0104).
- The override is effective.
- If input signals for jogging 1 and 2 are simultaneously available, then an appropriate fault is signaled.
- If the position reference value is inverted (P0231, P0232), then the direction of rotation also changes in the jogging mode.
- For speed-controlled jogging, the drive is in the follow-up status. In this case, the velocity setpoint and actual value are formed from the speed controller.

---

**Parameter overview (refer to Chapter A.1)**

The following parameters are available for the "jogging mode" function:

- **P0108** Velocity setpoint, jogging 1
- **P0109** Velocity setpoint, jogging 2
- **P0122** Jogging 1, increments (from SW 4.1)
- **P0123** Jogging 2, increments (from SW 4.1)

---

**Input signals (refer to Chapter 6.4)**

The following signals are available for the "jogging mode" function:

- Input signals (refer under index entry "Input signal, digital - ")
  - Input signal "jogging 1 ON/jogging 1 OFF"
    --> using an input terminal with function number 62
    --> via PROFIBUS control signal "STW1.8"
  - Input signal "jogging 2 ON/jogging 2 OFF"
    --> using an input terminal with function number 63
    --> via PROFIBUS control signal "STW1.9"
  - Input signal, "incremental jogging " (from SW 4.1)
    --> using an input terminal with function number 61
    --> via the PROFIBUS control signal "PosStw.5"
### 6.2.10 Programming traversing blocks

**Overview**
A maximum of 64 (256 from SW 10.1) traversing blocks can be programmed. The information associated with each block is listed in the following table:

<table>
<thead>
<tr>
<th>Block memory...</th>
<th>Description</th>
<th>Description</th>
<th>Memory</th>
</tr>
</thead>
<tbody>
<tr>
<td>80:0 80:1 ...</td>
<td>Block number</td>
<td>A traversing block must be assigned a block number between 0 and 63, so that it becomes valid and can be started.</td>
<td>80:63/255</td>
</tr>
<tr>
<td>81:0 81:1 ...</td>
<td>Position</td>
<td>Specifies the target position in the block to be approached.</td>
<td>81:63/255</td>
</tr>
<tr>
<td>82:0 82:1 ...</td>
<td>Velocity</td>
<td>Specifies the velocity with which the target position is approached.</td>
<td>82:63/255</td>
</tr>
<tr>
<td>83:0 83:1 ...</td>
<td>Acceleration override</td>
<td>This allows the acceleration to be influenced, referred to P0103.</td>
<td>83:63/255</td>
</tr>
<tr>
<td>84:0 84:1 ...</td>
<td>Deceleration override</td>
<td>This allows the deceleration to be influenced, referred to P0104.</td>
<td>84:63/255</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
<th>Memory</th>
</tr>
</thead>
<tbody>
<tr>
<td>85:0 85:1 ...</td>
<td>Command</td>
<td>Each traversing block must contain a command (refer to Table 6-38).</td>
</tr>
<tr>
<td>1 POSITIONING (Standard)</td>
<td>+: Block number, position, velocity, Acceleration override, deceleration override, mode</td>
<td>85:63/255</td>
</tr>
<tr>
<td>2/3 ENDLESS TRAVERSING_POS/ENDLESS TRAVERSING_NEG</td>
<td>+: Block number, velocity, Acceleration override, deceleration override, mode</td>
<td></td>
</tr>
<tr>
<td>4 WAIT</td>
<td>+: Block number, delay time in the &quot;command parameter&quot;, mode</td>
<td></td>
</tr>
<tr>
<td>5 GOTO</td>
<td>+: Block no., target block no. in the &quot;command parameter&quot;, mode</td>
<td></td>
</tr>
<tr>
<td>6/7 SET_O/RESET_O</td>
<td>+: Block number, output No. in the &quot;command parameter&quot;, mode</td>
<td></td>
</tr>
<tr>
<td>8 FIXED ENDSSTOP (from SW 3.3)</td>
<td>+: Block number, position, velocity, Acceleration override, deceleration override, Value range and units for clamping torque/clamping force in the &quot;Command parameter&quot;, mode</td>
<td></td>
</tr>
<tr>
<td>9/10 COUPLING_IN/COUPLING_OUT (from SW 3.3)</td>
<td>+: Block number, mode</td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Command parameters</th>
<th>Description</th>
<th>Memory</th>
</tr>
</thead>
<tbody>
<tr>
<td>86:0 86:1 ...</td>
<td>Command parameters</td>
<td>Additionally required information to execute the command is specified here.</td>
</tr>
</tbody>
</table>
### Table 6-37 Overview of the traversing blocks, continued

<table>
<thead>
<tr>
<th>Block memory...</th>
<th>Description</th>
<th>Description</th>
<th>Memory</th>
</tr>
</thead>
<tbody>
<tr>
<td>87:0 87:1 ...</td>
<td>Mode</td>
<td>Block change enable</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Spindle positioning (from SW 5.1)</td>
<td>xXxx</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Target position via 0: Traversing block running 1: PROFIBUS</td>
<td>0: END (standard) 1: CONTINUE WITH STOP 2: CONTINUE FLYING 3: CONTINUE EXTERNAL</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Positioning mode</td>
<td>xxXx</td>
<td></td>
</tr>
<tr>
<td></td>
<td>0: ABSOLUTE (standard) 1: RELATIVE 2: ABS_POS 3: ABS_NEG</td>
<td>1: SKIP BLOCK</td>
<td></td>
</tr>
<tr>
<td></td>
<td>IDs</td>
<td>xxxX</td>
<td></td>
</tr>
<tr>
<td></td>
<td>1: SKIP BLOCK</td>
<td>...</td>
<td>87:63/255</td>
</tr>
</tbody>
</table>
## Command-dependent block information

The minimum block information which has to be made in a traversing block with this command, is specified in the following table, for each command.

### Table 6-38 Command-dependent block information

<table>
<thead>
<tr>
<th>Block information</th>
<th>Command-dependent block information which is required</th>
</tr>
</thead>
<tbody>
<tr>
<td>Block number</td>
<td>P0080:64/256</td>
</tr>
<tr>
<td></td>
<td>x x x x x x x</td>
</tr>
<tr>
<td>Position</td>
<td>P0081:64/256</td>
</tr>
<tr>
<td></td>
<td>x - - - - - -</td>
</tr>
<tr>
<td>Velocity</td>
<td>P0082:64/256</td>
</tr>
<tr>
<td></td>
<td>x x - - - - x</td>
</tr>
<tr>
<td>Acceleration override</td>
<td>P0083:64/256</td>
</tr>
<tr>
<td></td>
<td>x x - - - - x</td>
</tr>
<tr>
<td>Deceleration override</td>
<td>P0084:64/256</td>
</tr>
<tr>
<td></td>
<td>x x x x - - - - x</td>
</tr>
<tr>
<td>Command</td>
<td>P0085:64/256</td>
</tr>
<tr>
<td></td>
<td>POSITIONING</td>
</tr>
<tr>
<td></td>
<td>ENDELESS TRAVERSING_POS</td>
</tr>
<tr>
<td></td>
<td>ENDELESS TRAVERSING_NEG</td>
</tr>
<tr>
<td></td>
<td>WAITING</td>
</tr>
<tr>
<td></td>
<td>GOTO</td>
</tr>
<tr>
<td></td>
<td>SET_O</td>
</tr>
<tr>
<td></td>
<td>RESET_O</td>
</tr>
<tr>
<td></td>
<td>FIXED STOP (from SW 3.3)</td>
</tr>
<tr>
<td></td>
<td>COUPLING_IN (from SW 3.3)</td>
</tr>
<tr>
<td></td>
<td>COUPLING_OUT (from SW 3.3)</td>
</tr>
<tr>
<td>Command parameters</td>
<td>P0086:64/256</td>
</tr>
<tr>
<td></td>
<td>- - - x x x x</td>
</tr>
<tr>
<td>Mode</td>
<td>P0087:64/256</td>
</tr>
<tr>
<td>IDs</td>
<td>+ + + + + + + +</td>
</tr>
<tr>
<td>- SKIP BLOCK</td>
<td></td>
</tr>
<tr>
<td>Positioning mode</td>
<td></td>
</tr>
<tr>
<td>1)</td>
<td></td>
</tr>
<tr>
<td>- ABSOLUTE</td>
<td>x - - - - - - - x</td>
</tr>
<tr>
<td>- RELATIVE</td>
<td>x - - - - - - - x</td>
</tr>
<tr>
<td>- ABS_POS (from SW 2.4)</td>
<td>x - - - - - - - - x</td>
</tr>
<tr>
<td>- ABS_NEG (from SW 2.4)</td>
<td>x - - - - - - - - x</td>
</tr>
<tr>
<td>Block change enable</td>
<td></td>
</tr>
<tr>
<td>1)</td>
<td></td>
</tr>
<tr>
<td>- END</td>
<td>x x x x x x -</td>
</tr>
<tr>
<td>- CONTINUE WITH STOP</td>
<td>x - - - - - - x - x x x x</td>
</tr>
<tr>
<td>- CONTINUE FLYING</td>
<td>x - - - - - - x x x x -</td>
</tr>
<tr>
<td></td>
<td>x x x x - - - - - -</td>
</tr>
</tbody>
</table>

### Note:

- 1) Only 1 info can be alternatively specified
- 2) Only possible for rotary axis with modulo correction
- x: This information must be specified for this command
- +: This information can be specified
- -: This information is not relevant
6.2 Positioning mode (P0700 = 3, from SW 2.1)

---

**Note**

Input errors when entering block information are displayed using the appropriate error messages, for all traversing blocks after a traversing block has started.

---

**Parameter overview**

All of the parameters, which are used to program traversing blocks, are shown in the following.

Table 6-39  Parameters used to program traversing blocks

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0079</td>
<td>Reformatting the memory</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... the memory for the traversing blocks can be re-formatted, i.e. re-assigned.

- 0: Inactive, initial status
- 0 -> 1: Memory is being re-formatted

When re-formatting, increasing block numbers are written into the blocks at the beginning of the memory. Invalid blocks (block number - 1) are at the end of the memory.

**Note:**

- After reformatting has been completed, the parameter is automatically reset to 0.
- Advantages of a re-formatted memory:

When the blocks are displayed via SimoCom U or via the display unit on the front panel, the blocks are located at the beginning of the memory and are sorted according to increasing block numbers; there are no gaps.

P0080

<table>
<thead>
<tr>
<th>:0</th>
<th>:1</th>
<th>:2</th>
<th>:3</th>
<th>:63</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1</td>
<td>20</td>
<td>-1</td>
<td>15</td>
<td>...</td>
</tr>
<tr>
<td>xxx</td>
<td>xxx</td>
<td>xxx</td>
<td>xxx</td>
<td>...</td>
</tr>
<tr>
<td>to</td>
<td>...</td>
<td>...</td>
<td>...</td>
<td>...</td>
</tr>
</tbody>
</table>

P0081

<table>
<thead>
<tr>
<th>:0</th>
<th>:1</th>
<th>:2</th>
<th>:3</th>
<th>:63</th>
</tr>
</thead>
<tbody>
<tr>
<td>15</td>
<td>20</td>
<td>-1</td>
<td>-1</td>
<td>...</td>
</tr>
<tr>
<td>xxx</td>
<td>xxx</td>
<td>xxx</td>
<td>xxx</td>
<td>...</td>
</tr>
</tbody>
</table>

P0088

<table>
<thead>
<tr>
<th>:0</th>
<th>:1</th>
<th>:2</th>
<th>:3</th>
<th>:63</th>
</tr>
</thead>
<tbody>
<tr>
<td>YYY</td>
<td>YYY</td>
<td>YYY</td>
<td>YYY</td>
<td>...</td>
</tr>
</tbody>
</table>

---

**before reformatting**

---

**after reformatting**

---
Table 6-39  Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0080:64</td>
<td>Block number</td>
<td>-1</td>
<td>-1</td>
<td>63 (256, from SW 10.1)</td>
<td>-</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

A traversing block must be assigned a valid block number so that it can be started.

-1  Invalid block number
Blocks, with this block number are not taken into account by the program interpreter.

0 to 63/256  Valid block number

**Note:**
- The block change enable is saved in the traversing block in P0087:64 (mode - block change enable).
- There are the following possibilities for the block change enable:
  - END  (standard)
  - CONTINUE WITH STOP
  - CONTINUE FLYING
  - CONTINUE EXTERNAL (from SW 3.1)
- Several blocks are processed in an increasing sequence of the block numbers (e.g. for blocks with the block change enable condition CONTINUE FLYING).
- The block number must be unique overall traversing blocks otherwise fault 109 (block number available twice) is output when a traversing block is started.
- A valid block is "disabled" by entering the block number "-1", i.e. the block information remains saved, unchanged and when this block is re-assigned a valid block number, then the block information becomes visible again.

Recommendation:
Disable the block with "skip block" (refer to P0087:64/256).

<table>
<thead>
<tr>
<th>0081:64</th>
<th>Position</th>
<th>-200 000 000</th>
<th>0</th>
<th>200 000 000</th>
<th>MSC</th>
<th>PrgE</th>
</tr>
</thead>
</table>

... specifies the target position in the traversing block.

**Note:**
- The target position is approached depending on P0087:64 (mode - positioning mode).
- If, when selecting the traversing block, it is identified that the traversing range has been violated, then an appropriate fault signal is output.
Table 6-39  Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0082:64/256</td>
<td>Velocity</td>
<td>prior to SW 10.1: 1 000 starting with SW 10.1: 6</td>
<td>600 000</td>
<td>2 000 000 000</td>
<td>c*MSR/min</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... defines the velocity with which the target position is approached.

Programmed velocity

![Programmed velocity diagram](attachment:image)

Maximum acceleration

![Maximum acceleration diagram](attachment:image)

Maximum deceleration

![Maximum deceleration diagram](attachment:image)

Velocity and acceleration profile for "long" or "short" blocks

**Note:**
- x: Space retainer in the block memory
- If the programmed velocity in P0082:64/256 is greater than in P0102 (maximum velocity), then the axis is limited to the maximum velocity and warning 803 is issued (programmed velocity > maximum velocity).
- For short traversing distances, it is possible that the programmed velocity will not be reached.
- starting with SW 10.1:
  - For ultra-fine surface machining, the velocity can now be programmed at 0.006 mm/min, for example, for "slow feedrates".
  - With a small override factor and a slow feedrate, the velocity setpoint of the interpolator can end up being zero, even though the override factor is not zero. In this case, a warning (810) is issued, and the velocity setpoint is set to the smallest value.

<table>
<thead>
<tr>
<th>0083:64/256</th>
<th>Acceleration override</th>
<th>1</th>
<th>100</th>
<th>100</th>
<th>%</th>
<th>PrgE</th>
</tr>
</thead>
</table>

... specifies which override is effective at the maximum acceleration (P0103).

\[ a_{act} = P0103 \cdot \frac{P0083:x}{100 \%} \]

x: Space retainer in the block memory

<table>
<thead>
<tr>
<th>0084:64/256</th>
<th>Deceleration override</th>
<th>1</th>
<th>100</th>
<th>100</th>
<th>%</th>
<th>PrgE</th>
</tr>
</thead>
</table>

... specifies which override is effective at the maximum deceleration (P0104).

\[ a_{brake, act} = P0104 \cdot \frac{P0084:x}{100 \%} \]

x: Space retainer in the block memory
6 Description of the Functions

6.2 Positioning mode (P0700 = 3, from SW 2.1) ! not 611ue !

Every traversing block must include precisely one command for execution.

1  POSITIONING
Using this command, the axis can be linearly traversed (point to point, PTP).
Note: Other block parameters are still effective (refer to Table 6-38).

2  ENDLESS TRAVERSING_POS

3  ENDLESS TRAVERSING_NEG
With this command, the axis can be traversed with the velocity specified in the block, up to
- a limit switch is reached
- the motion is interrupted by the input signal "OC/intermediate stop"
- the motion is interrupted by the input signal "OC/reject traversing task"
Note: Other block parameters are still effective (refer to Table 6-38).
Limitation for rotary axis (modulo):
If a higher speed is entered in a traversing block (e.g. >1000 RPM) and if a low de-
celeration is set (e.g. standard setting 100 degrees/s²), then a fault is output.
Remedy:
The resulting braking travel must be <1000000 degrees.
The braking travel depends on the deceleration and the velocity.

\[
\text{Braking travel} = \frac{v^2}{2 \cdot a}\text{[degrees/s²]}
\]

4  WAITING
A delay time, which should expire before the following traversing block is pro-
cessed, can be defined using this command.
The delay time is specified in the command parameter (P0086:x).
Note:
The command parameter is entered in ms, and is internally and automatically
rounded-off to a multiple of the interpolation clock cycle (P1010).

5  GOTO
Jumps can be executed within a sequence of traversing blocks using this com-
mand.
The jump destination and the block number are specified in the command param-
eter (P0096:x).
Note:
If the specified block number does not exist, then an appropriate fault is signaled
when a traversing block is started.

Table 6-39  Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0085:64/256</td>
<td>Command</td>
<td>1</td>
<td>1</td>
<td>10</td>
<td>-</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

- Every traversing block must include precisely one command for execution.
- POSITIONING
  - Using this command, the axis can be linearly traversed (point to point, PTP).
  - Note: Other block parameters are still effective (refer to Table 6-38).
- ENDLESS TRAVERSING_POS
- ENDLESS TRAVERSING_NEG
  - With this command, the axis can be traversed with the velocity specified in the block, up to
    - a limit switch is reached
    - the motion is interrupted by the input signal "OC/intermediate stop"
    - the motion is interrupted by the input signal "OC/reject traversing task"
  - Note: Other block parameters are still effective (refer to Table 6-38).
  - Limitation for rotary axis (modulo):
    - If a higher speed is entered in a traversing block (e.g. >1000 RPM) and if a low de-
      - a limit switch is reached
      - the motion is interrupted by the input signal "OC/intermediate stop"
      - the motion is interrupted by the input signal "OC/reject traversing task"
    - Note: Other block parameters are still effective (refer to Table 6-38).
    - The resulting braking travel must be <1000000 degrees.
    - The braking travel depends on the deceleration and the velocity.

\[
\text{Braking travel} = \frac{v^2}{2 \cdot a}\text{[degrees/s²]}
\]

- WAITING
  - A delay time, which should expire before the following traversing block is pro-
    - The delay time is specified in the command parameter (P0086:x).
  - Note:
    - The command parameter is entered in ms, and is internally and automatically
      - a limit switch is reached
      - the motion is interrupted by the input signal "OC/intermediate stop"
      - the motion is interrupted by the input signal "OC/reject traversing task"
  - Limitation for rotary axis (modulo):
    - If a higher speed is entered in a traversing block (e.g. >1000 RPM) and if a low de-
      - a limit switch is reached
      - the motion is interrupted by the input signal "OC/intermediate stop"
      - the motion is interrupted by the input signal "OC/reject traversing task"
    - Note: Other block parameters are still effective (refer to Table 6-38).
    - The resulting braking travel must be <1000000 degrees.
    - The braking travel depends on the deceleration and the velocity.

\[
\text{Braking travel} = \frac{v^2}{2 \cdot a}\text{[degrees/s²]}
\]

- GOTO
  - Jumps can be executed within a sequence of traversing blocks using this com-
    - The jump destination and the block number are specified in the command parameter (P0096:x).
  - Note:
    - If the specified block number does not exist, then an appropriate fault is signaled
      - a limit switch is reached
      - the motion is interrupted by the input signal "OC/intermediate stop"
      - the motion is interrupted by the input signal "OC/reject traversing task"
### 6.2 Positioning mode (P0700 = 3, from SW 2.1)

**Table 6-39** Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td>SET_O</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>7</td>
<td>RESET_O</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

An output signal can be set or reset using these commands.

P0086:x (command parameter) is used to specify which output terminal or which status bit is to be controlled.

- P0086:x = 1 --> Output with Fct. No. 80 (direct output 1 via traversing block)
- P0086:x = 2 --> Output with Fct. No. 81 (direct output 2 via traversing block)
- P0086:x = 3 --> Output with Fct. Nos. 80 and 81 are controlled

Note:
The function numbers for the outputs and the PROFIBUS bits are listed in the list of output signals (refer to Chapter 6.4.6) under "Output signal, direct output 1/2 via traversing block".

The output signals, influenced using SET_O or RESET_O remain "frozen", when a fault develops, when a traversing block is interrupted, or at the end of the program. This means, that the signals are exclusively influenced using the SET_O/RESET_O commands. When starting or exiting the program, the output signals may possibly have to be "programmed" in an initial status.

<table>
<thead>
<tr>
<th>8</th>
<th>FIXED STOP</th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>9</td>
<td>COUPLING_IN</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>10</td>
<td>COUPLING_OUT</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Using these commands, the axis coupling that can be switched--in/out can be switched--in/out in the "positioning" mode.

Note:
The block change enable "CONTINUE EXTERNAL" can be parameterized in the traversing block "COUPLING IN". In the "COUPLING OUT" traversing block, a fault is output for "CONTINUE EXTERNAL".

<table>
<thead>
<tr>
<th>0086:64/256</th>
<th>Command parameters</th>
<th>0</th>
<th>1</th>
<th>65 535</th>
<th>-</th>
<th>PrgE</th>
</tr>
</thead>
</table>

... specifies the additional information required for the following commands.

- Command Additional information
- WAITING Waiting time in ms
- GOTO block number
- SET_O 1, 2, 3: Set direct output 1, 2 or 3 (both signals)
- RESET_O 1, 2, 3: Reset, direct output 1, 2 or 3 (both signals)
- FIXED STOP (from SW 3.3) Clamping torque or clamping force
  - Rotary drive: 1 - 65 535 [0.01 Nm]
  - Linear drive: 1 - 65 535 [N]

Note:
The command-dependent required block information is listed in the Table 6-38.
Table 6-39  Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0087:64/256</td>
<td>Mode</td>
<td>0</td>
<td>0</td>
<td>1331</td>
<td>Hex</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the following additional information for several commands:

- **0: ABSOLUTE** (Standard)
- **1: RELATIVE**
- **2: ABS_POS**
- **3: ABS_NEG**

only for rotary axes with modulo correction (from SW 2.4)

```
<table>
<thead>
<tr>
<th>Block</th>
<th>change enable</th>
<th>Positioning mode</th>
<th>IDs</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td>0: END (Standard)</td>
<td>1: SKIP_BLOCK</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1: CONTINUE WITH STOP</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>2: CONTINUE FLYING</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>3: CONTINUE EXTERNAL (from SW 3.1)</td>
<td></td>
</tr>
</tbody>
</table>
```

**SKIP_BLOCK ID**

A block with the ID SKIP_BLOCK is not processed, and is skipped.

**0087:64/256**

```
xxxX
```

**ABSOLUTE or RELATIVE positioning mode**

This data defines whether the program position should be interpreted as being absolute (as coordinate point) or relative (as the distance to be moved).

- **ABSOLUTE** or RELATIVE for linear axis or rotary axis without modulo correction
  - **ABSOLUTE**
    - The axis moves to the specified position and references itself to the axis zero. The software limit switch monitoring is effective.
  - **RELATIVE**
    - The axis moves around the specified position in the negative or positive direction and references itself to the last position it approached. The software limit switch monitoring is effective.

Examples for **ABSOLUTE**:

<table>
<thead>
<tr>
<th>Position</th>
<th>Travel</th>
</tr>
</thead>
<tbody>
<tr>
<td>+30</td>
<td>to 30</td>
</tr>
<tr>
<td>-10</td>
<td>to -10</td>
</tr>
</tbody>
</table>

Examples for **RELATIVE**:

<table>
<thead>
<tr>
<th>Position</th>
<th>Travel</th>
</tr>
</thead>
<tbody>
<tr>
<td>-10</td>
<td>through 10 negative</td>
</tr>
<tr>
<td>+10</td>
<td>through 10 positive</td>
</tr>
</tbody>
</table>
### Table 6-39 Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>ABSOLUTE or RELATIVE for rotary axis with modulo correction (from SW 2.4)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- ABSOLUTE: The axis approaches the program position within the modulo range, and it automatically selects the shortest distance. For the same distance in both directions, the axis moves in the positive direction. For values with a negative sign or a value outside the modulo range, an appropriate fault is output when a traversing block starts.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- RELATIVE: The axis traverses through the programmed position in a negative or positive direction and refers itself to the position which was last approached. The traversing distance can also be greater than the modulo range.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Positioning mode ABS_POS or ABS_NEG (only rotary axis with modulo correction)**

With this information, for a rotary axis with modulo correction (P0241 = 1), the direction of travel is specified along with the reference position.

- ABS_POS (from SW 2.4): The rotary axis traverses in the positive direction with respect to the reference position within the modulo range.
- ABS_NEG (from SW 2.4): The rotary axis traverses in the negative direction with respect to the reference position within the modulo range.

**Note:** An appropriate fault is signaled when starting a traversing block for values with negative sign or for a value outside the modulo range.

![Diagram showing ABS_POS and ABS_NEG positioning modes](image)

**Example:**
Positioning mode = ABS_POS Position = 315
--> traverse to 315° in a pos. direction

**Example:**
Positioning mode = ABS_NEG Position = 315
--> traverse to 315° in a neg. direction

**Block change enable END**

The block change enable can be used for the following traversing blocks:

- For pure single block operation, i.e. each block must be individually selected and started
- At the last block of a block sequence, i.e. the block identifies the end of the block sequence.
### Table 6-39: Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0087:64</td>
<td>Block change enable CONTINUE WITH STOP</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>/256</td>
<td>This block change enable has the following properties</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>xXxx</td>
<td>(corresponds to &quot;precise stop G60&quot; acc. to DIN 66025):</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The position programmed in the block is precisely approached</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The axis braked until the positioning window is reached (P0321)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>For P0321=0 or if the following error is less than P0321, the block change is executed as soon as the interpolator has reached its position reference value.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>• The block is changed when the positioning window is reached.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Blk</td>
<td>Pos.</td>
<td>Vel.</td>
<td>Command</td>
<td>Pos. mode</td>
<td>Block change enable</td>
<td></td>
</tr>
<tr>
<td>0</td>
<td>10</td>
<td>100</td>
<td>POSITIONING</td>
<td>ABSOLUTE</td>
<td>CONTINUE WITH STOP</td>
<td></td>
</tr>
<tr>
<td>1</td>
<td>30</td>
<td>150</td>
<td>POSITIONING</td>
<td>RELATIVE</td>
<td>CONTINUE WITH STOP</td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>10</td>
<td>50</td>
<td>POSITIONING</td>
<td>RELATIVE</td>
<td>END</td>
<td></td>
</tr>
</tbody>
</table>

#### Example:
Programming 3 traversing blocks

Example:
Programming 3 traversing blocks

Note:
For an existing axis coupling (position coupling), the positioning window is not effective for CONTINUE WITH STOP. If this represents a problem in an application when the master drive is stationary, then the PLC would first have to release the coupling and then position the slave drive normally.

### 0087:64 Block change enable CONTINUE FLYING

This block change enable has the following properties
(corresponds to "precise stop G64" acc. to DIN 66025):

- The following block is immediately processed when the time to apply the brake is reached
- For a direction change, the axis brakes down to standstill and waits until the position actual value has reached the positioning window (this corresponds to the block change enable "continue with stop"
- If the deceleration override (P0084:64) between the actual block and the block to be changed into on the fly differ, then the flying block change is automatically prevented and instead of this, the CONTINUE WITH STOP block change executed

<table>
<thead>
<tr>
<th>Blk</th>
<th>Pos.</th>
<th>Vel.</th>
<th>Command</th>
<th>Pos. mode</th>
<th>Block change enable</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>10</td>
<td>100</td>
<td>POSITIONING</td>
<td>ABSOLUTE</td>
<td>CONTINUE FLYING</td>
</tr>
<tr>
<td>1</td>
<td>30</td>
<td>150</td>
<td>POSITIONING</td>
<td>ABSOLUTE</td>
<td>CONTINUE FLYING</td>
</tr>
<tr>
<td>2</td>
<td>10</td>
<td>50</td>
<td>POSITIONING</td>
<td>ABSOLUTE</td>
<td>END</td>
</tr>
</tbody>
</table>

#### Example:
Programming 3 traversing blocks

Example:
Programming 3 traversing blocks

There is a direction of reversal between block 1 and block 2. This is the reason that at the braking instant, the drive brakes from block 1 down to standstill and waits until the position actual value reaches the positioning window. After this, block 2 is executed.

**Note:**
For traversing blocks whose distance is able to be travelled through within an IPO clock cycle, then the drive brakes briefly.
Table 6-39  Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0087:64 /256</td>
<td><strong>Block change enable CONTINUE EXTERNAL (from SW 3.1)</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>This block change enable has the following properties:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- For a traversing block with the block change enable CONTINUE EXTERNAL, a flying block change is made if an edge of the input signal &quot;external block change&quot; is identified. If the deceleration override (P0084:64/256) differs between the current and the block which is to be changed into flying, then a flying block change is made.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- When using the commands SET_O and RESET_O, it is not possible to use the block change enable CONTINUE EXTERNAL!</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- What happens, if...?</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The following traversing block is programmed in the RELATIVE positioning mode</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The programmed position refers to the actual value at the instant that the external block change is requested</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The braking travel is greater than the distance programmed in the following block</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The axis is held at the parameterized deceleration ramp and then traverses to the target position in the opposite direction.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- A different behavior is necessary for “external block change”?</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Then the required behavior must be set in P0110:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0110 = 0 (standard) -- &gt; If the signal is not available up to the start of braking, then the axis is stopped in front of the target position (dependent on: Acceleration, deceleration, positioning velocity) and fault 109 (external block change not requested in the block) is output.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0110 = 1 -- &gt; If the signal is not present up to the start of braking, then a flying block change is made (refer to block change enable CONTINUE FLYING).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0110 = 2 -- &gt; The block is traversed, independent of the signal, to the end. The system only waits for the signal at the end of the block; when the signal is detected, a block change is executed.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0110 = 3 (from SW 5.1) -- &gt; if the signal is not present up to the end of the block, then the axis waits for the signal and when the signal is identified, a block change is made.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong>  When P0110 is changed, the change is not accepted after v_set = 0, but instead, only after the end of the program when the traversing block is re-started.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The subsequent traversing block is programmed with the WAIT command?</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>After the signal edge has been detected, the position actual value is written into P0026, and the axis is braked down to standstill with the programmed deceleration (P0104 + deceleration override in P0084:64/256) and then the system waits. The other position data refer to the block change position.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- Does the acceleration override (P0083:64/256) or deceleration override (P0084:64/256) differ between the actual (current) block and the following block to be changed into? When the “external block change” input signal is detected, the acceleration or deceleration override of the block, which is now current, becomes valid and is immediately effective.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- Was the deceleration changed during the braking ramp when positioning in absolute terms?</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- a change is not accepted. Positioning is realized with the previously set braking ramp (P0084 or P0094).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- The subsequent traversing block in the positioning mode ABS_POS/ABS_NEG (only rotary axis with modulo correction) and the deceleration override (P0084:64/256) between the actual block and the block to be changed into on the fly differ</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>- A block change enable &quot;CONTINUE FLYING&quot; or &quot;CONTINUE WITH STOP&quot; is executed depending on the block change position and the braking travel, i.e. the programmed position is reached by the shortest distance.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong>  For the block change configuration P0110 = 2 or 3, it is not permissible that fast inputs I0.x are used, as, for these, the block change can be initiated from different signal edges.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
6.2 Positioning mode (P0700 = 3, from SW 2.1)

### Table 6-39 Parameters used to program traversing blocks, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td><strong>Note:</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Refer under the index entry &quot;Input signal - external block change&quot;.</td>
</tr>
</tbody>
</table>

- **Example:**
  - Programming 3 traversing blocks
  - Block 1 with **CONTINUE EXTERNAL**

![Diagram](image)

**Note:**
- Refer under the index entry "Input signal - external block change".

#### Spindle positioning (from SW 5.1)

For the "Spindle positioning" function, the target position is programmed in P0081 or transferred via PROFIBUS-DP.

**Note:**
- Refer under the index entry "Spindle positioning"
6.2.11 Starting, interrupting and exiting traversing blocks

Overview

The following input/output signals are available for traversing blocks:

<table>
<thead>
<tr>
<th>Input signals</th>
<th>Output signals</th>
</tr>
</thead>
<tbody>
<tr>
<td>Activate traversing task (edge)</td>
<td>Setpoint acknowledge</td>
</tr>
<tr>
<td>Operating condition/</td>
<td>Setpoint static</td>
</tr>
<tr>
<td>Reject traversing task</td>
<td>Drive stationary/</td>
</tr>
<tr>
<td>Operating condition/</td>
<td>drive moves</td>
</tr>
<tr>
<td>Intermediate stop</td>
<td>Refer, position reached/</td>
</tr>
<tr>
<td>Block selection</td>
<td>Outside the ref. position</td>
</tr>
<tr>
<td>1st input/2^0</td>
<td>Status, block selection</td>
</tr>
<tr>
<td>2nd input/2^1</td>
<td>(from SW 10.1) 1st output/2^0</td>
</tr>
<tr>
<td>3rd input/2^2</td>
<td>2nd output/2^1</td>
</tr>
<tr>
<td>4th input/2^3</td>
<td>3rd output/2^2</td>
</tr>
<tr>
<td>5th input/2^4</td>
<td>4th output/2^3</td>
</tr>
<tr>
<td>6th input/2^5</td>
<td>5th output/2^4</td>
</tr>
<tr>
<td>(from SW 10.1) 7th input/2^6</td>
<td>6th output/2^5</td>
</tr>
<tr>
<td>(from SW 10.1) 8th input/2^7</td>
<td>(from SW 10.1) 7th output/2^6</td>
</tr>
<tr>
<td>(from SW 10.1) 8th output/2^7</td>
<td></td>
</tr>
</tbody>
</table>

Fig. 6-26  Input/output signals for traversing blocks

Note

- Prerequisite for "activate traversing task":
  - All of the enable signals are set and the controlled drive is in the controller enable status (refer to Chapter 5.5, Fig. 5-8).
  - Previous jog operation must have been fully completed – this means that the output signal "Follow-up mode active" must be 0 (Fct. No. 70 or PosZsw.0).
- When starting blocks, there must be at least 3 IPO clock cycles between the signal "activate traversing task" and the motion being interrupted via "OC/reject traversing task" or "OC/intermediate stop". This applies both for operation using PROFIBUS–DP as well as when using terminals.

Reader’s note

Generally, input/output signals are used in the following.
The following is true when viewed from "SIMODRIVE 611 universal":
- for input signals:
  - when entered via terminals -> input terminal signals
  - when entered via PROFIBUS–DP -> control signals
- for output signals:
  - if output via terminals -> output terminal signals
  - if output via PROFIBUS–DP -> status signals
Example: Sequential start of individual blocks

In this case, a new traversing block is only started if the previous block had been completed, i.e. the drive has reached the reference position.

Fig. 6-27 Sequentially starting individual blocks

Note

The selection and the status of the block selection are not binary-coded, but represented, simplified as value.
Intermediate stop

A traversing block can be interrupted using the "operating condition/intermediate stop" control signal.

Features:

- A block which has been interrupted with "intermediate stop" can then be continued.
- An axis in "intermediate stop" can be traversed in the jog mode or referencing can be started. The interrupted traversing block is exited.
- If a traversing block is interrupted using the "wait" command with "Intermediate stop", then the delay (waiting) time is stopped.

**Fig. 6-28** Characteristics of an intermediate stop of a traversing block
6.2 Positioning mode (P0700 = 3, from SW 2.1)

Reject traversing task

A traversing block can be interrupted using the "OC reject/traversing task" control signal.

Features:
- A block, interrupted with "reject traversing task" can no longer be continued.
- A "delete distance to go" is executed.
- It is also possible for a block with intermediate stop.

---

<table>
<thead>
<tr>
<th>Control signal</th>
<th>Status signal</th>
<th>Status signal</th>
<th>Status signal</th>
</tr>
</thead>
<tbody>
<tr>
<td>OC/reject traversing task</td>
<td>Setpoint acknowledge</td>
<td>Reference position reached</td>
<td>Drive at standstill</td>
</tr>
<tr>
<td>OC/intermediate stop</td>
<td>Activate traversing task</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>IPO clock cycles</td>
<td></td>
</tr>
</tbody>
</table>

1. Selecting and starting the traversing block
2. Interrupting the traversing block using "reject traversing task"
   - "operating condition/reject traversing task" is reset
   - "setpoint acknowledgement" is reset
   - the axis is braked down to standstill with the maximum deceleration and "drive stationary" signaled if the speed limit for standstill is fallen below.
   "Reference position reached" is not set.
3. Selecting and starting an additional (or the same) traversing block
4. End of positioning

Fig. 6-29 Characteristics when aborting a traversing block
Diagnostics:
Image of the actual traversing block (refer to Chapter A.1)

Information about the traversing block presently being processed can be read from the following parameters:

- P0001 Actual traversing block - block number
- P0002 Actual traversing block - position
- P0003 Actual traversing block - velocity
- P0004 Actual traversing block - acceleration override
- P0005 Actual traversing block - deceleration override
- P0006 Actual traversing block - command
- P0007 Actual traversing block - command parameter
- P0008 Actual traversing block - mode
6.2.12 MDI operation (from SW 7.1)

**Description**
Using the "MDI operation" function and when in the "positioning" mode it is possible to change the parameters of the MDI block (e.g. reference position, velocity, etc.) via process data and PROFIBUS–DP and/or via parameters (P0091 to P0094, P0097) while this is executed. If, for this particular block, the block change enable CONTINUE EXTERNAL is parameterized, then the changes which were made can be immediately activated with the signal to change the block. This means that the changes are accepted in the interpolator. For the block change enable END, the changes only become effective when this traversing block is re-started in the interpolator.

In this MDI block, only RELATIVE, ABSOLUTE positioning operations can be executed and for rotary axes with modulo correction, in addition, ABS_POS and ABS_NEG.

In this case, only END or CONTINUE EXTERNAL with P0110 = 2 or 3 are permissible as block change enable condition.

**Signal timing MDI**

1. For the earliest possible instant in time to enter new block parameters (PZD and/or default block), refer to Table 6-50 output signal function No. 67.
2. A new positioning operation is started without the MDI end position having been reached.

Fig. 6-30 Control and status signals for MDI
The data available in the block parameters (PZD and/or default block) at instant in time TA is transferred into the interpolator and processed. This data (MDI A) remains valid up to instant in time TB when new data is transferred into the interpolator. In turn, these (MDI B) remain valid until new data is transferred (TC/MDI C).

Note

The following applies for the MDI mode:

- MDI is switched-in using the "activate MDI" signal via terminal (Fct.No. 83) or PROFIBUS (SatzAnw.15). The "MDI active" signal is used for the feedback signal which is either transferred via terminal (Fct. No. 83) or PROFIBUS (AktSatz.15). A traversing block can be entered using process data (MDIPos, MDIVel, MDIAcc, MDIDec, MDIMode) via PROFIBUS-DP and started using the signal "activate traversing task".

- If either no MDI block or only individual block parameters are entered via PROFIBUS-DP, then the missing parameters are taken from the MDI default block (P0091 to P0094, P0097). However, if MDI process data are parameterized in P0915:17 and these are also transferred via PROFIBUS-DP, then the values in parameters P0091 to P0094 and P0097 are not taken into account.

- If CONTINUE EXTERNAL is parameterized as block change enable, then actual block parameters of the MDI block (entered via PZDs and/or MDI default block) are immediately transferred into the interpolator with the signal "external block change".

- For an MDI block, the block change enable signals CONTINUE WITH STOP and CONTINUE FLYING, are not possible. The block change enable CONTINUE EXTERNAL is only permissible with P0110 = 2 or 3 (configuration of an external block change).

- If the signal "Activate MDI" is set to 0 while an MDI block is still running, then fault 144 is initiated. This means that MDI operation can only be disabled after the target position has been reached.

- The signals "operating condition/reject traversing task" and "operating condition/intermediate stop" are effective just the same as in the normal "positioning" operating mode. The monitoring functions, e.g. software and hardware switches are also active.
The MDI block is a positioning block which can contain the following data:

- Position input MSR
- Velocity input \( c \cdot \text{MSR/min} \)
- Acceleration override percentage of P0103
- Deceleration override percentage of P0104
- Mode ID
  - \( x0x = \text{ABSOLUTE} \)
  - \( x1x = \text{RELATIVE} \)
  - \( x2x = \text{ABS_POS} \)
  - \( x3x = \text{ABS_NEG} \)
  - \( 0xx = \text{END} \)
  - \( 3xx = \text{CONTINUE EXTERNAL} \)

The block parameters entered using PZDs via PROFIBUS-DP, are cyclically transferred. The block parameters which do not exist here, are supplemented by the data from the default block (P0091 to P0094, P0097). The parameters, valid up to when the traversing task is activated or the external block change, are then transferred into the interpolator and executed. This means, for example, that it may be sufficient to just enter the position reference value using PZD and to use the remaining data (velocity, acceleration override, etc.) from the default block.

If CONTINUE EXTERNAL block change enable is parameterized in the MDI block then the transfer of the "possibly modified" block parameter into the running or "waiting" MDI block is triggered using the "external block change" signal. P0110 defines when the values become effective i.e. when they are transferred into the interpolator:

- \( P0110 = 2 \)
  The system only waits for the signal at the end of the block; when the signal is detected, a block change is executed.
- \( P0110 = 3 \)
  If the signal is not present up to the end of the block, then the axis waits for the signal and when this is detected, a block change is made. (from SW 5.1).

For the MDI function, only the configuration \( P0110 = 2 \) or \( 3 \) is permitted.

**Note**

If the deceleration was changed during the braking ramp with absolute positioning, then this is not accepted. Positioning is realized with the previously set braking ramp (P0084:256 or P0094).

The input signal "reject traversing task" deletes the programmed MDI block.

The input signal "intermediate stop" holds the MDI block.
6.2 Positioning mode (P0700 = 3, from SW 2.1)

Boundary conditions

- There is only one MDI block.
- The reference point must be approached or set, also for incremental MDI blocks.
- The MDI block can be entered via PROFIBUS–DP or the default block (P0091 to P0094, P0097). A combination is also possible. This means, for example, the position is entered via PROFIBUS and the remaining block parameters are taken from the default block.
- The interpolator requires 2 IPO clock cycles for a block change.
- If the transfer of modified block parameters is initiated using the “external block change” signal while the MDI block is interrupted with an intermediate stop - then after the intermediate stop is withdrawn, the modified block is executed.
- For MDI blocks where the programmed position can no longer be reached in the specified direction of rotation, initially the axis is braked down to standstill and is then moved to the target position in the opposite direction.
- If relative positioning (incremental dimension) is parameterized for an MDI block, then for a CONTINUE EXTERNAL block change enable positioning is re–started from the current actual position with “external block change”.
- The clock cycles (current controller, speed controller, positioning controller and interpolation clock cycle) are, for “SIMODRIVE 611 universal” set as standard and must be increased for a double–axis module for two–axis operation (P1000, P1001, P1009, P1010).
- If, for an MDI block, the deceleration override (STW MDIDec or P0094) is reduced too much, then fault 131 is output. However, for absolute positioning, this only applies if the braking ramp has still not started.
- If, for an MDI block, a block change is initiated, and the new target position does not differ from the previous target position, then the “reference position reached” output signal is not reset.

Parameter overview (refer to Chapter A.1)

The following parameters are available for the "MDI" function:

- P0091: MDI position
- P0092: MDI velocity
- P0093: MDI acceleration override
- P0094: MDI deceleration override
- P0097: MDI mode
- P0110: Configuration, external block change
- P0655: Image, input signals, Part 3
- P0657: Image, output signals, Part 2
- P0915: PZD setpoint assignment, PROFIBUS
- P0916: PZD actual value assignment, PROFIBUS
- P0922: Telegram selection PROFIBUS
The MDI traversing block, transferred using the MDI telegram can be read, as before, using parameters P0001 to P0008.

The following signals are used for the "MDI" function:

- **Input signals**
  
  (refer under the index entry "Input signal, digital - ...)
  
  - Input signal "activate MDI"
    
    --> using an input terminal with function number 83
    --> using the PROFIBUS control signal "SatzAnw.15"
  
  - Input signal "external block change"
    (declares the MDI block valid)
    
    --> using an input terminal with function number 67
    --> using PROFIBUS control signal "STW1.13"
  
  - Input signal "operating condition/reject traversing task (deletes the programmed MDI block)
    
    --> using an input terminal with function number 58
    --> using the PROFIBUS control signal "STW1.4"
  
  - Input signal "operating condition/intermediate stop"
    (holds the MDI block)
    
    --> using an input terminal with function number 59
    --> using the PROFIBUS control signal "STW1.5"

- **Output signals**
  
  (refer under the index entry, "output signal, digital - ...)
  
  The output signals are only effective when "Activate MDI" is selected.
  
  - Output signal "MDI active"
    
    --> using an output terminal with function number 83
    --> using the PROFIBUS status signal "AktSatz.15"
  
  - Output signal "external block change" (this is an image of the input signal "external block change")
    
    --> using an output terminal with function number 67
    --> using the PROFIBUS status signal "AktSatz14"
6.3  Axis couplings (from SW 3.3)

General

"SIMODRIVE 611 universal" allows drives to be coupled via PROFIBUS-DP or via terminals.

The main applications include:

- Position reference value and position actual value coupling ("synchronous operation")
  --> Refer to Chapter 6.3.1
- Torque setpoint coupling ("master/slave operation")
  --> Refer to Chapter 6.3.3

Coupling via PROFIBUS DP

Possible position setpoint sources include:

- PROFIBUS DP master
  
  The position setpoint is provided from a higher-level control, e.g. SIMATIC S7-300.

- Synchronous coupling
  
  Communications is realized using PROFIBUS-DP slave-to-slave communications. One or several slaves (drives) are operated as publishers, i.e. they not only provide their actual values to the DP master, but also to other slaves (subscribers) per broadcast.

  Configuring defines which subscribers accept which data as setpoints from which publisher.

  From the perspective of the coupling, the master drive is a publisher and a slave drive is a subscriber.

Coupling via terminals

The coupling is realized for a

- Position actual value coupling via the angular incremental encoder interface (X461/X462) where the direction can be changed-over.
  
  Up to 31 angular incremental encoder inputs can be connected at angular incremental encoder output. The terminating resistor should be switched-in at the last device (node) (S1.7 and S1.8).

- Torque coupling via analog inputs (X441/X442) or analog outputs (X451/X452).
6.3 Axis couplings (from SW 3.3)

6.3.1 Position reference value and position actual value coupling

"SIMODRIVE 611 universal" as master drive

The master drive must output process data via PROFIBUS–DP which the slave drive can use as position reference value. The following process data is available:

- XsollP (position reference value, number 50208)
- XistP (position actual value, number 50206)

Depending on the actual requirements, it is possible/necessary to output additional process data.

Beyond the output of these signals, the master drive is parameterized as a conventional positioning drive ("Positioning" mode, P0700 = 3). "SIMODRIVE 611 universal" assumes that when the position reference value XsollP is output via PROFIBUS–DP, that it is being used as master drive. In order that the master and slave drive simultaneously process the position reference values, the master drive correspondingly delays transferring data to its own position controller. If the position reference value is only to be output for diagnostic purposes, then the delay can be disabled using P1004.9 = 0.

The angular incremental encoder interface (X461/X462) is set as output with P0890 = 1. This means that the incremental position actual value of the motor encoder or a direct measuring system is output (refer to Chapter 6.8.1).

"SIMODRIVE 611 universal" as master drive, angular increm. encoder interface

An interface for an external position reference value is available in the "positioning" mode (P0700 = 3).

Possible signal sources include:
- PROFIBUS DP
- Angular incremental encoder interface (X461/X462, switched as input)
- Internal coupling in the double axis module

The external position reference value is entered via PROFIBUS–DP with the following process data

- Xext (external position reference value, number 50207)

Depending on the actual requirements, it is possible/necessary to output additional process data.

The normalization of the process data XsollP, XistP (master drive) or Xext (slave drive) can be parameterized using a numerator/denominator pair. This means that not only is a coupling possible between "SIMODRIVE 611 universal" drives, but also with other bus nodes (DP master or DP slave).

When the interface is switched-in, the drive responds to absolute position reference values which are entered via the angular incremental encoder interface, switched as input, or PROFIBUS–DP. In addition, traversing blocks can be executed, which result in superimposed motion.
When the interface is switched-out, the drive can execute, as usual, autonomous movements via traversing blocks.

The position reference value interface can be switched-in/switched-out via an input signal (PROFIBUS-DP or terminal) or via a traversing block.

The following possibilities are available to reference incremental position measuring systems:

- When the interface is switched-out, the drive can be individually referenced as usual (refer to Chapter 6.2.4).

- When the interface is switched-in, the drive follows the reference motion of the master drive via the "passive referencing" function (from SW 5.1).
## 6.3 Axis couplings (from SW 3.3)

### Table 6-40 Overview: Position reference value interface

<table>
<thead>
<tr>
<th>Property</th>
<th>Description</th>
</tr>
</thead>
</table>
| Can be switched-in/out | • Activated via input signal "activate coupling" and "activate coupling via I0.x" or PROFIBUS bit PosStw.4  
  P0410 = 1 Speed-synchronous  
  P0410 = 2 Position-synchronous  
  P0410 = 7 To the absolute position of the master drive from +P0412 (from SW 4.1)  
  • via a traversing block with the COUPLING_IN or COUPLING_OUT command  
  P0410 = 3 Speed-synchronous  
  P0410 = 4 Position-synchronous  
  P0410 = 8 To the absolute position of the master drive from +P0412 (from SW 4.1)  
  • via the traversing block with the COUPLING_IN or COUPLING_OUT command and queue functionality (being prepared)  
  P0410 = 5 Speed-synchronous  
  P0410 = 6 Position synchronous + P0412 |
| Superimposed motion | Yes, via traversing blocks with the coupling switched-in |
| Autonomous motion | Yes, via traversing blocks with the coupling switched-out |
| Possible position reference value source | • Angular incremental encoder interface switched as input  
  • Drive A (for an internal coupling)  
  • PROFIBUS-DP master (clock cycle synchronous operation) (from SW 4.1)  
  • PROFIBUS-DP slave (slave-to-slave communications) (from SW 4.1) |
| Parameterize the angular incremental encoder interface as output | • P0892 Factor, angular incr. enc. pulse no./enc. pulse no.  
  • P0893 Angular incremental encoder zero pulse offset  
  --> Refer to Chapter 6.8.1 |
| Parameterize the angular incremental encoder interface as input | • P0891 Source, external position reference value  
  • P0894 Angular incremental encoder input signal waveform  
  • P0895 External position reference value - No. of increments  
  • P0896 Ext. position reference value - No. of dimension system grids  
  • P0897 Inversion, external position reference value  
  • P0401 Coupling factor, revolutions master drive  
  • P0402 Coupling factor, revolutions slave drive  
  --> Refer to Chapter 6.8.2 |
| Parameterize PROFIBUS interface as input | • P0891 Source, external position reference value  
  • P0895 External position reference value - No. of increments  
  • P0896 Ext. position reference value - No. of dimension system grids  
  • P0897 Inversion, external position reference value  
  • P0898 Modulo range, master drive  
  • P0401 Coupling factor, revolutions master drive  
  • P0402 Coupling factor, revolutions slave drive |
| Referencing for incremental measuring systems | Required, if autonomous or superimposed motion has to be executed via traversing blocks  
  --> Refer to Chapter 6.2.4 |
| Available in the operating mode | "Positioning" (P0700 = 3) |
Application possibilities

- Angular incremental encoder interface, switched as input, as position reference value source.

For a double-axis module, an internal coupling can be switched-in with drive A as master drive and drive B as slave drive.

Advantage:
For the internal position actual value coupling, the angular incremental encoder interface is not assigned.

---

**Fig. 6-31 Angular incremental encoder interface as position reference value source**

**Fig. 6-32 Internal position actual value coupling**
• DP master as position reference value source (clock cycle synchronous operation recommended).

Fig. 6-33 DP master, e.g. SIMATIC S7-300, as source for "external position reference value"

• Synchronous coupling between several DP slaves via slave-to-slave communications, of which, one must be a master drive.

Fig. 6-34 Synchronous coupling between several DP slaves
6.3 Axis couplings (from SW 3.3)

**Parameterizing the setpoint source**

The external position reference value source is selected using P0891.

- P0891 = 0  Angular incremental encoder interface (X461/X462)
- P0891 = 1  Motor encoder Drive A  
  (only for compatibility, recommended P0891 = 2)
- P0891 = 2  Position actual value, drive A
- P0891 = 3  Position reference value, drive A
- P0891 = 4  Coupling via PROFIBUS-DP  
  (the telegram must be appropriately parameterized for the master and slave drive sides)

P0891 = 1, 2 or 3 is only possible on drive B for a double-axis module.

In case of resolvers and changeover of the resolution 12 bits → 14 bits in Drive A, a four-fold value is to be parameterized using SimoCom U as follows in Drive B:

- In the display of the information of the selected "Couplings" dialog box
  → "Position input evaluation" entry field
- In the "Expert list"
  → Changing Parameter P0895

**PROFIBUS-DP process data and standard telegrams**

The following process data is available for the master drive:

- XsollP (position reference value, number 50208)
- XistP (position actual value, number 50206)
- QZsw (status word, slave-to-slave communications, number 50118)
- dXcor (correction, position reference/actual value, number 50210)

The process data XsollP, QZsw and dXcor are included in standard telegram 108.

The following process data are available for the slave drive:

- Xext (external position reference value, number 50207)
- QStw (status word, slave-to-slave communications, number 50117)
- dXcorExt (correction, external position reference value, number 50209)

The process data Xext, QStw and dXcorExt are included in standard telegram 109.

For a position reference value coupling between "SIMODRIVE 611 universal" drives, we recommend that standard telegram 108 is used for the master drive and standard telegram 109 for the slave drive.
Note

- It is not necessary to transfer $dX_{cor}$ or $dX_{corExt}$ if, with the coupling switched-in, no external jumps/steps can occur in the external position reference value.

- It is not necessary to transfer $QZ_{sw}$ or $Q_{Stw}$ if, when the coupling is switched-in, no external jumps/steps can occur in the position reference value and the "passive referencing" function is not required.

- In the example in Chapter 5.10.5 for coupling 2 drives (master, slave drive) a description is provided how the hardware configuration can be parameterized for the necessary slave-to-slave data transfer and with SimoCom U, the telegrams.
Setpoints, entered via the source, are evaluated at the input for the following couplings:

- --> via the angular incremental encoder (P0891 = 0 or 1)
- --> via PROFIBUS–DP (P0891 = 4)

- Input format (slave drive):
  - Xext (external position reference value, number 50207)
  - dXcorExt (correction, external position reference value, number 50209)

  The following applies: Position in MSR = input value \( \frac{P0896}{P0895} \)

- The output is evaluated --> PROFIBUS–DP
  
  Output format (master drive):
  - XsollP (position reference value, number 50208)
  - XistP (position actual value, number 50206)
  - dXcor (correction, position reference/actual value, 50210)

  The following applies: Output value = position in MSR \( \frac{P0884}{P0896} \)

  The output value must be able to be represented using 32 bits. This means that the maximum traversing distance that can be represented is:

  \[
  -2^{31} \frac{P0896}{P0895 (P0884)} \cdots \left(2^{31}-1\right) \frac{P0896}{P0895 (P0884)}
  \]

- The standard settings for PROFIBUS–DP are:
  - P0884 = 10000
  - P0895 = 10000
  - P0896 = 10000 MSR (\(\mu\)m)

  Recommendation: Modify the standard setting as follows to achieve the best possible resolution:
  - P0884 = 2048
  - P0895 = 2048
  - P0896 = 5 MSR (\(\mu\)m)

  For this setting, the resolution is \(\frac{5}{2048}\) \(\mu\)m

  and the traversing distance that can be represented is \(\pm\ 5.24\) m.

---

**Note**

Changes to P0884, P0895 and P0896 are incorporated in P0032 (external position reference value).

---

**Position reference value inversion**

The external position reference value can be inverted using P0897.

---

**Note**

Changes to P0897 are incorporated in P0032 (external position reference value).
6 Description of the Functions

6.3 Axis couplings (from SW 3.3)

**Coupling factor**
A coupling factor for all setpoint sources can be defined using P0401 and P0402. Revolutions of the master drive (P0401) correspond to revolutions of the slave drive (P0402).

**Setpoint steps**
If steps (jumps) occur in the external position reference value, e.g. after referencing the master drive, this must be signaled to the slave drive so that this does not execute this step.

- Coupling via PROFIBUS DP
  --> QZsw.0 = 1 (publisher) or QStw.0 = 1 (subscriber)
  The amplitude of the step is transferred in dXcor and is received in the dXcorExt.

- Coupling via the angular incremental encoder
  --> not necessary, as it involves an incremental setpoint input
  Exception:
  For P0891 = 7 or 8, it may be necessary to use the signal "setpoint, master drive" on the slave drive side.

**Note**
- A "SIMODRIVE 611 universal" as slave drive also operates with PROFIBUS master drives together which do not support the concept of multiple correction value transfer. The only thing that is necessary, is that, for a setpoint step, the control bit and the correction value are correctly set. In this case, there is a danger, that after the telegram has been lost, a setpoint step occurs.
- The slave drive corrects the setpoint when the 0/1 edge of the control bit is detected.
- If it can be ensured that at the instant that the setpoint step occurs, there is no coupling, then it is not necessary to transfer the step location Xcor.

**Coupling configuration (P0410)**
The coupling type is configured in the slave drive using P0410. The following is defined for a coupling via P0410:

- Can be switched--in/switched--out via an input signal or traversing block
- Speed synchronism, position synchronism or to the absolute position of the master drive

--> refer to the following information.

For PROFIBUS-DP, P0410 = 7, i.e. can be switched-in/out via the input signal, coupling is preset to the absolute position.
For P0410 = 1, 2 or 7, the coupling can be switched-in/out via an input signal.

The following applies:

- When switching-in/switching-out the coupling, the drive to be coupled must remain stationary and a traversing program may not run.
- The coupling is switched-in/switched-out using the "activate coupling" input signal. The input signal can be entered via input terminal or via PROFIBUS DP.
  - via an input terminal with function number 72 and 73
  - Via PROFIBUS signal "PosStw.4"

What can be programmed for the coupling that is switched-in?

After the "activate traversing task" input signal, traversing blocks can be programmed with the commands:
- Relative position input, WAIT, GOTO, SET_O, RESET_O,
- ENDLESS TRAVERSING_POS, ENDLESS TRAVERSING_NEG

- Additional block change enable circuits are:
  - Block change enable END, CONTINUE WITH STOP, CONTINUE FLYING and CONTINUE EXTERNAL (only for P0110 = 2)
- The coupling can be configured for speed synchronism, position synchronism or an absolute position.
  - P0410 = 1 Speed synchronism via input signal
    --> refer to Fig. 6-35
  - P0410 = 2 Position synchronism via input signal
    --> refer to Fig. 6-36
  - P0410 = 7 Absolute position (from SW 4.1)

Note

If a traversing block is parameterized with COUPLING_IN and/or COUPLING_OUT and if the coupling is to be controlled using a digital signal, then when any traversing block is started, fault 166 is always output (not that traversing block with COUPLING_IN or with COUPLING_OUT).
6 Description of the Functions

6.3 Axis couplings (from SW 3.3)

Coupling-in/out via traversing block (P0410 = 3, 4 or 8)

For P0410 = 3, 4 or 8, the coupling can be switched-in/switched-out via a traversing block.

The following applies:

- The coupling is switched-in/switched-out using the following commands:
  - COUPLING_IN
    What happens after COUPLING_IN?
    The drive waits until synchronism is achieved, and then executes the appropriate block change enable.
    When programmed with CONTINUE FLYING, the command always results in the block change enable CONTINUE WITH STOP.
    What can be programmed for the coupling that is switched-in?
    Traversing blocks can be programmed with the commands: Relative position data, WAIT, GOTO, SET_O, RESET_O.
    For ENDLESS TRAVERSING_POS, ENDLESS TRAVERSING_NEG, fault 105 is output.
    For a coupling that is kept closed, the programmed value is switched to the position reference value, received via the angular incremental encoder interface, so that a superimposed motion is obtained.
  - COUPLING_OUT
    What happens after COUPLING_OUT?
    The drive switches-out the coupling, brakes down to standstill, and then executes the programmed block change enable.

- Additional block change enable circuits are:
  Block change enable END, CONTINUE WITH STOP, CONTINUE FLYING and CONTINUE EXTERNAL (only for P0110 = 2)

Note

- For blocks with COUPLING_IN/COUPLING_OUT, a block change enable with CONTINUE FLYING is not possible.
- For blocks with COUPLING_OUT, a block change enable with CONTINUE EXTERNAL is not possible.

- The coupling can be configured for speed synchronism, position synchronism or an absolute position.
  - P0410 = 3  Speed synchronism via traversing block
    --> refer to Fig. 6-35
  - P0410 = 4  Position synchronism via traversing block
    --> refer to Fig. 6-36
  - P0410 = 8  Absolute position (from SW 4.1)
    --> refer to Fig. 6-37
6.3 Axis couplings (from SW 3.3)

**Speed synchronism (P0410 = 1 or 3)**

For a speed-synchronous coupling, the drive accelerates after the coupling has been switched-in, with the acceleration in P0103, up to the speed of the master drive.

The following error, that is automatically obtained when the slave drive accelerates due to the different output velocities, is no longer reduced to zero.

The position difference of the two drives is constant in the synchronous phase.

![Diagram of speed synchronism](image)

**Fig. 6-35  Speed synchronism (P0410 = 1 or 3)**

**Reader’s note**

The phases are described in Table 6-41.
For the position--synchronous coupling, the slave drive takes into account the distance moved by the master drive and the position offset, entered in P0412.

After speed synchronism has been reached, the following error which has occurred and the position offset in P0412 is moved through with the supplementary speed in P0413.

Contrary to the coupling to the absolute position, an offset between the master and slave drives, existing before the coupling was established, is no longer taken into account in the offset phase.

**Reader’s note**

The phases are described in Table 6-41.
With this function, the slave drive, for P0410 = 7 or 8, synchronizes to the absolute position of the master drive plus an adjustable offset P0412. After synchronization, the master and slave drives have the same absolute position with the exception of the offset P0412.

The coupling can be switched-in/out using an input signal (P0410 = 7) or using a traversing block (P0410 = 8).

The following secondary conditions must be observed in order to realize a coupling to an absolute position:

- For P0891 = 2, 3 or 4, the master drive absolute position is available to the slave drive.
- For P0891 = 0 or 1, the slave drive absolute position is not automatically made available to the slave drive.

The reference point coordinates are communicated to the slave drive once using the input signal "set position reference value, master drive" (function number 74) if the source of the external position reference value is either the angular incremental encoder interface (P0891 = 0), or for double-axis modules, the motor encoder of drive A (P0891 = 1). The value of P0400 (reference point coordinate, master drive) is written into P0032 (external position reference value).

After a positive edge, the display parameter P0032 "External position reference value" coincides with the master drive absolute position.

A coupling should only be closed at the absolute position of the master drive after "set setpoint, master drive" as only then can be guaranteed that the slave drive has been correctly referenced.

- --> refer to the example, Chapter 5.10.5
Fig. 6-37 To absolute position (P0410 = 7 or 8)

Reader’s note
The phases are described in Table 6-41.
Table 6-41 Description of the phases for speed or position synchronism

<table>
<thead>
<tr>
<th>Phases</th>
<th>Speed-synchronous (P0410 = 1 or 3)</th>
<th>Position-synchronous (P0410 = 2 or 4)</th>
<th>Absolute position (P0410 = 2 or 4) (from SW 4.1)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ramp-up phase</td>
<td>After the coupling has been switched-in, the speed setpoint for the slave drive is ramped up to the master drive speed. The ramp gradient corresponds to the acceleration in P0103. This phase is completed after the slave drive has reached the speed of the master drive.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Offset phase</td>
<td>-</td>
<td>After speed synchronism has been reached, the summed following error and the position offset, entered in P0412 is moved through with speed vLA + P0413.</td>
<td>After speed synchronism has been reached, the drive moves by the offset in the absolute position of the master and slave drive and the position offset, entered into P0412 with speed vLA + P0413.</td>
</tr>
</tbody>
</table>
| Synchronous phase| For coupling-in/out using the input signal, the following applies (P0410 = 1, 2 or 7):  
- -> A traversing program can be started.  
For coupling-in/out using the traversing block, the following applies (P0410 = 3, 4 or 8):  
- -> The traversing program is continued.  
Note:  
• The setpoint input via the angular incremental encoder interface, switched as input, and the setpoint input via the traversing blocks are superimposed on one another.  
• Traversing blocks with relative position data are permissible.  
• -> refer under the index entry "Output signal, digital - in synchronism" |                                                                                            |                                                  |
| Braking phase    | After the coupling has been switched-out, the drive goes into the braking phase and brakes down to standstill with the deceleration set in P0104.  
For coupling-in/out using the input signal, the following applies (P0410 = 1, 2 or 7):  
- -> A traversing program can be started.  
For coupling-in/out using the traversing block, the following applies (P0410 = 3, 4 or 8):  
- -> The traversing program is continued.  
Note:  
For coupling-in/out via input signal, the braking phase may only be initiated, if a traversing program is no longer running for the slave drive. |                                                                                            |                                                  |
6 Description of the Functions

6.3 Axis couplings (from SW 3.3)

**Coupling using the queue functionality (P0410 = 5 or 6) (being prepared)**

With this function, a coupling is established between the master and slave drives depending on a position memory (queue) being processed.

- Coupling always switched-in/out always via the traversing program
- P0410 = 5: Speed-synchronous
- P0410 = 6: Position-synchronous

**Application example, queue functionality (refer to Fig. 6-38)**

The master drive drives a conveyor belt. The position of the workpieces is detected using a measuring probe and saved in the slave drive in P0425:16. If a workpiece approaches its waiting position, the slave drive must accelerate in plenty of time so that it can move in synchronism with the workpiece in the machinery range.

**Requirements:**

If a workpiece is detected, the distance, measured to the actual slave drive position is continuously entered into P0425:16. The first workpiece is entered under P0425:0 and the last under P0425:15.

A maximum of 16 positions can be saved --> otherwise, fault 168 is output (overflow, buffer memory).

For slave drives, a traversing program cyclically runs with coupling and machining commands.

**Sequence:**

1. The COUPLING IN command is executed, i.e. the slave drive waits to be synchronized to the master drive.

2. When will synchronization start, i.e. when will the coupling be switched-in?

   Synchronization is started when the next workpiece has reached the slave drive, i.e. if the distance between the workpiece and the slave drive in the next interpolation clock cycle k is

   \[ \frac{v_{LA}^2}{2a_{FA}} \] less than

   - \( v_{LA} \) Velocity, master drive
   - \( a_{FA} \) Acceleration, slave drive

3. To start, speed synchronism is established. After this, the oldest position is deleted from the position memory and for P0410 = 6, position synchronism established.

   The equalization motion is extremely short, as synchronization is predictive.

   After synchronization has been established, additional commands can be executed (e.g. to machine the workpiece).

   For the commands, the same conditions apply as for the program-mable couplings.
4. The coupling is switched-out using the command COUPLING_OUT. The drive remains stationary and the program is continued. From this time onwards, there are no restrictions regarding the commands.

The slave drive can be returned to the waiting position e.g. using an additional command (POS ABS).

---

**Traversing program in the slave drive**

COUPLING IN ; wait until the next workpiece comes close
POS REL ; relative traversing motion
... blocks to be processed (i.e. for machining)
COUPLING OUT
POS ABS waiting position ; retraction to the waiting position
GOTO start

---

Fig. 6-38 Application example: Coupling via an input terminal with queue functionality
In order to implement an axis coupling for modulo rotary axes, the following settings must be made:

- Which settings have to be made for the master axis?
  - "Positioning" mode (P0700 = 3)
  - Set the modulo rotary axis (P0241, P0242)

- Which settings have to be made for the slave axis?
  - "Positioning" mode (P0700 = 3)
  - Set the modulo rotary axis (P0241, P0242)
  - For the slave axis, the modulo range of the master axis must be specified in P0898.

  i.e.: P0242 (master axis) = P0898 (slave axis)

**Note**

The modulo range of the master axis can be the same or not equal to the modulo range of the slave axis.

i.e.: P0242 (master axis) = or ≠ P0242 (slave axis)

---

**Modulo correction**

Position reference value steps as a result of modulo correction are detected by the slave drive itself, i.e. it is not permissible that control bit QStw.0 or the correction value dXcorExt are set.

The following is required:

- P0898 must be correctly parameterized for the slave drive.
- The traversing difference between two position reference values is the maximum of half the modulo range (so that the direction of motion is clear)

**Telegram loss**

Telegrams may be lost when transferring data via Profibus-DP. In this case, the slave drive must extrapolate a new reference value position from the previous acceleration and velocity.

The correct position is only approached with the next valid telegram. If more telegrams are lost than are parameterized in P0879, Fault 595 or 597 is output and the drive comes to a standstill.

**Boundary conditions**

The following secondary conditions must be observed for position reference value and actual value coupling:

- Resolution of the angular incremental encoder interface
  
  It should be carefully observed that the coupling must be configured with a high resolution (encoder), e.g. for
  
  --> a good resolution: 2048 pulses correspond to 10 mm
  
  --> a poor resolution: 1250 pulses correspond to 1500 mm
• **Travel to fixed stop and axis coupling**
  - It is not permissible to activate the "travel to fixed stop" function when in the coupled mode (Fault 173).
  - The axis coupling cannot be switched-in during the "travel to fixed stop" function (Fault 173).

• If it is predicted that a software limit switch will be passed, for coupled axes, one of the following faults/warnings will be signaled:
  - Fault 132 or 133 after a software limit switch has been passed (minus or plus)
  - Warning 891 (software limit switch PLUS actuated, coupled)
  - Warning 892 (software limit switch MINUS actuated, coupled)

For a coupled drive, there is no response to warning 891 or 892. This can be signaled to the master drive using the output signal "warning present"; this then allows the master drive to respond.

• **Only relative position data is permissible for traversing blocks when in the coupled mode (Fault 165).**

• **During an active coupling, a block change enable CONTINUE EXTERNAL** is only possible with P0110 = 2 (Fault 172).

• **The position of the master drive, at which the coupling was requested, is in P0425:0.**

• **The following applies for P0410 = 1, 2 or 7:**
  - It is not possible to program the commands COUPLING_IN or COUPLING_OUT (Fault 166).
  - The coupling can be switched-in/switched-out via input terminal as follows:
    1.) Assign function 72 to any input terminal
    --> Input signal "activate coupling"
    or
    2.) (recommendation, as it is a fast input)
    Assign function number 73 to input terminal I0.x
    --> Assign the input signal "Activate coupling via I0.x"
    and
    function number 72 to any other input terminal
    --> Input signal "Activate coupling"
    (refer to Chapter 6.4.3 Function numbers 72 and 73)

• **The following applies for P0410 = 3, 4 or 8:**
  The coupling cannot be switched-in/switched-out via an input signal.
6 Description of the Functions

6.3 Axis couplings (from SW 3.3)

- Rotary axis with modulo correction and basic coupling

  The following applies for SW 3.3:
  The coupling mode for rotary axes with modulo correction is not per-
  missible for the master and slave drive.

  The following applies from SW 3.5:
  The coupling mode is permissible for rotary axes with modulo
  correction.

- Direct measuring system and axis coupling

  For a drive with direct measuring system, the actual values of the
  motor measuring system are always output via the angular incre-
  mental encoder interface switched as output.

  This means that an actual value coupling cannot be realized using
  the direct measuring system.

- The following applies for P0410 = 5 or 6 (from SW 3.5):
  - It is only possible to precisely determine the position using the
    fast input I0.x.
  
    --> refer under the index entry "Input signal, digital – flying mea-
  
    - The standstill time of the slave drive up to the next workpiece
      must be at least 1 IPO clock cycle (P1010).
  
    - After COUPLING OUT for the slave drive, the drive should re-
  
    - After COUPLING OUT for the slave drive, the drive should re-
  
  
- The following secondary conditions have to be taken into consider-
  ation when parameterizing P0891:
  - The following applies for P0891 = 1:
    
    --> only exists for drive B;
  
    --> for drive A, P0891 must be 0
  
  - The following applies for P0891 = 2 or 3:
    
    --> Selectable for drive A or B
  
    --> The other drive is then the master drive where P0891
      must be set to 0.

    --> Coupling via the input signal "Activate coupling via
  
    - If a setpoint source is selected, which is not available for the drive,
  

• It is possible to have mixed operation of position reference value sources within a drive group. For instance, drive A can receive its setpoint via the angular incremental encoder and transfer this to other drives via PROFIBUS-DP. The following secondary conditions must be observed:
  - The synchronous operation of the drive group is poor as a result of the different data propagation times.
  - There are differences in the position resolution between the individual sources.

• Limitations for a slave axis

**Warning**

When superimposing the speed of the master and slave drives, a resulting slave drive speed can be obtained which is greater than the maximum speed P0102. For slave axes, the speed monitoring in P1147, P1401:8 and P1405:8 applies.

**Note**

For coupled operation via PROFIBUS-DP, we recommend that internal couplings are not used. Instead, the second drive should be parameterized as subscriber (refer to Chapter 5.10).

• Display of position actual value X_{act}\hspace{1mm}P\hspace{1mm}position actual value X_{set} for double-axis modules with "SimoCom U commissioning tool":

The displayed value of X_{act}\hspace{1mm}P/X_{set}\hspace{1mm}P in the information display of the selected "PROFIBUS parameterization" dialog box can vary slightly as compared to the displayed actual values/setpoints at the position displays of the SimoCom U (approx. 1 \mu s).

• Coupling via angular incremental encoder interface with "coarse encoder resolution":

Prior to SW 10.1:
For axis couplings, the angular incremental encoder interface can be configured as documented previously.

Starting with SW 10.1:
For an axis coupling with the "Source, external position reference value" function, "Angular incremental encoder interface X461/X642 (coarse)" must be selected. This results in P0891 = 5.
The slave drive cannot autonomously reference if there is a permanent coupling. Instead, the master drive specifies the referencing motion. Using passive referencing, the slave drive can also be referenced.

When executing passive referencing, the slave drive is precisely repositioned at its own reference point.

The following commissioning help is available to determine and enter the reference point offset for the slave drive.

This means, e.g. that it is possible, for a gantry group, to automatically correct any possible skewing.

Passive referencing is possible for axes with absolute or incremental encoder. However, the drive with the absolute value encoder must first be adjusted using absolute value setting (Fault 176).

- Master and slave drive with incremental encoder.

**Passive referencing for a slave drive (from SW 5.1)**

---

**Fig. 6-39 Sequence when passively referencing (master and slave drive with incremental encoder)**

<table>
<thead>
<tr>
<th>Phase 1</th>
<th>2</th>
<th>3</th>
<th>4</th>
</tr>
</thead>
<tbody>
<tr>
<td>Zero mark</td>
<td>P0162</td>
<td>Reference point (P0160)</td>
<td></td>
</tr>
<tr>
<td>Output signal</td>
<td>&quot;request passive referencing&quot;</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Velocity profile</td>
<td>Master drive (encoder: incremental)</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Velocity profile</th>
<th>Slave drive (encoder: incremental) (permanent coupling)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Input signal</td>
<td>&quot;reference cams&quot;</td>
</tr>
<tr>
<td>Input signal</td>
<td>&quot;request passive referencing&quot;</td>
</tr>
<tr>
<td>Output signal</td>
<td>&quot;in synchronism&quot;</td>
</tr>
<tr>
<td>P0160</td>
<td>Reference point coordinates</td>
</tr>
<tr>
<td>P0162</td>
<td>Reference point offset</td>
</tr>
</tbody>
</table>

---

| Velocity profile | Slave drive (encoder: incremental) | |
|-----------------|-----------------------------------|
| Zero mark | P0162 | Reference point (P0160) |
| possible offset due to "soft" coupling | | |
| Synchronization function | | |

---

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SIMODRIVE 611 universal Function Manual (FBU) - 05/2010 Edition
- Master drive with absolute value encoder and slave drive with incremental encoder.

Fig. 6-40  Sequence when passively referencing (master drive with absolute value encoder, slave drive with incremental encoder)

If the slave drive with incremental encoder does not have any reference cams, then it must be referenced using the "set reference point" input signal.
• Master drive with incremental encoder and slave drive with absolute value encoder.

![Diagram showing sequence when passively referencing (master drive with incremental encoder and slave drive with absolute value encoder)](image)

**Note**

For a rigid mechanical coupling between the master and slave axes, it is not permissible that P0179 is set to 2 if the slave drive is equipped with an absolute value encoder. Otherwise, the slave drive would position (in absolute terms) to the position specified in P0160.

• Master and slave drive with absolute value encoder.

For master and slave drive with absolute value encoder, passive referencing is not practical, as the axes have been adjusted corresponding to Chapter 6.2.7 (Adjustment for absolute measuring systems).
The following timing for passive referencing applies when using incremental encoders for the master and slave drives. When referencing the master drive, after its zero mark is reached, passive referencing for the slave drive is requested. The master drive then traverses through the reference point offset up to the reference point.

During this travel, the slave drive must detect a 1/0 edge at the "reference cam" input signal and then its own zero mark.

After the master drive has reached its reference point, the slave drive is moved to its reference point.

- **Phase 1**  
  Master drive searches for its zero mark  
  The master drive has moved away from the reference cam and searches for the next zero mark.  
  After the zero mark has been found, the following is initiated:  
  - The drive is braked down to standstill  
  - Master drive:  
    Set the "request passive referencing" output signal  
  - Slave drive:  
    When the "request passive referencing" input signal has been detected, the slave drive starts to search for the 1/0 edge of the input signal "reference cam" after which it searches for the zero mark

- **Phase 2**  
  The master drive starts to its reference point  
  The master drive moves to traverse to its reference point. During this traversing operation, the slave drive continues to search for its zero mark.

- **Phase 3**  
  The master drive approaches its reference point  
  When the reference point is reached, the following is initiated:  
  - The "request passive referencing" output signal is reset  
  If the slave drive, up to this instant in time, has not found a zero mark, fault 175 is signaled.

- **Phase 4**  
  Slave drive referenced  
  - For P0179 = 0  
    After the reference point is reached, the value from P0160 is accepted as new actual value (set reference point).  
  - For P0179 = 2  
    After the axis has reached its standstill position, the axis is traversed, corresponding to P0162, to its own reference point with the velocity defined in P0413. The value from P0160 is then accepted as new actual value.

--- Refer under the commissioning help for passive referencing of the slave drive
Commissioning help to passively reference the slave drive (from SW 5.1)

The commissioning help is used to determine the reference point offset in P0162 for the slave drive.

Requirements: Set P0179 = 0

1. Carry-out passive referencing as usual (Fig.6-39).

Note

To execute the following points, the master drive must be precisely positioned at its reference point!

2. Slave drive:
   - In the jogging mode, the axis moves to its measured reference point

Note

Before "jogging", the coupling must be switched-out, otherwise "jogging" is not possible. Switch-in the coupling again afterwards.

3. Slave drive:
   - Set P0179 = 1
     --> the distance between the zero mark and approached reference point is saved as offset in P0162
   - P0179 is internally set to 2

4. Save the parameters in the FEPROM

5. Carry-out a power on

This means that for future referencing, the reference point of the slave drive is "correctly" approached.

Secondary conditions and limitations when passively referencing (from SW 5.1)

The following secondary conditions apply:

- The slave drive must find its own zero mark during phases 2 and 3.
- Passive referencing between the master and slave drive is controlled using the following signals:
  - Master drive: Output signal "request passive referencing"
    --> using the output terminal with function number 69 (refer to Chapter 6.4)
    --> using the PROFIBUS status signal QZsw.1 (refer to Chapter 5.6.3)
  - Slave drive: Input signal "request passive referencing"
    --> using an input terminal with function number 69 (refer to Chapter 6.4)
    --> using the PROFIBUS control signal QStw.1 (refer to Chapter 5.6.2)
The master drive output signal should be connected to the input signal of the slave drive.

Exception:

If, for a double-axis module, \( P0891 \) (B) = 1, i.e. the position actual value of drive A is internally connected to the position reference value from drive B, then the following applies:

The "request passive referencing" output signal from drive A (master drive A) is internally and automatically recognized by drive B (slave drive). In this case, external wiring is not required.

- The permanent coupling can be switched-in via an input signal or with the traversing block. Additional traversing blocks are not permitted.

Example, switching-in with a traversing block using the "Start-up Tool SimoCom U":
Command: COUPLING IN
Block change enable: End

- If reference point approach is started at the master drive, and the slave drive is coupled-out and coupled-in again, then the slave drive outputs faults 131 and 605 if the master drive has reached its reference point. This means that after a reference point approach has been started, it is no longer possible to de-couple the axes.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0179</td>
<td>Mode, passive referencing (from SW 5.1)</td>
</tr>
<tr>
<td>P0400</td>
<td>Ref. point coordinate, master drive (from SW 4.1)</td>
</tr>
<tr>
<td>P0401</td>
<td>Coupling factor, revolutions master drive</td>
</tr>
<tr>
<td>P0402</td>
<td>Coupling factor, revolutions slave drive</td>
</tr>
<tr>
<td>P0410</td>
<td>Configuration, coupling that can be switched-in</td>
</tr>
<tr>
<td>P0412</td>
<td>Synchronous offset position</td>
</tr>
<tr>
<td>P0413</td>
<td>Offset, synchronous velocity</td>
</tr>
<tr>
<td>P0420</td>
<td>Position difference, measuring probe to the zero point, slave drive (from SW 3.5)</td>
</tr>
<tr>
<td>P0425:16</td>
<td>Coupling positions</td>
</tr>
<tr>
<td>P0884</td>
<td>Position output value PROFIBUS - No. of increments</td>
</tr>
<tr>
<td>P0891</td>
<td>Source, external position reference value</td>
</tr>
<tr>
<td>P0895</td>
<td>External position reference value - No. of increments</td>
</tr>
<tr>
<td>P0896</td>
<td>Ext. position reference value - No. of dimension system grids</td>
</tr>
<tr>
<td>P0897</td>
<td>Inversion, external position reference value</td>
</tr>
<tr>
<td>P0898</td>
<td>Modulo range, master drive (from SW 3.5)</td>
</tr>
</tbody>
</table>
The following signals are used for the function "axis coupling":

- **Input signals**
  (refer under index entry "Input signal, digital - ...")
  - Input signal, "activate coupling"
    --> using an input terminal with function number 72
    --> using the PROFIBUS control signal "PosStw.4"
  - Input signal, "activate coupling via I0.x"
    --> using an input terminal with function number 73
  - Input signal "set setpoint, master drive" (from SW 4.1)
    --> using an input terminal with function number 74
  - Input signal "request passive referencing" (from SW 5.1)
    --> using an input terminal with function number 69
    --> using the PROFIBUS control signal "STW1.15" or alternatively "QStw.1"

- **Output signals**
  (refer under the index entry, "Output signal, digital - ...")
  - Output signal "in synchronism"
    --> using an output terminal with function number 71
    --> using the PROFIBUS status signal "PosZsw.3"
  - Output signal "Request passive referencing" (from SW 5.1)
    --> using an output terminal with function number 69
    --> using the PROFIBUS control signal "ZSW1.15" or alternatively "QZsw.1"

**Additional input/output signals**

- **Input signals**
  (refer under index entry "Input signal, digital - ...")
  - Input signal, "set reference point"
  - Input signal "reference cams"

- **Output signals**
  (refer under the index entry, "Output signal, digital - ...")
  - Output signal, "controller enable status"
  - Output signal "fault present"
  - Output signal, "warning present"
6.3.2 Handling faults in the master and slave drives

Overview

If a coupling is active, the master drive must be able to respond to slave drive faults.

It must also be guaranteed that the slave drive is reliably stopped, if the master drive develops a fault.

Faults in the slave drive

Dependent on the stop responses, the following should be observed for faults and warnings in the slave drive:

Table 6-42 Behavior when faults develop in the slave drive

<table>
<thead>
<tr>
<th>Fault situations</th>
<th>What happens when these fault situations occur?</th>
</tr>
</thead>
</table>
| Faults with stop response STOP I STOP II STOP III | • The coupling is disconnected (switched-out)  
• The slave drive is appropriately braked  
• Output signals  
  - Status, controller enable = 0  
  - Fault present = 1  
  - Warning present = 0 |
| Faults with stop response STOP IV STOP V STOP VI | • Block processing is interrupted  
• The slave drive remains closed-loop controlled and coupled  
• Output signals  
  - Status, controller enable = 1  
  - Fault present = 1  
  - Warning present = 0 |
| Warnings with stop response STOP VII | • No response for the slave drive  
• Output signals  
  - Status, controller enable = 1  
  - Fault present = 0  
  - Warning present = 1 |
| Controller enable withdrawn | • When the controller enable is withdrawn, this does not have to result in faults being output  
• Output signals  
  - Status, controller enable = 0  
  - Fault present = 0  
  - Warning present = 0 |

Note:

The required stop response can be initiated for a group of axes by appropriately externally evaluating the output signals of the slave drive.
**Example:**

In Fig. 6-42 it is shown how a differentiation can be made between these three stop classes as well as the withdrawal of the controller enable from the three output signals "status, controller enable", "fault present" and "warning present". Furthermore, it is indicated how the master drive and therefore the other slave drives could respond to these signals.

---

**Note**

The logical operations can be further optimized for the displayed behavior. However, at this position, it is important that a differentiation can be made between the various fault classes.

---

![Diagram](image)

**Faults in the master drive**

Faults in the master drive can be just as flexibly handled as the faults in the slave drive which were discussed above.

In this case, the master drive output signals are used, and are correspondingly connected to the input signals of the slave drive.

For an actual value coupling, it is not absolutely necessary to handle master drive faults, as the slave drive follows the actual value of the master drive anyway, and brakes when a fault situation develops.

On the other hand, for a setpoint coupling, it should be ensured that when the setpoints fail, the group of axes is correctly stopped.
6.3.3 Torque setpoint coupling (from SW 4.1)

Description
A torque setpoint coupling (master/slave operation) between two rigidly connected drives can be established via analog signals or PROFIBUS-DP.

How is this function activated?
- The master drive is changed-over into the closed-loop speed controlled mode.
- The torque setpoint at the speed controller output of the master drive is provided via the process data "Msoll" (number 50114).
- The slave drive must be changed-over into the open-loop torque controlled mode using process data "STW1.14".
- The torque setpoint of the master drive should be read into the slave drive using process data "MsollExt" (number 50113).

Normalization
P0882 determines the normalization of process data "Msoll" and "MsollExt". The percentage value of the rated motor torque, entered into P0882, corresponds to value 16384 in the PROFIBUS interface.

The polarity of the torque setpoint can be inverted by entering negative values.

The torque, corresponding to 16384, is displayed in Nm in P1725 (P0882 \cdot rated motor torque).

Smoothing and clock cycle
The "Msoll" process data is smoothed using the transition frequency set in P1252. The pre-setting P1252 = 100 Hz can result in problems for mechanical couplings. If required, the smoothing (dead time) should be disabled using P1252 = 0.

Note
For torque setpoint couplings via PROFIBUS-DP, when compared to coupling via analog signals (refer to Chapter 6.6), there is a longer dead time (≥ 1 ms instead of the speed controller clock cycle).
The master/slave functionality is realized using analog signals or PROFIBUS-DP.

**Note**
Master/slave operation is only possible for motors with encoders!

- An example of a coupling between two drives with analog input/outputs is described in Chapter 6.6.5.
- The following example shows a coupling with PROFIBUS-DP.

**Application example master/slave**

The master/slave functionality is realized using analog signals or PROFIBUS-DP.

**Note**
Master/slave operation is only possible for motors with encoders!

- An example of a coupling between two drives with analog input/outputs is described in Chapter 6.6.5.
- The following example shows a coupling with PROFIBUS-DP.

---

**Fig. 6-43** Example: Coupling two drives with master/slave to PROFIBUS-DP

---

**Warning**

If, for a master/slave configuration, the rigid mechanical coupling is released (the coupling is opened) then at the same time the slave drive must be changed over to \( n_{\text{set}} \) operation as otherwise the slave drive would accelerate in an uncontrolled fashion to the maximum speed.
Parameterizing DP master

The diagrams 6-45 and 6-44 indicate the steps when configuring S7 for an example with the standard telegram 102 as template.

In the example, it is assumed that the encoder interface is not required. The appropriate process data is therefore canceled.

The following data should be parameterized in the DP master (e.g. SIMATIC S7):

- Configuration, master drive --> Number of process data which must match the selected telegrams
  - 4 words, PKW
  - 6 words, actual values to the DP master
  - 5 words, setpoints from the DP master

![Diagram of DP Slave Eigenschaften](image)

**Fig. 6-44** Example, configuring the master drive for S7

- Configuring the slave drive to match the telegram
  --> define the slave-to-slave communication link
  - 4 words, PKW
  - 5 words, actual values to the DP master
  - 5 words, setpoints from the DP master
  - 1 word, setpoints via slave-to-slave communications
Parameterizing the master drive

The following parameters should be set:

- **P0922 = 0**

  In the example, the standard telegram 102 is extended by Msoll.

  \[ \text{--> the telegram should be configured as follows:} \]

- **P0916:6 = 50114 --> status word Msoll**

- **Check P1252 (smoothing, Msoll)**

- **P0915:6 = 0 and P0916:7... 10 = 0**

  \[ \text{--> disable the encoder interface (optional)} \]
The following parameters should be set:
- **P0922 = 0**

In the example, the standard telegram 102 is extended by MsollExt.

--> the telegram should be configured as follows:

<table>
<thead>
<tr>
<th>PZD1</th>
<th>PZD2</th>
<th>PZD3</th>
<th>PZD4</th>
<th>PZD5</th>
<th>PZD6</th>
</tr>
</thead>
<tbody>
<tr>
<td>STW1</td>
<td>NSOLL_B</td>
<td>STW2</td>
<td>MomRed</td>
<td>MsollExt</td>
<td></td>
</tr>
<tr>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
</tr>
<tr>
<td>:1</td>
<td>:2</td>
<td>:3</td>
<td>:4</td>
<td>:5</td>
<td>:6</td>
</tr>
<tr>
<td>50001</td>
<td>50007</td>
<td>50007</td>
<td>50003</td>
<td>50101</td>
<td>50113</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>PZD1</th>
<th>PZD2</th>
<th>PZD3</th>
<th>PZD4</th>
<th>PZD5</th>
</tr>
</thead>
<tbody>
<tr>
<td>ZSW1</td>
<td>NIST_B</td>
<td>ZSW2</td>
<td>MeldW</td>
<td></td>
</tr>
<tr>
<td>P0916</td>
<td>P0916</td>
<td>P0916</td>
<td>P0916</td>
<td>P0916</td>
</tr>
<tr>
<td>:1</td>
<td>:2</td>
<td>:3</td>
<td>:4</td>
<td>:5</td>
</tr>
<tr>
<td>50002</td>
<td>50008</td>
<td>50008</td>
<td>50004</td>
<td>50102</td>
</tr>
</tbody>
</table>

Fig. 6-47 Configuring a telegram, slave drive

- **P0915:6 = 50113** --> control word MsollExt
- **P0916:6 ... 10 = 0** --> disables the encoder interface (optional)

**Note**

The normalization at the master and slave drive can be influenced using P0882.

**Parameter overview (refer to Chapter A.1)**

The following parameters are available for the "torque setpoint coupling" function:
- **P0607** Analog setpoint, terminal 56.x/14.x
- **P0612** Analog setpoint, terminal 24.x/20.x
- **P0618** Normalization voltage, speed setpoint
- **P0619** Normalization voltage, torque setpoint
- **P0620** Normalization voltage, torque/power reduction
- **P0882** Evaluation, torque setpoint PROFIBUS
- **P0881** Evaluation, torque/power reduction PROFIBUS
- **P0916** PZD actual value assignment, PROFIBUS
- **P0922** Telegram selection PROFIBUS
- **P1240:8** Offset, torque setpoint (closed-loop speed-controlled)
- **P1241:8** Normalization, torque setpoint
- **P1242:8** Offset, torque setpoint (open-loop torque-controlled)
- **P1243:8** Normalization, torque/power reduction
- **P1252** Transition frequency, torque setpoint smoothing
- **P1725** Normalization, torque setpoint
### Input/output signals (refer to Chapter 6.4)

The following signals are used for the function "torque setpoint coupling":

- **Input signals**
  (refer under index entry "Input signal, digital - ...")
  - Input signal "open-loop torque controlled operation"
    --> using an input terminal with function number 4
    --> using the PROFIBUS control signal "STW1.14"
  - Input signal "external torque setpoint"
    --> using the PROFIBUS control signal "MsollExt"
  - Input signal "torque limit reduction"
    --> using the PROFIBUS control signal "MomRed"

- **Output signals**
  (refer under the index entry, "Output signal, digital - ...")
  - Output signal "in synchronism"
    --> using an output terminal with function number 71
    --> using the PROFIBUS status signal "PosZsw.3"
  - Output signal "open-loop torque controlled operation"
    --> using the PROFIBUS status signal "ZSW1.14"
  - Output signal "smoothed torque setpoint"
    --> using the PROFIBUS status signal "Msoll"
  - Output signal "smoothed torque-generating current Iq"
    --> using the PROFIBUS status signal "IqGl"
### 6.3.4 Equalization controller (from SW 7.1)

#### General information

**Description**

For mechanically coupled axes, e.g. a rotating track which is driven through two axes, it is not sufficient to just enter identical speed setpoints at both axes. Due to the drift, which is always present in a real system, different torques occur at the coupling element.

A torque equalization controller is implemented in the "SIMODRIVE 611 universal" software for applications such as these.

**Control structure**

The mechanically coupled axes are in the master/slave mode. The actual equalization controller is computed in the slave axis. The slave and master axes are set using parameters.

If a pre-tensioning torque is required (gearbox, play), a parameterizable supplementary torque is entered at the torque comparison location, which, when the equalization controller is activated, gradually increases along a smoothing characteristic which can be parameterized.

If different motors are used or if these are installed so that they oppose each other, then torque weighting can be parameterized.

**Parameters**

- **P1490 = 1**: Analog terminal 24/20 is the source for the master - slave torque setpoint comparison
- **P1490 = 2**: The adjacent drive (double-axis module, drive A or B) is the source for the comparison, torque setpoint master-slave
- **P1490 = 3**: PROFIBUS-DP (from SW 13.1) is the source for the master-slave torque setpoint comparison

**Diagram**

Fig. 6-48 Closed-loop control structure, equalization controller
How is the torque setpoint transferred?

As can be seen from Fig. 6-48, for the equalization control, \( M_{\text{set}} \) must be transferred from the master axis to the slave axis. This can be done in the following ways:

- **Double-axis module - internal coupling**
  \( M_{\text{set}} \) is coupled between the master drive and slave drive in the software.

- **Single-axis/double-axis modules coupled via I/O terminals**
  For most applications, the torque coupling is limited to higher power ratings. This means that typically single-axis modules are used.

  In this case, the electrical coupling is established using analog I/O terminals.

![Diagram](image)

**Fig. 6-49** Axis coupling with 2 single-axis modules through analog I/O terminals

- **Single-axis/double-axis modules coupled via PROFIBUS-DP (from SW 13.1)**

**Warning**

If the master axis is not in the closed-loop control mode or if the mechanical coupling is released, the slave axis, for a set tensioning torque, can accelerate up to the maximum speed if the torque is sufficient. This also occurs if the equalization controller has, after a longer period of time, a high system deviation due to the integrator. This then enters a high supplementary setpoint.

**Note**

When the equalization controller is activated, induction motors cannot be changed-over!
The following parameters should be set for the "equalization controller" function, if the coupling is realized via analog I/O terminals:

- **P0607** Analog setpoint, terminal 56.x/14.x
  Parameterize the speed setpoint at both axes:
  - Master axis: P0607 = 1
  - Slave axis: P0607 = 1
    P0608 = 1, if the direction of rotation is to be inverted

- **P0626** Signal number, analog output terminals 75.x/15
  (only for an analog setpoint coupling)
  - Master axis: P0626 = 36 (torque setpoint, finely normalized)
  - P0625 = 50
  - P0631 = 1

- **P0612** Signal number, analog setpoint terminals 24.x/20.x
  (only for an analog setpoint coupling)
  - Slave axis: P0612 = 3, is automatically set if, when using the parameterizing and start-up tool "SimoCom U", "slave axis with analog coupling" is selected in the parameterizing screen form "equalization controller" for activate equalization controller.
  - P0619 = 5 (P0619 refers to P1241)
  - P1241 – pre-assigned the rated torque

**Note**

If P1490 = 1 and P0612 ≠ 3, then fault 738 is output.

- **P1490** Activates the equalization controller
  - Master axis: P1490 = 0
  - Slave axis: P1490 = 0
    - → No source or no equalization controller
  - P1490 = 1
    - → Equalization controller is active,
      Source is terminal 24/20
      Parameterization of P0626, P0625, P0612, P0619
  - P1490 = 2
    - → Equalization controller is active
      The source is the adjacent drive (drive A or B)
  - P1490 = 3 (from SW 13.1)
    - → Equalization controller is active
      Source is PROFIBUS-DP (P0922, P0915)
6.3 Axis couplings (from SW 3.3)

Settings for the slave axis:

- **P1491** P gain, equalization controller

  Recommended setting:
  
  \[ V_p \text{ equalization controller (P1491)} = 0.5 / V_p \text{ speed controller (P1407)} \]

  The sign of the torque weighting must be taken into consideration when inverting the speed!

- **P1492** Integral action time, equalization controller

  Recommended setting:
  
  \[ T_N \text{ equalization controller (P1492)} = 10 \times T_N \text{ speed controller (P1409)} \]

- **P1493** Pre-tensioning torque (pre-tensioning force)

  If a pre-tensioning torque is required (e.g. gearbox, play), a supplementary torque can be added at the torque comparison point using P1493. When the equalization controller is activated, this supplementary torque gradually increases. This delay is achieved using a PT1 element which can be set using P1494.

- **P1494** Pre-tensioning torque (pre-tensioning force)

  P1494 is used to enter the time constant for the PT1 element which ensures that the pre-tensioning torque gradually increases (pre-tensioning force) when the equalization controller is activated.

- **P1495** Torque weighting, equalization controller - master

  If different motors are involved in the closed-loop equalization control, then a torque weighting of the torque setpoint (or force weighting of the force setpoint (SLM)) of the master axis can be set using P1495.

- **P1496** Torque weighting, equalization controller - slave

  If various motors are involved in the closed-loop equalization control, then a torque weighting of the torque setpoint or force weighting of the force setpoint (SLM) of the slave axis can be set.

The equalization controller is computed in the 1 ms clock cycle time and the speed controller is computed in the speed controller clock cycle. In order to achieve a softer transition between these times slices, the setpoint steps (jumps) can be smoothed using a speed setpoint filter as PT1 system (1 ms time constant).
How is the equalization controller commissioned?

The equalization controller is set as follows using SimoCom U:

Example:

- **Setting for the master axis for an analog coupling**

  The settings in the menu view "equalization controller" result in the analog output being set.

![Fig. 6-50 Setting the master axis](image)

The output normalization of the master axis is displayed as follows in the menu view "equalization controller":

![Fig. 6-51 Display, output normalization, master axis](image)

- **Setting for the slave axis for an analog coupling**

  The settings in the menu view "equalization controller" cause the equalization controller to be activated and the input of the slave axis to be set. As the motors move in opposite directions, the direction of rotation is inverted.

![Fig. 6-52 Setting for the slave axis](image)
The torque setpoint of the master axis is transferred via the analog inputs. The output normalization and the input normalization must match.

**Fig. 6-53** Display, input normalization, slave axis

**Recommended setting, equalization controller:**

\[ V_p^{\text{equalization controller}} = 0.5/V_p^{\text{speed controller}} \]

\[ T_N^{\text{equalization controller}} = 10 \cdot T_N^{\text{speed controller}} \]

When inverting the speed, the sign of the torque weighting should be carefully observed.

**Fig. 6-54** Inverting the direction of rotation, slave axis
Equalization controller via PROFIBUS-DP (from SW 13.1)

How is the equalization controller commissioned?

Using SimoCom U the equalization controller is set as follows:

Example:

- **Setting for the master axis for a coupling via PROFIBUS-DP**

  The "Master axis with coupling via PROFIBUS" setting is realized in the menu view "Activate equalization controller".

  ![Fig. 6-55 Setting for the master axis](image)

- **Setting for the slave axis for a coupling via PROFIBUS-DP**

  The settings in the menu view “Activate equalization controller“ activate the equalization controller and the input of the slave axis is set (P1490 = 3, from SW 13.1.). If the motors should operate in the opposite directions, then for “Torque weighting master” a negative value should be entered.

  ![Fig. 6-56 Setting for the slave axis](image)

The torque setpoint of the master axis is transferred via PROFIBUS-DP.

Recommended settings for the equalization controller:

\[
\begin{align*}
V_P \text{ equalization controller} &= 0.5 / V_P \text{ speed controller} \\
T_N \text{ equalization controller} &= 10 \times T_N \text{ speed controller}
\end{align*}
\]
The torque setpoint at the speed controller output of the master drive is available via the process data “Mset” (number 50114).

In the slave drive, the torque setpoint of the master drive is read-in with the new process data “Msetequal” (number 50123) that will be newly introduced.

To achieve this, for both the master as well as the slave drive, a suitable standard telegram should first be selected (e.g. standard telegram 3 or 102) and then the telegram for the master drive should be extended by the process data “Mset” (number 50114) and for the slave drive extended by the process data “Msetequal” (number 50123).

P0882 defines the scaling of the process data “Mset” and “Msetequal”. The percentage value of the rated motor torque entered in P0882 corresponds to the value 16384 in the PROFIBUS interface.

The torque corresponding to 16384 is displayed in P1725 in Nm (P0882 rated motor torque).

The process data “Mset” is smoothed via the corner frequency set in P1252. The default setting P1252 = 100 Hz can cause problems for a mechanical coupling. If required, the smoothing (dead time) should be disabled using P1252 = 0.

The following diagrams show the steps of the S7 configuring for an example with standard telegram 102 as template.

In the example, it is assumed that the encoder interface is not required. The corresponding process data have therefore been deselected.
The following data should be parameterized in the DP master (e.g. SIMATIC S7):

- Configuration of the master drive → number of process data, which must match the selected telegram:
  - 10 words actual values to the DP master
  - 6 words setpoints from the DP master

Fig. 6-58 Configuration example of a master drive for S7 configuration

- Configuration of the slave drive matching the telegram → definition of the cross-transfer connection.
  - 10 words actual values to the DP master
  - 6 words setpoints from the DP master
  - 1 word setpoints via cross-transfer
### 6.3 Axis couplings (from SW 3.3)

**Fig. 6-59** Configuration example of a slave drive for S7 configuration

<table>
<thead>
<tr>
<th>Slot</th>
<th>Antrieb</th>
<th>PROFIBUS Partner</th>
</tr>
</thead>
<tbody>
<tr>
<td>4</td>
<td>Kein PKW</td>
<td></td>
</tr>
<tr>
<td>5</td>
<td>Istwert</td>
<td>PZD 1 Eingang</td>
</tr>
<tr>
<td>6</td>
<td>Sollwert</td>
<td>PZD 1 Ausgang</td>
</tr>
<tr>
<td>7</td>
<td>Sollwert</td>
<td>PZD 7 Querverkehr</td>
</tr>
</tbody>
</table>

Sender: (5) 611U DP2, DP3  
Zugeordnete Station: (2) SIMATIC 300(1)  
Kommentar: 

---

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Parameterization, master drive

The following parameters should be set:

- $P092 = 0 $ In the example, standard telegram 102 is extended by $Mset$.  
  → The telegram should be configured as follows: 
  $P0916:6 = 50114 \rightarrow \text{status word } Mset \ (50114)$ 
  $P1252 \ check \ (\text{smoothing } Mset)$ 
  $P0915:6 = 0$ and 
  $P0916:7 \ ... \ 10 = 0 \rightarrow \text{deselect encoder interface (optional)}$

<table>
<thead>
<tr>
<th>PZD1</th>
<th>PZD2</th>
<th>PZD3</th>
<th>PZD4</th>
<th>PZD5</th>
<th>Setpoint</th>
</tr>
</thead>
<tbody>
<tr>
<td>STW1</td>
<td>NSOLL_B</td>
<td>STW2</td>
<td>MomRed</td>
<td></td>
<td></td>
</tr>
<tr>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td></td>
</tr>
<tr>
<td>.1</td>
<td>.2</td>
<td>.3</td>
<td>.4</td>
<td>.5</td>
<td>.6</td>
</tr>
<tr>
<td>50001</td>
<td>50007</td>
<td>50007</td>
<td>50003</td>
<td>50101</td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>ZSW1</th>
<th>NIST_B</th>
<th>ZSW2</th>
<th>MeldW</th>
<th>Mset</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
</tr>
<tr>
<td>.1</td>
<td>.2</td>
<td>.3</td>
<td>.4</td>
<td>.5</td>
</tr>
<tr>
<td>50002</td>
<td>50008</td>
<td>50008</td>
<td>50004</td>
<td>50102</td>
</tr>
</tbody>
</table>

Fig. 6-60 Telegram configuration, master drive

Parameterization, slave drive

The following parameters should be set:

- $P092 = 0 $ In the example standard telegram 102 is extended by $Msetequal \ (50123)$.
  → The telegram should be configured as follows: 
  $P0915:6 = 50123 \rightarrow \text{control word } Msetequal$
  $P0916:6 \ ... \ 10 = 0 \rightarrow \text{deselect encoder interface (optional)}$

<table>
<thead>
<tr>
<th>PZD1</th>
<th>PZD2</th>
<th>PZD3</th>
<th>PZD4</th>
<th>PZD5</th>
<th>Setpoint</th>
</tr>
</thead>
<tbody>
<tr>
<td>STW1</td>
<td>NSOLL_B</td>
<td>STW2</td>
<td>MomRed</td>
<td>Msetequal</td>
<td></td>
</tr>
<tr>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td></td>
</tr>
<tr>
<td>.1</td>
<td>.2</td>
<td>.3</td>
<td>.4</td>
<td>.5</td>
<td>.6</td>
</tr>
<tr>
<td>50001</td>
<td>50007</td>
<td>50007</td>
<td>50003</td>
<td>50101</td>
<td>50123</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>ZSW1</th>
<th>NIST_B</th>
<th>ZSW2</th>
<th>MeldW</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
<td>P0915</td>
</tr>
<tr>
<td>.1</td>
<td>.2</td>
<td>.3</td>
<td>.4</td>
</tr>
<tr>
<td>50002</td>
<td>50008</td>
<td>50008</td>
<td>50004</td>
</tr>
</tbody>
</table>

Fig. 6-61 Telegram configuration, slave drive

Note

The scaling at the master and slave drives can be influenced using $P0882$.  

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6.4 Input/output terminals of the control board

6.4.1 Permanently-connected input terminals

Table 6-43  Permanently-connected input terminals

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Drive A</th>
<th>Drive B</th>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
</table>
| 663      | X431.4  |         | Pulse enable, module-specific | The inverter is enabled (motor control), if the enable voltage is available at the following terminals:  
1. Terminal 63 (pulse enable, group-specific, at the NE and monitoring module)  
2. Terminal 64 (controller enable, group-specific, at the NE or monitoring module)  
3. Terminal 48 (contactor control, at the NE module)  
4. Terminal 663 (pulse enable, board-specific)  
5. Terminal 65.x (controller enable, axis-specific)  
If terminal 663 is opened while the motor is rotating, the inverter is immediately (< 1 ms) inhibited, and the motors connected to this module coast down in a no-current condition.  
If the module is enabled using terminal 663, then the enable operation takes approx. 20 ms. |
| 65.A     | X451.5  | X452.5  | Axis-specific controller enable | The controller enable is dependent on the following enable signals:  
1. Terminal 63 (pulse enable, group-specific, at the NE and monitoring module)  
2. Terminal 64 (controller enable, group-specific, at the NE or monitoring module)  
3. Terminal 663 (pulse enable, board-specific)  
4. Terminal 65.x (controller enable, axis-specific)  
5. RFG, fault drive x (internal enable signal)  
6. PROFIBUS enable signals  
If the associated terminal 65.x is opened while the motor is rotating, then the drive brakes along the ramp–function generator ramp.  
If the \( n_{min} \) threshold (P1403) is exceeded (as absolute value), or after the pulse cancellation timer has expired (P1404), the inverter is inhibited (pulses canceled), and the motor is shutdown without any overshoot. |

Note:  
• x: Space retainer for drive A or B  
• If the enable signals are missing, which are required to operate the drive, these can be determined using P0600 (operating display) (refer to Chapter 4.5).
6.4.2 Freely-parameterizable digital input terminals

Description
There are 4 freely parameterizable input terminals for every axis.
A terminal is parameterized by entering the appropriate required function number into the assigned parameter.
Which function numbers are available? --> Refer to Chapter 6.4.3

Note
- Rules when assigning input terminals a multiple number of times
  The terminals are evaluated in the following sequence:
  I0.x - I1.x - I2.x - I3.x - I4 - I5 - ... - I11
  If a function is assigned a multiple number of times to an input terminal, influence is only possible using the "last" terminal assigned this particular function.
- Rule regarding hardware terminal and PROFIBUS signal
  The hardware terminal has priority over the PROFIBUS signal, this means that a signal via a terminal always has priority over the "same" PROFIBUS signal.

Notice
The terminals may only be parameterized when the drive pulses are canceled.
If terminal functions are activated, however, are not connected-up, then the "0" signal is effective.

Overview of the terminals and parameters
There is the following assignment between terminals, drives and parameters:

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Drive A</th>
<th>Drive B</th>
<th>No.</th>
<th>Name</th>
<th>Parameter</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>I0.A</td>
<td>X451.7</td>
<td>I0.B</td>
<td>X452.7</td>
<td>0660</td>
<td>Function, input terminal I0.x</td>
<td>0</td>
<td>0 (SRM, SLM) 35 (ARM)</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>I1.A</td>
<td>X451.8</td>
<td>I1.B</td>
<td>X452.8</td>
<td>0661</td>
<td>Function, input terminal I1.x</td>
<td>0</td>
<td>0 (SRM, SLM) 7 (ARM)</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>
### Table 6-44  Overview of the freely-parameterizable input terminals, continued

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Parameter</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Drive A</td>
<td>Drive B</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>I2.A</td>
<td>I2.B</td>
<td>0662</td>
<td>Function, input terminal I2.x</td>
<td>0</td>
<td>3</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>I3.A</td>
<td>I3.B</td>
<td>0663</td>
<td>Function, input terminal I3.x</td>
<td>0</td>
<td>4</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

Each input terminal can be assigned a function using these parameters. The function number from the list of input signals is entered (refer to Chapter 6.4.3).

**Note:**
The status of the input terminals is displayed in P0678 for diagnostic purposes (refer to Chapter 4.5).

### 6.4.3  List of input signals

**Reader's note**
The drive receives the input signals, listed in the Tables 6-45 and 6-46 either from an input terminal or as control bit from PROFIBUS-DP. All of the input signals can be found under the index entry "Input signal...".

The following must be specified for each signal:

- **Fct. No.**:
  The function number is required to parameterize the input terminal via the display and operator control unit.

- **Operating mode (P0700)**:
  This specifies in which operating mode the signal is available (x: Available, -: Not available).
  - n-set: "Speed/torque setpoint" mode
  - pos: "Positioning" mode

- **PROFIBUS bit**:
  The bit name is required to control the signal via PROFIBUS-DP (refer to Chapter 5.6.1).
  Example: STW1.4  --> that means control word 1, bit 4
Table 6-45  Overview of the input signals

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td>n-set</td>
<td>pos</td>
</tr>
<tr>
<td>Inactive</td>
<td>0</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Activate function generator immediately (from SW 11.1)</td>
<td>2</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Reset the fault memory</td>
<td>3</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Open-loop torque controlled mode</td>
<td>4</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Motor data set changeover (from SW 2.4)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1st input/2⁰</td>
<td>5</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>2nd input/2¹</td>
<td>6</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Ramp–up time zero</td>
<td>7</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Integrator inhibit, speed controller</td>
<td>8</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Parameter set changeover</td>
<td>9</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>1st input/2⁰</td>
<td>10</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>2nd input/2¹</td>
<td>11</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Fixed speed setpoint (from SW 3.1)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1st input/2⁰</td>
<td>15</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>2nd input/2¹</td>
<td>16</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>3rd input/2²</td>
<td>17</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>4th input/2³</td>
<td>18</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>First speed setpoint filter off</td>
<td>25</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Suppress fault 608 (from SW 3.1)</td>
<td>26</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Spindle positioning on (from SW 5.1)</td>
<td>28</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>ON/OFF 1 (from SW 8.3)</td>
<td>31 (from SW 8.3)</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Operating condition/OFF 2</td>
<td>32 (from SW 4.1)</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Operating condition/OFF 3</td>
<td>33 (from SW 5.1)</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Enable inverter/pulse inhibit</td>
<td>34 (from SW 4.1)</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Ramp–up generator enabled</td>
<td>35</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Selection, parking axis</td>
<td>40</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Activate function generator (edge) (from SW 8.1)</td>
<td>41 (from SW 9.1)</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Activate function generator (edge) (from SW 9.1)</td>
<td>41</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Opening the holding brake for test purposes (from SW 4.1)</td>
<td>42</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>
### Table 6-45  Overview of the input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Block selection</td>
<td></td>
<td>n-set</td>
<td>pos</td>
</tr>
<tr>
<td>1st input/2⁰</td>
<td>50</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>2nd input/2¹</td>
<td>51</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>3rd input/2²</td>
<td>52</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>4th input/2³</td>
<td>53</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>5th input/2⁴</td>
<td>54</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>6th input/2⁵</td>
<td>55</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>56</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>(being prep., from SW 10.1)</td>
<td>57</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Operating condition/reject traversing task</td>
<td>58</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Oper. condition/intermediate stop</td>
<td>59</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Activate traversing task (edge)</td>
<td>60</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Incremental jogging (from SW 4.1)</td>
<td>61</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Jogging 1 ON/jogging 1 OFF</td>
<td>62</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Jogging 2 ON/jogging 2 OFF</td>
<td>63</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Activate teach-in (edge) (from SW 4.1)</td>
<td>64</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Control requested/no control requested</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Start referencing/cancel referencing</td>
<td>65</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>External block change (from SW 3.1)</td>
<td>67</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Fixed stop, sensor (from SW 3.3)</td>
<td>68</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Request passive referencing (from SW 5.1)</td>
<td>69</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Follow-up mode</td>
<td>70</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Setting the home position</td>
<td>71</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Activate coupling (from SW 3.3)</td>
<td>72</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Activate coupling via I0.x (from SW 3.3)</td>
<td>73</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Set setpoint, master drive (from SW 4.1)</td>
<td>74</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Invert the angular incremental encoder input (from SW 3.5)</td>
<td>75</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Reference cams</td>
<td>78</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Equivalent zero mark</td>
<td>79</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Flying measurement/length measurement (from SW 3.1)</td>
<td>80</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Plus hardware limit switch (NC contact) (n-set from SW 8.1)</td>
<td>81</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Minus hardware limit switch (NC contact) (n-set from SW 8.1)</td>
<td>82</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Activate MDI (from SW 7.1)</td>
<td>83</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Activate angular incremental encoder, handwheel (from SW 8.1)</td>
<td>84</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 0 (from SW 8.1)</td>
<td>85</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1)</td>
<td>86</td>
<td>-</td>
<td>x</td>
</tr>
</tbody>
</table>
### Table 6-45  Overview of the input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ramp-function generator start/ramp-function generator stop</td>
<td>-</td>
<td>x</td>
<td>STW1.5</td>
</tr>
<tr>
<td>Enable setpoint/inhibit setpoint</td>
<td>-</td>
<td>x</td>
<td>STW1.6</td>
</tr>
<tr>
<td>Accelerating time zero for controller enable (from SW 3.1)</td>
<td>-</td>
<td>x</td>
<td>STW1.13</td>
</tr>
<tr>
<td>Motor changed over (from SW 2.4)</td>
<td>-</td>
<td>x</td>
<td>STW2.11</td>
</tr>
<tr>
<td>Master sign-of-life (from SW 3.1)</td>
<td>-</td>
<td>x</td>
<td>STW2.12</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>STW2.13</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>STW2.14</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>STW2.15</td>
</tr>
</tbody>
</table>

### Table 6-46  List of input signals

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inactive</td>
<td>0</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

The input with this function is switched "inactive". The input terminal can still be connected-up, but is not evaluated.

**Application:**
During commissioning (start-up), "disturbing" inputs are first disabled, and are then activated later and commissioned.

**Activate function generator immediately (from SW 11.1)**

Through this input signal the function generator can be activated immediately in the "Speed/Torque set-point" operating mode and thus the "Oscillate" function be implemented analog, as at the SIMODRIVE 611 drive.

- 1 signal  Function generator is activated immediately
- 0 signal  Function generator is deactivated

**Note:**
- Activating the function generator immediately is described in Chapter 6.19.
Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Reset the fault memory</td>
<td>3</td>
<td>x, x</td>
<td>STW1.7</td>
</tr>
</tbody>
</table>

Faults that are present that are acknowledged with RESET FAULT MEMORY, are reset via this input signal.
Before acknowledging faults/ errors, their cause must first be removed.

**Requirements:** The controller enable signal at terminal 65.x has been withdrawn.
1 signal No effect
0/1 signal The fault memory is reset and the fault(s) acknowledged using a 0/1 edge.
0 signal No effect

**Note:**
- Faults, which can be acknowledged with POWER ON, cannot be reset in this fashion.
- The drive remains in the fault condition until all of the faults/errors have been removed.
- In the PROFIBUS mode the system then goes into the “power--on inhibit” status.
- From SW 6.1 and for P1012.12 = 1, the fault can also be acknowledged without the prerequisite that the control signal STW1.0 = 0. The drive however, remains in the “power--on inhibit” condition.

**Open-loop torque controlled mode**

<table>
<thead>
<tr>
<th>4</th>
<th>x</th>
<th>-</th>
<th>STW1.14</th>
</tr>
</thead>
</table>

It is possible to toggle between closed-loop speed controlled and open-loop torque controlled operation via this input signal.
1 signal Open-loop torque controlled operation (M_set mode)
0 signal Closed-loop speed controlled operation (n_set mode)

**Application:** Master/slave, refer to Chapter 6.6.5.

**Motor data set changeover (from SW 2.4)**

<table>
<thead>
<tr>
<th>5</th>
<th>x</th>
<th>-</th>
<th>STW2.9</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td>x</td>
<td>-</td>
<td>STW2.10</td>
</tr>
</tbody>
</table>

It is possible to toggle between a total of 4 motors/motor data sets using these 2 input signals.

<table>
<thead>
<tr>
<th>Motor data set</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st input/weighting 2⁰</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>2nd input/weighting 2¹</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

**Note:**
- The motor changeover version and therefore the behavior of the terminal, is selected using P1013 (motor changeover).
- Output terminal signals with function numbers 11, 12, 13 and 14 (motors 1, 2, 3 or 4 selected) are used to control the contactors to change over the motor.
- In order to ensure that the function changes over in a controlled fashion (identified as being simultaneous) the switching operation of the inputs must be completed with one interpolation clock cycle (P1010).
- Motor changeover is described in Chapter 6.11.

**Ramp-up time zero**

| 7 | x | x | STW2.4 |

The ramp-function generator (RFG) can be switched-in and out via this input signal.
1 signal Ramp-function generator off
This acts just like a ramp-up and ramp-down of the ramp-function generator of 0 ms.
0 signal Ramp-function generator on
5 4

6.4  Input/output terminals of the control board

Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Integrator inhibit, speed controller</td>
<td>8</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

The integral component of the speed controller can be inhibited or enabled using this input signal.

1 signal  Integrator inhibit, speed controller
0 signal  The speed controller integrator is not inhibited

Note:
For a 1 signal, the integral component of the speed controller is deleted (cleared) and the integrator is inhibited.

Parameter set changeover

<table>
<thead>
<tr>
<th>Parameter set</th>
<th>0</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>6</th>
<th>7</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st input/weighting 2(^0)</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>2nd input/weighting 2(^1)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>3rd input/weighting 2(^2)</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

Note:
- The bits, which are not assigned to an input terminal, are treated just like a 0 signal.
- To change over, e.g. from parameter set 0 to 1, only the signal of the 1st input is necessary.
- In order to ensure that the function changes over in a controlled fashion (identified as being simultaneous) the switching operation of the inputs must be completed with one interpolation clock cycle (P1010).
- The “parameter set changeover” function is described in Chapter 6.10.
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fixed speed setpoint (from SW 3.1)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1st input/2⁰</td>
<td>15</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>2nd input/2¹</td>
<td>16</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>3rd input/2²</td>
<td>17</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>4th input/2³</td>
<td>18</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

Using these input signals, the "fixed speed setpoint" function can be selected with the required fixed setpoints 1 to 15, or the function can be canceled.

<table>
<thead>
<tr>
<th>Fixed speed setpoint</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>...</th>
<th>15</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st input/weighting 2⁰</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>...</td>
<td>1</td>
</tr>
<tr>
<td>2nd input/weighting 2¹</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>...</td>
<td>1</td>
</tr>
<tr>
<td>3rd input/weighting 2²</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>...</td>
<td>1</td>
</tr>
<tr>
<td>4th input/weighting 2³</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
</tr>
</tbody>
</table>

Active fixed speed setpoint

- **P0641:1**
- **P0641:2**
- **P0641:3**
- **P0641:15**

**Note:**
- The "fixed speed setpoint" function is described in Chapter 6.1.6.
- If the function is canceled, an analog setpoint can be entered via terminals 56.x/14 and/or terminals 24.x/20.
- In order to ensure that the function changes over in a controlled fashion (identified as being simultaneous) the switching operation of the inputs must be completed with one interpolation clock cycle (P1010).
- Refer to the "status, fixed speed setpoint 1st to 4th input" output signal in Chapter 6.4.6.

<table>
<thead>
<tr>
<th>First speed setpoint filter off</th>
<th>25</th>
<th>x</th>
<th>x</th>
</tr>
</thead>
</table>

The first speed setpoint filter is switched-in/switched-out using this input signal.

**Important:**
This function is only effective if the filter was parameterized using P1501:8 as lowpass filter (e.g. PT1). Thus, the low-pass filter of the 1st speed setpoint filter can be disabled/enabled using this input signal, which allows the speed setpoint to be smoothed.

- 1 signal  First speed setpoint filter is disabled  - - >  Low-pass filter is disabled
- 0 signal  First speed setpoint filter is enabled  - - >  Low-pass filter is enabled

**Note:**
The status of the 1st speed setpoint filter is displayed using the "first speed setpoint filter inactive" output signal.
Table 6-46 List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Suppress fault 608 (from SW 3.1)</td>
<td>26</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

Fault 608 (speed controller output limited) can be suppressed/displayed using this input signal.

1 signal Fault 608 (speed controller output limited) is suppressed
0 signal Fault 608 is not suppressed

Note:
- The status of the suppressed function is signaled via the PROFIBUS status signal ZSW2.8 "Suppressing fault 608 active (from SW 3.1)".
- Refer under the index entry "Output signal - suppress fault 608 active (from SW 3.1)"
- It is also possible to suppress the fault using P1601.8 (faults which can be suppressed 2, Fault 608).

Spindle positioning on (from SW 5.1) 28 x - STW1.15

The function is activated using this input signal.

1 signal Activates the "spindle positioning" function
0 signal De-activates the function

Note:
- Prerequisites to activate the "spindle positioning" function
  - "n-set" mode --> P0700 = 1
- The "spindle positioning" function is described in Chapter 6.15 (from SW 5.1).

ON/OFF 1 31 (from SW 8.3) x x STW1.0

0/1 signal ON state "drive ready"
The prerequisite is that STW1.1 and STW1.2 of the input signals "operating condition/OFF2" (Fct. No. 32) and the "operating condition/OFF3" (Fct. No. 33) are also set.
The pulses remain canceled until the prerequisites for pulse enable have been fulfilled.

0 signal OFF 1 Stop
The drive brakes along the ramp-function generator ramp.
The gating pulses of the power transistors are cancelled (pulse inhibit) if one of the following conditions is fulfilled:
- |I_{accl}| < n (P1403)
or
- the pulse cancellation timer stage (P1404) has expired

Operating condition/OFF 2 32 (from SW 4.1) x x STW1.1

1 signal Operating condition
Prerequisite for the "drive ready" status.

0 signal OFF 2
The motor is switched into a no-current condition and "coasts down".

Note:
The characteristics at power-on again can be defined via P1012.12.
P1012.12 = 1 Power-on inhibit for alarm and OFF 2/OFF 3
= 0 No power-on inhibit
### Table 6.46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode n-set</th>
<th>pos</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Operating condition/OFF 3</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Operating condition</td>
<td>33 (from SW 5.1)</td>
<td>x</td>
<td>x</td>
<td>STW1.2</td>
</tr>
<tr>
<td>1 signal Operating condition</td>
<td>Prerequisite for the &quot;drive ready&quot; status and &quot;ready to power-up&quot;.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal OFF 3 Fast stop</td>
<td>The drive brakes along the torque limit/current limit without ramp-function generator. In the open-loop torque controlled mode, this limit only corresponds to the specified torque setpoint and not the maximum possible torque. The gating pulses of the power transistors are cancelled (pulse inhibit) if one of the following conditions is fulfilled:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>[nact] &lt; n (P1403)</td>
<td>or</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>- the pulse cancellation timer stage (P1404) has expired</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
The characteristics at power-on again can be defined via P1012.12.
P1012.12 = 1 Power-on inhibit for alarm and OFF2/OFF3
P1012.12 = 0 No power-on inhibit

<table>
<thead>
<tr>
<th>Enable inverter/pulse inhibit</th>
<th>34 (from SW 4.1)</th>
<th>x</th>
<th>x</th>
<th>STW1.3</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal Enable inverter</td>
<td>Pulse enable, ramp-up with the setpoint entered</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal Pulse inhibit</td>
<td>The motor coasts down. In closed-loop speed controlled operation, the &quot;drive ready&quot; state remains set.</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Ramp-function generator enable</th>
<th>35</th>
<th>x</th>
<th>-</th>
<th>STW1.4</th>
</tr>
</thead>
<tbody>
<tr>
<td>This input signal has the following characteristics, dependent on the signal level:</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal Ramp-function generator is enabled</td>
<td>Any speed setpoint can be entered.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1/0 signal Ramp-function generator is not longer enabled</td>
<td>The drive brakes at the torque/current limit without ramp-function generator.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The ramp-function generator output (speed setpoint) is set to 0.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Application:**
The drive can be braked as quickly as possible using this signal, i.e. not along the ramp-function generator ramp, but at the torque limit.
### Table 6-46 List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Selection, parking axis</td>
<td>40</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

The drive can be declared a "parking axis", using this input signal.

1 signal "Parking axis" selected
- The parking axis selection is only activated when the pulses are canceled or the controller is inhibited with subsequent pulse cancellation (e.g. using terminal 663, 63, 65.x, control signal ON/OFF 1) (refer to the output signal "parking axis selected").
- The encoder-specific monitoring functions are suppressed for a parking axis.
- The output signal "reference point set" is withdrawn.

0 signal "Parking axis" canceled
- The monitoring functions are active corresponding to the setting in P1600.

**Application:**
It is possible to change over from one motor encoder unit to another unit using the "parking axis" function, without having to power down the drive.

**Note:**
After the "parking axis" function has been canceled, the following is valid:
- Incremental measuring system: The axis must be re-referenced (refer to Chapter 6.2.5).
- Absolute measuring system (EnDat): The axis must be re-adjusted (refer to Chapter 6.2.7).

The adjustment status cannot be withdrawn by just selecting or canceling the "parking axis" function. This status is only permanently withdrawn when another absolute value encoder has also been automatically detected.

<table>
<thead>
<tr>
<th>Activate function generator (edge) (from SW 8.1)</th>
<th>41 (from SW 9.1)</th>
<th>x</th>
<th>-</th>
<th>STW1.8 (from SW 8.1)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Activate function generator (edge) (from SW 9.1)</td>
<td>41</td>
<td>-</td>
<td>x</td>
<td>PosStw.15</td>
</tr>
</tbody>
</table>

When the function generator or the measuring function is appropriately parameterized, a synchronous start of the function generator or the measuring function is activated - e.g. for mechanically coupled axes (gantry axis group).

0/1 signal Function generator or measuring function is activated
1/0 signal Function generator or measuring function is de-activated

**Note:**
The function generator is described in Chapter 7.4.1.

<table>
<thead>
<tr>
<th>Opening the holding brake for test purposes (from SW 4.1)</th>
<th>42</th>
<th>x</th>
<th>x</th>
<th>STW1.12</th>
</tr>
</thead>
</table>

A holding brake can be opened for test purposes during the commissioning phase using this input signal.

1 signal The function is activated
0 signal De-activates the function

**Note:**
This input signal is only evaluated if the brake control is activated using P0850 = 1. In the operating mode, the brake is controlled using P0850 (operating sequence control) and not via this input signal.
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode n-set</th>
<th>pos</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Block selection</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1st input/2³</td>
<td>50</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.0</td>
</tr>
<tr>
<td>2nd input/2²</td>
<td>51</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.1</td>
</tr>
<tr>
<td>3rd input/2²</td>
<td>52</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.2</td>
</tr>
<tr>
<td>4th input/2³</td>
<td>53</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.3</td>
</tr>
<tr>
<td>5th input/2⁴</td>
<td>54</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.4</td>
</tr>
<tr>
<td>6th input/2⁵</td>
<td>55</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.5</td>
</tr>
<tr>
<td>7th input/2⁶ (from SW 10.1)</td>
<td>56</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.6</td>
</tr>
<tr>
<td>8th input/2⁷ (from SW 10.1)</td>
<td>57</td>
<td>x</td>
<td>x</td>
<td>SatzAnw.7</td>
</tr>
</tbody>
</table>

Traversing blocks 0 to 63/255 can be selected using these 6 (8 from SW 10.1) input signals.

<table>
<thead>
<tr>
<th>Block number</th>
<th>0</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>...</th>
<th>31</th>
<th>...</th>
<th>63</th>
<th>255</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st input/weighting 2³</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>2nd input/weighting 2²</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>3rd input/weighting 2¹</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>4th input/weighting 2²</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>5th input/weighting 2⁴</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>6th input/weighting 2⁵</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>7th input/weighting 2⁶</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>8th input/weighting 2⁷</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>1</td>
</tr>
</tbody>
</table>

**Note:**
- The bits, which are not assigned to an input terminal, are treated just like a 0 signal.
- When a block is selecting using PROFIBUS-DP (control word SatzAnw), the sign is not evaluated. The PROFIBUS bits SatzAnw.8...15 are ignored, e.g. an input of 257 is interpreted as 1.
- Also refer to the input signal "activate traversing task (edge)"

<table>
<thead>
<tr>
<th>Operating condition/reject traversing task</th>
<th>58</th>
<th>-</th>
<th>x</th>
<th>STW1.4</th>
</tr>
</thead>
</table>

This input signal is used as traversing enable to process traversing blocks.

1 signal Operating condition for positioning
The 1 signal is a prerequisite so that a traversing task can be activated.

0 signal The traversing task is rejected
When the block is being actively processed, the drive brakes with the specified deceleration (P0104) taking into account the deceleration override (P0084) to n = 0 with the following effects:
- The drive remains in closed-loop position control and the standstill monitoring function is activated.
- The actual traversing task is rejected and delete residual distance is carried-out.

**Note:**
- If the axis was stopped with an "intermediate stop", and "reject traversing task" was requested, then a delete distance to go is also executed.
- As long as "reject traversing task" is present, a traversing block cannot be started, i.e. the "activate traversing task (edge)" signal is ignored.

**Execute traversing blocks:**
- Before SW 3.3 the following applies:
  This signal must be supplied to execute traversing blocks.
- From SW 3.3, the following applies:
  In order to execute traversing blocks, it is no longer necessary to supply this signal.
  However, only if the signals are not connected to an input.
- Also refer to the input signal "activate traversing task (edge)"
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Operating condition/intermediate stop</td>
<td>59</td>
<td>-</td>
<td>x</td>
</tr>
</tbody>
</table>

Using this input signal, traversing block processing can be interrupted and then continued.

1 signal  Operating condition for positioning
The 1 signal must be continuously present in order to process a traversing block.

0/1 signal  A traversing block, interrupted by "intermediate stop", is continued.

0 signal  Intermediate stop
When the block is being actively processed, the drive brakes with the specified deceleration (P0104) taking into account the deceleration override (P0084:256) to n = 0 with the following effects:
- The drive remains in closed-loop position control and the standstill monitoring function is activated.
- The actual traversing task is not rejected and is continued for a 0/1 edge.

#### Notes:
- An axis in "intermediate stop" can be traversed in the jog mode or referencing can be started.
- The interrupted traversing block is exited.
- Execute traversing blocks:
  - Before SW 3.3 the following applies:
    - This signal must be supplied to execute traversing blocks.
  - From SW 3.3, the following applies:
    - In order to execute traversing blocks, it is no longer necessary to supply this signal.
    - However, only if the signals are not connected to an input.
Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode n-set</th>
<th>pos</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Activate traversing task (edge)</td>
<td>60</td>
<td>-</td>
<td>x</td>
<td>STW1.6</td>
</tr>
</tbody>
</table>

A 0/1 edge of this input signal starts the traversing block selected using "block selection". An edge change is only permissible, if

- The drive has confirmed the previous traversing block via the "acknowledge setpoint" output signal
- The axis is referenced (reference point set/no reference point set” output signal = "1")
- The input signals "operating condition/intermediate stop" and "operating condition/reject traversing task" must be set to 1 in order to be able to start a block.

If a traversing task is activated and the secondary conditions are not fulfilled, then an appropriate warning is signaled. The "setpoint acknowledgment" output signal is only set if the block was started so that a traversing task can be activated with the next signal edge.

![Diagram of signal transitions](image)

1. Select and start a traversing block
2. End of the positioning operation and automatic block change
3. End of the positioning operation and end of program
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Incremental jogging (from SW 4.1)</td>
<td>61</td>
<td>-</td>
<td>PosStw.5</td>
</tr>
</tbody>
</table>

This input signal is used to define whether jogging is executed via velocity or via velocity and increments.

1 signal Jogging via velocity and increments is effective
0 signal Jogging via velocity is effective

**Note:**
This input signal is effective for jogging 1 and jogging 2.
The "jogging mode" function is described in Chapter 6.2.9.

<table>
<thead>
<tr>
<th>Jogging 1 ON/jogging 1 OFF</th>
<th>62</th>
<th>-</th>
<th>STW1.8</th>
</tr>
</thead>
<tbody>
<tr>
<td>Jogging 2 ON/jogging 2 OFF</td>
<td>63</td>
<td>-</td>
<td>STW1.9</td>
</tr>
</tbody>
</table>

Using these input signals closed-loop speed controlled traversing is possible in the "positioning" mode, without changing the mode.

- For jogging 1, the drive traverses with the speed/velocity in P0108.
- For jogging 2, the drive traverses with the speed/velocity P0109.

1 signal The drive traverses with the parameterized speed/velocity

1/0 signal The drive brakes down to standstill with the deceleration set in P0104 (maximum deceleration). The closed-loop position control is re-activated after the braking operation has been completed.

0 signal Output status for jogging

0/1 signal The drive accelerates to the speed/velocity, parameterized in P0108/P0109 with the acceleration set in P0103 (maximum acceleration)

**Note:**
For jogging, the software limit switch and the override are effective.
**6.4 Input/output terminals of the control board**

Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Activate teach-in (edge) (from SW 4.1)</td>
<td>64</td>
<td>n-set</td>
<td>x</td>
</tr>
</tbody>
</table>

The "teach-in" function is activated using this input signal.
When activated, the actual position reference value is entered as position reference value for the selected traversing block.

1 signal  No effect
1/0 signal  Resets the "teach-in successful" output signal
0 signal  No effect
1/0 edge  Activates "teach-in" and transfer the instantaneous axis position into the teach-in block

**Note:**
- Prerequisites to activate the "teach-in" function:
  - "Positioning" mode ----> P0700 = 3
  - Traversing program isn't running ----> output signal "drive stationary" = "1"
  - Axis is referenced ----> output signal "reference point set" = "1"
- Refer under the index entry "Output signal - teach-in successful"
- The "teach-in" function is described in Chapter 6.13.

Control requested/no control requested

<table>
<thead>
<tr>
<th>Control requested/no control requested</th>
<th>-</th>
<th>x</th>
<th>x</th>
<th>STW1.10</th>
</tr>
</thead>
</table>
| 1 signal |  |  |  | This input signal must be set so that process data, transferred from the PROFIBUS master, is accepted by the slave and becomes effective.
**Recommendation:**
The input signal should only be set to "1", after the PROFIBUS slave has signaled back a realistic status using the status bit "control requested/no control possible" = "1".
| 0 signal |  |  |  | Data transferred from the PROFIBUS master is rejected by the slave, i.e. it is accepted as zero.

Start referencing/cancel referencing

<table>
<thead>
<tr>
<th>Start referencing/cancel referencing</th>
<th>65</th>
<th>-</th>
<th>x</th>
<th>STW1.11</th>
</tr>
</thead>
</table>
| 1/0 signal |  |  |  | ... starts the reference point approach of an axis.
The reference point approach is started
A reference point approach which has been started is interrupted
The drive brakes with the deceleration rate specified in P0104 (maximum deceleration).
The "reference point set" output signal remains at "0". |
Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>External block change (from SW 3.1)</td>
<td>67</td>
<td>n-set x</td>
<td>STW1.13</td>
</tr>
</tbody>
</table>

For a traversing block with the block change enable CONTINUE EXTERNAL, a flying block change can be initiated using this input signal (refer to Chapter 6.2.10).

0/1 edge or 1/0 edge

The external block change is initiated
When the edge is detected, in addition to the block change, the position actual value of the axis is written into P0026 (position actual value, block change).
The behavior when the signal edge is missing can be set using P0110 (configuration, external block change).

Note:
If the braking distance of the new block is too high due to a lower velocity override, then the block change enable is changed from CONTINUE FLYING to CONTINUE WITH STOP.

The "external block change" function can be initiated as follows:

- Using input terminal I0.x or, for a direct measuring system, via I0.B (P0672)
  - Recommended if P0110 ≤ 1, as it is a fast input
  - If the "external block change" function was parameterized at input terminal I0.x, then other terminals with this function, or the "external block change" PROFIBUS control signal, no longer have any effect.
  - The external block change is detected depending on the direction.
    The following applies:
    Traversing in a positive direction --> the 1/0 edge is identified as external block change
    Traversing in the negative direction --> the 0/1 edge is identified as external block change
    The actual value can be inverted using P1011.0, P0231 and P0232.
    There is no inversion, if none or 2 of these parameters are set to invert
    --> increasing (decreasing) position actual value corresponds to a positive (negative) direction
    The value is inverted, if 1 or all 3 parameters are set to invert.
    --> increasing (decreasing) position actual value corresponds to a negative (positive) direction
    - The value in P0026 corresponds to the existing position when the block change is detected.

- Using input terminal I1.x to I3.x or I4 to I11
  - Recommended, if P0110 ≥ 2
  - The external block change is independent of the direction.
  - The value in P0026 does not precisely correspond to the block change position due to internal signal propagation times.

- Using the PROFIBUS control signal STW1.13
  - The external block change is independent of the direction.
  - The value in P0026 does not precisely correspond to the block change position due to internal signal propagation times.

- Refer under the index entry "Block change enable - CONTINUE EXTERNAL".

Note:
If P0110 ≥ 2, then input terminal I0.x or I0.B may not be used as input, as, for these, the block change can be initiated from different signal edges.
### Table 6-46 List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fixed stop, sensor (from SW 3.3)</td>
<td>68</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Operating mode</td>
<td></td>
<td></td>
<td>PosStw.3</td>
</tr>
</tbody>
</table>

Using this input signal, the drive recognizes the "fixed stop reached" status via an external sensor.

1 signal Fixed stop is reached
0 signal Fixed stop has not been reached (standard)

**Requirements:**
The signal is only effective, if P0114 (fixed stop, configuration 2) = 1.

**Note:**
The "travel to fixed stop" function is described in Chapter 6.12.

**Request passive referencing**
(from SW 5.1)

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Operating mode</td>
<td></td>
<td></td>
<td>STW1.15</td>
</tr>
</tbody>
</table>

Using this input signal, passive referencing for the slave drive is controlled.

1/0 signal Set reference point

- 0: The value in P0160 (reference point coordinate) is set as the actual axis position.
- 2: The axis moves through the deviation to the reference position.

0/1 signal The reference cam and zero mark search are activated

An appropriate fault is signaled if a zero mark has not been found up to the 1/0 edge.

**Note:**
The "passive referencing" function is described in Chapter 6.3.

**Follow-up mode**

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Operating mode</td>
<td></td>
<td></td>
<td>PosStw.0</td>
</tr>
</tbody>
</table>

The follow-up mode for the axis is selected via this input signal.

1 signal Selecting follow-up operation

The axis is switched into the follow-up mode if the controller enable is additionally withdrawn via terminal 65.x.

In the follow-up mode, the position control loop is open. The position reference value continuously follows up the actual value, i.e. the actual value is further sensed and updated but a setpoint is not output.

If the axis is shifted from its position due to external effects, then the monitoring does not output an error message.

0 signal Canceling the follow-up mode

If the controller is re-enabled, then the axis movement continues at the new actual position which could have changed.

The position control loop is closed.

**Note:**
- The follow-up mode status is displayed via the "follow-up mode active" output signal.
- The follow-up mode can also be selected as internal control response to an error.
- Refer under the index entry "Follow-up mode"
Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Setting home position</td>
<td>71</td>
<td>-</td>
<td>PosStw.1</td>
</tr>
</tbody>
</table>

An axis can be assigned a required actual value (P0160) (actual value setting) at any position using the 0/1 edge of the input signal. This is only possible if a traversing block is not being executed.

0/1 signal  The home position is set, i.e. the value P0160 is assigned as actual position. After this, the axis is considered to have been referenced (output signal "home position set" = "1").

Note:
If the home position is set again (new command), then for the backlash compensation, the system behaves as if the home position was not set again.

<table>
<thead>
<tr>
<th>Activate coupling (from SW 3.3)</th>
<th>72</th>
<th>-</th>
<th>x</th>
<th>PosStw.4</th>
</tr>
</thead>
<tbody>
<tr>
<td>The coupling, set via P0410, is activated using this input signal.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal  No function</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0/1 signal  Activate coupling</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The coupling is activated corresponding to P0410.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P0410</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>= 1 or 2  --&gt; Coupling is switched-in</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>= 3 or 4  --&gt; The signal has no significance</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>= 5 or 6  --&gt; The coupled position is transferred into the queue (being prepared)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>= 7     --&gt; Coupling is switched-in at the absolute position of the master drive (from SW 4.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>= 8     --&gt; Coupling via the traversing program to the absolute position of the master drive (from SW 4.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

0 signal  Coupling-out, initial status

Note:
- Recommended for powering-up with a precise position:
  Use the fast input I0.x on the control board.
  --> refer to the input signal "activate coupling via I0.x" (function number 73)
- The position when switching-in the coupling is displayed in P0425:0.
- The "axis coupling" function is described in Chapter 6.3.
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Activate coupling via I0.x (from SW 3.3)</td>
<td>73</td>
<td>n-set</td>
<td>&lt;br&gt;pos</td>
</tr>
</tbody>
</table>

The coupling, set via P0410, is activated via the fast input I0.x using this input signal.

The activate coupling "input signal" (function number 72) prepares the switching-in process via terminal I0.x.

The edge of the input signal "activate coupling via I0.x" (function number 73) switches-in the coupling.

The coupling is switched-out via the "activate coupling" input signal (function number 72).

- **1 signal** No significance
- **1/0 signal** This edge switches-in the coupling for a positive traversing direction of the master axis
- **0/1 signal** This edge switches-in the coupling for a negative traversing direction of the master axis

**Prerequisites:**

Input signal, "activate coupling" (function number 72) = "1"

- **0 signal** No significance

- **Input signal, "activate coupling"**
- **Input terminal with function number 72 or control signal PosStw.4**
- **Input signal, "activate coupling via I0.x"**
- **Input terminal I0.x with function number 73**

**Coupling in**

**Coupling out**

**Note:**

- The position when switching-in the coupling is displayed in P0425:0.
- Function number 73 is only effective when assigned to input terminal I0.x.
- The "activate coupling via I0.x" signal is recognized, dependent on the direction.
- --> refer under the index entry "Input signal, digital - external block change"
- The "axis coupling" function is described in Chapter 6.3.

### Set setpoint, master drive (from SW 4.1) | 74 | - | x | QStw.0

The absolute position of the master drive is set in the slave drive to the reference point coordinates using this input signal.

- **1 signal** No significance
- **0/1 signal** The absolute position of the master drive is signaled to the slave drive once
- **0 signal** No significance

**Note:**

- The input signal "set setpoint, master drive" is only required for P0891 = 0 or 1. Only after this, may a coupling be switched-in to the absolute position of the master drive (P0410 = 7 or 8)
- --> otherwise, Fault 177 is output.
- The reference point coordinates of the master drive are signaled to the slave drive using P0400.
- The "axis coupling" function is described in Chapter 6.3.
### Table 6-46 List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Invert the ang. incr. encoder input (from SW 3.5)</td>
<td>75</td>
<td>-</td>
<td>x</td>
</tr>
</tbody>
</table>

The incremental position reference value, received via the angular incremental encoder interface, can be inverted using this input signal. When inverting, the incremental position reference value becomes effective in the opposite direction.

1 signal Inverting the incremental position reference value via the angular incremental encoder interface

0 signal No inversion

**Note:**
- Angular incremental encoder interface as input refer to Chapter 6.8.2
- The signal may only change when the axis is stationary.

### Reference cams

| | 78 | - | x | PosStw.2 |

This input signal is used to signal, when referencing, whether the axis remains stationary at the reference cam.

1 signal The axis is located at the reference cam

0 signal The axis is not located at the reference cam

### Equivalent zero mark

| | 79 | x | x | - |

If the encoder zero pulse cannot be evaluated when referencing, then a signal supplied from a mounted sensor can be fed via this input as "zero mark equivalent".

1 signal No significance

1/0 signal When passing the zero mark cam in a positive direction, this edge is detected as the equivalent zero mark

0/1 signal When passing the zero mark cam in a negative direction, this edge is detected as the equivalent zero mark

0 signal No significance

**Assumption:**

The BERO is high active

**Signal characteristics at input I0.x**

- 1 signal
- 0 signal

1. **Starting in front of or at the cam and traversing in a positive direction** --> the 1/0 edge at input I0.x is identified as equivalent zero mark

2. **Starting at the cam and traversing in a negative direction** --> an equivalent zero mark is not identified

3. **Starting after the cam and traversing in a negative direction** --> the 0/1 edge at input I0.x is identified as the equivalent zero mark
### 6.4 Input/output terminals of the control board

#### Table 6-46 List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Operating mode</th>
<th>Fct. No.</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td>n-set</td>
<td>pos</td>
</tr>
</tbody>
</table>

**Note:**
- This function must be executed via input terminal I0.x (fast input).
- Activate the "equivalent zero mark" function for an incremental measuring system:
  - refer to P0174
  - refer to P0879.13 or P0879.14
- The equivalent zero mark is identified as a function of the direction.
- The actual value can be inverted using P1011.0, P0231 and P0232.
  - There is no inversion, if none or 2 of these parameters are set to invert
    - in increasing (decreasing) position actual value corresponds to a positive (negative) direction
  - The value is inverted, if 1 or all 3 parameters are set to invert.
    - in increasing (decreasing) position actual value corresponds to a negative (positive) direction

**Flying measurement/length measurement (from SW 3.1)**

<table>
<thead>
<tr>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>Signal name, description</th>
</tr>
</thead>
<tbody>
<tr>
<td>80</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

The encoder actual value can be retrieved via an input with this function.

- 0/1 signal or 1/0 signal: The actual encoder value is retrieved.

**Note:**
- This function must be executed via the fast I0.x input.
- The function is only available for "Motion Control with PROFIBUS-DP".
  - refer under the index entry "Encoder interface (from SW 3.1)"
- The function is only available for the control board "SIMODRIVE 611 universal" from Order No. 6SN1118-xxxxx-OAA and control board "SIMODRIVE 611 universal HR/HRS".
- This function cannot be executed for spindle positioning active (P0125 = 1).
- The measuring probe signal is defined depending on the parameterized edge in control word Gx_STW.0/1 (refer to Chapter 5.6.4).
- The edge clearance must be at least 150 ms. Measuring probe edges that are received faster (low clearance between signals) cannot be evaluated.
- If the measuring probe signal is to be transferred via PROFIBUS in Gx_ZSW.8 then it must be present at input I0.x ≥ 4 ms.

**Plus hardware limit switch (NC contact)**

<table>
<thead>
<tr>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>Signal name, description</th>
</tr>
</thead>
<tbody>
<tr>
<td>81</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

A hardware limit switch can be connected at an input with this function in order to limit the traversing range in either the positive or negative direction.

- 1/0 signal: The plus or minus hardware limit switch has been actuated.
  - The axis is braked. The drive remains in closed-loop control.
  - In the pos mode:
    - The axis can be moved away from the limit switch in the jog mode.
  - In the n-set mode (from SW 8.1):
    - The axis can be moved away from the limit switch using a setpoint that is opposite to the approach direction.

**Note:**
- 1 signal: No significance
- 1) from SW 8.1
  - refer under the index entry "hardware limit switch"
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Activate MDI (from SW 7.1)</td>
<td>83</td>
<td>- x</td>
<td>SatzAnw.15</td>
</tr>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>If MDI is switched-in with the traversing program active, or is switched-out while the traversing block is running, alarm 144 is initiated which interrupts the traversing program/traversing block.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Activate angular incremental encoder, handwheel (from SW 8.1)</td>
<td>84</td>
<td>- x</td>
<td>SatzAnw.13</td>
</tr>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>If the input signal &quot;jogging 1 ON/jogging 1 OFF&quot; or &quot;jogging 2 ON/jogging 2 OFF&quot; and &quot;activate angular incremental encoder, handwheel&quot; are switched-in, Alarm 121 is output.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 0 (from SW 8.1)</td>
<td>85</td>
<td>- x</td>
<td>SatzAnw.11</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1)</td>
<td>86</td>
<td>- x</td>
<td>SatzAnw.12</td>
</tr>
<tr>
<td>The factors entered using the following parameters are calculated-in using these 2 input signals.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Before SW 9.1: P0900:4</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>From SW 9.1: P0889:4</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Ang. incr. enc. hwh. eval.</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Bit 0</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>Bit 1</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>--&gt; refer under the index entry &quot;Angular incremental encoder interface&quot;</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Ramp-function generator start/ramp-function generator stop</td>
<td>- x -</td>
<td>STW1.5</td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>The ramp-function generator is enabled</td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>The setpoint at the ramp-function generator output is frozen</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Enable setpoint/inhibit setpoint</td>
<td>- x -</td>
<td>STW1.6</td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>Enable setpoint</td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>Inhibit setpoint</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>The setpoint at the ramp-function generator input is enabled.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>The setpoint at the ramp-function generator input is set to zero.</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Motor changed over (from SW 2.4)</td>
<td>-</td>
<td>x, -</td>
<td>STW2.11</td>
</tr>
</tbody>
</table>

For P1249 = 1 motor changeover is controlled via this input signal.

- **1 signal**: Initial status
- **1/0 signal**: Pulse enable is withdrawn
- **0 signal**: Initial status, selecting a motor corresponding to the motor data set
- **0/1 signal**: Enable the pulses

**Input signals (selection)**
- Motor data set changeover 1st input,
- motor data set changeover 2nd input

**Control signal STW2.11**
"motor changed over"

**Pulse enable**
(SIMODRIVE 611 universal internal)

**Output signals**
- Actual motor 1st signal (ZSW2.9)
- Actual motor 2nd signal (ZSW2.10)

**Output signal**
"status, controller enable" (ZSW1.2)

**Output signals from the SIMATIC S7**
(Contactor control)

1. Selects the required motor data set
2. Signal to "SIMODRIVE 611 universal": The pulse enable is internally withdrawn after STW2.11 = 0
3. The motors are only changed over when the pulses have been canceled (switched-in a no-current condition)
4. Selects the motor corresponding to the motor data set
5. Signal to "SIMODRIVE 611 universal": enable the pulses (STW2.11 edge 0 - 1)

**Note:**
The "motor changeover" function is described in Chapter 6.11.
### Table 6-46  List of input signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Accelerating time zero for controller enable (from SW 3.1)</td>
<td>[208x146]</td>
<td>STW1.13</td>
</tr>
</tbody>
</table>

The ramp-function generator (RFG) can be enabled/disabled as a function of the controller enable via this input signal.

1 signal  
Operating case: Controller enabled  
--- > the drive ramp-function generator is off  
--- > the “zero ramp-up time” is controlled  
--- > a higher-level control can assume the ramp-fct generator function  
Error situation: Controller not enabled  
--- > drive ramp-function generator is on  
--- > the drive brakes via P1257.8 (ramp-fct. generator ramp-down time)

0 signal  
Ramp-function generator on

**Application:**

The following is valid when the signal is set:

If the controller is enabled, a higher-level control can assume the ramp-function generator function. If the controller is not enabled, the drive ramp-function generator is again effective.

**Note:**

Refer to the "zero ramp-up time" input signal

<table>
<thead>
<tr>
<th>Master sign-of-life (from SW 3.1)</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>- x x</td>
<td>STW2.12 STW2.13 STW2.14 STW2.15</td>
</tr>
</tbody>
</table>

For the "Motion Control with PROFIBUS-DP" function, these control signals are used as sign-of-life (4-bit counter).

The sign-of-life counter is incremented from 1 to 15 and then starts again with the value 1.

**Note:**

The "Motion Control with PROFIBUS-DP" function is described in Chapter 5.8.
6.4.4 Permanently-connected output terminals

Table 6-47 Permanently-connected output terminals

<table>
<thead>
<tr>
<th>Terminal</th>
<th>Drive A</th>
<th>Function</th>
<th>Drive B</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>X421</td>
<td></td>
<td>Checkback signal, start inhibit</td>
<td></td>
<td>The relay contact (NC contact) pulls-in, if the enable voltage is available at terminal 663 (module-specific pulse enable).</td>
</tr>
<tr>
<td>AS1</td>
<td></td>
<td></td>
<td>AS2</td>
<td></td>
</tr>
</tbody>
</table>

Note

Mode of operation, application purpose and additional information on the "safe start inhibit" is included in:

Reference: /PJU/ SIMODRIVE 611, Configuration Manual, Drive Converters Chapter "Start inhibit in the drive modules"

6.4.5 Freely-parameterizable digital output terminals

Description

There are 4 freely-parameterizable output terminals for each axis. A terminal is parameterized by entering the appropriate required function number into the assigned parameter.

Which function numbers are available? --> Refer to Chapter 6.4.6

P0699 is used to define as to whether the output signal is output, inverted, or not inverted.

Notice

The terminals may only be parameterized when the drive pulses are canceled.

Warning

Digital outputs can assume non-definable states while the module boots, the module is being initialized, for a computation time overflow or processor crash. This can result in a safety risk at the machine which must be completely eliminated using the appropriate external resources!
There is the following assignment between terminals, drives and parameters:

### Table 6-48  Overview for freely-parameterizable output terminals

<table>
<thead>
<tr>
<th>Terminal Drive A</th>
<th>Terminal Drive B</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>O0.A X461.7</td>
<td>O0.B X462.7</td>
<td>0680</td>
<td>Signaling function, output terminal O0.x</td>
<td>0</td>
<td>33</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>O1.A X461.8</td>
<td>O1.B X462.8</td>
<td>0681</td>
<td>Signaling function, output terminal O1.x</td>
<td>0</td>
<td>2</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>O2.A X462.9</td>
<td>O2.B X462.9</td>
<td>0682</td>
<td>Signaling function, output terminal O2.x</td>
<td>0</td>
<td>1</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>O3.A X461.10</td>
<td>O3.B X462.10</td>
<td>0683</td>
<td>Signaling function, output terminal O3.x</td>
<td>0</td>
<td>5</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

A function can be assigned to each output terminal using these parameters. The function number from the list of output signals is entered (refer to Chapter 6.4.6).

**Note:**
The status of the output terminals is displayed in P0698 for diagnostics (refer to Chapter 4.5).

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Inversion Output terminal signals</th>
<th>0</th>
<th>0</th>
<th>FFF</th>
<th>Hex</th>
<th>immediately</th>
</tr>
</thead>
</table>

The output terminal signals can be inverted using this parameter.

\[
\begin{align*}
2^0 &= 1 \\
2^1 &= 2 \\
2^2 &= 4 \\
2^3 &= 8
\end{align*}
\]

\[
P0699 = 0 \quad 5 \quad 0 \quad 6 \quad \text{hex}
\]

Example: \[\rightarrow\] O8 O10 O1.x O2.x are output inverted

**Note:**
O4 - O11 are available on the optional TERMINAL module (refer to Chapter 6.5).
6.4.6 List of output signals

Reader’s note
The drive “signals” the output signals, listed in the Tables 6-49 and 6-50 either through an output terminal or as status bit to PROFIBUS-DP.
All of the output signals can be found in the Index under Output signal...

For output signals, which are assigned to terminals, an inversion can be parameterized. In this list, these output signals are represented as not inverted.
If an output signal inversion has been parameterized, then this must be appropriately taken into account when representing the signal.

The following must be specified for each signal:
• Fct. No.:
The function number is required to parameterize the output terminal via the display and operator control unit.

• Operating mode (P0700):
This specifies in which operating mode the signal is available (x: Available, -: Not available).

  n-set: "Speed/torque setpoint" mode
  pos: "Positioning" mode

• PROFIBUS bit:
The bit name is required to read the signal via PROFIBUS-DP (refer to Chapter 5.6.1).
Example: ZSW2.10 --> that means, status 2 bit 10
### Table 6-49  Overview of the output signals

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inactive</td>
<td>0</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>(</td>
<td>n_{\text{act}}</td>
<td>&lt; n_{\text{min}} )</td>
<td>1</td>
</tr>
<tr>
<td>Ramp-up completed</td>
<td>2</td>
<td>x</td>
<td>x(^{(1)(2)})</td>
</tr>
<tr>
<td>(</td>
<td>M</td>
<td>&lt; M_{x} )</td>
<td>3</td>
</tr>
<tr>
<td>(</td>
<td>n_{\text{acl}}</td>
<td>&lt; n_{x} )</td>
<td>4</td>
</tr>
<tr>
<td>Motor overtemperature pre-warning</td>
<td>5</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Heatsink temperature pre-warning</td>
<td>6</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Variable signaling function</td>
<td>7</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Open-loop torque controlled mode</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Integrator inhibit, speed controller</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Parameter set</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1st input/2(^0)</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>2nd input/2(^1)</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>3rd input/2(^2)</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Motor 1 selected (from SW 2.4)</td>
<td>11</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Motor 2 selected</td>
<td>12</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Motor 3 selected</td>
<td>13</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Motor 4 selected</td>
<td>14</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Status, fixed speed setpoint (from SW 3.1)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1st output/2(^0)</td>
<td>15</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>2nd output/2(^1)</td>
<td>16</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>3rd output/2(^2)</td>
<td>17</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>4th output/2(^3)</td>
<td>18</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>( n_{\text{set}} = n_{\text{act}} )</td>
<td>20</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Function generator active</td>
<td>24 (from SW 11.1)</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Spindle positioning on (from SW 5.1)</td>
<td>28</td>
<td>x</td>
<td>-</td>
</tr>
<tr>
<td>Warning present/no warning present (from SW 3.3)</td>
<td>29</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>DC link monitoring ( V_{\text{DC link}} &gt; V_{x} )</td>
<td>30</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Fault present/no fault present</td>
<td>31</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Status, controller enable</td>
<td>32</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Ready or no fault</td>
<td>33</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Parking axis selected</td>
<td>34</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Open holding brake</td>
<td>35</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Pulses enabled (from SW 3.1)</td>
<td>36</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Power module current not limited (from SW 3.1)</td>
<td>37</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

1) In the pos mode, the signal can only be conditionally used.
2) From SW 11.1 the "Programmed velocity reached" output signal, Fct. No. 88, can be configured.
### Table 6-49 Overview of the output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>Fct. No.</td>
<td>n-set</td>
</tr>
<tr>
<td>Control via PROFIBUS (from SW 3.1)</td>
<td>38</td>
<td>x</td>
</tr>
<tr>
<td>Status, block selection 1st output/2⁰</td>
<td>50</td>
<td>x</td>
</tr>
<tr>
<td>2nd output/2¹</td>
<td>51</td>
<td>x</td>
</tr>
<tr>
<td>3rd output/2²</td>
<td>52</td>
<td>x</td>
</tr>
<tr>
<td>4th output/2³</td>
<td>53</td>
<td>x</td>
</tr>
<tr>
<td>5th output/2⁴</td>
<td>54</td>
<td>x</td>
</tr>
<tr>
<td>6th output/2⁵</td>
<td>55</td>
<td>x</td>
</tr>
<tr>
<td>(from SW 10.1) 7th output/2⁶</td>
<td>56</td>
<td>x</td>
</tr>
<tr>
<td>(from SW 10.1) 8th output/2⁷</td>
<td>57</td>
<td>x</td>
</tr>
<tr>
<td>Ready to be powered-up/not ready to be powered-up</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>No OFF 2 present/OFF 2 present</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>No OFF 3 present/OFF 3 present</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Power-on inhibit/no power-on inhibit</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>No following error/following error</td>
<td>58</td>
<td>-</td>
</tr>
<tr>
<td>Spindle position reached (from SW 5.1)</td>
<td>59</td>
<td>x</td>
</tr>
<tr>
<td>Control requested/no control possible</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Comparison value reached/comparison value not reached</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Reference position reached/outside reference position</td>
<td>60</td>
<td>-</td>
</tr>
<tr>
<td></td>
<td></td>
<td>x</td>
</tr>
<tr>
<td>Reference point set/no reference point set</td>
<td>61</td>
<td>-</td>
</tr>
<tr>
<td>Setpoint acknowledge</td>
<td>62</td>
<td>-</td>
</tr>
<tr>
<td>Teach-in executed (from SW 4.1)</td>
<td>64</td>
<td>-</td>
</tr>
<tr>
<td>Drive stationary/drive moving</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>First speed setpoint filter inactive</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Ramp-function gen. inactive</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Actual motor (from SW 2.4) 1st signal</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>2nd signal</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Motor being changed over (from SW 3.3)</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Slave sign-of-life (from SW 3.1)</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Suppress fault 608 active (from SW 3.1)</td>
<td>-</td>
<td>x</td>
</tr>
<tr>
<td>Travel to fixed stop active (from SW 3.3)</td>
<td>66</td>
<td>-</td>
</tr>
<tr>
<td>External block change (from SW 7.1)</td>
<td>67</td>
<td>-</td>
</tr>
</tbody>
</table>
### Table 6-49  Overview of the output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fixed stop reached (from SW 3.3)</td>
<td>68</td>
<td>-</td>
<td>PosZsw.12</td>
</tr>
<tr>
<td>Request passive referencing (from SW 5.1)</td>
<td>69</td>
<td>-</td>
<td>ZSW1.15</td>
</tr>
<tr>
<td>Followup mode active</td>
<td>70</td>
<td>-</td>
<td>PosZsw.0</td>
</tr>
<tr>
<td>In synchronism (from SW 3.3)</td>
<td>71</td>
<td>-</td>
<td>PosZsw.3</td>
</tr>
<tr>
<td>Setpoint static</td>
<td>72</td>
<td>-</td>
<td>PosZsw.2</td>
</tr>
<tr>
<td>Fixed stop clamping torque reached (from SW 3.3)</td>
<td>73</td>
<td>-</td>
<td>PosZsw.13</td>
</tr>
<tr>
<td>Axis moves forwards</td>
<td>74</td>
<td>-</td>
<td>PosZsw.4</td>
</tr>
<tr>
<td>Axis moves backwards</td>
<td>75</td>
<td>-</td>
<td>PosZsw.5</td>
</tr>
<tr>
<td>Minus software limit switch actuated</td>
<td>76</td>
<td>-</td>
<td>PosZsw.6</td>
</tr>
<tr>
<td>Plus software limit switch actuated</td>
<td>77</td>
<td>-</td>
<td>PosZsw.7</td>
</tr>
<tr>
<td>Cam switching signal 1</td>
<td>78</td>
<td>-</td>
<td>PosZsw.8</td>
</tr>
<tr>
<td>Cam switching signal 2</td>
<td>79</td>
<td>-</td>
<td>PosZsw.9</td>
</tr>
<tr>
<td>Direct output 1 via the traversing block</td>
<td>80</td>
<td>-</td>
<td>PosZsw.10</td>
</tr>
<tr>
<td>Direct output 2 via the traversing block</td>
<td>81</td>
<td>-</td>
<td>PosZsw.11</td>
</tr>
<tr>
<td>Velocity limiting active</td>
<td>82</td>
<td>-</td>
<td>PosZsw.1</td>
</tr>
<tr>
<td>MDI active (from SW 7.1)</td>
<td>83</td>
<td>-</td>
<td>AktSatz.15</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel active (from SW 8.1)</td>
<td>84</td>
<td>-</td>
<td>AktSatz.13</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 0 (from SW 8.1)</td>
<td>85</td>
<td>-</td>
<td>AktSatz.11</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1)</td>
<td>86</td>
<td>-</td>
<td>AktSatz.12</td>
</tr>
<tr>
<td>Block processing inactive (from SW 8.1)</td>
<td>87</td>
<td>x</td>
<td>AktSatz.10</td>
</tr>
<tr>
<td>Programmed velocity reached (from SW 11.1)</td>
<td>88</td>
<td>-</td>
<td>MeldW.0</td>
</tr>
</tbody>
</table>
### 6.4 Input/output terminals of the control board

#### Table 6-50 List of output signals

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inactive</td>
<td>0</td>
<td>n-set x</td>
<td>pos x</td>
</tr>
</tbody>
</table>

An output with this function is "disabled", i.e. a signal is not output (continuously 0 V). The output terminal can still be connected-up, but it is not evaluated.

**Application:**
To start-up a drive (commission a drive) the "disturbing outputs" are first switched-out, and then are subsequently activated to be commissioned.

| \[|n_{act}| < n_{\text{min}}\] | 1 | x | x | MeldW.2 |
|-----------------------------|---|---|---|---------|

This output signal is used to display whether the absolute actual speed (\(|n_{act}|\)) is less than or greater than the selected threshold speed (\(n_{\text{min}}\), P1418:8).

![Diagram showing fixed hysteresis of 2 RPM](image)

**Application:**
The gearbox stage is only mechanically changed-over if the speed is less than that set in P1418:8, in order to reduce the stressing on the mechanical system.

<table>
<thead>
<tr>
<th>Ramp-up completed</th>
<th>2</th>
<th>x</th>
<th>x^1)</th>
<th>MeldW.0</th>
</tr>
</thead>
</table>

The end of a ramp-up operation is displayed after the speed setpoint has been changed, using this output signal.

1 signal Ramp-up has been completed
1/0 signal Ramp-up starts
The start-up is identified, if
- the speed setpoint changes
and
- the defined tolerance bandwidth (P1426) is exited.

0 signal Ramp-up runs
0/1 signal Ramp-up has been completed
The end of ramp-up is identified, if
- the speed setpoint is constant
and
- the speed actual value is within the tolerance bandwidth around the speed setpoint
and
- the delay time has expired (P1427).

**Note:**
Detailed information on the ramp-function generator is provided in Chapter 6.1.3.

1) In the pos mode, the signal can only be conditionally used because the speed setpoint is controlled and there is no ramp-function generator.
Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>(</td>
<td>M</td>
<td>&lt; M_x )</td>
<td>3</td>
</tr>
</tbody>
</table>

This output signal indicates whether the absolute torque \(|M|\) is less than or greater than the selected torque \((M_x, P1428)\). The value refers to the actual torque limiting when motoring including all limits (refer to Chapter 6.1.8, Fig. 6-7).

The evaluation \(|M| < M_x\) is only realized in the n-set mode, if
- The "ramp-up completed" status is signaled and
- The delay time in P1429 has expired.

Application:
Using this signal, a motor overload condition can be detected in order to be able to introduce an appropriate response (stop the motor or reduce the load).

Note:
- In the pos mode, the "ramp-up completed" state is always signaled, i.e. the delay time in P1429 has already expired. The signal \(|M| < M_x\) immediately changes the signal state. Only when the delay time in P1429 changes, is the signal \(|M| < M_x\) output delayed by this time.
- Parameter P1428 is referred to the threshold torque \(M_X\) (ARM. SRM) or the threshold force \(F_X\) (SLM).
- In the pos mode, the signal can only be conditionally used because the speed setpoint is controlled and there is no ramp-function generator.
Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>$</td>
<td>n_{act}</td>
<td>&lt; n_x $</td>
<td>4</td>
</tr>
</tbody>
</table>

This output signal is used to display as to whether the absolute actual speed ($| n_{act}|$) is less than or greater than the selected threshold speed ($n_x$, P1417:8).

![Fixed hysteresis= 12 RPM](image)

| $| n_{act}| < n_x $ | 1 signal | 0 signal |
|------------------|----------|----------|
| $| n_{act}| > n_x $ | $| n_{act}| < n_x $ | $| n_{act}| > n_x $ |

### Application:

**Speed monitoring**

**Motor overtemperature pre-warning**

This output signal is used to display whether the motor temperature ($\theta_{Mot}$) is less than or greater than the selected motor temperature ($\theta_x$, P1602) warning threshold.

**Note:**
- If the motor temperature warning threshold is exceeded, initially, "only" an appropriate signal is output. When the warning threshold is fallen below, the signal is automatically withdrawn.
- If the overtemperature remains for a time longer than that set in P1603, then an appropriate fault is output.
- The motor temperature monitoring function can be disabled/enabled using P1601.14.

![Motor temperature](image)

<table>
<thead>
<tr>
<th>Motor temperature pre-warning</th>
<th>5</th>
<th>x</th>
<th>x</th>
<th>MeldW.6</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Application:
The user can respond to this message by reducing the load, thereby preventing the motor from shutting down with the "Motor temperature exceeded" fault after the set time has elapsed.

**Heatsink temperature pre-warning**

This output signal is used to display whether the temperature of the heatsink in the power module has been exceeded.

The hardware temperature switch-in the power module cannot be parameterized.

<table>
<thead>
<tr>
<th>Heatsink temperature pre-warning</th>
<th>6</th>
<th>x</th>
<th>x</th>
<th>MeldW.7</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

This output signal is used to display whether the temperature of the heatsink in the power module has been exceeded.

<table>
<thead>
<tr>
<th>1 signal</th>
<th>No heatsink temperature pre-warning</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>The temperature is within the permissible range.</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>0 signal</th>
<th>Heatsink temperature pre-warning</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>The temperature is outside the possible range.</td>
</tr>
<tr>
<td></td>
<td>If the excessive temperature remains, then the drive is powered down after approx. 20 s (tripped).</td>
</tr>
</tbody>
</table>
### Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Variable signaling function</td>
<td>7</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

This output signal indicates whether any selected internal quantity has been fallen below or exceeded a selectable threshold value.

A hysteresis (P1624) can be specified for the threshold value and a time for the pull-in or drop-out delay (P1625, P1626) can be specified for the signal output.

The quantity to be monitored can either be selected by entering a signal number (P1621) or by entering an address (P1620.1 and P1622).

- **P1620.0** 1: Active  
  0: Not active
- **P1620.1** 1: address range Y  
  0: address range X
- **P1620.2** 1: comparison with the sign  
  0: comparison without the sign
- **P1621** Signal number, variable signaling function  
  The signal number from the signal selection list for analog outputs must be entered here (refer to Chapter 6.7 under Table 6-57).  
  If the signal number = 1 (physical address), then the address must be entered into P1620.1 of the address range and in P1622, the address (this is only relevant for Siemens service activities).
- **P1622** Address, variable signaling function
- **P1623** Threshold, variable signaling function
- **P1624** Hysteresis, variable signaling function

**Note:** The threshold and hysteresis are obtained from the signals specified in the normalization P1621. The normalization is described in Chapter 6.7 under Table 6-57 and can be partially read-out of parameters.

- **P1625** Pull-in delay variable signaling function
- **P1626** Drop-out delay variable signaling function

![Diagram](image_url)

- 1 signal
- 0 signal

<table>
<thead>
<tr>
<th>threshold, P1623</th>
<th>P1624</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;</td>
<td>P1625</td>
</tr>
<tr>
<td>&gt;</td>
<td>P1626</td>
</tr>
</tbody>
</table>

- Fallen below
- Exceeded
- Fallen below
### Table 6-50 List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Open-loop torque controlled mode</td>
<td></td>
<td>n-set</td>
<td>pos</td>
</tr>
<tr>
<td>This output signal is used to signal whether closed-loop speed controlled or open-loop torque controlled operation has been selected (STW1.14).</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal Moist-loop torque controlled operation ((M_{\text{set}}) mode)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal Closed-loop speed controlled operation ((n_{\text{set}}) mode)</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**

For the "travel to fixed stop" function (positioning mode), after the fixed stop was reached, the position controller goes into the state "open-loop torque controlled mode". The signal ZSW1.14 is then also set to 1 in the pos mode.

<table>
<thead>
<tr>
<th>Integrator inhibit, speed controller</th>
<th></th>
<th>x</th>
<th>x</th>
<th>ZSW2.6</th>
</tr>
</thead>
<tbody>
<tr>
<td>This output signal is used to signal whether the integral component of the speed controller is inhibited or enabled.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal Moist-integrator inhibit, speed controller</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The speed controller integrator is not inhibited</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Parameter set</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st input/(2^0)</td>
<td></td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>2nd input/(2^1)</td>
<td></td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>3rd input/(2^2)</td>
<td></td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

These 3 output signals are used to output the selected parameter set.

<table>
<thead>
<tr>
<th>Parameter set</th>
<th>0</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>6</th>
<th>7</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st input/weighting (2^0)</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>2nd input/weighting (2^1)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>3rd input/weighting (2^2)</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

**Note:**

- The "parameter set changeover" function is described in Chapter 6.10.

| Motor 1 selected (from SW 2.4) | 11 | x  | -  | -  |
| Motor 2 selected                | 12 | x  | -  | -  |
| Motor 3 selected                | 13 | x  | -  | -  |
| Motor 4 selected                | 14 | x  | -  | -  |

The motor changeover contactors are controlled via these output terminal signals.

| Motor 5 selected                | 15 | x  | -  | -  |

**Note:**

- The motor changeover version and therefore the behavior of the terminal, is selected using P1013 (motor changeover).
- To select the motors or motor data sets, input terminal signals are available with function numbers 5 and 6 (motor data set changeover 1st input/2nd input).
- Motor changeover is described in Chapter 6.11.
Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Status, fixed speed setpoint (from SW 3.1)</td>
<td>Fct. No.</td>
<td>n-set</td>
</tr>
<tr>
<td>1st output/2⁰</td>
<td>15</td>
<td>x</td>
</tr>
<tr>
<td>2nd output/2¹</td>
<td>16</td>
<td>x</td>
</tr>
<tr>
<td>3rd output/2²</td>
<td>17</td>
<td>x</td>
</tr>
<tr>
<td>4th output/2³</td>
<td>18</td>
<td>x</td>
</tr>
</tbody>
</table>

These output signals are used to display which fixed setpoint is selected via the input signals, and which parameters specify the speed setpoint.

### Fixed speed setpoint

<table>
<thead>
<tr>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>...</th>
<th>15</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st output/weighting 2⁰</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>...</td>
</tr>
<tr>
<td>2nd output/weighting 2¹</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>...</td>
</tr>
<tr>
<td>3rd output/weighting 2²</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>...</td>
</tr>
<tr>
<td>4th output/weighting 2³</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
</tr>
</tbody>
</table>

Effective fixed speed setpoint

<table>
<thead>
<tr>
<th>Fct. No.</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0641:1</td>
<td>P0641:2</td>
</tr>
<tr>
<td>P0641:3</td>
<td>to P0641:15</td>
</tr>
</tbody>
</table>

**Note:**

- The "fixed speed setpoint" function is described in Chapter 6.1.6.
- Refer to the "Fixed speed setpoint 1st to 4th input" output signal in Chapter 6.4.3.

### n_set = n_act

<table>
<thead>
<tr>
<th>20</th>
<th>ZSW1.8</th>
</tr>
</thead>
<tbody>
<tr>
<td>x</td>
<td>-</td>
</tr>
</tbody>
</table>

This output signal is used to display whether the speed actual value (n_act) has entered the tolerance bandwidth (P1426), and has remained in this tolerance bandwidth for at least a time (P1427).

**Note:**

When spindle positioning is selected (P0125 = 1), ZSW1.8 behaves/responds just the same as Fct. No. 58 (pos mode)

In the pos mode, the signal can only be conditionally set as the speed setpoint is controlled.
### Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Function generator active</td>
<td>24 (from SW 11.1)</td>
<td>x</td>
<td>ZSW1.13 (from SW 6.1)</td>
</tr>
</tbody>
</table>

The output signal provides information about the status of the function generator or the measuring function.

1 signal The function generator or the measuring function in the drive is active.
0 signal The function generator or the measuring function in the drive is not active.

**Operating mode**

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Spindle positioning on (from SW 5.1)</td>
<td>28</td>
<td>x</td>
<td>ZSW1.15</td>
</tr>
</tbody>
</table>

This signal displays as to whether the "spindle positioning" function has been activated.

1 signal "Spindle positioning" function is active
0 signal Function is not active

**Note:**
- Refer under the index entry "Input signal - spindle positioning on"
- The "spindle positioning" function is described in Chapter 6.15 (from SW 5.1)

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Warning present/no warning present</td>
<td>29 (from SW 3.3)</td>
<td>x</td>
<td>ZSW1.7</td>
</tr>
</tbody>
</table>

The output signal indicates whether the drive is signaling at least one warning.

1 signal Warning present
Which warning(s) is(are) present?
This can be identified by evaluating P0953 to P0960 (Warnings 800 to 927) (refer to Chapter 5.9).
0 signal Warning not present

**Note:**
- Refer to Chapter 7 for information on the faults as well as their acknowledgment.

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>DC link monitoring $V_{DC link} &gt; V_x$</td>
<td>30</td>
<td>x</td>
<td>MeldW.4</td>
</tr>
</tbody>
</table>

This output signal is used to display whether the DC link voltage ($V_{DC link}$) is less than or greater than the selected DC link undervoltage warning threshold ($V_x$, P1604).

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fault present/no fault present</td>
<td>31</td>
<td>x</td>
<td>ZSW1.3</td>
</tr>
</tbody>
</table>

The output signal indicates whether the drive is signaling at least one fault.

1 signal Fault present
There is at least one fault present.
The cause of the fault or faults which is (are) present, must be removed and the fault then acknowledged.
0 signal No fault present

**Note:**
- Refer to Chapter 7 for information on the faults as well as their acknowledgment.
### 6.4 Input/output terminals of the control board

Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Status, controller enable</strong></td>
<td>32</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>This output signal is used to display whether the speed controller is active and is ready to accept speed setpoints.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The speed controller is active and setpoints can be accepted</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The speed controller is not active</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Ready or no fault</strong></td>
<td>33</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Depending on P1012.2, this output signal indicates whether</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The drive is ready (→ &quot;Ready&quot; message)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• No faults present (→ &quot;No fault&quot; message)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>if P1012.2 = &quot;1&quot;, the following is valid:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>if P1012.2 = &quot;0&quot;, the following is valid:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Signal</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>&quot;Ready&quot;</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Drive is ready</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Not ready</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Conditions</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>No faults are present</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>and</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>the board-specific pulse enable</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>is present (T. 663 = &quot;1&quot;)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>and</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>the drive-specific controller enable</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>is available (T. 65.x = &quot;1&quot;)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>and</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>the group-specific enable signals are</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>available (NE module, terminals 48, 63 and 64)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>and</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>the following PROFIBUS control signals</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>are available:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>independent of the control signals</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>STW1.0 = &quot;1&quot; (ON/OFF 1)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>STW1.1 = &quot;1&quot; (Operating condition/OFF 2)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>STW1.2 = &quot;1&quot; (Operating condition/OFF 3)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;no fault&quot; message is also transferred to the line supply infeed module (NE module, terminals 72, 73, 74).</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• From SW 6.1 and for P1012.12 = 1 a fault can also be acknowledged without STW1.0 = 0. However, the drive then remains in the &quot;Power-on inhibit&quot; state (refer to Chapter 5.5 &quot;Forming the power-on inhibit&quot;; Fig.5-9).</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Parking axis selected</strong></td>
<td>34</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>This output signal is used to indicate whether the axis &quot;parks&quot;.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>For a &quot;parking axis&quot;, all of the encoder-specific monitoring and evaluation functions are disabled. This allows the encoder to be withdrawn without initiating an alarm.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Parking axis selected</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Parking axis not selected</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
6.4 Input/output terminals of the control board

Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Open holding brake</td>
<td>35</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

A motor holding brake can be controlled using an external auxiliary contactor via an output with this function.

The brake sequence control is executed in the “SIMODRIVE 611 universal”.

1 signal  The auxiliary contactor for the motor holding brake is energized
0 signal  The auxiliary contactor is not energized

Note:
Refer to Chapter 6.9 for information on the motor holding brake.

Pulses enabled (from SW 3.1)  | 36       | x              | x            | MeldW.13     |

This output signal is used to display whether the motor control pulses for this drive are enabled or inhibited.

1 signal  The motor control pulses are enabled
0 signal  The pulses are inhibited

Application:
An armature short-circuit contactor may only be energized when the pulses are inhibited.
This signal can be evaluated as one of several conditions to control an armature short-circuit contactor.

Power module current not limited (from SW 3.1)  | 37       | x              | x            | MeldW.10     |

This output signal is used to display whether the power module current is limited via the $i^2t$ power module limiting.

1 signal  Power module current not limited
0 signal  Power module current is limited

Note:
The example is valid for the following motors:
1FT6, 1FK6, 1FNx

The "$i^2t$ power module limiting" function is described in Chapter A.2.
### 6.4 Input/output terminals of the control board

#### Table 6-50 List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Control via PROFIBUS (from SW 3.1)</td>
<td>38</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

The output terminal with this function can be controlled via PROFIBUS.

In this case, process data has to be configured, and then signal 50107 assigned to the PZD to be controlled in the setpoint telegram (digital outputs, terminals O0.x to O3.x, DIG_OUT).

The following definitions apply:

- **Assigning the function to the terminal**
- **Parameterizing the control using**
  - Term. O0.x
    - \( \rightarrow P0680 = 38 \) Bit 0 from PZD "DIG_OUT"
  - Term. O1.x
    - \( \rightarrow P0681 = 38 \) Bit 1 from PZD "DIG_OUT"
  - Term. O2.x
    - \( \rightarrow P0682 = 38 \) Bit 2 from PZD "DIG_OUT"
  - Term. O3.x
    - \( \rightarrow P0683 = 38 \) Bit 3 from PZD "DIG_OUT"

**Note:**
- P0699 (inverting output terminals) can be used to set the output signal inversion by the drive.
- Refer to Chapter 5.6.5 for information on configuring process data.

#### Status, block selection

<table>
<thead>
<tr>
<th>Status, block selection</th>
<th>1st output/2⁰</th>
<th>2nd output/2¹</th>
<th>3rd output/2²</th>
<th>4th output/2³</th>
<th>5th output/2⁴</th>
<th>6th output/2⁵</th>
<th>7th output/2⁶</th>
<th>8th output/2⁷</th>
</tr>
</thead>
<tbody>
<tr>
<td>(from SW 10.1)</td>
<td>50</td>
<td>x</td>
<td>x</td>
<td>AktSatz.0</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>51</td>
<td>x</td>
<td>x</td>
<td>AktSatz.1</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>52</td>
<td>x</td>
<td>x</td>
<td>AktSatz.2</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>53</td>
<td>x</td>
<td>x</td>
<td>AktSatz.3</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>54</td>
<td>x</td>
<td>x</td>
<td>AktSatz.4</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>55</td>
<td>x</td>
<td>x</td>
<td>AktSatz.5</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>56</td>
<td>x</td>
<td>x</td>
<td>AktSatz.6</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>(from SW 10.1)</td>
<td>57</td>
<td>x</td>
<td>x</td>
<td>AktSatz.7</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

These output signals are used to display which traversing block is being presently processed.

#### Block number

<table>
<thead>
<tr>
<th>Block number</th>
<th>0</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>...</th>
<th>31</th>
<th>...</th>
<th>63</th>
<th>255</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st output/weighting 2⁰</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
<td></td>
</tr>
<tr>
<td>2nd output/weighting 2¹</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>3rd output/weighting 2²</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>4th output/weighting 2³</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>5th output/weighting 2⁴</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>6th output/weighting 2⁵</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>...</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>7th output/weighting 2⁶</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>8th output/weighting 2⁷</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>...</td>
<td>0</td>
<td>1</td>
</tr>
</tbody>
</table>

#### Ready to be powered-up/not ready to be powered-up

<table>
<thead>
<tr>
<th>Ready to be powered-up/not ready to be powered-up</th>
<th>-</th>
<th>x</th>
<th>x</th>
<th>ZSW1.0</th>
</tr>
</thead>
</table>

The output signal indicates whether the drive is ready to be powered-up.

- **1 signal Ready to power-up**
  - In order that the drive goes into this state, the following conditions must be fulfilled:
    - the two operating conditions are available via STW1 (xxxx xxxx xxxx x1x)
    - the following enable signals are available: Terminal 63 (NE module), terminal 663
    - No fault present
    - No power-on inhibit present

- **0 signal Not ready to be powered-up**
  - The drive is not ready to be powered-up.
### List of Output Signals, Continued

<table>
<thead>
<tr>
<th>Signal Name, Description</th>
<th>Operating Mode n-set</th>
<th>Operating Mode pos</th>
<th>PROFIBUS Bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>No OFF 2 present/OFF 2 present</td>
<td>-</td>
<td>x</td>
<td>ZSW1.4</td>
</tr>
<tr>
<td>1 signal: No OFF 2 present</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal: OFF 2 present</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>No OFF 3 present/OFF 3 present</td>
<td>-</td>
<td>x</td>
<td>ZSW1.5</td>
</tr>
<tr>
<td>1 signal: No OFF 3 present</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal: OFF 3 present</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Power-on inhibit/no power-on inhibit</td>
<td>-</td>
<td>x</td>
<td>ZSW1.6</td>
</tr>
<tr>
<td>1 signal: Power-on inhibit</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>It is only possible to power-up the drive again using OFF 1 and then ON (STW1.0) (or withdrawing terminal 65.x).</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal: No power-on inhibit</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The &quot;power-on inhibit&quot; function can be disabled via P1012.12.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>No following error/following error</td>
<td>58</td>
<td>-</td>
<td>ZSW1.8</td>
</tr>
<tr>
<td>1 signal: No following error</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The actual following error is within the defined following error window, defined using P0318.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal: Following error</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The actual following error of the axis is outside the defined following error window.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Refer under the index entry &quot;Following error monitoring&quot;.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Spindle position reached (from SW 5.1)</td>
<td>59</td>
<td>X</td>
<td>MeldW.15</td>
</tr>
<tr>
<td>1 signal: The spindle has reached the target position within the tolerance window (P0134).</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal: The spindle has not reached the target position or alarms 131, 134 and 135 have occurred.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The &quot;spindle positioning&quot; function is described in Chapter 6.15 (from SW 5.1).</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Table 6-50 List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Control requested/no control possible</td>
<td>-</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>

The status of the DP slave is signaled to the DP master using this output signal.

1 signal Control requested
The DP master is requested to accept control.

**Recommendation:**
As a result of this output signal, the DP master should accept control and control bit STW1.10 "Control requested/not control requested" should be set to "1".

**Note:** (from SW 4.1)
For a two-axis drive, this bit is only influenced at axes which also retrieve data from a publisher via slave-to-slave communications (refer to Chapter 5.10).

0 signal Control not possible
The DP master is signaled that control is not possible. This is, for example, the case for the following states:
- the "DP slave 611U" has still not run-up
- the "SimoCom U" tool has taken-over the master control
- the clock-cycle synchron. PROFIBUS no longer operates with clock cycle synchronism
- for slave-to-slave communications, not all of the links have been established to the publisher (from SW 4.1)

Comparison value reached/comparison value not reached | - | x | - | ZSW1.10

The output signal indicates whether the comparison value, set using P1418:8, has been fallen below.

1 signal actual value > comparison value (P1418:8)
0 signal actual value < comparison value (P1418:8)

**Note:**
- The output signal corresponds to the \(| n_{act} | < n_{min} \) signal with inverted logic.
- In n-set operation, this signal occupies the PROFIBUS bit ZSW1.10 if spindle positioning has not been selected (from SW 5.1) (P0125 = 0). For the "spindle positioning" function (from SW 5.1), the "reference position reached/outside reference position" signal occupies ZSW1.10 (P0125 = 1), refer to output signal Function No. 60.
### 6.4 Input/output terminals of the control board

#### Table 6-50 List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Reference position reached/outside reference position</td>
<td>60</td>
<td>n-set</td>
<td>pos</td>
</tr>
<tr>
<td></td>
<td>x</td>
<td>-</td>
<td>x</td>
</tr>
</tbody>
</table>

This output signal is used to display, in the positioning mode (ZSW1.10), whether the axis has reached the end of the traversing block (position reference value = target position) and the position actual value lies within the positioning window (P0321).

In the n-set mode, MeldW.14 indicates that the reference position has been reached when positioning the spindle

<table>
<thead>
<tr>
<th>1 signal</th>
<th>Reference position reached</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>The axis/spindle is at the end of a traversing task and the positioning monitoring time (P0320) has expired within the positioning window (P0321).</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>0 signal</th>
<th>Outside the reference position</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>The axis/spindle is outside the positioning window.</td>
</tr>
</tbody>
</table>

**Note:**

- The signal is not set when the axis stops, if
  - the axis is in the closed-loop speed controlled jogging mode
  - an ongoing traversing block is interrupted or canceled using "intermediate stop" or "stop" which means that the target position has not been reached
- The signal remains set, until
  - a new traversing block is started
  - the axis is traversed in the jogging mode
  - a reference point approach is started
  - a fault (alarm) occurs (e.g. one of the monitoring windows P0318, P0321 or P0326) has been exceeded
- The signal remains set if a traversing block is re-started and there is no difference between the target position and the previous position.

#### Reference point set/no reference point set

<table>
<thead>
<tr>
<th>Reference point set/no reference point set</th>
<th>61</th>
<th>-</th>
<th>x</th>
<th>ZSW1.11</th>
</tr>
</thead>
</table>

The output signal indicates whether an axis is referenced.

When referencing, the incremental measuring system of the axis is synchronized with the drive.

<table>
<thead>
<tr>
<th>1 signal</th>
<th>Reference point set</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>The axis has a valid reference point.</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>0 signal</th>
<th>Reference point set</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>The axis does not have a valid reference point.</td>
</tr>
</tbody>
</table>

**Note:**

The following functions are not effective for an axis which is not referenced:

- Software limit switches
- Backlash compensation
- Start the traversing blocks
### Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Setpoint acknowledge</td>
<td>62</td>
<td>-</td>
<td>x</td>
</tr>
</tbody>
</table>

Using this output signal, the drive indicates that a new traversing tasks was accepted with the input signal "activate traversing task (edge)" and when this traversing task was executed.

- **1 signal** The traversing task is processed
  - The signal is set as soon as the traversing task in the drive is started with the "Activate traversing task" input signal.

- **0 signal** A traversing task is not being processed
  - After a traversing task has been completed and (from SW 2.4) the "activate traversing task (edge)" input signal has been reset, the output signal is again reset.
  - A new traversing task may be started via the "Activate traversing task (edge)" input signal.

#### Input signal "Activate traversing task (edge)"

<table>
<thead>
<tr>
<th>Signal</th>
<th>Operating mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal</td>
<td>On</td>
</tr>
<tr>
<td>0 signal</td>
<td>Off</td>
</tr>
</tbody>
</table>

#### Block processing

<table>
<thead>
<tr>
<th>Signal</th>
<th>Operating mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal</td>
<td>Short traversing blocks</td>
</tr>
<tr>
<td>0 signal</td>
<td>Long traversing blocks</td>
</tr>
</tbody>
</table>

**Example:**
- Short traversing blocks
- Long traversing blocks

**Note:**
- Refer to the input signal "Activate traversing task (edge)" in Chapter 6.4.3.

### Teach-in executed (from SW 4.1)

<table>
<thead>
<tr>
<th>Signal</th>
<th>Operating mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal</td>
<td>Teach-in function executed</td>
</tr>
<tr>
<td>0 signal</td>
<td>Function not executed</td>
</tr>
</tbody>
</table>

**Note:**
- Refer under the index entry "Input signal - activate teach-in (edge)"
- The "teach-in" function is described in Chapter 6.13.

### Drive stationary/drive moving

<table>
<thead>
<tr>
<th>Signal</th>
<th>Operating mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal</td>
<td>Drive stationary</td>
</tr>
<tr>
<td></td>
<td>The absolute actual speed is less than or equal to the threshold speed ( n_{\text{min}} ) ( \text{P1418:8} ).</td>
</tr>
<tr>
<td>0 signal</td>
<td>Drive is traversing</td>
</tr>
<tr>
<td></td>
<td>The absolute actual speed is greater than the threshold speed ( n_{\text{min}} ) ( \text{P1418:8} ).</td>
</tr>
</tbody>
</table>

**Note:**
- The function of the output signal \( |n_{\text{act}}| < n_{\text{min}} \) corresponds to this signal.
- This output signal cannot be used to identify whether the drive is crawling.
### Table 6-50 List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>First speed setpoint filter inactive</td>
<td>-</td>
<td>x x</td>
<td>ZSW2.3</td>
</tr>
</tbody>
</table>

The output signal specifies whether the first speed setpoint filter is active/inactive.
1 signal First speed setpoint filter is inactive - - > Low-pass filter is disabled
0 signal First speed setpoint filter is active - - > Low-pass filter is enabled

**Note:**
The first speed setp. filter can be enabled/disabled using the "first speed setpoint filter off" input signal.

<table>
<thead>
<tr>
<th>Ramp-function gen. inactive</th>
<th>-</th>
<th>x x</th>
<th>ZSW2.4</th>
</tr>
</thead>
</table>

The output signal specifies whether the ramp–function generator is active. The ramp–function generator can be switched–in/switched–out, e.g. using the input signal "Ramp–up time zero".
1 signal Ramp–function generator inactive
0 signal Ramp–function generator active

**Note:**
If the input signal STW2.4 = 0 is selected, then ZSW2.4 remains at 1 as long as the motor is stationary. ZSW2.4 only goes to zero when the motor is moving.

| Actual motor (from SW 2.4) | 1st signal | 2nd signal | - | x | - | ZSW2.9 | ZSW2.10 |
|-----------------------------|------------|------------|----------|----------------|----------|----------------|

These 2 status signals can be used to identify which motor/motor data set is selected.

<table>
<thead>
<tr>
<th>Motor data set</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
</tr>
</thead>
<tbody>
<tr>
<td>1st signal/ZSW2.9</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>2nd signal/ZSW2.10</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

**Note:**
- Motor changeover is described in Chapter 6.11.
- If, for P1249 = 1 a motor changeover was initiated via the input signals "motor data set changeover 1st input or 2nd input" and these output signals did not change, then P1013 (motor changeover) was incorrectly parameterized.

<table>
<thead>
<tr>
<th>Motor being changed over (from SW 3.3)</th>
<th>-</th>
<th>x</th>
<th>-</th>
<th>ZSW2.11</th>
</tr>
</thead>
</table>

The output signal indicates whether the motor is being changed over.
1 signal The motor is being changed over
   During this time, the drive pulses are canceled.
0 signal Otherwise

**Note:**
The "motor changeover for induction motors (from SW 2.4)" function is described in Chapter 6.11.
Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Slave sign-of-life (from SW 3.1)</td>
<td></td>
<td>n-set</td>
<td>pos</td>
</tr>
</tbody>
</table>

For the "Motion Control with PROFIBUS–DP" function, these status signals are used as sign-of-life (4-bit counter).

The sign-of-life counter is incremented from 1 to 15 and then starts again with the value 1. It only starts to count, if:

- The clock-cycle synchronous PROFIBUS operates in clock-cycle synchronism
- For slave-to-slave communications, all of the links between the publisher and subscriber have been established (from SW 4.1)

**Note:**
The "Motion Control with PROFIBUS–DP" function is described in Chapter 5.8. The "slave-to-slave communications" function is described in Chapter 5.10 (from SW 4.1).

<table>
<thead>
<tr>
<th>Suppress fault 608 active (from SW 3.1)</th>
<th></th>
<th></th>
<th></th>
<th>ZSW2.8</th>
</tr>
</thead>
<tbody>
<tr>
<td>This output signal is the checkback signal when suppressing fault 608 is activated via the input signal &quot;suppress fault 608&quot; (from SW 3.1).</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal Suppressing fault 608 is active (speed controller output limited)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal Suppressing fault 608 is not active</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- Suppressing fault 608 (speed controller output limited) can be activated as follows:
  - via an input terminal with function number 26
  - via the PROFIBUS control signal STW2.8
- Refer under the index entry "Input signal - suppressing fault 608 (from SW 3.1)"

<table>
<thead>
<tr>
<th>Travel to fixed stop active (from SW 3.3)</th>
<th>66</th>
<th></th>
<th></th>
<th>PosZsw.14</th>
</tr>
</thead>
<tbody>
<tr>
<td>This output signal is used to display whether the &quot;travel to fixed stop&quot; function is active.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal Block with the FIXED STOP command is being processed</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal No block with the FIXED STOP command is being processed</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
The "travel to fixed stop" function is described in Chapter 6.12.

<table>
<thead>
<tr>
<th>External block change (from SW 7.1)</th>
<th>67</th>
<th></th>
<th></th>
<th>AktSatz.14</th>
</tr>
</thead>
<tbody>
<tr>
<td>This output signal is used to display whether the &quot;External block change&quot; function is active.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The &quot;external block change&quot; function is selected.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The &quot;external block change&quot; function is canceled.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- This output signal is an image of the input signal "External block change" (Fct. No. 67 and STW1.13).
- When the edge of this output signal changes, this indicates that a block change has taken place, i.e. especially in the MDI mode, a new MDI block may now be entered via PZD and/or default block (refer to Chapter 6.2.12).
### Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fixed stop reached (from SW 3.3)</td>
<td>68</td>
<td>1-set</td>
<td>PosZsw.12</td>
</tr>
<tr>
<td>This output signal is used to display whether the drive is in the &quot;fixed stop reached&quot; status.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The drive is in the &quot;fixed stop reached&quot; status</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The drive is not in the &quot;fixed stop reached&quot; status</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;fixed stop reached&quot; status is assumed, dependent on the setting in P0114 (fixed stop, configuration 2).</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;travel to fixed stop&quot; function is described in Chapter 6.12.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Request passive referencing (from SW 5.1)</td>
<td>69</td>
<td>1-set</td>
<td>ZSW1.15</td>
</tr>
<tr>
<td>The master drive requests passive referencing for the slave drive, using this output signal.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>To realize this, this output signal must be logically interlocked with the input signal &quot;request passive referencing&quot; for the slave drive.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The master drive has detected its zero mark</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>This means that for the slave drive, the reference cam and zero mark search are activated While the signal is set, the slave axis must move over a zero mark otherwise an appropriate fault is signaled.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The master drive has reached its reference point</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• If, for a double-axis module P0891 (B) = 1, this means that the position actual value from drive A is internally connected to the position reference value of drive B, then the following applies:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>The output signal &quot;request passive referencing&quot; from drive A (master drive) is internally and automatically detected from drive B (slave drive). In this case, external wiring is not required.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;request passive referencing&quot; output signal is always output at the reference point approach when the zero mark has been recognized.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;passive referencing&quot; function is described in Chapter 6.3.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Follow-up mode active</td>
<td>70</td>
<td>1-set</td>
<td>PosZsw.0</td>
</tr>
<tr>
<td>This output signal is a checkback signal that the follow-up mode has been activated via the &quot;follow-up mode&quot; input signal.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal Follow-up mode active</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal Follow-up mode not active</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>If the follow-up mode is active as internal response to an error/fault, then this is also displayed using this input signal.</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 6-50 List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>In synchronism (from SW 3.3)</td>
<td></td>
<td></td>
<td>PosZsw.3</td>
</tr>
<tr>
<td>This output signal is used to display whether the slave drive is in synchronism with the master drive.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The slave drive is in synchronism with the master drive</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The slave drive is not in synchronism</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• When is a drive in synchronism</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>If, for an active axis coupling, the following error is less than the following error tolerance set in P0318.8.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>- - &gt; refer under the index entry &quot;Dynamic following error monitoring&quot;</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• For axis couplings in the &quot;positioning&quot; mode, the signal is not influenced by superimposed axis motion as a result of traversing blocks.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;axis coupling&quot; function is described in Chapter 6.3.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Setpoint static</td>
<td>72</td>
<td></td>
<td>PosZsw.2</td>
</tr>
<tr>
<td>This output signal indicates the processing status of a traversing block on the setpoint side.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The axis is stationary as far as the setpoint is concerned, i.e. the interpolator outputs the velocity setpoint 0.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal A traversing block is being processed in the interpolator, i.e. a velocity setpoint ≠ 0 is output.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• Together with the &quot;status block selection&quot; output signal, it can be defined as to which traversing block is being processed.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• This output signal is also supplied for the &quot;Jogging, incremental&quot; function.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• Refer under the index entry &quot;Positioning monitoring&quot;</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Fixed stop clamping torque reached</td>
<td>73</td>
<td></td>
<td>PosZsw.13</td>
</tr>
<tr>
<td>(from SW 3.3)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>This output signal displays whether the drive is in the &quot;fixed stop reached&quot; status and whether the programmed clamping torque has been reached.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The drive has provided the programmed clamping torque</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The drive provides less torque than the clamping torque</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;behavior, clamping torque not reached&quot; can be set using P0113.1.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The &quot;travel to fixed stop&quot; function is described in Chapter 6.12.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Axis moves forwards</td>
<td>74</td>
<td></td>
<td>PosZsw.4</td>
</tr>
<tr>
<td>Axis moves backwards</td>
<td>75</td>
<td></td>
<td>PosZsw.5</td>
</tr>
<tr>
<td>The actual direction of motion of the axis for an active traversing block is displayed using these output signals.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal The axis moves forwards or backwards</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal The axis does not move forwards or does not move backwards</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>If both signals = &quot;0&quot;, then no axis movement is active.</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 6.50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Minus software limit switch actuated</td>
<td>76</td>
<td>-</td>
<td>PosZsw.6</td>
</tr>
<tr>
<td>Plus software limit switch actuated</td>
<td>77</td>
<td>-</td>
<td>PosZsw.7</td>
</tr>
</tbody>
</table>

The traversing range of the axis can be defined using the software limit switches plus (P0316) and minus (P0315) (refer under the index entry “Software limit switch”).

The output signals indicate whether the appropriate software limit switch has been actuated.

- **1 signal**: The plus or minus software limit switch has been actuated
- **0 signal**: Neither the plus nor minus software limit switch has been actuated

![Diagram](image_url)

**Note:**

The software limit switches only become active after the axis has been referenced.
Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Cam switching signal 1</td>
<td>78</td>
<td>n-set</td>
<td>PosZsw.8</td>
</tr>
<tr>
<td>Cam switching signal 2</td>
<td>79</td>
<td>pos</td>
<td>PosZsw.9</td>
</tr>
</tbody>
</table>

For the “position–related switching signals (cams)” function, the simulated cam signal is output via these output signals.

**Cam switching signal 1**

1 signal  Position actual value $x_{act} \leq$ cam switching position 1 (P0310)
0 signal  Position actual value $x_{act} >$ cam switching position 1 (P0310)

**Cam switching signal 2**

1 signal  Position actual value $x_{act} \leq$ cam switching position 2 (P0311)
0 signal  Position actual value $x_{act} >$ cam switching position 2 (P0311)

Signal characteristics for a linear axis

<table>
<thead>
<tr>
<th>Signal</th>
<th>P0310</th>
<th>P0311</th>
<th>Actual position value</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal Cam switching</td>
<td></td>
<td></td>
<td>$x_{act}$ [mm]</td>
</tr>
<tr>
<td>signal 1</td>
<td></td>
<td></td>
<td>$x_{act} \leq$ P0310</td>
</tr>
<tr>
<td>0 signal Cam switching</td>
<td></td>
<td></td>
<td>$x_{act} &gt;$ P0310</td>
</tr>
<tr>
<td>signal 2</td>
<td></td>
<td></td>
<td>$x_{act} \leq$ P0311</td>
</tr>
<tr>
<td>0 signal Cam switching</td>
<td></td>
<td></td>
<td>$x_{act} &gt;$ P0311</td>
</tr>
</tbody>
</table>

Signal characteristics for a rotary axis with modulo correction (from SW 2.4)

<table>
<thead>
<tr>
<th>Signal</th>
<th>P0310</th>
<th>P0311</th>
<th>Actual position value</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 signal Cam switching</td>
<td></td>
<td></td>
<td>$x_{act}$ [degrees]</td>
</tr>
<tr>
<td>signal 1</td>
<td></td>
<td></td>
<td>$x_{act} &gt;$ P0310</td>
</tr>
<tr>
<td>0 signal Cam switching</td>
<td></td>
<td></td>
<td>$x_{act} \leq$ P0310</td>
</tr>
<tr>
<td>signal 2</td>
<td></td>
<td></td>
<td>$x_{act} &gt;$ P0311</td>
</tr>
<tr>
<td>0 signal Cam switching</td>
<td></td>
<td></td>
<td>$x_{act} \leq$ P0311</td>
</tr>
</tbody>
</table>

Note:
- Only after the axis has been referenced can it be guaranteed that the cam switching signals have a "true" position reference when they are output. This is the reason that an external AND logic operation must be established between the output signal "reference point set/no reference point set" and the output signals "cam switching signals 1, 2" (e.g. using an external PLC).
- The function "position–related switching signals (cams)” is described in Chapter 6.2.3.
### Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Fct. No.</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Direct output 1 via the traversing block</td>
<td>80</td>
<td>-</td>
<td>PosZsw.10</td>
</tr>
<tr>
<td>Direct output 2 via the traversing block</td>
<td>81</td>
<td>-</td>
<td>PosZsw.11</td>
</tr>
</tbody>
</table>

- For output terminals:
  - If an output is parameterized with this function, then this output can be set or reset from the traversing block using the SET_O or RESET_O command.
- For PROFIBUS- DP:
  - The status signals can be set or reset from the traversing block using the SET_O or RESET_O command.

**Note:**
- The following commands are used to set and reset output signals:
  - SET_O/RESET_O command and command parameter = 1 -> set/reset direct output 1
  - SET_O/RESET_O command and command parameter = 2 -> set/reset direct output 2
  - SET_O/RESET_O command and command parameter = 3 -> set/reset both signals
- Programming traversing blocks is described in Chapter 6.2.10.

<table>
<thead>
<tr>
<th>Velocity limiting active</th>
<th>82</th>
<th>-</th>
<th>PosZsw.1</th>
</tr>
</thead>
<tbody>
<tr>
<td>The output signal indicates whether the velocity is limited. The limiting is, for example, active if the programmed velocity is greater than the maximum velocity (P0102), taking into consideration the override.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>Velocity is limited</td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>Velocity is not limited</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

![Diagram](image)

**Note:**
- This signal is not output when jogging via velocity!

<table>
<thead>
<tr>
<th>MDI active (from SW 7.1)</th>
<th>83</th>
<th>-</th>
<th>AktSatz.15</th>
</tr>
</thead>
<tbody>
<tr>
<td>The output signal indicates whether the MDI function is operational.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>The MDI function is active.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>The MDI function is not active.</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Table 6-50  List of output signals, continued

<table>
<thead>
<tr>
<th>Signal name, description</th>
<th>Operating mode</th>
<th>PROFIBUS bit</th>
</tr>
</thead>
<tbody>
<tr>
<td>Angular incremental encoder handwheel active (from SW 8.1)</td>
<td>84</td>
<td>x</td>
</tr>
<tr>
<td>The output signal indicates whether the angular incremental encoder handwheel function is operational.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>The angular incremental encoder handwheel function is active.</td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>The angular incremental encoder handwheel function is not active.</td>
<td></td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 0 (from SW 8.1)</td>
<td>85</td>
<td>x</td>
</tr>
<tr>
<td>Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1)</td>
<td>86</td>
<td>x</td>
</tr>
<tr>
<td>These 2 status signals can be used to define which angular incremental encoder handwheel evaluation is selected via the following parameter.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Before SW 9.1: P0900:4</td>
<td></td>
<td></td>
</tr>
<tr>
<td>From SW 9.1: P0889:4</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Ang. incr. enc. hwh. eval.</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>Bit 0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>Bit 1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>Note:</td>
<td></td>
<td></td>
</tr>
<tr>
<td>The &quot;angular incremental encoder handwheel evaluation&quot; function is described in Chapter 6.8.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Block processing inactive (from SW 8.1)</td>
<td>87</td>
<td>x</td>
</tr>
<tr>
<td>The output signal indicates whether a traversing block has been processed.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>A traversing block has been completely processed.</td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>A traversing block is still being processed - even if the override is zero and motion has stopped.</td>
<td></td>
</tr>
<tr>
<td>Programmed velocity reached (from SW 11.1)</td>
<td>88</td>
<td>x</td>
</tr>
<tr>
<td>The output signal indicates whether a programmed velocity has been reached.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1 signal</td>
<td>The function is active in the pos mode under the following conditions:</td>
<td></td>
</tr>
<tr>
<td>• An &quot;Activate traversing task&quot; was given</td>
<td></td>
<td></td>
</tr>
<tr>
<td>• A velocity has been programmed</td>
<td></td>
<td></td>
</tr>
<tr>
<td>• Set velocity setpoint is constant</td>
<td></td>
<td></td>
</tr>
<tr>
<td>• The actual velocity lies within the tolerance window (P0117)</td>
<td></td>
<td></td>
</tr>
<tr>
<td>0 signal</td>
<td>The function is not active if the conditions specified under 1 signal are not fulfilled.</td>
<td></td>
</tr>
<tr>
<td>Note:</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Since the actual velocity does not equal 100% of the setpoint velocity due to physical influences, a tolerance window (P0117) has to be assigned to the actual speed. This avoids unnecessary switching on and off of the output signal.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>In jogging mode (Jogging 1, Jogging 2) or when faults occur (follow-up mode is active), the &quot;Programmed velocity reached&quot; output signal reacts like the &quot;ramp-up completed&quot; output signal (Fct. No. 2).</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
6.5 Input/output terminals for the optional TERMINAL module

**Description**

An optional TERMINAL module has 8 input and 8 output terminals, which can be freely parameterized (refer to Chapter 1.3.3).

A terminal is assigned any function by entering the function number corresponding to the required function into the parameter assigned to the terminal.

---

**Notice**

The terminals may only be parameterized when the drive pulses are canceled.

---

**Overview of the terminals and parameters**

The following assignment exists between the input/output terminals, drives and parameters:

Table 6-51 Terminals and parameters for the optional TERMINAL module

<table>
<thead>
<tr>
<th>Terminal Drive A/B</th>
<th>No.</th>
<th>Parameter</th>
<th>Min.</th>
<th>Std.</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Input terminals</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>I4</td>
<td>X422.1</td>
<td>0664</td>
<td>Function, input terminal I4</td>
<td>0</td>
<td>60</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I5</td>
<td>X422.2</td>
<td>0665</td>
<td>Function, input terminal I5</td>
<td>0</td>
<td>59</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I6</td>
<td>X422.3</td>
<td>0666</td>
<td>Function, input terminal I6</td>
<td>0</td>
<td>58</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I7</td>
<td>X422.4</td>
<td>0667</td>
<td>Function, input terminal I7</td>
<td>0</td>
<td>50</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I8</td>
<td>X422.5</td>
<td>0668</td>
<td>Function, input terminal I8</td>
<td>0</td>
<td>51</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I9</td>
<td>X422.6</td>
<td>0669</td>
<td>Function, input terminal I9</td>
<td>0</td>
<td>52</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I10</td>
<td>X422.7</td>
<td>0670</td>
<td>Function, input terminal I10</td>
<td>0</td>
<td>53</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>I11</td>
<td>X422.8</td>
<td>0671</td>
<td>Function, input terminal I11</td>
<td>0</td>
<td>54</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td><strong>Output terminals</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>O4</td>
<td>X432.1</td>
<td>0684</td>
<td>Signaling function output terminal O4</td>
<td>0</td>
<td>72</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>O5</td>
<td>X432.2</td>
<td>0685</td>
<td>Signaling function output terminal O5</td>
<td>0</td>
<td>60</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>O6</td>
<td>X432.3</td>
<td>0686</td>
<td>Signaling function output terminal O6</td>
<td>0</td>
<td>62</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>O7</td>
<td>X432.4</td>
<td>0687</td>
<td>Signaling function output terminal O7</td>
<td>0</td>
<td>50</td>
<td>82</td>
<td>-</td>
</tr>
<tr>
<td>O8</td>
<td>X432.5</td>
<td>0688</td>
<td>Signaling function output terminal O8</td>
<td>0</td>
<td>51</td>
<td>82</td>
<td>-</td>
</tr>
</tbody>
</table>
### Table 6-51 Terminals and parameters for the optional TERMINAL module, continued

<table>
<thead>
<tr>
<th>Terminal Drive A/B</th>
<th>No.</th>
<th>Name</th>
<th>Parameter</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>O9</td>
<td>0689</td>
<td>Signaling function output terminal O9</td>
<td>X432.6</td>
<td>0</td>
<td>52</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>O10</td>
<td>0690</td>
<td>Signaling function output terminal O10</td>
<td>X432.7</td>
<td>0</td>
<td>53</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>O11</td>
<td>0691</td>
<td>Signaling function output terminal O11</td>
<td>X432.8</td>
<td>0</td>
<td>54</td>
<td>82</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>Inversion, output terminal signals</td>
<td>0699</td>
<td>0</td>
<td>0</td>
<td>FFF</td>
<td>Hex</td>
<td>immediately</td>
</tr>
</tbody>
</table>

- **2<sup>0</sup> = 1**
  - Res. O8 O4
  - O0.x:
- **2<sup>1</sup> = 2**
  - Res. O9 O5
  - O1.x:
- **2<sup>2</sup> = 4**
  - Res. O10 O6
  - O2.x:
- **2<sup>3</sup> = 8**
  - Res. O11 O7
  - O3.x:

\[
P0699 = \begin{array}{ccc}
0 & 5 & 0 \\
6 & \text{hex} & \\
\end{array}
\]

Example: O10 O2.x are output inverted

Each input/output terminal can be assigned a function using these parameters.

**Note:**
- **Input terminals:**
  - The function number from the list of input signals is entered (refer to Chapter 6.4.3).
  - The status of the input terminals is displayed in P0678 for diagnostic purposes (refer to Chapter 4.5).
- **Output terminals:**
  - The function number from the list of output signals is entered (refer to Chapter 6.4.6).
  - The status of the output terminals is displayed in P0698 for diagnostics (refer to Chapter 4.5).
  - The signals of the output terminals can be output inverted (P0699).
- **Assignment of the terminals:**
  - Before SW 4.1 the following applies:
  - All of the input/output terminals for the optional TERMINAL module are permanently assigned drive A.
  - From SW 4.1, the following applies:
  - For a double-axis module, the input/output terminals can be assigned, blockwise to either drive A or B (P0676, P0696).
6.6 Analog inputs

Description

For "SIMODRIVE 611 universal", there are two analog inputs for each drive.

In the "speed/torque setpoint" mode, the setpoint can be entered for the following functions via these analog inputs:

- **Speed**: Speed-controlled operation ($n_{set}$ operation)

  For the $n_{set}$ mode, the analog voltage at terminal 56.x/14.x and/or terminal 24.x/20.x is used as speed setpoint.

- **Torque**: Open-loop torque controlled operation ($M_{set}$ mode)

  For the $M_{set}$ mode the analog voltage at terminal 56.x/14.x and/or terminal 24.x/20.x is used as torque setpoint.

  Open-loop torque control is used, if
  - the speed controller is implemented in a higher-level control, or
  - the master/slave functionality is used

- **Torque/power reduction ($M_{red}$ mode)**

  It may be necessary to reduce the maximum drive torque to protect the machine components. The following possibilities exist:
  - Permanent torque limiting
    This limit function can be set via parameters P1230 or P1235 (refer to Chapter 6.1.8).
  - Variable torque limiting
    In this case, analog input 2 is set to $M_{red}$ mode and the analog voltage at terminal 24.x/20.x is used to continuously reduce the torque.

In the "positioning" mode, a setpoint can be entered for the velocity override via analog input 1.
### 6.6.1 Basic setting of the analog inputs

The following functions can be assigned to analog input 1 and 2 of a drive using the appropriate parameterization:

#### Table 6-52 Parameters for the function of the analog inputs

<table>
<thead>
<tr>
<th>Analog input</th>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0607</td>
<td>Analog setpoint, terminal 56.x/14.x</td>
<td>0</td>
<td>1</td>
<td>2</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>56 x 14 x</td>
<td></td>
<td>The parameter defines whether and how the analog setpoint is used at this analog input.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>= 0 -- --&gt; off</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>= 1 -- --&gt; n_{set}/M_{set} mode (refer to Note)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>= 2 -- Velocity override (refer under the index entry &quot;Override&quot;)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>0612</td>
<td>Analog setpoint, terminal 24.x/20.x</td>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>24 x 20 x</td>
<td></td>
<td>The parameter defines whether and how the analog setpoint is used at this analog input.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>= 0 -- --&gt; off</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>= 1 -- --&gt; n_{set}/M_{set} mode (refer to Note)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>= 2 -- --&gt; M_{red} mode</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- \(x\): Space retainer for drive A or B
- \(n_{set}/M_{set}\) mode:
  It is always possible to toggle between \(n_{set}\) and \(M_{set}\) mode using the "open-loop torque controlled operation" input signal (refer to Chapter 6.4.2).
  - 0 signal: \(n_{set}\) mode
  - 1 signal: \(M_{set}\) mode

Input terminal I3.x is assigned, as standard, to the "open-loop torque controlled mode" signal.

When toggling between \(n_{set}\) and \(M_{set}\) mode, it should be noted, that a setpoint, which may be present at the terminals, becomes immediately effective in the other operating mode.
6.6.2 \( n_{set} \) mode or \( n_{set} \) with \( M_{\text{red}} \) mode

\textbf{\( n_{set} \) mode via term.} 56.x/14.x and/or term. 24.x/20.x

The voltage for the speed setpoint is dependent on the parameterization of the analog inputs and can comprise the voltage at terminal 56.x/14.x and/or terminal 24.x/20.x as well as the appropriate offset corrections and inversions (refer to Fig. 6-62).

Requirements:

- "Open-loop torque controlled operation" input signal = 0 signal
- P0607 P0612 Speed setpoint via
  \[= 1 = 1 \quad \text{T.} \quad 56.x/14.x \quad \text{and} \quad \text{T.} \quad 24.x/20.x\]
  \[= 0 = 1 \quad \text{T.} \quad 24.x/20.x\]
  \[= 1 = 0 \quad \text{T.} \quad 56.x/14.x\]

![Diagram showing the setup of \( n_{set} \) mode with analog inputs and offsets.]

Fig. 6-62  Closed-loop speed control via terminal 56.x/14.x and/or terminal 24.x/20.x
6.6 Analog inputs

**Requirements:**

- "Open-loop torque controlled operation" input signal = 0 signal
- P0607 = 1 Speed setpoint via terminal 56.x/14.x
- P0612 = 2 Setpoint for \( M_{\text{red}} \) via terminal 24.x/20.x

---

### Reader’s note

The torque/power reduction via terminal 24.x/20.x is described in Chapter 6.6.4.
### Parameter overview

The following parameters are available to parameterize the \( n_{\text{set}} \) mode using terminal 56.x/14.x and/or terminal 24.x/20.x:

#### Table 6-53 Parameters for the \( n_{\text{set}} \) mode

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0606</td>
<td>Voltage at terminals 56.x/14.x</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>V(pk)</td>
<td>RO</td>
</tr>
<tr>
<td>0611</td>
<td>Voltage at terminals 24.x/20.x</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>V(pk)</td>
<td>RO</td>
</tr>
<tr>
<td></td>
<td>... indicates the analog voltage presently available at this input terminal.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0608</td>
<td>Inversion, terminal 56.x/14.x</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>0613</td>
<td>Inversion, terminal 24.x/20.x</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

An inversion internally inverts the sign of the analog setpoint at this terminal. The motor direction of rotation is reversed.

0  No inversion
1  Inversion

There is the following assignment between inversion, direction of rotation, and setpoint:
- Without inversion, the motor rotates clockwise for a positive setpoint
- With inversion, the motor rotates anti-clockwise for a positive setpoint

Definition of the direction of rotation:
- When viewing the output shaft, the shaft rotates counter-clockwise → The motor direction of rotation is counter-clockwise
- When viewing the output shaft, the shaft rotates clockwise → The motor direction of rotation is clockwise

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0609</td>
<td>Smoothing time, terminal 56.x/14.x (SRM, SLM) (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td>0614</td>
<td>Smoothing time, terminal 24.x/20.x (SRM, SLM) (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
</tbody>
</table>

This allows the output of the A/D converter to be smoothed using a PT₁ filter.

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0610</td>
<td>Drift/offset correction terminal 56.x/14.x</td>
<td>-9999.9</td>
<td>0.0</td>
<td>9999.9</td>
<td>mV(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td>0615</td>
<td>Drift/offset correction terminal 24.x/20.x</td>
<td>-9999.9</td>
<td>0.0</td>
<td>9999.9</td>
<td>mV(pk)</td>
<td>immediately</td>
</tr>
</tbody>
</table>

If the motor still continues to turn even with a speed setpoint of 0 V, and this is not desired, then this parameter can be used to enter a voltage offset to adjust the analog input for zero output.
Table 6-53  Parameters for the \( n_{\text{set}} \) mode, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0618</td>
<td>Normalization voltage speed setpoint</td>
<td>5.0</td>
<td>9.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td>1401:8</td>
<td>Speed for max. useful motor speed (SRM, ARM)</td>
<td>~100 000.0</td>
<td>0.0</td>
<td>100 000.0</td>
<td>RPM m/min</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Velocity for max. motor useful velocity (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P0618:</td>
<td>This defines the input voltage at which the maximum useful motor speed is reached.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>P1401:8:</td>
<td>The parameter specifies the maximum motor useful speed, and represents the reference value for P0618.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The standard value is pre-assigned for the hardware configuration depending on the motor used.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Example:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P0618 = 9</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>P1401:8 = 2000</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>--&gt; at 9 V, the motor reaches a speed of 2000 RPM</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
The maximum useful motor speed, set using P1401:8 is taken into account when calculating the speed setpoint. This means that P1401:8 acts as a speed limit.

This is independent of whether the setpoint is entered via a terminal or PROFIBUS.

| 1240:8| Offset, torque setpoint (closed-loop speed controlled) (SRM, ARM)           | ~50 000.0 | 0.0 | 50 000.0 | Nm N | immediately |
|       | Offset, force setpoint (closed-loop speed controlled) (SLM)                  |       |      |        |     |           |
|       | This parameter value is added to the torque setpoint or force setpoint (SLM). |     |      |        |     |           |

**Note:**
This allows a weight equalization to be set.

| 0620  | For the torque/power reduction via terminal 24.x/20.x (refer to Chapter 6.6.4), this parameter can be used to make adjustments. |     |      |        |     |           |
6.6.3  \( M_{\text{set}} \) mode or \( M_{\text{set}} \) with \( M_{\text{red}} \) mode

\( M_{\text{set}} \) mode via terminal 56.x/14.x and/or term. 24.x/20.x

The analog torque setpoint \( M_{\text{set analog}} \) is dependent on the parameterization of the analog inputs and can comprise the voltage at terminal 56.x/14.x and/or terminal 24.x/20.x as well as the offset correction, inversions and the torque setpoint offset (refer to Fig. 6-64).

Requirements:

- "Open-loop torque controlled operation" input signal = 1 signal
- \( P0607 \) \( P0612 \) Torque setpoint via
  - \( = 1 \) \( = 1 \) T. 56.x/14.x and T. 24.x/20.x
  - \( = 0 \) \( = 1 \) T. 24.x/20.x
  - \( = 1 \) \( = 0 \) T. 56.x/14.x

Fig. 6-64  Open-loop torque control via terminal 56.x/14.x and/or terminal 24.x/20.x

Note

Before SW 4.2:
The setpoint for \( M_{\text{set}} \) operation can only be entered via analog inputs (terminals). It is not possible to enter a setpoint via PROFIBUS.

From SW 4.2:
The setpoint for \( M_{\text{set}} \) operation can either be entered via analog inputs (terminals) or PROFIBUS-DP.
### M_set mode via term. 56.x/14.x and M_red mode via term. 24.x/20.x

**Requirements:**

- "Open-loop torque controlled operation" input signal = 1 signal
- P0607 = 1 Torque setpoint via terminal 56.x/14.x
- P0612 = 2 Setpoint for M_red via terminal 24.x/20.x

---

**Reader’s note**

The torque/power reduction via terminal 24.x/20.x is described in Chapter 6.6.4.
Parameter overview

The following parameters are provided to parameterize the $M_{\text{set}}$ mode using terminal 56.x/14.x and/or terminal 24.x/20.x:

Table 6-54  Parameter for $M_{\text{set}}$ mode using terminal 56.x/14.x and/or terminal 24.x/20.x

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0606</td>
<td>Voltage at terminals 56.x/14.x</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>V(pk)</td>
<td>RO</td>
</tr>
<tr>
<td>0611</td>
<td>Voltage at terminals 24.x/20.x</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>V(pk)</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates the analog voltage presently available at this input terminal.

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0608</td>
<td>Inversion, terminal 56.x/14.x</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>0613</td>
<td>Inversion, terminal 24.x/20.x</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

An inversion internally inverts the sign of the analog setpoint at this terminal. This causes the torque to be reversed.

1  Inversion
0  No inversion

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0609</td>
<td>Smoothing time, terminal 56.x/14.x (SRM, SLM) (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td>0614</td>
<td>Smoothing time, terminal 24.x/20.x (SRM, SLM) (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
</tbody>
</table>

This allows the output of the A/D converter to be smoothed using a PT1 filter.

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0610</td>
<td>Drift/offset correction terminal 56.x/14.x</td>
<td>-9 999.9</td>
<td>0.0</td>
<td>9 999.9</td>
<td>mV(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td>0615</td>
<td>Drift/offset correction terminal 24.x/20.x</td>
<td>-9 999.9</td>
<td>0.0</td>
<td>9 999.9</td>
<td>mV(pk)</td>
<td>immediately</td>
</tr>
</tbody>
</table>

If, for a setpoint input of 0 volt, the motor starts to rotate, and this is not desired, then a voltage offset can be entered using this parameter to adjust the analog input for zero output.

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0619</td>
<td>Normalization voltage, torque setpoint</td>
<td>5.0</td>
<td>10.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td>1241:8</td>
<td>Normalization, torque setpoint (SRM, ARM) Normalization, force setpoint (SLM)</td>
<td>1.0</td>
<td>10.0</td>
<td>50 000.0</td>
<td>Nm</td>
<td>immediately</td>
</tr>
</tbody>
</table>

P0619: This defines at which input voltage the torque setpoint normalization is reached.
P1241:8: The parameter represents the reference value for P0619. The standard value for $M_{\text{rated}}$ is pre-assigned “calculate controller data”.

Standard values:
P0619 = 10
P1241:8 = $M_{\text{rated}}$
-- at 10 V, $M_{\text{rated}}$ is reached
Table 6-54 Parameter for $M_{\text{set}}$ mode using terminal 56.x/14.x and/or terminal 24.x/20.x, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1242:8</td>
<td>Offset torque setpoint (open-loop torque controlled) (SRM, ARM)</td>
<td>-50 000.0</td>
<td>0.0</td>
<td>50 000.0</td>
<td>Nm</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Offset force setpoint (open-loop torque controlled) (SLM)</td>
<td>0.0</td>
<td>0.0</td>
<td>50 000.0</td>
<td>N</td>
<td></td>
</tr>
</tbody>
</table>

This parameter value is added to the torque setpoint or force setpoint (SLM).

Note: Thus, a pre-tensioning torque can be generated.

0620

1243:8 For the torque/power reduction via terminal 24.x/20.x (refer to Chapter 6.6.4), this parameter can be used to make adjustments.

1244

6.6.4 Torque/power reduction via terminal 24.x/20.x

Description A continuous torque/power reduction ($M_{\text{red}}$ mode) is possible via analog input 2 (terminal 24.x/20.x) by entering an analog voltage.

The reduction is:

- In the constant torque range, referred to the 1st torque limit (P1230)
- Constant power range referred to the first power limit (P1235)

Characteristics to reduce the torque/power

The following characteristics can be set, as a function of parameter P1244, using the setpoint from terminal 24.x/20.x:

- Negative characteristic (P1244 = 1)
  - Application
    - For wire breakage, the input voltage is 0 V
    - The limits for the torque/power are effective, defined with the normalization (maximum values)
    - This case is suitable for applications which require a torque when a fault occurs (e.g. hanging axes)

- Positive characteristic (P1244 = 2)
  - Application
    - For a wire breakage, a 0 V input voltage becomes effective
    - There is no torque/power
    - This case is suitable for applications which do not require torque under fault/error conditions
## 6.6 Analog inputs

The following parameters are available to parameterize the $M_{red}$ mode using terminal 24.x/20.x:

### Table 6-55 Parameter for the $M_{red}$ mode

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0611</td>
<td>Voltage at terminals 24.x/20.x</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>V(pk)</td>
<td>RO</td>
</tr>
<tr>
<td>0613</td>
<td>Inversion, terminal 24.x/20.x</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>0614</td>
<td>Smoothing time, terminal 24.x/20.x (SRM, SLM)</td>
<td>0.0</td>
<td>0.0</td>
<td>3.0</td>
<td>1 000.0</td>
<td>ms</td>
</tr>
<tr>
<td>0615</td>
<td>Drift/offset correction terminal 24.x/20.x</td>
<td>-9 999.9</td>
<td>0.0</td>
<td>9 999.9</td>
<td>mV(pk)</td>
<td>immediately</td>
</tr>
</tbody>
</table>

**Note:**

These parameters are described in Chapter 6.6.3.

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0620</td>
<td>Normalization voltage, torque/power reduction (SRM, ARM)</td>
<td>5.0</td>
<td>10.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td>1243:8</td>
<td>Normalization, torque/power reduction (SRM, ARM)</td>
<td>0.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>immediately</td>
</tr>
</tbody>
</table>

**Example:**

For the torque/power reduction, internally only positive setpoints are effective. For a negative analog setpoint at terminal 24.x/20.x, an inversion function must be switched-in.

**Note:**

The actual reduction is displayed in P1717.
Table 6-55  Parameter for the \( M_{red} \) mode, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1244</td>
<td>Characteristic type, torque/power reduction (SRM, ARM)</td>
<td>1</td>
<td>1</td>
<td>2</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Characteristic type, force/power reduction (SLM)</td>
<td>1</td>
<td>1</td>
<td>2</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... defines whether the reduction is realized with a negative or a positive characteristic.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 Negative characteristic</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 2 Positive characteristic</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1259</td>
<td>Torque/power reduction mot./gen. (SRM, ARM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>Force/power reduction mot./gen. (SLM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... defines how the torque/power reduction or force/power reduction is effective depending on the state motoring/regenerating.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 0 Reduction is effective, motoring and generating</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 Reduction is only effective motoring</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>In an emergency situation, the axis can still be quickly braked for P1259 = 1.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
6.6.5 Application example master/slave

The master/slave functionality is implemented using the analog inputs/outputs.

The master enters the torque setpoint for the slave via an analog output (terminals 75.x/15 or 16.x/15). Refer to Chapter 6.7).

**Note**

Master/slave operation is only possible for motors with encoders!

---

**Warning**

If, for a master/slave configuration, the rigid mechanical coupling is released (the coupling is opened) then at the same time the slave drive must be changed over to $n_{set}$ operation as otherwise the slave drive would accelerate in an uncontrolled fashion to the maximum speed.
Example: Settings for the master drive

The following settings are necessary for the master drive:

- Setting the analog output
  Term. 75.x/15  P0626 = 36 (torque setpoint (finely normalized))
  P0627 = 0 (shift factor)
  P0631 = 1 (overcontrol protection on)
  Term. 16.x/15  P0633 = 36 (torque setpoint (finely normalized))
  P0634 = 0 (shift factor)
  P0638 = 1 (overcontrol protection on)

- Set DAU (D/A converter) normalization
  P0625 = 50  \(\rightarrow +5 \text{ V} \approx \text{twice the rated torque}\)

Example: Settings for the slave drive

For the slave drives the following settings are necessary:

- Set the analog input
  Terminal 56.x/14.x  P0607 = 1 (\(n_{\text{set}}/M_{\text{set}}\) mode)
  Terminal 24.x/20.x  P0612 = 1 (\(n_{\text{set}}/M_{\text{set}}\) mode)

- Set the normalization
  P0619 = 5  (normalization voltage, torque setpoint)
  P1241 = rated torque, slave-motor
    (normalization, torque setpoint)

- Set the digital input
  Function number = 4  (open-loop torque controlled mode)
  Terminal on the control board  \(\rightarrow\) refer to Chap. 6.4.2
  Terminal on the optional TERMINAL module  \(\rightarrow\) refer to Chap. 6.5
6.7 Analog outputs

Description

There are two freely parameterizable analog outputs with the following features for each drive:

- Resolution of the DAU (D/A converter): 8 bit
- Rated operating voltage: -10 V to +10 V
- Update: in the speed controller clock cycle (P1001)
### Parameter overview

The following parameters are available to parameterize the analog outputs:

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Parameter</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0626</td>
<td></td>
<td>Signal number analog output terminals 75.x/15</td>
<td>0</td>
<td>34</td>
<td>530</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td></td>
<td>... defines which signal is output. In this case, the appropriate signal number must be entered from the &quot;signal selection list for analog output&quot; (refer to Table 6-57).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0627</td>
<td></td>
<td>Shift factor analog output terminals 75.x/15</td>
<td>0</td>
<td>0</td>
<td>47</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td></td>
<td>... defines the shift factor, with which the output signal is manipulated (refer to Fig. 6-69). Only an 8 bit output window can be output from a 24/48 bit signal due to the 8-bit resolution. The shift factor can be used to define which 8 of the 24/48 bits are located in the output window and should be output. A shift factor for each signal is recommended in the signal selection list for analog outputs (refer to Table 6-57).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0628</td>
<td></td>
<td>Offset analog output terminal 75.x/15</td>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td></td>
<td>... specifies an offset to the 8-bit output signal. ( \text{Note:} )</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>* The signal to be output is shifted by 20/256 V (78 mV) by changing the offset by 1 digit.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>* P0628 = -128 ( \Rightarrow ) -10 V, P0628 = 127 ( \Rightarrow ) +10 V</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0631</td>
<td></td>
<td>Overcontrol protection analog output, terminal 75.x/15</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td></td>
<td>... switches the over-control protection on or off.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>( = 1 ) Overcontrol protection on (standard) The bits above the 8-bit wide window cause +10 V or -10 V to be output, i.e. the output is not overcontrolled.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>( = 0 ) Over-control protection off The bits above the 8-bit wide window are ignored. The analog value is exclusively defined by the 8-bit window, i.e. the output can be overcontrolled.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>0632</td>
<td></td>
<td>Smoothing time analog output terminal 75.x/15</td>
<td>0.0</td>
<td>0.0</td>
<td>1 000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
</tbody>
</table>
|              |             | ... smooths the output signal with a 1st order proportional element (PT1 element, low-pass filter). The filter is de-activated with P0632 = 0.0. The following generally applies: low smoothing time \( \Rightarrow \) low smoothing effect high smoothing time \( \Rightarrow \) high smooth effect
### Table 6-56 Parameter overview for the analog outputs, continued

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>Parameter</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>16.A</td>
<td>X441.2</td>
<td>Signal number</td>
<td>0633</td>
<td>analog output terminals 16.x/15</td>
<td>0</td>
<td>35</td>
<td>530</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>X441.4</td>
<td>Shift factor</td>
<td>0634</td>
<td>analog output terminals 16.x/15</td>
<td>0</td>
<td>0</td>
<td>47</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>16.B</td>
<td>X441.5</td>
<td>Offset analog output terminal</td>
<td>0635</td>
<td>16.x/15</td>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td>15</td>
<td>X441.5</td>
<td>Overcontrol protection,</td>
<td>0638</td>
<td>analog output terminal 16.x/15</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>X441.5</td>
<td>Smoothing time</td>
<td>0639</td>
<td>analog output terminal 16.x/15</td>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
</tbody>
</table>

#### Signal No. 34

### DAU normalization, speed actual value (SRM, ARM)

### DAU normalization, actual motor velocity (SLM)

... defines, for the output of "absolute motor speed, finely normalized" (Signal No. 34), which voltage is output at the maximum speed $n_{\text{max}}$.

The maximum speed $n_{\text{max}}$ is given by:

for SRM: minimum (1.2 x P1400, P1147)

for ARM/SLM: minimum (P1146, P1147)

#### Examples:

- P0623 = 100% $\Rightarrow$ +10 V $\doteq n_{\text{max}}$
- P0623 = 50% $\Rightarrow$ +5 V $\doteq n_{\text{max}}$
- P0623 = 200% $\Rightarrow$ +10 V $\doteq 0.5 n_{\text{max}}$
- P0623 = -50% $\Rightarrow$ -5V $\doteq n_{\text{max}}$
### Table 6-56 Parameter overview for the analog outputs, continued

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>0624</td>
<td>DAU normalization, motor utilization</td>
<td>-200.0</td>
<td>100.0</td>
<td>200.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<td></td>
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<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

... defines, for the output of "utilization (M_set/M_set, limit, finely normalized" (Signal No. 35) which voltage is obtained when
- | maximum torque | (at n = 0 to n_{rated})
- | power | (at n > n_{rated}).

Examples:
P0624 = 100 % -> +10 V = Max. torque or power
P0624 = 50 % -> +5 V = Max. torque or power

<table>
<thead>
<tr>
<th>Terminal No.</th>
<th>Designation</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>0625</td>
<td>D/A normalization, torque setpoint (SRM, ARM)</td>
<td>-200.0</td>
<td>100.0</td>
<td>200.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>D/A normalization, force setpoint (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

... defines for the output of "torque setpoint, finely normalized" (Signal No. 36), which voltage is output when 200% rated torque is reached.

Examples:
P0625 = 100 % -> +10 V = twice the rated torque
P0625 = 50 % -> +5 V = twice the rated torque

**Note:**
The output of signal No. 36 is signed.
### Signal selection list for analog output

Table 6-57  Signal selection list for analog outputs

<table>
<thead>
<tr>
<th>No.</th>
<th>Signal Designation</th>
<th>Operating mode</th>
<th>Displayed in</th>
<th>Shift factor</th>
<th>Bit width</th>
<th>Unit</th>
<th>Normalization (corresponds to LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>No signal</td>
<td>x x</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>1</td>
<td>Physical address</td>
<td>x x</td>
<td>-</td>
<td>0</td>
<td>24</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>Current actual value, phase U</td>
<td>x x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μA pak</td>
<td>P1710</td>
</tr>
<tr>
<td>3</td>
<td>Current actual value, phase V</td>
<td>x x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μA pak</td>
<td>P1710</td>
</tr>
<tr>
<td>4</td>
<td>Field-generating current actual value Iq</td>
<td>x x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μA pak</td>
<td>P1710</td>
</tr>
<tr>
<td>5</td>
<td>Torque-generating current actual value Iq</td>
<td>x x</td>
<td>x</td>
<td>P1708 (%)</td>
<td>4</td>
<td>24</td>
<td>μA pak P1710</td>
</tr>
<tr>
<td>6</td>
<td>Current setpoint Iq (limited after the filter)</td>
<td>x x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μA pak</td>
<td>P1710</td>
</tr>
<tr>
<td>7</td>
<td>Current setpoint Iq (before filter)</td>
<td>x x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μA pak</td>
<td>P1710</td>
</tr>
<tr>
<td>8</td>
<td>Speed actual value, motor (SRM, ARM)</td>
<td>x x</td>
<td>x</td>
<td>P0602</td>
<td>6</td>
<td>24</td>
<td>RPM m/min P1711</td>
</tr>
<tr>
<td></td>
<td>Velocity actual value, motor (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>Speed setpoint (SRM, ARM)</td>
<td>x x</td>
<td>x</td>
<td>P0601 (only for controller enable)</td>
<td>6</td>
<td>24</td>
<td>RPM m/min P1711</td>
</tr>
<tr>
<td></td>
<td>Velocity setpoint (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>10</td>
<td>Speed setpoint, reference model (SRM, ARM)</td>
<td>x x</td>
<td>-</td>
<td>6</td>
<td>24</td>
<td>RPM m/min P1711</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Velocity setpoint, reference model (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>11</td>
<td>Torque setpoint (speed controller output) (SRM, ARM)</td>
<td>x x</td>
<td>x</td>
<td>P1716</td>
<td>4</td>
<td>24</td>
<td>μNm P1713</td>
</tr>
<tr>
<td></td>
<td>Force setpoint (speed controller output) (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>12</td>
<td>Torque setpoint limit (pos.) (SRM, ARM)</td>
<td>x x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μNm</td>
<td>P1713</td>
</tr>
<tr>
<td></td>
<td>Force setpoint limit (pos.) (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>13</td>
<td>Motor utilization max (Mset/Mmax, Pset/Pmax)</td>
<td>x x</td>
<td>x</td>
<td>P0604</td>
<td>8</td>
<td>16</td>
<td>% 8000H ≡ 100%</td>
</tr>
<tr>
<td>14</td>
<td>Active power</td>
<td>x x</td>
<td>-</td>
<td>12</td>
<td>16</td>
<td>kW</td>
<td>0.01 kW</td>
</tr>
<tr>
<td>15</td>
<td>Rotor flux setpoint</td>
<td>x x</td>
<td>-</td>
<td>1</td>
<td>24</td>
<td>μVs</td>
<td>P1712</td>
</tr>
<tr>
<td>16</td>
<td>Rotor flux actual value</td>
<td>x x</td>
<td>-</td>
<td>1</td>
<td>24</td>
<td>μVs</td>
<td>P1712</td>
</tr>
</tbody>
</table>
### Table 6-57  Signal selection list for analog outputs, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Signal</th>
<th>Designation</th>
<th>Operating mode</th>
<th>Displayed in</th>
<th>Shift factor</th>
<th>Bit width</th>
<th>Unit</th>
<th>Normalization (corresponds to LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>17</td>
<td>Quadrature voltage $V_q$</td>
<td>x x -</td>
<td>11 24</td>
<td>V</td>
<td>P1709 • VDC link/2</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>18</td>
<td>Direct-axis voltage $V_d$</td>
<td>x x -</td>
<td>11 24</td>
<td>V</td>
<td>P1709 • VDC link/2</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>19</td>
<td>Current setpoint $I_d$</td>
<td>x x 4</td>
<td>24</td>
<td>$\mu A_{pk}$</td>
<td>P1710</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>20</td>
<td>Motor temperature</td>
<td>x x P0603</td>
<td>13 24</td>
<td>°C</td>
<td>0.1 °C</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>21</td>
<td>DC link voltage at the NE module</td>
<td>x x P1701</td>
<td>13 24</td>
<td>V</td>
<td>1 V</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>22</td>
<td>Zero mark signal, motor measuring system</td>
<td>x x -</td>
<td>17 16</td>
<td>-</td>
<td>-</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>23</td>
<td>Zero mark signal, equivalent zero mark (bit 11, inverted)</td>
<td>x x -</td>
<td>12 16</td>
<td>-</td>
<td>-</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>24</td>
<td>Absolute speed actual value (SRM, ARM)</td>
<td>x x -</td>
<td>6 24</td>
<td>RPM</td>
<td>P1711</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Absolute velocity actual value (SLM)</td>
<td>x x -</td>
<td>6 24</td>
<td>m/min</td>
<td>P1711</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>25</td>
<td>Slip frequency setpoint</td>
<td>x x -</td>
<td>8 24</td>
<td>1/s</td>
<td>$2000 \times 2\Pi \times 800000H \times 1s$</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>26</td>
<td>Zero mark signal, direct measuring system</td>
<td>x x -</td>
<td>17 24</td>
<td>-</td>
<td>-</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>27, 28</td>
<td>Reserved</td>
<td>- - -</td>
<td>- - -</td>
<td>-</td>
<td>-</td>
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<tr>
<td>29</td>
<td>Control voltage $Q$ feedforward control</td>
<td>x x -</td>
<td>11 24</td>
<td>V</td>
<td>P1709 • VDC link/2</td>
<td></td>
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</tr>
<tr>
<td>30</td>
<td>Control voltage $D$ feedforward control</td>
<td>x x -</td>
<td>11 24</td>
<td>V</td>
<td>P1709 • VDC link/2</td>
<td></td>
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<tr>
<td>31</td>
<td>Normalized, electrical rotor position (10 000 hex = 360°)</td>
<td>x x -</td>
<td>7 24</td>
<td>Degrees</td>
<td>-</td>
<td></td>
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<td></td>
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<tr>
<td>32</td>
<td>Absolute voltage setpoint</td>
<td>x x P1705</td>
<td>11 24</td>
<td>V</td>
<td>P1709</td>
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<tr>
<td>33</td>
<td>Absolute current actual value</td>
<td>x x P1719</td>
<td>4 24</td>
<td>$\mu A_{pk}$</td>
<td>P1710</td>
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<tr>
<td>34</td>
<td>Absolute speed actual value (finely normalized) (SRM, ARM)</td>
<td>x x 0</td>
<td>24</td>
<td>RPM</td>
<td>P1740</td>
<td></td>
<td></td>
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<tr>
<td></td>
<td>Absolute velocity actual value (finely normalized) (SLM)</td>
<td>x x 0</td>
<td>24</td>
<td>m/min</td>
<td>P1740</td>
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<td>Note: P0623 is the reference</td>
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<td>35</td>
<td>Utilization (finely normalized)</td>
<td>x x -</td>
<td>0 24</td>
<td>%</td>
<td>P1741</td>
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<td>Note: P0624 is the reference</td>
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### 6.7 Analog outputs

#### Table 6-57  Signal selection list for analog outputs, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Designation</th>
<th>Operating mode</th>
<th>Displayed in</th>
<th>Shift factor</th>
<th>Bit width</th>
<th>Unit</th>
<th>Normalization (corresponds to LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>36</td>
<td>Torque setpoint (finely normalized) (SRM, ARM)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>0</td>
<td>24</td>
<td>μNm</td>
</tr>
<tr>
<td></td>
<td>Force setpoint (finely normalized) (SLM)</td>
<td></td>
<td></td>
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<td></td>
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</tr>
<tr>
<td></td>
<td>Note: P0625 is the reference</td>
<td></td>
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<tr>
<td>37</td>
<td>Speed setpoint at terminals 56.x/14.x, 24.x/20.x (SRM, ARM)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>6</td>
<td></td>
<td>RPM</td>
</tr>
<tr>
<td></td>
<td>Velocity setpoint at terminals 56.x/14.x, 24.x/20.x (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>m/min</td>
</tr>
<tr>
<td>38</td>
<td>Signal DAU1 from PROFIBUS-PPO</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>0</td>
<td>16</td>
<td>-</td>
</tr>
<tr>
<td>39</td>
<td>Signal DAU2 from PROFIBUS-PPO</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>0</td>
<td>16</td>
<td>-</td>
</tr>
<tr>
<td>40</td>
<td>Speed setpoint from PROFIBUS PPO (SRM, ARM)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>6</td>
<td>24</td>
<td>RPM</td>
</tr>
<tr>
<td></td>
<td>Velocity setpoint from PROFIBUS PPO (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>m/min</td>
</tr>
<tr>
<td>41</td>
<td>Rotor position, finely/coarsely synchronized (from SW 5.1)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>21</td>
<td>16</td>
<td>-</td>
</tr>
<tr>
<td></td>
<td>0: Still not synchronized</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<tr>
<td></td>
<td>1: Coarsely synchronized</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>3: Coarsely and finely synchronized</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<tr>
<td>42</td>
<td>Input terminals (refer to P0678) (from SW 5.1)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>7</td>
<td>16</td>
<td>-</td>
</tr>
<tr>
<td>43</td>
<td>Torque setpoint limit (neg.) (SRM, ARM)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>4</td>
<td>24</td>
<td>μNm</td>
</tr>
<tr>
<td></td>
<td>Force setpoint limit (neg.) (SLM) (from SW 7.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>μN</td>
</tr>
<tr>
<td>44</td>
<td>Speed correction value (SRM, ARM)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>0</td>
<td>24</td>
<td>RPM</td>
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<tr>
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<td>Velocity correction value (SLM) (from SW 7.1)</td>
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<td></td>
<td></td>
<td></td>
<td></td>
<td>m/min</td>
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<td>45 to 69</td>
<td>Reserved</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>70</td>
<td>Position controller output (SRM, ARM) (SLM)</td>
<td>x</td>
<td>x</td>
<td>-</td>
<td>6</td>
<td></td>
<td>RPM</td>
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### Table 6-57  Signal selection list for analog outputs, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Signal Designation</th>
<th>Operating mode n-set</th>
<th>Displayed in pos</th>
<th>Shift factor</th>
<th>Bit width</th>
<th>Unit</th>
<th>Normalization (corresponds to LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>71</td>
<td>Pre-control speed (SRM, ARM) (SLM)</td>
<td>x</td>
<td>x</td>
<td>2</td>
<td>24</td>
<td>RPM m/min</td>
<td>P1711</td>
</tr>
<tr>
<td>72</td>
<td>System deviation, position controller input</td>
<td>x</td>
<td>x</td>
<td>19</td>
<td>48</td>
<td>MSC</td>
<td>MSR • 2^-11</td>
</tr>
<tr>
<td>73</td>
<td>Actual position value</td>
<td>x</td>
<td>x</td>
<td>19</td>
<td>48</td>
<td>MSC</td>
<td>MSR • 2^-11</td>
</tr>
<tr>
<td>74</td>
<td>Position setpoint</td>
<td>x</td>
<td>x</td>
<td>19</td>
<td>48</td>
<td>MSC</td>
<td>MSR • 2^-11</td>
</tr>
<tr>
<td>75</td>
<td>Velocity setpoint IPO</td>
<td>x^4</td>
<td>x</td>
<td>30</td>
<td>48</td>
<td>MSR/s</td>
<td>P1743</td>
</tr>
<tr>
<td>76</td>
<td>Following error</td>
<td>x</td>
<td>x</td>
<td>27</td>
<td>48</td>
<td>MSC</td>
<td>MSR • 2^-11</td>
</tr>
<tr>
<td>77</td>
<td>Following error, dynamic model</td>
<td>x</td>
<td>x</td>
<td>27</td>
<td>48</td>
<td>MSC</td>
<td>MSR • 2^-11</td>
</tr>
<tr>
<td>78</td>
<td>External position reference value (from SW 3.5)</td>
<td>x</td>
<td>x</td>
<td>19</td>
<td>48</td>
<td>MSC</td>
<td>MSR • P0403/P0404 • 2^-11</td>
</tr>
<tr>
<td>79</td>
<td>External velocity setpoint (from SW 3.5)</td>
<td>x</td>
<td>x</td>
<td>30</td>
<td>48</td>
<td>MSC</td>
<td>P1744</td>
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<tr>
<td>80</td>
<td>DSC system deviation (from SW 4.1)</td>
<td>x</td>
<td>-</td>
<td>4</td>
<td>32</td>
<td>-</td>
<td>P1745</td>
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<tr>
<td>81</td>
<td>DSC pre-controlled speed, motor (from SW 4.1)</td>
<td>x</td>
<td>-</td>
<td>6</td>
<td>32</td>
<td>RPM</td>
<td>P1711</td>
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<tr>
<td>82</td>
<td>DSC system deviation from PROFIBUS PPO (from SW 7.1)</td>
<td>x</td>
<td>-</td>
<td>6</td>
<td>32</td>
<td>RPM</td>
<td>P1711</td>
</tr>
<tr>
<td>83</td>
<td>Equalization controller input (from SW 7.1)</td>
<td>x</td>
<td>x</td>
<td>4</td>
<td>24</td>
<td>μNm/μN</td>
<td>P1713</td>
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<td>84</td>
<td>Equalization controller output (from SW 7.1)</td>
<td>x</td>
<td>x</td>
<td>4</td>
<td>24</td>
<td>RPM</td>
<td>P1711</td>
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<tr>
<td>85</td>
<td>Torque setpoint – master axis (from SW 7.1)</td>
<td>x</td>
<td>x</td>
<td>4</td>
<td>24</td>
<td>μNm/μN</td>
<td>P1713</td>
</tr>
<tr>
<td>86</td>
<td>Thermal motor load (from SW 11.2)</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>16</td>
<td>%</td>
<td>P1288\ P1607 up to SW 12.1</td>
</tr>
<tr>
<td>499</td>
<td>PROFIBUS PKW task (request) identification (from SW 5.1)</td>
<td>x</td>
<td>x</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>500</td>
<td>PROFIBUS PKW response ID (from SW 5.1)</td>
<td>x</td>
<td>x</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>501</td>
<td>PROFIBUS control word 1 (STW1) (from SW 5.1)</td>
<td>x</td>
<td>x</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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### Table 6-57  Signal selection list for analog outputs, continued

<table>
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<tr>
<th>No.</th>
<th>Signal Designation</th>
<th>Operating mode</th>
<th>Displayed in</th>
<th>Shift factor</th>
<th>Bit width</th>
<th>Unit</th>
<th>Normalization (corresponds to LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>502</td>
<td>PROFIBUS status word 1 (ZSW1) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>503</td>
<td>PROFIBUS control word 2 (STW2) (from SW 5.1)</td>
<td>x x</td>
<td>P1788:x¹)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>504</td>
<td>PROFIBUS status word 2 (ZSW2) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>505</td>
<td>PROFIBUS encoder 1 control word (G1_STW) (from SW 5.1)</td>
<td>- x</td>
<td>P1788:x¹)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>506</td>
<td>PROFIBUS encoder 1 status word (G1_ZSW) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>507</td>
<td>PROFIBUS encoder 2 control word (G2_STW) (from SW 5.1)</td>
<td>x x</td>
<td>P1788:x¹)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<td>508</td>
<td>PROFIBUS encoder 2 status word (G2_ZSW) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>509</td>
<td>PROFIBUS distributed inputs (DezEing) (from SW 5.1)</td>
<td>x x</td>
<td>P1788:x¹)</td>
<td>8</td>
<td>16</td>
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<tr>
<td>510</td>
<td>PROFIBUS message word (MeldW) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>511</td>
<td>PROFIBUS digital outputs, terminals 00.x to 03.x (DIG_OUT) (from SW 5.1)</td>
<td>x x</td>
<td>P1788:x¹)</td>
<td>19</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>512</td>
<td>PROFIBUS digital inputs terminals 00.x to 03.x (DIG_IN) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>19</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>513</td>
<td>PROFIBUS block selection (SatzAnw) (from SW 5.1)</td>
<td>x x</td>
<td>P1788:x¹)</td>
<td>17</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>514</td>
<td>PROFIBUS currently selected block (AktSatz) (from SW 5.1)</td>
<td>x x</td>
<td>P1789:x²)</td>
<td>17</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>515</td>
<td>PROFIBUS position control word (PosStw) (from SW 5.1)</td>
<td>- x</td>
<td>P1788:x¹)</td>
<td>8</td>
<td>16</td>
<td>-</td>
<td>-</td>
</tr>
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<td>516</td>
<td>PROFIBUS position status word (PosZsw) (from SW 5.1)</td>
<td>- x</td>
<td>P1789:x²)</td>
<td>8</td>
<td>16</td>
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<td>-</td>
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<td>517</td>
<td>PROFIBUS control word slave-to-slave communications (QStw) (from SW 5.1)</td>
<td>- x</td>
<td>P1788:x¹)</td>
<td>22</td>
<td>16</td>
<td>-</td>
<td>-</td>
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<tr>
<td>518</td>
<td>PROFIBUS status word slave-to-slave communications (QZsw) (from SW 5.1)</td>
<td>- x</td>
<td>P1789:x²)</td>
<td>22</td>
<td>16</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>519</td>
<td>PROFIBUS encoder 1 position actual value 1 (G1_XIST1) (from SW 7.1)</td>
<td>x -</td>
<td>P1789:x¹)</td>
<td>8</td>
<td>32</td>
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### Table 6-57  Signal selection list for analog outputs, continued

<table>
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<tr>
<th>No.</th>
<th>Signal</th>
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<th>Operating mode</th>
<th>Displayed in</th>
<th>Shift factor</th>
<th>Bit width</th>
<th>Unit</th>
<th>Normalization (corresponds to LSB)</th>
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<tbody>
<tr>
<td>520</td>
<td>PROFIBUS encoder 1 position</td>
<td>actual value 2 (G1_XIST2) (from SW 7.1)</td>
<td>x</td>
<td>P1789:x¹)</td>
<td>8</td>
<td>32</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>522</td>
<td>PROFIBUS encoder 2 position</td>
<td>actual value 1 (G2_XIST1) (from SW 7.1)</td>
<td>x</td>
<td>P1789:x¹)</td>
<td>8</td>
<td>32</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>523</td>
<td>PROFIBUS encoder 2 position</td>
<td>actual value 2 (G2_XIST2) (from SW 7.1)</td>
<td>x</td>
<td>P1789:x¹)</td>
<td>8</td>
<td>32</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>524</td>
<td>PROFIBUS encoder 3 position</td>
<td>actual value 1 (G3_XIST1) (from SW 7.1)</td>
<td>x</td>
<td>P1789:x¹)</td>
<td>8</td>
<td>32</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>525</td>
<td>PROFIBUS encoder 3 position</td>
<td>actual value 2 (G3_XIST2) (from SW 7.1)</td>
<td>x</td>
<td>P1789:x¹)</td>
<td>8</td>
<td>32</td>
<td>-</td>
<td>-</td>
</tr>
</tbody>
</table>

#### Note:
- **Abbreviations**
  - rms: rms value
  - pk: Peak value
  - LSB: Least Significant Bit
  - MSR: Dimension system grid
- **Signal marking?**
  - Not marked: For SimoCom U, the signal is available as standard
  - Marked in gray: For SimoCom U, the signal is only available when the expert mode is activated

1) Dependent on the assignment in P0915.17
2) Dependent on the assignment in P0916.17
3) PROFIBUS signal only supplies a value if it is set in P0615 or P0916.
4) This only applies for spindle positioning
Where are the signals taken from?

Figs. 6-67 and 6-68 show, using the controller structures, where the most important analog signals are taken from for the current and speed controller or for the position controller.

![Diagram of analog signals](image)

**Signal No.** | **Signal name**
--- | ---
2 | Current actual value phase U
3 | Current actual value phase V
4 | Field-generating current actual value I_d
5 | Torque-generating current actual value I_q
6 | Current setpoint I_q (limited after the filter)
7 | Current setpoint I_q (in front of the filter)
8 | Speed actual value motor (SRM, ARM), velocity actual value, motor (SLM)
9 | Speed setpoint (SRM, ARM), velocity setpoint (SLM)
11 | Torque setpoint (SRM, ARM), force setpoint (SLM)
17 | Quadrature-axis voltage V_q
18 | Direct-axis voltage V_d

**Induction motor/1FE1 motor flux sensing and closed-loop flux control**

Synchronous motor without 1FE1 motor

\[
I_q = \frac{M_{set}}{K_T} (P1113)
\]

\[
I_d = 0
\]

Fig. 6-67  Analog signals for the current and speed control loop
6.7 Analog outputs

![Diagram of Analog Outputs]

**Signal No.** | **Signal Name** |
--- | --- |
70 | Output, position controller |
71 | Pre-control speed |
72 | System deviation, position controller input |
73 | Position actual value |
74 | Position reference value |
75 | Velocity setpoint IPO |
76 | Following error |
77 | Following error, dynamic model |

Fig. 6-68 Analog signals for the position control loop
6 Description of the Functions

6.7 Analog outputs

Shift factor

<table>
<thead>
<tr>
<th>Bit 23 (MSB)</th>
<th>16 15</th>
<th>8 7</th>
<th>0 (LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Analog output value</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 0</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 1</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 8</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 16</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MSB = Most Significant Bit
LSB = Least Significant Bit

Fig. 6-69 Shift factor for analog output of 24-bit signals

<table>
<thead>
<tr>
<th>Bit 47 (MSB)</th>
<th>40 39</th>
<th>8 7</th>
<th>0 (LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Analog output value</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 0</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 1</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 8</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 40</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MSB = Most Significant Bit
LSB = Least Significant Bit

Fig. 6-70 Shift factor for analog output of 48-bit signals

Voltage range

Output voltage [V]

0

+10.0

1st overflow

2nd overflow

3rd overflow

4th overflow

-10.0

000000H

200000H

400000H

600000H

800000H

A00000H

C00000H

E00000H

000000H

2nd overflow 3rd overflow 4th overflow

Offset = 0 V
Fine normalization = 100%

Shift factor = 0

Shift factor = 2

Hexadecimal value

Fig. 6-71 Analog output voltage with overcontrol protection (P0631/P0638 = 1)
6.7 Analog outputs

Fig. 6-72 Analog output voltage without overcontrol protection (P0631/P0638 = 0)
6.8 Angular incremental encoder interface (X461, X462)

Description
Incremental setpoints can be read-in (input, from SW 3.3) and incremental actual values output via this interface.

An electronic handwheel can be connected to this interface (from SW 8.1).

- Incremental position actual value is output via the angular incremental encoder interface
  ---> P0890 = 1
  ---> the interface is switched as output
  ---> refer to Chapter 6.8.1

The incremental position actual value of the drive is output via the interface. The actual value can be used by a high-level control.

Notice
The control board only supplies “correct” angular incremental encoder signals after it has been completely booted.
In order that a higher-level control does not go into a fault condition, the control board must first run up, before the angular incremental encoder interface signals can be evaluated. The criterion for this is the "ready" signal.

Switch-on sequence (e.g.):
"SIMODRIVE 611 universal" control board --> higher-level control

- Enter the incremental position setpoint value via the angular incremental encoder interface (from SW 3.3)
  ---> P0890 = 2
  ---> the interface is switched as input
  ---> refer to Chapter 6.8.2

An incremental position reference value can be entered via the interface.
Parameterizing the angular incremental encoder interface (P0890 and P0891)

The angular incremental encoder interface is set for drive A and B using P0890. For drive B, the position actual value of drive A can be internally connected to the position reference value (position setpoint) of drive B using P0891.

For a position-synchronous coupling via the angular incremental encoder interface, synchronization of the position can be delayed. This is especially noticeable for a coarse resolution of the position (just a few increments per revolution) at the angular incremental encoder interface.

**Fig. 6-73 Angular incremental encoder interface for drives A and B: Parameterized using P0890 and P0891**
### 6.8.1 Angular incremental encoder interface as output (P0890 = 1)

**Description**

The angular incremental encoder interface (X461, X462) is set as output using P0890 = 1, i.e. the incremental position actual value of the motor encoder is output via terminals A+./A-.x, B+./B-.x, R+./R-.x.

The encoder signals are output, depending on the encoder type, and can still be partially manipulated (e.g. scaling or shifting, refer to Table 6-58).

**Note**

If, from SW 8.1, an induction motor with TTL encoder is connected to "SIMODRIVE 611 universal HR/HRS", then it is not permissible that the angular incremental encoder interface is used as output.
Overview: Encoder - angular incremental encoder signals - manipulation

The following table shows which signals are output for which encoder types and with which parameters they can be manipulated.

<table>
<thead>
<tr>
<th>Sensor type</th>
<th>Angular incremental encoder signals</th>
<th>Distance between the zero pulses</th>
<th>Factor, angular enc. pulse no./ enc. pulse no. which can be used?</th>
<th>Can the angular increment. encoder zero pulse be shifted?</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resolver (pole pair no.) 2p = 1 (1-speed) 4p = 2 (2-speed) 6p = 3 (3-speed) 8p = 4 (4-speed)</td>
<td>1024 pulses/rev 2048 pulses/rev 3072 pulses/rev 4096 pulses/rev</td>
<td>Can be evaluated</td>
<td>1024 pulses 4096 pulses (from SW 6.1)</td>
<td>Yes Yes</td>
</tr>
<tr>
<td>Encoder with sin/cos 1Vpp, incremental (without EnDat), rotating/linear</td>
<td>P0892 = 0 (factor 1:1) output timing unchanged via the angular incremental encoder interface (sinusoidal becomes squarewave/TTL)</td>
<td>Can be evaluated</td>
<td>Dependent on the encoder</td>
<td>Yes (from SW 5.1) No</td>
</tr>
<tr>
<td>Encoder with sin/cos 1Vpp with EnDat, rotating</td>
<td>P0892 = 1, 2, 3 (factor 1:x) are output corresponding to the factor (sinusoidal becomes squarewave/TTL) P0892 = 4 (factor 2:1, from SW 5.1)</td>
<td>For pulse number 2^n: Can be evaluated</td>
<td>2^n Encoder pulses/rev</td>
<td>Yes Yes</td>
</tr>
<tr>
<td>Encoder with sin/cos 1Vpp with EnDat, linear</td>
<td>Signal available, but random (this means that it cannot be evaluated)</td>
<td>Cannot be evaluated (as it is a random signal)</td>
<td></td>
<td>Yes No</td>
</tr>
</tbody>
</table>

Note:
- When using absolute value encoders (EnDat), an absolute value is not transferred via the angular incremental encoder interface, but encoder signals conditioned from "SIMODRIVE 611 universal".
- In order that the zero offset is correctly taken into account, the drive must be stationary while the control board boots.
6.8 Angular incremental encoder interface (X461, X462)

**Encoder with sin/cos 1Vpp**

The TTL signals of the pulse encoder simulation (angular incremental encoder) are derived from the zero cross-overs of the sin/cos signals. These signals are relatively flat which means that at lower speeds, multiple edges can occur at the changeover points with up to approx. half of the sampling frequency.

For several counter modules, encoder monitoring circuits erroneously signal faults. This is the reason that there is a secondary module with a lower sampling frequency which can prevent the erroneous response of the encoder monitoring function, e.g. the SIMATIC FM 354.

- Module, Order No. 6SN1118-0NH00-0AA2 (Catalog)
  - Angular incremental encoder sampling frequency 32 MHz
  - Multiple edges up to approx. 16 MHz
  - Useful angular incremental encoder signal, max. to approx. 350 kHz (for encoders with 2048 pulses/rev. max. 10500 RPM)
- Module, Order No. [MLFB] 6SN1118-0NH00-0BA2 (alternative)
  - Angular incremental encoder sampling frequency 1.2 MHz
  - Multiple edges up to approx. 600 kHz
  - Useful angular incremental encoder signal, max. to approx. 200 kHz (for encoders with 2048 pulses/rev. max. 6000 RPM)

From the following module, it can be assumed that the encoder monitoring will no longer incorrectly respond for several counter modules.

- Module Order No. [MLFB] 6SN1118-VNH01-0AA
  - Angular incremental encoder sampling frequency 4 MHz
  - Multiple edges up to approx. 2 MHz
  - Useful angular incremental encoder signal, max. to approx. 420 kHz (for encoders with 2048 pulses/rev. max. 12300 RPM)

**Angular incremental encoder interface output for pulse/direction signal**

If the angular incremental encoder interface is to be operated as setpoint input, as pulse/direction signal or as forwards/reverse signal, then the angular incremental encoder interface of another "SIMODRIVE 611 universal" module may not be used as setpoint source. The axis undesirably traverses as a result of the multiple edges inherent to the system.

If the angular incremental encoder interface is used as setpoint input (pulse/direction signal or up/down signal), then a suitable setpoint source, e.g. stepping motor control must be used with exactly the same pulse number as master.

In order to couple to SIMODRIVE 611 universal modules, the quadrature signal input signal waveform (P0894 = 0) should be used.

**Parameter overview (refer to Chapter A.1)**

The following parameters must be observed when setting the angular incremental encoder interface as output for incremental position actual values:

- P0890 Activates the angular incr. enc./encoder interface
- P0892 Factor, angular incr. enc. pulse no./enc. pulse no.
- P0893 Angular incremental encoder zero pulse offset
### Angular incremental encoder signals for resolvers

<table>
<thead>
<tr>
<th>P</th>
<th>Pulses/rev</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1024</td>
</tr>
<tr>
<td>2</td>
<td>2048</td>
</tr>
<tr>
<td>3</td>
<td>3072</td>
</tr>
<tr>
<td>4</td>
<td>4096</td>
</tr>
</tbody>
</table>

Distance between the zero pulses = 1024 pulses

A+.x/B+.x/R+.x: Angular incremental signals (x: space retainer for drive A or B)

P: Pole pair number of the resolver

**Fig. 6-75** Angular incremental encoder signals for resolvers

### Angular incremental encoder signals for incremental encoders with sin/cos 1Vpp

**Encoder signals**

1 pulse

<table>
<thead>
<tr>
<th>Signal</th>
<th>Encoder signals</th>
</tr>
</thead>
<tbody>
<tr>
<td>Signal A</td>
<td>90° 1 pulse (≈ 360°)</td>
</tr>
<tr>
<td>Signal B</td>
<td></td>
</tr>
</tbody>
</table>

**Angular incremental encoder signals**

1 zero pulse/rev

x: Space retainer for drive A or B

**Fig. 6-76** Angular incremental encoder signals for incremental encoders with sin/cos 1Vpp
Angular incremental encoder signals for absolute value encoders with sin/cos 1Vpp and EnDat interface

Note:

The zero pulse is generated from "SIMODRIVE 611 universal". Zero pulses which can be evaluated are only available for rotary encoders with pulse number $2^n$.

If the absolute value encoder has more than $2^n=2048$ increments ($n = 11$), then one zero mark is output for each 2048 increments. This means, that encoder pulse number/2048 zero marks are output at the angular incremental encoder interface per motor revolution; whereby the factor angular incremental encoder pulse number/encoder pulse number is selected as 1:1.
6.8 Angular incremental encoder interface (X461, X462)

6.8.2 Angular incremental encoder interface as input (P0890 = 2, from SW 3.3)

**Description**

The angular incremental encoder interface (X461, X462) is set as input with P0890 = 2, i.e. an incremental position reference value can be entered from an external control via terminals A+.x/A-.x, B+.x/B-.x and R+.x/R-.x.

**Incremental position reference value via angular incremental encoder interface**

The incremental position reference values, entered via the angular incremental encoder interface, are entered after the fine interpolator.

- **Parameter (refer to Chapter A.1):**
  - P0020 Position reference value
  - P0023 Velocity setpoint
  - P0032 External position reference value
  - P0210:8 Time constant, position reference value filter
  - P0401 Coupling factor, revolutions master drive
  - P0402 Coupling factor, revolutions slave drive
  - P0890 Activates the angular incr. enc./encoder interface
  - P0895 Number of input pulse periods
  - P0896 Number of dimension system grids
  - P0897 Inversion, external position reference value

- **Analog signals (refer to Chapter 7.4.3):**
  - 74 Position setpoint
  - 75 Velocity setpoint

1) From SW 3.3, from SW 4.1, no longer possible.

Fig. 6-78 Incremental position reference value via angular incremental encoder interface
The following input waveforms can be selected:

**Quadrature signal (P0894 = 0)**

The position reference value is entered via track A and track B, offset through 90 degrees. The direction of rotation identification is realized via the signal sequence.

![Fig. 6-79 Position reference value input via quadrature signals (P0894 = 0)](image)

**Pulse/direction signal (P0894 = 1)**

The position reference value is entered via track A and the direction identification via track B.

![Fig. 6-80 Position reference value input via pulse/direction signal (P0894 = 1)](image)

**Forwards/backwards signal (P0894 = 2)**

The position reference value is entered, depending on the selected direction, via Track A or B with the corresponding other track.

![Fig. 6-81 Position reference value entered via the forwards/backwards signal (P0894 = 2)](image)
These parameters are used to define how many signal periods correspond to the distance to be traveled.

Example:

Assumption:
The dimension system is set to linear, metric
--> 1 MSR = 0.001 mm

The axis should move through 10 mm with 2048 signal periods.
--> P0895 = 2 048
--> P0896 = 10 000 [MSR]

If the angular incremental encoder interface is operated as input, then the following applies:
--> Switch-in the terminating resistor via switch 1
--> Refer to Chapter 1.3.2

The position reference value, entered via the angular incremental encoder interface, is displayed using this parameter.

- P0032 --> Pos. ref. value via the angular incr. enc. interf.
- P0020 --> Position reference value for the pos. controller

It is not absolutely necessary that P0032 and P0020 are the same (e.g. for an axis coupling).

It is only guaranteed that the input signals are correctly identified and processed via the angular incremental encoder interface, switched as input if the following input limiting frequencies and signal limits are maintained:

<table>
<thead>
<tr>
<th>Input signal waveform</th>
<th>Input limiting frequency Position controller clock cycle (P1009)</th>
<th>Signal limits</th>
</tr>
</thead>
<tbody>
<tr>
<td>Quadrature signal (P0894 = 0)</td>
<td>2.5 MHz            2 MHz            1 MHz</td>
<td>Edge clearance tₑ ≥ 100 ns Pulse width tₜₕₘₜ, tₜ₍ₗ ≥ 100 ns</td>
</tr>
<tr>
<td>Pulse/direction signal (P0894 = 1)</td>
<td>5 MHz            5 MHz            4 MHz</td>
<td>Set-up time tₛ ≥ 20 ns</td>
</tr>
<tr>
<td>Forwards/backwards signal (P0894 = 2)</td>
<td>5 MHz            5 MHz            4 MHz</td>
<td></td>
</tr>
</tbody>
</table>

1) For clock-synchronous PROFIBUS operation, each time that clock synchronism is established, the position controller clock is briefly and internally increased in the slave. This means, at this particular instant, the signal frequency may not exceed half of the permissible input limiting frequency.
When switching-out (releasing) the coupling, it should be noted that the interpolator controls the velocity to the last value that was present, before it starts to brake. For high fluctuations in the velocity setpoint, this can lead to the drive first briefly accelerating before braking. This has to be taken into consideration for coarse resolutions of the position setpoint (e.g. 1 increment > 0.5 mm), as synchronization distances with different lengths can occur.

From SW 8.3.7 and higher, it is also possible to use an encoder with a coarse resolution (1 increment = approx. 1 mm or 1 degree). From SW 10.1.1. and higher, P0891 must also be set to 5 (angular encoder interface X461/X462 coarse).

If the acceleration in P0104 is set too low, then when synchronizing, higher acceleration levels can be reached.

When setting the angular incremental encoder interface as input for incremental position reference values, the following parameters must be observed:

- P0032 External position reference value
- P0890 Activates the angular incr. enc./encoder interface
- P0891 Source, external position reference value
- P0894 Angular incremental encoder input signal waveform
- P0895 External position reference value - No. of increments
- P0896 Ext. position reference value - No. of dimension system grids
- P0897 Inversion, external position reference value

For "angular incremental encoder interface as input", the following signal is available:

- Input signal "invert angular incr. encoder input" (from SW 3.5) (refer under the index entry "Input signal, digital ...")
  --> using an input terminal with function number 75
  --> using the PROFIBUS control signal "PosStw.7"
6.8.3 Electronic handwheel (from SW 8.1)

Description

An electronic handwheel can be connected to the angular incremental encoder interface. Electronic handwheels can be used to traverse the selected axes simultaneously in manual mode. The evaluation of the handwheel pulses is defined using the indexing dimension evaluation.

Angular incremental encoder handwheel evaluation

The electronic handwheel can, in the positioning mode, be activated via an input terminal function and via PROFIBUS-DP. The signals from the angular incremental encoder interface are velocity signals. The handwheel and drive do not move in synchronism.

Acceleration and braking is realized according to P0103 and P0104. The drive speed is limited by P0102.

The increments of the electronic handwheel can be assigned four factors using two input terminals.

The factors should be entered, before SW 9.1 in P0900 and from SW 9.1 onwards, in P0889:

<table>
<thead>
<tr>
<th>Bit 1</th>
<th>Bit 0</th>
<th>Handwheel evaluation (standard)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1 MSR</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>10 MSR</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>100 MSR</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1000 MSR</td>
</tr>
</tbody>
</table>

Before SW 9.1:
Sub-parameters P0900[0] up to P0900[3] can be optionally assigned factors of between 1 and 10000.

From SW 9.1:
Sub-parameters P0889[0] to P0889[3] can be optionally assigned factors of between 1 and 10000.

Reader’s note

If the drive is moved using the electronic handwheel, then the drive behavior corresponds to that of jogging, refer to Chapter 6.2.9.

Example:

The electronic handwheel supplies 100 incr./rev. One handwheel revolution corresponds to a value of 1 mm.

200 handwheel revolutions in one minute correspond to a velocity of 200 mm/min. The handwheel evaluation is entered using the input signal "angular incremental encoder handwheel evaluation, bit 0".

The following should be parameterized:

- Spindle pitch 10 mm/rev  --> P0236 = 10.000
- Quadrature signal activated --> P0894 = 0
- Angular incremental encoder handwheel evaluation 10  --> P0900/P0889[1] = 10
An axis is moved using the "electronic handwheel" dependent on the direction.

The direction should be set as follows using parameter P0899:8:

- P0899:8 = 0: positive and negative direction (standard)
- P0899:8 = 1: only in the positive direction
- P0899:8 = 2: only in the negative direction

**Note**

Angular incremental encoder pulses in the inhibited direction do not result in the output of faults or warnings.

In the inhibited direction, only the pulses of the velocity setpoint are cancelled. The velocity actual value must not necessarily follow the velocity setpoint, e.g. as a result of external forces or transient operations. As a result, motion is also possible in the direction that has not been enabled.

The handwheel direction of rotation can be inverted as follows:

- Using the input terminal function No. 75 "Invert angular incremental encoder input", i.e. when the axis is stationary, the incremental position reference value is immediately inverted with a 1 signal at the input terminals.
- "External inversion position reference value", via parameter P0897 - i.e. the inversion of the incremental position reference value with P0897 = 1 - is only effective after power on.

The following actions are not possible and initiate the appropriate faults:

- If the input terminals Fct. No. 62 or control signal STW1.8 (jogging 1 ON) or Fct. No. 63 or STW1.9 (jogging 2 ON) and Fct. No. 84 or SatzAnw.13 (activate angular incremental encoder, handwheel) are simultaneously activated, then fault 121 is output.
- If input terminal Fct. No. 72 or control signal PosStw.4 (activate coupling) and Fct. No. 84 or SatzAnw.13 (activate angular incremental encoder handwheel) are simultaneously activated, if a position reference value source is active via Parameter P0891, then fault 167 is output.
The following parameters must be observed when connecting a handwheel to the angular incremental encoder interface:

- **P0890**: Activates the angular incr. enc./encoder interface
- **P0899**:8: Enters the angular incremental encoder direction
- **P0900**:4: Angular incremental encoder handwheel evaluation (before SW 9.1)
- **P0889**:4: Angular incremental encoder handwheel evaluation (from SW 9.1)
- **P0102**: Maximum velocity
- **P0103**: Maximum acceleration
- **P0104**: Maximum deceleration
- **P0655**: Image, input signals, Part 3
- **P0657**: Image, output signals, Part 2

The following signals are used to connect a handwheel to the angular incremental encoder interface:

**Input signals**
- Input signal, "activate angular incremental encoder handwheel" (from SW 8.1)
  - --> using an input terminal with function number 84
  - --> using the PROFIBUS control signal "SatzAnw.13"
- Input signal, "angular incremental encoder handwheel evaluation, bit 0" (from SW 8.1)
  - --> using an input terminal with function number 85
  - --> using the PROFIBUS control signal "SatzAnw.11"
- Input signal, "angular incremental encoder handwheel evaluation, bit 1" (from SW 8.1)
  - --> using an input terminal with function number 86
  - --> using the PROFIBUS control signal "SatzAnw.12"

**Output signals**
- Output signal, "angular incremental encoder handwheel active" (from SW 8.1)
  - --> using an output terminal with function number 84
  - --> using the PROFIBUS status signal "AktSatz.13"
- Output signal, "angular incremental encoder handwheel evaluation, bit 0" (from SW 8.1)
  - --> using an output terminal with function number 85
  - --> using the PROFIBUS status signal "AktSatz.11"
- Output signal, "angular incremental encoder handwheel evaluation, bit 1" (from SW 8.1)
  - --> using an output terminal with function number 86
  - --> using the PROFIBUS status signal "AktSatz.12"

**Note**
Compared to the input of control signals via PROFIBUS-DP, the input terminal functions No. 84 to 86 have a higher priority.
6.9  Motor holding brake

Description

For axes, which must be secured against undesirable motion when powered down, the brake sequence control of "SIMODRIVE 611 universal" can be used to control the motor holding brake.

The relay for the motor holding brake is controlled via a freely-parameterizable output terminal.

SIEMENS motors are optionally available with a motor holding brake.

Warning

It is not permissible to use the motor holding brake as working brake, as it is generally only designed for a limited number of emergency braking operations.

Activating

The brake sequence control is activated by setting P0850 to 1.

This function is possible either in the n-set mode or pos mode.

Connecting the motor holding brake

The brake sequence control operates with the "open holding brake" output signal. The signal can be output as follows:

- Using a freely-parameterizable output terminal
  
  The required output signal for the control board or the optional TERMINAL module must therefore be assigned function No. 35 for the motor holding brake by appropriately parameterizing it.

  Output terminals on the control board
  O.x, O1.x, O2.x and O3.x  (parameterization, refer to Chap. 6.4.5)

  Output terminals for the optional TERMINAL module
  O2, O3 to O11  (parameterization, refer to Chapter 6.5)

  P0699 can be used, for each output terminal, to set whether the signal is output inverted.

  The relay for the motor holding brake is connected at the parameterized output terminal.

- Via status signal for PROFIBUS–DP
  
  The DP master must process the "open holding brake" status signal. The signal must be connected to the digital output of the master, to which the relay for the motor holding brake is connected.
### Parameter overview (refer to Chapter A.1)

The following parameters are used for the "motor holding brake" function:

- **P0850** Activates the brake control
- **P0851** Brake opening time
- **P0852** Speed, close holding brake (SRM, ARM)
  Motor velocity, close holding brake (SLM)
- **P0853** Brake delay time
- **P0854** Controller inhibit time

### Information for enabling the controller and pulses

**Note**

For controller enable:
Issuing and withdrawing the controller enable is dependent on several internal and external enable signals (refer to Chapter 6.4.1).

For pulse enable:
Issuing and withdrawing the pulse enable is dependent on several internal and external enable signals (refer to Chapter 6.4.1).
Open brake

When "controller enable" is issued, the speed controller is active and controls with $n_{\text{set}} = 0$.
The speed setpoints are only transferred after the brake opening time has expired.
This is signaled using the "status, controller enable" output signal.

Objective when setting the brake opening time

The brake opening time should be selected, so that after the "controller enable" is issued, the speed controller becomes active when the motor holding brake opens.
For all other settings, the control acts against the brake.
The following applies:
Brake opening time (P0851) $\geq$ Time to open the holding brake

![Diagram showing the characteristics when issuing "controller enable".](image)

Fig. 6-82  Release brake: Characteristics when issuing "controller enable"
The axis is actively braked when the "controller enable" is withdrawn. The brake delay time (P0853) is started when the "controller enable" signal drops-out, i.e. at \( n_{set} = 0 \).

At \( n = n_{holding\ brake} \) (P0852), the following is valid:

- The "open holding brake" output signal is deleted

Note:

After the brake delay time has expired (P0853), the "open holding brake" output signal is always canceled.

For \( n_{set} = 0 \), the controller inhibit time (P0854) starts to run down.

Objective for this setting

The time required to close the holding brake should be adjusted so that the control is only withdrawn after the brake has closed. This prevents an axis from possibly sagging.

![Diagram of closing the brake](image)

**Note**

The signals designated as internal (e.g. "open holding brake") differ - as a result of the additional internal run times and interlocks - from the appropriate digital input and output signals or PROFIBUS signals.
6 Description of the Functions

6.9 Motor holding brake

Closing the brake when the "pulse enable" is withdrawn

When the pulse enable is withdrawn, the drive coasts down, and the "open holding brake" output signal is canceled.

After the time taken for the brake to close, the drive is braked by the motor holding brake.

Fig. 6-84 Closing the brake: Behavior when withdrawing "pulse enable"
### Task description, assumptions:

A motor with holding brake for a hanging axis is connected to drive A. The motor holding brake is to be controlled via output terminal O3.A.

What other settings are required?

1. Connect-up the relay to control the motor holding brake
2. Assign the function "holding brake" to output terminal O3.A
   \[ P0683 = 35 \]
3. Activate the brake sequence control in the drive \( P0850 = 1 \)
4. Set the parameter to open the holding brake
   \[ P0851 \text{ (brake opening time)} \]
   This time must be set, so that it is equal to or greater than the time to open the holding brake.
5. Set the parameters for closing the holding brake when withdrawing the controller enable
   \[ P0852 \text{ (speed, close holding brake)} \]
   \[ P0853 \text{ (brake delay time)} \]
   The brake delay time \( P0853 \) must be harmonized with the speed at which the holding brake closes \( P0852 \).
   \[ P0854 \text{ (controller inhibit time)} \]
   The controller inhibit time must be harmonized with the time that it takes to close the brake so that the drive cannot drop.
   
   **Example of determining the controller inhibit time:**
   Mark the position of the axis and initiate an alarm that withdraws the controller enable.
   Does the axis sag? If yes, then increase the controller inhibit time.

---

**Diagram:**

![Diagram of motor holding brake control](image)

**Fig. 6-85 Example: Controlling the motor holding brake via output O3.A**
6.10 Parameter set changeover

Description

By selecting parameter sets, the appropriate parameter set-dependent parameters become effective. This means that parameters can be adapted to various requirements, e.g.

- Dynamic adaptations
- Gearbox stage changeover (high or low speed)

It is possible to toggle between a maximum of 8 parameter blocks (parameter blocks 0 to 7) via the appropriate input signals.

Parameters that are independent and dependent on the parameter set

For "SIMODRIVE 611 universal" the following parameter types are available, referred to the parameter set changeover:

- Parameter set-independent parameters
  
  These parameters only have one parameter value, and are effective, independent of the selected parameter set.
  
  Example:
  
P0660 Function, input terminal I0.x

- Parameter set-dependent parameters
  
  These parameters have, for every parameter set, a parameter value which is effective, dependent on the selected parameter set.
  
  Example:
  
P1407:8 P-gain, speed controller (ARM, SRM)
P1407:0 is effective, if parameter set 0 is selected (standard)
...P1407:7 is effective, if parameter set is selected

Table 6-60 Parameter set-dependent parameters

<table>
<thead>
<tr>
<th>Parameters for parameter set</th>
<th>Operating mode</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0115:0</td>
<td>-</td>
<td>Fixed stop, max. following error (from SW 3.3)</td>
</tr>
<tr>
<td>0116:0</td>
<td>-</td>
<td>Fixed stop, monitoring window (from SW 3.3)</td>
</tr>
<tr>
<td>0200:0</td>
<td>x</td>
<td>Kv factor (position loop gain)</td>
</tr>
<tr>
<td>0204:0</td>
<td>x</td>
<td>Factor, speed pre-control</td>
</tr>
<tr>
<td>0205:0</td>
<td>x</td>
<td>Balancing filter, speed pre-control (dead time)</td>
</tr>
<tr>
<td>0206:0</td>
<td>x</td>
<td>Balancing filter, speed pre-control (PT1)</td>
</tr>
<tr>
<td>0210:0</td>
<td>x</td>
<td>Time constant, position reference value filter</td>
</tr>
<tr>
<td>0237:0</td>
<td>x</td>
<td>Encoder revolutions</td>
</tr>
<tr>
<td>Parameters for parameter set</td>
<td>Operating mode</td>
<td>Description</td>
</tr>
<tr>
<td>------------------------------</td>
<td>----------------</td>
<td>-------------</td>
</tr>
<tr>
<td>0238:0 0238:1 ... 0238:7</td>
<td>x (^1) x</td>
<td>Load revolutions</td>
</tr>
<tr>
<td>0318:0 0318:1 ... 0318:7</td>
<td>x (^1) x</td>
<td>Dynamic following error monitoring tolerance</td>
</tr>
<tr>
<td>1123:0 1123:1 ... 1123:7</td>
<td>x x</td>
<td>Load moment of inertia (ARM, SRM) (from SW 2.4) Load mass (SLM)</td>
</tr>
<tr>
<td>1200:0 1200:1 ... 1200:7</td>
<td>x x</td>
<td>Current setpoint filter</td>
</tr>
<tr>
<td>1201:0 ... 1221:0 to 1221:1</td>
<td>x x</td>
<td>1. Torque limit value (ARM, SRM) 1. Force limit value (SLM)</td>
</tr>
<tr>
<td>1230:0 1230:1 ... 1230:7</td>
<td>x x</td>
<td>Regenerative limiting</td>
</tr>
<tr>
<td>1233:0 1233:1 ... 1233:7</td>
<td>x x</td>
<td>1. power limit value</td>
</tr>
<tr>
<td>1240:0 1240:1 ... 1240:7</td>
<td>x x</td>
<td>Offset, torque setpoint (speed controlled) (ARM, SRM) Offset, force setpoint (speed-controlled) (SLM)</td>
</tr>
<tr>
<td>1241:0 1241:1 ... 1241:7</td>
<td>x -</td>
<td>Normalization, torque setpoint (ARM, SRM) Normalization, force setpoint (SLM)</td>
</tr>
<tr>
<td>1242:0 1242:1 ... 1242:7</td>
<td>x -</td>
<td>Offset, torque setpoint (torque controlled) (ARM, SRM) Offset, force setpoint (open-loop torque contr.) (SLM)</td>
</tr>
<tr>
<td>1243:0 1243:1 ... 1243:7</td>
<td>x x</td>
<td>Normalization, torque/power reduction (ARM, SRM) Normalization, force/power reduction (SLM)</td>
</tr>
<tr>
<td>1256:0 1256:1 ... 1256:7</td>
<td>x -</td>
<td>Ramp-function generator, ramp-up time (from SW 2.4)</td>
</tr>
<tr>
<td>1257:0 1257:1 ... 1257:7</td>
<td>x -</td>
<td>Ramp-function generator, ramp-down time (from SW 2.4)</td>
</tr>
<tr>
<td>1401:0 1401:1 ... 1401:7</td>
<td>x x</td>
<td>Speed for max. useful motor speed (ARM, SRM) Velocity for max. useful motor velocity (SLM)</td>
</tr>
<tr>
<td>1405:0 1405:1 ... 1405:7</td>
<td>x x</td>
<td>Monitoring speed, motor (ARM, SRM) Monitoring velocity, motor (SLM)</td>
</tr>
<tr>
<td>1407:0 1407:1 ... 1407:7</td>
<td>x x</td>
<td>P gain, speed controller (ARM, SRM) P gain, velocity controller (SLM)</td>
</tr>
<tr>
<td>1408:0 1408:1 ... 1408:7</td>
<td>x x</td>
<td>P gain, upper adaptation speed (ARM, SRM) P gain, upper adaptation velocity (SLM)</td>
</tr>
<tr>
<td>1409:0 1409:1 ... 1409:7</td>
<td>x x</td>
<td>Integral action time, speed controller (ARM, SRM) Integral action time, velocity controller (SLM)</td>
</tr>
<tr>
<td>1410:0 1410:1 ... 1410:7</td>
<td>x x</td>
<td>Integral action time, upper adaptation speed (ARM, SRM) Integral action time, upper adaptation velocity (SLM)</td>
</tr>
<tr>
<td>1414:0 1414:1 ... 1414:7</td>
<td>x x</td>
<td>Natural frequency, reference model, speed (ARM, SRM) Natural frequency, reference model, velocity (SLM)</td>
</tr>
<tr>
<td>1415:0 1415:1 ... 1415:7</td>
<td>x x</td>
<td>Damping, reference model, speed (ARM, SRM) Damping, reference model, velocity (SLM)</td>
</tr>
</tbody>
</table>
### Table 6-60  Parameter set-dependent parameters, continued

<table>
<thead>
<tr>
<th>Parameters for parameter set</th>
<th>Operating mode</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>...</td>
</tr>
<tr>
<td>1417:0</td>
<td>1417:1</td>
<td>...</td>
</tr>
<tr>
<td>1418:0</td>
<td>1418:1</td>
<td>...</td>
</tr>
<tr>
<td>1421:0</td>
<td>1421:1</td>
<td>...</td>
</tr>
<tr>
<td>1426:0</td>
<td>1426:1</td>
<td>...</td>
</tr>
<tr>
<td>1428:0</td>
<td>1428:1</td>
<td>...</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1451:0</td>
<td>1451:1</td>
<td>...</td>
</tr>
<tr>
<td>1453:0</td>
<td>1453:1</td>
<td>...</td>
</tr>
<tr>
<td>1500:0</td>
<td>1500:1</td>
<td>...</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- The parameter is available in this operating mode
- The parameter is not available in this operating mode
- for spindle positioning (from SW 5.1)

---

**Note**

Only parameter set 0 is parameterized using this SimoCom U parameterizing and start-up tool via the interactive dialog operation.

Parameter sets 1 to 7 must be parameterized using the Expert list of SimoCom U.

**How can you toggle between parameter sets?**

You can toggle between parameter sets 0 and 7 using the following input signals:

- Input signal "parameter set changeover 1st input"
- Input signal "parameter set changeover 2nd input"
- Input signal "parameter set changeover 3rd input"
6.10 Parameter set changeover

Note
The input signals to change over the parameter set can be entered via input terminals or via PROFIBUS--DP (refer to Chapter 6.4.3 or under the index entry "input signal, parameter set changeover"). For a parameter set changeover in the positioning mode (P0700 = 3), for the same gear set ratios, the reference point is lost. This is not the case if P0239 = 1.

Application
Example

Task description:
Drive A and therefore the coupled mechanical system is loaded to various degrees (e.g. with and without load).

In order to adapt the system to the masses to be moved, the parameter set-dependent parameters are defined in parameter sets 0 and 1 corresponding to the different loads.

Input terminal I0.A is to be used to toggle between parameter set 0 and 1:

<table>
<thead>
<tr>
<th>Input terminal</th>
<th>Parameter Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>I0.A</td>
<td>1st input P0660 = 9 Changeover</td>
</tr>
<tr>
<td>xx</td>
<td>2nd input xx</td>
</tr>
<tr>
<td>xx</td>
<td>3rd input xx</td>
</tr>
</tbody>
</table>

The input terminals to toggle between the parameter sets, is controlled from a higher-level PLC as a function of the mass being moved.

Fig. 6-86 Example: Parameter set changeover
6.11 Motor changeover for induction motors (from SW 2.4)

6.11.1 General information on motor changeover

The following changeover functions can be implemented depending on the setting in P1013 (motor changeover):

Table 6-61 Motor changeover versions

<table>
<thead>
<tr>
<th>P1013</th>
<th>Changeover</th>
<th>Description</th>
<th>Reference</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>None</td>
<td>Property: Motor data set 1 (P1xxx) is always selected.</td>
<td>-</td>
</tr>
<tr>
<td>1</td>
<td>Max. 4 motors, each with 1 motor data set</td>
<td>Characteristics: • The motor/motor data sets are changed over using freely-parameterizable input/output terminals. • The pulses are canceled at each changeover operation. Application: • Changing over several motors¹²)</td>
<td>Refer to Chapter 6.11.2</td>
</tr>
<tr>
<td>2</td>
<td>1 motor with max. 4 motor data sets</td>
<td>Characteristics: • The motor data sets are changed over using freely-parameterizable input terminals. • The pulses are not canceled when changing over. Application: • Adaptation of the motor and controller data (e.g. pulse frequency changeover)</td>
<td>Refer to Chapter 6.11.3</td>
</tr>
<tr>
<td>3</td>
<td>Max. 2 motors each with 2 motor data sets</td>
<td>Characteristics: • The motors/motor data sets are changed over via a freely parameterizable input terminal and via the speed thresholds. • If an input terminal is used to change over, the pulses are canceled. • The pulses are not canceled if changeover is realized using speed thresholds. Application: • Speed-dependent adaptation of the motor and controller data (e.g. pulse frequency changeover) for - one motor - two motors - star/delta operation</td>
<td>Refer to Chapter 6.11.4</td>
</tr>
</tbody>
</table>

¹) Encoder changeover is not possible.
²) Only 1 motor can be used with encoder.
Motor data sets

For the “SIMODRIVE 611 universal” control board, there are data sets for a maximum of 4 induction motors.

Note

The currently effective motor data set is displayed in P0599 (active motor data set).

It is only possible to enable motor changeover in the "speed/torque setpoint" mode (P0700 = 1).

Before motor changeover can be selected, the motor data must be entered into the associated parameters 2xxx, 3xxx and/or 4xxx. For motors with Code No., it is sufficient to make the entry in P\textsubscript{x}102. After this, in both cases, it is necessary to carry-out a "calculate controller data" routine using P\textsubscript{x}080 = 1.

Table 6-62 Motor data set-dependent parameters

<table>
<thead>
<tr>
<th>Motor data set</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1100</td>
<td>2100</td>
<td>3100</td>
<td>4100</td>
<td>Frequency, pulse-width modulation</td>
<td></td>
</tr>
<tr>
<td>1102</td>
<td>2102</td>
<td>3102</td>
<td>4102</td>
<td>Motor code number (99 is entered for non-catalog motors)</td>
<td></td>
</tr>
<tr>
<td>\textbf{Note}:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>\textbullet</td>
<td>When using several catalog motors, the motor data is only valid after first entering the appropriate motor code, followed by data save and POWER ON.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>\textbullet</td>
<td>For a motor changeover with &quot;gap&quot; (e.g. from motor 1 to 3), a motor code number (dummy code) must be entered in the intermediate motor data set, i.e. the appropriate parameter may not have the value zero.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>\textbullet</td>
<td>After manually changing the motor code number, the following parameters must be checked, and if required, set to practical values:</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>\textbullet</td>
<td>P1401, P2401, P3401 or P4401 (speed for the maximum useful motor speed)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>\textbullet</td>
<td>P1147, P2147, P3147 or P4147 (speed limiting)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1103</td>
<td>2103</td>
<td>3103</td>
<td>4103</td>
<td>Rated motor current</td>
<td></td>
</tr>
<tr>
<td>1117</td>
<td>2117</td>
<td>3117</td>
<td>4117</td>
<td>Motor moment of inertia</td>
<td></td>
</tr>
<tr>
<td>1119</td>
<td>2119</td>
<td>3119</td>
<td>4119</td>
<td>Inductance of the series reactor</td>
<td></td>
</tr>
<tr>
<td>1120</td>
<td>2120</td>
<td>3120</td>
<td>4120</td>
<td>P gain, current controller</td>
<td></td>
</tr>
<tr>
<td>1121</td>
<td>2121</td>
<td>3121</td>
<td>4121</td>
<td>Integrator time of current controller</td>
<td></td>
</tr>
<tr>
<td>1123:8</td>
<td>2123:8</td>
<td>3123:8</td>
<td>4123:8</td>
<td>Load moment of inertia</td>
<td></td>
</tr>
<tr>
<td>1125</td>
<td>2125</td>
<td>3125</td>
<td>4125</td>
<td>Ramp-up time 1 for V/Hz operation</td>
<td></td>
</tr>
</tbody>
</table>
### Table 6-62  Motor data set-dependent parameters, continued

<table>
<thead>
<tr>
<th>Motor data set</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1127</td>
<td>Voltage at f = 0, V/Hz mode</td>
</tr>
<tr>
<td>1129</td>
<td>cos phi power factor</td>
</tr>
<tr>
<td>1130</td>
<td>Rated motor power</td>
</tr>
<tr>
<td>1132</td>
<td>Rated motor voltage</td>
</tr>
<tr>
<td>1134</td>
<td>Rated motor frequency</td>
</tr>
<tr>
<td>1135</td>
<td>Motor no-load voltage</td>
</tr>
<tr>
<td>1136</td>
<td>Motor no-load current</td>
</tr>
<tr>
<td>1137</td>
<td>Stator resistance, cold</td>
</tr>
<tr>
<td>1138</td>
<td>Rotor resistance, cold</td>
</tr>
<tr>
<td>1139</td>
<td>Stator leakage reactance</td>
</tr>
<tr>
<td>1140</td>
<td>Rotor leakage reactance</td>
</tr>
<tr>
<td>1141</td>
<td>Magnetizing reactance</td>
</tr>
<tr>
<td>1142</td>
<td>Speed at the start of field weakening</td>
</tr>
<tr>
<td>1145</td>
<td>Stall torque reduction factor</td>
</tr>
<tr>
<td>1146</td>
<td>Maximum motor speed</td>
</tr>
<tr>
<td>1147</td>
<td>Speed limitation</td>
</tr>
<tr>
<td>1148 1)</td>
<td>Speed at the start of the stall power</td>
</tr>
<tr>
<td>1150</td>
<td>P gain, flux controller</td>
</tr>
<tr>
<td>1151</td>
<td>Integral action time, flux controller</td>
</tr>
<tr>
<td>1160</td>
<td>Speed at the start of flux sensing</td>
</tr>
<tr>
<td>1167</td>
<td>Response value of the ground fault test (from SW 13.1)</td>
</tr>
<tr>
<td>1168</td>
<td>Maximum rotation, ground fault test (from SW 13.1)</td>
</tr>
<tr>
<td></td>
<td>Maximum motion, ground fault test (SLM) (from SW 13.1)</td>
</tr>
<tr>
<td>1180</td>
<td>Lower current limit adaptation</td>
</tr>
<tr>
<td>1181</td>
<td>Upper current limit adaptation</td>
</tr>
<tr>
<td>1182</td>
<td>Factor, current controller adaptation</td>
</tr>
<tr>
<td>1230:8</td>
<td>1st torque limit value</td>
</tr>
<tr>
<td>1233:8</td>
<td>Regenerative limiting</td>
</tr>
<tr>
<td>1235:8</td>
<td>1st power limit value</td>
</tr>
<tr>
<td>1238</td>
<td>Current limit value</td>
</tr>
<tr>
<td>1240:8</td>
<td>Offset, torque setpoint (speed controlled)</td>
</tr>
<tr>
<td>1241:8</td>
<td>Normalization, torque setpoint</td>
</tr>
<tr>
<td>1242:8</td>
<td>Offset, torque setpoint (torque controlled)</td>
</tr>
<tr>
<td>1243:8</td>
<td>Normalization, torque/power reduction</td>
</tr>
<tr>
<td>1245</td>
<td>Threshold for speed-dep. Mset smoothing</td>
</tr>
</tbody>
</table>
Table 6-62  Motor data set-dependent parameters, continued

<table>
<thead>
<tr>
<th>Motor data set</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1246 2246 3246 4246</td>
<td>Hysteresis for speed-dep. Mset smoothing</td>
</tr>
<tr>
<td>1256:8 2256:8 3256:8 4256:8</td>
<td>Ramp-function generator, ramp-up time</td>
</tr>
<tr>
<td>1257:8 2257:8 3257:8 4257:8</td>
<td>Ramp-function generator, ramp-down time</td>
</tr>
<tr>
<td>1288 2288 3288 4288</td>
<td>Shutdown threshold, thermal motor model</td>
</tr>
<tr>
<td>1400 2400 3400 4400</td>
<td>Rated motor speed</td>
</tr>
<tr>
<td>1401:8 2401:8 3401:8 4401:8</td>
<td>Speed for the max. useful motor speed</td>
</tr>
<tr>
<td>1403 2403 3403 4403</td>
<td>Shutoff speed for pulse suppression</td>
</tr>
<tr>
<td>1405:8 2405:8 3405:8 4405:8</td>
<td>Monitoring speed, motor</td>
</tr>
<tr>
<td>1407:8 2407:8 3407:8 4407:8</td>
<td>P gain of speed controller</td>
</tr>
<tr>
<td>1408:8 2408:8 3408:8 4408:8</td>
<td>P gain, upper adaptation speed</td>
</tr>
<tr>
<td>1409:8 2409:8 3409:8 4409:8</td>
<td>Integral action time, speed controller</td>
</tr>
<tr>
<td>1410:8 2410:8 3410:8 4410:8</td>
<td>Integral action time, upper adaptation speed</td>
</tr>
<tr>
<td>1411 2411 3411 4411</td>
<td>Lower adaptation speed</td>
</tr>
<tr>
<td>1412 2412 3412 4412</td>
<td>Upper adaptation speed</td>
</tr>
<tr>
<td>1413 2413 3413 4413</td>
<td>Select adaptation, speed controller</td>
</tr>
<tr>
<td>1417:8 2417:8 3417:8 4417:8</td>
<td>nx for “nact &lt; nx” signal</td>
</tr>
<tr>
<td>1418:8 2418:8 3418:8 4418:8</td>
<td>nmin for “nact &lt; nmin” signal</td>
</tr>
<tr>
<td>1426:8 2426:8 3426:8 4426:8</td>
<td>Tolerance bandwidth for “nset = nact” signal</td>
</tr>
<tr>
<td>1451:8 2451:8 3451:8 4451:8</td>
<td>P gain, speed controller IM</td>
</tr>
<tr>
<td>1453:8 2453:8 3453:8 4453:8</td>
<td>Integral action time, speed controller IM</td>
</tr>
<tr>
<td>1458 2458 3458 4458</td>
<td>Current setpoint, open-loop controlled range IM</td>
</tr>
<tr>
<td>1459 2459 3459 4459</td>
<td>Torque smoothing time constant IM</td>
</tr>
<tr>
<td>1465 2465 3465 4465</td>
<td>Changeover speed, MSD/IM</td>
</tr>
<tr>
<td>1466 2466 3466 4466</td>
<td>Changeover speed, closed-loop/open-loop control IM</td>
</tr>
<tr>
<td>1602 2602 3602 4602</td>
<td>Warning threshold, motor overtemperature</td>
</tr>
<tr>
<td>1607 2607 3607 4607</td>
<td>Shutdown limit, motor temperature</td>
</tr>
<tr>
<td>1608 2608 3608 4608</td>
<td>Fixed temperature</td>
</tr>
<tr>
<td>1712 ¹ 2712 ¹ 3712 ¹ 4712 ¹</td>
<td>Weighting, rotor flux representation</td>
</tr>
<tr>
<td>1713 ¹ 2713 ¹ 3713 ¹ 4713 ¹</td>
<td>Weighting, torque representation</td>
</tr>
<tr>
<td>1725 ¹ 2725 ¹ 3725 ¹ 4725 ¹</td>
<td>Normalization, torque setpoint</td>
</tr>
</tbody>
</table>

1) These parameters are read-only.
Selecting the motor data sets and motors via input/output signals

The following input and output signals are used to select the motor data set and the associated motor:

- **Input terminal with Fct. No. 5**: “Motor data set changeover, 1st input”
- **Input terminal with Fct. No. 6**: “Motor data set changeover, 2nd input”
- **Output terminal with Fct. No. 11**: “Motor 1 selected”
- **Output terminal with Fct. No. 12**: “Motor 2 selected”
- **Output terminal with Fct. No. 13**: “Motor 3 selected”
- **Output terminal with Fct. No. 14**: “Motor 4 selected”

**Note:**
Output terminals with Fct. Nos. 11...14 are only controlled, if P1249 = 0!

Fig. 6-87 Input/output signals: freely-parameterizable terminals

- **Control signal**: “Motor data set changeover, 1st input”
  - STW2.9
- **Control signal**: “Motor data set changeover, 2nd input”
  - STW2.10
- **Control signal**: “Motor changed over”
  - STW2.11

- **Status signal**: “Actual motor, 1st signal”
  - ZSW2.9
- **Status signal**: “Actual motor, 2nd signal”
  - ZSW2.10
- **Status signal**: “Motor being changed over”
  - ZSW2.11
  (from SW 3.3)

Fig. 6-88 Input/output signals: PROFIBUS signals
Reader’s note

- Input signals: refer under the index entry “Input signal…”
- Output signals: refer under the index entry “Output signal…”
- The wiring of the input/output terminals for the control board and for the optional TERMINAL module is described in Chapter 2.2.
- The following input/output terminals are available:
  - for the control board: I0.x to I3.x or O0.x to O3.x
  - Space retainer for drive A or B
  - for the optional TERMINAL module: I4 to I11 or O4 to O11
- The parameterization of the input/output terminals is described as follows:
  - for the control board: in Chapter 6.4.2 and 6.4.5
  - for the optional TERMINAL module: in Chapter 6.5

Pulse frequency changeover

A dedicated power module pulse frequency (P1100) can be parameterized for each motor data set.

The speed requirement of the motor can be better adapted by changing over the pulse frequency. With a higher pulse frequency, higher speeds can be achieved.

The following applies for the pulse frequency, it must have at least approx. 6 the frequency of the instantaneous motor frequency.

High pulse frequencies mean high switching losses and therefore poor utilization.

At a pulse frequency of 8 kHz, only 40–55% of the possible current that is available at 3.2 kHz is available.
6.11.2 Changeover, max. 4 motors each with 1 data set (P1013 = 1)

Description

For this changeover version (P1013 = 1), a maximum of 4 motors each with 1 associated motor data set can be changed over.

Note

The pulses are canceled at each changeover.

Input/output signals for changeover

The following 2 input and 4 output signals are available to changeover a maximum of 4 motors/motor data sets:

Table 6-63 Input/output terminal signals

<table>
<thead>
<tr>
<th>Input terminal with function No.</th>
<th>Effective motor data set</th>
<th>Output terminal with function No.</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td></td>
<td>14</td>
</tr>
<tr>
<td>5</td>
<td></td>
<td>13</td>
</tr>
<tr>
<td>14</td>
<td></td>
<td>12</td>
</tr>
<tr>
<td>13</td>
<td></td>
<td>11</td>
</tr>
<tr>
<td>0</td>
<td>P1xxx</td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td>P2xxx</td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td>P3xxx</td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td>P4xxx</td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td></td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td></td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td></td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td></td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td></td>
<td>0</td>
</tr>
<tr>
<td>0</td>
<td></td>
<td>0</td>
</tr>
</tbody>
</table>

Note

The number of contactors which can be controlled for motor changeover is limited by the number of output terminals.

Output terminals 11, 12, 13 and 14 are not controlled, if P1249 = 1.

How does a changeover work?

"SIMODRIVE 611 universal" receives a request for changeover, if the signal status at one of the two input terminals for motor data set changeover has changed.

A changeover is then realized automatically as follows:

1. The pulses are canceled and the motor selection outputs are reset
2. Time t1 starts (this is set to 320 ms)
3. After time t1 expires, the "correct" output terminal is set to select the motor
4. Time t2 starts (this is set to 160 ms)
5. After time t2 expires, the pulses are enabled
**Application example**

4 motors should be operated with drive A from "SIMODRIVE 611 universal".

**Assumptions for the example:**

- An optional TERMINAL module is used.
- The changeover is realized via the following input/output terminals:
  
<table>
<thead>
<tr>
<th>Input Terminals</th>
<th>Function</th>
<th>Output Terminals</th>
<th>Function</th>
</tr>
</thead>
<tbody>
<tr>
<td>I8 (X422.5)</td>
<td>P0668 (function, input terminal I8) = 5</td>
<td></td>
<td></td>
</tr>
<tr>
<td>I9 (X422.6)</td>
<td>P0669 (function, input terminal I9) = 6</td>
<td></td>
<td></td>
</tr>
<tr>
<td>O8 (X432.5)</td>
<td>P0688 (signaling function, output terminal O8) = 11</td>
<td></td>
<td></td>
</tr>
<tr>
<td>O9 (X432.6)</td>
<td>P0689 (signaling function, output terminal O9) = 12</td>
<td></td>
<td></td>
</tr>
<tr>
<td>O10 (X432.7)</td>
<td>P0690 (signaling function, output terminal O10) = 13</td>
<td></td>
<td></td>
</tr>
<tr>
<td>O11 (X432.8)</td>
<td>P0691 (signaling function, output terminal O11) = 14</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Fig. 6-89** Recommended circuit: Changing over 4 motors, each with one motor data set

1) Several motors cannot be simultaneously selected as this is interlocked per software. The recommended contactor interlocking additionally guarantees that only one motor can be operated at any one time.

2) Only necessary for special high-speed motors.
### 6.11.3 Changeover, 1 motor with max. 4 data sets (P1013 = 2)

**Description**
For this changeover version (P1013 = 2) for one motor, a maximum of 4 motor data sets can be changed over.

**Note**
The pulses are **not** canceled at changeover, i.e. the changeover is made with the pulses enabled.

This version can be used to adapt the motor and controller data.

**Input/output signals**
The following input/output signals are used for this changeover version:

<table>
<thead>
<tr>
<th>Input terminal with function No.</th>
<th>Effective motor data set</th>
<th>Output terminal with function No.</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td>5</td>
<td>P1xxx</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>P1xxx</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>P2xxx</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>P3xxx</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>P4xxx</td>
</tr>
</tbody>
</table>

1) The output terminals with function numbers 11 to 14 are not energized.
6.11.4 Changeover, max. 2 motors each with 2 data sets (P1013 = 3)

Description

For this changeover version (P1013 = 3) a maximum of 2 motors each with 2 associated motor data sets can be changed over.

The changeover is realized using the input terminal with function number 6 and using the appropriately selected speed thresholds in P1247 or P1248. At changeover, the absolute speed value is considered.

Changeover is also possible during operation. When changing over between star and delta operation, it is possible to additionally select between eight drive parameter sets [0...7].

Input/output signals

The following input/output signals are used for this changeover version:

<table>
<thead>
<tr>
<th>Input terminal with function No.</th>
<th>Speed threshold</th>
<th>Effective motor data set</th>
<th>Output terminal with function No.</th>
</tr>
</thead>
<tbody>
<tr>
<td>61)</td>
<td>n&lt;P1247</td>
<td>P1xxx</td>
<td>14a)</td>
</tr>
<tr>
<td>52)</td>
<td>-</td>
<td></td>
<td>13</td>
</tr>
<tr>
<td>144)</td>
<td>n&gt;P1247</td>
<td>P2xxx</td>
<td>12a)</td>
</tr>
<tr>
<td>11</td>
<td>n&lt;P1248</td>
<td>P3xxx</td>
<td>11</td>
</tr>
<tr>
<td>0</td>
<td>n&gt;P1248</td>
<td>P4xxx</td>
<td></td>
</tr>
</tbody>
</table>

1) If the input terminal is used to change over the motor, then the pulses are canceled at the changeover.
2) The input terminal with function number 5 is inactive for this changeover version.
3) The pulses are not canceled if changeover is realized using speed thresholds.
4) Output terminals with function numbers 12 and 14 are not energized.

Note

Output terminals 11 and 13 are not energized, if P1249 = 1.
Motors with star/delta changeover support a wide constant power range.

At lower speeds, the motor is operated in the star circuit configuration (high torque) and at higher speeds, in the delta circuit configuration (high stall torque).

Assumptions for the example:

- The motor is operated with drive A.
- An optional TERMINAL module is used.
- The changeover is realized via the following input/output terminals:
  - I8 (X422.5) P0668 (function, input terminal I8) = 6
  - O8 (X432.5) P0688 (signaling function, output terminal O8) = 11
  - O9 (X432.6) P0689 (signaling function, output terminal O9) = 13
- P1247 = 700
  - i.e. 0 < n < 700 --> motor in the star mode
  - n > 700 --> motor in the delta mode
6.11 Motor changeover for induction motors (from SW 2.4)

1) A safe operating stop is not guaranteed by just opening K1 and K2. This is the reason that for safety-related reasons, contactor $K_x$ should be used to provide electrical isolation. This contactor may only be switched—in the no-current condition, i.e. the pulse enable must be withdrawn 40 ms before the contactor is opened (de-energized).

Fig. 6-90 Recommended circuit: Changing over a motor in star/delta operation

Notice

Main contactors K1 and K2 must be switched in the no-current condition.

If this is not observed, the drive converter and contactors could be destroyed.
### 6.11.5 Parameters for motor changeover

The following parameters are available for motor changeover:

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1013</td>
<td>Enable, motor changeover (ARM)</td>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>PO</td>
</tr>
</tbody>
</table>

... the motor changeover is enabled or the motor changeover type is selected

<table>
<thead>
<tr>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Motor changeover inhibited</td>
</tr>
<tr>
<td>1</td>
<td>Motor changeover with pulse cancellation</td>
</tr>
<tr>
<td>2</td>
<td>Motor changeover without pulse cancellation (data set changeover)</td>
</tr>
<tr>
<td>3</td>
<td>Motor changeover using speed thresholds (P1247, P1248)</td>
</tr>
</tbody>
</table>

**Note:**

It is only possible to enable motor changeover in the "speed/torque setpoint" mode (P0700 = 1).

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1247</td>
<td>Speed threshold motor changeover 1/2 (ARM)</td>
<td>100.0</td>
<td>100 000.0</td>
<td>100 000.0</td>
<td>RPM</td>
<td>immediately</td>
</tr>
<tr>
<td>1248</td>
<td>Speed threshold motor changeover 3/4 (ARM)</td>
<td>100.0</td>
<td>100 000.0</td>
<td>100 000.0</td>
<td>RPM</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... the speed thresholds for the motor changeover are defined with speed threshold (P1013 = 3).

**P1247:**

Below P1247 minus 5% hysteresis, the first motor data set is selected (P1xxx).
Above P1247 plus 5% hysteresis, the second motor data set is selected (P2xxx).

**P1248:**

Below P1248 minus 5% hysteresis, the third motor data set is selected (P3xxx).
Above P1248 plus 5% hysteresis, the fourth motor data set is selected (P4xxx).
6.11 Motor changeover for induction motors (from SW 2.4)

Table 6-66  Parameters for motor changeover, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1249</td>
<td>External contactor control motor changeover (ARM)</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... specifies whether the contactors for motor changeover are controlled from the drive or from an external control.

1  Motor changeover via external control
   The contactor control for the motor changeover is realized using an external control via the "motor changeover" input signal (STW2.11).
   The output terminals with function numbers 11, 12, 13 and 14 are not energized.

0  Motor changeover via drive
   The contactors to change over the motor are controlled from the drive via the output terminals with function numbers 11, 12, 13 and 14.

**Note:**

The contactors used to change-over the motor must be switched in a no-current condition. If an external control is used to changeover the motor, and it is "incorrectly" changed over (e.g. the pulses are present), it is possible that the power/supply infeed module will be destroyed.

**Recommendation:**

Motor changeover should be realized using the drive output terminals (P1249 = 0).
6.12 Travel to fixed stop (positioning mode) (from SW 3.3)

Description

A linear or rotary axis can be traversed in the "positioning" mode by specifying a target position and a maximum possible torque using the "travel to fixed endstop" function. When a fixed stop is reached, then the defined torque/force is established.

This property can be used, e.g. for the following tasks:

- To clamp workpieces (e.g. to press the spindle sleeve against the workpiece)
- Approaching the mechanical reference point
- Carry out simple measuring operations (e.g. with a low torque)

The function is programmed using the FIXED STOP command. The clamping torque must also be specified in this traversing block. The following applies:

<table>
<thead>
<tr>
<th>Drive</th>
<th>Value range and units for the clamping torque/clamping force</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rotating</td>
<td>1 - 65 535 [0.01 Nm]</td>
</tr>
<tr>
<td>Linear</td>
<td>1 - 65 535 [0.01 N]</td>
</tr>
</tbody>
</table>

A selectable fixed endstop monitoring window prevents the drive from continuing after the fixed endstop has been reached (e.g. when the fixed endstop breaks-off).

Note

When jogging (closed-loop speed control), travel to fixed stop is also possible by suppressing fault 608 (speed controller output limited) using the "suppress fault 608" input signal.

The "travel to fixed stop" function may not be used for coupled axes.

Application example

The following applies to axes with incremental measuring system:

After a traversing block has been executed with the "fixed stop" command and the block change enable END, the axis can be re-referenced at the fixed stop using the "set reference point" function.
The following sequence applies for the "travel to fixed stop" function:

- **How is this function started?**

  The function is started when executing a traversing block with the FIXED STOP command.

  The same data as for a positioning set should be made in this traversing block and, in addition, also the clamping torque in \([0.01 \text{ Nm}]\) or the clamping force in \([\text{N}]\) (refer under the index entry "Command-dependent block information").

  In order that the fixed endstop (workpiece) can be reached at all, it must be located between the start and target positions. The target position must be selected a considerable distance behind the fixed stop.

- **How is the axis moved after start?**

  - After starting the block, the axis travels in the direction of the target position with the programmed velocity.
  
  - The clamping torque/clamping force, programmed in this block, already becomes effective from the starting position, i.e. the axis moves to the fixed stop with the reduced torque limit/force limit.
  
  - The dynamic following error monitoring is not effective when traveling to the fixed stop.

- **What happens if ...**

  - ... the fixed stop is reached before the target position is reached (standard case)?
    
      --> refer to "What happens if the fixed stop is reached?"
  
  - ... the fixed stop is not reached, but the target position is approached?
    
      --> refer to "What happens if the fixed stop is not reached?"
  
  - ... the programmed clamping torque is not reached.
    
      --> refer to "What happens if the fixed stop is reached but the programmed clamping torque is not reached?"
  
  - ... the axis is first at the fixed stop and then leaves this position, i.e. has the fixed stop broken off?
    
      --> then the fixed endstop monitoring becomes effective, i.e. the axis then moves by the distance, set in P0116:8 (fixed endstop monitoring window) plus the braking ramp.
      
      --> refer to “fixed endstop” monitoring window
What happens if the fixed stop is reached?

If the axis moves to a fixed stop, then the behavior is as follows:

- The closed-loop drive control increases the torque for the axis up to the programmed clamping torque, and then keeps it constant.
- The “fixed stop reached” status is reached as follows, depending on P0114 (fixed stop, configuration 2):

Table 6-67 Behavior, if the fixed stop is reached

<table>
<thead>
<tr>
<th>If P0114 = 0 (standard)</th>
<th>The status is automatically reached, if the following error exceeds the theoretically calculated following error by the value entered in P0115:8.</th>
<th>Note:</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>Refer under the index entry “Dynamic following error monitoring”</td>
<td></td>
</tr>
<tr>
<td></td>
<td>The following applies for the target position:</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Target position &gt; position, fixed stop + P0115:8 + braking travel</td>
<td></td>
</tr>
<tr>
<td>P0114 = 1</td>
<td>The status is only reached, if it is recognized via the &quot;sensor, fixed stop” input signal.</td>
<td></td>
</tr>
</tbody>
</table>

- The following applies after the “fixed stop reached” status has been recognized:
  - The distance to go is deleted
  - The position reference value is tracked
  - The fixed endstop monitoring is activated
  - The controller enable remains active
  - The “fixed stop reached” output signal is set
  - Is the programmed clamping torque reached?
    Yes ----> the output signal “fixed stop, clamping torque reached” is set
    No ----> the behavior is dependent on P0113.1

Table 6-68 Behavior, if the clamping torque is not reached

<table>
<thead>
<tr>
<th>If P0113.1 = 0 (standard)</th>
<th>Warning 889 is signaled The block change enable is only realized, as programmed in the block, only after the clamping torque has been reached.</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0113.1 = 1</td>
<td>Warning 889 is signaled and a block change is made The block change enable is realized as programmed in the block.</td>
</tr>
</tbody>
</table>

Note: The block change enable CONTINUE FLYING, behaves just like the block change enable CONTINUE WITH STOP.
The clamping torque remains, if ... subsequently, e.g. blocks are processed with the commands WAIT, GOTO, SET_O or RESET_O
There is no subsequent block, i.e. the traversing program has been completed
- the position can be read in P0002 (actual traversing block – position)

**What happens if the fixed stop is not reached?**

If, for a traversing block, the axis moves to the brake initiation point with the FIXED STOP command, without detecting the status "fixed stop reached", then the following behavior applies, dependent on P0113.0:

<table>
<thead>
<tr>
<th>If</th>
<th>Then the following is valid:</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0113.0 = 0 (standard)</td>
<td>Fault 145 is signaled</td>
</tr>
<tr>
<td></td>
<td>The torque limiting is automatically disabled. The axis is braked and comes to a standstill in front of the programmed target position. The deviation from the reference position depends on:</td>
</tr>
<tr>
<td></td>
<td>• Positioning velocity</td>
</tr>
<tr>
<td></td>
<td>• Acceleration</td>
</tr>
<tr>
<td></td>
<td>• Deceleration</td>
</tr>
<tr>
<td>P0113.0 = 1</td>
<td>A block change is made</td>
</tr>
<tr>
<td></td>
<td>The torque limiting is automatically disabled. The block change enable is realized as programmed in the block.</td>
</tr>
</tbody>
</table>

**Canceling the "travel to fixed stop" function**

The "travel to fixed stop" function is interrupted, and if warning 889 is present it is acknowledged, if one of the following occurs:
- The next block is processed with the POSITIONING command
- the jogging mode is selected if previously interrupted
  --> with the input signal "reject operating condition/traversing task"
- The controller enable is withdrawn (--> fault 147)
- Pulse enable is withdrawn (--> fault 147)

**Interrupting or exiting the "travel to fixed stop" function**

The following applies for a traversing block with the FIXED STOP command:
- Interrupt and continue
  --> using the "operating condition/intermediate stop" input signal
- Exit
  --> using the "operating condition/reject traversing task" input signal

In all of these cases, the drive is correspondingly braked.

**Interruption at the fixed stop:**

The drive remains at the fixed stop, and can be moved away from it either in the jog mode, or by starting a new traversing block.
Abort

---> while "travel to fixed stop"

The drive brakes and maintains this position with a reduced torque as "traverse to fixed stop" is still active. The position is monitored using P0326. Fault 145 is signaled when the tolerance window in P0326 is exceeded.

Fixed endstop monitoring window

If the axis travels by more than the monitoring window, set in P0116:8 when it reaches the "fixed stop reached" status, then the "travel to fixed stop" function is canceled as a result of fault 146 (fixed stop, axis outside the monitoring window), and the axis is stopped.

The following applies for the fixed endstop monitoring window:

- Set using P0116:8 (fixed endstop monitoring window).
- The monitoring window generally applies for a drive, which means, in order to adapt it for an individual traversing block, P0116:8 must be correspondingly re-written into before the block starts.
- The value in P0116:8 is valid both in the positive as well as the negative travel directions.
- The window setting must be selected, so that a fault is only initiated if the endstop breaks.

If the monitoring window P0116:8 is set too large (e.g. to the maximum value) and if the fixed endstop breaks away, then the drive accelerates.

From SW 12.1, the following applies: The speed is limited to the value that the drive had before reaching the fixed endstop. The limit is implemented using a two-step control:

- Speed too high --> torque = 0
- Speed too low --> programmed torque

Hanging axis without mechanical weight equalization

For a hanging axis without mechanical weight equalization, when programming the clamping torque and when defining the fixed endstop monitoring window, it must be taken into consideration as to whether the electronic weight equalization is set via P1240:8.

The clamping torque, effective for "travel to fixed stop" is made up as follows:

- Programmed clamping torque in the traversing block

and

- P1240:8 (offset, torque setpoint speed-controlled)

The following applies when programming the clamping torque for a hanging axis without mechanical weight equalization:

Table 6-70 Clamping torque for a hanging axis

<table>
<thead>
<tr>
<th>If</th>
<th>Then</th>
</tr>
</thead>
<tbody>
<tr>
<td>A torque offset is not entered (P1240:8 = 0)</td>
<td>Take into account the weight equalization when programming the clamping torque.</td>
</tr>
<tr>
<td>A torque offset is entered (P1240:8 \neq 0)</td>
<td>The weight equalization is not taken into account when programming the clamping torque</td>
</tr>
</tbody>
</table>
The following diagnostics are available for the activated function:

- Display via P0600 (operating status)
- Display via "travel to fixed stop active" output signal

The motor current, following error, input/output signals and positions for the "travel to fixed endstop" function are illustrated in the following diagram.

---

**Diagnostics for "travel to fixed stop"**

**Signal characteristics**

---

![Diagram showing signal timing for the "travel to fixed stop" function]

- **Motor current**
- **Following error**
- **"Fixed stop sensor" input signal**
- **"Fixed stop reached" output signal**
- **"Fixed stop, clamping torque reached" output signal**
- **Monitoring window**
- **Blocks**
  - * FIXED STOP *
  - * WAITING *
  - * POSITIONING *

**Parameters**

- P0086:64/256: Command parameter - clamping torque
- P0114: Fixed stop, configuration 2
- P0115:8: Fixed stop, maximum following error
- P0116:8: Fixed stop, monitoring window

---

Fig. 6-91  Signal timing for the "travel to fixed stop" function
Travel to fixed endstop and EMERGENCY OFF

Caution

It must be ensured, that after the "travel to fixed endstop" function is withdrawn as a result of EMERGENCY OFF, the machine cannot go into a potentially hazardous state (e.g. the clamped workpiece drops out of the clamping mechanism after EMERGENCY OFF).

Parameter overview (refer to Chapter A.1)

The following parameters are available for the "travel to fixed stop" function:

- P0113 Fixed stop, configuration 1
- P0114 Fixed stop, configuration 2
- P0115:8 Fixed stop, maximum following error
- P0116:8 Fixed stop, monitoring window
- P1240:8 Offset, torque setpoint (speed controlled)
  Offset, force setpoint (speed controlled)

Input/output signals

The following signals are used for the function "traverse to fixed stop":

- Input signals
  (refer under index entry "Input signal, digital - ...")
  - "Fixed stop sensor" input signal
    --> using an input terminal with function number 68
    --> using PROFIBUS control signal PosStw.3
- Output signals
  (refer under the index entry, "Output signal, digital - ...")
  - "Fixed stop reached" output signal
    --> using an output terminal with function number 68
    --> using PROFIBUS status signal PosZsw.12
  - "Fixed stop, clamping torque reached" output signal
    --> using an output terminal with function number 73
    --> using PROFIBUS status signal PosZsw.13
  - "Travel to fixed stop active" output signal
    --> using an output terminal with function number 66
    --> using PROFIBUS status signal PosZsw.14
6.13 Teach-in (from SW 4.1)

**Description**
Using this function, an approached axis position can be directly entered into a specific traversing block as position reference value. The axis can be traversed to the required position e.g. using "jogging" and/or "incremental jogging.

The "teach-in" function is activated using the "activate teach-in (edge)" input signal in the "positioning" mode.

It is not possible to activate "teach-in" while a traversing program is running.

<table>
<thead>
<tr>
<th>Table 6-71</th>
<th>Overview of teach-in</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Question?</strong></td>
<td><strong>Parameter</strong></td>
</tr>
<tr>
<td>In which traversing block is the position value be written?</td>
<td>P0120 = -1 (standard)</td>
</tr>
<tr>
<td></td>
<td>P0120 ≥ 0</td>
</tr>
<tr>
<td>How does the teach-in block become a complete traversing block?</td>
<td>P0121 = -1 (standard)</td>
</tr>
<tr>
<td></td>
<td>P0121 ≥ 0</td>
</tr>
<tr>
<td>Teach-in configuration</td>
<td>P0124.0 = 1</td>
</tr>
<tr>
<td></td>
<td>P0124.1</td>
</tr>
</tbody>
</table>
The following parameters are available for the "teach-in" function:

- P0120   Teach-in block
- P0121   Teach-in standard block
- P0124   Teach-in configuration

The following signals are used for the "teach-in" function:

- **Input signals**
  (refer under index entry "Input signal, digital - ")
  - Input signal "activate teach-in (edge)"
    --> using an input terminal with function number 64
    --> using the PROFIBUS control signal "PosStw.6"
  - up to SW 9.2
    Input signal "block selection 1st to 6th input"
    --> using an input terminal with function number 50-55
    --> using PROFIBUS control signal SatzAnw.0-.5
  - From SW 10.1
    Input signal "block selection 1st to 8th input"
    --> using an input terminal with function number 50-57
    --> using PROFIBUS control signal SatzAnw.0-.7
- **Output signals**
  (refer under the index entry, "Output signal, digital - ")
  - Output signal "teach-in successful"
    --> using an output terminal with function number 64
    --> using the PROFIBUS status signal "PosZsw.15"

**Note**

The positions with teach-in are only transferred into the RAM memory. Data is manually saved using the "SimoCom U" parameterizing and start-up tool with "Save in the drive (FEPROM)".
6.14 Dynamic Servo Control (DSC, from SW 4.1)

**Description**

The "Dynamic Servo Control" (DSC) is a closed-loop control structure which is computed in a fast speed controller clock cycle and is supplied with setpoints by the control in the position controller clock cycle. This allows higher position controller gain factors to be achieved.

**Condition**

The following prerequisites are necessary to use Dynamic Servo Control:

- n-set mode
- Isochronous PROFIBUS-DP
- The position controller gain factor (KPC) and the system deviation (XERR) must be included in the PROFIBUS-DP setpoint telegram (refer to P0915)
- The position actual value must be transferred to the master in the actual value telegram of PROFIBUS-DP via the encoder interface Gx_XIST1 (refer to Chapter 5.6.4)
- When DSC is activated, the speed setpoint N_SOLL_B from the PROFIBUS telegram is used as speed pre-control value
- The internal quasi-position controller uses the position actual value from the motor measuring system (G1_XIST1)
### Activating

If the prerequisites for DSC have been fulfilled, the function is activated by transferring a value for KPC > 0 in the PROFIBUS telegram.

When DSC is activated, the position controller gain in the master should be set again.

If the PROFIBUS control words XERR (system deviation, DSC) and KPC (position controller gain factor, DSC) are activated in the PROFIBUS telegram the closed-loop control structure is also activated. This means that the ramp function generator, for example, is no longer active.

### Deactivating

The DSC function is de-activated by setting KPC = 0. Then, only the speed pre-control is effective.

Higher gain factors can be set using DSC. This is the reason that the control loop can become unstable when DSC is disabled. Before disabling DSC (e.g. for optional tests) the KV factor must be reduced in the master.

### Speed setpoint value filter

When using DSC, a speed-setpoint filter is no longer required to round-off the speed setpoint stages.

When using the DSC function, it only makes sense to use speed setpoint filter 1 to support the position controller, e.g. to suppress resonance effects.

---

Fig. 6-92  Principle of Dynamic Servo Control; the speed setpoint is used for speed precontrol
6.15 Spindle positioning (from SW 5.1)

Description
Using the “spindle positioning” function, in the “n-set” mode, the spindle can be traversed to a specific position and then held there.

Activating
The function is activated in the “n-set” mode (P0700 = 1) via the input signal “spindle positioning on” or via PROFIBUS-DP (STW1.15), if P0125 = 1 (spindle positioning active).

Note
If the “spindle positioning” function is carried-out using NC functionality (e.g. SINUMERIK 802D), then P0125 must be set to 0 (spindle positioning de-activated).

In addition, a traversing block number must be entered via a terminal or PROFIBUS-DP. If a bit is not selected for the traversing block number, then data in traversing block 0 is used.

The following is mainly defined in the traversing block:
- The target position (also via PROFIBUS-DP control word XSP is possible, being prepared)
- The search velocity, and
- How the axis approaches the target position

The target position can be approached as follows:
- With the actual direction of rotation
- With a defined direction of rotation (clockwise, counter-clockwise)

Position actual value sensing
- With a motor encoder (sin/cos 1 Vpp)
- With a motor encoder (sin/cos 1 Vpp) and external zero (BERO) at the spindle when the gearbox stage is being changed-over
- With direct measuring system (spindle encoder, sin/cos 1 Vpp) via encoder connection X412 (drive B)

Boundary conditions
- Spindle positioning only with motor 1.
- If spindle positioning has been selected, then the encoder information for PROFIBUS-DP (G1_STW, G1_ZSW) is no longer precisely transferred.
- If “spindle positioning on” is selected using a terminal or PROFIBUS-DP (for P0125 = 1), then the “relative” positioning mode (P0087:64/256) may no longer be programmed in the currently selected traversing block.
- When spindle positioning is selected, it is not possible to change over the motor via PROFIBUS-DP.
- Spindle positioning is not supported in conjunction with the absolute distance-coded measuring systems.
Positioning operation

If the drive has still not been referenced, it is automatically referenced after activating the "spindle positioning on" function.

The positioning operation is executed via the position controller and is carried out in several phases:

1. Selecting the "spindle positioning on" function via terminal or PRO-FIBUS-DP in the "n-set" mode
2. Traversing to the search velocity
3. Traversing with search velocity and searching for the zero mark (BERO)
4. Braking to the 1st target position (angle)

![Diagram showing the positioning operation steps](image_url)

If the drive is at the 1st target position, then the additional target positions can be approached immediately by selecting another traversing block.

In order to guarantee a defined changeover to the next position (via terminals), only one bit should be changed when selecting the traversing block.

If, when the controller is inhibited, the spindle is pushed (pressed) out of a parameterized tolerance window (P0131), then the position actual value is corrected (tracked). If the controller is then re-enabled, the spindle remains at that particular position. It is only re-positioned again if "spindle positioning" is activated.

Parameter overview (refer to Chapter A.1)

The following parameters are available for the "spindle positioning" function:

- **P0080:256** Block number (traversing blocks)
- **P0081:256** Position reference value (traversing blocks)
- **P0082:256** (Search) velocity (traversing blocks)
- **P0083:256** Acceleration override
- **P0084:256** Deceleration override
- **P0087:256** (Spindle) positioning mode
- **P0102** Maximum velocity
- **P0103** Maximum acceleration
- **P0104** Maximum deceleration
- **P0125** Spindle positioning active
- **P0126** Spindle positioning, zero mark tolerance window
- **P0127** Spindle positioning, setting the internal zero mark
- **P0128** Spindle positioning, offset, zero mark
6.15 Spindle positioning (from SW 5.1)

The following diagnostic parameters are available for the "spindle positioning" function:

- **P0129** Spindle positioning, tolerance, search velocity
- **P0130** Spindle positioning, lowest search velocity
- **P0131** Spindle positioning, motion window
- **P0133** Spindle positioning, max. search velocity
- **P0174** Referencing mode - position measuring system
- **P0200:8** Kv factor (position loop gain)
- **P0231** Position act. value inversion
- **P0232** Position ref. value inversion
- **P0237:8** Encoder revolutions
- **P0238:8** Load revolutions
- **P0242** Modulo range, rotary axis
- **P0250** Activating the direct measuring system

Setting values for the position actual value monitoring:

- **P0132** Spindle positioning, zero mark difference (bero)
- **P0136** Spindle positioning, active/inactive
- **P0137** Spindle positioning, status

**Warning**

When the monitoring is disabled via parameters P0318:8, P0321 and P0326, it should be noted that under fault conditions, the drive can accelerate up to the max. speed.
### 6.15 Spindle positioning (from SW 5.1)

The target position approach is defined using the parameters of the selected traversing block.

#### Table 6-72 Parameters for "spindle positioning"

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Parameter text</th>
<th>Value and description</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0080:N</td>
<td>Block number</td>
<td>0... 63</td>
</tr>
<tr>
<td>P0081:N</td>
<td>Position</td>
<td>Target position in degrees</td>
</tr>
<tr>
<td>P0082:N</td>
<td>Velocity</td>
<td>Search velocity in degrees/min. The velocity is always referred to the load side, i.e. for a ratio of 4:1 (motor/load), the motor rotates 4 x faster.</td>
</tr>
<tr>
<td>P0083:N</td>
<td>Acceleration override</td>
<td>This allows the acceleration to be influenced, referred to P0103.</td>
</tr>
<tr>
<td>P0084:N</td>
<td>Deceleration override</td>
<td>This allows the deceleration to be influenced, referred to P0104.</td>
</tr>
<tr>
<td>P0087:N</td>
<td>Mode</td>
<td>U = target position input</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0: Input via traversing block (P0081:N)</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1: Input via PROFIBUS-DP; control word XSP (Signal No. 50109)</td>
</tr>
</tbody>
</table>

**W = Positioning mode**

The behavior when approaching the target position is defined in parameter P0087. The behavior depends on whether the "spindle positioning" function is already active and the 1st position was approached or not.

<table>
<thead>
<tr>
<th>Behavior for nset active</th>
<th>Behavior if the 1st target position has already been reached</th>
</tr>
</thead>
<tbody>
<tr>
<td>W = 0 ABSOLUTE (Standard)</td>
<td>The position is approached with the actual direction of rotation The new target position is approached through the shortest distance</td>
</tr>
<tr>
<td>W = 1 RELATIVE</td>
<td>Not supported The new position is incrementally approached.</td>
</tr>
<tr>
<td>W = 2 ABS_POS</td>
<td>The position is approached in the positive direction. The new target position is approached in absolute terms and in the positive direction (clockwise rotation)</td>
</tr>
<tr>
<td>W = 3 ABS_NEG</td>
<td>The position is approached in the negative direction. The new target position is approached in absolute terms and in the negative direction (counter-clockwise).</td>
</tr>
</tbody>
</table>
Structure of the traversing block

<table>
<thead>
<tr>
<th>No. (P0080)</th>
<th>Command (P0087)</th>
<th>Mode (P0081)</th>
<th>Position (P0082)</th>
<th>Velocity (degrees/min)</th>
<th>Acceleration (referred to P0103)</th>
<th>Deceleration (referred to P0104)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Positioning</td>
<td>ABSOLUTE</td>
<td>0°</td>
<td>72000</td>
<td>100 %</td>
<td>100 %</td>
</tr>
<tr>
<td>1</td>
<td>Positioning</td>
<td>ABS_POS</td>
<td>90°</td>
<td>3600</td>
<td>100 %</td>
<td>100 %</td>
</tr>
</tbody>
</table>

1) only this entry is possible

Fig. 6-94 Example: Programming the traversing block

If no bit is selected when selecting the block with the "spindle positioning on" command, then traversing block 0 is automatically selected. The axis then positions with the values from traversing block 0.

In the example, Fig. 6-94 (Standard setting) the drive moves to the position value 0 degrees from the actual speed and direction of rotation, at a search velocity of 72000 degrees/min (200 RPM).

If bit 0 is set in this state, when selecting the traversing block (via terminal or PROFIBUS-DP), then the drive rotates according to the ABS_POS mode in the clockwise sense with the max. velocity of 3600 degrees/min and remains stationary at the 90 degrees position.

After bit 0 is switched-out, the axis moves from 90 degrees to 0 degrees.

The "spindle positioning on" command must always be present. If the command is switched-out, then the axis rotates at the speed of the currently effective speed setpoint.

Search rate

The search velocity depends on the initial velocity at the instant that the "spindle positioning" function is activated at n-set (refer to Fig. 6-95).

In this case, the following parameters are effective:

- P0082:256 Velocity
- P0083:256 Acceleration override
- P0084:256 Deceleration override
- P0103 Max. acceleration
- P0104 Max. deceleration
- P0129 Spindle positioning, tolerance, search velocity
- P0130 Spindle positioning, lowest search velocity
- P0133 Spindle positioning, max. search velocity
- P1256:8 Ramp-function generator, ramp-up time
- P1257:8 Ramp-function generator, ramp-down time
In this velocity range, the drive accelerates to the search velocity \( v_1 \). The drive traverses to the target position if the zero mark is recognized.

2. In this velocity range (search velocity), the drive traverses without changing its velocity until the zero mark has been recognized. The drive then traverses to the target position.

3. In this velocity range, the drive brakes to the search velocity \( v_2 \). The drive traverses to the target position if the zero mark is recognized.

Condition: The maximum velocity \( P0102 \) must be greater than \( v_2 \).

**Spindle positioning, zero mark offset**

Procedure to shift the zero mark and set it to a specific value:

1st possibility:
- Enter the zero mark offset directly into \( P0128 \).

2nd possibility:
- Traverse the spindle to the required position, e.g. manually rotate
- Set \( P0127 \) to 1. This means that the actual position value is transferred into \( P0128 \). \( P0127 \) automatically changes to 0.
6.15 Spindle positioning (from SW 5.1)

Encoder configuration effective

P0250 and P0174 must be set to the existing measuring system.

Table 6-73 Encoder configuration for spindle positioning

<table>
<thead>
<tr>
<th>Encoder configuration</th>
<th>P0250</th>
<th>P0174</th>
</tr>
</thead>
<tbody>
<tr>
<td>Indirect measuring system (motor encoder) with encoder zero mark</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>In addition, the gearbox ratio must be entered into P0237:8 (encoder revolutions) and P0238:8 (load revolutions)</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Indirect measuring system (motor encoder) with external zero mark</td>
<td>0</td>
<td>2</td>
</tr>
<tr>
<td>In addition, the gearbox ratio must be entered into P0237:8 (encoder revolutions) and P0238:8 (load revolutions)</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Direct measuring system with encoder zero mark</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

It is possible to select position actual value inversion using parameter P0231.

Spindle drive with gearbox (BERO)

For spindle drives with gearboxes, an external zero mark (BERO) should be provided as reference point if the spindle has to be positioned.

For multi-stage gearboxes, the gearbox stage ratios must be taken into account. The ratios must be entered via parameter P0237 (gearbox revolutions) and P0238 (load revolutions). For parameter set 0, the ratio of the first gearbox stage can be defined using SimoCom U in the menu screen "Mechanical system" (1:1 is the basic setting).

Additional gearbox stage ratios must be entered using the Expert list (P0237:x, P0238:x; x = 1 to 7).

Example:

If a changeover gearbox with a ratio of 1:1 or 1:4 is used, for the 1st gearbox stage, parameters P0237:0 and P0238:0 remain unchanged (because 1:1) and for the ratio 1:4, the following values are entered into parameters P0237:1 = 1 and P0238:1 = 4. These values become valid after "Power on".

The ratio can be checked using parameter P0132. In this case, the distance between two zero marks is displayed in degrees. If the values which are displayed deviate from 360 degrees, then the gear-up/gear-down ratio was not correctly parameterized.
Input/output signals (refer to Chapter 6.4)

The following signals are used for the "spindle positioning" function:

- **Input signals**
  (refer under the index entry "Input signal, digital - ...")
  - Input signal, "spindle positioning on"
    --> using an input terminal with function number 28
    --> using the PROFIBUS control signal "STW1.15"
  - Input of traversing blocks
    --> via an input terminal, or
    --> via PROFIBUS-DP

  When the traversing block selection is changed (number), the position is immediately changed to the position specified in the traversing block.

- **Output signals**
  (refer under the index entry, "output signal, digital - ...")

  The output signals are only effective when selecting "spindle position on".
  - Output signal, "spindle positioning on"
    --> using an output terminal with function number 28
    --> using the PROFIBUS status signal "ZSW1.14"
  - Output signal "spindle position reached"
    --> setting a window with P0134
    --> using an output terminal with function number 59
    --> using PROFIBUS status signal "MeldW.15"
  - Output signal "reference position reached/outside reference position"
    --> setting values with P0320, P0321
    --> using an output terminal with function number 60
    --> using PROFIBUS status signal "MeldW.14"
6.15 Spindle positioning (from SW 5.1)

Short commissioning (example)

Hardware structure: Encoder signals and zero pulse from the motor encoder

Software prerequisites:
- Software release \( \geq \) SW 5.1
- The spindle positioning program must be activated via SimoCom U or P0125 = 1.
- Select the "spindle positioning on" function via terminal (Fct. No. 28) or PROFIBUS-DP (STW1.15). (e.g. "spindle position-i on" via terminal I2.A).

1. Enable the controller and pulses
2. Select "spindle position on"
   ---> the spindle positions to the position specified in traversing block 0

Is a zero offset required?

-- No

1. Inhibit the controller
2. Disable the selection of "spindle positioning on"

Can the position be selected by manually rotating the spindle?

-- No

1. Rotate the spindle to the required position
2. Set the actual position as zero position using the SimoCom U menu screen "Spindle positioning" or set P0127 to 1
   ---> Zero mark offset is displayed using P0128

Enter the zero offset value in degrees, either directly via P0128 or SimoCom U or enable the controller; approach the position and set the actual position as zero mark via SimoCom U or set P0127 to 1. When setting the zero position, the controller inhibit and the "spindle position on" selection must be disabled.

Save the new zero mark (P0652 = 1)

Fig. 6-96 Commissioning example, spindle positioning
1. Current controller
2. Speed controller
3. Ramp-up/ramp-down time (P1256:8/P1257:8)
4. Search velocity via P0082 (traversing block), if necessary, increase P0133
5. Max. deceleration/acceleration (P0103, P0104) and input the override via traversing blocks
6. Position controller ($K_v$ factor adaptation via P0200:8)

**Note:**
Observe the parameter set changeover!

Save parameters which have been changed

End
6.16 Rotor position identification/pole position identification

**Note**
Terminology change:
Rotor position identification (RLI), corresponds to the pole position identification (PLI)!

**Description**
Drive converters with field-orientated closed-loop control impress the current into permanent-magnet synchronous motors to establish the magnetic flux in the motor. At power-on, the rotor position identification (RLI) automatically determines the absolute rotor position using the maximum of the magnetic flux.

The rotor position identification is used for:
- Determining the rotor position (coarse synchronization and fine synchronization)
- Supports commissioning when determining the commutation angle offset

Two techniques can be used for the rotor position identification routine:
- For the technique based on saturation (P1075 = 1)
- A technique based on movement (P1075 = 3) (from SW 6.1).

The particular technique can be selected using parameter P1075.

**Coarse synchronization**

Determining the rotor position
The rotor position identification routine automatically determines the motor rotor position. This means that the motor encoder does not require any additional position information from the encoder (C/D track). For linear motors, Hall sensors are not required if the limitations and secondary conditions are maintained.

**Fine synchronization**

- with zero marks: P1011.13 = 0
  For the fine synchronization (P1011.13 = 0), the commutation offset is transferred when passing the zero mark.
  Advantages:
  - The fine synchronization with zero mark guarantees a consistent and optimum and force and torque utilization.
  - An increase in robustness thanks to renewed encoder monitoring (absolute information and internal pole position).
  Parameter P1016 must be appropriately set.

**Notice**
When replacing the motor/encoder, the commutation angle (P1016) must be re-determined.

- with pole position identification: P1011.13 = 1
  For P1011.13 = 1, fine synchronization is replaced by the pole position identification. P1016 is not effective.
Encoder adjustment is not required if the rotor position identification routine is used for coarse and fine synchronization.

In P1011, bit 12 (identify coarse position) is set in order that the rotor position identification technique is initiated when powering-up the drive. If bit 13 is set (fine position identification), a rotor position identification is executed independently of bit 12.

The following parameters are used for the rotor position synchronization/rotor position identification:

- P1011 IM configuration, actual value sensing
- P1016 Angular commutation offset
- P1017 Commissioning support
- P1019 Current, rotor position identification
- P1020 Maximum rotation, rotor position identification (SRM)
  Maximum movement, rotor position identification (SLM)
- P1075 Technique, rotor position identification
- P1076 Load moment of inertia RLI (SRM)
  Load mass RLI (SLM)
- P1523 Time constant, speed actual value filter (PT1) RLI (from SW 9.1)

The following diagnostics parameters are used rotor position synchronization/rotor position identification:

- P1734 Diagnostics, rotor position identification
- P1736 Test, rotor position identification
- P1737 Difference, rotor position identification

The techniques can only be started when the controller and pulses are enabled as current must flow through the motor.

When using an absolute motor measuring system, the rotor position identification can only be used to determine the commutation angle offset (P1016).

The technique can only be started when the controller and pulses are enabled as current must flow through the motor.

This technique can be used for both braked and non-braked motors.

The technique cannot be used for motors which are moving.

The current which is entered must be adequate in order to generate a significant measuring signal.

The measurement and evaluation take approx. 250 ms.
Due to the different mechanical designs, for the motion-based rotor position identification technique, the result must be checked once when the drive system is first commissioned. The deviation of measured rotor position should be < 10° electrical.

The measuring system must stiffly mounted.

The axis static friction must be low in comparison to the rated motor force or rated motor torque. An excessively high static friction can have a significant negative impact on the accuracy of the rotor position identification and, under certain circumstances, make it impossible to execute the rotor position identification with motion.

The technique may only be used for horizontal axes which can freely move and which do not have a brake.

During the rotor position identification run, it is not permissible that external forces are applied to the motor.

If the previous secondary conditions/limitations are not fulfilled, then linear motors can only be operated with Hall sensor boxes or with absolute measuring systems.

When this technique is used, under worst case condition, movement in the range of ± 10 mm or ±5 degrees can occur.

In the pos mode, until the identification has been completed, the axis to be identified must be set in the follow-up mode in order to suppress fault 135 during the identification routine (standstill monitoring).

When starting the rotor position identification routine via P1736 as a test:
- For a test start, fault 135 (standstill monitoring) can be output, which must be acknowledged with RESET.
- For coupled axes, the test start for rotor position identification is not permitted

**Warning**

When the motors are not braked, the motor rotates or moves as a result of the current impressed during the measurement. The magnitude of the motion depends on the magnitude of the current and the moment of inertia of the motor and load.
6.16 Rotor position identification/pole position identification

Parameterization for the motion-based technique (P1075 = 3) (from SW 6.1)

For the parameterization of the rotor position identification for the motion-based technique, initially, a rotor position identification run must be made with a standard parameterization.

The noise which is generated should be heard as a sequence of soft surges.

The following should be done if faults occur:

- Fault 611 (inadmissible motion):
  --> Increase the parameterized load mass (P1076), check the maximum permissible motion (P1020) and if required, increase.

- Fault 610 (rotor position identification unsuccessful) and P1734 = -4 (current rise too low):
  --> The motor is not correctly connected
  --> The motor power connections must be checked.

- Fault 610 (rotor position identification unsuccessful) and P1734 = -6 (max. permissible duration exceeded):
  --> This can be due to the following reasons:
    - external forces have faulted the identification routine (e.g. coupled axes have not been opened, surges, etc.),
    - if the drive emits an excessive noise (a loud whistling sound) during the identification routine, then the identification technique has become unstable:
      --> P1076 must be reduced,
      from SW 9.1 also possible in the negative range
    - Extremely low encoder resolution:
      --> use an encoder with a higher resolution
    - encoder mounting is not stiff enough:
      --> improve the mounting.

- Fault 610 (rotor position identification unsuccessful) and P1734 = -7 (no clear rotor position has been found):
  --> This can be due to the following reasons:
    - the axis cannot freely move (e.g. the motor rotor is locked)
    - external forces have disturbed the identification routine (refer above)
    - the axis has an extremely high friction:
      --> the identification current (P1019) must be increased

If the rotor position identification routine was successful, the rotor position which was found should be checked. This test function can determine the difference between the determined rotor position angle and the rotor position angle used by the closed-loop control.

The following procedure should be applied several times:

1. Start the test function using P1736 = 1.
2. Evaluate the difference in P1737 – a spread of the measured values of less than 10 degrees is acceptable. If this is not the case, then a higher current must be used for the identification routine (P1019).
Steps when commissioning the system

1. Step: Determine the pole position
   - Incremental measuring system (with zero mark)
     Set P1011.12 = 1
     Set P1011.13 = 0
     Carry-out a HW-RESET
     Set P1017.0 = 1
     Switch-in the pulse and controller enable signals
     Move the axis over the zero mark (e.g. enter low n_{set})
     --> The angular offset is automatically entered into P1016
     --> Fault 799 is displayed
       (Save to FEPROM and HW-RESET required)
       Save to FEPROM and carry-out a HW-RESET
   - Absolute measuring system (with CD track)
     Power-up with the controller and pulses disabled
     Set P1017.0 = 1
     Switch-in the controller and pulse enable
     --> The angular offset is automatically entered into P1016
     --> Fault 799
       (Save to FEPROM and HW-RESET required) is displayed
       Save to FEPROM and carry-out a HW-RESET

2. Step: Check the pole position
   To check the rotor position identification, using a test function, you can determine the difference between the calculated rotor angle position and that actually used by the closed-loop control. Proceed as follows:
   - Start the test function several times and evaluate the difference
     Start Set P1736 (test rotor position identification) to 1
     Difference P1737 (difference, rotor position identification)

     = - - - -' - - - -' - - - -' - - - -' - - - -'

   - Is the spread of the measured values less than 2 degrees electrical?
     Yes: OK
     No: Increase P1019 (e.g. by 10 %)
     and repeat the measurements
     If OK after having repeated the measurements, then the angular commutation offset can be re-determined:
     For an incremental measuring system:
     as for Point 2. (determining the angular commutation offset)
6 Description of the Functions

6.16 Rotor position identification/pole position identification

For an absolute measuring system:
Power—down the drive (POWER ON—RESET)
Power—up the drive with the pulse or controller enable signals switched—out
Set P1017.0 to 1
Switch—in the pulse and enable signals
--> The angular offset is automatically entered into P1016
--> Fault 799 (Save to FEPROM and HW—RESET required) is displayed
Save to FEPROM and carry—out a HW—RESET

Supplement from SW 9.1

Measuring systems with coarser encoder resolution are being increasingly used. This is the reason that when carrying—out a rotor position identification routine, method 3 (P1075 = 3), it is possible to enter a time constant for the speed actual value filtering using P1523 during the rotor position identification routine. P1522 is then not effective during the pole position identification.

Plausibility monitoring, encoder (from SW 10.1)

To increase the ruggedness of the drive as regards incorrect encoder information, rotor/pole position identification is carried out after every ramp—up function and each time a parking axis is deselected. The result is compared with the rotor position calculated using the absolute encoder information. If the deviation is more than 45 degrees, an error is recorded.

Note:
An offset by one of more pole pitches cannot be detected!

Fig. 6—98 Limits of plausibility monitoring (rotary axis example)
6.16 Rotor position identification/pole position identification

Activation with P1011:

- Bit 10 = 0 --> No rotor/pole position check (standard)
- Bit 10 = 1 --> Automatic rotor/pole permissible check permitted

![Flowchart](image)

Fig. 6-99 Plausibility monitoring for absolute encoder

**Note**

P1019 must be adapted at the motor.
For P1075 = 3 (motion-based) - the motor can move.
For P1075 = 1 (saturation-based) - noise can be emitted.
The secondary conditions/constraints for both of these techniques must be carefully observed!
6.17 Electrical braking when the encoder fails (from SW 9.1)

Description
For a feed drive with synchronous motor (SRM, SLM), if the encoder fails without the encoder information, then the drive is braked up to the changeover speed/velocity parameterized in P1466.

Note
Electrical braking when the encoder fails has not been designed for operation with coupled axes!

Activating
The function “electrical braking when the encoder fails” is activated with P1049 = 1. The standard setting (default setting) is P1049 = 0.

Braking sequence
If P1049 = 1, then braking is carried-out in the following steps:
- Initially, the pulse inhibit is suppressed.
- The speed controller enable to initiate braking is simultaneously withdrawn.
- The drive brakes down to the changeover speed/velocity parameterized in P1466. The pulses are only inhibited then and the motor costs down.
- If the motor speed/velocity at the instant that the encoder fails lies below the changeover speed/velocity defined in P1466, then the pulse inhibit is directly initiated and the motor coasts down.

Boundary conditions
- The timer for pulse cancellation in P1404 should be greater than the duration of the braking operation.
- The changeover speed/velocity P1403 should be less than the value of the changeover speed/velocity in P1466.
- The maximum torque for a regenerative stop is always reduced with P1097.
- The function to monitor whether the speed controller is at its end-stop is always disabled (P1096.1 = 1).
- The following criteria always apply for the use, otherwise fault 722 is output:
  - Rotating motors (SRM) P1466 > 40000/P1114
  - Linear motors (SLM): P1466 > 1386/P1114
When commissioning a motor, P1466 is automatically set to this limit.
6.17 Electrical braking when the encoder fails (from SW 9.1)

---

**Note**

This braking can withdraw a large proportion of the kinetic energy from the system. This means that at the end the motor coasts down with a low amount of energy and depending on the particular application and the motors selected, the machinery construction OEM should provide additional protective measure.

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**Parameter overview (refer to Chapter A.1)**

The following parameters are used for "electrical braking when the encoder fails":

- P1049 Activate EMF brake (SRM SLM)
- P1097 Red. max. torque for regen. stop
- P1403 Shutdown speed, pulse cancellation (SRM)
  
  (SLM)
- P1404 Timer, pulse cancellation
- P1466 Changeover speed, closed-loop control/pulse cancellation (SRM)
  
  (SLM)
6.18 Active oscillation damping (APC, from SW 10.1)

Description

Mechanical oscillation/vibration in the tool and at the machine can be dampened using control-related measures in the form of this function. The required damping is achieved by means of feedback or input of suitable signals from the direct measuring system of an axis to the speed setpoint.

![Diagram of Active Oscillation Damping (APC)](image_url)

Fig. 6-100 Principle APC structure
Activating

Activating with P1560 bit 5.
- Bit 5 = 0 --> APC is de-activated
- Bit 5 = 1 --> APC is activated
- Bit 6 Reserved
- Bit 7 Selecting the input for 2nd cascade APC
- Bit 8 Filter input APC of the function generator
- Bit 9 Do not connect filter output of APC
- Bit 10 Input 1st cascade APC
- Bit 11 Speed control with direct measuring system (pulse de-coupling)
- Bit 12 Reserved
- Bit 13 APC, disable 1st cascade
- Bit 14 APC, disable 2nd cascade
- Bit 15 Reserved

Additionally:
- The direct measuring system must be activated (P0250 = 1) during nset mode and the position actual value transferred to the higher-level control.
- P1562 must be pre-assigned.

Boundary conditions

- An axis must have two measuring systems – i.e. a motor measuring system and a direct measuring system. This means that APC can only be used for 1 axis.
- APC only functions with "SIMODRIVE 611 universal HR/HRS".
- The mechanical components to be dampened must be suitable.

Caution

Exercise caution for axes holding workpieces and axes where the mass changes!
The following sequence is practical when commissioning:

1. Define the APC mode (P1560).

2. Parameterize the ratio between the motor measuring system and direct measuring system.

The ratio is entered as a factor, by which the direct measuring system pulse frequency must be multiplied in order to obtain the motor measuring system pulse frequency - assuming uniform, consistent motion. This includes the measuring system resolution differences and any gearbox or measuring gearbox, which are possibly being used. If the direction of rotation is different, then this is taken into account with a negative sign. The sign is included in the ratio.

*Example 1:*
Rotating motor, 2,048 pulses/rev, with a ball screw pitch of 10 mm/rev, direct measuring system 20 μm.
Converted to the motor side: (10 mm/rev)/(20 μm) = 500 pulses per motor revolution on the load side; factor: 2048/500 = 4.096

*Example 2:*
Rotating motor, 2048 pulses/rev, gearbox to the load with a ratio or 25:1, rotating load with load measuring system 8192 pulses/rev. 8192/25 pulses per motor revolution on the load side; factor: 2048/8192 ⋅ 25 = 6.25

*Example 3:*
Rotating motor, 2048 pulses/rev, load directly coupled to the direct measuring system 1024 pulses/rev
Converted to the motor side: 1024 pulses per motor revolution on the load side; factor: 2048/1024 = 2.0

3. Define the acceleration filter type (P1570:8).

4. Parameterize the sub-sampling of the acceleration filter (P1569).

The sub-sampling factor is entered here for filters 1, 2, 4, and 5.

1 means no sub-sampling (standard).

Sub-sampling should be used for filters with a low blocking frequency. It is generally recommended that

Blocking frequency ⋅ Sampling time ⋅ Sub-sampling factor should be ≥ 1/160.

This can easily be ensured using the sub-sampling factor. It is effective for filters 1, 2, 4, and 5. The 3rd filter is always processed in the speed controller cycle and can serve to interpolate the filters, which have been sub-sampled. All filters can only be deactivated by being suitably parameterized (e.g., using default values); there is no on/off switch.

5. Parameterize the filter characteristics (P1571:8...P1594:8)
Note

Filters 1 and 2 or 4 and 5 can be disabled by selecting PT1 and setting the time constant to zero.

Filter 3 cannot be configured as PT1 and therefore cannot be disabled.

The "SimoCom U" start-up tool is used to display the filter frequency characteristics.

Parameter overview (refer to Chapter A.1)

The following parameters are used for APC:

- P1560  APC mode (ARM SRM)
  APC mode (SLM)
- P1562  Ratio, motor to DM (ARM SRM)
  Ratio, motor to DM (SLM)
- P1564:8 Derivative action time, load speed controller (ARM SRM)
  Derivative action time, load velocity controller (SLM)
- P1567:8 Derivative action time, load speed controller 2 (ARM SRM)
  Derivative action time, load velocity controller 2 (SLM)
- P1569  Sub-sampling, accel. filter (ARM SRM)
  Sub-sampling accel. filter (SLM)
- P1570:8 Type, acceleration filter (ARM SRM)
  Type, acceleration filter (SLM)
- P1571:8 Time constant, accel. filter 1 (ARM SRM)
  Time constant, accel. filter 1 (SLM)
- P1572:8 Denom., natural freq. Accel. filter 1 (ARM SRM)
  Denom. natural freq. Accel. filter 1 (SLM)
- P1573:8 Denom. damping accel. filter 1 (ARM SRM)
  Denom. damping accel. filter 1 (SLM)
- P1574:8 Numerator natural freq. Accel. filter 1 (ARM SRM)
  Numerator natural freq. Accel. filter 1 (SLM)
- P1575:8 Numerator damp. accel. filter 1 (ARM SRM)
  Numerator damp. accel. filter 1 (SLM)
- P1576:8 Time constant, accel. filter 2 (ARM SRM)
  Time constant, accel. filter 2 (SLM)
- P1577:8 Denom., natural freq. Accel. filter 2 (ARM SRM)
  Denom. natural freq. Accel. filter 2 (SLM)
- P1578:8 Denom. damping accel. filter 2 (ARM SRM)
  Denom. damping accel. filter 2 (SLM)
- P1579:8 Numerator natural freq. Accel. filter 2 (ARM SRM)
  Numerator natural freq. Accel. filter 2 (SLM)
- P1580:8 Numerator damp. accel. filter 2 (ARM SRM)
  Numerator damp. accel. filter 2 (SLM)
6 Description of the Functions

6.18 Active oscillation damping (APC, from SW 10.1)

- P1581:8 Denom., natural freq. Accel. filter 3 (ARM SRM)
  Denom. natural freq. Accel. filter 3 (SLM)
- P1582:8 Denom. damping accel. filter 3 (ARM SRM)
  Denom. damping accel. filter 3 (SLM)
- P1583:8 Numerator natural freq. Accel. filter 3 (ARM SRM)
  Numerator natural freq. Accel. filter 3 (SLM)
- P1584:8 Numerator damp. accel. filter 3 (ARM SRM)
  Numerator damp. accel. filter 3 (SLM)
- P1585:8 Time constant, accel. filter 4 (ARM SRM)
  Time constant, accel. filter 4 (SLM)
- P1586:8 Denom., natural freq. Accel. filter 4 (ARM SRM)
  Denom. natural freq. Accel. filter 4 (SLM)
- P1587:8 Denom. damping accel. filter 4 (ARM SRM)
  Denom. damping accel. filter 4 (SLM)
- P1588:8 Numerator natural freq. Accel. filter 4 (ARM SRM)
  Numerator natural freq. Accel. filter 4 (SLM)
- P1589:8 Numerator damp. accel. filter 4 (ARM SRM)
  Numerator damp. accel. filter 4 (SLM)
- P1590:8 Time constant, accel. filter 5 (ARM SRM)
  Time constant, accel. filter 5 (SLM)
- P1591:8 Denom., natural freq. Accel. filter 5 (ARM SRM)
  Denom. natural freq. Accel. filter 5 (SLM)
- P1592:8 Denom. damping accel. filter 5 (ARM SRM)
  Denom. damping accel. filter 5 (SLM)
- P1593:8 Numerator natural freq. Accel. filter 5 (ARM SRM)
  Numerator natural freq. Accel. filter 5 (SLM)
- P1594:8 Numerator damp. accel. filter 5 (ARM SRM)
  Numerator damp. accel. filter 5 (SLM)
6.19 Activate function generator immediately (from SW 11.2)

Description

The function generator can be activated immediately in the "Speed/torque setpoint" mode by using the "Activate function generator immediately" input signal.

Input/output signals

"Activate function generator immediately" activation:

- Using input terminal with function number 2
- Using PROFIBUS control word STW1.9

"Function generator active" message/display:

- Using an output terminal with function number 24
- Using PROFIBUS status word ZSW1.13

Boundary conditions

The "Activate function generator immediately" input signal cannot be activated simultaneously for Drive A and B. If the function generator is activated for Drive A and B or is parameterized incorrectly, Warning 824 "Faulty function generator" is triggered with additional information.

Note

The "Oscillate" function of the "SIMODRIVE 611 analog" can be simulated by using the "Activate function generator immediately" input signal. The parameters of the "Function generator" function are to be parameterized in a suitable manner (see Chapter 7.4.1).

The "PRBS white noise" function generator waveform is not suitable for the oscillating function. This waveform does not have any interlocking for "oscillating"!

Starting via PROFIBUS-DP is only possible if bit 6 is set to 1 in P0878.

If the oscillation function is canceled (controller enable is withdrawn) then the drive brakes along the braking ramp P1813. At zero speed, oscillation is ended and the drive is switched into the "Positioning" operating mode.
6.20 Monitoring of the direction of the axis motion (from SW 11.1)

Description

The ruggedness of the drive system with regard to encoder and pole position faults can be increased with this function.

It offers a solution for the following faults:

- Faulty absolute information from the encoder and thus false pole position information
- Demagnetized synchronous machine with faulty pole position identification

A check is carried out whether the acceleration/velocity of a machine always corresponds to the direction of the torque/force, referenced to all the torques/forces existing in the system. In the process, oscillatory systems, external torques/forces and the energy storage in the system are taken into account.

If the speed controller is longer at its limit than the period parameterized in P1645 and the direction of acceleration/speed and torque/force differs, Fault 510 is reported.

Activating

Activating with parameter:

- P1645 Missing orientation timer
  Parameterization of the duration for which speed controllers may have different directions during the acceleration/velocity and torque/force at the same limit.
- P1646 Threshold deactivating of the direction monitoring
  Parameterization from which speed/velocity the direction monitoring is to be deactivate.

Boundary conditions

The direction monitoring is activated by default. It can be deactivated by setting P1646 = 0. This may be necessary at the following applications:

- External torque
- Oscillating system
- Vertical axes
- Axes coupled at HLA
- Master slave with bias
- Traversing to fixed stop
- Extremely fast axis (reversing in 10 ms)
6.21 Power section derating (from SW 13.1)

Description

In order to protect the power section, currents $I_{\text{max}}$, $I_{\text{rated}}$ and $I_{\text{6}}$ must be reduced depending on the frequency, the ambient temperature and the installation altitude when compared to the standard power section values listed in the catalog (derating).

For “SIMODRIVE 611 universal”, the derating characteristic is determined as follows:

\[
\begin{align*}
&\text{Ambient temperatures up to 40 }^\circ\text{C} \\
&\quad \text{I} \\
&\quad 100\% \\
&\quad X1 \\
&\quad 0\% \\
&\quad f_0 \\
&\quad 8 \\
\end{align*}
\]

Fig. 6-101 Derating characteristic

If the pulse frequency $f_1$ (P1100) is higher than frequency $f_0$ (for SRM, SLM or PE spindle “FD operation in field weakening” (P1015 = 1 and P1172 = 1): 4 kHz, for ARM or PE spindle (P1015 = 1 and P1172 = 0): 3.2 kHz), the maximum permissible current of the power section (P1108 or P1175) is linearly reduced according to the characteristic above.

The gradient of the characteristic is defined by derating factor $X1$ associated with a pulse frequency of 8 kHz.

When commissioning a system for the first time, the derating factor $X1$ is pre-assigned when selecting a power section.

The currently effective derating factor is calculated when the system powers-up depending on the following:

- Pulse frequency (P1100)
- Ambient temperature (P1094), from SW 13.1
- Installation altitude (P1095), from SW 13.1

The derating factor can be seen in display data P1099.

The derating characteristics “pulse frequency-dependent”, “temperature-dependent” and “installation altitude-dependent” are the basis for this automatic calculation.

Reader’s note

Derating characteristics, refer to

References: /PJU/ Configuration Manual SIMODRIVE Converters
Chapter 4.4 Current reduction/derating
With this functionality, the following current reduction (derating) is obtained for the power section:

- For SRM, SLM or PE spindle “FD operation in field weakening” (P1015 = 1 and P1172 = 1)
  - $I_{\text{max}} = P1108$ (from power section list) $\times P1175$ (from power section list) $\times P1099$
  - $I_{S6} = P1109$ (from power section list) $\times P1176$ (from power section list) $\times P1099$
  - $I_{\text{rated}} = P1111$ (from power section list) $\times P1177$ (from power section list) $\times P1099$

- For ARM or PE spindle (P1015 = 1 and P1172 = 0)
  - $I_{\text{max}} = P1108$ (from power section list) $\times P1099$
  - $I_{S6} = P1109$ (from power section list) $\times P1099$
  - $I_{\text{rated}} = P1111$ (from power section list) $\times P1099$

The following parameters are used for “Power section derating“:

- P1106 Power section code number
- P1107 Transistor limit current
- P1108 Limiting power section current (rms)
- P1109 Limiting power section S6 (rms)
- P1111 Rated power section current (rms)
- P1175 Synch. reduction factor for P1108
- P1176 Synch. reduction factor for P1109
- P1177 Synch. reduction factor for P1111
- P1178 Synch. current reduction factor
- P1179 Asynch. current reduction factor
- P1094 Derating, ambient temperature
- P1095 Derating, installation altitude
- P1099 Limiting factor, power section currents
- P1260 $i^2t$ limiting, limit current power module S6
- P1261 $i^2t$ limiting, rated power module current
## 6.22 Dynamic energy management (from SW 13.1)

### Description
Dynamic energy management allows the infeed/regenerative feedback unit to be dimensioned in-line with the specific requirements and adapted to the overall system concept. Regenerative drive braking causes the DC link voltage to increase. While braking (which also means regenerative feedback into the line supply), for certain drives, the braking torque should be briefly reduced in order that the maximum permissible DC link voltage is not exceeded.

### Activation
Activated with P1155:
- **Bit 0**: Dynamic energy management function
  - Bit 0 = 0 --> not active
  - Bit 0 = 1 --> active
- **Bit 1**: Dynamic energy management function only effective for regenerative braking
  - Bit 1 = 0 --> not active
  - Bit 1 = 1 --> active

With an axis-specific configuring, using P1152 a “Minimum DC link voltage dynamic energy management” can be set, and using P1153 a “Maximum DC link voltage dynamic energy management” can be set.

### Boundary conditions
If the DC link voltage increases during operation (P1155 bit 1 = 0) or during regenerative braking (P1155 bit 1 = 1) via the “Maximum DC link voltage dynamic energy management” P1153, Alarm 617 “DC link overvoltage” is output and the torque is reduced to 0%, which opposes a voltage increase.

This torque reduction is only withdrawn if the DC link voltage subsequently falls below the “Minimum DC link voltage dynamic energy management” P1152.

In this case, the DC link voltage can again increase as a step function if the motor is still rotating. This can be reduced using the setting P1096/P1097 “Red. max. torque for regen. stop”.

For regenerative braking, the maximum torque is reduced to the percentage value specified in P1097 – assuming that P1096 bit 0 is active. This means that briefly occurring voltage spikes in the DC link voltage can be avoided.
Precondition

The times must lie within the configured times of P1403 “Shutdown speed pulse cancellation” and P1404 “Timer pulse cancellation” so that only a controller inhibit is initiated and not a pulse inhibit.

To achieve this, the controller inhibit must be configured as a shutdown response when Alarm 617 is output with P1613 “Shutdown response, fault 2”, bit 17 “DC link voltage”.

Note

When the upper limit for the DC link voltage dynamic energy management is exceeded (P1701 > P1153), then Alarm 617 “DC link overvoltage” is output.

The configuration must ensure that the sum of all of the motion axes, which regenerate into the line supply, cannot destroy the infeed/regenerative feedback unit. Alarm 617 can be influenced using P1613 bit 17.

Note

Speeding up the DC link sensing

The DC link voltage is measured using a multiplexer which is also used to sense the motor temperature for motor 1 and motor 2 and an internal reference measurement.

These “switchover deadtimes” are also included in the response of the DC link voltage sensing.

In order that the DC link voltage monitoring responds faster, after exceeding a speed threshold that can be entered into P1154 “only V DC link monitoring from motor speed”, the multiplexer can be prevented from switching over so that only the DC link voltage is monitored.

A 3% “Hysteresis” around the speed threshold prevents continuous toggling between the monitoring functions.

If the response threshold (0.97 ∙ P1154) is fallen below again, then the standard function is re-established.

The motor temperature monitoring and the reference measurement are inhibited for the time that it takes to measure the DC link voltage. This measure means that if the “Maximum DC link voltage dynamic energy management” P1153 is exceeded then this is detected with the shortest possible delay time.
Notice

At the same time, the machine concept must guarantee that the speed limit is also exceeded from time to time; otherwise, the following alarms or messages cannot be output – or cannot be responded to:

- Alarm 613 “Shutdown limit, motor overtemperature exceeded”
- Alarm 614 “Delayed shutdown for motor overtemperature”
- Warning 814 “Motor temperature pre-alarm”

Here, it makes sense to protect the motor against overload using the thermal motor protection function (P1265 – P1269).

Comment: The multiplexer shutdown is effective for both axes of a module.

Parameter overview (refer to Chapter A.1)

The following parameters are used for “Dynamic energy management”:

- P1152 Minimum DC link voltage dynamic energy management
- P1153 Maximum DC link voltage dynamic energy management
- P1164 Only V DC link monitoring from motor speed
- P1155 Dyn. energy management active
- P1403 Shutdown speed pulse cancellation
- P1404 Timer pulse cancellation
- P1613 Shutdown response faults 2 (bit 17)
- P1096 Red. max. torque for regen. stop active
- P1097 Red. max. torque for regen. stop
6.23 Motor diagnostics, ground fault test (from SW 13.1)

Description
This function can be used to detect a ground fault, i.e. a conductive connection between one of the motor phases and ground. This motor test takes place when the closed-loop control powers-up; however, it can also be specifically initiated in operation.

Note
The machine cannot be used for production during the motor diagnostics ground fault test.

Activation
Activated with P1166 (activate ground fault test):
- Bit 0: Automatic ground fault test after power on
  - Bit 0 = 0 --> automatic motor ground fault test after power-up disabled
  - Bit 0 = 1 --> automatic motor ground fault test after power-up enabled
- Bit 1: start ground fault test using P1166
  - Bit 1 = 1 --> Start: Start: activate motor ground fault test in operation using the signal edge 0-->1

The bit is automatically reset after the ground fault test has been performed.

Note
The ground fault test does not represent a protection function in the sense of the VDE guidelines.

Boundary conditions
- If, during the ground fault test, the current exceeds the value configured in P1167 “Response threshold of the ground fault test”, then Alarm 511 “Ground fault detected” is output. The cause of the alarm is saved in P1169 = -6.
- Current flows through the motor when the ground fault test is performed; this is the reason that the function can only be started after the controller and pulses have been enabled.
- If, during the ground fault test, the pulse enable is withdrawn, then the ground fault test waits for the next pulse enable – and then repeats the complete procedure.
6.23 Motor diagnostics, ground fault test (from SW 13.1)

The execution and/or error response are/is shown in Fig. 6-102:

- Start the ground fault test with P1166 bit 0 or bit 1
- Reset diagnostics parameters P1169
  0: function was not selected or was not exited
- Pulses enabled, but no motor/spindle motion?
  - Yes: Execute ground fault test
  - No: Diagnostics parameter P1169:
    - 1: Measurement completed, no ground fault occurred
    - Diagnostics parameter P1169:
      - 3: Short-circuit detected, current response threshold was exceeded
      - 4: Motor moved during the measurement more than is permitted in P1168
      - 5: Current was not able to be reduced in time during the measurement (measurement not possible)
      - 6: Measurement not possible/practical → configuration in P1167 illegal
      - 7: Short-circuit detected, current limit reached or calculated current rise too high
- Ground fault detected?
  - Yes: Power on Alarm 511 Ground fault detected
  - No: Diagnostics parameter P1169:
    - 1: Measurement completed, no ground fault occurred
    - 2: Measurement was not able to be started, motor/spindle turning
    - 8: Axis is parked

Fig. 6-102 Evaluation using diagnostics parameter P1169

- The ground fault test is not possible for a motor that is presently rotating. As a consequence, the motor must be stationary before the start of the test (speed actual value ≤ P1403 "shutdown speed pulse cancellation").
- If the brake control is activated (P0850 "Activate brake control"), then the speed actual value must be ≤ P0852 "Speed/motor velocity close holding brake".
6 Description of the Functions

6.23 Motor diagnostics, ground fault test (from SW 13.1)

- When booting after power on, the automatic ground fault test (P1166 bit 0 = 1) can only be performed for motor 1. If a ground fault test is to be performed for motors 2 to 4 from the motor data set changeover, then this must be explicitly realized using P1166 bit 1 = 1.

- A ground fault test for a hanging/suspended axis is possible, under the prerequisite that the axis is mechanically locked using the holding brake.

### Parameter overview (refer to Chapter A.1)

The following parameters are used for the “Motor diagnostics ground fault test”:

- **P1166** Activate ground fault test
- **P1167** Response threshold of the ground fault test
- **P1168** Maximum rotation, ground fault test (ARM SRM)  
  Maximum motion, ground fault test (SLM)
- **P1169** Motor diagnostics
### Fault Handling/Diagnostics

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</table>
### 7.1 Overview of faults and warnings

Table 7-1  Overview of faults and warnings

<table>
<thead>
<tr>
<th>Type</th>
<th>Range</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td>When faults occur</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• The segment display automatically changes over</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• The fault No. is output, flashing</td>
</tr>
<tr>
<td></td>
<td></td>
<td>e.g. E-A008 -- &gt; Error 8 from drive A</td>
</tr>
<tr>
<td></td>
<td></td>
<td>E-b714 -- &gt; Error 714 from drive B</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• An appropriate stop response is initiated</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Features</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• They are displayed in the sequence in which they occurred</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• If several faults are present, then the 1st fault and all of the additional</td>
</tr>
<tr>
<td></td>
<td></td>
<td>faults can be displayed using the PLUS key (refer to Fig. 7-2)</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Faults with/without supplementary information</td>
</tr>
<tr>
<td></td>
<td></td>
<td>- without supplementary information</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The cause of the fault is only defined by the fault number.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>- with supplementary information</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The cause of the fault is defined by the fault number and supplement-</td>
</tr>
<tr>
<td></td>
<td></td>
<td>ary information.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>For the display unit, a change is made between the fault (output with E.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>...) and the supplementary information (where only a value is output) .</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Starting from the fault display, you can changeover into the parameter-</td>
</tr>
<tr>
<td></td>
<td></td>
<td>izing mode using the MINUS key</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Faults have a higher priority than the warnings</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Fault correction</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Remove the cause of the fault</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Acknowledge the fault (is specified for every fault)</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Warning</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>When warnings occur</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• The segment display automatically changes over</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• The warning number is output flashing</td>
</tr>
<tr>
<td></td>
<td></td>
<td>e.g. E A805 -- &gt; Warning 805 from drive A</td>
</tr>
<tr>
<td></td>
<td></td>
<td>E b810 -- &gt; Warning 810 from drive B</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Features</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• If several warnings are present, there is no relationship between the</td>
</tr>
<tr>
<td></td>
<td></td>
<td>time which they occurred and their display</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Only one warning is displayed</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• The warning with the lowest number is displayed</td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Starting from the fault display, you can changeover into the parameter-</td>
</tr>
<tr>
<td></td>
<td></td>
<td>izing mode using the MINUS key</td>
</tr>
<tr>
<td></td>
<td></td>
<td><strong>Removing warnings</strong></td>
</tr>
<tr>
<td></td>
<td></td>
<td>• Warnings are self-acknowledging, i.e. they automatically reset themselves</td>
</tr>
<tr>
<td></td>
<td></td>
<td>once the condition is no longer fulfilled</td>
</tr>
</tbody>
</table>

Faults have the numbers < 800 and are displayed with "E-xxx"

Warnings have the numbers ≥ 800 and are displayed with "E-xxx"
7.1 Overview of faults and warnings

**Alarm log**

The parameterizing and commissioning tool “SimoCom U” enters the alarms and warnings that have occurred with data time into an alarm protocol file that is saved in the “SIMOCOMU installation path” under .../user/AlarmLog.txt.

Note:

If “SimoCom U” is connected to a drive that is already operational, then for the warnings that have occurred up until then, neither date nor time is specified in the log file. If the size of the alarm log file exceeds 50 kb, then after closing the parameterizing and commissioning tool “SimoCom U”, the contents of the log file are transferred into the AlarmLog.bak file and AlarmLog.txt is set-up again.

**Acknowledgement**

In the list of faults and warnings (refer to Chapter 7.3), for each fault and warning, an explanation is given under “Acknowledge”, as to how they can be acknowledged after the cause has been removed.

**Acknowledging faults with POWER ON**

Faults, which are to be acknowledged with POWER ON, can be alternatively acknowledged as follows:

1. POWER ON
   
   ---&gt; power-off/power-on "SIMODRIVE 611 universal"

2. Press the POWER-ON RESET button on the front panel of the control board

3. POWER-ON RESET with the “SimoCom U” tool

The processor runs up again, all of the faults are acknowledged, and the fault buffer is re-initialized.

**Acknowledging faults with RESET FAULT MEMORY**

Faults, which are to be acknowledged with RESET FAULT MEMORY, can be alternatively acknowledged as follows:

**Notice**

Prerequisites when acknowledging:

- **Disable the controller enable via terminal 65.x**
  
  or

- **Set the PROFIBUS control signal STW1.0 to "0"**

  From SW 6.1 and for P1012.12 = 1, the fault can also be acknowledged without this prerequisite. However, the drive then remains in the "Power-on inhibit" state (refer to Chapter 5.5 "Forming the power-on inhibit"; Fig.5-9).

- **Set the appropriate bus signal (e.g. for the CAN bus, from SW 8.1)**

1. Carry-out POWER ON acknowledgment

   In addition to the POWER ON faults, all of the faults, which can be acknowledged with RESET FAULT MEMORY, are also acknowledged.

2. Set the input terminal with the "reset fault memory" function to "1"

3. Press button P on the display and operator control unit
4. Using PROFIBUS-DP: Set STW1.7 (reset fault memory) to "1"

5. Set terminal R on the NE module to "1"
   When this terminal is energized, "reset fault memory" is effective for
   all of the control boards of the complete drive group.

6. For the "SimoCom U" tool in the dialog box "Alarm report" by pressing the "Reset fault memory" button

7. From SW 9.1:
   The fault buffer is cleared with parameter P0952 = 0 and the faults
   are acknowledged if the causes were resolved.

   If a fault is acknowledged, before the cause, e.g. overtemperature, DC
   link undervoltage etc. was removed, then the fault message is subse-
   quently de-activated at that instant in time when the cause is no longer
   present. The fault memory does not have to be reset again.
Stop responses

In the list of faults and warnings, for each fault and warning, the stop response and its effects are specified under “stop response”.

--> Refer to Chapter 7.3

**Note**

Handling faults in the master and slave drive for coupled axes, refer to Chapter 6.3.2.

<table>
<thead>
<tr>
<th>Stop response</th>
<th>Stopping via...</th>
<th>Effect</th>
</tr>
</thead>
</table>
| STOP I        | Internal pulse inhibit | • Immediate pulse cancellation.  
• The drive “coasts down”. |
| STOP II       | Internal control inhibit | • Speed-controlled operation  
  - By immediately entering \( n_{\text{set}} = 0 \) the drive is braked along the down ramp.  
  - If the speed actual value falls below the value in P1403 (shutdown speed, pulse cancellation), or if the time in P1404 (timer stage, pulse cancellation) has expired, then the pulses are canceled.  
  • Torque-controlled operation  
  - The drive does not actively brake.  
  - If the speed actual value falls below the value in P1403 (shutdown speed, pulse cancellation), or if the time in P1404 (timer stage, pulse cancellation) has expired, then the pulses are canceled.  
  • Torque/force limiting for setpoint 0 (only nset operation, from SW 8.3)  
  - P1096 can be used to activate torque limit reduction when regeneratively braking.  
  - P1097 can be used to parameterize the factor to reduce the torque limit when regeneratively braking. |
| STOP III      | \( n_{\text{set}} = 0 \) | • The axis is braked, closed-loop speed controlled with the maximum deceleration (P0104).  
• The drive remains in the closed-loop controlled mode. |
| STOP IV       | Interpolator \( P_{\text{0104}} \) | • The axis is braked closed-loop position controlled with the maximum deceleration (P0104).  
• The drive remains in the closed-loop controlled mode.  
• The axes remain coupled. |
7.1 Overview of faults and warnings

<table>
<thead>
<tr>
<th>Stop response</th>
<th>Stopping via...</th>
<th>Effect</th>
</tr>
</thead>
</table>
| STOP V        | Interpolator (P0104 • P0084:64/256) | • The axis is braked closed-loop position controlled using the programmed deceleration (P0104 • deceleration override in P0084:64/256).  
• The drive remains in the closed-loop controlled mode. |
| STOP VI       | End of block    | • Standstill after the end of a block.  
• The drive remains in the closed-loop controlled mode. |
| STOP VII      | none            | • No effect.  
• Acknowledgment is not required.  
• That is a warning |
| STOP VIII     | STOP I (ARM) STOP II (SRM, SLM) | Digital outputs are switched to 0 V and cyclic PROFINET communications are interrupted. **Caution:** Depending on the extent of the processor overload that occurs, it cannot always be guaranteed that all software modules, which initiate responses, are executed. This means that some responses may not be initiated. |

**Faults that can be suppressed**

This means that:

These faults can be de-activated.

• Which faults can be suppressed?

The faults, specified in P1600 and P1601 can be suppressed.

e.g. faults 508, 509, 608 etc.

• How can they be suppressed?

By setting the parameter bit assigned to the fault via P1600 and P1601.

Example:

Fault 608 is to be suppressed.

-> set P1601.8 to 1

**Faults which can be set**

This means that:

For these faults, either STOP I or STOP II can be set as stop response.

• Which faults can be set?

The faults, specified in P1612 and P1613, can be set.

e.g. faults 504, 505, 607 etc.

• How can these be set?

By setting the parameter bit assigned to the fault via P1612 and P1613.

Example:

STOP II should be initiated as response to fault 608.

-> set P1613.8 to 0
7.2 Displaying and handling faults and warnings

7.2.1 Display and operator control via the display and operator unit

The segment display is automatically changed over into the alarm mode when one or several faults or warnings occur. The faults and warnings are output flashing on the display unit. They can be displayed as follows:

Table 7-3 Displaying alarms on the display unit

<table>
<thead>
<tr>
<th>Display example (flashing display)</th>
<th>Description</th>
</tr>
</thead>
</table>
| 1. This is what it looks like if a fault has occurred (refer to Fig. 7-1). | E: it involves a fault (Code: 1 hyphen)  
• 1 hyphen: there is one fault present  
• A: the fault is assigned to drive A  
• 608: is the fault number |
| 2. This is what it looks like if several faults have occurred (refer to Fig. 7-2). | E: it involves several faults (Code: 3 hyphens)  
• 3 hyphens:  
  - several faults are present  
  - this is the first which occurred  
• A: the fault is assigned to drive A  
• 131: is the fault number  
Note:  
By pressing the PLUS button, several faults can be displayed for each additional fault.  
• E: it involves an additional fault (code: 2 hyphens)  
• 2 hyphens:  
  - several faults are present  
  - this is an additional fault  
• A: the fault is assigned to drive A  
• 134: is the fault number |
| 3. This is what it looks like if a warning is present (refer to Fig. 7-3). | E: it involves a warning (code: no hyphen)  
• A: the warning is assigned to drive A  
• 804: is the warning number |
7.2 Displaying and handling faults and warnings

**Operator control, if a fault is present**

When a fault occurs, it can be handled using the MINUS and P keys as shown in the following diagram.

![Diagram of displaying and handling faults](image)

Fig. 7-1 Operator control, if a fault is present

**Operator control, if several faults have occurred**

When faults occur, they can be handled as shown in the following diagram using the PLUS, MINUS and P keys.

![Diagram of displaying and handling several faults](image)

Fig. 7-2 Operator control, if several faults have occurred
When warnings occur, they can be handled using the MINUS key as shown in the following diagram.

**Operator action, if one warning is present**

![Diagram showing how to handle warnings using the MINUS key.]

**Fig. 7-3** Operator action, if one warning is present
7.2 Displaying and handling faults and warnings

## 7.2.2 FAULT LED on the front panel

There is a button with integrated LED on the front panel of the "SIMODRIVE 611 universal" control board.

![Fig. 7-4 FAULT LED on the front panel of the control board](image)

### What significance does the FAULT LED have?

If a FAULT-LED is lit on the front panel of the control board, it can be interpreted as follows:

<table>
<thead>
<tr>
<th>If</th>
<th>Then</th>
</tr>
</thead>
</table>
| The FAULT LED on the front panel of the control board lights up | - there is at least one fault (No.: < 800, the fault number is displayed on the display unit)  
- the control board is booting (approx. 2 sec). The LED goes dark after successful booting.  
- a first commissioning is requested  
- the memory module is not inserted on the control module or is not "correctly" inserted  
- the control board is defective |
7.3 List of faults and alarms

7.3.1 Fault without a number being displayed

**Fault**  
After power-on, the operating display is inactive

**Cause**
- At least 2 phases are missing (NE module)
- At least 2 input fuses have ruptured (NE module)
- Defective electronics power supply in the NE module
- Equipment bus connection (ribbon cable) from the NE module to the "SIMODRIVE 611 universal" control board is either not inserted or defective
- Defective control board

**Fault**  
After the controller enable, the motor is stationary at \( n_{set} \neq 0 \)

**Cause**
- P1401:8 is set to zero
- Power-on inhibit is present for PROFIBUS operation
  Remove the power-on inhibit with a "high - low - high" signal change at 65.x or the control bit STW1.0 (ON/OFF 1)
  or set bit 12 of parameter 1012 to zero

**Fault**  
After the controller has been enabled, the motor briefly moves

**Cause**
- Defective power module

**Fault**  
After the controller has been enabled, the motor rotates at max. 50 RPM at \( n_{set} > 50 \text{ RPM} \) or the motor oscillates at \( n_{set} < 50 \text{ RPM} \)

**Cause**
- Motor phase sequence is incorrect (interchange 2 phase connections)
- The entered encoder pulse number was too high

**Fault**  
After the controller is enabled, the motor accelerates to a high speed

**Cause**
- Encoder pulse number too small
- Open-loop torque controlled mode selection?

**Fault**  
"- - - - - -" is output on the display unit

**Cause**
- There is no drive firmware in this memory module.
- Remedy, refer to fault 001
7.3.2 Error with fault/warning number

Version: 13.01.02

Reader’s note
- In some instances, the space retainers (e.g. \%) are specified for the texts of the individual faults and warnings. In online operation with SimoCom U instead of a space retainer, an appropriate value is displayed.
- The complete list is updated corresponding to the Edition of this documentation (refer to the Edition in the header lines) and corresponds to the software release of “SIMODRIVE 611 universal” documented here. The individual faults/warnings are not coded dependent on the software release.

000 Alarm diagnostics not possible

Cause
- Communications to the drive have been interrupted.
- Different versions of the “SimoCom U” start-up and parameterizing tool and the drive.

Remedy
- Check the communications to the drive (cable, interfaces, ...)
- The V_611U<Version>.acc file on the hard disk of the PG/PC should be adapted to the drive as follows:
  - Exit “SimoCom U”
  - Delete the V_611U<Version>.acc file (search and delete the file)
  - Restart “SimoCom U” and go online
The V_611U<Version>.acc file is now re-generated and is harmonized to the drive version.
Never delete the file V000000.acc!

001 The drive does not have firmware

Cause
No drive firmware on the memory module.

Remedy
- Load the drive firmware via SimoCom U
- Insert the memory module with firmware

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)
<table>
<thead>
<tr>
<th>Fault Code</th>
<th>Description</th>
<th>Cause</th>
<th>Remedy</th>
<th>Acknowledgement</th>
<th>Stop response</th>
</tr>
</thead>
<tbody>
<tr>
<td>002</td>
<td><strong>Computation time overflow. Suppl. info: %X</strong>&lt;br&gt;<strong>Cause</strong>&lt;br&gt;The computation time of the drive processor is no longer sufficient for the selected functions in the specified cycle times.&lt;br&gt;<strong>Supplementary information:</strong> only for siemens-internal error diagnostics</td>
<td>Disable functions which take up a lot of computation time, e.g.:&lt;br&gt;- Variable signaling function (P1620)&lt;br&gt;- Trace function&lt;br&gt;- Start-up with FFT or analyzing the step response&lt;br&gt;- Speed feedforward control (P0203)&lt;br&gt;- Min/Max memory (P1650.0)&lt;br&gt;- DAC output (max. 1 channel)&lt;br&gt;<strong>Increase cycle times:</strong>&lt;br&gt;- Current controller cycle (P1000)&lt;br&gt;- Speed controller cycle (P1001)&lt;br&gt;- Position controller cycle (P1009)&lt;br&gt;- Interpolation cycle (P1010)</td>
<td>POWER ON</td>
<td>STOP VIII</td>
<td></td>
</tr>
<tr>
<td>003</td>
<td><strong>NMI due to watchdog. Suppl. info: %X</strong>&lt;br&gt;<strong>Cause</strong>&lt;br&gt;The watchdog timer on the control module has expired. The cause is a hardware fault in the time basis on the control module.&lt;br&gt;<strong>Supplementary information:</strong> only for siemens-internal error diagnostics</td>
<td>- Replace control module</td>
<td>POWER ON</td>
<td>STOP VIII</td>
<td></td>
</tr>
<tr>
<td>004</td>
<td><strong>Stack overflow. Suppl. info: %X</strong>&lt;br&gt;<strong>Cause</strong>&lt;br&gt;The limits of the internal processor hardware stack or the software stack in the data memory have been violated. The cause is probably a hardware fault on the control module.&lt;br&gt;<strong>Supplementary information:</strong> only for siemens-internal error diagnostics</td>
<td>- Power down / power up drive module&lt;br&gt;- Replace control module</td>
<td>POWER ON</td>
<td>STOP VIII</td>
<td></td>
</tr>
<tr>
<td>005</td>
<td><strong>Illegal Opcode, Trace, SWI, NMI (DSP). Suppl. info: %X</strong>&lt;br&gt;<strong>Cause</strong>&lt;br&gt;The processor has detected an illegal command in the program memory.&lt;br&gt;<strong>Supplementary information:</strong> only for siemens-internal error diagnostics</td>
<td>- Replace control module</td>
<td>POWER ON</td>
<td>STOP VIII</td>
<td></td>
</tr>
</tbody>
</table>
7.3 List of faults and alarms

**006 Checksum test error. Suppl. info: \%X**

**Cause**
During the continuous check of the checksum in the program / data memory, a difference was identified between the reference and actual checksum. The cause is probably a hardware fault on the control module.

Supplementary information: only for siemens-internal error diagnostics

**Remedy**
- Replace control module

**Acknowledgement**
POWER ON

**Stop response**
STOP VIII

**007 Error when initializing. Supplementary info: \%X**

**Cause**
An error occurred when loading the firmware from the memory module.

Cause: Data transfer error, FEPROM memory cell defective

Supplementary information: only for siemens-internal error diagnostics

**Remedy**
- Carry-out RESET or POWER-ON.
- If a download is still unsuccessful after several attempts, the memory module must be replaced. If this is unsuccessful the control module is defective and must be replaced.

**Acknowledgement**
POWER ON

**Stop response**
STOP VIII

**020 NMI due to cycle failure**

**Cause**
Basic cycle has failed.
Possible causes: EMC faults, hardware fault, control module

**Remedy**
- Check the plug-in connections
- Implement noise suppression measures (screening, check ground connections)
- Replace control module

**Acknowledgement**
POWER ON

**Stop response**
STOP VIII

**025 SSI interrupt**

**Cause**
An illegal processor interrupt has occurred. An EMC fault or a hardware fault on the control module could be the reason.

**Remedy**
- Check the plug-in connections
- Replace control module

**Acknowledgement**
POWER ON

**Stop response**
STOP VIII
026  **SCI interrupt**

**Cause**
An illegal processor interrupt has occurred. An EMC fault or a hardware fault on the control module could be the reason.

**Remedy**
- Check the plug-in connections
- Replace control module

**Acknowledgement**
POWER ON

**Stop response**
STOP VIII

027  **HOST interrupt**

**Cause**
An illegal processor interrupt has occurred. An EMC fault or a hardware fault on the control module could be the reason.

**Remedy**
- Check the plug-in connections
- Replace control module

**Acknowledgement**
POWER ON

**Stop response**
STOP VIII

028  **Actual current sensing during power-up**

**Cause**
When the current actual value sensing runs up, or in cyclic operation at pulse inhibit, a 0 current is expected. The drive system then identifies that no currents are flowing (excessive deviation to the theoretical center frequency). It is possible that the hardware for the current actual value sensing is defective.

**Remedy**
- Check the plug-in connections
- Check whether the control module is correctly inserted
- Replace control module
- Replace the power section

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

029  **Incorrect measuring circuit evaluation. Suppl. info:**

**Cause**
The motor measuring system has a motor encoder with voltage output which requires a measured circuit evaluation with voltage input, or a resolver with appropriate evaluation. Another measuring circuit evaluation was identified.

Supplementary information: only for siemens-internal error diagnostics

**Remedy**
- Check the plug-in connections
- Implement noise suppression measures (screening, check ground connections, ...)
- Control module and encoder must be the same type (sin/cos or resolver)
- Replace control module

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

**030**  
**S7 communication error. Supplementary info: \%X**

**Cause**  
A fatal communication error was identified, or the drive software is no longer consistent. The cause is erroneous communications or a hardware fault on the control module. 
Supplementary information: only for siemens-internal error diagnostics

**Remedy**  
- Implement noise suppression measures (screening, check ground connections, ...)
- Replace control module

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

**031**  
** Internal data error. Suppl. info: \%X**

**Cause**  
Error in the internal data, e.g. errors in the element / block lists (incorrect formats, ...). The drive software is no longer consistant. The cause is probably a hardware fault on the control module. 
Supplementary information: only for siemens-internal error diagnostics

**Remedy**  
- Re-load drive software
- Replace control module

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

**032**  
**Incorrect number of current setpoint filters**

**Cause**  
An illegal number of current setpoint filters was entered (> 4) (maximum number = 4).

**Remedy**  
Correct number of current setpoint filters (P1200).

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

**033**  
**Incorrect number of speed setpoint filters**

**Cause**  
An inadmissible number of speed setpoint filters (> 2) was entered (max. number = 2).

**Remedy**  
Correct number of speed setpoint filters (P1500)

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

**034**  
**Axis count function has failed**

**Cause**  
The function for determining the number of axes that physically exist on the power section has calculated an illegal value.

**Remedy**  
Check that the control module is correctly inserted in the power section or whether the power section is defective.

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)
**035** Error when saving the user data. Supplementary info: \\%X

**Cause**
An error occurred when saving the user data in the FEPROM on the memory module.
Cause: Data transfer error, FEPROM memory cell defective
Note: The user data which was last saved, is still available as long as a new data backup was unsuccessful.
Supplementary information: only for siemens-internal error diagnostics

**Remedy**
- Re-initiate data save.
  If unsuccessful after several back-up attempts, then the memory must be formatted via the menu Options-service-FEPROM.
  The memory module must be replaced if this is also unsuccessful.
  If the user data valid when the fault occurred are to be re-used with the new and/or formatted memory module, then these must first be read-out using SimoCom U.
- Carry-out RESET or POWER ON.

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

**036** Error when downloading the firmware. Suppl. info: \\%X

**Cause**
A error occurred when downloading a new firmware release.
Cause: Data transfer error, FEPROM memory cell defective
Note: As the previously used firmware was erased when downloading, the drive expects a new firmware download after RESET or POWER ON.
Supplementary information: only for siemens-internal error diagnostics

**Remedy**
Carry-out RESET or POWER-ON.
The memory module must be replaced if unsuccessful after several download attempts. If this is also unsuccessful, then the control module is defective and must be replaced.

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

**037** Error when initializing the user data. Supplementary info: \\%X

**Cause**
An error occurred when loading the user data from the memory module.
Cause: Data transfer error, FEPROM memory cell defective
Supplementary information: only for siemens-internal error diagnostics

**Remedy**
- Execute RESET or POWER ON
- Parameter file "Load and save in the drive" or re-configure drive
  If unsuccessful after several back-up attempts, then the memory must be formatted via the menu Options-Service-FEPROM.
  If this is unsuccessful, the memory module must be replaced. If this is also unsuccessful, then the control module is defective and must be replaced.

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

039 **Error during power section identification. Supplementary info: \%X**

**Cause**
Supplementary information
0x100000: More than 1 power section (unit) type was identified.
0x200000: No power section type was identified, although it would have been possible.
0x300000: The identified power module differs from the entered PM (P1106). To xxxx: the code of the identified PM is entered here.
0x400000: Different power section codes (P1106) are entered for this 2-axis module.

**Remedy**
- Execute RESET or POWER ON
- Check whether the control module is correctly inserted in the power module

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

040 **Expected option module is not available.**

**Cause**
The parameterization (P0875) expects an option module which is not available on this control module.

**Remedy**
Compare the type of the expected option module (P0875) with the type of the inserted option module (P0872) and check/replace the inserted option module or cancel the option module with P0875 = 0.

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

041 **The firmware does not support the option module.**

**Suppl. info: \%u**

**Cause**
Supplementary info = 1:
An option module is inserted (P0872) or parameterized (P0875), which is not supported by the firmware release of the control module.

**Remedy**
Supplementary info = 1:
- Upgrade the firmware
- Use a legal option module
- Cancel the option module with P0875 = 0
Supplementary info = 2:
- Use a permissible option module (DP3)
- Cancel the option module with P0875 = 0
Supplementary info = 3:
- Replace the option module hardware DP1 by option module DP2 or DP3, without changing the drive parameters and the master configuring. The parameter for the expected option module remains at P0875 = 2.

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)
042 Internal software error. Supplementary info \%u
Cause There is an internal software error.
Supplementary information: only for siemens-internal error diagnostics
Remedy
- Execute POWER ON-RESET (press button R)
- Re-load the software into the memory module (execute software update)
- Contact the Hotline
- Replace control module
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

043 Firmware, option module
Cause The option module does not contain the currently required firmware.
Remedy Use a module with suitable firmware or upgrade the firmware
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

044 Connection to the option module failed. Supplementary info \%X
Cause The BUS coupling has failed.
Remedy
- Execute POWER ON-RESET (press button R)
- Replace option module
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

045 Expected option module is axially unequal
Cause The option module type, expected from the parameterization, is different for the two axes of a 2-axis module.
Remedy Set the expected option module type in P0875 the same for both axes, or cancel for axis B by setting P0875 to 0.
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

048 Illegal status PROFIBUS hardware
Cause An illegal status of the PROFIBUS controller was recognized.
Remedy
- Execute POWER-ON RESET
- Check the PROFIBUS unit screw connection
- Replace drive module
Acknowledgement POWER ON
Stop response STOP II
### 101 Target position block \( \%n < \) plus software limit switch

**Cause**
The target position specified in this block lies outside the range limited by P0316 (plus software limit switch).

**Remedy**
- Change the target position in the block
- Set the software limit switches differently

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

### 102 Target position block \( \%n < \) minus software limit switch

**Cause**
The target position specified in this block lies outside the range limited by P0315 (minus software limit switch).

**Remedy**
- Change the target position in the block
- Set the software limit switches differently

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

### 103 Block number \( \%n \): Direct output function not possible

**Cause**
For the SET_0 or RESET_0 command, an illegal value was entered into P0086:256 (command parameter).

**Remedy**
Enter value 1, 2 or 3 into P0086:256 (command parameter).

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

### 104 Block \( \%n \): There is no jump target

**Cause**
A jump is programmed to a non-existent block number in this traversing block.

**Remedy**
Program the existing block number.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

### 105 Illegal mode specified in block \( \%n \)

**Cause**
Inadmissible information is in P0087:256/P0097 (mode). One position of P0087:256/P0097 has an illegal value.
For the commands SET_0 and RESET_0, the CONTINUE EXTERNAL block change enable is not permissible.
For MDI: The configuration of the external block change P0110 is incorrect. The external block change is only permissible with P0110 = 2 or 3.
Block change enable only with "END" or "CONTINUE EXTERNAL".
For axis couplings: For COUPLING_IN/COUPLING_OUT via a traversing block (P0410=3, 4 or 8), a block change enable with CONTINUE FLYING is not possible.

**Remedy**
Check and correct P0087:256/P0097.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI
106  **Block \%n: ABS_POS mode not possible for linear axis**

**Cause**
For a linear axes, the positioning mode ABS_POS was programmed (only for rotary axes).

**Remedy**
Change P0087:256/P0097 (mode).

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

107  **Block \%n: ABS_NEG mode not possible for a linear axis**

**Cause**
For a linear axes, the positioning mode ABS_NEG was programmed (only for rotary axes).

**Remedy**
Change P0087:256/P0097 (mode).

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

108  **Block number \%n available twice**

**Cause**
There are several traversing blocks with the same block number in the program memory. The block numbers must be unique over all traversing blocks.

**Remedy**
Assign unique block numbers.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

109  **External block change not requested in block \%n**

**Cause**
For a traversing block with the block change enable CONTINUE EXTERNAL and P0110 (configuration, external block change) = 0, the external block change was not requested.

**Remedy**
Remove the cause that the signal edge is missing at the input terminal or for a PROFIBUS control signal STW1.13 or for the appropriate fieldbus signal.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

110  **Selected block number \%n does not exist**

**Cause**
A block number was selected which is not available in the program memory or has been suppressed.

**Remedy**
Select the existing block number.
Program the traversing block with the selected block number.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI
7.3 List of faults and alarms

111  **GOTO in block number %n not permissible**

**Cause**
The step command GOTO may not be programmed for this block number.

**Remedy**
Program another command.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

112  **Activate traversing task and start referencing, handwheel simultaneously**

**Cause**
A positive signal edge was simultaneously detected for the input signals "Activate traversing task" and "Start referencing" and "Activate handwheel".
At power-on or POWER-ON RESET, if both input signals have a "1" signal, then for both signals a 0/1 edge (positive edge) is simultaneously identified.

**Remedy**
Reset both input signals, and re-start the required function after the fault has been acknowledged.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP IV

113  **Activate traversing task and jog, handwheel simultaneously**

**Cause**
A positive signal edge was simultaneously detected for the input signals "Activate traversing task" and "Jog 1", "Jog 2" and "Activate handwheel".
At power-on or POWER-ON RESET, if both input signals have a "1" signal, then for both signals a 0/1 edge (positive edge) is simultaneously identified.

**Remedy**
Reset both input signals, and re-start the required function after the fault has been acknowledged.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP IV

114  **Block change enable END in block number %n expected**

**Cause**
The traversing block with the highest block number does not have END as block step enable.

**Remedy**
- Program this traversing block with block step enable END.
- Program the GOTO command for this traversing block.
- Program additional traversing blocks with higher block number and program the block step enable END (highest block number) in the last block.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI
115  **Traversing range start reached**

**Cause**
The axis has moved to the traversing range limit in a block with the command ENDLOS_NEG (-200 000 000 MSR).

**Remedy**
- Acknowledge fault
- Move away in the positive direction (e.g. jog)

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

116  **Traversing range end reached**

**Cause**
The axis has moved to the traversing range limit in a block with the command ENDLOS_POS (200 000 000 MSR).

**Remedy**
- Acknowledge fault
- Move away in the negative direction (e.g. jog)

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

117  **Target position block \%n < start of the traversing range**

**Cause**
The target position specified in this block lies outside the absolute traversing range (-200 000 000 MSR).

**Remedy**
Change the target position in the block

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

118  **Target position block \%n < end of the traversing range**

**Cause**
The target position specified in this block lies outside the absolute traversing range (200 000 000 MSR).

**Remedy**
Change the target position in the block

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI

119  **PLUS software limit switch actuated**

**Cause**
For a block with the ENDLOS_POS command, the axis has actuated the plus software limit switch (P0316) for absolute or relative positioning. The behavior for software limit switch reached, can be set using P0118.0.

**Remedy**
- Acknowledge fault
- Move away in the negative direction, jog mode

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V
### List of Faults and Alarms

#### 120: MINUS software limit switch actuated

**Cause**
For a block with the ENDLOS_NEG command, the axis has actuated the minus software limit switch (P0315) for absolute or relative positioning. The behavior for software limit switch reached, can be set using P0118.0.

**Remedy**
- Acknowledge fault
- Move away in the positive direction, jog mode

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

#### 121: Jog 1, jog 2 or handwheel simultaneously active

**Cause**
The input signals "jog 1", "jog 2" or "activate handwheel" were simultaneously activated.

**Remedy**
- Reset both input signals
- Acknowledge the fault
- Activate the required input signal

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II

#### 122: Parameter \%u: value range limits violated

**Cause**
The value range limit of the parameter was violated when the dimension system was changed over from inches to millimeters.

**Remedy**
Place the parameter value within the value range.

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

#### 123: Linear encoder for the selected dimension system illegal

**Cause**
For a linear encoder, the dimension system was set to degrees.

**Remedy**
Change the dimension system setting (P0100).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

#### 124: Referencing and jog simultaneously started

**Cause**
For the "start referencing" and "Jog 1" and "Jog 2" input signals, a positive edge was simultaneously identified.

**Remedy**
Reset both input signals, and re-start the required function after the fault has been acknowledged.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V
125 **Falling edge of the reference cam not identified**

**Cause** When moving away from the reference cams, the traversing range limit was reached, as the 1/0 edge of the reference cam was not identified.

**Remedy** Check the "reference cam" input signal and repeat the reference point approach.

**Acknowledgement** RESET FAULT MEMORY

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

---

126 **Block \%n: ABS_POS for rotary axis, is not possible without modulo conversion**

**Cause** The ABS_POS positioning mode is only permitted for a rotary axis with activated module conversion (P0241 = 1).

**Remedy** Use the valid positioning mode for this axis type.

**Acknowledgement** RESET FAULT MEMORY

**Stop response** STOP VI

---

127 **Block \%n: ABS_NEG for rotary axis is not possible without modulo conversion**

**Cause** The ABS_NEG positioning mode is only permitted for a rotary axis with activated modulo conversion (P0241 = 1).

**Remedy** Use the valid positioning mode for this axis type.

**Acknowledgement** RESET FAULT MEMORY

**Stop response** STOP VI

---

128 **Block \%n: Target position lies outside the modulo range**

**Cause** The programmed target position (P0081:256/P0091) lies outside the set modulo range (P0242).

**Remedy** Program valid target position.

**Acknowledgement** RESET FAULT MEMORY

**Stop response** STOP VI

---

129 **Maximum velocity for a rotary axis with modulo conversion too high**

**Cause** The programmed maximum velocity (P0102) is too high to correctly calculate the modulo offset. The maximum velocity may only be so high, that 90% of the modulo range (P0242) can be traveled through within one interpolation cycle (P1010).

**Remedy** Reduce maximum velocity (P0102).

**Acknowledgement** RESET FAULT MEMORY

**Stop response** STOP V
7.3 List of faults and alarms

130 Controller or pulse enable withdrawn in motion

Cause
Possible causes are:
- One of the following enable signals was withdrawn while moving:
  Terminals 48, 63, 64, 663, 65.x, PROFIBUS or bus enable signals,
  PC enable from SimoCom U
- Another fault has occurred, which causes the controller or pulse enable to be withdrawn
- The drive is in the power-on inhibit state

Remedy
- Set the enable signals or check the cause of the first fault which occurred and remove
- Remove the power-on inhibit with the edge (0 --> 1) at control word STW1.0 or terminal 65.
- Withdraw the power-on inhibit from the fieldbus signal.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

131 Following error too high

Cause
Possible causes are:
- The torque or acceleration capability of the drive is exceeded
- Position measuring system fault
- The position control sense is not correct (P0231)
- Mechanical system blocked
- Excessive traversing velocity or excessive position setpoint differences

Remedy
Check the above causes and remove.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

132 Drive located after the minus software limit switch

Cause
The axis was moved to the minus software limit switch (P0315), jog mode.
The fault can also occur if the software limit switches are inactive if the position actual value falls below the limit value of -200 000 000 MSR, that corresponds to 555 revolutions for a rotary axis.

Remedy
Return the drive into the traversing range using jog button 1 or 2. Then acknowledge the fault.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP III
133 Drive located after the plus software limit switch

Cause
The axis was moved to the plus software limit switch (P0316), jog mode.
The fault can also occur if the software limit switches are inactive if the position actual value exceeds the limit value of 200 000 000 MSR, that corresponds to 555 revolutions for a rotary axis.

Remedy
Return the drive into the traversing range using jog button 1 or 2. Then acknowledge the fault.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP III

134 Positioning monitoring has responded

Cause
The drive has not yet reached the positioning window (P0321) after the positioning monitoring time (P0320) has expired.
Possible causes:
- Positioning monitoring time (P0320) parameters too low
- Positioning window (P0321) parameters too low
- Position loop gain (P0200) too low
- Position loop gain (P0200) too high (instability/tendency to oscillate)
- Mechanical block

Remedy
Check above parameters and correct.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

135 Standstill monitoring has responded

Cause
The drive has left the standstill window (P0326) after the standstill monitoring time (P0325) has expired.
Possible causes are:
- Position actual value inversion (P0231) incorrectly set
- Standstill monitoring time (P0325) parameters too low
- Standstill window (P0326) parameters too low
- Position loop gain (P0200) too low
- Position loop gain (P0200) too high (instability/tendency to oscillate)
- Mechanical overload
- Check connecting cable motor/ converter (phase missing, exchanged)

Remedy
Check above parameters and correct.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II
7.3 List of faults and alarms

136 **Conv.factor,feedforward contr.speed,parameter set \%d,cannot be represented**

**Cause**
The conversion factor in the position controller between velocity and speed cannot be displayed. This factor depends on the following parameters:
- Spindle pitch (P0236), for linear axes
- Gearbox ratio (P0238:8 / P0237:8).

**Remedy**
Check the above mentioned parameters and correct.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II

137 **Conv.factor,pos.contr.output,parameter set \%d,cannot be represented**

**Cause**
The conversion factor in the position controller between the following error and the speed setpoint cannot be represented. This factor depends on the following parameters:
- Spindle pitch (P0236) (for linear axes)
- Gearbox ratio P0238:8 / P0237:8
- Position control loop gain P0200:8

**Remedy**
Check the above mentioned parameters and correct.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II

138 **Conversion factor between the motor and load too high**

**Cause**
The conversion factor between the motor and load is greater than 2 to the power of 24 or less than 2 to the power of -24.

**Remedy**
Check the following parameters and correct:
P0236, P0237, P0238, P1005, P1024

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

139 **Modulo range and ratio do not match**

**Cause**
For EnDat absolute value encoders or for distance-coded measuring systems the ratio between the encoder and load must be so that the full range of the encoder is a multiple of the modulo range. The following condition must be fulfilled (for single turn or for distance-coded encoder 1 instead of P1021/P1031):
- IM: P1021 * P0238:8 / P0237:8 * 360 / P0242 must be an integer number.
- DM: P1031 * 360 / P0242 must be an integer number

**Remedy**
- Check and correct P1021, P0238:8, P0237:8
- Adapt the modulo range (P0242)

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

140 Minus hardware limit switch

Cause A 1/0 edge was identified at the "Minus hardware limit switch" input signal.

Remedy Return the drive into the traversing range using jog button 1 or 2. Then acknowledge the fault.

Acknowledgement RESET FAULT MEMORY

Stop response STOP III

141 Plus hardware limit switch

Cause A 1/0 edge was identified at the "Plus hardware limit switch" input signal.

Remedy Return the drive into the traversing range using jog button 1 or 2. Then acknowledge the fault.

Acknowledgement RESET FAULT MEMORY

Stop response STOP III

142 Input I0.x not parameterized as equivalent zero mark

Cause When entering an external signal as equivalent zero mark (P0174 = 2), input I0.x must be assigned "equivalent zero mark" function (Fct. No.: 79). If a direct measuring system is used, input I0.B must be assigned the "equivalent zero mark" function (Fct. No.: 79).

Remedy - Motor measuring system: P0660 = 79
- Direct measuring system: P0672 = 79

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV

143 Endless traversing and external block change in block

Cause The block change enable CONTINUE_EXTERNAL for the ENDLESS_POS or ENDLESS_NEG command is only permitted with P0110 = 0 or 1.

Remedy Block change enable or change P0110.

Acknowledgement RESET FAULT MEMORY

Stop response STOP VI

144 Switching-in/switching-out MDI erroneous

Cause In the active traversing program, MDI was switched-in or, in the active MDI block, MDI was switched-out.

Remedy Acknowledge fault
Change P0110

Acknowledgement RESET FAULT MEMORY

Stop response STOP II
7.3 List of faults and alarms

145 Fixed endstop not reached

Cause
In a traversing block with the FIXED ENDSTOP command, the fixed endstop was not reached. The fixed endstop lies outside the position programmed in this block.
After interrupting the function, traverse to fixed stop, the drive was pushed out of its position (drop position).

Remedy
Check programming
Increase kP0326 if the drive was forced out of the position.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP V

146 Fixed endstop, axis outside the monitoring window

Cause
In the "Fixed endstop reached" status, the axis has moved outside the defined monitoring window.

Remedy
- Check P0116:8 (fixed endstop, monitoring window)
- Check mechanical system

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

147 Enable signals withdrawn at the fixed endstop

Cause
Possible causes are:
- One of the following enable signals was withdrawn while traversing to the fixed endstop: Terminals 48, 63, 64, 663, 65.x, PROFIBUS and bus enable signals, PC enable from SimoCom U
- Another fault has occurred, which causes the controller or pulse enable to be withdrawn

Remedy
Set the enable signals and check the cause of the first fault and remove.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

148 Velocity in block \%n outside the range

Cause
The velocity specified in this block lies outside the range (6 to 2 000 000 000 c*MSR/min).

Remedy
Change the velocity in the block

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP VI
149 Incorrect data for modulo axis with absolute encoder.
Supplementary info \%u

Cause
- Data error for modulo drive with absolute encoder and any gear factor.
- Data was not able to be saved after power-on.
- Absolute position was not able to be read-out of the encoder.
- P1021 * P0238:8 / P0237:8 * 360 / P0242 must be greater than or equal to 1.
- Modulo range must be n * 360 Degrees with n = 1, 2, ....
- Drive booting was interrupted.
- When parameter set > 0 is selected the ratios P0238:8 / P0237:8 are not equal.

Supplementary information: only for siemens-internal error diagnostics

Remedy
- Adjust the drive by setting the absolute value.
- Check the switching threshold in P1162 (minimum DC link voltage).
- Check the hysteresis of the DC link voltage monitoring in P1164.
- Check parameters P0237:8, P0238:8, P0242.
- Check that the DC link voltage is deactivated (P1161 = 0).
- Wait until "run" appears in the seven-segment display before booting.
- Check that the activation threshold is less than the DC link voltage (P1162 + P1164 < P1701).

Acknowledgement
POWER ON

Stop response
STOP V

150 External position reference value < max. traversing range suppl. info \%u

Cause
The external position reference value has exceeded the upper traversing range limit.

Supplementary info = 0:
Limit exceeded after the coupling factors P0401/P0402 identified, i.e. P0032 > 200 000 000 MSR.

Supplementary info = 1:
Limit exceeded after the coupling factors P0401/P0402 identified, i.e. P0032 * P0402 / P0401 > 200 000 000 MSR.

Remedy
Return the external position reference value to the value range. Then acknowledge the fault.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II
7.3 List of faults and alarms

151 External position reference value < min. traversing range suppl. info %u

Cause
The external position reference value has fallen below the lower traversing range limit.
Supplementary info = 0:
Limit fallen below after the coupling factors P0401/P0402 identified, i.e. P0032 < - 200 000 000 MSR.
Supplementary info = 1:
Limit fallen below after the coupling factors P0401/P0402 identified, i.e. P0032 * P0402 / P0401 < - 200 000 000 MSR.

Remedy
Return the external position reference value to the value range. Then acknowledge the fault.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

152 Pos.ref.val. and act.val. output via the bus interf. limited. Suppl. info %X

Cause
The output of the position reference value, position actual value or position correction value is parameterized via PROFIBUS or the bus interface. However, the value to be output can no longer be represented in 32 bits and was therefore limited to the maximum values 0x7ffffff or 0x80000000.
The traversing range which can be displayed is given by
Lower limit: \(-2147483648 \times \frac{P896}{P884}\)
Upper limit: \(+2147483647 \times \frac{P896}{P884}\)
The supplementary information explains which process data has violated the lower or upper limit:

<table>
<thead>
<tr>
<th>Supplementary info process data</th>
<th>Violation</th>
</tr>
</thead>
<tbody>
<tr>
<td>xx1 Position reference value Xset (No. 50208)</td>
<td>Upper limit exceeded</td>
</tr>
<tr>
<td>xx2 Position reference value Xset (No. 50208)</td>
<td>Lower limit fallen below</td>
</tr>
<tr>
<td>x1x Position actual value Xact (No. 50206)</td>
<td>Upper limit exceeded</td>
</tr>
<tr>
<td>x2x Position actual value Xact (No. 50206)</td>
<td>Lower limit fallen below</td>
</tr>
<tr>
<td>1xx Position correction value dxKorr (No. 50210)</td>
<td>upper limit exceeded</td>
</tr>
<tr>
<td>2xx Position correction value dxKorr (No. 50210)</td>
<td>lower limit fallen below</td>
</tr>
</tbody>
</table>

Remedy
- Move drive back e.g. by jogging in the representable traversing range.
- Adapt the lower and upper limit to the required traversing range using P884 and P896.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP III
160 **Reference cam not reached**

**Cause**
After starting the reference point approach, the axis moves through the distance in P0170 (max. distance to the reference cam) without finding the reference cam.

**Remedy**
- Check the "reference cam" signal
- Check P0170
- If it is an axis without reference cam, then set P0173 to 1

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

161 **Reference cams too short**

**Cause**
When the axis moves to the reference cam, and does not come to a standstill at the cam, then this error is signaled, i.e. the reference cam is too short.

**Remedy**
- Set P0163 (reference point approach velocity) to a lower value
- Increase P0104 (maximum deceleration)
- Use larger reference cam

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

162 **No zero reference pulse present**

**Cause**
- After the reference cam has been left, the axis has moved through the distance in P0171 (max. distance between the reference cam/zero pulse), without finding a zero pulse.
- For distance-coded measuring system (from SW 8.3 onwards):
The maximum permissible distance (clearance) between two reference marks was exceeded.

**Remedy**
- Check the encoder with reference to the zero mark
- Set P0171 to a higher value

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP V

163 **Encoderless operation and operating mode do not match**

**Cause**
Encoderless operation was parameterized (P1006) and the "Positioning" mode selected.

**Remedy**
Set operating mode "speed/torque setpoint" (P0700 = 1)

**Acknowledgement**
POWER ON

**Stop response**
STOP V

164 **Coupling released during the traversing job.**

**Cause**
The coupling was disconnected while a traversing task was running

**Remedy**
First exist the traversing task and then disconnect the coupling.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP III
### 7.3 List of faults and alarms

<table>
<thead>
<tr>
<th>Fault Number</th>
<th>Description</th>
<th>Cause</th>
<th>Remedy</th>
<th>Acknowledgement</th>
<th>Stop response</th>
</tr>
</thead>
<tbody>
<tr>
<td>165</td>
<td><strong>Absolute positioning block not possible</strong></td>
<td>Traversing blocks with absolute position data are not permitted while the axis coupling is activated.</td>
<td>Correct traversing block</td>
<td>RESET FAULT MEMORY</td>
<td>STOP IV</td>
</tr>
<tr>
<td>166</td>
<td><strong>Coupling not possible</strong></td>
<td>- No coupling can be established in the actual operating status.</td>
<td>- Check the coupling configuration (P0410)</td>
<td>RESET FAULT MEMORY</td>
<td>STOP VI</td>
</tr>
<tr>
<td></td>
<td></td>
<td>- For P0891=2 or 3, it is not possible to couple using the input signal &quot;Activate coupling through I0.x&quot; (fast input).</td>
<td>- Set angular encoder interface (P0890, P0891)</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>- Check the source of the external position reference value and input signal source.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>167</td>
<td><strong>Activate coupling signal present</strong></td>
<td>- The input signal &quot;Activate coupling&quot; is present. An edge of the input signal is necessary to activate the coupling.</td>
<td>Reset &quot;Activate coupling&quot; input signal</td>
<td>RESET FAULT MEMORY</td>
<td>STOP II</td>
</tr>
<tr>
<td></td>
<td></td>
<td>- In the jog mode, while traversing, the input signal &quot;coupling on&quot; was entered.</td>
<td>Acknowledge fault</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>- The &quot;coupling in&quot; input signal was entered in handwheel operation.</td>
<td>Set the input signal again to switch-in the coupling</td>
<td></td>
<td></td>
</tr>
<tr>
<td>168</td>
<td><strong>Overflow, buffer memory</strong></td>
<td>Occurs for couplings with queue functionality. A maximum of 16 positions can be saved in P0425:16.</td>
<td>Ensure that maximum 16 positions are saved.</td>
<td>POWER ON</td>
<td>STOP IV</td>
</tr>
</tbody>
</table>
169 Coupling trigger missed

Cause Occurs for couplings with queue functionality. Synchronization is requested using the KOPPLUNG_ON command and it is identified that the position at which the coupling is switched-in, has already been passed.

Remedy Ensure that the slave drive was stationary for at least 1 IPO clock cycle (P1010), before the coupling for the next element in the position memory must be switched-in.

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV

170 Coupling switched-out during the traversing program

Cause While the drive was executing a traversing program, the "Activate coupling" input signal was reset.

Remedy Only switch-out the coupling if the traversing program has been completed.

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV

171 Coupling not possible

Cause While the drive was executing a traversing program, the "Active coupling" input signal was set.

Remedy Only switch-in the coupling if the traversing program has been completed.

Acknowledgement RESET FAULT MEMORY

Stop response STOP V

172 External block change for coupling not possible

Cause If there is an existing coupling, traversing blocks with external block enable are only permitted if P0110 = 2.

Remedy Correct traversing program Change P0110 (configuration, external block change)

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV

173 Coupling and traverse to endstop simultaneously

Cause Not possible to simultaneously couple and traverse to the endstop.

Remedy Correct traversing program

Acknowledgement RESET FAULT MEMORY

Stop response STOP V
7.3 List of faults and alarms

174 Passive referencing not possible

Cause For the passive referencing, the encoder interface must be switched as input and the "Positioning" mode must be set.

Remedy - Set the "Positioning" mode (P0700)
- Set angular encoder interface (P0890, P0891)

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV

175 Passive referencing not realized. Supplementary info: 

Causes While the master drive corrects the zero mark offset, the slave drive must pass over a zero mark.

Supplementary information
0 = reference cam not found
1 = Reference cam not left
2 = Zero reference pulse not found

Remedy Ensure that the cam of the slave drive is located between the cam and the reference point of the master drive. Appropriately shift the cam and/or increase the reference point offset (P0162) at the master drive. If the zero pulse is not found, the reference point offset (P0162) must also be increased at the master drive.

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV

176 Absolute encoder must be adjusted

Cause Passive referencing with absolute encoders (e.g. EnDat encoders) is only possible after the encoder has been adjusted.

Remedy Adjust the drive by setting the absolute value.

Acknowledgement RESET FAULT MEMORY

Stop response STOP IV
7.3 List of faults and alarms

177 Start-up passive referencing P179 not possible

Cause
The start-up help for passive referencing determines the reference point offset in P0162 in the slave drive. The following prerequisites must be available:
- (permanent) position coupling exists to the master drive
- Master drive must be precisely at its reference point
- Slave drive has passed the zero mark.

Remedy
- Establish a coupling at the slave drive: PosStw.4 or input terminal function 72/73
- Reference the master drive: STW1.11 or input terminal function 65 at the master drive
- "Wiring" check: The requirement for passive referencing must be transferred from the master to the slave drive:
  Masterdrive: Output via ZSW1.15, QZsw.1 or output terminal function 69
  Slave drive: read-in via STW1.15, QStw.1 or input terminal function 69

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

180 Teach-in without reference point

Cause
Teach-in only possible for a referenced axis.

Remedy
Request reference axis and teach in

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP IV

181 Teach-in block invalid

Cause
The specified teach-in block is invalid.

Remedy
Specify the valid and existing traversing block.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP IV

182 Teach-in standard block invalid

Cause
The specified teach-in standard block is invalid.

Remedy
Specify the valid and existing traversing block.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP IV

183 Teach-in block not found

Cause
The specified teach-in block is not found.

Remedy
Select the valid and existing traversing block.
Activate "Automatically search for block number" function.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP IV
### 7.3 List of faults and alarms

<table>
<thead>
<tr>
<th>Fault Code</th>
<th>Fault Description</th>
<th>Cause</th>
<th>Remedy</th>
<th>Acknowledgement</th>
<th>Stop response</th>
</tr>
</thead>
<tbody>
<tr>
<td>184</td>
<td>Teach-in standard block not found</td>
<td>The specified teach-in standard block is not found.</td>
<td>Generate the required standard block for the specified block number</td>
<td>Enter the correct block number.</td>
<td>RESET FAULT MEMORY</td>
</tr>
<tr>
<td>185</td>
<td>Positioning mode invalid</td>
<td>For the &quot;Spindle positioning&quot; function, the positioning mode (P0087) is not valid.</td>
<td>Program traversing block positioning as absolute, absolute positive or absolute negative.</td>
<td>RESET FAULT MEMORY</td>
<td>STOP II</td>
</tr>
</tbody>
</table>
| 186        | Spindle cannot be referenced, supplementary info \%d    | For the "Spindle positioning" function, an error has occurred while positioning. | Supplementary info  
   Significance  
   0  the distance between the last two zero marks was not correct.  
   1  For two revolutions a zero mark was no longer detected, which was in a tolerance bandwidth of P0126. | RESET FAULT MEMORY               | STOP II       |

Remedy: Check cable and connections.
7.3 List of faults and alarms

187 Conversion factor spindle pos. cannot be represented, supplementary info \( \%d \)

**Cause**
Conversion factors for spindle positioning was not able to be initialized
Supplementary info, ones and tens position:
00: Conversion factor, velocity to speed too small
01: Conversion factor, velocity to speed too high
02: Conversion factor, adaptation filter too low (\( \rightarrow \) increase P0210)
03: Conversion factor, adaptation filter too high (\( \rightarrow \) reduce P0210)
04: Conversion factor, pre-control balancing filter too low
(\( \rightarrow \) increase P0206)
05: Conversion factor, pre-control balancing filter too high
(\( \rightarrow \) reduce P0206)
06: Conversion factor, sum delay too small
07: Conversion factor, sum delay too large
08: Conversion factor, following error model too small
09: Conversion factor, following error model too large
The hundreds position of the supplementary info contains the parameter set involved.

**Remedy**
Check and correct specified parameters.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II

188 Spindle positioning: P\( \%d \) illegal

**Cause**
Spindle positioning requires the following parameterization:
P0241 = 1
P0100 = 3

**Remedy**
Correct the specified parameter or cancel spindle positioning by setting P0125 to 0.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II

189 Jogging, incremental invalid

**Cause**
1. Jogging incremental is not valid in this mode.
2. An attempt was made to move an axis away from a software limit switch using incremental jogging - however the axis is not at the software limit switch, but behind it.
3. An attempt was made while executing one or several traversing blocks (also via an axis coupling) to activate incremental jogging.

**Remedy**
1. Commission the drive in the positioning mode.
2. Move back with jog key 1 or 2 with velocity.
3. Interrupt traversing blocks with the operating condition, reject traversing task.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP VI
7.3 List of faults and alarms

190 Actual firmware does not support spindle positioning

Cause This firmware does not support the spindle positioning function.

Remedy Set parameter P0125 to 0

Acknowledgement POWER ON

Stop response STOP II

191 Zero mark setting unsuccessful

Cause It is not possible to set the internal zero mark, if
1. Input signal "Spindle positioning on" is set, or
2. Still no zero mark found.

Remedy Maintain the following sequence:
1. Execute spindle positioning --> zero mark found
2. Withdraw input signal "spindle positioning on"
3. Set the internal zero mark (P0127=1).

Acknowledgement RESET FAULT MEMORY

Stop response STOP II

192 Max. search velocity too high

Cause The maximum search velocity for spindle positioning is greater than the maximum motor speed.

Remedy Reduce parameter P0133 or reduce the velocity in the traversing block.

Acknowledgement RESET FAULT MEMORY

Stop response STOP II

193 Zero mark not found

Cause The zero mark (encoder or equivalent zero mark, e.g. BERO) was not found. Gearbox ratio (mechanical system) was not correctly parameterized using parameter P0237/P0238.

Remedy - Check the equivalent zero mark (BERO) function, if required, replace the BERO
- Readjust the clearance when using BERO
- Check the cabling
- Correctly parameterize the gearbox ratio (mechanical system) using parameter P0237/P0238

Acknowledgement RESET FAULT MEMORY

Stop response STOP II

194 Spindle positioning is only possible with motor 1

Cause Spindle positioning is only possible with motor 1.

Remedy Activate motor data set 1 before the spindle positioning command.

Acknowledgement RESET FAULT MEMORY

Stop response STOP II
7.3 List of faults and alarms

195 Speed pre-control not permissible

Cause
Speed pre-control is not permissible with spindle positioning.

Remedy
Cancel the speed pre-control (P0203)

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

196 Illegal combination of input signals (warning \%u)

Cause
An illegal combination of signals is present at the inputs, at the Profibus control words or at the appropriate bus signals. The detailed cause of the error can be taken from the help text associated with the warning that is entered as supplementary information.

This fault can be activated or suppressed using Parameter P338.

Supplementary information: Warning number

Remedy
Change the input signals or suppress the fault using P338.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II

501 Measuring circuit error, absolute current

Cause
1. The smoothed absolute current (P1254, current monitoring time constant) is greater than 120 % of the permissible power section current (P1107).
2. For an active rotor position identification, the permissible current threshold was exceeded.
3. The P gain of the controller (P1120) has been set too high.

Remedy
- Motor/controller data not correct
- For active rotor position identification P1019 (current, rotor position identification) check and if required reduce
- Reduce the P gain of current controller (P1120), check the current controller adaptation (P1180, P1181, P1182)
- Replace control module
- Replace the power section

Acknowledgement
POWER ON

Stop response
parameterizable
7.3 List of faults and alarms

504 Measuring circuit error, motor measuring system

Cause
The encoder signal level is too low, faulted (incorrect shielding), or the cable breakage monitoring function has responded. After separately shutting down the supply voltage at the drive, for SIMODRIVE 611 universal HRS with 1Vpp encoder or SIMODRIVE universalE HRS with 1Vpp encoder, this fault message can be output during the shutdown procedure without any significance for the control.

Remedy
- Use the original Siemens pre-assembled encoder cables (better screening)
- Check for sporadic interruptions (loose contact, e.g. when the drag cable is being moved)
- For toothed-wheel encoders, check the clearance between the toothed wheel and sensor
- Check the encoder, encoder cables and connectors between the motor and control module
- Check the screen connection at the front panel of the control module (top screw)
- Replace the encoder cables or the control module
- Exchange the encoder or motor
- If this fault was signaled without any significance, then it should either be acknowledged in the control or the drive and control should be powered-down together.

Acknowledgement
POWER ON

Stop response parameterizable

505 Meas.circ.error motor meas.syst.abs.track

Cause
1. The motor absolute track (CD track) is monitored for an interrupted conductor. For optical encoders, the absolute track supports the evaluation of the mechanical position within one motor revolution.
2. For absolute encoders with EnDat interface, this fault displays an initialization error.

Note:
Additional information on the reason for the fault is included in P1023 (IM diagnostics).

Remedy
- Incorrect encoder cable type
- Check for sporadic interruptions (loose contact, e.g. when the drag cable is being moved)
- Remove noise which is coupled in due to inadequate screening of the cable by replacing the encoder cable
- Incorrect encoder type configured (e.g. ERN instead of EQN)
- Check the encoder, encoder cables and connectors between the motor and control module
- Replace control module
- Replace encoder

Acknowledgement
POWER ON

Stop response parameterizable
**507  Synchronization error rotor position**

**Cause**
The difference between the actual rotor position and the new rotor position, which was determined by fine synchronization is greater than 45 degrees electrical. When commissioning a linear motor with rotor position identification (e.g. linear motor, 1FE1 motor), the fine synchronization was not adjusted.

**Remedy**
- Adjust the fine synchronization using P1017 (commissioning help function)
- Check encoder cable, encoder cable connection and grounding (possibly EMC problems)
- Check the shield contact, front panel, control module (upper screw)
- Replace control module
- Exchange the encoder or motor

**Acknowledgement**
POWER ON

**Stop response**
parameterizable

**508  Zero mark monitoring, motor measuring system**

**Cause**
The measured rotor position fluctuates between 2 encoder zero marks (encoder lines may have been lost).

**Note:**
The encoder monitoring function can be disabled using P1600.8.

**Remedy**
- Use the original Siemens pre-assembled encoder cables (better screening)
- Check for sporadic interruptions (loose contact, e.g. due to cable drag movements)
- For toothed-wheel encoders, check the clearance between the toothed wheel and sensor
- Check the encoder, encoder cables and connectors between the motor and control module
- Check the shield contact, front panel, control module (upper screw)
- Replace the encoder cables or the control module
- Replace control module
- Exchange the encoder or motor

**Acknowledgement**
POWER ON

**Stop response**
parameterizable
7.3 List of faults and alarms

509 Drive converter limiting frequency exceeded

Cause
The drive converter has exceeded the maximum permissible drive converter frequency.

Remedy
- Encoder pulse number is too low, enter the actual encoder pulse number in P1005
- Stop the belt slipping in open-loop torque controlled mode (the belt slips)
- Check P1400 (rated motor speed)
- Check P1146 (maximum motor speed)
- Check P1147 (speed limiting)
- Check P1112 (motor pole pair number)
- Check P1134 (rated motor frequency)

Acknowledgement
RESET FAULT MEMORY

Stop response parameterizable

510 Positive feedback identified

Cause
Ramp-up:
The actual rotor position and the position information read-out of the encoder were compared with one another while booting and a deviation of more than 45 Degrees was identified, P1011[10].

Operational:
The acceleration/velocity direction is different than the torque(force direction).

This monitoring function can be set using P1645 and P1646.

Remedy
- This alarm can also occur when axes are mechanically blocked.
  Check the fault cause analog to Alarm 605 "Speed controller output limited".
- Operation may only be resumed after the fault has been removed otherwise there is a danger of uncontrollable motion.

Ramp-up:
- The deviation is due to dirt on the encoder or incorrect mounting/installation of the encoder or encoder cable.

Operational:
- If the load oscillates strongly increase the delay for the monitoring (P1645).
- Caution: The value in P1645 influences the duration of the axis motion, triggered by positive feedback until the fault responds.
- Check the encoder: Mounting, dirt, absolute track fault, lost pulses, encoder cable

Acknowledgement
POWER ON

Stop response parameterizable
7.3 List of faults and alarms

511 Ground fault detected

Cause
Firmware has detected a ground fault.
Measured phase currents are greater than the response value of the
ground fault test configured in P1167 or the motion is greater than the
maximum permitted motion for the ground fault test configured in
P1168.

Remedy
- Ground fault in the power cables or at the motor.
During the ground fault test, at least one phase increases above the
threshold P1167 or P1168.
Detailed information can be taken from the diagnostics parameter
P1169.

Acknowledgement
POWER ON
Stop response
parameterizable

512 Measuring circuit error, direct measuring system

Cause
The encoder signal level is too low, faulted (incorrect shielding), or the
cable breakage monitoring function has responded.

Remedy
- Use the original Siemens pre-assembled encoder cables
  (better screening)
- Check for sporadic interruptions (loose contact, e.g. due to cable
drag movements)
- For toothed-wheel encoders, check the clearance between the
toothed wheel and sensor
- Check the encoder, encoder cables and connectors between the
  encoder and control module
- Check the shield contact, front panel, control module (upper screw)
- Replace the encoder cables or the control module
- Replace encoder

Acknowledgement
POWER ON
Stop response
parameterizable
513 Measuring circuit error, direct measuring system absolute track

Cause
For absolute encoders with EnDat interface, this fault indicates an initialization error.

Note:
Additional information on the reason for the fault is included in P1033 (DM diagnostics).

Remedy
- Incorrect encoder cable type
- Check for sporadic interruptions (loose contact, e.g. when the drag cable is being moved)
- Remove noise which is coupled in due to inadequate screening of the cable by replacing the encoder cable
- Incorrect encoder type configured (e.g. ERN instead of EQN)
- Check the encoder, encoder cables and connectors between the encoder and control module
- Replace control module
- Replace encoder

Acknowledgement POWER ON
Stop response parameterizable

514 Zero mark monitoring, direct measuring system

Cause
A fluctuation in the measured values has occurred between 2 encoder zero marks (encoder pulses may have been lost).

Note:
The encoder monitoring can be disabled using P1600.14.

Remedy
- Use the original Siemens pre-assembled encoder cables (better screening)
- Check for sporadic interruptions (loose contact, e.g. due to cable drag movements)
- For toothed-wheel encoders, check the clearance between the toothed wheel and sensor
- Check the encoder, encoder cables and connectors between the motor and control module
- Check the shield contact, front panel, control module (upper screw)
- Replace the encoder cables or the control module
- Replace encoder

Acknowledgement POWER ON
Stop response parameterizable
515  **Power module temperature, exceeded**

**Cause**
The power section temperature is sensed using a temperature sensor on the heatsink. The drive is immediately shut down 20 seconds after the heatsink temperature alarm in order to prevent the power section being thermally destroyed (regenerative stop).

**Remedy**
Improve the drive module cooling, e.g. using:
- Higher airflow in the switching cabinet, possibly cool the ambient air of the drive modules
- Avoid many acceleration and braking operations which follow quickly one after the other
- Check that the power section for the axis/spindle is adequate, otherwise use a higher-rating module
- Ambient temperature too high (refer to the Planning Guide)
- Permissible installation altitude exceeded (refer to the Planning Guide)
- Pulse frequency too high (refer to the Planning Guide)
- Check fan, if required, replace
- Maintain the minimum clearance above and below the power section (refer to the Planning Guide)

**Acknowledgement**
POWER ON

**Stop response**
parameterizable

591  **Pos.contr.clock cycle not equal to DP clock cycle/master applic. clock cycle**

**Cause**
For a 2-axis module, one axis is in the n-set mode and one axis in the positioning mode. For the axis in the n-set mode, a position controller clock cycle (of the master) is entered via the clock-cycle synchronous PROFIBUS or the bus interface. This position controller clock cycle differs from the parameterized position controller clock cycle (P1009) of the axis in the positioning mode. The position controller clock cycle of the master is obtained, in the n-set mode, from the DP clock cycle (Tdp) or the clock cycle of the bus interface multiplied by the time grid Tmapc.

**Remedy**
For a clock cycle synchronous PROFIBUS (isochronous) or the bus interface, the clock cycles configured for the bus (parameterization) are aligned with the position controller clock cycle P1009 from the positioning axis and n-set axis.

**Acknowledgement**
POWER ON

**Stop response**
STOP II
592  Spindle positioning: Pos. contr. not equal to master application clock cycle

Cause
The function "spindle positioning" requires, for a clock-cycle synchronous PROFIBUS or the bus interface, that the position controller clock cycle of the master matches the parameterized position controller clock cycle (P1009). The position controller clock cycle of the master is obtained from the DP clock cycle (Tdp) multiplied by the time grid Tmapc.

Remedy
For the clock-cycle synchronous PROFIBUS or the bus interface, the clock cycles configured for the bus (parameterization) are aligned with the position controller clock cycle P1009.

Acknowledgement  POWER ON
Stop response  STOP II

593  Fieldbus: Drive is not in synchronism. Supplementary info: \%X

Cause
Supplementary information
0x01: The master sign-of-life has more consecutive failures than permitted. The permissible sign-of-life errors are specified using P0879 bits 2–0 (configuration).
0x02: The Global Control telegram to synchronize the clock cycles has failed in operation for several consecutive DP clock cycles or in several DP clock cycles has violated the time grid specified using the parameterizing telegram (refer to times Tdp and Tpliw). If the complete DP communications permanently fails, at the latest after the response monitoring times specified when configuring the bus, fault 595 is also output.

Remedy
- Check whether communications is briefly or continuously interrupted.
- Check whether the BUS master can operate in clock cycle synchronism and outputs the global control telegrams, necessary for clock cycle synchronous operation, in the equidistant DP clock cycle.
- Check whether clock synchronism has been activated in the bus configuration, although it is not controlled by the master used.
- Check whether the master sign-of-life is received and incremented in the parameterized clock cycle.

Acknowledgement  RESET FAULT MEMORY
Stop response  STOP II
595 **Fieldbus: Cyclic data transfer was interrupted**

**Cause**
The cyclic data transfer between the master and slave was interrupted due to the fact that cyclic frames were missing, or due to the reception of a parameterizing or configuring frame.

Examples:
- Bus connection interrupted
- Master runs up again
- Master has changed into the ‘Clear’ state

For a passive axis, fault cannot be acknowledged using "RESET FAULT MEMORY”.

**Remedy**
Check the master and bus connection to the master. As soon as cyclic data transfer runs again, the fault can be acknowledged.

Set P0875 to 0 in the passive axis.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II

596 **PROFIBUS: Connection to the publisher \%u interrupted**

**Cause**
Cyclic data transfer between this slave and a slave-to-slave communications publisher was interrupted as cyclic telegrams were missing.

Examples:
- Bus connection interrupted
- Publisher failure
- Master runs up again
- The response monitoring (Watchdog) for this slave was de-activated via the parameterizing telegram (SetPrm)
  (Diagnostics: P1783:1 bit 3 = 0).

**Supplementary info:** PROFIBUS address of the publisher

**Remedy**
Check the publisher and bus connections to the publisher, to the master and between the master and publisher. If the watchdog is de-activated, activate the response monitoring for this slave via Drive ES.

As soon as cyclic data transfer runs again, the fault can be acknowledged.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II
597  PROFIBUS: Drive not in synchronism. Supplementary information: \%X

Cause
Supplementary information
0x01:
The master sign-of-life (STW2, bits 12-15) has more consecutive failures than permitted. The permissible sign-of-life error is specified using P0879 bit 2-0 (PROFIBUS configuration).
0x02:
The Global Control telegram to synchronize the clock cycles has failed in operation for several DP cycles in a row or has violated the time grid (refer to times Tdp and Tpllw) - specified using the parameterizing telegram - for several DP clock cycles in a row. If the complete DP communications fails permanently, then Fault 599 is also output - at the latest after the response monitoring time specified when the bus was configured, expires.

Remedy
- Check whether communications is briefly or continuously interrupted.
- Check whether the PROFIBUS master can operate in clock cycle synchronism and the Global Control Telegrams, required for clock cycle synchronous operation, are output in the equidistant DP clock cycle.
- Check whether clock synchronism has been activated in the bus configuration, although it is not controlled by the master used.
- Check whether the master sign-of-life (STW2, bits 12-15) is received and is incremented in the parameterized clock cycle.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II
598  PROFIBUS: Synchronization error. Supplementary info: \%X

Cause  Supplementary information
0x01: The expected 1st global control clock cycle display did not occur within the waiting time.
0x02: PLL synchronization unsuccessful
0x03: When synchronizing to the clock cycle, the global control clock cycle had more consecutive failures than are permitted.
0x06: The data frames w. the process data (setpoint direction) were only received after the time (To=125 μs)) in the slave has expired.

Remedy  - Check whether the PROFIBUS master can operate in synchronism with the clock cycle, and that the necessary global-control frames are output for operation in synchronism with the clock cycle.
- Check whether clock synchronism has been activated in the bus configuration, although it is not controlled by the master used.
- Check whether the equidistant DP clock cycle, transferred with the parameterizing telegram, was actually set and activated at the master.
- Check whether the time Tdx - defined in the master configuring - corresponds to the actual data transfer time to all slaves and is less than the configured time (To=125 μs).

Acknowledgement  RESET FAULT MEMORY
Stop response  STOP II

599  PROFIBUS: Cyclic data transfer was interrupted

Cause  The cyclic data transfer between the master and slave was interrupted due to the fact that cyclic frames were missing, or due to the reception of a parameterizing or configuring frame.
Examples:
- Bus connection interrupted
- Master runs up again
- Master has changed into the 'Clear' state
For a passive axis, fault cannot be acknowledged using "RESET FAULT MEMORY".

Remedy  Check the master and bus connection to the master. As soon as cyclic data transfer runs again, the fault can be acknowledged.
Set P0875 to 0 in the passive axis.

Acknowledgement  RESET FAULT MEMORY
Stop response  STOP II
<table>
<thead>
<tr>
<th>Fault Code</th>
<th>Description</th>
<th>Cause</th>
<th>Remedy</th>
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<tbody>
<tr>
<td>600</td>
<td>Pole position (P1016) has not been set</td>
<td>The pole position set (P1016) is 0. Commissioning using P1017= -1 is only possible if P1016 is not equal to 0.</td>
<td>First measure the pole position and enter ( P1016 ), then complete commissioning ( P1017 = -1 ). If P1016 should be precisely 0, enter 0.001.</td>
<td>RESET FAULT MEMORY</td>
<td>parameterizable</td>
</tr>
<tr>
<td>601</td>
<td>Error in AD conversion, terminal 56/14 or 24/20</td>
<td>A timing error was identified when reading-out the A/D converter for terminal 56.x/14.x or 24.x/20.x. The read values are probably incorrect/faulty.</td>
<td>Replace closed-loop control module</td>
<td>RESET FAULT MEMORY</td>
<td>parameterizable</td>
</tr>
<tr>
<td>602</td>
<td>Open-loop torque controlled oper. w/o encoder is not perm.</td>
<td>In the IM mode, open-loop torque controlled operation was selected via an input terminal or via PROFIBUS-DP or the bus interface.</td>
<td>Deselect the torque-controlled operation or leave the IM mode (change-over speed P1465).</td>
<td>RESET FAULT MEMORY</td>
<td>parameterizable</td>
</tr>
<tr>
<td>603</td>
<td>Changeover to non-parameterized motor data set</td>
<td>An attempt was made to change over to a motor data set which was not parameterized.</td>
<td>Parameterizing motor data set</td>
<td>RESET FAULT MEMORY</td>
<td>parameterizable</td>
</tr>
</tbody>
</table>
604  **Motor encoder is not adjusted**  
**Cause**  
For an EnDat motor measuring system, it was identified that the serial number does not match that saved, i.e. the encoder has still not run with this drive.

**Remedy**  
1FN3 linear motors (if P1075=1):  
Measure the rotor position offset to the EMF of the U_R phase and add to P1016 as the commutation angle offset. Then set P1017 to -1 in order to save the serial number of the EnDat encoder.  
otherwise:  
To determine commutation angle offset in P1016, initiate the rotor position identification routine via P1017=1. The rotor position identification routine is executed by acknowledging the fault and setting the enable signals.  
Note:  
also refer to description of P1017

**Acknowledgement**  
RESET FAULT MEMORY

**Stop response**  
parameterizable

605  **Position controller output limited**  
**Cause**  
The speed setpoint requested from the position controller lies above the max. motor speed.  
Possible causes:  
- Programmed velocity (P0082:256) too high  
- Max. acceleration (P0103) or deceleration (P0104) too high  
- Axis is overloaded or blocked

**Remedy**  
- Check and correct the above parameter

**Acknowledgement**  
RESET FAULT MEMORY

**Stop response**  
parameterizable

606  **Flux controller output limited**  
**Cause**  
The specified flux setpoint cannot be realized, although maximum current is input.  
- Motor data are incorrect  
- Motor data and motor connection type (star/delta) do not match  
- Motor has stalled because motor data are extremely inaccurate  
- Current limit is too low for the motor (0.9 * P1238 * P1103 < P1136)  
- Power section is too small

**Remedy**  
- Correct the motor data  
- If required use a larger power section

**Acknowledgement**  
RESET FAULT MEMORY

**Stop response**  
parameterizable
7.3 List of faults and alarms

607 Current controller output limited
Cause The entered setpoint cannot be impressed in the motor, although the maximum voltage has been entered. The cause could be that the motor is not connected, or a phase is missing.
Remedy
- Check the connecting cable, motor/drive converter (phase missing)
- Check the motor contactor
- DC link voltage present?
- Check the DC link busbar (check that the screws are tight)
- Uce monitoring function in the power section has responded (RESET by powering off/powering on)
- Replace the power section or control module
Acknowledgement RESET FAULT MEMORY
Stop response parameterizable

608 Speed controller output limited
Cause The speed controller is at its limit for an inadmissibly long time (torque and current limit). The permissible duration is defined in P1605, the speed upper limit up to when the monitoring responds is defined in P1606.
Synchronous motor:
In normal operation, the correct, optimized axis drive should never reach its current limit - not even for extremely large speed changes (changeover sequences from rapid traverse in the positive direction to rapid traverse in the negative direction).
P1605 = 200 ms
P1606 = 8000 rev/min
Induction motor:
Acceleration and braking with the maximum torque/current are usual in operation, only a stalled drive (0 speed) is monitored.
P1605 = 200 ms
P1606 = 30 rev/min
1. At the first commissioning, after the software has been replaced or the software has been upgraded, after the parameters have been entered the "calculate motor data" or "calculate controller data" function was not executed. The drive then keeps the default values (for the values to be calculated this is zero) which can, under certain circumstances, result in this fault (P1605 and P1606 should be adapted to the mechanical and dynamic capabilities of the axis).
2. An undesirable input of a high torque reduction via the analog inputs or via PROFIBUS and the bus interface. For PROFIBUS and the bus interface, this effect especially occurs when changing from the positioning mode to the speed setpoint input mode (check as to whether a torque reduction is entered. Diagnostics using P1717, 0%: No torque, 100%: Full torque).
Remedy
- Check connecting cable motor/converter (phase missing, exchanged)
- Check the motor contactor
- Check the torque reduction (P1717)
- DC link voltage present?
- Check the DC link voltage (check that the screws are tight)
- Unblock the motor
- Is the motor encoder connected?
7.3 List of faults and alarms

- Check the motor encoder cable screen
- Is the motor grounded (PE connection)?
- Check the encoder pulse number (P1005)
- Does the encoder cable fit to the encoder type?
- Check the direction of rotation of the encoder tracks (e.g. toothed-wheel encoder, P1011)

Adapt parameters P1605 and P1606 to the mechanical and dynamic capabilities of the axis. Check whether a torque reduction has been entered (diagnostics via P1717, 0%: no torque, 100%: full torque).

For linear motors:
- Check actual value inversion
- Check the reduction in the maximum motor current (P1105) and if required increase the value
- Check the power cable connection
- For the parallel circuit configuration, are the motors correctly assigned and electrically connected?
- Ucemonitoringfunctioninthepowersectionhasresponded(RESETbypoweringoff/poweringon)
- Replace the power section or control module

Acknowledgement: RESET FAULT MEMORY

Stop response: parameterizable

609 Encoder limit frequency exceeded

Cause: The speed actual value exceeds the encoder frequency.
- Incorrect encoder
- P1005 does not correspond to the no. of encoder pulses
- Encoder defective
- Motor cable defective or not properly attached
- Shield on motor encoder cable is not connected
- Defective control module

Remedy:
- Enter correct encoder data / replace encoder
- Check the encoder pulse number (P1005)
- Attach motor cable correctly or replace
- Connect the motor encoder cable screen
- Reduce the speed setpoint input (P1401)
- Replace control module

Acknowledgement: RESET FAULT MEMORY

Stop response: parameterizable
7.3 List of faults and alarms

610 Rotor position identification has failed

**Cause**

if P1075=1 (technique based on saturation)
A rotor position could not be determined from the measurement signals (motor current), as no significant saturation effects occurred.
Also refer to parameter P1734 for detailed diagnostics.

if P1075=3 (motion-based technique)
1. Current increase too low.
2. Maximum permissible duration exceeded.
3. No clear rotor position found.

**Remedy**

if P1075=1
- Increase current via P1019  
- Check armature inductance (P1116) and if required, increase  
- Check the connecting cable, motor/drive converter (phase missing)  
- Check the motor contactor  
- DC link voltage present?  
- Check the DC link busbar (check that the screws are tight)  
- Uce monitoring function in the power section has responded (RESET by powering off/powering on)  
- Replace the power section or control module

if P1075=3
To 1.
- The motor is not correctly connected  
- The motor power connection must be checked

To 2.
- Remove disturbing external forces (e.g. axis couplings which are not released)  
- Identification technique must remain stable (P1076 must be reduced)  
- Use an encoder with higher resolution  
- Improve the encoder mounting (it is not stiff enough)

To 3.
- Remove disturbing external forces (e.g. axis couplings which are not released)  
- The axis must be able to freely move (e.g. the motor rotor may not be locked)  
- Reduce the high axis friction (increase P1019)

**Acknowledgement**

RESET FAULT MEMORY

**Stop response**

parameterizable
611 Illegal motion during rotor position identification

Cause
During the rotor position identification (motor current measurement), the motor rotated more than the value entered in P1020. The rotation could be caused by having powered on with the motor already rotating, or caused by the identification routine itself.

Remedy
if P1075=1
- If the interchange was caused by the identification itself and if the error occurs again, then reduce P1019 or increase P1020.
- Lock the motor rotor during the identification routine.
if P1075=3
- Increase the parameterized load mass (P1076)
- Check the maximum permissible motion (P1020) and if required, increase
- Reduce the current, rotor position identification (P1019)

If the current and speed controller clock cycle have low values (62.5 microseconds), then it maybe necessary to increase P1019.

Acknowledgement
RESET FAULT MEMORY
Stop response parameterizable

612 Illegal current during rotor position identification

Cause
1. Current was \( \geq 1.2 \times 1.05 \times \ P1107 \) while rotor position identification was active
2. Current was \( \geq \ P1104 \) while rotor position identification was active

Remedy
With the rotor position identification (P1011.12 and P1011.13) activated, if required, check and reduce P1019 (current, rotor position identification)

Acknowledgement
RESET FAULT MEMORY
Stop response parameterizable

613 Shutdown limit, motor overtemperature exceeded.

Supplementary information \( \%X \)

Cause
.. is specified in the additional information:
1. The motor temperature is sensed using a KTY temperature sensor.
   a) The motor temperature has exceeded the temperature limit in P1607.
   b) The sensor or the cable is interrupted or has a short-circuit.
2. The motor temperature is sensed using a PTC temperature sensor.
   b) The sensor or the cable has a short-circuit.
3. The thermal motor model has tripped because the permitted thermal motor utilization in P1266 was exceeded.

Remedy
- Avoid many acceleration and braking operations which follow one another quickly.
- Motor overload?
- Check whether the motor output is sufficient for the drive, otherwise use a more powerful motor, possibly together with a higher-rating power section.
- Check the motor data. The current could be too high due to incorrect motor data.
- Temperature sensor monitoring.
- Check whether the sensor type (KTY or PTC) is correctly set in P1609.
- If the alarm occurs with the motor in the cold condition check whether the sensor is short-circuited or the cable is interrupted.
- Check the motor fan.
- Check the motor encoder cable.
- Motor encoder defective?
- Check and possibly reduce P1230 or P1235.
The motor temperature monitoring can be disabled with P1601 bit 13 = 1.

For linear motors:
- Check the parameters for the motor temperature monitoring
  P1602 (alarm threshold, motor overtemperature) = 120 degrees C
  P1603 (timer, motor temperature alarm) = 240 s
  P1607 (shutdown limit, motor temperature) = 155 degrees C
  P1608 (fixed temperature) = 0 degrees C
  P1608 = 0 --> Temperature sensing active
  P1608 > 0 --> Fixed temperature active
- If the temperature monitoring is exclusively realized using an external PLC, a fixed temperature must be entered into P1608 (e. g. 80 degrees C). This disables the drive temperature monitoring.
- Check the parameters for the thermal motor model
  P1265 (thermal motor model configuration)
  P1268 (winding time constant)
  P1288 (shutdown threshold, thermal motor model)
- Check the power connector at the motor
- Check the connection of the temperature sensor coupling cable at the end of the power cable, approx. 580 Ohm (KTY) or 100 Ohm (PTC) must be able to be measured at 20 Degrees C
- If the measuring system connector is withdrawn (X411 for 611U or MOT ENCODR for POSMO) is approx. 580 Ohm (KTY) or 100 Ohm (PTC) measured between PIN 13 (611U) or 20 (POSMO) and PIN 25 (611U) or 21 (POSMO) at 20 Degree C?
- Check the measuring system connector at the drive (X411 or MOT ENCODR) to ensure that it is correctly inserted
- For drives connected in parallel, both KTY temperature sensors may not be directly connected. In this case an appropriate evaluation unit, e.g. SME-92 or SME-94 should be used for 2 drives.
- If the temperature switch and temperature sensor are connected in series, the temperature sensor (NC contact) may have responded, or the temperature switch is defective

Acknowledgement
RESET FAULT MEMORY

Stop response parameterizable

614 Delayed shutdown for motor overtemp. (P1602 / P1603). Supplementary info. \%X

Cause
.. is specified in the additional information:
1 The motor temperature is sensed using a KTY temperature sensor.
   a) The motor temperature has exceeded the temperature limit, motor overtemperature P1602 for a longer period of time than that permitted in P1603.
   b) The sensor or the cable is interrupted or has a short-circuit.
2 The motor temperature is sensed using a PTC temperature sensor.
7.3 List of faults and alarms

- Avoid many acceleration and braking operations which follow one another quickly.
- Motor overload?
- Check whether the motor output is sufficient for the drive, otherwise use a more powerful motor, possibly together with a higher-rating power section.
- Check the motor data. The current could be too high due to incorrect motor data.
- Check the thermal motor utilization alarm threshold P1269.
- Temperature sensor monitoring.
- Check whether the sensor type (KTY or PTC) is correctly set in P1609.
- If the alarm occurs with the motor in the cold condition check whether the sensor is short-circuited or the cable is interrupted.
- Check the motor fan.
- Check the motor encoder cable.
- Motor encoder defective?
- Check and possibly reduce P1230 or P1235.

The motor temperature monitoring can be disabled with P1601 bit 14 = 1.

For linear motors:
- Check the parameters for the motor temperature monitoring
  P1602 (alarm threshold, motor overtemperature) = 120 degrees C
  P1603 (timer, motor temperature alarm) = 240 s
  P1607 (shutdown limit, motor temperature) = 155 degrees C
  P1608 (fixed temperature) = 0 degrees C
  P1608 = 0 temperature sensing active
  P1608 > 0 fixed temperature active
- If the temperature monitoring is exclusively realized using an external PLC, a fixed temperature must be entered into P1608 (e.g. 80 degrees C). This disables the drive temperature monitoring.
- Check the parameters for the thermal motor model
  P1265 (thermal motor model configuration)
  P1268 (winding time constant)
  P1288 (shutdown threshold, thermal motor model)
- Check the power connector at the motor
- Check the connection of the temperature sensor coupling cable at the end of the power cable, approx. 580 Ohm (KTY) or 100 Ohm (PTC) must be able to be measured at 20 Degrees C
- If the measuring system connector is withdrawn (X411 for 611U or MOT ENCODR for POSMO) is approx. 580 Ohm (KTY) or 100 Ohm (PTC) measured between PIN 13 (611U) or 20 (POSMO) and PIN 25 (611U) or 21 (POSMO) at 20 Degree C?
- Check the measuring system connector at the drive (X411 or MOT ENCODR) to ensure that it is correctly inserted.
- For drives connected in parallel, both KTY temperature sensors may not be directly connected. In this case an appropriate evaluation unit, e.g. SME-92 or SME-94 should be used for 2 drives.
- If the temperature switch and temperature sensor are connected in series, the temperature sensor (NC contact) may have responded, or the temperature switch is defective

Acknowledgement: RESET FAULT MEMORY
Stop response: parameterizable

615 **DM encoder limiting frequency exceeded**

**Cause**
The speed actual value of the direct measuring system exceeds the permissible encoder limiting frequency.
- Incorrect encoder
- P1007 does not coincide with the encoder pulse number
- Encoder defective
- Defective encoder cable or not correctly retained
- Encoder cable shield is not connected
- Defective control module

**Remedy**
- Enter correct encoder data / replace encoder
- Check encoder pulse number (P1007)
- Correctly retain encoder cable / replace
- Connect encoder cable shield
- Reduce speed setpoint input
- Replace control module

Acknowledgement: RESET FAULT MEMORY
Stop response: parameterizable

616 **DC link undervoltage**

**Cause**
The infeed has gone into a fault condition and the DC link voltage has fallen below the permissible lower limit P1162.

**Remedy**
- Check whether the line supply voltage is available
- Check whether the pulsed resistor is overloaded
- Switch-off/switch-on infeed

Acknowledgement: RESET FAULT MEMORY
Stop response: parameterizable

617 **DC link overvoltage**

**Cause**
The DC link voltage has exceeded the permissible upper limit P1163. Dynamic energy management has been activated using P1155, bit 0 and the DC link voltage has exceeded the "Maximum DC link voltage dyn. energy management" P1153 (from SW 13.1).

**Remedy**
- Check whether the line supply voltage is available
- Reduce load duty cycle
- Check P1163
- If P1155 bit 0 is activated, increase P1153 or deactivate P1155 bit 0 (from SW 13.1)

Acknowledgement: RESET FAULT MEMORY
Stop response: parameterizable
7.3 List of faults and alarms

680 **Illegal motor code number**

Cause A motor code was entered in P1102 for which no data is available.

Remedy - Commission the system again and enter the correct motor code number (P1102).
- The "SimoCom U" parameterizing and start-up tool includes motors that are still not known in this particular drive version. Either upgrade the drive version or enter the motor as non-listed motor.

Acknowledgement POWER ON

Stop response STOP II (SRM, SLM) STOP I (ARM)

681 **Illegal power section code number**

Cause A power section code was entered in P1106, for which no data is available.

Remedy - Enter the correct power unit code in P1106.
- For power modules with automatic identification, upgrade firmware.

Acknowledgement POWER ON

Stop response STOP II (SRM, SLM) STOP I (ARM)

682 **Illegal encoder code number in P\%u**

Cause An encoder code was entered in P1006 or P1036, for which there is no data.
The direct measuring system (P0250/P0879.12) is activated, although an encoder was not specified in P1036.

Remedy Enter the correct encoder code or the code for third-party encoders (99) in P1006 or P1036.
De-activate direct measuring system (P0250/P0879.12).

Acknowledgement POWER ON

Stop response STOP II (SRM, SLM) STOP I (ARM)
683 Calculate controller data was unsuccessful at first start-up (%d)

Cause
An error occurred at the first start-up with “calculate controller data”. Under fault conditions, the parameters for the current controller, flux controller and speed controller could not be optimally assigned.

Remedy
Read-out the detailed cause of the error from P1080 and remove the cause.
Then initiate “calculate controller data” again with P1080 = 1. Repeat this operation, until no error is displayed in P1080. Then save in the FEPROM and execute a POWER ON-RESET.

Error coding in the supplementary info and P1080:
-15 magnetizing reactance (P1141) = 0
-16 leakage reactance (P1139 / P1140) = 0
-17 rated motor frequency (P1134) = 0
-18 rotor resistance (P1138) = 0
-19 motor moment of inertia (P1117) = 0
-21 threshold speed for field weakening (P1142) = 0
-22 motor standstill current (P1118) = 0
-23 The ratio between the maximum motor current (P1104) and the motor stall current (P1118) is greater than the maximum value for the torque limit (P1230) and the power limit (P1235).
-24 The ratio between the rated motor frequency (P1134) and the rated motor speed (P1400) is inadmissible (pole pair number).

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

703 Invalid current controller cycle

Cause
An illegal value was entered in P1000.

Remedy
Enter a valid value in P1000.
Permissible values for P1000 are:
2 (62.5 μs) for single-axis positioning or for speed setpoint input
4 (125 μs) in each operating mode

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

704 Invalid speed controller cycle

Cause
An illegal value was entered into P1001.

Remedy
Enter a valid value in P1001.
Permissible values for P1001 are 2 (62.5 μs), 4 (125 μs), 8 (250 μs), 16 (500 μs).
Setting 2 (62.5 μs) is only permissible for single-axis operation.
Further, P1001 must be >= P1000.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)
705 **Invalid position controller cycle**

Cause The monitoring function identified a position controller cycle (P1009) outside the permissible limits.

Remedy Enter a valid value in P1009. Permissible values for P1009 lie between 32 (1 ms) and 128 (4 ms). Further, the position control cycle must be an integral multiple of the speed control cycle.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

706 **Invalid interpolation cycle**

Cause The monitoring function has identified an interpolation clock cycle (P1010) that is outside the permissible limits or an illegal ratio between the interpolation clock cycle and the position controller clock cycle (P1009).

Remedy Enter a valid value in P1010 or correct P1009. Permissible values for P1010 lie between 128 (4 ms) and 640 (20 ms) or, only for the 1-axis version, also 64 (2 ms) if P1009 is also 64 (2 ms). Further, the interpolation cycle must be an integral multiple of the position controller cycle.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

708 **Axial deviations in current controller cycle**

Cause On a 2-axis module, the current controller cycle is different for both axes.

Remedy Check P1000 and set the input values the same for both drives.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

709 **Axial deviations in speed controller cycle**

Cause On a 2-axis module, the speed controller cycle is different for both axes.

Remedy Check P1001 and set the input values the same for both drives.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

710 **Axial deviations in position controller or interpolation cycle**

Cause For a 2-axis module, the position controller clock cycle (P1009) or the interpolation clock cycle (P1010) is different for the two axes.

Remedy Check P1009 / P1010 and set the input values for both drives the same.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)
716 **Invalid torque constant**

**Cause**
The ratio between the rated torque and rated current (torque constant \([\text{Nm/A}]\)) in P1113 is incorrect (less than/equal to zero) or the ratio \(P1113 / P1112\) is greater than 70.

**Remedy**
Enter the valid torque/current ratio for the motor used in P1113 or enter a permissible ratio of \(P1113 / P1112\).
- Third-party motor:
The torque constant should be determined from the motor data sheet.
- Siemens motor:
The torque constant is defined by the motor code (P1102).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

718 **BERO shutdown threshold exceeded**

**Cause**
BERO speed actual value is greater than the shutdown threshold specified in P1468 (the motor is prevented from accelerating in an uncontrolled fashion) or for a calculated speed > 1200 rpm, BERO pulses are no longer received (e.g. the cable is interrupted)

**Remedy**
Check the parameterization of the induction motor
Check BERO or BERO cable, BERO pulse length

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

719 **Motor not parameterized for delta operation**

**Cause**
When the star-delta changeover is activated using P1013, the motor is not parameterized for delta operation (motor 2).

**Remedy**
Check and enter the parameters for delta operation (motor 2).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

720 **Invalid maximum motor speed**

**Cause**
Due to the high maximum motor speed in P1401 and the speed controller cycle in P1001, high partial speeds can occur which can result in a format overflow.

**Remedy**
Check P1401 and P1001 and correct.
The drive software is designed for large reserve margins, so that the displayed alarm can only occur as a result of a parameterizing error.

- Example:
  For a speed controller cycle time of 125 \(\mu\)s, a motor speed of 480 000 RPM can still be processed correctly!

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

721 **Spindle speed too high**

**Cause**
As a result of the high spindle speed and the interpolation clock cycle (P1010), the modulo value can no longer be correctly taken into account. The alarm is initiated, if jerky equalization motion occurs - e.g. due to incorrect parameter values.

**Remedy**
Shorten the interpolation clock cycle.
If possible, increase the modulo range of the rotary axis (P0242).
Calculating the spindle speed limit \[\text{[RPM]} = 7 / \text{IPO clock cycle[ms]} \times 60 \times 1000\] (for the modulo range, 360 degrees = 1 spindle revolution)
Example:
IPO clock cycle = 4 ms, for max. 7 revolutions (up to 7 x modulo range) - a maximum spindle speed of 105000 RPM is obtained per IPO clock cycle.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

722 **Changeover speed/velocity too low**

**Cause**
For the selected setting of P1466, the induced voltage is too low in the lower speed range in order to be able to reliably guarantee sensorless operation. The induced voltage must be at least 40 Volt (phase-to-phase, RMS) at the particular speed.

**Remedy**
The following should be ensured:
Induction motor : P1466 >= 150 RPM
Rotary synchronous motor: P1466 > 40000 / P1114
Linear motor: P1466 > 1386 / P1114

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

723 **Axial deviations in STS configuration**

**Cause**
On a 2-axis module, the gating unit configuration (P1003) is different for the two gating units.

**Remedy**
Check P1003 and set the bits for the two module axes the same (do not change the standard setting, this represents the optimum configuration).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

724 Invalid motor pole pair number

Cause
- Synchronous motors:
  - The pole pair number in P1112 is zero or negative.
  - Encoder with CD track (P1027.6 = 0): The pole pair number in P1112 is greater than 6.
  - Encoder without CD track or with Hall sensors (P1027.6 = 1): The motor pole pair number is dependent on the encoder pulse number (max. 4096 for P1005 >= 32768).
- Induction motors:
  - An invalid pole pair number was determined from P1134 and P1400.
  - Motor with resolver:
    - The maximum motor pole pair number for the modules 6SN1118-*NK01-0AA0 or 6SN1118-*NJ01-0AA0 is 64, otherwise 4 or 6.

Remedy
- Synchronous motors:
  - Check P1112, P1027.6 and P1014.
- Induction motors:
  - Determine and correctly enter rated speed and/or rated frequency.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

725 Invalid encoder pulse number

Cause
The encoder pulse number of the motor measuring system (P1005) is set to zero.

Remedy
Harmonize the encoder pulse number of the motor measuring system in P1005 to the encoder used. The indirect motor measuring system must always be configured for synchronous and induction motors (exception: Induction motor operation).

Standard setting: 2 048 increments/revolution

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

726 Invalid voltage constant

Cause
The voltage constant of the motor in P1114 is set to zero.

Remedy
Determine the voltage constant of the motor used, and enter in P1114. The voltage constant is measured as induced voltage (EMF) under no-load conditions at n = 1 000 RPM as RMS valued at the motor terminals (phase to phase).

Third-party motor:
- The voltage constant should be determined from a motor data sheet.
- Siemens motor:
  - The voltage constant is determined from the motor code (P1102).

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)
727 Invalid combination of power section and synchronous motor

**Cause**
The power module has not been released for synchronous motors.

**Remedy**
- Check configuring
- Use a valid power section

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

728 Torque/current adaptation factor too high

**Cause**
The adaptation factor between the setpoint torque and the torque generating current (Iq) in the speed controller is too high.

**Remedy**
Check P1103, P1107 and P1113 and if required, enter correct values.
Third-party motor:
The values should be determined from a motor data sheet.
Siemens motor:
The values are determined from the motor code (P1102).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

729 Invalid motor stall current

**Cause**
The motor stall current (P1118) is less than or equal to zero.

**Remedy**
Determine the stall current of the motor used and enter in P1118.
Third-party motor:
The stall current should be determined from a motor data sheet.
Siemens motor:
The stall current is determined from the motor code (P1102).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

731 Invalid rated output

**Cause**
The rated motor output (P1130) of the motor is less than or equal to zero.

**Remedy**
Determine the rated motor output of the motor used and enter in P1130.
Third-party motor:
The rated motor output should be determined from a motor data sheet.
Siemens motor:
The rated motor output is determined from the motor code (P1102).

**Acknowledgement**
POWER ON

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
732 Invalid rated speed
Cause The rated motor speed (P1400) of the motor is less than or equal to zero.
Remedy Determine the rated speed of the motor being used and enter into P1400.
Third-party motor:
The rated motor speed should be determined from a motor data sheet.
Siemens motor:
The rated motor speed is determined from the motor code (P1102).
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

738 Incorrect mode, analog input for the equalization controller
Cause If the equalization controller is parameterized with P1490 = 1 --> then P0612 must be parameterized with the value 3
Remedy - P0612=3 or
- P1490 not equal to 1
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

739 Incorrect axis number, equalization controller
Cause If the equalization controller is parameterized with P1490 = 2 --> two active axes must be available on the module.
Remedy - P1490 equal to 1 (coupling via analog terminals) or
- Activate the 2nd axis or
- Use a 2-axis module
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

742 V/f operation: Drive frequency, motor \%d not permissible
Cause In V/f operation, only drive converter frequencies of 4 or 8 kHz are permissible.
Remedy Change P1100 or cancel V/f operation (P1014).
When operating with several motors/motor data sets, also set P2100/P3100/P4100 to 4 or 8 kHz.
Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)
**743**  
**Function is not possible using this control board**  
**Cause**  
"  
**Remedy**  
"  
**Acknowledgement**  
POWER ON  
**Stop response**  
STOP II (SRM, SLM) STOP I (ARM)

**744**  
**Motor changeover only permissible for the closed-loop speed controlled mode**  
**Cause**  
Motor changeover (P1013) may only be activated in the closed-loop speed controlled mode (P0700 = 1).  
**Remedy**  
- Inhibit motor changeover (P1013 = 0)  
- Change over into the closed-loop speed controlled mode (P0700 = 1)  
**Acknowledgement**  
POWER ON  
**Stop response**  
STOP I

**745**  
**New EnDat encoder**  
**Cause**  
For a direct measuring system with EnDat it was identified that the serial number does not correspond with that saved – i.e. the serial number of the encoder has still not been saved.  
**Remedy**  
Save parameters, then power on  
**Acknowledgement**  
POWER ON  
**Stop response**  
parameterizable

**749**  
**Speed measuring range is not sufficient**  
**Cause**  
The maximum speed which can be achieved with speed feedback cannot be measured using the module.  
**Remedy**  
- Parameterize the encoder type corresponding to the type of motor and the control module.  
- Synchronous motor: P1147 * resolver pole pair number must be less than the limiting frequency of the control module (12 bit: 25402 RPM; 14 bit: 6350 RPM).  
- Induction motor: min ( P1146, P1465 ) * resolver pole pair number must be less than the limiting frequency of the control module (12 bit: 25402 RPM; 14 bit: 6350 RPM).  
**Acknowledgement**  
POWER ON  
**Stop response**  
STOP II (SRM, SLM) STOP I (ARM)
750 Speed monitoring BERO incorrectly configured

Cause
- for the BERO speed monitoring function, parameter P0890 "Activate angular encoder/encoder interface" must be set to 4 (input for TTL encoder),
- Parameter P0894 "Angular encoder input signal form" must be set to 1 (pulse/direction signal),
- Parameter P1465 "changeover speed MS/DM" set to 0,
- Parameter P1006 "IM encoder code number" or P1036 "DM encoder code number" must be set to 98 (without encoder).

Remedy
Adapt the angular encoder interface, change over to operation without encoder, correct the changeover speed.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

751 Speed controller gain too high

Cause
P gain, speed controller for the lower speed range (P1407) and the upper speed range (P1408) were selected to be too high.
In AM (induction motor) operation:
The P gain of the speed controller (P1451) is too high.

Remedy
Reduce the P gain of the speed controller.
Only optimized with the adaption disabled (P1413 = 0). The P gain (P1407) is then effective over the complete speed range. After the optimum setting has been found, adaption can be re-enabled (P1413 = 1) and the P gain optimized for the upper speed range (P1408).
In AM (induction motor) operation:
For the speed controller, enter a lower value for the P gain (P1451).

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II (SRM, SLM) STOP I (ARM)

753 Current, rotor position identification less than the min. value

Cause
A current was parameterized in P1019 (current, rotor position identification) which is less than the minimum value permissible for the motor.

Remedy
Enter a current in P1019, which is not less than the permissible minimum value for the motor (40% for third-party synchronous linear motor). It may be necessary to use a larger power module.
If permissible for the motor used, suppress the fault by setting P1012, bit 5.
Caution:
For motors with weak saturation effects (e.g. 1FN3 linear motors), as a result of the low identification current, orientation may be erroneous, thus resulting in uncontrolled motion.

Acknowledgement
RESET FAULT MEMORY

Stop response
STOP II (SRM, SLM) STOP I (ARM)
756  **Invalid speed hysteresis of the current setpoint smoothing**

**Cause**  
The hysteresis of the speed for the current setpoint smoothing (P1246) may not be greater than the threshold speed of the hysteresis (P1245), as otherwise a "negative" lower speed would be obtained.

**Remedy**  
P1246 (standard value: 50 [RPM]) must be entered lower than the threshold for the speeddependent setpoint smoothing (P1245, standard value: 4 000 [RPM]).

**Acknowledgement**  
RESET FAULT MEMORY

**Stop response**  
STOP II (SRM, SLM) STOP I (ARM)

757  **PZD config.: illegal frame no. in P0922**

**Cause**  
The frame number set in P0922 is illegal or impermissible for the operating mode currently selected via P0700.

**Remedy**  
Check P0922 and enter valid value.

**Acknowledgement**  
POWER ON

**Stop response**  
STOP II

758  **Setpoint source incorrectly parameterized. Supplementary info \%u**

**Cause**  
The selected setpoint source in P0891 is invalid.  
1 Internal coupling not possible for POSMO or single-axis module  
2 Internal coupling not possible for drive A  
3 Coupling via PROFIBUS-DP or the bus interface selected, but the matching option module is not inserted

**Remedy**  
Check P891 and enter a valid value.

**Acknowledgement**  
POWER ON

**Stop response**  
STOP II
7.3 List of faults and alarms

759 Encoder/motor types do not match

Cause
A linear motor was selected, and no linear scale configured (P1027.4 = 0).
A rotating motor was selected and a linear scale configured (P1027.4 = 1).
A resolver has been selected the pole pair number (P1018) of which is illegal. A pole pair number =1 or the pole pair number of the motor (P1112) is admissible.
The maximum speed (P1146) cannot be measured with the resolver.
The required resolution (1011[2]=1 or 1030[2]=1, resolver evaluation) cannot be set with this module.
For this setting, either 6SN1118-*NK01-0AA0 or 6SN1118-*NJ01-0AA0 is required.

Remedy
- Parameterize the encoder type corresponding to the type of motor and the control module.
- Use the required (6SN1118-*NK01-0AA0 or 6SN1118-*NJ01-0AA0) control module.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

760 Pole pair width/scale graduations cannot be represented internally

Cause
For linear motors, the equivalent (internal) pole pair number and (internal) encoder pulse number are calculated from the pole pair width and grid division. In this case, the encoder pulse number must be an integer multiple of one or x pole pair widths. This error message is output if the pole pair width/grid division * x (up to x=4096) is not an integer multiple or if an internal encoder pulse number which was calculated is too high.
A result with a tolerance of +/- 0.001 absolute is interpreted to be an integer.

Remedy
Long travel paths:
A linear measuring system with an encoder mark number that is an integral divisor of x* pole pair widths should be used.
Short travel paths:
For short travel, only a low error can accumulate which has hardly any effect on the maximum achievable force and on the temperature rise, if the encoder pulse number fits with a deviation of more than +/-0.001 in the pole pair width. We then recommend that the pole pair width is slightly changed.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)
761 P0892 cannot be used with this measuring system

Cause
The following settings are permitted (Order No.[MLFB] 6SN1118-.....):
Incremental measuring systems (7 bit) with sin/cos 1 Vpp without EnDat interface (.NH00-0AA*, ..NH10-0AA*) : 0
Incremental measuring systems (7 bits) with sin/cos 1 Vpp with EnDat interface (.NH00-0AA*, ..NH10-0AA*) : 0,1,2,3
Incremental measuring systems (11 bit) with sin/cos 1 Vpp (.NH01-0AA*, ..NH11-0AA*) : 0,1,2,3,4
Resolver (12 bit) (.NK00-0AA0 or ..NJ00-0AA0) : 0,1,2,3
Resolver (12 bit) (.NK01-0AA0 or ..NJ01-0AA0) with 12-bit resolution (1011[2]=0 or 1030[2]=0) : 0,1,2,3,4,5
Resolver (14 bit) (.NK01-0AA0 or ..NJ01-0AA0) with 14 bit resolution (1011[2]=1 or 1030[2]=1) : -2,-1,0,1,2,3

Remedy
Set P0892 (factor, angular encoder pulse number/encoder pulse number) to a valid value.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

762 P0893 cannot be used with this measuring system

Cause
For incremental measuring systems with sin/cos 1 Vpp without EnDat interface and for linear measuring systems with sin/cos 1 Vpp with EnDat interface, a zero pulse offset cannot be set via P0893.

Remedy
Set P0893 (angular encoder zero pulse offset) to 0.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

764 Multiple assignment of terminal A or B (P0890)

Cause
When selecting 3 in P0890, from drive A or B (setpoint at terminal A and actual value at terminal B), it was identified, that terminal A or B were already being used by another drive. Thus, this configuration is not possible.

Remedy
Check the configuration of terminals A and B in P0890 and eliminate multiple assignments of both drives.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)

765 P0890 and P0891 configure both setpoint inputs

Cause
An actual value coupling is switched-in for drive B (P0891 = 1). At the same time, for the same drive, terminal A or B was parameterized as position setpoint input (P0890 = 2 or 3).

Remedy
Check the configuration of terminals A and B in P0890, compare with P0891 and eliminate multiple setpoint sources.

Acknowledgement
POWER ON

Stop response
STOP II (SRM, SLM) STOP I (ARM)
766  **Blocking frequency > Shannon frequency**

**Cause**
The bandstop frequency of a speed setpoint filter is greater than the Shannon sampling frequency from the sampling theorem.

**Remedy**
The bandstop frequency for P1514, filter 1 or P1517 for filter 2 must be less than the inverse value of two speed controller clock cycles 1 / (2 * P1001 * 31.25 microseconds).

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

767  **Natural frequency > Shannon frequency**

**Cause**
The natural frequency of a speed setpoint filter is greater than the Shannon sampling frequency from the sampling theorem.

**Remedy**
The natural frequency of a speed setpoint filter must be lower than the reciprocal of two speed controller cycles.
- Speed setpoint filter 1:
  \[ P1520 \times 0.01 \times P1514 < \frac{1}{2 \times P1001 \times 31.25 \text{ microseconds}} \]
- Speed setpoint filter 2:
  \[ P1521 \times 0.01 \times P1517 < \frac{1}{2 \times P1001 \times 31.25 \text{ microseconds}} \]

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

768  **Numerator bandwidth > twice the blocking frequency**

**Cause**
The numerator bandwidth of a current or speed setpoint filter is greater than twice the blocking frequency. This alarm is only generated for the general bandstop, if the following is valid:
- Speed setpoint filter 1: P1516 > 2 * P1514 or P1520 <> 100.0
- Speed setpoint filter 2: P1519 > 0.0 or P1521 <> 100.0
- Current setpoint filter 1: P1212 > 0.0
- Current setpoint filter 2: P1215 > 0.0
- Current setpoint filter 3: P1218 > 0.0
- Current setpoint filter 4: P1221 > 0.0

**Remedy**
The numerator bandwidth must be less than twice the bandstop frequency.
- Current setpoint filter 1: P1212 <= 2 * P1210
- Current setpoint filter 2: P1215 <= 2 * P1213
- Current setpoint filter 3: P1218 <= 2 * P1216
- Current setpoint filter 4: P1221 <= 2 * P1219
- Speed setpoint filter 1: P1516 <= 2 * P1514
- Speed setpoint filter 2: P1519 <= 2 * P1517

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
769 **Denominator bandwidth > twice the natural frequency**

**Cause**
The denominator bandwidth of a current or speed setpoint filter is greater than twice the natural frequency. This alarm is only generated for the general bandstop, if the following is valid:
- Speed setpoint filter 1: \( P1516 > 2 \times P1514 \) or \( P1520 \neq 100.0 \)
- Speed setpoint filter 2: \( P1519 > 0.0 \) or \( P1521 \neq 100.0 \)
- Current setpoint filter 1: \( P1212 > 0.0 \)
- Current setpoint filter 2: \( P1215 > 0.0 \)
- Current setpoint filter 3: \( P1218 > 0.0 \)
- Current setpoint filter 4: \( P1221 > 0.0 \)

**Remedy**
The denominator bandwidth of a current or speed setpoint filter must be less than twice the natural frequency.
- Speed setpoint filter 1: \( P1515 \leq 2 \times P1514 \times 0.01 \times P1520 \)
- Speed setpoint filter 2: \( P1518 \leq 2 \times P1517 \times 0.01 \times P1521 \)
- Current setpoint filter 1: \( P1211 \leq 2 \times P1210 \)
- Current setpoint filter 2: \( P1214 \leq 2 \times P1213 \)
- Current setpoint filter 3: \( P1217 \leq 2 \times P1216 \)
- Current setpoint filter 4: \( P1220 \leq 2 \times P1219 \)

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

770 **Format error**

**Cause**
The calculated bandstop filter coefficients cannot be represented in the internal format.

**Remedy**
Change filter setting.

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

771 **Induction motor oper.: drive converter frequency motor \( \%d \) not permissible**

**Cause**
In induction motor operation (selected by \( P1465 < P1146 \)), drive converter frequencies of 4 or 8 kHz are permissible.

**Remedy**
- Change \( P1100 \)
- Cancel induction motor operation (\( P1465 > P1146 \))

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

772 **Induction motor oper.: speed controller gain, motor \( \%d \) too high**

**Cause**
The P gain of the speed controller (\( P1451 \)) is too high.

**Remedy**
For the speed controller, enter a lower value for the P gain (\( P1451 \)).

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

773  Not permissible to active analog input

Cause  For this particular hardware version, it is not permissible to activate the analog input.

Remedy  - Set P0607 to 0 and P0612 to 0 or
        - Use the "SIMODRIVE 611 universal" control module.

Acknowledgement  POWER ON

Stop response  STOP II (SRM, SLM) STOP I (ARM)

774  Induction motor oper.: changeover speed motor \%d not permissible

Cause  For mixed operation (with / without encoder) P1465 > 0, only closed-loop controlled induction motor operation is permissible (P1466 <= P1465).

Remedy  Eliminate error by selecting pure induction motor operation (P1465 = 0) or by canceling induction motor open-loop controlled operation (P1465 > P1466).

Acknowledgement  RESET FAULT MEMORY

Stop response  STOP II (SRM, SLM) STOP I (ARM)

775  SSI encoder incorrectly parameterized. Supplementary info \%u

Cause  Incorrect parameterization of the SSI absolute value encoder.
        Supplementary info = 0x1, 0x11 (indirect, direct measuring system):
        --> The single-turn resolution cannot be 0.
        Supplementary info = 0x2, 0x12 (indirect, direct measuring system):
        --> The number of parameterized bits is greater than the telegram length.
        Supplementary info = 0x3, 0x13 (indirect, direct measuring system):
        --> For linear encoders, it is not possible to have multi-turn resolution.

Remedy  For supplementary info 1 or 11:
        Check P1022 and P1032
        For supplementary info 2 or 12:
        Check P1021, P1022, P1027.12 and P1027.14 with respect to P1028 and check P1031, P1032, P1037.12 and P1037.14 with respect to P1041
        For supplementary info 3 or 13:
        Check P1021 and P1031

Acknowledgement  POWER ON

Stop response  STOP I
776 TTL encoder not possible for older basic module

Cause For an old basic module, which does not support TTL encoders, a TTL encoder was selected as motor measuring system.

Remedy Use a new basic module or incremental measuring system with sin/cos 1 Vpp.

Acknowledgement POWER ON
Stop response STOP I

777 Current for the rotor position identification too high

Cause A current was parameterized in P1019, which is greater than the current which is permissible for the motor and the power section used.

Remedy Reduce the current via P1019.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

778 Impermissible converter frequency for rotor position ID

Cause When selecting the rotor position identification (P1019), drive converter frequencies (P1100) of 4 or 8 kHz are permissible.

Remedy Change the drive converter frequency or cancel the rotor position identification.

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

779 Motor moment of inertia, motor \%d invalid

Cause The motor moment of inertia (P1117) is incorrect (less than/equal to zero).

Remedy Enter the valid motor moment of inertia for the motor used, in P1117. Third-party motor:
The motor moment of inertia should be determined from a motor data sheet.
Siemens motor:
The characteristic motor data should be determined from the motor code (P1192).

Acknowledgement RESET FAULT MEMORY
Stop response STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

780 No-load current, motor \( \%d \) > rated motor current

Cause The motor no-load current (P1136) has been parameterized greater than the rated motor current (P1103).

Remedy Enter the valid currents for the motor used in P1136 and P1103.
Third-party motor:
The required currents should be determined using a motor data sheet.
Siemens motor:
The currents are determined using the motor code (P1102).

Acknowledgement RESET FAULT MEMORY
Stop response STOP II (SRM, SLM) STOP I (ARM)

781 No-load current, motor \( \%d \) > rated power section current

Cause The motor no-load current (P1136) has been set to higher values than the rated power section current.
before SW 2.4 the following is valid: Rated power section current = P1111
from SW 2.4 the following is valid: Rated power section current = P1111 * P1099

Remedy - Enter the valid current for the motor used in P1136.
Third-party motor:
The required currents should be determined using a motor data sheet.
Siemens motor:
The currents are determined using the motor code (P1102).
- Reduce the power section pulse frequency P1100.
- Use a higher-rating power section (re-commission).

Acknowledgement RESET FAULT MEMORY
Stop response STOP II (SRM, SLM) STOP I (ARM)

782 Reactance motor \( \%d \) invalid

Cause The stator leakage reactance (P1139), the rotor leakage reactance (P1140) or the magnetizing reactance (P1141) of the motor is incorrect (less than/equal to zero).

Remedy Determine the stator, rotor leakage reactance and magnetizing reactance of the motor being used and enter into P1139, P1140 and P1141.
Third-party motor:
The values should be determined from a motor data sheet.
Siemens motor:
The values are determined from the motor code (P1102).

Acknowledgement RESET FAULT MEMORY
Stop response STOP II (SRM, SLM) STOP I (ARM)
### 783 Rotor resistance, motor \%d invalid

**Cause**
The rotor resistance (P1138, cold) of the motor is zero or there was a format overflow for an internal conversion.

**Remedy**
The following parameters can have incorrect values:
- P1001 (speed controller cycle)
- P1134 (rated motor frequency)
- P1138 (rotor resistance)
- P1139 (leakage stator reactance)
- P1140 (leakage rotor reactance)
- P1141 (magnetizing field reactance)

Check the parameter, and if required, correct using the motor data sheet.

The following condition must be fulfilled:
\[
16 \times P1001 \times 0.00003125 \times P1138 \times 2\pi \times P1134 / (P1140 + P1141) < 1
\]

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)

### 784 No-load voltage, motor \%d invalid

**Cause**
Error in no-load voltage P1135:
- P1135 <= 0 or
- P1135 > P1132 or
- P1135 * P1142 / P1400 + Vser.react. > 450V.

With Vser.react. = 0.181 * P1136 * P1142 * P1119

**Remedy**
Determine the no-load voltage of the motor being used and enter into P1135.

Third-party motor:
The following parameters may have incorrect values:
- P1119 (inductance of the series reactor)
- P1132 (rated motor voltage)
- P1135 (no-load motor voltage)
- P1400 (rated motor speed)
- P1142 (threshold speed for field weakening)
- P1136 (no-load motor current)

Check parameters and if required correct using a motor data sheet.

Siemens motor:
The no-load voltage is determined from the motor code (P1102).

**Acknowledgement**
RESET FAULT MEMORY

**Stop response**
STOP II (SRM, SLM) STOP I (ARM)
785  No-load current, motor \%d invalid

Cause  The no-load current (P1136) of the motor (ARM) is incorrect (less than/equal to zero).

Remedy  Determine the no-load current of the motor (ARM) being used and enter into P1136.
Third-party motor:
The no-load current should be determined from a motor data sheet.
Siemens motor:
The no-load current is determined from the motor code (P1102).

Acknowledgement  RESET FAULT MEMORY
Stop response  STOP II (SRM, SLM) STOP I (ARM)

786  Field-weakening speed, motor \%d invalid

Cause  The threshold speed for field weakening for induction motors (P1142) is incorrect (less than/equal to zero).

Remedy  Determine the speed at which field weakening starts for the motor being used and enter into P1142.
Third-party motor:
The field weakening speed should be determined from a motor data sheet.
Siemens motor:
The field weakening speed is determined from the motor code (P1102).

Acknowledgement  RESET FAULT MEMORY
Stop response  STOP II (SRM, SLM) STOP I (ARM)

787  Induction motor oper.: feedforward control gain motor \%d cannot be displayed

Cause  The feedforward control gain for induction motors cannot be represented in the internal numerical format if the motor moment of inertia and rated motor torque were unfavorably selected.

Remedy  Operation without encoder:
Reduce the encoder pulse number (P1005), as this is used in the internal numerical format.
Operation with encoder:
Reduce the speed controller cycle (P1001).

Acknowledgement  RESET FAULT MEMORY
Stop response  STOP II (SRM, SLM) STOP I (ARM)

788  P0891 for drive B only

Cause  An actual-value link has been activated (P0891 = 1) for drive A. The hardware does not permit this setting.

Remedy  For drive A, set P0891 to the value 0.

Acknowledgement  POWER ON
Stop response  STOP II (SRM, SLM) STOP I (ARM)


789 Setpoint transfer SimoCom U ==> drive interrupted

Cause The setpoint transfer from SimoCom U to the drive was interrupted, i.e. there is no longer an online connection. The Master Control was returned to the drive. Communication between the two communication partners was faulty. While moving the drive using SimoCom U, other functions were carried out on the PG/PC (e.g. online help was opened, a file was opened) so that from SimoCom U the drive can only be irregularly supplied with data.

Remedy
- Check whether SimoCom U is still operating correctly, if required, restart
- Check whether the communication connection is OK, if required, replace the connecting cable
- When in the online mode, do not select any time-intensive functions

Acknowledgement POWER ON

Stop response STOP II (SRM, SLM) STOP I (ARM)

790 Illegal operating mode. Supplementary info: \%u

Cause The selected operating mode (P0700) is not permitted for this module or axis.

Supplementary info = 0x1:
Operating mode ==0 selected on the 1st axis
Supplementary info = 0x2:
"Positioing" operating mode selected for the Nset control module
Supplementary info = 0x3:
Operating mode is not possible with this firmware release
Supplementary info = 0x4:
"External position reference value" operating mode no longer possible.

Remedy
For supplementary info 1:
Select valid operating mode (P0700 > 0)
For supplementary info 2:
Select Nset operating mode or use a positioning module.
For supplementary info 3:
Use a firmware release which supports this operating mode.
For supplementary info 4:
Select "Positioning" operating mode.

Acknowledgement POWER ON

Stop response STOP I

791 TTL encoder interface incorrectly parameterized

Cause The TTL encoder interface may only be parameterized as follows for this particular hardware version:
Drive A: P0890 = 0 or 4, 0: Interface inactive, 4: TTL encoder input
Drive B: P0890 = 0

Remedy Set P0890 to permissible value.

Acknowledgement POWER ON

Stop response STOP II (SRM, SLM) STOP I (ARM)
7.3 List of faults and alarms

792 Direct measuring system incorrectly parameterized.
Supplementary info: \%u

Cause
It is not permitted to parameterize the direct measuring system.
Supplementary info = 0x1:
A direct measuring system cannot be used using this board.
Supplementary info = 0x2:
The direct measuring system cannot be simultaneously operated with drive B.
Supplementary info = 0x3:
The direct measuring system is active and drive A is set for encoder-less operation (P1027 bit 5 = 1).

Remedy
For supplementary info 1:
Use the required board.
For supplementary info 2:
- De-activate the direct measuring system for drive A (P0250/P0879.12 = 0)
or
- Switch drive B inactive (P0700 = 0)
For supplementary info 3:
- De-activate the direct measuring system for drive A (P0250/P0879.12 = 0)
or
- Commission the motor measuring system for drive A

Acknowledgement POWER ON
Stop response STOP I

793 Angular encoder signal waveform different for drive A and B

Cause
The input signal waveform for the angular encoder interface must be set the same for the drives.

Remedy
Check P0894 for both drives and set the same

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)

794 P0890 = 3 not permitted for drive B

Cause
This angular encoder interface setting is not permitted for drive B.

Remedy
Check P0890 for drive B and set to a permissible value

Acknowledgement POWER ON
Stop response STOP II (SRM, SLM) STOP I (ARM)
795  **Ang. encoder, pos. ref. value normalization factor too large. Suppl. info: \%u**

**Cause**
The position reference value normalization for the angular encoder interface is not permissible.

**Supplementary info**
= 1 --> Condition $P0401 \times P0895 < 8388608$
v= 2 --> Condition $P0402 \times P0896 < 8388608$

**Remedy**
Check parameterization via $P0401$, $P0402$, $P0895$ and $P0896$. It may be possible to achieve the conditions above by shortening the numerator $P0401 \times P0895$ with the denominator $P0402 \times P0896$.

**Acknowledgement** POWER ON

**Stop response** STOP II

---

797  **Error in center frequency measurement**

**Cause**
The speed was too high while measuring the center frequency (adjusting the current actual value sensing). The center frequency is automatically measured when ramping-up or when the pulses are inhibited.

**Remedy**
Check the encoder cable.
Power up the drive converter if the motor runs at a reduced speed.

**Acknowledgement** POWER ON

**Stop response** STOP I

---

798  **Measured value memory active**

**Cause**
The measured-value memory was active during power-up.

**Remedy**
Run up again.

**Acknowledgement** POWER ON

**Stop response** STOP I

---

799  **FEPROM backup and HW Reset required**

**Cause**
Parameters were re-calculated. Parameters must be saved and the module run up again after this new calculation.

**Remedy**
The newly calculated data should be saved in the FEPROM. The new parameters become effective the next time that the module runs up!

**Acknowledgement** POWER ON

**Stop response** STOP II (SRM, SLM) STOP I (ARM)

---

800  **Minus hardware limit switch**

**Cause**
A 1/0 edge was identified at the "Minus hardware limit switch" input signal.

**Remedy**
- In the pos mode: Return the drive to the traversing range using jog key 1 or 2.
- In the n-set mode: Enter a setpoint that opposes the approach direction.

**Acknowledgement** not required

**Stop response** STOP VII
### 801 Plus hardware limit switch

**Cause**
A 1/0 edge was identified at the "Plus hardware limit switch" input signal.

**Remedy**
- In the pos mode: Return the drive to the traversing range using jog key 1 or 2.
- In the n-set mode: Enter a setpoint that opposes the approach direction.

**Acknowledgement**
not required

**Stop response**
STOP VII

---

### 802 Drive rotates in response to angular encoder output parameters

**Cause**
The drive was not stationary as the zero pulse offset was programmed on the angular encoder interface. Low speeds are not critical, but the inaccuracy of the zero pulse position increases in proportion to speed.

**Remedy**
Ensure that the drive is at a standstill, or take into account a higher inaccuracy of the zero pulse.

**Acknowledgement**
not required

**Stop response**
STOP VII

---

### 804 Controller enable or on/off 1(edge) or on/off 2/3 missing

**Cause**
When starting a traversing block, the controller enable has not been set, or the controller enable is missing during a traversing program when re-starting the axis from standstill.

Controller enable missing, i.e. one of the following signals missing:
- PROFIBUS control signals (STW1.0: ON / OFF 1 (signal edge), STW1.1: OC / OFF2, STW1.2: OC / OFF 3, STW1.3: Enable inverter / pulse inhibit) and the appropriate signals of the bus interface
- PC enable (SimoCom U)
- Terminal 64
- Terminal 65.x

**Remedy**
Set the missing signal, and re-start the traversing block or enter a signal edge via PROFIBUS.

**Acknowledgement**
not required

**Stop response**
STOP VII
805 Pulse enable missing

Cause When starting a traversing block, the pulse enable is not set, or the pulse enable is missing during a traversing program when re-starting the axis from standstill.

Pulse enable missing, i.e. one of the following signals missing:
- PROFIBUS control signals (STW1.1: OC / OFF 2, STW1.3: Enable inverter / pulse inhibit) or the appropriate signals of the bus interface
- Terminal 48 (NE module)
- Terminal NS1/NS2 (NE module)
- Terminal 63 (NE module)
- Terminal 663 (control module)

Remedy Set the missing enable signal and then re-start the traversing block.

Acknowledgement not required

Stop response STOP VII

806 OC/reject traversing task missing

Cause When starting a traversing block, the "operating condition / reject traversing task" input signal is not set.

Remedy Set the "operating condition / reject traversing task" input signal and then re-start the traversing block.

Acknowledgement not required

Stop response STOP VII

807 OC/intermediate stop missing

Cause When starting a traversing block the "operating condition / intermediate stop" input signal is not set.

Remedy Set the "operating condition / intermediate stop" input signal and then re-start the traversing block.

Acknowledgement not required

Stop response STOP VII

808 Reference point not set

Cause When starting a traversing block, a reference point is not set.

Remedy Execute referencing or set a reference point using the "set reference point" input signal.

Acknowledgement not required

Stop response STOP VII

809 Parking axis selected

Cause When starting a traversing block or when starting referencing, the "parking axis" function is selected.

Remedy Cancel the "parking axis" function and then re-start the required function.

Acknowledgement not required

Stop response STOP VII
810  **Velocity in the block \%n with override = 0**

**Cause**
The velocity programmed in this block was calculated with the actual override and a value of 0 was obtained. The velocity is set to the lowest unit.

**Remedy**
Increase override.

**Acknowledgement**
not required

**Stop response**
STOP VII

811  **Absolute value memory, alarm threshold**

**Cause**
Not enough absolute value memory space.

**Remedy**
- Power-down the drive and power-up again
- POWER-ON RESET

**Acknowledgement**
not required

**Stop response**
STOP VII

814  **Motor temperature, pre-alarm**

**Cause**
1. The motor temperature is sensed using a temperature sensor (KTY84 or PTC) and evaluated in the drive. This alarm is output if the motor temperature reaches the alarm threshold, motor overtemperature (P1602 for KTY or the PTC-specific switching temperature for PTC).
2. The thermal motor model has reached the thermal motor utilization alarm threshold P1269.

**Remedy**
- Avoid many acceleration and braking operations which follow one another quickly.
- Check whether the motor output is sufficient for the drive, otherwise use a more powerful motor, possibly together with a higher-rating power section.
- Check the motor data. It is possible that the motor current is too high as a result of incorrect motor data.
- Check the thermal motor utilization alarm threshold P1269.
- Temperature sensor monitoring.
- Check the motor fan.

**Acknowledgement**
not required

**Stop response**
STOP VII
815  **Power module temperature, pre-alarm**

**Cause**
The power unit heatsink temperature is sensed using a thermosensor located on the main heatsink. If the overtemperature condition remains, then the drive shuts down after approx. 20 s.

**Remedy**
Improve the drive module cooling, e.g. using:
- Higher airflow in the switching cabinet, possibly cool the ambient air of the drive modules
- Avoid many acceleration and braking operations which follow quickly one after the other
- Check that the power section for the axis/spindle is adequate, otherwise use a higher-rating module
- Ambient temperature too high (refer to the Planning Guide)
- Permissible installation altitude exceeded (refer to the Planning Guide)
- Pulse frequency too high (refer to the Planning Guide)
- Check fan, if required, replace
- Maintain the minimum clearance above and below the power section (refer to the Planning Guide)

**Acknowledgement**
not required

**Stop response**
STOP VII

816  **Resolver sensing at its limit**

**Cause**
At run-up, the speed with an existing resolver evaluation was extremely high. It is possible that this was not the actual speed, and that the resolver was not connected to the measuring circuit input.

**Remedy**
Insert the measuring circuit connector and enter a reset.

**Acknowledgement**
not required

**Stop response**
STOP VII

820  **Power module in i2t limiting**

**Cause**
The power module is being operated too long above the permissible load limit.

**Remedy**
- Avoid many acceleration and braking operations which follow quickly one after the other
- Check that the power section for the axis/spindle is adequate, otherwise use a higher-rating module
- Pulse frequency too high (refer to the Planning Guide)
- Check P1260 and P1261

**Acknowledgement**
not required

**Stop response**
STOP VII

824  **Function generator faulted \%d**

**Cause**
An error has occurred when activating the function generator.

**Remedy**
Read-out the detailed fault cause from P1800 and remove the cause. Fault coding in supplementary info and P1800.

**Acknowledgement**
not required

**Stop response**
STOP VII
827 Fieldbus is not in the data exchange state

Cause The bus interface is still not in the data exchange state or data exchange was interrupted.

Causes:
- The master has not yet run up, or has not yet established a connection to the slave.
- The bus addresses differ in the master configuring and slave parameterization.
- The bus connection has been physically interrupted.
- The master is still in the clear condition.
- An illegal parameterization or configuration was received.
- A BUS address was assigned several times.

Remedy Master, check the assignment of bus addresses and bus connection.

Acknowledgement not required

Stop response STOP VII

828 Fieldbus is not in clock-cycle synchronism to the master

Cause The bus interface is in the data exchange state and was selected using the parameterizing telegram of the clock-cycle synchronous operation. It was not possible to synchronize to the clock cycle specified by the master and to the master sign of life.

Causes:
- The master does not send an equidistant global control frame although clock synchronism has been selected via the bus configuration.
- The master uses a different equidistant DP clock cycle as was communicated to the slave in the parameterizing telegram.
- The master does not increment its sign-of-life in the configured time grid Tmapc.

Remedy Check master application and bus configuration

Check the consistency between the clock cycle input for the slave configuring and the clock cycle setting at the master.

If the master (e.g. SIMATIC S7) does not transfer a sign-of-life, the sign-of-life evaluation can also be suppressed using P0879 bit 8.

Acknowledgement not required

Stop response STOP VII
829 PROFIBUS: Illegal parameterization received. Reason: \%u

Cause
An illegal parameterizing frame was received via PROFIBUS. Cyclic data transfer cannot start.
Reasons:
8 = The parameterizing telegram has an illegal length
9 = The length data in the equidistant block is illegal
10 = A block header has an unknown ID.
11 = The basis time Tbasedp is not permissible (not equal to 125 \(\mu\)s).
12 = The DP clock cycle Tdp is not permissible (less than 1ms or greater than 32ms).
13 = The time Tmapc is less than 1*Tdp or greater than 14*Tdp.
14 = The base time Tbaseio is not permissible (not equal to 125 \(\mu\)s).
15 = Time Ti is greater than the DP clock cycle (Tdp).
16 = Time To is greater than the DP clock cycle (Tdp).
17 = For active Data Exchange, a new parameterization was received with different contents.
18 = Clock cycle synchronous operation was selected without a suitable option module having been activated (refer to P0875).
19 = IsoM_Req (state 3, bit 4) is requested in the DPV1 header without there being an isochron block (ID 0x04).
20 = Fail_Safe (state 1, bit 6), IsoM_Req (state 3, bit 4) or Prm_Structure (state 3, bit3) missing in the DPV1 header although an isochron block (ID 0x04) is available.
21 = The time Tdx is greater than (To - 125us) or greater than (Tdp - 250 \(\mu\)s).
22 = The time Tpllw is greater than 1us.
23 = Slave-to-slave communication access target address and length do not conform to word boundary.
24 = Maximum number (3 external + 1 internal) of slave-to-slave communication links has been exceeded.
25 = Maximum number (8) of accesses per link has been exceeded.
26 = Unknown version ID in the slave-to-slave communications block.
27 = The maximum overall length of the filter table has been exceeded.
31 = The permitted maximum length of the parameterizing telegram for the option module has been exceeded.
32 = The option module firmware does not support slave-to-slave communications

Remedy
Check the bus configuration at the master, and if required correct the parameterization.
If required, insert (reason 18) a suitable option module and activate.
If required, (reason 31 or reason 32) upgrade the option module firmware to a version greater than or equal to 04.01.

Acknowledgement
not required

Stop response
STOP VII
830 PROFIBUS: Illegal configuration received. Reason: \%u

Cause
An illegal configuration frame was received via PROFIBUS. Cyclic data transfer cannot start.

Reasons:
1 = In the master, more axes are configured than are physically present in the power module.
2 = The number of axes configured in the master is not equal to the number axes for which the PROFIBUS-DP option module is actively switched via P0875. Note: Even if axis B is de-activated (passivated), communications with axis B are not automatically de-activated.
3 = Configuration incomplete (too short) for one of the PPL types (only for vor P875 = 2).
4 = No PPO type detected (only for P875 = 2).
5 = Length calculation different between firmware and option module.
6 = For active data exchange, a new configuration was received with different length.
7 = Configuration contained unknown S7 ID.
19 = More PZD's have been configured than the maximum permissible.
20 = The configuration contains an unknown special character (only axis separators are permitted).
22 = Target offset of slave-to-slave communications access exceeds the maximum number of PZDs.
28 = Number of slave-to-slave communication IDs differs from the number of accesses in the parameterizing telegram.
29 = Setpoint PZDs are not uniformly supplied by the master or slave (drive) publisher.
30 = The permitted maximum length of the configuration telegram for the option module has been exceeded.

Remedy
Check the bus configuring at the master and if required correct.
If required, using P875, activate the option module PROFIBUS-DP, which are previously configured in the PROFIBUS Master for the number of axes involved.

Acknowledgement not required

Stop response STOP VII
831 PROFIBUS is not in the data transfer condition

Cause
The PROFIBUS is not in a data transfer status (data exchange) or data transfer was interrupted.

Causes:
- The master has not yet run up, or has not yet established a connection to the slave.
- The bus addresses differ in the master configuring and slave parameterization.
- The bus connection has been physically interrupted.
- The master is still in the clear condition.
- An illegal parameterization or configuration was received.
- A PROFIBUS address was assigned several times.

Remedy
Master, check the assignment of bus addresses and bus connection.

Acknowledgement not required

Stop response STOP VII

832 PROFIBUS not clock-synchronous with the master

Cause
The PROFIBUS is in a data transfer status (data exchange) and has been selected via the parameterizing frame of synchronous operation. It could not yet be synchronized to the clock preset by the master resp. to the master sign-of-life.

Causes:
- The master does not send an equidistant global control frame although clock synchronism has been selected via the bus configuration.
- The master uses a different equidistant DP clock cycle as was communicated to the slave in the parameterizing telegram.
- The master increments its sign-of-life (STW2 Bits 12–15) not in the configured time frame Tmapc.

Remedy
Check master application and bus configuration
Check the consistency between the clock cycle input for the slave configuring and the clock cycle setting at the master.
If the master (e.g. SIMATIC S7) does not transfer a sign-of-life, the sign-of-life evaluation can also be suppressed using P0879 bit 8.

Acknowledgement not required

Stop response STOP VII
### 7.3 List of faults and alarms

#### 833 PROFIBUS: No connection to the publisher \%u

**Cause**
Cyclic data transfer between this slave and a slave-to-slave communications publisher was still not started or was interrupted.

Examples:
- Bus connection interrupted
- Publisher failure
- Master runs up again
- The response monitoring (Watchdog) for this slave was de-activated via the parameterizing telegram (SetPrm)
  (Diagnostics: P1783:1 bit 3 = 0).

**Supplementary info:** PROFIBUS address of the publisher

**Remedy**
Check the publisher and bus connections to the publisher, to the master and between the master and publisher.

if the watchdog is de-activated, activate the response monitoring for this slave via Drive ES.

**Acknowledgement**
not required

**Stop response**
STOP VII

---

#### 840 Teach-in for running traversing program

**Cause**
Teach-in was requested during a running traversing program.

**Remedy**
Exit the traversing program and re-request teach-in.

**Acknowledgement**
not required

**Stop response**
STOP VII

---

#### 841 Teach-in for relative block

**Cause**
The traversing block as "teach in block" is relative instead of absolute.

**Remedy**
Change the traversing block mode "teach in block" from relative to absolute.

**Acknowledgement**
not required

**Stop response**
STOP VII

---

#### 842 Teach-in for a relative standard block

**Cause**
The traversing block as "teach in standard set", is relative instead of absolute.

**Remedy**
Change the traversing block mode "teach in standard block" from relative to absolute.

**Acknowledgement**
not required

**Stop response**
STOP VII
843  **Search velocity too high**

Cause  The search velocity for spindle positioning is too high for the selected maximum deceleration.

Remedy  Reduce the search speed P0082:256 or increase the maximum deceleration P0104.

Acknowledgement  not required

Stop response  STOP VII

845  **Jogging not effective for active coupling**

Cause  Jogging is not possible while a coupling is closed.

Remedy  Release the coupling and re-activate jogging.

Acknowledgement  not required

Stop response  STOP VII

849  **PLUS software limit switch actuated**

Cause  For a block with the ENDLOS_POS command, the axis has actuated the plus software limit switch (P0316) for absolute or relative positioning.

Remedy  
- Move away in the negative direction, jogging.
- Move away in the negative direction using the traversing block.

Acknowledgement  not required

Stop response  STOP VII

850  **MINUS software limit switch actuated**

Cause  For a block with the ENDLOS_NEG command, the axis has actuated the minus software limit switch (P0315) for absolute or relative positioning.

Remedy  
- Move away in the positive direction, jogging.
- Move away in the positive direction using the traversing block.

Acknowledgement  not required

Stop response  STOP VII

864  **Parameterization error in speed controller adaptation**

Cause  The upper adaption speed (P1412) was parameterized with a lower value than the lower adaption speed (P1411).

Remedy  P1412 must contain a higher value than P1411.

Acknowledgement  not required

Stop response  STOP VII
865  **Invalid signal number**  
**Cause**  
The signal number for the analog output is not permissible.  
An analog value can be output for diagnostic, service and optimization tasks  
Term. 75.x/15, 16.x/15, DAC1, DAC2  
**Remedy**  
Enter valid signal number  
(refer to the Description of Functions SIMODRIVE 611 universal)  
**Acknowledgement**  
not required  
**Stop response**  
STOP VII  

866  **Parameterizing error, current controller adaption**  
**Cause**  
For the current controller adaption, the upper current limit (P1181) was parameterized with a lower value than the lower current limit (P1180).  
Adaption is de-activated when the parameterizing error is output.  
**Remedy**  
P1181 must contain a higher value than P1180.  
**Acknowledgement**  
not required  
**Stop response**  
STOP VII  

867  **Generator mode: Response voltage > shutdown threshold**  
**Cause**  
The sum of the values in P1631 + P1632 is greater than the value in P1633.  
**Remedy**  
Boot module  
Note:  
P1630 to P1633 are internal Siemens parameters  
**Acknowledgement**  
not required  
**Stop response**  
STOP VII  

868  **Regenerative operation: shutdown threshold > response threshold**  
**Cause**  
The input value for the shutdown threshold, regenerative operation (P1633) is greater than (or equal to) the response threshold, DC link voltage (P1630).  
**Remedy**  
Boot module  
Note:  
P1630 and P1633 are internal Siemens parameters  
**Acknowledgement**  
not required  
**Stop response**  
STOP VII  

869  **Reference point coordinate limited to modulo range**  
**Cause**  
The reference point coordinate is internally limited to the modulo range.  
**Remedy**  
Enter a value in P0160 which lies within the modulo range (P0242).  
**Acknowledgement**  
not required  
**Stop response**  
STOP VII
870 Jerk: jerk time is limited

Cause When calculating the jerk time \( T \) from the acceleration \( a \) and the jerk \( r \), the result was an excessively high jerk time, so that the time is limited internally. 

The following is valid: \( T = \frac{a}{r} \), where 
- \( r \): Jerk (P0107)
- \( a \): Acceleration (higher value from P0103 and P0104)

Remedy
- Increase jerk (P0107)
- Reduce maximum acceleration (P0103) or maximum deceleration (P0104)

Acknowledgement not required

Stop response STOP VII

871 Induction motor operation: drive converter frequency motor not permissible

Cause In induction motor operation (selected by P1465 < P1146), drive converter frequencies of 4 or 8 kHz are permissible.

Remedy
- Change P1100
- Cancel induction motor operation (P1465 > P1146)

Acknowledgement not required

Stop response STOP VII

872 PARAMETERIZING ERROR: P gain, equalization controller too high

Cause PARAMETERIZING ERROR: P gain, equalization controller does not fit into the format.

Remedy
- Change P1491

Acknowledgement not required

Stop response STOP VII

875 Axial deviations in fixed voltage

Cause For the axes of a drive module, an unequal fixed voltage (P1161) was set.

As a fixed voltage \(<>\) 0 replaces the DC link voltage measured value, but the DC link voltage is only measured once for all drives of a drive module, the fixed voltage on all module axes must be equal, before it is accepted.

Remedy Set the same fixed voltage (P1161) on all module axes.

Acknowledgement not required

Stop response STOP VII
7.3 List of faults and alarms

876 Terminal function \%u in the actual mode illegal

Cause The function number, used as input terminal or distributed input (P0888) may not be used in the actual mode.

Remedy Change P0700 (operating mode) or enter a suitable function number in P0888 or P0660, P0661 etc.

Acknowledgement not required

Stop response STOP VII

877 Output function \%u not permissible in the actual operating mode

Cause The function number, used as output, may not be used in the actual operating mode.

Remedy Change P0700 (operating mode) or enter a suitable function number in P0680, P0681, etc.

Acknowledgement not required

Stop response STOP VII

878 Input I0.x not parameterized as equivalent zero mark

Cause When entering an external signal as equivalent zero mark (P0174 = 2) input I0.x must be assigned the function "equivalent zero mark" (Fct. No.: 79).

if a direct measuring system is used, input I0.B must be assigned the "equivalent zero mark" function (Fct. No.: 79).

Remedy
- Motor measuring system: P0660 = 79
- Direct measuring system: P0672 = 79

Acknowledgement not required

Stop response STOP VII

879 Time constant deadtime, speed feedforward control (P0205:\%u) too high

Cause P0205:8 may not be greater than two position controller clock cycles. Higher values are internally limited.

Remedy Reduce P0205:8 to max. two position controller clock cycles (P1009). Parameterize an addition delay via P0206:8.

Acknowledgement not required

Stop response STOP VII
881  PZD configuring: Signal number in P0915:u invalid
Cause
An undefined or illegal signal number in the current operating mode (P0700) was identified for the process data software. P0915:1 is not equal to 50001 (STW1). The process data for encoder 1 has been configured although encoderless operation is activated (P1011.5). The process data for encoder 2 were configured although the direct measuring system is not activated (P0879.12).

Remedy
Correct P0915:17

Acknowledgement not required

Stop response STOP VII

882  PZD configuring: Double word signal number in P0915:u invalid
Cause
For signals with double words (length = 32 bits), the corresponding signal identifier must be configured twice for adjacent process data. The following subparameter must therefore also be parameterized with the same signal number.

Remedy
Correct P0915:17

Acknowledgement not required

Stop response STOP VII

883  PZD configuring: Signal number in P0916:u invalid
Cause
An undefined or illegal signal number in the current operating mode (P0700) was identified for the process data software. P0916:1 is not equal to 50002 (ZSW1). The process data for encoder 1 has been configured although encoderless operation is activated (P1011.5). The process data for encoder 2 were configured although the direct measuring system is not activated (P0879.12).

Remedy
Correct P0916:17

Acknowledgement not required

Stop response STOP VII

884  PZD configuring: Double word signal number in P0916:u invalid
Cause
For signals with double words (length = 32 bits), the corresponding signal identifier must be configured twice for adjacent process data. The following subparameter must therefore also be parameterized with the same signal number.

Remedy
Correct P0916:17

Acknowledgement not required

Stop response STOP VII
7.3 List of faults and alarms

885 P1261 greater than 100.0 % not permissible

Cause P1261 greater than 100.0 % is not permissible for permanent-magnet synchronous motors with field weakening (PE spindle, P1015 = 1). It is internally limited to 100.0 %.

Remedy Set P1261 to max. 100.0 %.

Acknowledgement not required

Stop response STOP VII

886 Pre-tensioning torque greater than 16x rated torque

Cause The parameterized pre-tensioning torque (P1493) is greater than 16x the standstill torque (SRM), rated motor torque (ARM) and standstill force (SLM) of the motor.
Note: refer to the index entry "Limits"

Remedy Reduce pre-tensioning torque (P1493)

Acknowledgement not required

Stop response STOP VII

889 Fixed endstop, axis has not reached the clamping torque

Cause The axis has reached the fixed stop - however was not able to establish the programmed clamping torque

Remedy Check the parameters for the limits.

Acknowledgement not required

Stop response STOP VII

890 Acceleration - deceleration override incorrect

Cause The acceleration override or the deceleration override is not in the range from 1% to 100%.
if the value > 100%, then it is limited to 100%.
if the value < 1%, then limited to 1%.
The traversing block is not interrupted.

Remedy Check the programming of the acceleration override and deceleration override

Acknowledgement not required

Stop response STOP VII
891  PLUS software limit switch actuated coupled
Cause  With the actual master drive velocity, this coupling axis will probably reach or pass the PLUS software limit switch. This warning is output if the coupled axis has fallen below 200% of the braking travel up to the PLUS software limit switch.
Remedy  Traverse the master drive so that this coupling axis goes into the permissible traversing range.
Acknowledgement  not required
Stop response  STOP VII

892  MINUS software limit switch actuated coupled
Cause  With the actual master drive velocity, this coupling axis will probably reach or pass the MINUS software limit switch. This warning is output if the coupled axis has fallen below 200% of the braking travel up to the MINUS software limit switch.
Remedy  Traverse the master drive so that this coupling axis goes into the permissible traversing range.
Acknowledgement  not required
Stop response  STOP VII

893  Function 73 only effective at terminal I0.x
Cause  The terminal function 73 "Coupling on I0" is only effective at terminal I0.x.
Remedy  Assign terminal I0.x to function 73.
Acknowledgement  not required
Stop response  STOP VII

894  Inputs, optional TERMINAL module assigned twice
Cause  The input terminals on the optional TERMINAL module can only be used by one drive.
Remedy  Check and correct P0676 (A) and P0676 (B).
Acknowledgement  not required
Stop response  STOP VII

895  Outputs, optional TERMINAL module assigned twice
Cause  Only one drive can use the output terminals on the optional TERMINAL module.
Remedy  Check and correct P0696 (A) and P0696 (B).
Acknowledgement  not required
Stop response  STOP VII
7.4 Commissioning functions

Overview

The commissioning functions and support tools help during start-up, during service, when optimizing the drive, and troubleshooting.

The "SIMODRIVE 611 universal" control board has the following commissioning and help functions:

- Function generator (FG) refer to Chapter 7.4.1
- Trace function refer to Chapter 7.4.2
- Test sockets (DAC1, DAC2) refer to Chapter 7.4.3
- Measuring function refer to Chapter 7.4.4

Caution

Setpoints entered via analog inputs (e.g., via terminals 56.x/14.x and/or 24.x/20.x) or speeds entered via PROFIBUS-DP are added when the function generator starts.

Note:
The analog inputs can be disabled via P0607 = 0 (for terminal 56.x/14.x) or P0612 = 0 (for terminal 24.x/20.x).

Note

For a "SIMODRIVE 611 universal" control board, only 1 function generator or 1 measuring function can be started at the same time, i.e., either for drive A or B.

Start-up (commissioning) functions and "SimoCom U" tool

The SimoCom U parameterization and start-up tool can, in the online mode, start the commissioning functions "function generator" and "measuring function" with the control authority for PG/PC.

Note

If online operation between SimoCom U and "SIMODRIVE 611 universal" is interrupted while a start-up function is being executed, then this start-up function is exited, and an appropriate fault is displayed on the display unit.
7.4.1 Function generator (FG)

Overview

Using the function generator:

- The influence of the higher-level control loops can be specifically disabled.
- The dynamic performance can be compared for coupled drives.
- A simple characteristic (traversing profile) can be selected as setpoint and repeated, without having to program a traversing program.
- From SW 11.1 the "Oscillate" function of the "SIMODRIVE 611 analog" can be simulated.

The function generator generates various types of setpoints (square-wave, staircase, delta, PRBS or sinusoidal), and enters this setpoint, corresponding to the selected mode, as current setpoint, disturbing torque or as speed setpoint.

Danger

If the function generator is active, then traversing motion is not monitored.

Starting the function generator

The following must be observed when starting the function generator:

- The function generator is started as follows:
  - Setting P1800 = 1
    The function generator is immediately started.
  - Setting P1800 = 2 (from SW 8.1)
    Synchronous start of the function generator, e.g. for gantry axes, if in the n-set mode, the PROFIBUS control word STW1.8 is 1. From SW 9.1 onwards, also with PROFIBUS control word PosStw.15 in the pos mode or with the digital input terminal function No. 41 "activate function generator (signal edge)".
    - From SW 11.2 onwards for the realization of the "Oscillation" function with PROFIBUS control word STW1.9 = 1 or with input terminal function No. 2 "Activate function generator immediately".

- The following starting conditions and enable signals must be available:

Table 7-5 Starting conditions for the function generator

<table>
<thead>
<tr>
<th>Starting conditions</th>
<th>Operating mode FG P1804 = 1</th>
<th>Operating mode FG P1804 = 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Speed controlled</td>
<td>3 (only V/Hz operation)</td>
<td>3 (without V/Hz operation)</td>
</tr>
<tr>
<td>operation on</td>
<td></td>
<td>X</td>
</tr>
<tr>
<td>Controller enable</td>
<td>X</td>
<td>X</td>
</tr>
</tbody>
</table>
### 7.4 Commissioning functions

<table>
<thead>
<tr>
<th>Starting conditions</th>
<th>Operating mode FG P1804 = 1</th>
<th>Operating mode FG P1804 = 2</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>= 1 (only V/Hz operation)</td>
<td>= 2 (without V/Hz operation)</td>
</tr>
<tr>
<td>Pulse enable</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Internal regenerative stop inactive</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>Ramp-up generator enabled</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>x: Start condition must be fulfilled</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

#### Fault

If a fault is identified when starting or during operation, then the function generator is exited, and the reason for the fault is displayed by entering a negative value in P1800.

#### Stopping the function generator

The function generator can be stopped as follows:

- **Stopped via P1800 = 1 + 0**
  
  If the function generator is stopped using this parameter, then the drive is braked with the deceleration set in P1813.

- **Stopping is possible via STW1.8 = 0 for P1800 = 2 (from SW 8.1)**
  
  From SW 9.1 also with PROFIBUS control word PosStw.15 in the pos mode or with digital input terminal functions No. 41 "activate function generator (signal edge)".

  If the function generator is stopped using this PROFIBUS control word, then the drive is braked with the deceleration set in P1813.

  After stopping, the value -23 appears in P1800.

- **Cancel**
  
  As soon as one of the function generator starting conditions is no longer fulfilled, the drive brakes along the braking ramp P1813 or "coasts down" when the pulse enable is withdrawn.

  Further, the function generator is stopped, if incorrect parameterization is executed during operation.

#### Note

The control structure of the drive is re-established each time that the function generator is stopped or aborted.

While the function generator runs, e.g. in the mode "current setpoint" (P1804 = 1), all of the higher-level control loops are open. The control loops are re-closed when the function generator is either stopped or canceled.
The following parameters are used to parameterize the function generator:

Table 7-6  Parameters for the function generator

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1800</td>
<td>Function generator control</td>
<td>-40</td>
<td>0</td>
<td>2</td>
<td></td>
<td>immediately</td>
</tr>
</tbody>
</table>

... starts, exits the function generator and if a fault/error is present, displays the reason.

- 2  Synchronous start of the function generator (from SW 8.1)
- 1  Starts the function generator. The FG is again terminated with P1800 = 1 → 0.
- 0  Function generator is inactive
- -1 Commissioning-function was started; but was possibly already running on another drive
- -2 Inadmissible mode or the mode was changed while the FG was active
- -4 The period is 0 or too high
- -6 The absolute amplitude is too high
- -7 The offset lies outside the permitted range
- -8 The limit is greater than permitted
- -9 Incorrect waveform or the waveform was changed while the FG was active
- -10 The pulse width is negative or greater than the period
- -11 The bandwidth is less than 1 Hz or greater than the maximum possible bandwidth (for a sampling time of 0.125 ms, the maximum possible bandwidth is 4000 Hz)
- -15 The 2nd amplitude for the “staircase” waveform is too high
- -16 The commissioning function was not started or was aborted due to an active internal regenerative stop
- -17 The commissioning function was not started or was aborted due to the missing pulse enable
- -18 The commissioning function was not started or was aborted due to the missing speed controller enable
- -19 The commissioning function was not started or was aborted due to the missing “speed controlled mode” enable
- -20 The commissioning function was not started or was aborted due to a missing ramp-function generator enable signal
- -21 The commissioning function was not started due to a traversing axis (e.g. active traversing block)
- -23 The commissioning function was canceled because the synchronous start enable was withdrawn
### Table 7-6 Parameters for the function generator, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1804</td>
<td>Function generator mode</td>
<td>1</td>
<td>3</td>
<td>5</td>
<td>-</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... specifies at which input the generated setpoint is entered.

= 1 Current setpoint
   The current control loop is closed, all of the higher-level control loops are open. The function generator output is the current setpoint in the current controller clock cycle.

= 2 Disturbing torque
   The speed control loop is closed, all of the higher-level control loops are open. The function generator output is the current setpoint in the speed controller clock cycle.
   When starting and stopping, the acceleration/deceleration is limited by the ramp-function generator of the function generator.

= 3 Speed setpoint
   The speed control loop is closed, all of the higher-level control loops are open. The function generator output is the speed setpoint in the speed controller clock cycle.
   When starting and stopping, the acceleration/deceleration is limited by the ramp-function generator of the function generator.

= 4 Disturbing torque with the ramp-function generator (from SW 2.4)
   The speed control loop is closed and all of the higher-level control loops are open. The function generator output is the current setpoint in the speed controller clock cycle.
   When starting and stopping, the acceleration/deceleration is limited by the ramp-function generator of the function generator as well as by the ramp-function generator in the speed setpoint channel. The maximum value from the ramp-up/ramp-down time (P1256/P1257) of the RFG in the speed setpoint channel and the time of the ramp-function generator of the function generator (P1813) is always used.

= 5 Speed setpoint with the ramp-function generator (from SW 2.4)
   The speed control loop is closed and all of the higher-level control loops are open. The function generator output is the speed setpoint in the controller clock cycle.
   When starting and stopping, the acceleration/deceleration is limited by the ramp-function generator of the function generator as well as by the ramp-function generator in the speed setpoint channel. The maximum value from the ramp-up/ramp-down time (P1256/P1257) of the RFG in the speed setpoint channel and the time of the ramp-function generator of the function generator (P1813) is always used.
   When moving along the characteristic, the ramp-up and ramp-down time of the ramp-function generator in the speed setpoint channel is taken into account.

**Note:** When a parameter is changed with the function generator active, this causes the system to crash.
Table 7-6  Parameters for the function generator, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1805</td>
<td>Function generator, waveform</td>
<td>1</td>
<td>1</td>
<td>5</td>
<td>–</td>
<td>immediately</td>
</tr>
</tbody>
</table>

... specifies which function generator waveform should be output.

**Note:** When a parameter is changed with the function generator active, this causes the system to crash.

- **Start = 1** Rectangle

- **Start = 2** Staircase

- **Start = 3** Triangular

- **Start = 4** PRBS (pseudo random binary signal)

- **Start = 5** Sinusoidal
### 7.4 Commissioning functions

Table 7-6  Parameters for the function generator, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1806</td>
<td>Start-up function, amplitude</td>
<td>-1 600.0</td>
<td>5.0</td>
<td>1 600.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... specifies the amplitude of the signal to be output. The units are dependent on P1804. if then P1804 = 1, 2 the units are referred to P1103 (rated motor current) P1804 = 3 the units are referred to P1400 (rated motor speed)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1807</td>
<td>Start-up function, offset</td>
<td>-1 600.0</td>
<td>0.0</td>
<td>1 600.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... defines the offset of the signal to be output. The units are dependent on P1804. if then P1804 = 1 the unit is referred to P1103 (rated motor current) P1804 = 2, 3 the units are referred to P1400 (rated motor speed)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>For P1804 = 2 (&quot;fault torque&quot; mode), the offset does not affect the current setpoint, but the speed setpoint, to compensate for the effects of backlash (play).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1808</td>
<td>Function generator limiting</td>
<td>0.0</td>
<td>100.0</td>
<td>1 600.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>... defines the limit of the signal to be output. The units are dependent on P1804. if then P1804 = 1, 2 the units are referred to P1103 (rated motor current) P1804 = 3 the units are referred to P1400 (rated motor speed)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td><strong>Note:</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The limit is effective, symmetrically around the zero point. For P1804 = 2 (&quot;disturbance torque&quot; mode), the limit only acts on the current setpoint, but not on the speed setpoint (= offset).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1809</td>
<td>Function generator 2nd amplitude</td>
<td>-1 600.0</td>
<td>7.0</td>
<td>1 600.0</td>
<td>%</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>(only for P1805 = 2, staircase)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... specifies the 2nd amplitude for the &quot;staircase&quot; waveform. The units are dependent on P1804. if then P1804 = 1, 2 the units are referred to P1103 (rated motor current) P1804 = 3 the units are referred to P1400 (rated motor speed)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1810</td>
<td>Function generator period</td>
<td>1</td>
<td>1 000</td>
<td>65 535</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>(not for P1805 = 4, PRBS)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the period of the signal to be output.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1811</td>
<td>Function generator pulse width</td>
<td>0</td>
<td>500</td>
<td>65 535</td>
<td>ms</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>(only for P1805 = 1, squarewave)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the pulse width of the &quot;squarewave&quot; waveform.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1812</td>
<td>Start-up function, bandwidth (FFT)</td>
<td>1</td>
<td>4 000</td>
<td>8 000</td>
<td>Hz</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>(only for P1805 = 4, PRBS)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the bandwidth in the PRBS mode.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Table 7-6 Parameters for the function generator, continued

<table>
<thead>
<tr>
<th>No.</th>
<th>Description</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1813</td>
<td>Start-up function, ramp-up time at P1400 (only for P1804 = 2, 3 -- &gt; closed speed control loop)</td>
<td>0.0</td>
<td>32.0</td>
<td>100 000.0</td>
<td>ms</td>
<td>immediately</td>
</tr>
</tbody>
</table>

...specifies the time in which the drive accelerates or decelerates (brakes) to the required speed. In this case, the parameter refers to P1400 (rated speed).

The following applies: \( P1813 = \frac{P1400}{\text{required speed}} \) • required ramp-up time

Example:

Rated speed \( n_{\text{rated}} = 3000 \text{ RPM} \) (P1400)
The drive should accelerate up to 500 RPM in 20 ms

\(- > P1813 = \frac{3000}{500} \times 20 \text{ ms} = 120 \text{ ms}\)

---

### Additional waveforms

Additional waveforms are available using the appropriate parameterization.

Example:

For the "triangular" waveform, a triangular waveform without peak is obtained by appropriately parameterizing the limit.

![Triangular Waveform

Fig. 7-5 "Triangular" waveforms with no peak

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Details of the "staircase" waveform

The "staircase" waveform is especially significant when optimizing the speed controller. Depending on how the amplitude is parameterized, the following interesting possibilities are obtained:

- **Amplitude = 0** (P1806 = 0)

  **Advantages:**
  - Reversing is possible
  - The axis stops at the end points

  **Disadvantage:**
  - There is play and static friction if there is no offset
  - With offset, the axis continually distances itself from the starting point

![Fig. 7-6 "Staircase" waveform with amplitude = 0 and offset > amplitude 2](image1)

- **Amplitude ≠ 0** (P1806 ≠ 0)

  **Advantages:**
  - Reversing is possible
  - A higher (2nd amplitude) is selected from a basic velocity (amplitude)
  - The traversing profile periodically repeats itself.
    This means that when optimizing the control loop, the effect can be immediately monitored, e.g. using an oscilloscope connected to test sockets DAC1/DAC2.
  - The axis always moves through the same distance in each direction

![Fig. 7-7 "Staircase" waveform with amplitude > 0 and offset = 0](image2)
7.4.2 Trace function

Description
Selected measuring quantities in the drive can be measured corresponding to the specified measuring parameters, using the trace function and graphically displayed using SimoCom U.

Overview of functions
The trace function has the following properties and features:

- 4 trace buffers with up to 2048 measured values
   The actual number of possible measured values is dependent on whether the measuring signal is 24 or 48 bit.

- Freely-selectable measuring signals
   The required signal is selected from a signal selection box.

- Triggering
  - without triggering (the trace starts immediately after START)
  - with triggering to an additional trigger signal with signal edge/signal level/bit pattern triggering and trigger delay/pre-trigger
  - trigger is initiated by a change in the bit mask (from SW 5.1)
    A trigger is initiated as soon as one of the bits in the bit mask changes.

- X/Y scaling: Automatic and selectable
  Using the scaling, a sub-range can be specified for the abscissa (x axis) and ordinate (y axis), so that a section can be displayed. It is possible to zoom in using an appropriately set scaling factor.

- Signal measurement via cursor
  This means that the signals can be analyzed using the X cursor (time axis) and/or Y cursor.

- From SW 5.1, individual bits of a signal can be evaluated.
  One or several bits can be selected in the "SimoCom U" in the "trace" input mask using the "bit masking" button. The bit masking can be set, independently for each channel and can be recognized by the units of the associated signal.

Reader’s note
The trace function can only be used together with the SimoCom U parameterizing and start-up tool, i.e. SimoCom U is used to control the trace function and to display the measured values.

Additional information on the trace function is provided in the online help for SimoCom U.
7.4 Commissioning functions

7.4.3 Test sockets, DAC1, DAC2

**Description**

For "SIMODRIVE 611 universal", there are two test sockets to output analog signals, with the following features:

- **Resolution of the DAC**: 8 bit
- **Voltage range**: 0 V to +5 V
- **Measurement clock cycle**: Speed controller clock cycle
- **Shift factor** (refer to Figs. 7-8 and 7-9)

The resolution is 8 bit. Thus, only an 8 bit section can be output from a 24/48 bit signal. The shift factor defines how finely the selected signal is quantized.

- **Module-specific**

  The test sockets are provided for each module, i.e. they can be activated and deactivated from each drive.
  Only one drive can output one value at a test socket.

- **Signal selection list**

  The signals which can be output via the test sockets, can be taken from the signal selection list for analog outputs (refer to Chap. 6.7).

---

**Note**

The test sockets are only provided for test purposes during commissioning or for service.
### Parameter overview

The assignment between the test sockets and parameters is as follows:

<table>
<thead>
<tr>
<th>Test sockets</th>
<th>Parameter</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>X34 DAC1</td>
<td>Signal number, test socket 1</td>
<td>1820</td>
<td>0</td>
<td>8</td>
<td>530</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines which signal is output via the DAC (D/A converter). The signal number from the signal selection list must be entered for analog output (refer to Chapter 6.7 under Table 6-57).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Shift factor, test socket 1</td>
<td>1821</td>
<td>0</td>
<td>6</td>
<td>47</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the shift factor, with which the output signal is manipulated. Only an 8 bit output window can be output from a 24/48 bit signal due to the 8-bit resolution. The shift factor can be used to define which 8 of the 24/48 bits are located in the output window and should be output.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Offset, test socket 1</td>
<td>1822</td>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... specifies the offset, which is added to the 8-bit output signal. The signal to be output is shifted by 5/256 V (19.5 mV) by changing the offset by 1 digit. P1822 = -128 = 0 V, P1822 = 0 = +2.5 V, P1822 = 127 = +5V</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Status, test socket 1</td>
<td>1826</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>... defines the status of the test socket for this drive. = 0 Test socket is inactive = 1 Test socket is active</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>As always only one drive can output one value at a test socket, when changing the parameter in one drive, the parameter in the other drive is automatically adapted.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Note:</td>
<td>For a 2-axis module, the test sockets are preset as follows after the first start-up: Drive A Drive B</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Test socket 1 active (P1826 = 1) inactive (P1826 = 0)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Test socket 2 inactive (P1836 = 0) active (P1836 = 1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Test sockets</th>
<th>Parameter</th>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>X34 DAC1</td>
<td>Signal number, test socket 2</td>
<td>1830</td>
<td>0</td>
<td>14</td>
<td>530</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Description, refer to that for P1820.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Shift factor, test socket 2</td>
<td>1831</td>
<td>0</td>
<td>12</td>
<td>47</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Description, refer to that for P1821.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Offset, test socket 2</td>
<td>1832</td>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Description, refer to that for P1822.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Status, test socket 2</td>
<td>1836</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>imme-diately</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Description, refer to that for P1826.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
7 Fault Handling/Diagnostics

7.4 Commissioning functions

**Shift factor**

<table>
<thead>
<tr>
<th>Bit</th>
<th>23 (MSB)</th>
<th>16 15</th>
<th>8 7</th>
<th>0 (LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Analog output value with shift factor = 0</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 1</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 8</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 16</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MSB = Most Significant Bit
LSB = Least Significant Bit

Fig. 7-8  Shift factor for analog output of 24-bit signals

<table>
<thead>
<tr>
<th>Bit</th>
<th>47 (MSB)</th>
<th>40 39</th>
<th>8 7</th>
<th>0 (LSB)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Analog output value with shift factor = 0</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 1</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 8</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with shift factor = 40</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

MSB = Most Significant Bit
LSB = Least Significant Bit

Fig. 7-9  Shift factor for analog output of 48-bit signals

**Voltage range**

![Voltage range diagram](image)

Fig. 7-10  Voltage range for test sockets
### 7.4.4 Measurement function

**Overview**
Using the measuring function, by using simple parameterization, the influence of higher-level control circuits can be disabled and the dynamic performance of the individual drives can be displayed without using any external measuring equipment. This means that it is possible to evaluate and analyze important quantities of the current and speed control loop in the time and frequency domains.

**Measuring principle**
Test signals with a selectable time interval are input into the drives to determine the measured values for graphic display of the time and frequency characteristics of drives and closed-loop control functions.

---

**Fig. 7-11** Block diagram of the drive optimization (schematic)

---

**Reader’s note**
The trace function can only be used together with the SimoCom U parameterizing and start-up tool, i.e. SimoCom U is used to control the trace function and to display the measured values.

Additional information on the measuring functions is provided in the online help for SimoCom U.
7.5 V/Hz operation (diagnostics function)

Description
V/Hz operation allows the following motors to be used:

- Induction motors without encoder evaluation
- 1FK6/1FT6 feed motors without encoder evaluation

Note
The V/Hz operation is exclusively provided for diagnostics purposes for synchronous (SRM) and induction motors (ARM).

V/Hz operation may only be used with converter switching frequencies (P1100) of 4 or 8 kHz. After changing P1100, "calculate controller data" must be re-executed.

For operation with encoder, the speed actual value from the measuring system is displayed, and for operation without encoder, a calculated speed actual value.

7.5.1 V/Hz operation with induction motors (ARM)

Commissioning
For V/Hz operation, it is first necessary to carry-out the standard commissioning for an induction motor with motor selection to obtain practical pre-assignment values (default values) for all of the parameters.

If a motor measuring system is not used, then "no encoder" must be selected as the encoder type.

As "unlisted motors" are generally used, for simple sensorless (no encoder) operation, the rating plate data should be entered and the "calculate equivalent circuit diagram data" and "calculate controller data" functions executed.

V/Hz operation is then activated using P1014 = 1.

Parameters for V/Hz operation with induction motors (ARM)
For V/Hz operation with induction motors, the following parameters are available:

Table 7-8 Parameters for V/Hz operation with ARM

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Name</th>
</tr>
</thead>
<tbody>
<tr>
<td>P1014</td>
<td>Activates V/f mode</td>
</tr>
<tr>
<td>P1125</td>
<td>Ramp-up time 1 for V/Hz operation</td>
</tr>
<tr>
<td>P1127</td>
<td>Voltage at f = 0, V/Hz mode</td>
</tr>
<tr>
<td>P1132</td>
<td>Rated motor voltage</td>
</tr>
</tbody>
</table>
Table 7-8 Parameters for V/Hz operation with ARM, continued

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Name</th>
</tr>
</thead>
<tbody>
<tr>
<td>P1134</td>
<td>Rated motor frequency</td>
</tr>
<tr>
<td>P1146</td>
<td>Maximum motor speed</td>
</tr>
<tr>
<td>P1103</td>
<td>Rated motor current</td>
</tr>
<tr>
<td>P1238</td>
<td>Current limit value</td>
</tr>
<tr>
<td>P1400</td>
<td>Rated motor speed</td>
</tr>
<tr>
<td>P1401</td>
<td>Speed for the max. useful motor speed</td>
</tr>
<tr>
<td>P1405:8</td>
<td>Monitoring speed, motor</td>
</tr>
</tbody>
</table>

V/Hz characteristic ARM

The speed setpoint is converted into the frequency to be used as reference, taking into account the pole pair number, which is determined from the rated motor frequency and rated motor speed. This means the synchronous frequency, associated with the speed setpoint, is output (no slip compensation).

Ramp-up time

The ramp-up time can be set via P1125.

7.5.2 V/Hz operation with synchronous motors (SRM)

Commissioning

For synchronous motors, V/Hz operation is only used for diagnostic purposes.

In this case, the standard commissioning must first be executed with motor selection, to obtain practical pre-assignment values for all of the motor data.

V/Hz operation is then activated using P1014 = 1.
For V/Hz operation with synchronous motors, the following parameters are available:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Name</th>
</tr>
</thead>
<tbody>
<tr>
<td>P1014</td>
<td>Activates V/f mode</td>
</tr>
<tr>
<td>P1104</td>
<td>Maximum motor current</td>
</tr>
<tr>
<td>P1105</td>
<td>Reduced maximum motor current</td>
</tr>
<tr>
<td>P1112</td>
<td>Motor pole pair number</td>
</tr>
<tr>
<td>P1114</td>
<td>Voltage constant</td>
</tr>
<tr>
<td>P1125</td>
<td>Ramp-up time 1 for V/Hz operation</td>
</tr>
<tr>
<td>P1400</td>
<td>Rated motor speed</td>
</tr>
<tr>
<td>P1401</td>
<td>Speed for the max. useful motor speed</td>
</tr>
<tr>
<td>P1405:8</td>
<td>Monitoring speed, motor</td>
</tr>
</tbody>
</table>

The speed setpoint conversion into the frequency to be used as reference is obtained from the pole pair number.

![V/Hz characteristic SRM](image)

Fig. 7-13  V/Hz characteristic SRM

Generally, only speeds up to approx. 25% of the rated speed can be reached due to the strong tendency for synchronous motors to oscillate in the V/Hz mode.

The ramp-up time can be set via P1125.
7.5.3 Parameters for V/Hz operation

Parameter overview

The following parameters are available for V/Hz operation

Table 7-10 Parameter overview for V/Hz operation

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Min.</th>
<th>Standard</th>
<th>Max.</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1014</td>
<td>Activates V/f mode</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>PO</td>
</tr>
<tr>
<td></td>
<td>... V/Hz operation for this drive is activated/de-activated.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 1 V/Hz operation is activated</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>= 0 V/Hz operation is de-activated</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1125</td>
<td>Ramp-up time 1 for V/Hz operation</td>
<td>0.01</td>
<td>5.0</td>
<td>100.0</td>
<td>s</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>When V/Hz operation is activated, this is the time in which the speed setpoint is changed from 0 to the maximum motor speed (P1146).</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1127</td>
<td>Voltage at f = 0 V/Hz operation (ARM)</td>
<td>0.0</td>
<td>2.0</td>
<td>20.0</td>
<td>V(pk)</td>
<td>immediately</td>
</tr>
<tr>
<td></td>
<td>When V/Hz operation is activated, and at 0 frequency, the voltage which is output is increased by the value in this parameter.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The parameter is preset when carrying-out the &quot;calculate controller data&quot; function.</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

7.6 Spare parts

Table 7-11 Terminals for SIMODRIVE 611 universal

<table>
<thead>
<tr>
<th>Designation</th>
<th>Terminal</th>
<th>Item number</th>
<th>Order No. [MLFB]</th>
</tr>
</thead>
<tbody>
<tr>
<td>X421</td>
<td>AS1, AS2</td>
<td>GWE-000000590513</td>
<td>6SY9907</td>
</tr>
<tr>
<td>X431</td>
<td>P24, M24,9 663,19</td>
<td>GWE-000000588343</td>
<td>6SY9908</td>
</tr>
<tr>
<td>X451, X452</td>
<td>56.x, 14.x, 24.x, 20.x, ...</td>
<td>GWE-000000588293</td>
<td>6SY9910</td>
</tr>
<tr>
<td>X461, X462 (10 pin)</td>
<td>A+.x, A-.x, B+.x, B-.x</td>
<td></td>
<td>6SY9913</td>
</tr>
<tr>
<td>X461, X462 (11 pin)</td>
<td>A+.x, A-.x, B+.x, B-.x</td>
<td>A5E0009717</td>
<td>6SY9913</td>
</tr>
<tr>
<td>X453, X454</td>
<td>A+.x, A-.x, B+.x, B-.x</td>
<td></td>
<td>6SY9911</td>
</tr>
<tr>
<td>X441</td>
<td>75.x, 16.x, 15</td>
<td>GWE-000000588277</td>
<td>6SY9912</td>
</tr>
<tr>
<td>X422, X432</td>
<td>14...11, 04...011</td>
<td>GWE-000000588285</td>
<td>6SY9904</td>
</tr>
<tr>
<td>Power connector, motor connection</td>
<td></td>
<td></td>
<td>6SY9905s</td>
</tr>
<tr>
<td>Power connector, pulsed resistor</td>
<td></td>
<td></td>
<td>6SY9905s</td>
</tr>
</tbody>
</table>
Space for your notes
## Lists

<table>
<thead>
<tr>
<th>Section</th>
<th>Description</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>A.1</td>
<td>Parameter list</td>
<td>A-780</td>
</tr>
<tr>
<td>A.2</td>
<td>Power module list</td>
<td>A-922</td>
</tr>
<tr>
<td>A.3</td>
<td>List of motors</td>
<td>A-925</td>
</tr>
<tr>
<td>A.3.1</td>
<td>List of the rotating synchronous motors</td>
<td>A-925</td>
</tr>
<tr>
<td>A.3.2</td>
<td>List of permanent-magnet synchronous motors with field weakening (1FE1, 2SP1, PE spindle)</td>
<td>A-935</td>
</tr>
<tr>
<td>A.3.3</td>
<td>List of permanent-magnet synchronous motors without field weakening, built-in torque motors (1FW6, from SW 6.1)</td>
<td>A-942</td>
</tr>
<tr>
<td>A.3.4</td>
<td>List of linear synchronous motors</td>
<td>A-946</td>
</tr>
<tr>
<td>A.3.5</td>
<td>List of induction motors</td>
<td>A-952</td>
</tr>
<tr>
<td>A.4</td>
<td>Encoder list</td>
<td>A-962</td>
</tr>
<tr>
<td>A.4.1</td>
<td>Encoder code</td>
<td>A-965</td>
</tr>
<tr>
<td>A.4.2</td>
<td>Encoder adaptation</td>
<td>A-965</td>
</tr>
</tbody>
</table>
A.1 Parameter list

Reader's note

The parameters listed in the following are valid for all of the software releases of "SIMODRIVE 611 universal".

The complete list is updated corresponding to the edition of this documentation (refer to the edition in the header lines) and corresponds here to the documented software releases of "SIMODRIVE 611 universal".

The parameters are designated depending on the particular software release.

General information on the parameter list

The parameters are listed as follows:

<table>
<thead>
<tr>
<th>Significance of the parameter numbers (examples)</th>
<th>Valid for ... motors</th>
</tr>
</thead>
<tbody>
<tr>
<td>(refer under the index entry &quot;Parameters - ...)</td>
<td>none all</td>
</tr>
<tr>
<td>P1400 Parameter 1400 with sub-parameters</td>
<td>SRM rotating synchronous</td>
</tr>
<tr>
<td>P1401:8 Parameter 1401 with 8 sub-parameters</td>
<td>ARM rotating induction</td>
</tr>
<tr>
<td>P0081:64 Parameter 0081 with 64 sub-parameters</td>
<td>SLM synchronous linear</td>
</tr>
</tbody>
</table>

Software release
- no data: ...
  available from SW 2.1
- e.g.: -> 2.4 :
  ...
  available from SW 2.4

Units
- MSR: Dimension system grid
  1 MSR = 0.001 mm for P0100 = 1
  1 MSR = 0.0001 inch for P0100 = 2
  1 MSR = 0.001 degrees for P0100 = 3
- \( c \times MSR \)
  \( c = 1: \) for a dimension system mm or inch
  \( c = 10: \) for a dimension system, degrees

Example:
- P0082:64 = 50 000 \([c*MSR/min]\)
- Dimens. system Significance
  - mm 50 mm/min
  - inch 5 inch/min
  - degrees 500 degrees/min

Fig. A-1 Parameter list

Information on effective
In order that a parameter "immediately" becomes effective after a change, it may be necessary to execute the associated function (e.g. P0160 (reference point coordinates) a reference point approach must be carried out).
The following parameters are available for the “SIMODRIVE 611 universal” control board:

**Version**: 13.01.02

### 0001 Actual traversing block – block number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Integer16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode and for the "spindle positioning" function it specifies the block number of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0080:256

### 0002 Actual traversing block – position

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>MSR</td>
<td>Integer32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode and for the "spindle positioning" function it specifies the programmed position of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0081:256

### 0003 Actual traversing block – velocity

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode and for the "spindle positioning" function it specifies the programmed velocity of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0082:256

### 0004 Actual traversing block – acceleration override

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode and for the "spindle positioning" function it specifies the programmed acceleration override of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0083:256

### 0005 Actual traversing block – deceleration override

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode and for the "spindle positioning" function it specifies the programmed deceleration override of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0084:256

### 0006 Actual traversing block – command

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode specifies the programmed command of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0085:256

### 0007 Actual traversing block – command parameter

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... in the "Positioning" mode specifies the programmed command parameter of the traversing block being processed.

Note: Refer under the index entry "traversing blocks" or for P0086:256
A.1 Parameter list

0008  Actual traversing block - mode
Min  Standard  Max  Unit  Data type  Effective
-  -  -  Hex  Unsigned16  RO
... in the "Positioning" mode and for the "Spindle positioning" function it specifies the pro-
grammed mode of the traversing block being processed.
Note: Refer under the index entry "traversing blocks" or for P0087:256

0020  Position setpoint
Min  Standard  Max  Unit  Data type  Effective
-  -  -  MSR  Integer32  RO
... in the "positioning" mode and for the "Spindle positioning" function, displays the actual abso-
lute reference position.

0021  Position actual value
Min  Standard  Max  Unit  Data type  Effective
-  -  -  MSR  Integer32  RO
... in the "positioning" mode and for the "Spindle positioning" function, displays the actual
system deviation (reference value - actual difference) at the absolute actual position.

0022  Distance to go
Min  Standard  Max  Unit  Data type  Effective
-  -  -  MSR  Integer32  RO
... indicates the distance to go in the operating mode "positioning" and for the function "spindle
positioning".
The distance to go is the difference up to the end of the actual traversing block (P0001).

0023  Velocity setpoint
Min  Standard  Max  Unit  Data type  Effective
-  -  -  c*MSR/min  Integer32  RO
... in the "positioning" mode and for the "Spindle positioning" function, displays the actual
system deviation (reference value - actual difference) at the actual setpoint - traversing veloc-
ity.

0024  Actual velocity
Min  Standard  Max  Unit  Data type  Effective
-  -  -  c*MSR/min  Integer32  RO
... in the "positioning" mode and for the "Spindle positioning" function, displays the actual tra-
versing velocity.

0025  Effective override
Min  Standard  Max  Unit  Data type  Effective
-  -  -  %  Floating Point  RO
... in the "Positioning" mode displays the actual, effective velocity override.
Note:
The currently effective override can differ from the specified override due to limits (e. g. P0102
(maximum velocity)).
0026  Position actual value, external block change  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>MSR</td>
<td>Integer32</td>
</tr>
</tbody>
</table>

... displays, in the "Positioning" mode, the position actual value displayed when an edge is detected at the "External block change" input signal.

Note:
The parameter is reset when starting a traversing block with the block change enable CONTINUE EXTERNAL.
refer to the index entry "block step enable -- CONTINUE EXTERNAL"

0029  Following error

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>MSR</td>
<td>Integer32</td>
</tr>
</tbody>
</table>

... in the "positioning" mode and for the "Spindle positioning" function, displays the actual following error.

The following error is the difference between the position setpoint (before the position setpoint filter, interpolator output) and the position actual value.

Note: refer to the index entry "Kv factor" or "Analog signals for the position control loop"

0030  Control deviation, position controller input

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>MSR</td>
<td>Integer32</td>
</tr>
</tbody>
</table>

... in the "positioning" mode and for the "Spindle positioning" function, displays the actual system deviation (reference value - actual difference) at the position controller input.

Note: refer to the index entry "Kv factor" or "Analog signals for the position control loop"

0031  Actual Kv factor (position loop gain)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>1000/min</td>
<td>Floating Point</td>
</tr>
</tbody>
</table>

... in the "positioning" mode and for the "Spindle positioning" function, displays the actually available (measured) Kv factor.

Example:
A Kv factor = 1 is set in P0200:8.
When traversing the axis, the current (measured) Kv factor is calculated and displayed in this parameter.

Note:
The actual Kv factor display (P0031) can have large values at low velocities due to the rounding-off errors.
At standstill, the selected (required) Kv factor (P0200:8) is displayed.

0032  Position reference value, external  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>MSR</td>
<td>Integer32</td>
</tr>
</tbody>
</table>

... displays the externally entered position reference value.

Note:
The quantities of P0895 to P0897 are incorporated in P0032.
refer under the index entry "axis couplings"
### A.1 Parameter list

**0079 Reformat memory**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>0</td>
<td>0</td>
<td>1</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the memory can be reformatted for the traversing blocks, i.e. re-segmented.

0 inactive, initial status
0 -> 1 Re-format memory is initiated

Advantages of a re-formatted memory:

When displaying the blocks via SimoCom U or via the display unit on the front panel, the blocks are located at the beginning of the memory, are sorted according to increasing block numbers, and there are no gaps.

Note:
The parameter is automatically reset to 0 when reformating has been completed.

**0080:256 Block number**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>-1</td>
<td>-1</td>
<td>255</td>
<td></td>
<td>Integer16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

A traversing block must be assigned a valid block number, so that it can be started.

-1 invalid block number
0 to 255 Valid block number

The block change enable (progress condition) itself is saved in the traversing block in P0087:256 (mode - block change enable).

Several blocks (e.g. for blocks with the block step enable CONTINUE FLYING) are processed in the increasing sequence of the block numbers.

The block number must be unique over all traversing blocks.

Note: refer to the index entry "Traversing blocks"

**0081:256 Position**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the target position in the traversing block.

The target position is approached dependent on P0087:256 (mode - positioning mode).

Note: refer to the index entry "Traversing blocks"

**0082:256 Velocity**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>6</td>
<td>60000</td>
<td>2000000000</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... defines the velocity, with which the target position is approached.

Note: refer to the index entry "Traversing blocks"

**0083:256 Acceleration override**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>1</td>
<td>100</td>
<td>100</td>
<td>%</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies which override has an effect on the maximum acceleration (P0103).

Note: refer to the index entry "Traversing blocks"

**0084:256 Deceleration override**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>1</td>
<td>100</td>
<td>100</td>
<td>%</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies which override has an effect on the maximum deceleration (P0104).

Note: refer to the index entry "Traversing blocks"
0085:256 Command

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>10</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

Each traversing block must contain precisely one command for execution.

Value command

1  POSITIONING
2  ENDLESSTRAVERSING_POS
3  ENDLESSTRAVERSING_NEG
4  WAIT
5  GOTO
6  SET_O
7  RESET_O
8  FIXED ENDSTOP (from SW 3.3 onwards)
9  COUPLING_ON (from SW 3.3)
10 COUPLING_OFF (from SW 3.3)

Depending on the command, additional block information is required in a traversing block.

Note:
refer to the index entry "Traversing blocks" or "Command-dependent block information"

0086:256 Command parameter

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>6535</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the supplementary block information required for the following commands.

Command Additional information

WAIT Waiting time in ms
GOTO Block number
SET_O 1, 2, 3: Set direct output 1, 2 or 3 (both signals)
RESET_O 1, 2, 3: Reset direct output 1, 2 or 3 (both signals)
FIXED ENDSTOP (from SW 3.3)

<table>
<thead>
<tr>
<th>Clamping torque or clamping force</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rotary drive: 1 - 65 535 [0.01 Nm]</td>
</tr>
<tr>
<td>Linear drive: 1 - 65 535 [N]</td>
</tr>
</tbody>
</table>

Note:
refer to the index entry "Traversing blocks" or "Command-dependent block information"
### A.1 Parameter list

#### 0087:256 Mode

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1331</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the following additional information for several commands.

P0087:256 = UVWX

- **U**
  - Bit 0 Target position source for spindle positioning (from SW 5.1)
    - = 0 Target position via traversing block (P0081)
    - = 1 Target position via PROFIBUS (STW XSP)
  - **V** block step enable function
    - = 0 END (standard)
    - = 1 CONTINUE WITH STOP
    - = 2 CONTINUE FLYING
    - = 3 CONTINUE EXTERNAL (from SW 3.1)
  - **W** Positioning mode
    - = 0 ABSOLUTE (standard)
    - = 1 RELATIVE
    - = 2 ABS_POS (only for modulo rotary axis, from SW 2.4)
    - = 3 ABS_NEG (only for modulo rotary axis, from SW 2.4)
  - **X** Identifications
    - = 1 suppress block

Note: refer to the index entry "Traversing blocks"

#### 0091 MDI position

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>Vsoet_0</td>
</tr>
</tbody>
</table>

... specifies the target position in the MDI traversing block.
The value, entered here, is used if the position is not entered as cycle process data (refer to P0915) via PROFIBUS.
The target position is approached dependent on P0097 (mode - positioning mode).

Note:
The parameter is not effective for Vset_0 if P0110 = 3 and P0097 = U3WX are set. The parameter becomes effective when the signal edge of the digital input signal "external block change" changes and if MDI is not entered via PROFIBUS-DP control words (STW).

refer under the index entry "traversing blocks"

#### 0092 MDI velocity

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td>3000</td>
<td>200000000</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>Vsoet_0</td>
</tr>
</tbody>
</table>

... defines the velocity with which the MDI target position is approached.
The value, entered here, is used if the velocity is not entered as cycle process data (refer to P0915) via PROFIBUS.

Note:
The parameter is not effective for Vset_0 if P0110 = 3 and P0097 = U3WX are set. The parameter becomes effective when the signal edge of the digital input signal "external block change" changes and if MDI is not entered via PROFIBUS-DP control words (STW).

refer under the index entry "traversing blocks"
0093 MDI acceleration override

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>100</td>
<td>100</td>
<td>%</td>
<td>Unsigned16</td>
<td>Vset_0</td>
</tr>
</tbody>
</table>

... specifies which override is effective for the MDI block at the maximum acceleration (P0103). The value, entered here, is used if the acceleration override is not entered as cycle process data (refer to P0915) via PROFIBUS.

Note:
The parameter is not effective for Vset_0 if P0110 = 3 and P0097 = U3WX are set. The parameter becomes effective when the signal edge of the digital input signal “external block change” changes and if MDI is not entered via PROFIBUS-DP control words (STW).

refer under the index entry “traversing blocks”

0094 MDI deceleration override

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>100</td>
<td>100</td>
<td>%</td>
<td>Unsigned16</td>
<td>Vset_0</td>
</tr>
</tbody>
</table>

... specifies which override is effective for the MDI block at the maximum deceleration (P0104). The value, entered here, is used if the acceleration override is not entered as cycle process data (refer to P0915) via PROFIBUS.

Note:
The parameter is not effective for Vset_0 if P0110 = 3 and P0097 = U3WX are set. The parameter becomes effective when the signal edge of the digital input signal “external block change” changes and if MDI is not entered via PROFIBUS-DP control words (STW).

refer under the index entry “traversing blocks”

0097 MDI mode

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>310</td>
<td>330</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>Vset_0</td>
</tr>
</tbody>
</table>

... for several commands, for the MDI block it provides the following additional information.
P0097 = VMX

V block step enable function
- 0 END
- 3 CONTINUE EXTERNAL (Standard)

W Positioning mode
- 0 ABSOLUTE
- 1 RELATIVE (standard)
- 2 ABS_POS (only for modulo rotary axis)
- 3 ABS_NEG (only for modulo rotary axis)

X Identifications
not relevant

Note: refer to the index entry “Traversing blocks”

0100 Dimension system

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the measuring system grid pattern (MSR) which is being used.
1  --> 1 MSR = 1/1000 mm
2  --> 1 MSR = 1/10000 inch
3  --> 1 MSR = 1/1000 degrees

Example: P0100 = 1  -->  345123 MSR = 345.123 mm

Note: refer to the index entry "Dimension system"
0101 Actual dimension system

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the currently active measuring system.
If at POWER ON it is identified that P0100 is not equal to P0101, then a measuring system changeover is automatically executed.
Note: refer to the index entry "Dimension system"

0102 Maximum motor velocity

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>30000000</td>
<td>20000000000</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the maximum traversing velocity of the axis, in the mode "Positioning" and "n-set, when selecting spindle positioning"
Note: Refer under the index entry "Closed-loop position control" and "Spindle positioning "

0103 Maximum acceleration

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>100</td>
<td>999999</td>
<td>1000MSR/s²</td>
<td>Unsigned32</td>
<td>Vsoet_0</td>
</tr>
</tbody>
</table>

... defines the maximum acceleration on the axis/spindle when approaching.
The effective acceleration can be programmed in the traversing block using an override (P0083:256).
Note: refer to the index entry "Position control"

0104 Maximum deceleration

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>100</td>
<td>999999</td>
<td>1000MSR/s²</td>
<td>Unsigned32</td>
<td>Vsoet_0</td>
</tr>
</tbody>
</table>

... defines the maximum deceleration on the axis/spindle when braking.
The effective deceleration can be programmed in the traversing block using an override (P0084:256).
Note: refer to the index entry "Position control"

0107 Jerk limiting

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>100000000</td>
<td>1000MSR/s²</td>
<td>Unsigned32</td>
<td>Vsoet_0</td>
</tr>
</tbody>
</table>

... defines an increase (jerk) in the form of a ramp for acceleration and deceleration, so that approach and deceleration are "smooth" (jerk-limited).
The duration of the acceleration ramp (jerk time) is calculated from the higher value of maximum acceleration (P0103) resp. maximum deceleration (P0104) and the jerk limitation set (P0107).
0 jerk limiting off
> 0 jerk limiting on, the set value is effective
Note:
- The calculated jerk time which is currently effective is displayed in P1726 (calculated jerk time).
- The jerk time is limited internally to 200 ms.
- refer to the index entry "jerk limitation"

0108 Velocity setpoint jog 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-2000000000</td>
<td>-300000</td>
<td>20000000000</td>
<td>c*MSR/min</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines which setpoint is used for jogging 1.
Note: refer to the input signal "Jog 1 ON/Jog 1 OFF"
0109 Velocity setpoint jog 2

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>2000000000000</td>
<td>300000</td>
<td>2000000000000</td>
<td>c*MSR/min</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines which setpoint is used for jogging 2.
Note: refer to the input signal "Jog 2 ON/Jog 2 OFF"

0110 Configuration, external block change

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... defines the behavior of the "external block change".

0
If the signal is not available up to start of braking, then the axis stops in front of the target position and a fault is output (standard).
1
If the signal is not available up to the start of braking, then a flying block change is executed.
2
A signal is only expected at the end of block, and a block change is only made after this has been identified.
3
If the signal is not present up to the end of the block, then the system waits for the signal and when this is identified, the block is changed (from SW 5.1).

Note:
A change made to P0110 is not accepted after v_set=0, but only at the end of the program when the traversing program is restarted.
refer to the index entry "block step enable - CONTINUE EXTERNAL"

0111 Normalization voltage, override

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>5.0</td>
<td>10.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines at which input voltage at terminal 56.x/14.x, the override in P0112 is reached.
Prerequisite:
- position setpoint interface (P0700 = 2) or positioning (P0700 = 3) selected
- P0607 = 2 (override)
Example:
P0111 = 10, P0112 = 100 --> for 10 V at terminal 56.x/14.x, the override is 100 percent
Note: refer to the index entry "Override"

0112 Normalization of override

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>0</td>
<td>100</td>
<td>255</td>
<td>%</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines at which override is reached when connecting the voltage in P0111 at terminal 56.x/14.x.
Prerequisite:
- position setpoint interface (P0700 = 2) or positioning (P0700 = 3) selected
- P0607 = 2 (override)
Example:
P0111 = 10, P0112 = 100 --> for 10 V at terminal 56.x/14.x, the override is 100 percent
Note: refer to the index entry "Override"
### 0113 Fixed endstop, configuration 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the behavior for fixed end stop/clamping torque not reached.

- **Bit 0** Behavior for fixed end stop not reached
  - **Bit 0 = 1** Block change is executed
    - The torque limiting is automatically withdrawn. The block step enable is realized as programmed in the block.
  - **Bit 0 = 0** Fault 145 is signaled
    - The axis is braked and stops in front of the programmed target position.

- **Bit 1** Characteristics for the clamping torque not reached
  - **Bit 1 = 1** Warning 889 is signaled and a block change executed
    - The block step enable is realized as programmed in the block.
  - **Bit 1 = 0** Warning 889 is signaled
    - The block step enable changes as programmed in the block only when the clamping torque has been reached.

**Note:**
- Fault 145 (fixed endstop not reached)
- Warning 889 (fixed endstop, axis has not reached the clamping torque)

Refer to the index entry "Travel to endstop"

### 0114 Fixed endstop, configuration 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines how the system can switch into the status "fixed endstop".

- **0** above following error
  - The status is automatically reached if the following error exceeds the value set in P0115:8.
- **1** via input signal
  - The status is only reached, if it is identified via the input signal "Fixed endstop sensor".

**Note:**
- Refer to the index entry "Travel to endstop"

### 0115:8 Fixed endstop, maximum following error

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1000</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines at which following error the "fixed endstop reached" status is recognized.

The "fixed endstop reached" status is automatically reached, if the following error exceeds the theoretically calculated following error by the value entered in P0115:8.

**Note:**
- Prerequisite: P0114 = 0
- Refer to the index entry "Travel to endstop"

### 0116:8 Fixed endstop, monitoring window

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>100</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... Defines the monitoring window for the "fixed endstop reached" status. If the axis exits the positioning window an appropriate fault is signaled.

**Note:**
- Refer to the index entry "Travel to endstop"
0117 Tolerance window actual velocity (11.1)

Min | Standard | Max | Unit | Data type | Effective
--- | --- | --- | --- | --- | ---
1 | 5 | 100 | % | Unsigned16 | immed.

... defines the tolerance window for the output signal "programmable velocity reached".

Note:
Refer under output signal "programmed velocity reached"

0118 Software limit switch configuration (4.1)

Min | Standard | Max | Unit | Data type | Effective
--- | --- | --- | --- | --- | ---
0 | 0 | 1 | - | Unsigned16 | immed.

... defines which fault/warning is signaled if the axis comes to a standstill precisely at the software limit switch.

Bit 0 Behavior for software limit switch reached
Bit 0 = 1 Software limit switch reached with warning 849/850
Move away jogging in the opposite direction or via a traversing block
Bit 0 = 0 Software limit switch reached with fault 119/120
Move away in the opposite direction jogging, and acknowledge the fault.

0120 Teach-in block (4.1)

Min | Standard | Max | Unit | Data type | Effective
--- | --- | --- | --- | --- | ---
-1 | -1 | 255 | - | Integer16 | immed.

... specifies whether the block number for the teach in block is entered via input signals or via P0120.

-1 Enter a block number via input signals
0 to 255 Block number entered via P0120

Note:
refer under the index entry "Teach-in"

0121 Teach-in standard block (4.1)

Min | Standard | Max | Unit | Data type | Effective
--- | --- | --- | --- | --- | ---
-1 | -1 | 255 | - | Integer16 | immed.

... specifies which traversing block is used as teach in in the standard block
The standard block contains additional block data, which are not contained for teach-in.

-1 Not a standard block
Only the position value is transferred into the teach-in block.
0 bis 255 Standard block
This block is transferred into the teach-in block and the position value overwritten.

Note:
refer under the index entry "Teach-in"

0122 Jogging 1 increments (4.1)

Min | Standard | Max | Unit | Data type | Effective
--- | --- | --- | --- | --- | ---
0 | 1000 | 200000000 | MSR | Integer32 | immed.

... specifies the number of increments traversed for incremental jogging 1.

Note:
refer under the index entry "Jogging -- incremental"

0123 Jogging 2 increments (4.1)

Min | Standard | Max | Unit | Data type | Effective
--- | --- | --- | --- | --- | ---
0 | 1000 | 200000000 | MSR | Integer32 | immed.

... specifies the number of increments traversed for incremental jogging 2.

Note:
refer under the index entry "Jogging -- incremental"
A_1 Parameter list

0124 Teach-in configuration

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies in which mode teach in is executed.

Bit 0 Automatic block change enable
In this mode, after each successful "teach-in", the teach-in block in P0120 is automatically increased.

Bit 0 = 1 On
Bit 0 = 0 Off

Bit 1 Automatic block search
In this mode at "teach-in" a search is made for the block in P0120.

Bit 1 = 1 On
The block, entered in P0120 or the block selected via the input signals, is re-generated.
Bit 1 = 0 Off
A fault is initiated if the block in P0120 or the block selected via the input signals is not available.

Note:
refer under the index entry "Teach-in"

0125 Spindle positioning active

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... switches the "spindle positioning" function into the mode "n-set" on/off.

0 De-activate spindle positioning
1 Activate spindle positioning

Note:
refer under the index entry "Spindle positioning"

0126 Spindle positioning, zero mark tolerance window (BERO)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>7200</td>
<td>360000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the zero tolerance window in degrees, which is monitored by the spindle positioning, in order to secure, in conjunction with a BERO, the zero mark consistency. If the zero mark is not recognized, or if uneven zero mark clearances are measured which are outside the tolerance, then alarm message 186 or 193 is output, e.g. if the encoder cable is, for example, interrupted.

0 De-activate zero mark monitoring
>0 Zero mark monitoring is activated

Note:
refer under the index entry "Spindle positioning"

0127 Spindle positioning, setting the internal zero mark

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

By setting bit 0 to 1, the zero mark offset to the hardware zero mark is entered into P0128. After this, 0 is written back into P0127.

Note:
refer under the index entry "Spindle positioning"
0128  Spindle positioning offset, zero  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-2147483647</td>
<td>0</td>
<td>2147483647</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Difference to the hardware zero mark is entered and displayed in degrees

0129  Spindle positioning, tolerance search velocity  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>10000000</td>
<td>2147483647</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

This means that a tolerance in degrees/min (+/-) is specified, which must be reached in order to synchronize or to change-over to closed-loop position control

Note:
refer under the index entry “Spindle positioning”

0130  Spindle positioning, lowest search velocity  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>100</td>
<td>100</td>
<td>%</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... is used to enter a percentage value referred to the specified minimum search velocity (P0082), which must be reached, so that the spindle can be positioned.

Note:
refer under the index entry “Spindle positioning”

0131  Spindle positioning, motion window  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2000</td>
<td>2000000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If, when the controller is inhibited, the spindle is pushed out of this tolerance window in Degrees, the position actual value is corrected/tracked. If the controller is then re-enabled, the spindle remains stationary at that position. A new positioning operation is only executed if “spindle positioning” is activated (as defined in the traversing block). If the spindle remains in the motion window, then positioning is executed through the shortest path as soon as only the controller enable is re-set again.

Note:
refer under the index entry “Spindle positioning”

0132  Spindle positioning, zero mark difference (BERO)  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>MSR</td>
<td>Integer32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates the clearance between two consecutive BERO zero marks in degrees.

Note:
refer under the index entry “Spindle positioning”

0133  Spindle positioning, max. search velocity  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>36000000</td>
<td>2147483647</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the maximum reference velocity in degrees/min.

Note:
refer under the index entry “Spindle positioning”
### 0134 Spindle positioning, positioning window reached

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2000</td>
<td>20000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

...defines the tolerance range in degrees for the "Spindle position reached" output signal (Fct. No. 59 or PROFIBUS-DP MeldW.15). The position reference value is compared with the position actual value.

Note:
refer under the index entry "Spindle positioning"

### 0136 Spindle positioning active/inactive

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

...indicates whether the "spindle positioning" function is active or inactive.

0 Spindle positioning is not active
1 Spindle positioning is active

Note:
refer under the index entry "Spindle positioning"

### 0137 Spindle positioning status

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

...indicates the actual status for spindle positioning.

0 Spindle positioning is not activated
1 Status after the spindle positioning command
2 reserved
3 Approach to search velocity, if necessary, the zero mark is searched for
4 Position controller is switched-in
5 Positioning starts
6 Target position is reached
7 Pulse inhibit

Note:
refer under the index entry "Spindle positioning"

### 0160 Reference point coordinate

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>20000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

...specifies the position value which is set as the actual axis position after referencing or adjustment.

Note:
The range for an absolute value encoder is limited to +/-2048 revolutions. The value which was entered into P0160, is limited to this value and after POWER ON is overwritten with another value (remainder of division by 2048).

refer under the index entry "Referencing/adjusting"

### 0161 Stopping at marks

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

...defines the behavior when stopping at marks.

0 The reference point approach (homing) is not interrupted at marks (standard).
1 The reference point approach (homing) remains stationary if the first or, for distance-coded measuring systems, the second zero mark was found.
0162   Reference point offset

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-20000000</td>
<td>-2000</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

For incremental measuring systems, after the reference zero pulse has been detected, the axis is moved through this distance. At this position the axis has reached the reference point and accepts the reference points coordinates (P0160) as new actual value.

Note: refer to the index entry "Reference point approach"

0163   Reference point approach velocity

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>500000</td>
<td>200000000</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

The axes moves with this velocity after starting reference point approach, towards the reference cam.

The velocity must be set, so that after the reference cam has been reached, and subsequent braking, the following conditions are fulfilled:
- the axis must come to a standstill direct at the reference cam
- when braking it is not permissable that the HW limit switch is reached

Note: refer to the index entry "Reference point approach"

0164   Reference point creep speed

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>300000</td>
<td>200000000</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

Between identifying the reference cam and synchronization with the first zero pulse, the axis moves with this velocity (zero reference pulse).

Note: refer to the index entry "Reference point approach"

0165   Reference point entry velocity

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>300000</td>
<td>200000000</td>
<td>c*MSR/min</td>
<td>Unsigned32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

Between synchronizing with the first zero pulse (zero reference pulse) and reaching the reference point, the axis moves with this velocity.

Note: refer to the index entry "Reference point approach"

0166   Reference cam approach direction

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... defines in which direction the reference cam (for axes with reference cams, P0173 = 0) or the zero pulse (for axes without reference cams, P0173 = 1) is approached/searched.

1   Negative direction

0   Positive direction

Note: refer to the index entry "Reference point approach"

0167   Invert, reference cams

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the switching characteristics of the reference cam signal (input terminal with function number 78) is adapted.

1   Inverted

0   Not inverted

Note: refer to the index entry "Reference point approach" and "Invert reference cam signal"
0170 Maximum distance to the reference cam

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1000000</td>
<td>200000000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the max. distance the axis can travel from starting the reference point approach in order to find the reference cam.

Note: refer to the index entry "Reference point approach"

0171 Max. distance up to the zero pulse

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>200000000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... specifies the maximum distance that the axis can traverse from leaving the reference (homing) cam or from the start, in order to find the zero pulse.

Note:
For distance-coded measuring system (from SW 8.3):
The maximum permissible distance between the start and up to the 2nd zero pulse. Recommended setting: Select the basic distance (clearance) between two fixed reference marks.
Refer under the index entry "Reference point approach"

0172 Distance up to the zero pulse

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... the distance moved from leaving the reference cam or from the start up to reaching the zero pulse is entered.

The parameter supports, at start-up, reference cam adjustments.

Note: refer to the index entry "Reference point approach" and "Reference cam adjustment"

0173 Reference point approach without reference cams

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

0 reference cam available
1 no reference cam available

Note: refer to the index entry "Reference point approach"

0174 Referencing mode, position measuring system

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

1 Incremental measuring system available
2 Incremental measuring system with equivalent zero mark available (e. g. BERO at input terminal I0.x)

Note: refer to the index entry "Referencing/adjustment"

0175 Adjustment status - absolute position measuring system

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... displays the status when adjusting the absolute value encoder.

-1 error occurred when adjusting
0 Absolute value encoder is not adjusted (pre-setting at the first start-up)
1 Absolute value encoder has not yet been adjusted (encoder adjustment has been initiated)
2 Absolute encoder is adjusted (before SW 3.1)
3 Absolute value encoder IM is adjusted (from SW 3.1)
4 Absolute encoder DM is adjusted (from SW 3.3)

Note: refer to the index entry "Adjusting the absolute value encoder"
0179 mode, passive referencing

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the mode for passive referencing.
0 Accept reference point coordinate (P0160)
1 Initiate start-up help for passive referencing
2 Value after initiating the start-up help
Move through the offset (P0162) and accept the reference point coordinate (P0160)

Note:
For a rigid mechanical coupling between the master and slave axis, it is not permissible that P0179 is set to 2 if the slave drive is equipped with an absolute value encoder. Otherwise, the slave drive would move to an absolute position as specified in P0160.
refer to the index entry "Passive referencing"

0200:8 Kv factor (position loop gain)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>1.0</td>
<td>300.0</td>
<td>1000/min</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines at which traversing velocity of the axis/spindle which following error is obtained.

Kv factor significance
Low: Slow response to a setpoint-actual value difference, following error is high
High: Fast response to a setpoint-actual value difference, following error is low

Note:
The following diagnostic parameters are available:
- P0029 (following error)
- P0030 (system deviation, position controller input)
- P0031 (actual Kv factor (position loop gain))
refer to the index entry "Kv factor" or "Diagnostics of the motion status"

0201 backlash compensation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-20000</td>
<td>0</td>
<td>20000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... switches the backlash compensation in/out and defines the backlash amount for a positive or negative backlash.
0 backlash compensation is disabled
> 0 positive backlash (normal case)
< 0 negative backlash

Note: refer to the index entry "Backlash compensation"

0203 speed feedforward control mode

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

1 speed feedforward control active
0 feedforward control inactive

Note: refer to the index entry "speed feedforward control"

0204:8 speed feedforward control factor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the additionally entered speed setpoint is weighted.
If the axis control loop has been optimally set, and the equivalent time constant of the speed control loop (P0205, P0206) has been precisely determined, the pre-control factor is 100%.
Note: refer to the index entry "speed feedforward control"
0205:8  Balancing filter, speed feedforward control (deadtime)
Min  Standard  Max  Unit  Data type  Effective
0.0  0.0  10.0  ms  FloatingPoint  immed.
... allows the time behavior of the closed speed control loop to be emulated with a dead time.
The entered value is limited to two position controller cycles (P1009).
Note: refer to the index entry "speed feedforward control"

0206:8  Balancing filter, speed feedforward control (PT1)
Min  Standard  Max  Unit  Data type  Effective
0.0  0.0  100.0  ms  FloatingPoint  immed.
... permits, in addition to P0205:8, the closed speed control loop to be simulated using a PT1
filter (low pass).
Note: refer to the index entry "speed feedforward control"

0210:8  Time constant, position setpoint filter
Min  Standard  Max  Unit  Data type  Effective
0.0  0.0  1000.0  ms  FloatingPoint  immed.
... is the time constant of the PT1 position setpoint filter.
The effective Kv factor (position loop gain) can be reduced using the filter.
Note: refer to the index entry "speed feedforward control"

0231  Position actual value inversion
Min  Standard  Max  Unit  Data type  Effective
0  0  1  -- Unsigned16  PO
... the control sense of the position controller is established.
1  position actual value inversion
0  no position actual value inversion
If the position controller control sense is not OK, then the position actual value must be in-
verted.
The direction of motion is set using P0232 (position setpoint inversion)
Note: refer to the index entry "Direction adaptation"

0232  Position setpoint inversion
Min  Standard  Max  Unit  Data type  Effective
0  0  1  -- Unsigned16  PO
... the required motion direction is set.
1  position setpoint inversion
0  no position setpoint inversion
Note:
The control direction of the position controller remains unaffected, i.e. it is internally taken into
account (refer to the index entry "Direction adaptation").

0236  Spindle pitch (SRM ARM)
Min  Standard  Max  Unit  Data type  Effective
1  10000  8388607  MSR/rev  Unsigned32  PO  (SRM ARM)
Note: refer to the index entry "Encoder adaptation"

0237:8  Encoder revolutions (SRM ARM)
Min  Standard  Max  Unit  Data type  Effective
1  1  8388607  -  Unsigned32  PO  (SRM ARM)
... specifies the ratio (Ü) between the encoder and load.
T = P0237:8 / P0238:8
Note: refer to the index entry "Encoder adaptation"
### 0238:8 Load revolutions (SRM ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>8388607</td>
<td></td>
<td>Unsigned32</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

... specifies the ratio (Ü) between the encoder and load.

\[ T = \frac{P0237:8}{P0238:8} \]

Note: refer to the index entry "Encoder adaptation"

### 0239 Re-reference or re-adjust only if necessary

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td></td>
<td>Unsigned16</td>
<td>immed. (immediate)</td>
</tr>
</tbody>
</table>

0  
Referencing or adjustment is withdrawn when changing the parameter set (standard)

1  
Referencing or adjustment is only withdrawn when the parameter set is changed if the mechanical ratio (Ü = P0237:8 / P0238:8) changes.

Note: refer under the index entry "Referencing or adjustment"

### 0241 Activating, modulo conversion, rotary axis (SRM ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>MSR</td>
<td>Unsigned16</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

1  
modulo conversion activated, modulo correction is executed according to P0242

0  
modulo conversion de-activated

Note: refer to the index entry "rotary axis with modulo offset"

### 0242 Modulo range, rotary axis (SRM ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>360000</td>
<td>100000000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

... defines the modulo range of the rotary axis.

Practical modulo range values are: \(n \times 360\) degrees with \(n = 1, 2, \ldots\)

Note: refer to the index entry "rotary axis with modulo offset"

### 0250 Activate direct measuring system (SRM ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>MSR</td>
<td>Unsigned16</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

... the direct measuring system at X412 is activated/deactivated for drive A.

1  
Direct measuring system activated (only drive A)

0  
Direct measuring system deactivated

Note: refer to the index entry "Direct measuring system"

### 0310 Cam switching position 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed. (immediate)</td>
</tr>
</tbody>
</table>

... the cam switching position 1 is set.

Note: refer to the index entry "Position-related switching signals (cams)"

### 0311 Cam switching position 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed. (immediate)</td>
</tr>
</tbody>
</table>

... the cam switching position 2 is set.

Note: refer to the index entry "Position-related switching signals (cams)"
### 0314  Activating software limit switch

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

1  software limit switch active
0  software limit switch inactive (e.g. necessary for a rotary axes)

Note:
With P0314=0, for a linear axis, the software limit switch monitoring remains active. Only the limits are set to +-200000000.

### 0315  Minus software limit switch

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>-200000000</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... the position for the software limit switch is set to minus.

Note:
P0315 (minus software limit switch) < P0316 (plus software limit switch)

### 0316  Plus software limit switch

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>200000000</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>PrgE</td>
</tr>
</tbody>
</table>

... the position for the software limit switch is set to plus.

Note:
P0315 (minus software limit switch) < P0316 (plus software limit switch)

### 0318:8  Dynamic following error monitoring tolerance

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1000</td>
<td>200000000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the maximum deviation between the measured and the calculated position actual value before an error is output.

>= 1  The dynamic following error monitoring is active with this value
0  Monitoring is de-activated

Note: refer to the index entry "Dynamic following error monitoring"

### 0320  Position monitoring time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1000</td>
<td>100000</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the time after which the following error must be within the positioning window (P0321).

Note: refer to the index entry "Positioning monitoring"

### 0321  Positioning window

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>40</td>
<td>20000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the positioning window, within which the position actual value must be located after the position monitoring time has expired (P0320).

>= 1  The position monitoring is active with this value
0  Monitoring is de-activated

Note: refer to the index entry "Positioning monitoring"

### 0325  Standstill monitoring time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>400</td>
<td>1000000</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the time after which the following error must be within the standstill window (P0326).

Note: refer to the index entry "Standstill monitoring"
0326 Standstill window

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>200</td>
<td>20000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the standstill window, in which the position actual value must be after the standstill monitoring time has expired (P0325).

>= 1 The standstill monitoring is active with this value

0 Monitoring is de-activated

Note: refer to the index entry "Standstill monitoring"

0338 Fault response, illegal input signals

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>2</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the fault response which is initiated for an illegal combination of input signals.

Example: When starting a traversing block, the input signal "Operating conditions / reject traversing task" is not set.

0 No output

1 A warning is output

2 Fault 196 is output with the warning number as supplementary information

This involves signal combinations, which result in warnings 804,805,806,807,808,809,840,845.

0400 Reference point coordinates, master drive

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the reference point coordinates of the master drive.

0401 Coupling factor, master drive revolutions

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>8388607</td>
<td>-</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines the coupling factor between the master and slave drive.

0402 Coupling factor slave drive revolutions

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>8388607</td>
<td>-</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines the coupling factor between the master and slave drive.
**0410 Configuration, coupling which can be switched-in**  
\( \rightarrow 3.3 \)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>8</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines the switch-on and type coupling.

1. Coupling via digital input signal, speed-synchronous
2. Coupling via digital input signal, position-synchronous + P0412
3. Coupling via traversing program, speed-synchronous
4. Coupling via traversing program, position-synchronous + P0412
5. Coupling via traversing program with queue functionality speed-synchronous (being prepared)
6. Coupling via traversing program with queue functionality position synchronous + P0412 (being prepared)
7. Coupling via digital input signal to absolute position of the master drive + P0412 (from SW 4.1)
8. Coupling via traversing program to absolute position of the master drive + P0412 (from SW 4.1)

**Note:**
For P0410 = 7 or 8 it is necessary to communicate the absolute position P0400 of the master drive to the slave (following) drive using the input signal "Set setpoint master drive" refer under the index entry "axis couplings"

**0412 Synchronous offset position**  
\( \rightarrow 3.3 \)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines an offset between the slave drive and the synchronous position to the master drive.

**Note:**
If P0412 is changed, it becomes effective the next time that the coupling is switched-in.
refer under the index entry "axis couplings"

**0413 Offset, synchronous velocity**  
\( \rightarrow 3.3 \)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1000</td>
<td>30000000</td>
<td>2000000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines with which additional velocity the slave drive corrects the following error, built-up during the synchronization phase, and the synchronous offset position P0412.

**Note:**
refer under the index entry "axis couplings"

**0420 Pos. difference, meas. probe to the zero point, slave drive**  
\( \rightarrow 3.5 \)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200000000</td>
<td>0</td>
<td>200000000</td>
<td>MSR</td>
<td>Integer32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... for couplings with queue functionality, specifies the clearance between the measuring probe and the zero point of the slave drive.

**Note:**
refer under the index entry "axis couplings"
0425:16  Coupling positions  (-> 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>MSR</td>
<td>Integer32</td>
<td>RO</td>
</tr>
</tbody>
</table>

The following is valid for couplings without queue functionality:

The position of the master drive, at which the coupling was requested, is located in P0425:0.

For couplings with queue functionality (from SW 3.5) the following is valid:

The measured distances to the actual slave drive position are entered into P0425:16.

Note:
refer under the index entry "axis couplings"

0599  Active motor data set  (-> 2.4)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays whether the motor changeover has been enabled, and which motor data set is active.

0  Motor changeover inhibited (P1013 = 0)
1  Motor data set 1 (P1xxx) active
2  Motor data set 2 (P2xxx) active
3  Motor data set 3 (P3xxx) active
4  Motor data set 4 (P4xxx) active

Note: refer to the index entry "Motor changeover"

0600  Operating display

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the actual operating status of the unit.

Note:
refer to the index entry "Operating display" for the significance of the segments on the display unit.

0601  Motor speed setpoint (ARM SRM)
Velocity setpoint, motor (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>m/min</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>rpm</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is used to display the unfiltered summed setpoint for speed or velocity of the motor.

0602  Actual motor speed (ARM SRM)
Velocity actual value, motor (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>m/min</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>rpm</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is used to display the non-filtered actual value for the speed or velocity of the motor.

0603  Motor temperature

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>C</td>
<td>Integer16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the motor temperature measured using the temperature sensor.

Note:
The display is invalid if a fixed temperature was entered in P1608.
A.1 Parameter list

0604 Utilization, motor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

This parameter is used to display the utilization level of the motor. The ratio between "torque setpoint M" and "actual torque limit Mmax" or "force setpoint F" and "actual force limit Fmax" is displayed. Values of less than 100% indicate the system reserve.

Note:
The motor utilization display is smoothed using a PT1 filter (P1251).

0606 Voltage at term. 56.x/14.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

... displays the analog voltage presently available at this input terminal.

0607 Analog setpoint term. 56.x/14.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>2</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

... defines whether and how the analog setpoint is used at this analog input.

0       off
1   n-set/M-set operation (speed or torque setpoint interface, refer to Note)
2   override (position setpoint interface and positioning)

Note:
It is always possible to toggle between n-set/M-set operation using the "Open-loop torque controlled mode" input signal.
Analog setpoint for n-set/M-set --> refer to the index entry "Analog inputs"
Analog setpoint for velocity override --> refer to the index entry "Override"

0608 Inversion term. 56.x/14.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

An inversion inverts the polarity of the analog setpoint at this terminal internally.

0       Not inverted
1   Inverted

0609 Smoothing time, terminal 56.x/14.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>3.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

This allows the output value of the A/D converter to be smoothed using a PT1 filter.

0610 Drift/offset correction term. 56.x/14.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-9999.9</td>
<td>0.0</td>
<td>9999.9</td>
<td>mV(pk)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If the motor erroneously rotates when a speed setpoint of 0 V is entered, a voltage offset can be applied to set the analog input to zero using this parameter.

0611 Voltage at term. 24.x/20.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

... displays the analog voltage presently available at this input terminal.
0612  Analog setpoint term. 24.x/20.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines whether and how the analog setpoint is used at this analog input.

0  off
1  n-set/M-set operation (refer to Note)
2  M-red operation
3  Equalization controller operation

Note:
It is always possible to toggle between n-set/M-set operation using the “Open-loop torque controlled mode” input signal.
Analog setpoint for n-set/M-set/M-red --> refer to the index entry “Analog inputs”
Analog setpoint for velocity override --> refer to the index entry “Override”

0613  Inversion term. 24.x/20.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

An inversion inverts the polarity of the analog setpoint at this terminal internally.
1  Inverted
0  Not inverted

0614  Smoothing time, terminal 24.x/20.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>3.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

This allows the output value of the A/D converter to be smoothed using a PT1 filter.

0615  Drift/offset correction term. 24.x/20.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-9999.9</td>
<td>0.0</td>
<td>9999.9</td>
<td>mV(pk)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If the motor erroneously rotates when a speed setpoint of 0 V is entered, a voltage offset can be applied to set the analog input to zero using this parameter.

0616:8  Ramp-function generator ramp-up time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

During ramp-up, the setpoint is increased from zero to the maximum permissible actual speed.
Note:
Max. permissible actual speed for synchronous motors: Minimum from 1.2 x P1400 and P1147
Max. permissible actual speed for induction motors: Minimum from P1146 and P1147
refer to the index entry “Ramp-function generator”
From SW 2.4, this parameter is replaced by P1256:8 (P0616:8 = P1256:8).

0617:8  Ramp-function generator ramp-down time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

During ramp-down, the setpoint is reduced from the maximum permissible actual speed to zero.
Note:
Max. permissible actual speed for synchronous motors: Minimum from 1.2 x P1400 and P1147
Max. permissible actual speed for induction motors: Minimum from P1146 and P1147
refer to the index entry “Ramp-function generator”
From SW 2.4 this parameter is replaced by P1257:8 (P0617:8 = P1257:8).
0618 Normalization voltage, speed setpoint

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>9.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

This defines at which input voltage at terminal 56.x/14.x and/or terminal 24.x/20.x, the maximum useful motor speed (P1401:8, dependent on the motor data set) is reached for closed-loop speed controlled operation.

Example:
SRM: P0618 = 9, P1401:8 = 2000 - at 9 V, the motor speed is 2000 RPM
SLM: P0618 = 9, P1401:8 = 120 - at 9 V, the motor velocity is 120 m/min

0619 Normalization voltage, torque setpoint (ARM SRM)
Normalization voltage, force setpoint (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>10.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

This defines at which input voltage at terminal 56.x/14.x and/or terminal 24.x/20.x for open-loop torque controlled operation, the normalization of the torque setpoint (P1241:8) is reached.

Example:
SRM: P0619 = 10, P1241:8 = 10 Nm - at 10 V, the torque is 10 Nm
SLM: P0619 = 10, P1241:8 = 1720 N - at 10 V, the force is 1720 N

0620 Normalization voltage, torque/power reduction. (ARM SRM)
Normalization voltage, force/power reduction (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>10.0</td>
<td>12.5</td>
<td>V(pk)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter defines at which input voltage of terminal 24.x/20.x, the normalization, torque reduction (P1243:8, motor data set-dependent) is reached.

0623 DAC normalization, actual speed (ARM SRM)
DAC normalization, motor actual velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200.0</td>
<td>100.0</td>
<td>200.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If signal number 34 (actual motor speed, finely normalized) is selected for the analog output, when the maximum speed is reached, the following voltage is output as a function of parameter P0623:
P0623 = 100% - 1.0 * 10 V = +10 V
P0623 = 50% - 0.5 * 10 V = +5 V

The following is valid for the maximum speed:
Max. permissible actual speed for synchronous motors: Minimum from 1.2 x P1400 and P1147
Max. permissible actual speed for induction motors: Minimum from P1146 and P1147

0624 DAC normalization, motor utilization

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-200.0</td>
<td>100.0</td>
<td>200.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If signal number 35 (utilization, finely-normalized) is selected for the analog output, then when the motor is utilized to 100%, the following voltage is output dependent on P0624:
P0624 = 100% - 1.0 * 10 V = +10 V
P0624 = 50% - 0.5 * 10 V = +5 V

Note:
Motor utilization --> refer to P0604
# A.1 Parameter list

## 0625 DAC normalization, torque setpoint (ARM SRM)

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0625</td>
<td>-200.0</td>
<td>100.0</td>
<td>200.0</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If the signal number 36 (torque setpoint, finely-normalized) is selected for the analog output, then at twice the rated torque, the following voltage is output dependent on P0625:

- P0625 = 100% -> +10 V
- P0625 = 50% -> +5 V

Note: Signal No. 36 is output signed.

## 0626 Signal number analog output term. 75.x/15

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0626</td>
<td>0</td>
<td>34</td>
<td>530</td>
<td>-</td>
<td>Unsigned16 immed.</td>
</tr>
</tbody>
</table>

... defines which signal is output via Terminal 75.x/15.

In this case the appropriate signal number must be entered from the "Signal selection list for analog output".

Note: refer to the index entry "Analog outputs"

## 0627 Shift factor analog output term. 75.x/15

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0627</td>
<td>0</td>
<td>47</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the shift factor, with which the analog signal is manipulated.

An 8 bit window of the 24/48 bit signal can be represented via the DAC. Thus, the shift factor must be used to define which window of the internal 24/48 bit is to be displayed.

Note: refer to the index entry "Analog outputs"

## 0628 Offset analog output term. 75.x/15

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0628</td>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies an offset for the 8-bit output signal.

Note: refer to the index entry "Analog outputs"

## 0629 Segment address analog output term. 75.x/15

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0629</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

## 0630 Offset address analog output term. 75.x/15

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0630</td>
<td>0</td>
<td>FFFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

## 0631 Bias protection, analog output, term. 75.x/15

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>P0631</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... switches the bias protection on or off.

1 bias protection on

The bits above the 8-bit window result in an output of +10 V or -10 V, i.e. the output cannot be over-modulated.

0 bias protection off

The bits above the 8-bit wide window are ignored.

The analog value is defined exclusively by the 8-bit value, i.e. the output can be overmodulated.

Note: refer to the index entry "Analog outputs"
### A.1 Parameter list

#### 0632 Smoothing time, analog output, terminal 75.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... smooths the output signal with a 1st order proportional element (PT1 element, low pass filter).

0.0 filter is inactive

Note: refer to the index entry "Analog outputs"

#### 0633 Signal number analog output term. 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>35</td>
<td>530</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the description of P0626 for terminal 75.x/15

#### 0634 Shift factor analog output term. 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>47</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the description of P0627 for terminal 75.x/15

#### 0635 Offset analog output term. 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the description of P0628 for terminal 75.x/15

#### 0636 Segment address analog output term. 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

#### 0637 Offset address analog output term. 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

#### 0638 Bias protection, analog output, term. 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the description of P0631 for terminal 75.x/15

#### 0639 Smoothing time, analog output, terminal 16.x/15

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the description of P0632 for terminal 75.x/15

#### 0641:16 Fixed speed setpoint (ARM SRM) Fixed velocity setpoint (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-100000.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>FloatingPoint</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>-100000.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>FloatingPoint</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

... is used to set the fixed speed setpoints 1 to 15. The required fixed setpoint is selected via the "fixed speed setpoint 1st to 4th input" input signals.

The following is valid:

P0641:0 no meaning
P0641:1 Fixed setpoint 1, selection via input signals
P0641:2 Fixed setpoint 2, selection via input signals, etc.
0649 Delete parameters, drives A and B  

(-> 3.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... all parameters (user data) can be erased in the memory module FEPROM. After the FEPROM has been erased, the control board is in the condition when it was originally supplied.

0 Standard value
1 All of the parameters are to be erased (establish the status when initially supplied)

Proceed as follows to delete all of the parameters:
- Disable pulse and controller enable (e.g. via terminal 663, 65.A and 65.B)
- Remove write protection (P0651 = 10 hex, only for operator control and display unit)
- Activate erasion of all parameters in the FEPROM (P0649 = 1)
- Starting writing into the FEPROM (P0652 = 1)
- Execute a HW POWER-ON RESET

After run-up, the board is set to the status when it was first supplied.

0651 Read and write protection

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>10</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

This defines which parameters can be read (visible) and which can be written into.

0 Parameters can be read for standard installation & startup (operator prompting)
1 Parameters for standard installation & startup (operator prompting) can be read and written into
2 All parameters can be read
4 All parameters can be read and written to
8 Motor data parameters can be read and written into
10 All parameters (including the motor data) can be read and written into

Note:
The read and write protection is significant when parameterizing via the display and operator control unit.

0652 Transfer to FEPROM

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the parameter values from the RAM can be transferred into the FEPROM.

0 -> 1 the values in the RAM are written into the FEPROM
1 data backup runs, other parameters cannot be selected

Note:
The parameter is automatically set to 0 at the end of data backup.
### 0653 Image, input signals, Part 1

<table>
<thead>
<tr>
<th></th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Min</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of selected input signals (terminal and PROFIBUS signals).

- **Bit 0**: ON / OFF
- **Bit 1**: Operating condition / OFF
- **Bit 2**: Operating condition / OFF
- **Bit 3**: Enable inverter / pulse inhibit
- **Bit 4**: Ramp-function generator enable <--> operating condition / reject traversing task
- **Bit 5**: Start ramp-function generator / stop <--> operating condition / intermediate stop
- **Bit 6**: Enable setpoint <--> activate traversing task (edge)
- **Bit 7**: Reset fault memory
- **Bit 8**: Jog 1 ON / OFF
- **Bit 9**: Jog 2 ON / OFF
- **Bit 10**: Control requested / no control requested
- **Bit 11**: Start referencing / cancel referencing
- **Bit 12**: Open holding braking as test/do no open
- **Bit 13**: Ramp-up time zero for controller enable <--> external block change
- **Bit 14**: Torque-controlled operation
- **Bit 15**: Spindle positioning on <--> request passive referencing
- **Bit 16**: Signal status, terminal 65.x
- **Bit 17**: Supply infeed module, signal status terminal 64
- **Bit 18**: Signal status terminal 663
- **Bit 19**: Line supply infeed module signal status terminal 63 / terminal 48
- **Bit 21**: Equivalent zero mark
- **Bit 22**: Flying measurement / length measurement
- **Bit 24**: Activate the function generator (signal edge)

**Note:**

<-->: Signal in "speed/torque setpoint" <--> in "positioning"

/: 1 signal / 0 signal
### 0654 Image, input signals, Part 2

| Bit 0 | Parameter set changeover, 1st input |
| Bit 1 | Parameter set changeover, 2nd input |
| Bit 2 | Parameter set changeover, 3rd input |
| Bit 3 | First speed setpoint filter out |
| Bit 4 | Ramp-up time zero |
| Bit 5 | Reserved for Siemens (smooth running monitoring) |
| Bit 6 | Integrator inhibit, speed controller |
| Bit 7 | Select parking axis |
| Bit 8 | Suppress fault 608 |
| Bit 9 | Motor data set changeover, 1st input |
| Bit 10 | Motor data set changeover, 2nd input |
| Bit 11 | Motor changed-over |
| Bit 12 | Tracking operation |
| Bit 13 | Set reference point |
| Bit 14 | Reference cams |
| Bit 15 | Fixed end stop, sensor |
| Bit 16 | Hardware limit switch, plus |
| Bit 17 | Hardware limit switch, minus |
| Bit 18 | Fixed speed setpoint, 1st input <--> block selection, 1st input |
| Bit 19 | Fixed speed setpoint, 2nd input <--> block selection, 2nd input |
| Bit 20 | Fixed speed setpoint, 3rd input <--> block selection, 3rd input |
| Bit 21 | Fixed speed setpoint, 4th input <--> block selection, 4th input |
| Bit 22 | Block selection, 5th input |
| Bit 23 | Block selection, 6th input |
| Bit 24 | Block selection 7th input (from SW 10.1) |
| Bit 25 | Block selection 8th input (from SW 10.1) |

Note:
<-->: Signal in "speed/torque setpoint" <--> in "positioning"

### 0655 Image, input signal Part 3

| Bit 0 | Activate coupling |
| Bit 1 | Jogging incremental |
| Bit 2 | Activate teach-in |
| Bit 3 | Invert input pulses, angular encoder interface |
| Bit 11 | Angular incremental encoder handwheel evaluation, bit 0 (from SW 8.1) |
| Bit 12 | Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1) |
| Bit 13 | Activate angular incremental encoder handwheel (from SW 8.1) |
| Bit 17 | Activate MDI (from SW 7.1) |
| Bit 21 | Activate coupling via I0.x |
| Bit 22 | Set position reference value |
### 0656 Image, output signals, Part 1

<table>
<thead>
<tr>
<th>Bit</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Ready to power-on / not ready to power-on</td>
<td></td>
</tr>
<tr>
<td>1</td>
<td>Ready or no fault</td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>Status controller enable</td>
<td></td>
</tr>
<tr>
<td>3</td>
<td>Fault present / fault not present</td>
<td></td>
</tr>
<tr>
<td>4</td>
<td>No OFF 2 present / OFF 2 present</td>
<td></td>
</tr>
<tr>
<td>5</td>
<td>No OFF 3 present / OFF 3 present</td>
<td></td>
</tr>
<tr>
<td>6</td>
<td>Power-on inhibit / no power-on inhibit</td>
<td></td>
</tr>
<tr>
<td>7</td>
<td>Alarm present / no alarm present</td>
<td></td>
</tr>
<tr>
<td>8</td>
<td>$n_{set} = n_{act}$ &lt;-&gt; no following error / following error</td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>Control request / control not possible</td>
<td></td>
</tr>
<tr>
<td>10</td>
<td>Comparison value reached &lt;-&gt; reference position reached</td>
<td></td>
</tr>
<tr>
<td>11</td>
<td>Reference point set / no reference point set</td>
<td></td>
</tr>
<tr>
<td>12</td>
<td>Setpoint acknowledgement (edge)</td>
<td></td>
</tr>
<tr>
<td>13</td>
<td>Function generator active &lt;-&gt; drive stationary / drive moves</td>
<td></td>
</tr>
<tr>
<td>14</td>
<td>Torque-controlled operation &lt;-&gt; External block change</td>
<td></td>
</tr>
<tr>
<td>15</td>
<td>Spindle positioning on &lt;-&gt; request passive referencing</td>
<td></td>
</tr>
<tr>
<td>16</td>
<td>Programmed velocity reached</td>
<td></td>
</tr>
</tbody>
</table>

**Note:**

$\leftrightarrow$: Signal in "speed/torque setpoint" $\leftrightarrow$ in "positioning"

/: 1 signal / 0 signal
0657 Image, output signals, Part 2

<table>
<thead>
<tr>
<th>Bit 0</th>
<th>Status, parameter set, 1st output</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 1</td>
<td>Status parameter set, 2nd output</td>
</tr>
<tr>
<td>Bit 2</td>
<td>Status parameter set, 3rd output</td>
</tr>
<tr>
<td>Bit 3</td>
<td>First speed setpoint filter inactive</td>
</tr>
<tr>
<td>Bit 4</td>
<td>Ramp-function generator inactive</td>
</tr>
<tr>
<td>Bit 5</td>
<td>Open holding brake</td>
</tr>
<tr>
<td>Bit 6</td>
<td>Integrator inhibit, speed controller</td>
</tr>
<tr>
<td>Bit 7</td>
<td>Parking axis selected</td>
</tr>
<tr>
<td>Bit 8</td>
<td>Suppress fault 608 active</td>
</tr>
<tr>
<td>Bit 9</td>
<td>Actual motor, 1st signal</td>
</tr>
<tr>
<td>Bit 10</td>
<td>Actual motor, 2nd signal</td>
</tr>
<tr>
<td>Bit 11</td>
<td>Motor being changed-over &lt;--&gt; angular incremental encoder handwheel evaluation, bit 0 (from SW 8.1)</td>
</tr>
<tr>
<td>Bit 12</td>
<td>Angular incremental encoder handwheel evaluation, bit 1 (from SW 8.1)</td>
</tr>
<tr>
<td>Bit 13</td>
<td>Angular incremental encoder handwheel active (from SW 8.1)</td>
</tr>
<tr>
<td>Bit 14</td>
<td>Block processing inactive</td>
</tr>
<tr>
<td>Bit 17</td>
<td>MDI active (from 7.1)</td>
</tr>
<tr>
<td>Bit 18</td>
<td>Status, block selection, 1st output</td>
</tr>
<tr>
<td>Bit 19</td>
<td>Status block selection, 2nd output</td>
</tr>
<tr>
<td>Bit 20</td>
<td>Status, block selection, 3rd output</td>
</tr>
<tr>
<td>Bit 21</td>
<td>Status, block selection, 4th output</td>
</tr>
<tr>
<td>Bit 22</td>
<td>Status block selection, 5th output</td>
</tr>
<tr>
<td>Bit 23</td>
<td>Status, block selection, 6th output</td>
</tr>
<tr>
<td>Bit 24</td>
<td>Status, block selection 7th output (from SW 10.1)</td>
</tr>
<tr>
<td>Bit 25</td>
<td>Status, block selection 8th output (from SW 10.1)</td>
</tr>
</tbody>
</table>

Note:

<-->: Signal in "speed/torque setpoint" <--> in "positioning"
**0658  Image, output signals, Part 3**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of selected output signals (terminal and PROFIBUS signals).

- Bit 0 Ramp-up completed
- Bit 1 \(|M| < M_x\) (P1428:8, P1429)
- Bit 2 \(\text{n\_act}| < \text{n\_min}\) (P1418:8)
- Bit 3 \(\text{n\_act}| < \text{n\_x}\) (P1417:8)
- Bit 4 \(V_{DC} \text{ link} < V_x\) (P1604)
- Bit 5 Variable signaling function
- Bit 6 Motor temperature alarm (P1602)
- Bit 7 Heatsink temperature pre-alarm
- Bit 8 \(\text{n\_set} = \text{n\_act}\) (P1426, P1427)
- Bit 9 Fixed end stop reached
- Bit 10 Fixed end stop, clamping torque reached
- Bit 11 Traverse to fixed endstop active
- Bit 12 Tracking mode active
- Bit 13 Velocity limiting active
- Bit 14 Setpoint is zero
- Bit 15 Synchronized
- Bit 16 Axis moves forwards
- Bit 17 Axis moves backwards
- Bit 18 Minus software limit switch actuated
- Bit 19 Plus software limit switch actuated
- Bit 20 Cam switching signal 1
- Bit 21 Cam switching signal 2
- Bit 22 Direct output 1 via traversing block
- Bit 23 Direct output 2 via traversing block
- Bit 25 Power module current not limited
- Bit 28 Pulses enabled
- Bit 29 Position reached
- Bit 30 Spindle position 2 reached
- Bit 31 Teach In executed

**0659  Bootstrap loading**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... it is possible to toggle between the initialization and normal condition.

- 0 establish initialized condition
- 0 -> 1 initialize
- 1 normal condition
- 2, 3, 4 Internal Siemens

Note:

Only the most important parameters can be selected and changed (e.g. motor code, power section code) in the initialized condition.
In the normal condition, the motor code and power section code are write-protected.
When starting-up for the first time using "Load file", P0659 remains at 2 (internal siemens).
### 0660 Function of input terminal I0.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>35</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I0.x has on the control module.
The function number from the "List of input signals" is entered.

Note:
refer to the index entry "Terminals term. I0.x to I3.x" or "List of the input signals"

### 0661 Function of input terminal I1.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>7</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I1.x has on the control module.
The function number from the "List of input signals" is entered.

Note:
refer to the index entry "Terminals term. I0.x to I3.x" or "List of the input signals"

### 0662 Function of input terminal I2.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>3</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I2.x has on the control module.
The function number from the "List of input signals" is entered.

Note:
refer to the index entry "Terminals term. I0.x to I3.x" or "List of the input signals"

### 0663 Function of input terminal I3.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>4</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I3.x has on the control module.
The function number from the "List of input signals" is entered.

Note:
refer to the index entry "Terminals term. I0.x to I3.x" or "List of the input signals"

### 0664 Function of input terminal I4

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>60</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I4 has on the option module TERMINALS.
The function number from the "List of input signals" is entered.

Note:
refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"

### 0665 Function of input terminal I5

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>59</td>
<td>86</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I5 has on the option module TERMINALS.
The function number from the "List of input signals" is entered.

Note:
refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"
0666  **Function of input terminal I6**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>58</td>
<td>86</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I6 has on the option module TERMINALS. The function number from the "List of input signals" is entered.

Note: refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"

0667  **Function of input terminal I7**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>50</td>
<td>86</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I7 has on the option module TERMINALS. The function number from the "List of input signals" is entered.

Note: refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"

0668  **Function of input terminal I8**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>51</td>
<td>86</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I8 has on the option module TERMINALS. The function number from the "List of input signals" is entered.

Note: refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"

0669  **Function of input terminal I9**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>52</td>
<td>86</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I9 has on the option module TERMINALS. The function number from the "List of input signals" is entered.

Note: refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"

0670  **Function of input terminal I10**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>53</td>
<td>86</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I10 has on the option module TERMINALS. The function number from the "List of input signals" is entered.

Note: refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"

0671  **Function of input terminal I11**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>54</td>
<td>86</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that input terminal I11 has on the option module TERMINALS. The function number from the "List of input signals" is entered.

Note: refer to the index entry "Terminals term. I4 to I11" or "List of the input signals"
Function, input terminal I0.B  

<table>
<thead>
<tr>
<th>Function, input terminal I0.B</th>
<th>(-&gt; 3.3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Min</td>
<td>Standard</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

... defines the function of input terminal I0.B, drive B for the direct measuring system of drive A.

Note:
The function number from the "List of input signals" is entered.
Prerequisite: P0250 = 1 (direct measuring system)
The following functions can be executed via I0.B:
- External block change (function number 67)
- Flying measurement/length measurement (function number 80)
- Equivalent zero mark (function number 79)

Assignment, inputs: Optional TERMINAL module  

<table>
<thead>
<tr>
<th>Assignment, inputs: Optional TERMINAL module</th>
<th>(-&gt; 4.1)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Min</td>
<td>Standard</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

... defines which input terminals on the optional TERMINAL module are assigned to this drive.

| 0 | none |
| 1 | Input terminal I4 to I7 |
| 2 | Input terminals I8 to I11 |
| 3 | Input terminals I4 to I11 |

Note:
The terminals can only be assigned to a drive once.
Prerequisite for the assignment: P0875 = 1
Assignment, outputs: Refer to P0696

Image of the input terminals

The signal statuses of the input terminals are displayed using these parameters.

<table>
<thead>
<tr>
<th>Image of the input terminals</th>
</tr>
</thead>
<tbody>
<tr>
<td>Min</td>
</tr>
<tr>
<td>-</td>
</tr>
</tbody>
</table>

Bit 15 (Term. 63 / Term. 48), bit 14 (Term. 663), bit 13 (Term. 64), bit 12 (Term. 65.x),
Bit 11 (Term. I11), bit 10 (Term. I10), bit 9 (Term. I9), Bit 8 (Term. I8),
Bit 7 (Term. I7), bit 6 (Term. I6), bit 5 (Term. I5), bit 4 (Term. I4),
bit 3 (t. I3.x), bit 2 (t. I2.x), bit 1 (t. I1.x), bit 0 (t. I0.x)

| Bit x = "1" --> input terminal has signal status "1"
| Bit x = "0" --> input terminal has signal status "0"

Example: P0678 = F004 --> Term. 63 / Term. 48, Term. 663, Term. 64, Term. 65.x and Term. I2.x have signal status "1"

Note:
Non-assigned bits are displayed with "0".
Terminal I4 to terminal I11 are on the optional TERMINAL module.

signaling function of output terminal O0.x

<table>
<thead>
<tr>
<th>signaling function of output terminal O0.x</th>
</tr>
</thead>
<tbody>
<tr>
<td>Min</td>
</tr>
<tr>
<td>0</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O0.x has on the control module.
The function is entered from the "List of output signals".
Note:
refer to the index entry "Terminals term. O0.x to O3.x" or "List of the output signals"
A.1 Parameter list

0681 signaling function of output terminal O1.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2</td>
<td>88</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O1.x has on the control module. The function is entered from the "List of output signals".

Note:
refer to the index entry "Terminals term. O0.x to O3.x" or "List of the output signals"

0682 signaling function of output terminal O2.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>88</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O2.x has on the control module. The function is entered from the "List of output signals".

Note:
refer to the index entry "Terminals term. O0.x to O3.x" or "List of the output signals"

0683 signaling function of output terminal O3.x

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>5</td>
<td>88</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O3.x has on the control module. The function is entered from the "List of output signals".

Note:
refer to the index entry "Terminals term. O0.x to O3.x" or "List of the output signals"

0684 signaling function, output terminal O4

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>72</td>
<td>88</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O4 has on the option module TERMINALS. The function is entered from the "List of output signals".

Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0685 signaling function, output terminal O5

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>60</td>
<td>88</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O5 has on the option module TERMINALS. The function is entered from the "List of output signals".

Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0686 signaling function, output terminal O6

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>62</td>
<td>88</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that output terminal O6 has on the option module TERMINALS. The function is entered from the "List of output signals".

Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"
0687  signaling function, output terminal O7
Min  Standard  Max  Unit  Data type  Effective
0     50   88  -  Unsigned16  immed.

... defines the function that output terminal O7 has on the option module TERMINALS.
The function is entered from the "List of output signals".
Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0688  signaling function, output terminal O8
Min  Standard  Max  Unit  Data type  Effective
0     51   88  -  Unsigned16  immed.

... defines the function that output terminal O8 has on the option module TERMINALS.
The function is entered from the "List of output signals".
Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0689  signaling function, output terminal O9
Min  Standard  Max  Unit  Data type  Effective
0     52   88  -  Unsigned16  immed.

... defines the function that output terminal O9 has on the option module TERMINALS.
The function is entered from the "List of output signals".
Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0690  signaling function, output terminal O10
Min  Standard  Max  Unit  Data type  Effective
0     53   88  -  Unsigned16  immed.

... defines the function that output terminal O10 has on the option module TERMINALS.
The function is entered from the "List of output signals".
Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0691  signaling function, output terminal O11
Min  Standard  Max  Unit  Data type  Effective
0     54   88  -  Unsigned16  immed.

... defines the function that output terminal O11 has on the option module TERMINALS.
The function is entered from the "List of output signals".
Note:
refer to the index entry "Terminals term. O4 to O11" or "List of the output signals"

0696  Assignment, optional TERMINAL module outputs  (-- 4.1)
Min  Standard  Max  Unit  Data type  Effective
0     0    3   -  Unsigned16  immed.

... defines which output terminals on the TERMINAL option module are assigned to this drive.
0 none
1  Output terminal O4 to O7
2  Output terminals O8 to O11
3  Output terminals O4 to O11
Note:
The terminals can only be assigned to a drive once.
Prerequisite for the assignment: P0875 = 1
Assignment, inputs: Refer to P0676
### 0698 Image of the output terminals

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

The signal statuses of the output terminals are displayed using these parameters.

- bit 11 (t. O11), bit 10 (t. O10), bit 9 (t. O9), bit 8 (t. O8),
- bit 7 (t. O7), bit 6 (t. O6), bit 5 (t. O5), bit 4 (t. O4),
- bit 3 (T. O3.x), bit 2 (T. O2.x), bit 1 (T. O1.x), bit 0 (T. O0.x)

**Bit x = "1" --> output terminal has signal status "1"**
**Bit x = "0" --> output terminal has signal status "0"**

Example: P0698 = 0006 --> Term. O2.x and O1.x have signal status "1"

Note:
- Non-assigned bits are displayed with "0".
- Terminals O4 to O11 are on the optional TERMINAL module.

### 0699 Inversion output terminal signals

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

This parameter is used to define which output terminal signals are to be output inverted.

- bit 11 (Term. O11), bit 10 (Term. O10), bit 9 (Term. O9), bit 8 (Term. O8),
- bit 7 (Term. O7), bit 6 (Term. O6), bit 5 (O5), bit 4 (Term. O4),
- bit 3 (T. O3.x), bit 2 (T. O2.x), bit 1 (T. O1.x), bit 0 (T. O0.x)

**Bit x = "1" --> output terminal is inverted**
**Bit x = "0" --> output terminal is not inverted**

Example: P0699 = 0003 --> Term. O1.x and O0.x are output inverted

Note:
- Non-assigned bits are displayed with "0".
- Terminals O4 to O11 are on the optional TERMINAL module.

### 0700 Operating mode

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

**0 Drive inactive (only drive B)**

This means a double-axis module can only be operated with a single axis.

*Should there be no communication with the inactive drive B via PROFIBUS? If yes, then communication must be disabled with P0875 = 0.*

**1 Speed/torque setpoint**

The drive can be operated as follows in this operating mode:
- closed-loop speed controlled operation (n-set operation)
- open-loop torque controlled mode (M setpoint operation)
- Torque reduction (M reduction)

Note:
- Operation is possible via terminals, via PROFIBUS-DP or both together.

**2 External position reference value (from SW 3.3)**

No longer available from SW 4.1. Select "Positioning" mode.

**3 Positioning (from SW 2.1)**

The drive can be operated as follows in this operating mode:
- programming, selecting and starting traversing blocks
- enter velocity override
- Torque reduction (M reduction)

Note:
- Operation is possible via terminals, via PROFIBUS-DP or both together.
### 0701 Actual operating mode

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

- Drive inactive (only drive B)
- Speed/torque setpoint
  - closed-loop speed controlled operation (n-set operation)
  - open-loop torque controlled mode (M setpoint operation)
  - Torque reduction (M reduction)
- External position reference value (from SW 3.3)
  - No longer available from SW 4.1.
- Positioning (from SW 2.1)

### 0730:795 Saved parameters  
(-> 6.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

...includes all of the parameters taken into account when saving the drive configuration (save parameter in a file).

The following steps are necessary for a series start-up without using the SimoCom U start-up tool:
1. Signal the motor type (write into P1102 = motor code)
2. Writing 4 into P0659 (drive carries-out defaults)
3. Write into all of the parameters listed in parameter P0731
4. Write 2 into P0659 (pre-assign motor/ LT data, calculate controller data)
5. Write into all parameters listed in parameter P0730 (minus the parameters listed in P0731)

### 0731:250 Parameters required before start-up  
(-> 6.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

...contains all parameters which must be written into before commissioning.

The following steps are necessary for a series start-up without using the SimoCom U start-up tool:
1. Signal the motor type (write into P1102 = motor code)
2. Writing 4 into P0659 (drive carries-out defaults)
3. Write into all of the parameters listed in parameter P0731
4. Write 2 into P0659 (pre-assign motor/ LT data, calculate controller data)
5. Write into all parameters listed in parameter P0730 (minus the parameters listed in P0731)

### 0801 Changeover RS232/RS485

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>PO</td>
</tr>
</tbody>
</table>

The serial interface (X471) is set to RS232 or to RS485 using this parameter.

1. Interface is set to RS485
0. Interface is set to RS232
-1. reserved

Note:
The interface can be changed over from both drives. As the interface is either set to RS232 or to RS485, when changing the parameter in a drive, the parameter in the other drive is appropriately adapted.
The RS485 interface works only on control modules with the following hardware version:
- Order no. (MLFB): 6SN1118- _N_00-0AA0 --> RS485 is not operable
- from order no. (MLFB): 6SN1118- _N_00-0AA1 --> RS485 is operable

refer to the index entry "SimoCom U - via serial interface"
0802  Drive number for RS485

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>31</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

In an RS485 group, each drive must be assigned a unique drive number for addressing using this parameter.

0  the drive is not available in the RS485 group
1 to 31  the drive has this valid drive number

Note:
The drive number must be unique within the complete group refer to the index entry "SimoCom U - via serial interface"

0803  Adjacent drive number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

For a 2-axis module, this parameter displays the drive number of the adjacent axis.
The adjacent drive number of drive A is the drive number of drive B.
The adjacent drive number of drive B is the drive number of drive A.

0828:128  Warning value

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

The supplementary information of the warnings, displayed using P0953 - P0960, is entered in this parameter.
The following is valid:
P0828:0  Supplementary information, alarm 800 (P0953 bit 0)
P0828:1  Supplementary information, warning 801 (P0953 bit 1)
...
P0828:127 Supplementary information, alarm 927 (P0960 bit 15)

0850  Activate brake control

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... activates/de-actives the brake sequence control for this axis.
1  Brake sequence control is activated
0  Brake sequence control is de-activated

Note:
The pulse suppression control via P1403 (creep speed pulse suppression) and P1404 (timer pulse suppression) is ineffective when the motor holding brake is activated.
refer to the index entry "Motor holding brake"

0851  Brake release time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>10.0</td>
<td>600.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The setpoint transfer after "Controller enable" is delayed by this time.
During this time, the speed control is internally already active with n-set = 0, so that the axis does not move while the brake is opening.
After the time has expired, the closed-loop speed control is active and setpoints can be transferred.
Note: refer to the index entry "Motor holding brake"
0852  Speed, close holding brake (ARM SRM)
Motor velocity, close holding brake (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>500.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: refer to P0853

0853  Brake delay time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>10.0</td>
<td>400.0</td>
<td>600000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

P0852 and P0853 form the criterion for withdrawing the output signal "Open holding brake" to close the motor holding brake.

After "controller enable" is withdrawn the drive brakes with n-set = 0.
With the brake sequence control active, the "open holding brake" output signal is reset, if:
- $|n_{act}| < n$ holding brake (P0852)
or
- The brake delay time (P0853) has expired

Note: refer to the index entry "Motor holding brake"

0854  Controller disable time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>10.0</td>
<td>600.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

With n-set = 0, the drive is actively controlled (internal controller enable) until the controller locking time expires (P0854).
In order that the brake has time to close, the closing time is bypassed to prevent a hanging axis, for example, from sagging. The pulses are only canceled after this time.

Note: refer to the index entry "Motor holding brake"

0868  Baud rate selection, CAN bus

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>255</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... is used to set the baud rate for the CAN - option module (Robox Company).

0  1000 kBit/s
1  800 kBit/s
2  500 kBit/s
3  250 kBit/s
4  125 kBit/s
5  100 kBit/s
6  50 kBit/s
7  20 kBit/s
8  10 kBit/s
>8  Reserved
### 0870 Module type

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

The parameter displays the control module type and firmware.

P0870 = UVWX

- **U** = 0 Drive type is "SIMODRIVE 611 universal"
- **U** = x Reserved for another drive type (x = 1 to 15)
- **V** = 0 firmware for speed control
- **V** = 1 firmware for positioning
- **W** reserved
- **X** = 1 module, 2-axis for resolvers
- **X** = 2 Module, 2-axis for encoders with sin/cos 1 Vpp
- **X** = 3 module, 1-axis for resolvers
- **X** = 4 Module "SIMODRIVE 611 universal E", 2-axis for encoders with sin/cos 1 Vpp
- **X** = 5 Module HR, 2-axis for encoders with sin/cos 1 Vpp
- **X** = 7 Module HR, 2-axis for resolvers
- **X** = 8 Module HR, 1-axis for resolvers
- **X** = 9 Module HR "SIMODRIVE 611 universal E", 2-axis for encoders with sin/cos 1 Vpp
- **X** = A Module HRS, 2-axis for encoders with sin/cos 1 Vpp
- **X** = B Module HRS, 2-axis for resolvers
- **X** = C Module HRS, 1-axis for resolvers
- **X** = D Module HRS "SIMODRIVE 611 universal E", 2-axis for encoders with sin/cos 1 Vpp

Note: The module version is displayed in P0871.

### 0871 Module version

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the version of the particular module.

### 0872 Option module type

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays which option module was identified when the control module was powered-up.

0 no option module
1 Optional TERMINAL module, Order No. (MLFB): 6SN1114-0NA00-0AA0
2 Option module PROFIBUS-DP1 with PROFIBUS-ASIC SPC3, Order No. (MLFB): 6SN1114-0NB00-0AA0
3 Option module PROFIBUS-DP2 (from SW 3.1) with PROFIBUS ASIC DPC31 without PLL, Order No. (MLFB): 6SN1114-0NB00-0AA1
4 Option module PROFIBUS-DP3 (from SW 3.1) with PROFIBUS ASIC DPC31 with PLL, Order No. (MLFB): 6SN1114-0NB01-0AA0
253 CAN - option module, Robox company
255 Third-party module corresponding to the published interface spec. (from SW 4.1)

### 0873 Option module version

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the version of the respective option module.
### Expected option module type

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>255</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... displays which option module is expected as a result of the parameterization. During first startup, the parameter is automatically set according to P0872 (option module type).

**Note:**
Disable the communication or the "DP slave 611U":
- 1-axis module
  -- with P0875 = 0 from drive A, the "DP slave 611U" is disabled
- 2-axis module
  -- with P0875 = 0 from drive B, communication with drive B is disabled
  -- with P0875 = 0 in both drives, the "DP slave 611U" is disabled
This allows, for example, "disturbing" slaves to be temporarily disabled when commissioning other nodes (refer to the index entry "Commissioning PROFIBUS-DP").

### PROFIdrive configuration

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>127</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... several behavioral features are activated in order to achieve conformance with the PROFIdrive profile.

**Bit 0**
- Axis addressing according to PROFIdrive
**Bit 0 = 1**
  - For a non-cyclic access via the DPV1 parameter channel axis A is addressed with index 1 (this is in conformance with the profile)
**Bit 0 = 0**
  - For a non-cyclic access via the DPV1 parameter channel axis A is addressed with index 0 (this is not in conformance with the profile)

**Bit 1**
- P915/P916 cannot be changed for P922 > 0
**Bit 1 = 1**
  - P915/P916 cannot be written into if P922 is greater than 0 (this is in conformance with the profile)
**Bit 1 = 0**
  - P915/P916 can also be written into if P922 is greater than 0 (this is not in conformance with the profile)

**Bit 2**
- No. of Value = Length for string variables
**Bit 2 = 1**
  - For string variables, in the "DPV1 parameter response" the length of bytes is transferred under "No. of Values" (in conformance with the profile)
**Bit 2 = 0**
  - For string variables, in the "DPV1 parameter response" the number of values are transferred under "No. of Values" (this is not in conformance with the profile)

**Bit 3, bit 4, bit 5** selects the PROFIdrive profile version
**Bit 5 = 0, bit 4 = 0, bit 3 = 0:** PROFIdrive profile Version 3.1.2 is active
**Bit 5 = 0, bit 4 = 0, bit 3 = 1:** PROFIdrive profile version 4.1 is active (from SW 12.1)

**Bit 6**
- Function generator immediately active (from SW 11.2 onwards)
**Bit 6 = 1**
  - Function generator immediately active is activated in STW1 bit 9 (not in conformance with the profile)
**Bit 6 = 0**
  - Function generator immediately active is deactivated in STW1 bit 9 (in conformance with the profile)

**Note:**
The following parameters should be set for the PROFIdrive profile in conformance to profile version V3.1:
- P0878 bit 0 = 1, bit 1 = 1, bit 2 = 1
- P0879 bit 0 = 1, bit 1 = 0, bit 2 = 0, bit 9 = 1
- P1012 bit 12 = 1, bit 13 = 1, bit 14 = 0, bit 15 = 1
In addition, the following parameters must be set in order to achieve compatibility to profile version V4.1.
- P0878 bit 3 = 1
**0879**  PROFIBUS configuration

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>FFFF Hex</td>
<td>1</td>
<td>PO</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

... defines several types of behavior for operation with PROFIBUS-DP.

- **Bit 2, 1, 0**: Permissible sign-of-life error
  - Specifies in how many subsequent cycles (Tmapc) a sign-of-life error may occur without a fault being signaled.
  - Bit 7 = 1: Monitoring PLL window acc. to PROFIdrive (from SW 13.1)
  - Bit 7 = 0: The more accurate, monitoring in conformance with the profile is not activated
  - Bit 8 = 1: Operation with/without master sign-of-life monitoring
  - Bit 8 = 0: without sign-of-life monitor
  - Bit 9 = 1: Data types, profile parameters according to PROFIdrive
  - Bit 9 = 0: For PROFIdrive profile parameters, data types are interpreted according to PROFIdrive
  - Bit 10: reserved
  - Bit 11 = 1: PKW area: Subindex in the high byte from IND (from SW 3.3)
  - Bit 11 = 0: Sub-index in the low byte (standard for SIMODRIVE)
  - Bit 12: Activate direct measuring system (encoder 2) for the encoder interface (from SW 3.3)
  - Bit 13 = 1: Incremental motor measuring system with/without equivalent zero mark
    - (e. g. BERO at input terminal I0.x)
  - Bit 13 = 0: Incremental motor measuring system available
  - Bit 14 = 1: Incremental direct measuring system with equivalent zero mark available
    - (e. g. BERO at input terminal I0.x)
  - Bit 14 = 0: Incremental direct measuring system available
  - Bit 15: reserved

**0880**  Speed evaluation, PROFIBUS (ARM SRM)

Motor velocity evaluation, PROFIBUS (SLM)

- **Min**: -100000.0
- **Max**: 100000.0
- **Unit**: m/min
- **Data type**: Floating Point
- **Effective**: (SLM)

- **Min**: -100000.0
- **Max**: 100000.0
- **Unit**: rpm
- **Data type**: Floating Point
- **Effective**: (SRM ARM)

... defines the normalization of the speed or velocity when using PROFIBUS-DP. When entering a negative value, in addition, the motor direction of rotation is inverted.

**Note:**
4000hex or 16384dec in control word NSOLL_A corresponds to the speed or velocity in P0880. Refer to the index entry "Control words NSOLL_A or NSOLL_B"
### 0881 Evaluation torque/power reduction PROFIBUS (ARM SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>16384.0</td>
<td>16384.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>16384.0</td>
<td>16384.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

... defines the normalization of the torque/power reduction or force/power reduction when moving with PROFIBUS-DP.

**Note:**
4000Hex or 16384 dec in the MomRed control board corresponds to a reduction of the percentage specified in P0881.

Refer under the index entry "Control word MomRed".

### 0882 Evaluation, torque setpoint PROFIBUS (ARM SRM) (- -> 4.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-16384.0</td>
<td>800.0</td>
<td>16384.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>-16384.0</td>
<td>800.0</td>
<td>16384.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

... defines the normalization of the torque and force setpoint when using PROFIBUS-DP.

**Note:**
P0882 is a percentage value referred to the rated motor torque. The parameter affects the process data MsollExt (external torque setpoint in the input direction) and Msoll (torque setpoint in the output direction).

4000Hex or 16384 dec in the control word corresponds to the percentage entered in P0882.

Refer under the index entry "control word MsollExt", "Status word Msoll".

### 0883 Override evaluation PROFIBUS (- -> 3.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>16384.0</td>
<td>16384.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the normalization of the override when entered via PROFIBUS-DP.

**Note:**
4000Hex or 16384dec in the PROFIBUS-pPO corresponds to the override in P0883 (refer under the index entry "control word Over").

### 0884 Position output evaluation PROFIBUS - number of increments

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>10000</td>
<td>8388607</td>
<td>-</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... together with P0896, defines the format for the output of positions via PROFIBUS-DP.

**Note:**
Refer to P0896

Refer under the index entry "axis couplings".

### 0887 Speed actual value smoothing, PROFIBUS (ARM SRM)(- -> 13.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

This means that the speed actual value or velocity actual value can be smoothed via PROFIBUS using a PT1 filter.
The value defines the smoothing time constant of the PT1 filter (P0887 = 0 smoothing is not active).
0888:16 Function, distributed input (PROFIBUS)  (\(\rightarrow\) 4.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>83</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the function that a signal has – that has been read-in via PROFIBUS-PZD for distributed inputs (DezEing)
The function number from the "list of input signals" is entered. The following applies for the individual indices of P0888:
0  Function DezEing bit 0
1  Function DezEing bit 1
2  etc.

0889:4 Angular incremental encoder, handwheel evaluation  (\(\rightarrow\) 9.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>10000</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the factor with which the handwheel pulses are evaluated.

Note:
refer to the index entry "Angular encoder interface"

0890 Activate angular encoder/encoder interface

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines how the angular encoder interface and encoder interface are operated.
- Angular encoder interface (X461, X462 for "SIMODRIVE 611 universal")
- Encoder interface (X472 for "SIMODRIVE 611 universal E")
0  Angular encoder interface or encoder interface switched-out
1  Angular encoder interface switched-in as output for incremental position actual value
2  Angular encoder interface switched-in as input for incremental position reference value (from SW 3.3)
3  Angular encoder interface switched-in for drive A as input for the incremental position reference value. The incremental position actual value from drive A is output at the angular encoder interface from drive B, if P0890 (B) is 0. P0890 = 3 is only possible for drive A.
   (from SW 3.3)
4  Encoder interface enabled as input for TTL encoders (encoder 3, from SW 3.1)

For "SIMODRIVE 611 universal" a TTL signal can be downloaded/read-in via the angular incremental encoder interface and re-output via PROFIBUS-DP (encoder 3, e.g. standard telegram 104).

Note:
The terminating resistor must be set for the angular encoder interface --> switch S1
When injecting signals at the angular incremental encoder interface it should be ensured that the interface is not parameterized as output. Otherwise, the internal and external drivers will operate against one another and can mutually destroy themselves.

refer to the index entry "Angular encoder interface" or "Encoder interface"
Source, external position reference value  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1</td>
<td>-1</td>
<td>5</td>
<td>-</td>
<td>Integer16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines the source for the external position reference value.

-1 not an external position reference value

0 Angular encoder interface

1 Motor encoder, drive A (only drive B in double-axis modules)  
   (only for compatibility, recommended value = 2)

2 Position actual value drive A (only drive B in double-axis modules, from SW 4.1)

3 Position reference value drive A (only drive B in double-axis modules, from SW 4.1)

4 PROFIBUS-DP (from SW 4.1)

5 Angular incremental encoder interface coarse (resolution 1 increment corresponds to approx. 1 mm or 1 degree)

Note:
refer under the index entry "axis couplings"
## A.1 Parameter list

### 0892 No. of angular encoder marks / no. of encoder pulses factor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-2</td>
<td>0</td>
<td>5</td>
<td>-</td>
<td>Integer16</td>
<td>PO</td>
</tr>
</tbody>
</table>

**Resolvers:**

... defines the encoder pulse number via the angular encoder interface.

**Resolver, 12 bit module**: (6SN1118-*NK00-0AA0 or 6SN1118-*NJ00-0AA0):

- 0: P*1024
- 1: P*512
- 2: P*256
- 3: P*128

**Resolver 14 bit module**: (6SN1118-*NK01-0AA0 or 6SN1118-*NJ01-0AA0), 12 bit setting (1011[2]=0 or 1030[2]=0):

- 0: P*1024
- 1: P*512
- 2: P*256
- 3: P*128
- 4: P*64
- 5: P*32

**Resolver 14 bit module**: (6SN1118-*NK01-0AA0 or 6SN1118-*NJ01-0AA0), 14 bit setting (1011[2]=1 or 1030[2]=1):

- -2: P*4096
- -1: P*2048
- 0: P*1024
- 1: P*512
- 2: P*256
- 3: P*128

**Encoder with sin/cos 1Vpp**:

... defines the factor by which the encoder resolution is reduced (encoder pulse number or measuring length/grid spacing), before the signals (quadrature signals) are visible via the angular encoder output.

- 0: 1:1 scale
- 1: 1:2 scale
- 2: 1:4 scale
- 3: 1:8 scale
- 4: Doubling (from SW 5.1, with SIMODRIVE 611 universal HR/HRS)

**Note:**

- P --> Resolver pole pair number

The values -2,-1,4,5 for a resolver should only be set there where it is not intended to change over from 12 >> 14 bit resolution.

If, for example, high precision is not required for the position control, but however, high speeds, then the encoder pulse number, output via the angular incremental encoder interface can be less than then the encoder pulse number of the motor measuring system.

Refer to the index entry "Angular encoder interface"
0893 Angular encoder zero pulse offset

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-360.0</td>
<td>0.0</td>
<td>360.0</td>
<td>Degree</td>
<td>Floating Point</td>
<td>PO</td>
</tr>
</tbody>
</table>

... shifts the zero pulse of an encoder.
The zero pulses for the angular encoder interface are generated in the encoder hardware. For encoders with sin/cos 1 Vpp, there is 1 zero pulse per mechanical revolution. For resolvers, there is 1 zero pulse for each electrical revolution, i.e. for a resolver with pole pair number = 3, there are 3 zero pulses per mechanical revolution.

Note:
In order that the zero pulse offset is correctly taken into account, the drive must remain stationary while the control module is running up.
refer to the index entry "Angular encoder interface"

0894 Angular encoder input signal waveform

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>--</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines the input signal shape for the angular encoder interface.
0 Quadrature signal
1 Pulse/direction signal
2 Forwards/reverse signal

Note:
refer to the index entry "Angular encoder interface"

0895 External position reference value - number of increments

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>10000</td>
<td>8388607</td>
<td>--</td>
<td>unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... together with P0896, defines, for couplings, the ratio between the input increments and dimension system grids.

Note:
--> P0895 input pulses at the angular encoder correspond to P0896 MSR
--> Setpoint input from P0895 corresponds to P0896 MSR
refer to P0896
refer under the index entry "axis couplings"

0896 Ext. position ref. value - number of dimension system grids

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>10000</td>
<td>8388607</td>
<td>MSR</td>
<td>unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... together with P0895, defines, for couplings, the ratio between the input pulse periods (or input bit) and the measuring system grid.

Note:
refer to P0895
refer under the index entry "axis couplings"

0897 Invert external position reference value

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>--</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines whether the position reference value is entered externally and therefore the direction should be inverted.
1 position setpoint inversion
0 Not inverted

Note:
refer under the index entry "axis couplings"
### 0898 Modulo range master drive

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>100000000</td>
<td>MSR</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... informs the slave drive about the selected modulo range for the master drive.

**Note:**
The following applies: P0242 (master drive) = P0898 (slave drive)
The value 0 switches-out the modulo correction.
refer under the index entry "axis couplings"

### 0899:8 Enter angular incremental encoder direction

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines in which direction the angular incremental encoder interface pulses are permitted.

0   positive and negative direction
1   only the positive direction
2   only the negative direction

**Note:**
refer to the index entry "Angular encoder interface"

### 0900:4 Angular incremental encoder, handwheel evaluation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>10000</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the factor with which the handwheel pulses are evaluated.

**Note:**
From SW 9.1 onwards, P0900:4 is replaced by P0889:4 (P0900:4 = P0889:4).
refer to the index entry "Angular encoder interface"
0915:17 PZD setpoint value assignment PROFIBUS

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... serves for allocating the signals to the process data in the setpoint frame.

The following applies:

- **P0915:0** no meaning
- **P0915:1** PZD1, unable to configure (standard setting)
- **P0915:2** PZD2, Configuring and display of the signal ID (refer to P0922)
- **P0915:3** PZD3, etc.

**ID** Significance (abbreviation) (comments)

- **0** No signal (NIL)
- **50001** Control word 1 (STW1) (assignment n-set operation)
- **50001** Control word 1 (STW1) (assignment pos operation)
- **50003** Control word 2 (STW2)
- **50005** Speed setpoint A (NSOLL_A, nset-h) (n-set operation)
- **50007** Speed setpoint B (NSOLL_B, nset-(h+l)) (n-set operation)
- **50009** Encoder 1, control word (G1_STW) (n-set operation)
- **50013** Encoder 2 control word (G2_STW) (n-set, operation, from SW 3.3)
- **50017** Encoder 3 control word (G3_STW) (n-set operation)
- **50025** System deviation DSC (XERR) (n set operation, from SW 4.1)
- **50026** Position controller gain factor DSC (KPC) (n set operation, from SW 4.1)
- **50101** Torque reduction (MomRed)
- **50103** Analog output, T. 75.x/15 (DAU1)
- **50105** Analog output T. 16.x/15 (DAU2)
- **50107** Digital outputs, T. O0.x to O3.x (DIG_OUT)
- **50109** Target position for spindle positioning (XSP) (n set operation, from SW 5.1)
- **50111** Distributed inputs (DezEing) (from SW 4.1)
- **50113** External torque setpoint (MsollExt) (n set operation, from SW 4.1)
- **50117** Control word, slave-to-slave communications (QStw) (pos operation, from SW 4.1)
- **50201** Block selection (SatzAnw)
- **50203** Positioning control word (PosStw) (pos operation)
- **50205** Override (Over) (pos operation)
- **50207** External position reference value (Xext) (pos operation, from SW 4.1)
- **50209** Correction, external position reference value (XcorExt) (pos operation, from SW 4.1)
- **50221** MDI position (MDIPos) (pos mode, from SW 7.1)
- **50223** MDI velocity (MDIVel) (pos mode, from SW 7.1)
- **50225** MDI acceleration override (MDIAcc) (pos mode, from SW 7.1)
- **50227** MDI deceleration override (MDIDec) (pos mode, from SW 7.1)
- **50229** MDI mode (MDIMode) (pos mode, from SW 7.1)

**Note:**
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.

Operating mode not specified ---> possible in every operating mode

Refer to the index entry "Configuring the process data"
0916:17  **PZD actual value assignment PROFIBUS**  

### Effective

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... serves for allocating the signals to the process data in the actual value frame.

The following applies:

- **P0916:0**  no meaning
- **P0916:1**  PZD1, unable to configure (standard setting)
- **P0916:2**  PZD2, Configuring and display of the signal ID (refer to P0922)
- **P0916:3**  PZD3, etc.

<table>
<thead>
<tr>
<th>ID</th>
<th>Significance (abbreviation) (comments)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>No signal (NIL)</td>
</tr>
<tr>
<td>50002</td>
<td>Status word 1 (ZSW1) (assignment, n-set operation)</td>
</tr>
<tr>
<td>50008</td>
<td>Speed actual value B (NIST_B, nact-(h+l))</td>
</tr>
<tr>
<td>50010</td>
<td>Encoder 1 status word (G1_ZSW) (n-set operation)</td>
</tr>
<tr>
<td>50011</td>
<td>Encoder 1 position actual value 1 (G1_XACT1) (n-set operation)</td>
</tr>
<tr>
<td>50012</td>
<td>Encoder 1 position actual value 2 (G1_XACT2) (n-set operation)</td>
</tr>
<tr>
<td>50014</td>
<td>Encoder 2 status word (G2_ZSW) (n-set operation, from SW 3.3)</td>
</tr>
<tr>
<td>50015</td>
<td>Encoder 2 position actual value 1 (G2_XACT1) (n-set operation, from SW 3.3)</td>
</tr>
<tr>
<td>50016</td>
<td>Encoder 2 position actual value 2 (G2_XACT2) (n-set operation, from SW 3.3)</td>
</tr>
<tr>
<td>50018</td>
<td>Encoder 3 status word (G3_ZSW) (n-set operation)</td>
</tr>
<tr>
<td>50019</td>
<td>Encoder 3 position actual value 1 (G3_XACT1) (n-set operation)</td>
</tr>
<tr>
<td>50020</td>
<td>Encoder 3 position actual value 2 (G3_XACT2) (n-set operation)</td>
</tr>
<tr>
<td>50102</td>
<td>Message word (MeldW)</td>
</tr>
<tr>
<td>50104</td>
<td>Analog input T. 56.x/14 (ADU1)</td>
</tr>
<tr>
<td>50106</td>
<td>Analog input T. 24.x/20 (ADU2)</td>
</tr>
<tr>
<td>50108</td>
<td>Digital inputs, T. I0.x to I3.x (DIG IN)</td>
</tr>
<tr>
<td>50110</td>
<td>Utilization (util)</td>
</tr>
<tr>
<td>50112</td>
<td>Active power (Pwirk)</td>
</tr>
<tr>
<td>50114</td>
<td>Smoothed torque setpoint (Msoll)</td>
</tr>
<tr>
<td>50116</td>
<td>Smoothed torque-generating current Iq (IqGl)</td>
</tr>
<tr>
<td>50118</td>
<td>Status word, slave-to-slave communications (QZsw) (pos operation, from SW 4.1)</td>
</tr>
<tr>
<td>50119</td>
<td>DC link voltage (VDClink1) (from SW 8.3)</td>
</tr>
<tr>
<td>50202</td>
<td>Currently selected block (AktSatz)</td>
</tr>
<tr>
<td>50204</td>
<td>Positioning status word (PosZsw) (pos operation)</td>
</tr>
<tr>
<td>50206</td>
<td>Position actual value (positioning operation) (XistP) (pos operation)</td>
</tr>
<tr>
<td>50208</td>
<td>Position reference value (positioning operation) (XsollP) (pos operation, from SW 4.1)</td>
</tr>
</tbody>
</table>

**Note:**

If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.

Operating mode not specified ---> possible in every operating mode

Refer to the index entry "Configuring the process data"
### 0918 PROFIBUS node address

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>126</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the address of the drive as DP slave on PROFIBUS.

**Note:**

There is only one node address for the control module, although it is designed for two drives. When changing the parameters in one drive, the parameters in the other drive are automatically modified.

Every node connected to PROFIBUS must have a unique address.

### 0922 PROFIBUS frame selection

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>101</td>
<td>110</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... is used to set the free configurability or to select a standard telegram.

0 The frame can be freely configured (see P0915:17, P0916:17)
1 standard frame 1, n-set interface 16 bits
2 Standard frame 2, n-set interface 32 bits without encoder
3 Standard telegram 3, n set interface 32 bit with encoder 1
4 Standard telegram 4, n-set interface 32 bit with encoder 1 and encoder 2 (from SW 3.3)
5 Standard telegram 5, n set interface 32 bit with DSC and encoder 1 (from SW 4.1)
6 Standard telegram 6, n set interface 32 bit with DSC and encoder 1 and encoder 2 (from SW 4.1)
101 The frame has the same structure as in SW 2.4
102 Standard frame 102, n-set interface with encoder 1
103 Standard telegram 103, speed setpoint interface with encoder 1 and encoder 2 (from kSW 3.3)
104 Standard frame 104, n-set interface with encoder 1 and encoder 3
105 Standard telegram 105, n-set interface with DSC and encoder 1 (from SW 4.1)
106 Standard telegram 106, n-set interface with DSC and encoder 1 and encoder 2 (from SW 4.1)
107 Standard telegram 107, n-set interface with DSC and encoder 1 and encoder 3 (from SW 4.1)
108 Standard telegram 108, master drive for the position reference value coupling (from SW 4.1)
109 Standard telegram 109, slave drive for the position reference value coupling (from SW 4.1)
110 Standard telegram 110, positioning in the MDI mode (from SW 7.1)

**Note:** refer to the index entry "Process data configuring"

### 0923:300 List of PROFIBUS standard signals

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

This parameter can be read in order to define which PROFIdrive standard signals (signals 1...99) and manufacturer-specific signals are supported and which device-specific signal ID this signal represents.

**Note:**

If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.
**A.1 Parameter list**

**0930  PROFIBUS selector switch operating mode**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
</table>

This parameter cannot be changed and corresponds to P0700.

0  Drive inactive
1  Closed-loop speed controlled operation
0x8000  positioning mode

**0944  Fault message counter**  

This parameter corresponds to the fault message counter. It is incremented each time that the fault buffer changes.

This means that it can be ensured that the fault buffer can be consistently read-out.

Note:
This parameter is reset at POWER ON.
refer to the index entry "PROFIBUS-DP - evaluate faults"

**0945:65  Fault code**

The fault code, i.e. the number of the fault which occurred, is entered in this parameter.

The faults which occurred are entered as follows into the fault buffer:

first fault which has occurred  --> parameter with index 1 (with index 0 for the PROFIdrive profile)
To
A  eighth fault which has occurred---> parameter with index 8 (with index 7 for the PROFIdrive profile)

Note:
The following is associated with a fault: Fault code (P0945:65), fault number (P0947:65), fault time (P0948:65) and fault value (P0949:65).

For "reset fault memory" the fault code, previously entered into P0945, is shifted by 8 indices.

The description of the faults, how they can be acknowledged as well as a list of all the faults is provided in Section "Fault handling / diagnostics".

This parameter is reset at POWER ON.
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.
refer to the index entry "PROFIBUS-DP - evaluate faults"

**0946:901  Fault code list**  

This parameter contains the fault code list.

In the fault code list, every fault code, defined in the unit, is assigned a fault number.

Note:
The fault number is a consecutive number. The actual value is coded in the fault code to indicate which fault has occurred.

If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.

This means that here, the fault code (e.g. 130) cannot be found in the sub-index (in the example 64) corresponding to the fault number, but instead in the following sub-index (in the example 65).

refer to the index entry "PROFIBUS-DP - evaluate faults"
0947:65  Fault number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

The fault number is entered into this parameter.

Note:
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile. refer to the index entry "PROFIBUS-DP – evaluate faults"

0948:65  Fault time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>ms</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

This parameter specifies at which relative system time the fault occurred.

Note:
This parameter is set to zero at POWER ON, and the time is then started. If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile. refer to the index entry "PROFIBUS-DP – evaluate faults"

0949:65  Fault value

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

The supplementary information about a fault which has occurred is entered into this parameter.

Note:
The description of the faults, how they can be acknowledged as well as a list of all the faults is provided in Section "Fault handling / diagnostics". This parameter is reset at POWER ON. If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile. refer to the index entry "PROFIBUS-DP – evaluate faults"

0951:301  Fault number list

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

Note: This parameter has no significance.

0952  Number of faults

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter specifies the number of faults which occurred after POWER ON. From SW 9.1 onwards, the parameter can be reset with P0952 = 0. When the parameter is reset, the fault buffer is cleared and the faults are acknowledged if the causes were resolved.

Note:
This parameter is reset at POWER ON. refer to the index entry "PROFIBUS-DP – evaluate faults"
### 0953  Warnings 800–815

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>RO</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 815) ... Bit 0 (warning 800)

Note:

- Bit x = 1 alarm yyy present
- Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

### 0954  Warnings 816–831

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>RO</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 831) ... Bit 0 (warning 816)

Note:

- Bit x = 1 alarm yyy present
- Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

### 0955  Warnings 832–847

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>RO</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 847) ... Bit 0 (warning 832)

Note:

- Bit x = 1 alarm yyy present
- Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

### 0956  Warnings 848–863

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>RO</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 863) ... Bit 0 (warning 848)

Note:

- Bit x = 1 alarm yyy present
- Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

### 0957  Warnings 864–879

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>RO</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 879) ... Bit 0 (warning 864)

Note:

- Bit x = 1 alarm yyy present
- Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"
## Warnings 880-895

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 895) ... Bit 0 (warning 880)

Note:

Bit x = 1 alarm yyy present

Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

## Warnings 896-911

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 911) ... Bit 0 (warning 896)

Note:

Bit x = 1 alarm yyy present

Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

## Warnings 912-927

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

The parameter displays which warning(s) is(are) present.

Bit 15 (warning 927) ... Bit 0 (warning 912)

Note:

Bit x = 1 alarm yyy present

Bit x = 0 the alarm assigned to the bit, is not present

refer to the index entry "PROFIBUS-DP – evaluate warnings"

## Baud rate PROFIBUS

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

... contains the actual PROFIBUS baud rate.

0 9.6 kbit/s
1 19.2 kbit/s
2 93.75 kbit/s
3 187.5 kbit/s
4 500 kbit/s
6 1500 kbit/s
7 3000 kbit/s
8 6000 kbit/s
9 12000 kbit/s
10 31.25 kbit/s
11 45.45 kbit/s

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SIMODRIVE 611 universal Function Manual (FBU) – 05/2010 Edition
**0964:11 Equipment identification**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... includes all data for the device identification and provides this to the Identify Utility.

Indices:

1. Company  
2. Drive type  
3. Firmware version  
4. Firmware date (year)  
5. Firmware date (day/month)  
6. Number of axes  
7. Patch number of the FW version

Product type:

1101 SIMODRIVE 611 universal 2 axis with 1Vpp encoder, n-set  
1102 SIMODRIVE 611 universal 2 axis with 1 Vpp encoder, positioning  
1103 SIMODRIVE 611 universal 2 axis with resolver, n-set  
1104 SIMODRIVE 611 universal 2 axis with resolver, positioning  
1105 SIMODRIVE 611 universal 1 axis with resolver, n-set  
1106 SIMODRIVE 611 universal 1 axis with resolver, positioning  
1111 SIMODRIVE 611 universalE 2 axis with 1Vpp encoder, n-set  
1112 SIMODRIVE 611 universalE HR 2-axis with 1Vpp encoder, positioning  
1120 SIMODRIVE 611 universal HR 2-axis with 1Vpp encoder, n-set  
1121 SIMODRIVE 611 universal HR 2-axis with 1Vpp encoder, positioning  
1122 SIMODRIVE 611 universal HR 2-axis with resolver, n-set  
1123 SIMODRIVE 611 universal HR 2-axis with resolver, positioning  
1124 SIMODRIVE 611 universal HR 1-axis with resolver, n-set  
1125 SIMODRIVE 611 universal HR 1-axis with resolver, positioning  
1126 SIMODRIVE 611 universal HR 1-axis with 1Vpp encoder, n-set  
1127 SIMODRIVE 611 universal HR 1-axis with 1Vpp encoder, positioning  
1130 SIMODRIVE 611 universalE HRS 2 axis with 1Vpp encoder, positioning  
1131 SIMODRIVE 611 universal HRS 2 axis with 1Vpp encoder, n set  
1132 SIMODRIVE 611 universal HRS 2 axis with resolver, n set  
1133 SIMODRIVE 611 universal HRS 2 axis with resolver, positioning  
1134 SIMODRIVE 611 universal HRS 1 axis with resolver, n set  
1135 SIMODRIVE 611 universal HRS 1 axis with resolver, positioning

**0965 Profile number, PROFIdrive**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

... the profile identification is saved here. Byte 1 contains profile number 3 (this corresponds to the PROFIdrive profile).

Profile version 3.1 --> byte 2 = 3  
Profile version 4.1 --> byte 2 = 41 (from SW 12.1)

**0967 PROFIBUS control word**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

The parameter is the image of control word STW1.  

Note:  

Bit assignment, refer to Section "Communications via PROFIBUS-DP"
0968  PROFIBUS status word

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

This parameter is the image of status word ZSW1.

Note:
Bit assignment, refer to Section "Communications via PROFIBUS-DP"

0969  Current time difference

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFFFF</td>
<td>ms</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... contains the relative system time since the last time that the drive was powered-up or the last reset of the parameter or since the last counter overflow.
The counter only increments in real time after booting has been completed (Alarm 819 inactive).

Note:
This parameter can only be read and reset, i.e. only a value of 0 can be written into it.

0972  Request POWER-ON RESET

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... a POWER-ON RESET can be requested on the control board.

0  Output status
1  Request POWER-ON RESET
2  Request preparation for POWER-ON RESET

The DP master can check as follows, whether the power-on reset was executed:
- write 2 into P0972 and read-back the value
- write 1 into P0972 --> POWER-ON RESET is requested

Read P0972 after communications have been established:
P0972 = 0? --> the POWER-ON RESET was executed
P0972 = 2? --> the POWER-ON RESET was not executed

Note:
After P0972=1, the link between the drive and SimoComU is interrupted with the following message: "Reading from the interface was interrupted due to time overflow". The link is re-established when SimoCom U is re-started.
0979:32  Encoder format

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... specifies the encoder properties.

Sub-indices:
1. Header
2. Encoder type (encoder 1)
3. Encoder resolution (encoder 1)
4. Shift factor for signal G1_XIST1 (encoder 1)
5. Shift factor for absolute values in G1_XIST2 (encoder 1)
6. Resolution can be parameterized (encoder 1)
7 to 11 reserved
12. Encoder type (encoder 2)
13. Encoder resolution (encoder 2)
14. Shift factor for signal G2_XIST1 (encoder 2)
15. Shift factor for absolute values in G2_XIST2 (encoder 2)
16. Resolution can be parameterized (encoder 2)
17 to 21 reserved
22. Encoder type (encoder 3)
23. Encoder resolution (encoder 3)
24. Shift factor for signal G3_XIST1 (encoder 3)
25. Shift factor for absolute values in G3_XIST2 (encoder 3)
26. Resolution can be parameterized (encoder 3)
27 to 31 reserved

Note:
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile. refer under the index entry "encoder interface"

0980:999  Number list_1  (→ 6.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

All of the parameter numbers defined in the drive are saved in parameters 980 – 989 from sub-index 1. The arrays are assigned consecutively without any gaps. If a sub-index contains a zero, then this is the end of the list of defined parameters. If a sub-index contains the parameter number of the next list parameter, then the list continues there.

Note:
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.

0981:100  Number list_2  (→ 6.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

All of the parameter numbers defined in the drive are saved in parameters 980 – 989 from sub-index 1. The arrays are assigned consecutively without any gaps. If a sub-index contains a zero, then this is the end of the list of defined parameters. If a sub-index contains the parameter number of the next list parameter, then the list continues there.

Note:
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.
All of the parameter numbers defined in the drive are saved in parameters 980 – 989 from sub-index 1. The arrays are assigned consecutively without any gaps. If a sub-index contains a zero, then this is the end of the list of defined parameters. If a sub-index contains the parameter number of the next list parameter, then the list continues there.

Note:
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.

### Number list_3

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

### Number list_4

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

### Number list_5

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

### Number list_6

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

### Number list_7

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>
All of the parameter numbers defined in the drive are saved in parameters 980 – 989 from sub-index 1. The arrays are assigned consecutively without any gaps. If a sub-index contains a zero, then this is the end of the list of defined parameters. If a sub-index contains the parameter number of the next list parameter, then the list continues there.

**Note:**
If this parameter is read via non-cyclic communication (PROFIdrive), then the indices have been shifted. Index 1 corresponds to Index 0 (etc.) in the description of the PROFIdrive profile.

### 1000 Current controller cycle

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>4</td>
<td>4</td>
<td>31.25μs</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Current controller clock cycle = P1000 x 31.25 microseconds

**Note:**
refer to the index entry "Clock cycles"

### 1001 Speed controller cycle

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>4</td>
<td>16</td>
<td>31.25μs</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Speed controller clock cycle = P1001 x 31.25 microseconds

**Note:**
Current controller clock cycle <= speed controller clock cycle
refer to the index entry "Clock cycles"
1004 Structure configuration

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>100</td>
<td>315</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... allows the closed-loop control structure to be configured.

Bit 4 Integrator control
Bit 4 = 1 Integrator control in the speed controller inactive
The integrator is not held, but its absolute value is limited to twice the torque limit.
Bit 4 = 0 Integrator control in the speed controller active
The integrator is held, if the speed controller, current controller or the voltage has reached its limit.

Bit 8 Fine interpolation in positioning mode (P0700 = 3) (from SW 3.1)
Bit 8 = 1 The fine interpolation type II is active (standard from SW 3.1)
Bit 8 = 0 Fine interpolation, type I is active (standard before SW 3.1)

Bit 9 Deadtime adjustment position ref. value coupling via PROFIBUS-DP
(from SW 4.1)
Bit 9 = 1 Same deadtime behavior as the slave drive (standard from SW 4.1)
Prerequisite: Drive is not a slave drive (P891 = --1)
Output of position reference value XsolIP (50208).
Bit 9 = 0 Minimum deadtime behavior (standard before SW 4.1)

1005 IM encoder pulse number (SRM ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2048</td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note:
IM ----> Indirect measuring system (motor encoder)
If the encoder pulse number cannot be divided by 10 or 16 without a remainder, the zero mark monitoring is internally disabled.

1006 IM encoder code number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

The encoder number defines the connected measuring system.
Note:
IM ----> Indirect measuring system (motor encoder)
refer to the index entry “Encoder code”

1007 DM encoder pulse number (SRM ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>8388607</td>
<td>-</td>
<td>Unsigned32</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note:
DM ----> Direct measuring system
Encoder pulses for indirect measuring system (IM, motor encoder) ----> refer to P1005
If the encoder pulse number cannot be divided by 10 or 16 without a remainder, the zero mark monitoring is internally disabled.

1008 IM encoder phase error correction

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-20.0</td>
<td>0.0</td>
<td>+20.0</td>
<td>Degree</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Phase position of track A with respect to track B can be corrected using this parameter.
Note:
IM ----> Indirect measuring system (motor encoder)
Track A must have a 90 degree offset to track B
### 1009 Position controller cycle

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>32</td>
<td>32</td>
<td>128</td>
<td>31.25μs</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Position controller clock cycle time (TLR) = P1009 x 31.25 microseconds

Note:
The position controller clock cycle must be an integer multiple of the speed controller clock cycle.
Refer to the index entry "Clock cycles"

---

### 1010 Interpolation cycle

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>64</td>
<td>128</td>
<td>640</td>
<td>31.25μs</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Interpolation clock cycle time (TIPO) = P1010 x 31.25 microseconds

Note:
The interpolation clock cycle must be an integer multiple of the position controller clock cycle.
Refer to the index entry "Clock cycles"
1011 \hspace{1cm} IM configuration, actual value sensing

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>F003</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... allows the actual value sensing to be configured for an indirect measuring system.

Bit 0: Invert speed actual value
- Bit 0 = 1: Inversion, speed actual value
- Bit 0 = 0: No inversion

Bit 1: Encoder phase failure correction
- Bit 1 = 1: Encoder phase failure correction
- Bit 1 = 0: No encoder phase error compensation

Bit 2: Resolver resolution
- Bit 2 = 1: Resolver resolution, 14 bits
- Bit 2 = 0: Resolver resolution, 12 bits

Note:
A resolver resolution of 14 bit can only be set with "SIMODRIVE 611 universal HR/HRS", otherwise fault 759 is output.

After changing the resolver resolution from 12 bits to 14 bits, the resolution of some signals at the analog output or DAU (D/A converter) changes - refer under the index entry "Resolver resolution".

The resolution displayed in SimoComU is always correct.

Bit 10: Plausibility monitoring, encoder (from SW 10.1)
- Bit 10 = 0: No rotor position check - default (up to SW 10.1)
- Bit 10 = 1: Automatic rotor position check permitted (from SW 10.1)

Bit 12: Coarse position identification
- Bit 12 = 1: Identify rough position
- Bit 12 = 0: No coarse position identification

Note:
This bit has no significance for EnDat encoders.
For encoders without hall sensors and without C/D track (e.g. ERN 1387), the rotor position identification replaces the coarse synchronization. The zero mark must still be adjusted (shift or via P1017).

Bit 13: Fine position identification
- Bit 13 = 1: The fine position is identified (with pole position identification)
- Bit 13 = 0: The fine position is not identified (fine synchronization with zero mark)

Note:
This bit has no significance for EnDat encoders.
The rotor position identification replaces the coarse synchronization using Hall sensors or a C/D track. The zero mark neither has to be present nor does it have to be adjusted.
If the rotor position identification does not offer satisfactory results, then the zero mark must be adjusted.

Bit 14: Data transfer rate EnDat, bit 0
Bit 15: Transmission rate EnDat, Bit 1

Note:
Bits 14 and 15 are set as follows in the factory:
- Bit 15, 14 = 00 --> 100 kHz (standard)
- Bit 15, 14 = 01 --> 500 kHz (setting possible)
- Bit 15, 14 = 10 --> 1 MHz (setting, Siemens-internal)
- Bit 15, 14 = 11 --> 2 MHz (Siemens internal setting)

IM --> Indirect measuring system (motor encoder)
refer to the index entry "List of encoders"
### 1012 Function switch

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>A185</td>
<td>F1F5</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0</td>
<td>A105</td>
<td>F1F5</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... allows the closed-loop control functions to be activated/de-activated.

**Note:**
Standard value for an activated PROFIBUS option module:
B185 (ARM)
B105 (SRM SLM)

- **Bit 0** Ramp-function generator tracking
  - Bit 0 = 1 active
  - Bit 0 = 0 inactive
  **Note:** refer to the index entry "Ramp-function generator"

- **Bit 2** Ready or no fault (at the output signal)
  - Bit 2 = 1 "Ready" signal
  - Bit 2 = 0 "No fault" message
  **Note:** refer to the index entry "output signal ready or no fault"

- **Bit 5** Suppress fault 753
  - Bit 5 = 1
  - Bit 5 = 0

- **Bit 7** IM speed actual value after pulse inhibit
  - Bit 7 = 1 Speed actual value is zero
  - Bit 7 = 0 Speed actual value is the speed setpoint
  The drive brakes the motor towards 0 speed and accelerates to the setpoint speed present.

- **Bit 8** Average value filter, speed setpoint
  - Bit 8 = 1 Average value filter on
  - Bit 8 = 0 Average value filter off
  The avg.val.filter to adapt the pos.contr.clock cyc. to the sp. contr. clock cyc. is active in the speedsetpoint branch.

- **Bit 12** Power-on inhibit for alarm and OFF2/OFF3
  - Bit 12 = 1 Power-on inhibit for alarm or OFF2/OFF3 or terminal 63/663 de-energized
  **Note:** The power-on inhibit is removed again by withdrawing the controller enable via terminal 65.x or PROFIBUS control signal STW1.0 (ON/OFF1).

- **Bit 13** Status signals (ZSW1) according to the PROFIdrive profile (only PROFIBUS operation)
  - Bit 13 = 1 Power-on inhibit signal is formed independently of the status of the ready signal (PROFIdrive definition)
    - The power-up inhibit signal is only set when the pulses have been cancelled after the braking phase.
    - The ready signal remains set during OFF1 and OFF3 until the pulses have been cancelled after the braking phase.
    - The ready to power-up signal remains set during OFF3 until the pulses have been cancelled after the braking phase.
  - Bit 13 = 0 The power-on inhibit signal is only set from 0 to 1 if the ready signal is set.
    - The power-up inhibit signal is also set if the pulses have still not been deleted while the drive is braking.
    - The ready signal is immediately cancelled at OFF1 or OFF3, even if the drive is still braking.
    - The ready to power-up signal is immediately deleted for OFF3, even if the drive is still braking.
  **Note:** The power-up inhibit is only effective for bit 12 = 1.
Bit 14: No power-on inhibit with simultaneous enable signals
Bit 14 = 1: Deviating from the PROFIdrive profile, a power-on inhibit is not initiated if OFF2/OFF3 and OFF1 are simultaneously withdrawn
Bit 14 = 0: The power-on inhibit is generated when OFF2/OFF3 and OFF1 are simultaneously withdrawn
Note: Bit 14 is only effective for bit 13 = 1.

Bit 15: “Reset fault memory” is not saved (no latching effect)
Bit 15 = 1: Corresponding to the PROFIdrive profile, a positive edge of the signal "reset fault memory" is not saved. It is only possible to acknowledge a fault after the cause of the fault has been resolved.
Bit 15 = 0: A positive edge of the signal "reset fault memory" is saved and results in the fault being acknowledged even if the problem is only then subsequently resolved.
Note: The positive signal edge is only saved as long as a fault is present.

1013 Enable motor changeover (ARM)  (-> 2.4)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

... the motor changeover is enabled or the motor changeover type is set.
0 Motor changeover inhibited
1 Motor changeover with pulse suppression
2 Motor changeover without pulse suppression (data set changeover)
3 Motor changeover with speed thresholds (P1247, P1248)

Note:
It is only possible to enable motor changeover in the "Speed/torque setpoint" mode (P0700 = 1) (refer to the index entry "Motor changeover").

1014 Activate V/f operation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... the V/f operation is activated/de-activated for this drive.
1 V/f operation is activated
0 V/f operation is de-activated

Note: refer to the index entry "V/f operation"

1015 Activate PE-MSD (SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO (SRM)</td>
</tr>
</tbody>
</table>

... the permanently excited spindle (PE spindle, 1FE1 motor) is activated/de-activated for this drive.
1 permanently excited spindle is activated
0 PE spindle is de-activated

Note:
For synchronous motors, field-weakening operation can be switched-in using P1015.
Refer under the index entry "Permanent-magnet synchronous motor with and without field weakening (PE spindle)" or FD operation with field weakening".
1016 Commutation angle offset (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-360.0</td>
<td>0.0</td>
<td>360.0</td>
<td>Degree</td>
<td>Floating Point</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>

... provides information about the rotor position.

To electrically commutate a synchronous motor, the closed-loop drive control must have data regarding the absolute rotor position (position of the magnets with respect to the stator or secondary part). This data (commutation angle) is determined at synchronization.

Incremental measuring system:
... specifies the offset for a zero mark.

Note:
If the zero mark to the rotor position was already adjusted in the factory, a 0 is located in P1016.

Absolute measuring system (EnDat encoder):
... specifies the angular offset to the position actual value of the EnDat encoder.

Note:
The angular offset is read out each time the drive runs up.

1017 Start-up support (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

1: Determine the commutation angular offset
0: Function is de-activated (normal status)
-1: EnDat encoder: Serial numbers are read-in in P1025/P1026

The angular commutation offset is automatically determined during start-up:

Incremental measuring system with a zero mark:
- set P1017 to 1
- Move the axis over the zero mark (e.g. with inching 1)
- -> the angular offset is automatically entered into P1016
- -> fault 799 (save parameters in FEPROM and HW-RESET required) is displayed
- Save parameters in the FEPROM (P0652 = 1)
- Carry-out a HW_RESET

Absolute measuring system (EnDat encoder) (also 1FN3 linear motors, if P1075=3)
- De-activate controller and pulse enable
- Set P1017 to 1 (note: If, for 1FN1, the EnDat serial number, read from the measuring system, is not equal to P0125/P1026, P1017 is automatically set to 1.)
- Switch in the controller and pulse enable
- -> The angular offset is automatically entered into P1016 and the encoder serial number of the encoder into P1025 and P1026
- -> fault 799 (save parameters in FEPROM and HW-RESET required) is displayed
- Save to FEPROM and carry-out a HW-RESET

Absolute measuring system (EnDat encoder) with 1FN3 linear motor if a rotor position identification technique is not used:
- Determine the rotor position difference between the normalized electrical rotor position and EMF_V using the appropriate measuring techniques.
- Add rotor position difference to P1016
- set P1017 to -1
- -> fault 799 (save parameters in FEPROM and HW-RESET required) is displayed
- Save to FEPROM and carry-out a HW-RESET

Note: refer under the index entry "Rotor position identification", "PE spindle" or "linear motor"
### 1018 IM pole pair number, resolver

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>12.0</td>
<td>18.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the pole pair number of the resolver used.

Examples:
- Resolver (pole pair number)
  - \(2p = 1\) (1 speed)
  - \(2p = 2\) (2 speed)
  - \(2p = 3\) (3 speed)
  - \(2p = 4\) (4-speed)

Note:
- IM --> Indirect measuring system (motor encoder)

### 1019 Current, rotor position ID (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>45.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the current with which the rotor position identification is executed. P1019 refers to the maximum motor current (P1104) and only represents an approximate value, which is exceeded or fallen short of during the identification, dependent on the iron saturation and the accuracy of P1116 (armature inductance).

If a value is entered in P1019 which is too low, then the rotor position identification routine is incorrect (fault 610). If the value is too high, the maximum permissible current can be exceeded (fault 501 or 612) or an inadmissibly high movement can occur (refer to P1020 and fault 611).

The optimum setting of P1019 can be determined by starting - as a test only - the function several times using P1736.

Note: Also refer under the index entry "PE spindle" or "Linear motor"

### 1020 Maximum rotation, rotor position identification (SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>5.0</td>
<td>10.0</td>
<td>mm</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the distance which has been traveled during rotor position identification without a fault being signaled.

Note:
- If the distance is greater than the value entered in P1020, fault 611 is signaled (illegal movement during rotor position identification).
- Angle (electrical) = angle (mechanical) * pole pair number (P1112)

### 1021 IM multi-turn resolution, absolute value encoder

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2048</td>
<td>65535</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Number of revolutions which can be resolved.

Note:
- IM --> Indirect measuring system (motor encoder)

### 1022 IM single-turn resolution, absolute value encoder

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>8192</td>
<td>4294967295</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Resolution of the absolute value encoder in measuring pulses per revolution.

Note:
- IM --> Indirect measuring system (motor encoder)
### 1023 IM diagnostics

<table>
<thead>
<tr>
<th>Bit</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>light source failed</td>
</tr>
<tr>
<td>1</td>
<td>signal amplitude too low</td>
</tr>
<tr>
<td>2</td>
<td>code connection erroneous</td>
</tr>
<tr>
<td>3</td>
<td>overvoltage</td>
</tr>
<tr>
<td>4</td>
<td>undervoltage</td>
</tr>
<tr>
<td>5</td>
<td>overcurrent</td>
</tr>
<tr>
<td>6</td>
<td>battery must be changed</td>
</tr>
<tr>
<td>7</td>
<td>control check error</td>
</tr>
<tr>
<td>8</td>
<td>EnDat encoder cannot be used</td>
</tr>
<tr>
<td>9</td>
<td>CD track for ERN1387 encoder erroneous or EQN encoder connected, or incorrectly parameterized (not on EQN, P1027.3)</td>
</tr>
<tr>
<td>10</td>
<td>protocol cannot be exited</td>
</tr>
<tr>
<td>11</td>
<td>No encoder connected, or incorrect encoder cable</td>
</tr>
<tr>
<td>12</td>
<td>TIMEOUT for measured value read</td>
</tr>
<tr>
<td>13</td>
<td>CRC error or parity error</td>
</tr>
<tr>
<td>15</td>
<td>defective measuring encoder</td>
</tr>
</tbody>
</table>

**Note:**
- IM –> Indirect measuring system (motor encoder)
- Bit 7 and 13 = 1 –> Incremental and absolute track do not match
- ERN: incremental encoder system
- EQN: absolute encoder system

### 1024 IM Grid spacing (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>8388607 nm</td>
<td>Unsigned32</td>
<td>PO (SLM)</td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- IM –> Indirect measuring system (motor encoder)

### 1025 IM serial number, low part (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF Hex</td>
<td>Unsigned16</td>
<td>PO (SRM SLM)</td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- IM –> Indirect measuring system (motor encoder)

### 1026 IM serial number, high part (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF Hex</td>
<td>Unsigned16</td>
<td>PO (SRM SLM)</td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- IM –> Indirect measuring system (motor encoder)
1027 | **IM configuration, encoder**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... allows the encoder evaluation to be configured for an indirect measuring system.

Bit 2  TTL encoder
Bit 3 absolute encoder (EnDat interface)
Bit 4  linear measuring system
Bit 5 operation without motor measuring system
Bit 6  Coarse synchronous track, electrical revolution
Bit 7 Distance-coded measuring system (from SW 4.1)
Bit 8  zero mark selection, fine synchronization using the position controller

---

Note: IM --> Indirect measuring system (motor encoder)

1029 | **Delayed measurement, rotor position identification (SRM SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100.0</td>
<td>ms</td>
<td>Floating Point immed.</td>
<td>(SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the additional delay time between the 60 individual measuring pulses to identify the rotor position.

Note: Also refer under the index entry "PE spindle" or "Linear motor"

1030 | **DM actual value sensing configuration**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... allows the actual value sensing to be configured for a direct measuring system.

Bit 2 Resolver resolution
Bit 2 = 1 Resolver resolution, 14 bits
Bit 2 = 0 Resolver resolution, 12 bits
Bit 14 Data transfer rate EnDat, bit 0
Bit 15 Transmission rate EnDat, Bit 1

Note:

Bits 14 and 15 are set as follows in the factory:
Bit 15, 14 = 00 --> 100 kHz (standard)
Bit 15, 14 = 01 --> 500 kHz (setting possible)
Bit 15, 14 = 10 --> 1 MHz (setting, Siemens-internal)
Bit 15, 14 = 11 --> 10 MHz (setting, Siemens-internal)

DM --> Direct measuring system (motor encoder)

---

Refer to the index entry "List of encoders"  

1031 | **DM multi-turn resolution, absolute value encoder**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Number of revolutions which can be resolved.

Note:

DM --> Direct measuring system

Revolutions which can be resolved for indirect measuring system (IM, motor encoder) --> refer to P1021
1032  DM single-turn resolution, absolute value encoder  (→ 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4294967295</td>
<td>-</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

Resolution of the absolute value encoder in measuring pulses per revolution.

Note:
DM  →  Direct measuring system
Single-turn resolution for indirect measuring system (IM, motor encoder)  →  refer to P1022

1033  DM diagnostics  (→ 3.3)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>light source failed</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1</td>
<td>signal amplitude too low</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>code connection erroneous</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>3</td>
<td>overvoltage</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>4</td>
<td>undervoltage</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>5</td>
<td>overcurrent</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>6</td>
<td>battery must be changed</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>7</td>
<td>control check error</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>8</td>
<td>EnDat encoder cannot be used</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>CD track for ERN1387 encoder erroneous or EQN encoder connected, or incorrectly parameterized (not on EQN, P1027.3)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>10</td>
<td>protocol cannot be exited</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>11</td>
<td>No encoder connected, or incorrect encoder cable</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>12</td>
<td>TIMEOUT for measured value read</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>13</td>
<td>CRC error, parity bit</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>14</td>
<td>defective measuring encoder</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Note:
DM  →  Direct measuring system
Diagnostics for indirect measuring system (IM, motor encoder)  →  refer to P1023
Bit 7 and 13 = 1  →  Incremental and absolute track do not match
ERN: incremental encoder system
EQN: absolute encoder system

1034  DM grid spacing  (→ 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>4294967295</td>
<td>nm</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

Note:
DM  →  Direct measuring system

1036  DM encoder code number  (→ 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>65535</td>
<td>-</td>
<td></td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

The encoder number defines the connected measuring system.

Note:
DM  →  Direct measuring system
Encoder code for indirect measuring system (IM, motor encoder)  →  refer to P1006
refer to the index entry "Encoder code"
1037  **DM encoder configuration**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... allows the encoder evaluation to be configured for a direct measuring system.

Bit 2  TTL encoder
Bit 3  absolute encoder (EnDat interface)
Bit 4  linear measuring system
Bit 5  Operation without direct measuring system
Bit 7  Distance-coded measuring system (from SW 4.1)

Note:
DM --> Direct measuring system
Configuration of the indirect measuring system (IM, motor encoder) --> refer to P1027

1038  **DM serial number, low part (SRM SLM)**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Note:
DM --> Direct measuring system

1039  **DM serial number, high part (SRM SLM)**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Note:
DM --> Direct measuring system

1040  **DM pole pair number, resolver**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>64</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the pole pair number of the resolver used.

Examples:
Resolver  (pole pair number)
2p = 1  (1 speed)
2p = 2  (2 speed)
2p = 3  (3 speed)
2p = 4  (4-speed)

Note:
DM --> Direct measuring system
Pole pair number for indirect measuring system (IM, motor encoder) --> refer to P1018

1042  **Encoder 1 fine resolution G1_XIST1**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>11</td>
<td>11</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines how many fine resolution bits are transferred for the PROFIBUS encoder interface.

This parameter applies for the following:
- Fine resolution for process data G1_XIST1
- Fine resolution for G1_XIST2 for reference mark or flying measurement
A.1 Parameter list

1043  Encoder 1 fine resolution, absolute track G1_XIST2  (-> 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>9</td>
<td>11</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines how many fine resolution bits are transferred for the PROFIBUS encoder interface. This parameter applies for the fine resolution of process data G1_XIST2 when reading the absolute value.

Note:
The parameter is only valid for the absolute track of the absolute value encoder. The fine resolution for the value display for reference mark or flying measurement is defined in P1042.

1044  Encoder 2 fine resolution G2_XIST1  (-> 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>11</td>
<td>11</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines how many fine resolution bits are transferred for the PROFIBUS encoder interface. This parameter applies for the following:
- Fine resolution for process data G2_XIST1
- Fine resolution for G2_XIST2 for reference mark or flying measurement

1045  Encoder 2 fine resolution, absolute track G2_XIST2  (-> 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>9</td>
<td>11</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... defines how many fine resolution bits are transferred for the PROFIBUS encoder interface. This parameter applies for the fine resolution of process data G2_XIST2 when reading the absolute value.

Note:
The parameter is only valid for the absolute track of the absolute value encoder. The fine resolution for the value display for reference mark or flying measurement is defined in P1044.

1049  Active EMF brake (SRM SLM)  (-> 9.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>

... enables the electric brake when the encoder fails.

Note:
For a detailed description refer under the index entry "Electrical braking when the encoder fails"

1050  IM reference mark clearance for distance-coded scales  (-> 4.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>4294967295</td>
<td>μm</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the basic clearance between two fixed reference marks. If the closed-loop identifies that the distance between each second reference mark is different and is therefore incorrect, the axis remains stationary. Fault 508 (zero mark monitoring, motor measuring system) is signaled.

Note:
IM ----> Indirect measuring system (motor encoder)
This monitoring function is only activated if P1050/P1024*1000 can either be divided by 16 or by 10.
### 1051 IM ref. mark clearance for distance-coded rotary encoders

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>4294967295</td>
<td>mDegree</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

...specifies the basic clearance between two fixed reference marks. If the closed-loop identifies that the distance between each second reference mark is different and is therefore incorrect, the axis remains stationary. Fault 508 (zero mark monitoring, motor measuring system) is signaled.

Note:
IM ---> Indirect measuring system (motor encoder)
This monitoring function is only activated if P1051/1000*P1005/360 can either be divided by 16 or by 10.

### 1052 DM reference mark distance for distance-coded scales

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>4294967295</td>
<td>μm</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

...specifies the basic clearance between two fixed reference marks. If the closed-loop identifies that the distance between each second reference mark is different and is therefore incorrect, the axis remains stationary. Fault 514 (zero mark monitoring, direct measuring system) is signaled.

Note:
DM ---> Direct measuring system
This monitoring function is only activated if P1052/P1034*1000 can either be divided by 16 or by 10.

### 1053 DM ref. mark distance for distance-coded rotary encoders

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>20000</td>
<td>4294967295</td>
<td>mDegree</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

...specifies the basic distance between two fixed reference marks. If the control recognizes that the distance between each second reference mark differs, and is therefore incorrect, the axis remains stationary. Fault 514 (zero mark monitoring, direct measuring system) is signaled.

Note:
This monitoring function is only activated if P1053/1000*P1007/360 can either be divided by 16 or by 10.

### 1054 IM difference for distance-coded encoders

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>20.0</td>
<td>500000.0</td>
<td>μm</td>
<td>Floating Point</td>
<td>PO (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>20.0</td>
<td>450000.0</td>
<td>mDegree</td>
<td>Floating Point</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

...specifies the change of the difference between two reference marks for distance-coded encoders, indirect measuring system (motor measuring system).

### 1055 DM difference for distance-coded encoders

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>20.0</td>
<td>500000.0</td>
<td>μm</td>
<td>Floating Point</td>
<td>PO (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>20.0</td>
<td>450000.0</td>
<td>mDegree</td>
<td>Floating Point</td>
<td>PO (SRM ARM)</td>
</tr>
</tbody>
</table>

...specifies the change of the difference between two reference marks for distance-coded encoders, direct measuring system.

### 1058 IM zero mark distance for linear encoders

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>500000</td>
<td>10000000</td>
<td>μm</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

...specifies the distance between two reference marks for indirect, linear measuring systems.
<table>
<thead>
<tr>
<th>Parameter List</th>
<th>Data Type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>DM zero mark distance for a linear encoder</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
<tr>
<td>Rotor position identification technique (SRM SLM)</td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
<tr>
<td>Load moment of inertia RLI (SRM)</td>
<td>FloatingPoint</td>
<td>immed. (SRM)</td>
</tr>
<tr>
<td>Integral action time, RLI controller (SRM SLM)</td>
<td>FloatingPoint</td>
<td>immed. (SRM SLM)</td>
</tr>
<tr>
<td>Max. duration, rotor position identification. (SRM SLM)</td>
<td>FloatingPoint</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

---

**1059 DM zero mark distance for a linear encoder**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>500000</td>
<td>10000000</td>
<td>μm</td>
<td>Unsigned32</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the distance between two reference marks for direct, linear measuring systems.

**1075 Rotor position identification technique (SRM SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the rotor position identification technique.

1. Rotor position identification based on the saturation technique
2. Rotor position identification using the motion-based technique

P1075 is pre-assigned as follows at each "calculate controller data":

- -> 1FN3 motors: P1075 = 3
- -> all other motors: P1075 = 1

If the rotor position identification is successful, the contents of P1075 are copied into P1734 for diagnostics.

Note:
P1075 is immediately effective. However, if the drive is waiting for enable signals in order to carry-out a rotor position identification routine, a change made to P1075 only becomes effective at the next attempt (the identification routine is already running in the wait state).

For a detailed description refer under the index entry "Rotor position identification" or "pole position identification"

**1076 Load moment of inertia RLI (SRM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-10000.0</td>
<td>0.0</td>
<td>10000.0</td>
<td>kg</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>-500.0</td>
<td>0.0</td>
<td>500.0</td>
<td>kgm²</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

... defines the additional moment of inertia (SRM) or additional mass (SLM) which is used to set the controller parameters for the motion-based rotor position identification.

**1077 Integral action time, RLI controller (SRM SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>3.7</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the integral action time of the controller for the rotor position identification. If P1077 is set to 0, then the I component of the controller is displayed. For "Calculate controller data", P1077 is re-calculated and pre-assigned.

**1078 Max. duration, rotor position identification. (SRM SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>100.0</td>
<td>800.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the maximum time of an individual measurement for the rotor position identification. If this time is exceeded for an individual measurement, then fault 610 (rotor position identification not successful) is signaled and P1734 is set to -6.
1080  Calculate controller data

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Suitable settings for the control parameters are calculated from the motor parameters and several other parameters using this function.

0  ->  1  Controller data are being calculated, function is active
0  Function inactive or completed correctly

Error codes
-15 Magnetizing reactance (P1141) = 0
-16 Leakage reactance (P1139 / P1140) = 0
-17 Rated motor frequency (P1134) = 0
-18 Rotor resistance (P1138) = 0
-19 Moment of inertia (P1117+P1123) <= 0
-21 threshold speed for field weakening (P1142) = 0
-22 Motor stall current (P1118) = 0
-23 The ratio between the maximum motor current (P1104) and the motor stall current (P1118) is greater than the maximum value for the torque limit (P1230) and the power limit (P1235).
-24 The ratio between the rated motor frequency (P1134) and the rated motor speed (P1400) is inadmissible (pole pair number)

Note:
Recommendation: Execute this function using SimoCom U because the calculated parameters are displayed and are only accepted and overwritten after confirmation.

At the end of the calculation, the parameters are automatically reset to 0 or an error code is written into it.

When an error occurs, the parameters for the current controller, flux controller and speed controller could not be optimally pre-assigned. The standard values were entered.

After the cause of the error is resolved, the function can be re-started.
1081  Calculate equivalent circuit diagram data (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Procedure for third-party motor:
- Select "third-party motor" for the first start-up (refer to the index entry "Motor code")
- Enter all rating plate data
- Calculate the equivalent circuit diagram data via P1081 = 1

Note:
After the "Calculate equivalent circuit diagram data", a "Calculate third-party motor" should be carried out (P1082).
A 0 or another error code is automatically written into the parameter at the end of the calculation.

0 -> 1 Equivalent circuit diagram data are being calculated, function is active
0   Function inactive or completed correctly

Error codes
-51 Rated motor output (P1130) = 0
-52 Rated motor voltage (P1132) = 0
-53 Rated motor current (P1103) = 0
-54 Cos phi (P1129) = 0 or > 0.996
-55 The ratio between the rated motor frequency (P1134) and the rated motor speed (P1400) is inadmissible (pole pair number)
-56 Warning: The threshold speed for field weakening (P1142) < rated motor speed (P1400)
-57 The function is only permissible for third-party motors (P1102 = 99)

Note:
In the case of an error, no equivalent circuit diagram data were changed (exception: code -56).

1082  Calculate third-party motor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the "Calculate unlisted motor" function is started. Parameters P1105 (only SRM), P1147, P1241, P1401 are pre-assigned, the "calculate controller data" function executed and the appropriate unlisted motor code entered into P1102.

By entering the third-party motor code in P1102, at the next POWER ON, possibly changed motor data will no longer be overwritten by the catalog motor data (previous motor code).

0 -> 1 Third-party motor is being calculated, function is active
0   Function in inactive

Procedure for third-party motor:
Are all of the equivalent circuit diagram data known?
- if no: Calculate the equivalent circuit diagram data via P1081
- if yes: Enter all of the equivalent circuit diagram data and set P1082 to 1

Note:
At the end of the calculation, the parameter is automatically reset to 0 or an error code is written into it (refer to P1080).
1083  Function selection, motor data optimization (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>4</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

... the function number for motor data optimization is entered.

1 Calculate leakage inductance and rotor resistance
2 Calculate no-load current and magnetizing reactance
3 Calculate field-weakening speed
4 Calculate moment of inertia

Perform motor data optimization:

Step 1
P1083 = 1 and start with P1084 = 1 (if not 0, then evaluate the error code)
Calculated and written parameters: P1136, P1137, P1138, P1139, P1140, P1141

Step 2
P1083 = 2 and start with P1084 = 1 (if it is not 0, evaluate error code)
Calculated and written parameters: P1136, P1141

Step 3
P1083 = 3 and start with P1084 = 1 (if it is not 0, evaluate error code)
Calculated and written parameters: P1142

Step 4
P1083 = 4 and start with P1084 = 1 (if it is not 0, evaluate error code)
Calculated and written parameters: P1117

Note:
For a detailed description, please refer to the index entry "Motor data optimization".

1084  Start motor data optimization (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Integer16</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

The function is selected using P1083 and is started by setting P1084 to 1.
A 0 or another error code is automatically written into the parameter at the end of the calculation.

1 Function is active
0 Function inactive or completed correctly

Error codes
-2 Pulse frequency (P1100) of 4 kHz or 8 kHz required
-3 Controller / pulse enable missing
-4 Speed setpoint <> 0
-5 Motor changeover is currently active
-6 Error when determining the leakage inductance (result < 0)
-7 V/f operation is active
-8 The incorrect motor was selected by the motor changeover
-9 Parameterized maximum speed is too low for the measurement
-10 Power-up inhibit
-11 Changeover speed open-loop / closed-loop control is too large (P1466)
-12 Speed range too low (P1466 or P1160 too large)
-13 Ramp-function generator enable missing
-14 Open-loop torque-controlled operation is selected
-15 Motor data optimization for catalog motor illegal (from SW 3.3)
-16 If the current is too high, it is limited by the i2t power module model
1094  Derating, ambient temperature  
\[\text{(-} \rightarrow 13.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>30</td>
<td>40</td>
<td>55</td>
<td>°C</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the ambient temperature in Degrees Celsius for the power unit derating.  
When powering up, the currently effective derating factor is calculated as a function of the pulse frequency, the ambient temperature (P1094), the installation altitude (P1095) and the derating factor X1. It can be seen in display data P1099.  
Note: also refer to P1095, P1178 or P1179

1095  Derating, installation altitude  
\[\text{(-} \rightarrow 13.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.000000</td>
<td>1000.000000</td>
<td>5000.000000</td>
<td>m</td>
<td>Floating Point</td>
<td>PO</td>
</tr>
</tbody>
</table>

... specifies the installation altitude in meters for the power unit derating.  
When powering up, the currently effective derating factor is calculated as a function of the pulse frequency, the ambient temperature (P1094), the installation altitude (P1095) and the derating factor X1. It can be seen in display data P1099.  
Note: also refer to P1095, P1178 or P1179

1096  Red. max. torque for regenerative stop active  
\[\text{(-} \rightarrow 9.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... configures the torque reduction for a speed setpoint of zero.  
Bit 0: The torque limit is reduced for regenerative braking  
Bit 0 = 1: The limit torque is reduced for a regenerative stop with a speed setpoint of zero.  
Note: For EMF brakes, the torque is always reduced with P1097.  
Bit 0 = 0: inactive  
Bit 1: Disable monitoring for speed controller at its end stop so that the regenerative stop - that takes longer due to the reduced torque - is not interrupted by the monitoring function cancelling the pulses  
Note: For EMF brakes, the speed controller at its limit monitoring function is always disabled.  
Bit 1 = 1: not active  
Bit 1 = 0: Monitoring, speed controller at its limit for torque reduction  
Bit 2 - 15: Reserved  
Note: Refer under index entry "Faults, stop responses"

1097  Red. max. torque for regenerative stop  
\[\text{(-} \rightarrow 9.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>80</td>
<td>100</td>
<td>%</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the torque reduction for a speed setpoint of zero.  
Note: Refer under index entry "Faults, stop responses"
### 1099 Limiting factor, power section currents

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

the following applies before SW 13.1:
... displays the limiting factor for the power section currents (P1108, P1109, P1111) as a function of the pulse frequency (P1100).

from SW 13.1, the following applies:
... indicates the limit factor for the power unit currents (P1108, P1109, P1111).
When booting, the currently effective limit factor is calculated depending on the pulse frequency (P1100), the ambient temperature (P1094), the installation altitude (P1095) and derating factor X1.

Note: Refer under the index entry "Power unit currents"

### 1100 Pulse width modulation frequency

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2000.0</td>
<td>3200.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
<tr>
<td>2000.0</td>
<td>4000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines the clock frequency of the inverter.
We recommend the following frequencies: 2000, 2666, 3200, (4000), 5333, 6400 and (8000) Hz.

For low-leakage or high-speed third-party motors (motor frequency > 500 Hz) it makes sense to increase the switching frequency.

Further, it may make sense to change the switching frequency to reduce motor noise.

Note:
The frequencies specified in brackets are preferred values - intermediate values can also be set.

For IM operation (ARM without encoder), only frequencies of 4000 and 8000 Hz are permitted.
The current rating of the drive converter is reduced when the frequency is increased. This must already be taken into account when dimensioning the power section (refer to the de-rating characteristic).

### 1101 Calc. deadtime current control loop

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>124</td>
<td>µs</td>
<td>Integer16</td>
<td>PO</td>
</tr>
</tbody>
</table>

Note: Internal Siemens Firmware checks the setting at run-up and is automatically changed.

### 1102 Motor code number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

The motor code number describes the connected motor according to a table.

Note: refer to the index entry "Motor code"

### 1103 Rated motor current

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>A(rms)</td>
<td>Floating Point</td>
<td>PO</td>
</tr>
</tbody>
</table>

### 1104 Maximum motor current (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.04</td>
<td>500.0</td>
<td>A(rms)</td>
<td>Floating Point</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>
### A.1 Parameter list

#### 1105 Reduction in maximum motor current (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>100</td>
<td>100</td>
<td>%</td>
<td>Integer16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... reduces the maximum motor current (P1104) to the specified percentage.

**Note:**
If the motor current is at its limit, the monitoring intervenes with P1605/P1606.

#### 1106 Power section code number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td></td>
<td>65535</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO</td>
</tr>
</tbody>
</table>

The power section code number defines the power section used.

**Power section without automatic identification:**
The module code must be selected from a table, and at first start-up, entered into P1106 (refer under index entry "power section code").

**Power section with automatic identification:**
At the first start-up, the power section code of the power section used is automatically entered in P1106.

If the value in P1106 and the value of the detected power section in P1110 differ when the drive runs-up, then an appropriate fault is output.

**Power module Order No. [MLFB]power module code**

- 6SN112x-1Ax0x-0HAx 1
- 6SN112x-1Ax0x-0AAx 2
- 6SN112x-1Ax0x-0BAx 4
- 6SN112x-1Ax0x-0CAx 6
- 6SN112x-1Ax0x-0DAx 7
- 6SN112x-1Ax0x-0GAx 8 (only for PE spindle)
- 6SN112x-1Ax0x-0EAx 9
- 6SN112x-1Ax0x-0FAx 10
- 6SN112x-1Ax0x-0JAx 11 (only for PE spindle)
- 6SN112x-1Ax0x-0KAx 12
- 6SN112x-1Ax0x-0LAx 13 (only for PE spindle)

#### 1107 Transistor limiting current

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td></td>
<td>-</td>
<td>A(pk)</td>
<td>FloatingPoint</td>
<td>RO</td>
</tr>
</tbody>
</table>

... specifies the maximum transistor limiting current of the power section as peak value.

**Important:**
This parameter is used as normalization basis for the current actual value sensing.

**Note:** refer to the index entry "Power section currents"
### 1108 Limiting current, power section (RMS)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td>A(rms)</td>
<td>FloatingPoint</td>
<td>RO</td>
</tr>
</tbody>
</table>

Before SW 2.4, the following is valid:

- Displays the limiting current of the power section (I-max in A RMS) at the selected pulse frequency (P1100).

From SW 2.4 and before SW 13.1, the following applies:

- Displays the power section limiting current (I_max in A RMS) for the standard pulse frequency setting (P1100). The reduction factor for higher pulse frequencies is displayed in P1099.

From SW 13.1, the following applies:

- Indicates the limit current of the power unit (I-max. in A rms) for the default setting of the pulse frequency (P1100), ambient temperature (P1094) and installation altitude (P1095). The reduction factor at higher pulse frequencies, ambient temperatures or installation altitudes is displayed in P1099.

Note: refer to the index entry "Power section currents"

### 1109 Limiting current, power section S6 (RMS)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td>A(rms)</td>
<td>FloatingPoint</td>
<td>RO</td>
</tr>
</tbody>
</table>

Before SW 2.4, the following is valid:

- Displays the limiting current of the power section in S6 duty (I-s6 in A RMS) at the selected pulse frequency (P1100).

From SW 2.4 and before SW 13.1, the following applies:

- Displays the power section limiting current in S6 duty (I-S6 in A RMS) for the standard pulse frequency setting (P1100). The reduction factor for higher pulse frequencies is displayed in P1099.

From SW 13.1, the following applies:

- Indicates the limit current of the power unit in S6 duty (I-S6 in A rms) for the default setting of the pulse frequency (P1100), ambient temperature (P1094) and installation altitude (P1095). The reduction factor for higher pulse frequencies, ambient temperatures or installation altitudes is displayed in P1099.

Note: refer to the index entry "Power section currents"

### 1110 Power section version

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... Displays which power section was identified at run-up.

0  Power section without automatic identification
> 0  Power section with automatic identification

The code of the identified power section is in P1110 and must coincide with the code entered into P1106 (power section code number).

Note: Assignment, power module code number, refer to P1106
A.1 Parameter list

1111 Rated current, power section (RMS)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>A(rms)</td>
<td>Floating Point</td>
<td>RO</td>
<td></td>
</tr>
</tbody>
</table>

before SW 2.4, the following is valid:
... displays the rated current of the power section (I-rated in A RMS) at the selected pulse frequency (P1100).

from SW 2.4 and before SW 13.1, the following applies:
... displays the rated current of the power section (I-rated in A RMS) for the standard pulse frequency setting (P1100). The reduction factor for higher pulse frequencies is displayed in P1099.

from SW 13.1, the following applies:
... indicates the rated current of the power unit (I rated in A rms) for the default setting of the pulse frequency (P1100), ambient temperature (P1094) and installation altitude (P1095). The reduction factor for higher pulse frequencies, ambient temperatures or installation altitudes is displayed in P1099.

Note: refer to the index entry “Power section currents”

1112 No. of pole pairs of motor (SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4096</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO (SRM)</td>
</tr>
</tbody>
</table>

1113 Torque constant (SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>2000.0</td>
<td>N/A</td>
<td>Floating Point</td>
<td>PO (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>300.0</td>
<td>Nm/A</td>
<td>Floating Point</td>
<td>PO (SRM)</td>
</tr>
</tbody>
</table>

SRM:
The torque constant (kT) is the quotient of rated torque/rated current (RMS) for synchronous motors with permanent excitation.

SLM:
The force constant is the quotient of the rated force/rated current (RMS) for linear permanent-magnet synchronous motors.

1114 Voltage constant (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>10000.0</td>
<td>Vs/m</td>
<td>Floating Point</td>
<td>PO (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>10000.0</td>
<td>V(RMS)</td>
<td>Floating Point</td>
<td>PO (SRM)</td>
</tr>
</tbody>
</table>

SRM:
The voltage constant is measured as induced voltage (EMF) under no load conditions at n = 1000 RPM as RMS value between the motor terminals (phase-to-phase).

SLM:
The voltage constant is measured as induced voltage (EMF) under no load conditions at v = 1 m/s as RMS value between the motor terminal and star point (phase).

1115 Armature resistance (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>999.999</td>
<td>Ohm</td>
<td>Floating Point</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>

... specifies the ohmic resistance of a phase of the armature winding (phase value) at 20 Degrees.

For 1FN1 and 1FN3 linear motors, the resistance value at 120 Degrees (operating temperature) is entered.
The winding is in the star circuit configuration.
### 1116 Armature inductance (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>300.0</td>
<td>mH</td>
<td>Floating Point</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>

Inductance in the armature circuit for the single-phase equivalent circuit diagram.

### 1117 Moment of inertia of motor (ARM SRM)

#### Motor mass (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.001</td>
<td>9.99999</td>
<td>kgm$^2$</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>500.0</td>
<td>kg</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
<td></td>
</tr>
<tr>
<td>0.0</td>
<td>9.99999</td>
<td>kgm$^2$</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
<td></td>
</tr>
</tbody>
</table>

SRM, ARM: Moment of inertia of the motor rotor
SLM: Weight of the primary section

### 1118 Motor zero-speed current (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>A(rms)</td>
<td>Floating Point</td>
<td>PO (SRM SLM)</td>
</tr>
</tbody>
</table>

... corresponds to the thermally permissible continuous current when the motor is at a standstill with an overtemperature (temperature rise) of 100 Kelvin.

### 1119 Series reactor inductance (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>65.0</td>
<td>mH</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

### 1120 Current controller P gain

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>10000.0</td>
<td>U/A</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

### 1121 Current controller reset time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>3000.0</td>
<td>8000.0</td>
<td>μs</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>μs</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

### 1122 Motor current limit (SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.04</td>
<td>500.0</td>
<td>A(rms)</td>
<td>Floating Point</td>
<td>PO (SRM)</td>
</tr>
</tbody>
</table>

### 1123:8 Load moment of inertia (ARM SRM)

#### Load weight (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>kg</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>9.99999</td>
<td>kgm$^2$</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

Additional moment of inertia (SRM, ARM) and additional weight (SLM), which is caused by coupling a load to the motor. The contents of P1123:8 are added to the contents of P1117 for the speedtorque feedforward control in induction motor operation and for the "calculate controller data" function.

### 1124 Symmetrizing reference model current

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.5</td>
<td>1.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens
### 1125 Ramp-up time 1 for V/f operation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.01</td>
<td>5.0</td>
<td>100.0</td>
<td>s</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

When V/f operation is selected (P1014), this is the time, in which the speed setpoint is changed from 0 to the maximum motor speed (P1146).

### 1127 Voltage at f = 0 V/f operation (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2.0</td>
<td>20.0</td>
<td>V(pk)</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

### 1128 Optimum load angle (SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>90.0</td>
<td>90.0</td>
<td>135.0</td>
<td>Degree</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

For synchronous motors with non-symmetrical rotors in the rotational axis, the additional reluctance torque can be used to increase the torque.

The optimum load angle specifies at which load angle the torque reaches its maximum value at 150% rated current.

**Note:**
- Refer to P1149 (reluctance torque constant)
- Synchronous motors with non-symmetrical rotor in the rotational axis: e.g. 1FE motors
- Traverse with reluctance torque: P1128 and P1149 not equal to the standard value
- Traverse without reluctance torque: P1128 and P1149 equal to the standard value

### 1129 Cosine Phi power factor (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.8</td>
<td>1.0</td>
<td>-</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

### 1130 Rated motor power (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1500.0</td>
<td>kW</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

### 1132 Rated motor voltage (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>380.0</td>
<td>5000.0</td>
<td>V(RMS)</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

### 1134 Rated motor frequency (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>50.0</td>
<td>3000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

### 1135 Motor no-load voltage (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>V(RMS)</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

### 1136 Motor no-load current

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>A(rms)</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

P1136 (motor short-circuit current) --> this is the parameter name for SRM
P1136 (no-load motor current) --> this is the parameter name for ARM

### 1137 Stator resistance cold (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>120.0</td>
<td>Ohm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

### 1138 Rotor resistance cold (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>120.0</td>
<td>Ohm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>Parameter</td>
<td>Description</td>
<td>Min</td>
<td>Standard</td>
<td>Max</td>
<td>Unit</td>
</tr>
<tr>
<td>-----------</td>
<td>-------------</td>
<td>-----</td>
<td>----------</td>
<td>-----</td>
<td>------</td>
</tr>
<tr>
<td>1139</td>
<td>Stator leakage reactance (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>Ohm</td>
</tr>
<tr>
<td>1140</td>
<td>Rotor leakage reactance (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>Ohm</td>
</tr>
<tr>
<td>1141</td>
<td>Magnetizing reactance (ARM)</td>
<td>0.0</td>
<td>0.0</td>
<td>999.999</td>
<td>Ohm</td>
</tr>
<tr>
<td>1142</td>
<td>Threshold speed field weakening (ARM SRM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>Motor threshold speed for field weakening (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1145</td>
<td>Stall torque reduction factor</td>
<td>5.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
</tr>
<tr>
<td>1146</td>
<td>Maximum motor speed (ARM SRM) Maximum motor velocity (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>... specifies the maximum motor speed/maximum motor velocity defined by the motor manufacturer.</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1147</td>
<td>Speed limitation (ARM SRM) Velocity limiting, motor (SLM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1148</td>
<td>Threshold speed stall power (ARM)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

The rated output is reduced from the "Threshold speed of the stall power".

---

Note:
Refer under the index entry "Limits"
### 1149  Reluctance torque constant (SRM)  (→ 3.3)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-300.0</td>
<td>0.0</td>
<td>300.0</td>
<td>mH</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

For synchronous motors with non-symmetrical rotors in the rotational axis, the additional reluctance torque can be used to increase the torque. The reluctance torque constant, multiplied by the torque- and field-generating current, gives the torque increase due to the reluctance torque.

Note:
Refer to P1128 (optimum load angle)
Synchronous motors with non-symmetrical rotor in the rotational axis: e.g. 1FE motors
Traverse with reluctance torque: P1128 and P1149 not equal to the standard value
Traverse without reluctance torque: P1128 and P1149 equal to the standard value

### 1150  P-gain flux controller

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>400.0</td>
<td>99999.9</td>
<td>A/Vs</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

### 1151  Reset time flux controller

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

### 1152  Minimum DC link voltage, dyn. energy management  (→ 13.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>800</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the permissible lower limit for the DC link voltage, dynamic energy management.

Note:
This parameter is only effective if dynamic energy management is activated via P1155.

### 1153  Maximum DC link voltage dynamic energy management  (→ 13.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>800</td>
<td>800</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the permissible upper limit for the DC link voltage, dynamic energy management.
Fault 617 is output when exceeded.

Note:
This parameter is only active if dynamic energy management is activated via P1155.

### 1154  only VDClink monitoring from motor speed  (→ 13.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM SRM)</td>
</tr>
</tbody>
</table>

... specifies the speed setpoint, which when exceeded, only the DC link voltage is monitored and no longer the motor temperatures.
The normal functionality is restored if the response threshold is fallen below again.
This parameter is only active if dynamic energy management has been set - P1155.bit0 = 1 (= active).

Note:
This parameter is only active if dynamic energy management is activated via P1155.
### A.1 Parameter list

#### 1155 Dyn. energy manag. act.  
(\(\rightarrow 13.1\))

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... activates/deactivates the dynamic energy management.  
The dynamic energy management allows the infeed/regenerative feedback unit to be adapted to the system concept in-line with the actual requirements.  
**Bit 0** Dynamic energy management  
**Bit 0 = 0** inactive  
**Bit 0 = 1** active  
**Bit 1** Dynamic energy management function only effective for regenerative braking  
**Bit 1 = 0** Not active  
**Bit 1 = 1** Active

#### 1160 Threshold speed flux sensing (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>200.0</td>
<td>1500.0</td>
<td>10000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

... a fixed DC link voltage can be entered.  
> 0  Fixed DC link voltage, the measurement in P1701 (DC link voltage) is inactive  
0  The measurement in P1701 is active  
The fixed DC link reference is calculated in instead of the measurement:  
- DC link adaption  
- Flux sensing (ARM)  
- Field weakening and stall torque (ARM)  

Note:  
The DC link is measured in the I/R module, and is transferred as analog signal to the "SIMODRIVE 611 universal" via the unit bus for evaluation.

#### 1161 Fixed DC link voltage

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>700</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

#### 1162 Min. DC link voltage

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>800</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the permissible DC link voltage lower limit. Fault 616 is output if this limit is fallen below.

#### 1163 Max. DC link voltage

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>800</td>
<td>800</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the permissible DC link voltage upper limit. Fault 617 is output if this limit is exceeded.

#### 1164 Hysteresis, DC link monitoring  
(\(\rightarrow 8.1\))

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>50</td>
<td>600</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the hysteresis for the DC link voltage monitoring. This parameter refers to parameter 1162.

#### 1165 Peak filter, DC link voltage

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>50</td>
<td>10000</td>
<td>ms</td>
<td>Unsigned16</td>
</tr>
</tbody>
</table>

... defines the duration of the suppressed peak in the DC link voltage sensing.
1166  **Ground fault test active**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... activate the ground fault test

Bit 0  Automatic ground fault test after PO
Bit 0 = 1  Automatic motor ground fault test enabled after ramp-up
Bit 0 = 0  Automatic motor ground fault test disabled after ramp-up
Bit 1  Start ground fault test using P1166
Bit 1 = 1  Start: Activate motor ground fault test in operation using signal edge 0->1

*Note:
In the sense of the VDE Directives, the ground fault test does not represent a protective function.*

1167  **Response threshold of the ground fault test**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>4.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Response threshold of the ground fault test, referred to the transistor limit current, power unit (P1107).

*Note:
If the threshold exceeds the rated motor current P1103 it is not possible/practical to make a measurement in this combination of power unit and motor.
-6 is entered into P1169.

**Remedy:**
Reduce the threshold or adapt the power unit/motor configuration.

1168  **Maximum rotation, ground fault test (ARM SRM)**

**Maximum motion, ground fault test (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
<th>(SLM)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>5.0</td>
<td>10.0</td>
<td>mm</td>
<td>Floating Point</td>
<td>immed.  (SLM)</td>
<td></td>
</tr>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>30.0</td>
<td>Degree</td>
<td>Floating Point</td>
<td>immed.  (SRM ARM)</td>
<td></td>
</tr>
</tbody>
</table>

... enter the permitted rotation/motion for the ground fault test.

*Note:
If the distance is greater than that entered in P1168, fault 511 (ground fault detected) is signaled.*

1169  **Diagnostics, motor**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Integer16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... a positive value means that a ground fault was not detected.

0: Function was not selected or still not terminated
1: Measurement completed, no ground fault occurred
-1: Measurement was not able to be started, controller/pulse enable missing
-2: Measurement was not able to be started, motor/spindle rotating
-3: Short-circuit identified, current response threshold was exceeded
-4: During the measurement, the motor moved more than is permitted in P1168
-5: During the measurement, the current was not able to be decreased again in time (measurement not possible).
-6: Measurement not possible/practical – observe the configuration of P1167
-7: Short circuit detected, current limiting reached or calculated current rise too high.
-8: Parking axis selected
### 1170 Pole pair width (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>72.0</td>
<td>1000.0</td>
<td>mm</td>
<td>Floating Point</td>
<td>PO (SLM)</td>
</tr>
</tbody>
</table>

The pole pair width of a linear drive corresponds to the length from a north and south pole of the magnet.

### 1172 FD operation with field weakening (SRM) (→ 12.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>PO (SRM)</td>
</tr>
</tbody>
</table>

... defines feed drive operation with field weakening for this drive

1. FD operation with field weakening is activated
2. FD operation with field weakening is deactivated

**Note:**
This parameter is only active if P1015 has been set to 1 "Activate PE-MSD". see under the index entry "Permanent-magnet synchronous motor with and without field weakening (PE spindle)" or "FD operation with field weakening".

### 1175 Synchr. reduction factor for P1108

For SRM, SLM or PE spindle in field weakening (P1015 = 1 and P1172 = 1), the "limit current power unit (rms)" P1108 is multiplied by P1175 "synchr. reduction factor for P1108".

### 1176 Synchr. reduction factor for P1109

For SRM, SLM or PE spindle in field weakening (P1015 = 1 and P1172 = 1), the "limit current power unit S6 (rms)" P1109 is multiplied by P1176 "synchr. reduction factor for P1109".

### 1177 Synchr. reduction factor for P1111

For SRM, SLM or PE spindle in field weakening (P1015 = 1 and P1172 = 1), the "rated current power unit (rms)" P1111 is multiplied by P1177 "synchr. reduction factor for P1111".

### 1178 Synchr. current reduction factor

If, for SRM, SLM or PE spindle in field weakening (P1015=1 and P1172=1), parameter P1100 "Frequency pulse width modulation" is set greater than 4 kHz, then parameters P1108, P1109, P1111 are reduced using "Current reduction factor" P1178 and the derating characteristic. This reduction factor is saved in the power unit data and is automatically taken into account depending on P1100.

### 1179 Asynchr. current reduction factor

If, for ARM, parameter P1100 "Frequency pulse width modulation" is set greater than 3.2 kHz, then parameters P1108, P1109, P1111 are reduced using "Current reduction factor" P1178 and the derating characteristic. This reduction factor is saved in the power unit data and is automatically taken into account depending on P1100.
1180  Lower current limit adaption (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

Using the current controller adaptation (P1180, P1181, P1182), the P gain of the current controller (P1120) can be reduced depending on the current. P1180 defines the lower current value from which the adaptation linearly reduces the P gain up to the upper current value (P1181). In addition to current values P1180 and P1181, P1182 (factor, current controller adaptation) also defines the adaptation straight line (characteristic).

The following value pairs are obtained:
- First value pair: P1180 / 100%
- Second value pair: P1181 / P1182

Note:
- P1180, P1181 ----> Percentage values referred to P1104 (maximum current)
- P1182 ----> Percentage value, referred to P1120 (P gain, current controller)

The following applies: P1180 (lower current limit, adaptation) < P1181 (upper current limit adaptation)

(refer under the index entry "Current controller adaption")

1181  Upper current limit adaption (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

Note: Description, refer to P1180.

1182  Factor, current controller adaption (SRM SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

Note: Description, refer to P1180.

1185  Start-up factor P_IREG (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>10000.0</td>
<td>%</td>
<td>Floating Point</td>
<td>PO (ARM)</td>
</tr>
</tbody>
</table>

P1185 was introduced for 1PM4/1PM6 motors. For "calculate controller data" the current controller P gain is multiplied by the factor in P1185 and entered into P1120.

1200:8  No. of current setpoint filters

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>4</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the number of current setpoint filters.
The filter type (bandstop or low pass) is set using P1201:8.

0  No current setpoint value filter
1  Filter 1 active
2  Filters 1 and 2 active
3  Filters 1, 2 and 3 active
4  Filters 1, 2, 3 and 4 active

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2
### 1201:8 Current setpoint filter type

<table>
<thead>
<tr>
<th>Bit</th>
<th>Filter 1</th>
<th>Filter 2</th>
<th>Filter 3</th>
<th>Filter 4</th>
<th>Bit 15</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Low pass (filter parameters: P1202:8, P1203:8)</td>
<td>Low pass (filter parameters: P1204:8, P1205:8)</td>
<td>Low pass (filter parameters: P1206:8, P1207:8)</td>
<td>Low pass (filter parameters: P1208:8, P1209:8)</td>
<td>Z transformation</td>
</tr>
</tbody>
</table>

Note:
Before parameterizing the filter type, the appropriate filter parameters must be assigned.
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1202:8 Natural frequency current setp. filter 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1203:8 Damping, current setp. filter 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.05</td>
<td>0.7</td>
<td>5.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1204:8 Natural frequency current setp. filter 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1205:8 Damping, current setp. filter 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.05</td>
<td>1.0</td>
<td>5.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2
<table>
<thead>
<tr>
<th>Parameter Code</th>
<th>Description</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1206:8</td>
<td>Natural frequency current setp. filter 3</td>
<td>0.0</td>
<td>0.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1207:8</td>
<td>Damping, current setp. filter 3</td>
<td>0.05</td>
<td>1.0</td>
<td>5.0</td>
<td></td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
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<td></td>
<td></td>
</tr>
<tr>
<td>1208:8</td>
<td>Natural frequency current setp. filter 4</td>
<td>0.0</td>
<td>0.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1209:8</td>
<td>Damping, current setp. filter 4</td>
<td>0.05</td>
<td>1.0</td>
<td>5.0</td>
<td></td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1210:8</td>
<td>Blocking freq. current setp. filter 1</td>
<td>1.0</td>
<td>3500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1211:8</td>
<td>Bandwidth, current setp. filter 1</td>
<td>5.0</td>
<td>500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1212:8</td>
<td>Numerator, bandwidth current setpoint filter 1</td>
<td>0.0</td>
<td>0.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
<tr>
<td></td>
<td>Note:</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>The current setpoint filters are described in: References: /FBA/, Description of Functions, Drive Functions, Section DD2</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### 1213:8 Blocking freq. current setp. filter 2

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>1.0</td>
<td>3500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1214:8 Bandwidth, current setp. filter 2

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>5.0</td>
<td>500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1215:8 Numerator, bandwidth current setpoint filter 2

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Numerator</td>
<td>0.0</td>
<td>0.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1216:8 Blocking freq. current setp. filter 3

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>1.0</td>
<td>3500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1217:8 Bandwidth, current setp. filter 3

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>5.0</td>
<td>500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1218:8 Numerator, bandwidth current setpoint filter 3

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Numerator</td>
<td>0.0</td>
<td>0.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1219:8 Blocking freq. current setp. filter 4

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>1.0</td>
<td>3500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2
### 1220:8 Bandwidth, current setp. filter 4

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1221:8 Numerator, bandwidth current setpoint filter 4

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1222:8 Bandstop natural frequency, current setpoint filter 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1223:8 Bandstop natural frequency, current setpoint filter 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1224:8 Bandstop natural frequency, current setpoint filter 3

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1225:8 Bandstop natural frequency, current setpoint filter 4

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The current setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1230:8 1st torque limit value (ARM SRM)
1st force limit value (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>100.0</td>
<td>900.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter value refers to the stall torque (SRM), rated motor torque (ARM) and stall force (SLM) of the motor.
Note: refer to the index entry "Limits"

### 1233:8 Generative limitation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The setting refers to the parameter value in P1230.
### 1235:8 1st power limit

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>100.0</td>
<td>900.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter value refers to the motor output (SRM) and the rated motor output (ARM).

Note: refer to the index entry "Limits"

### 1237 Maximum generative power

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.1</td>
<td>100.0</td>
<td>500.0</td>
<td>kW</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... allows the regenerative power for the rectifier/regenerative feedback module to be limited. An appropriately lower value must be entered here especially when using a non-controlled NE module.

Note: refer to the index entry "Limits"

### 1238 Current limit value (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>150.0</td>
<td>400.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

The parameter value refers to the rated motor current (P1103).

Note: refer to the index entry "Limits"

### 1240:8 Torque setpoint offset (speed-contr.) (ARM SRM)  
Force setpoint offset (speed-contr.) (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-50000.0</td>
<td>0.0</td>
<td>50000.0</td>
<td>N</td>
<td>FloatingPoint</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>-50000.0</td>
<td>0.0</td>
<td>50000.0</td>
<td>Nm</td>
<td>FloatingPoint</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

This parameter value is added to the torque setpoint and force setpoint (SLM) if the closed-loop speed control is active (pos operation and nset operation with speed setpoint input). The parameter has no effect if, in the nset mode, open-loop torque controlled operation was selected.

Note: refer under the index entry "weight compensation"

### 1241:8 Normalization of torque setpoint (ARM SRM)  
Normalization of force setpoint (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>10.0</td>
<td>50000.0</td>
<td>N</td>
<td>FloatingPoint</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>1.0</td>
<td>10.0</td>
<td>50000.0</td>
<td>Nm</td>
<td>FloatingPoint</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

... defines the normalization for the torque setpoint and force setpoint (SLM) for open-loop torque controlled operation at the analog input terminals 56.x/14.x and/or terminals 24.x/20.x and displays the reference value for P0619.

Note: refer to the index entry "Open-loop torque controlled operation"

### 1242:8 Torque setpoint offset (torque-contr.) (ARM SRM)  
Offset, force setpoint (torque-controlled) (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-50000.0</td>
<td>0.0</td>
<td>50000.0</td>
<td>N</td>
<td>FloatingPoint</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>-50000.0</td>
<td>0.0</td>
<td>50000.0</td>
<td>Nm</td>
<td>FloatingPoint</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

The value is added to the torque setpoint or the force setpoint (SLM).

Note: refer to the index entry "Open-loop torque controlled operation"

### 1243:8 Normalization, torque/power reduction. (ARM SRM)  
Normalization, force/power reduction. (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the index entry "Torque/power reduction"
### 1244 Characteristic type, torque/power reduction (ARM SRM)
**Characteristic type, force/power reduction (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines whether reduction is realized with a negative or a positive characteristic.

1. Negative characteristic
2. Positive characteristic

Note: refer to the index entry "Torque/power reduction"

### 1245 Threshold, speed-dependent M_set smoothing (ARM SRM)
**Threshold, velocity-dependent F_set smoothing (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

Note:
... is described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1246 Hysteresis, speed-dependent M_set smoothing (ARM SRM)
**Hysteresis, velocity-dependent F_set smoothing (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>3.0</td>
<td>1000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>50.0</td>
<td>1000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

Note:
... is described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1247 Speed threshold, motor changeover 1 / 2 (ARM)  
\((- \rightarrow 2.4)\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>100.0</td>
<td>100000.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

... the speed threshold for the motor changeover is defined with speed threshold (P1013 = 3) to change over the motor data sets P1xxx to P2xxx.

Note: refer to the index entry "Motor changeover"

### 1248 Speed threshold, motor changeover 3 / 4 (ARM)  
\((- \rightarrow 2.4)\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>100.0</td>
<td>100000.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

... the speed threshold for the motor changeover is defined with the speed threshold (P1013 = 3) to change over the motor data sets P3xxx to P4xxx.

Note: refer to the index entry "Motor changeover"
### 1249 External contactor control, motor changeover (ARM)  (-- > 2.4)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed. (ARM)</td>
</tr>
</tbody>
</table>

... specifies whether the contactor control for the motor changeover is defined by the drive or from an external control.

1 Motor changeover via external control
The contactor control for motor changeover is determined via an external control via the "Motor changed over" input signal (STW2.11).

0 Motor changeover via the drive
The contactor control for motor changeover is determined by the drive via output terminals with function numbers 11, 12, 13 and 14.

Note:
refer to the index entry "Motor changeover"
The contactors for motor changeover must be switched to a no-current condition. If motor changeover is executed using an external control, and changed over with "Fault" (e. g. with drive pulses present), the power/supply infeed module could be destroyed.

Recommendation:
Change over the motor using the drive output terminals (P1249=0).
The output terminals 11, 12, 13 and 14 are not energized if P1249 = 1.

### 1250 Frequency limit, act. current smoothing

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

PT1 filter for the current actual value display
The parameter is used to smooth the following displays:
- P1708 (torque-generating current Iq)
- P1718 (torque-generating current Iq (A)), from SW 3.1
- PROFIBUS status word IqGl (smoothed, torque-generating current Iq) from SW 3.1

Note:
< 1 Hz --> the filter is inactive
This parameter has no effect on the closed-loop control.

### 1251 Time constant (smoothing) motor utilization

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Smoothing to display the motor utilization (P0604).

### 1252 Frequency limit, torque setpoint smoothing (ARM SRM)  Frequency limit, force setpoint smoothing (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

PT1 filter for the torque setpoint display (smoothing for P1716 and ZSW Mset, analog output from signal number 36).

Note:
< 1 Hz --> the filter is inactive
This parameter has no effect on the closed-loop control.

### 1254 Time constant current monitoring

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.5</td>
<td>2.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens
### 1255 Steady-state minimum speed (→ 11.1)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

... defines the steady-state minimum spindle speed in speed setpoint operation.

### 1256:8 Ramp-function generator ramp-up time (→ 2.4)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

During ramp-up, the setpoint is increased from zero to the maximum permissible actual speed.

Note:
- Max. permissible actual speed for synchronous motors: Minimum from 1.1 (1.05 from SW 7.1 onwards with "SIMODRIVE 611 universal HR/HRS", resolver) x P1400 and P1147
- Max. permissible actual speed for induction motors: Minimum from P1146 and P1147
- Max. permissible actual speed for linear motors: From P1147
  refer to the index entry "Ramp-function generator"

### 1257:8 Ramp-function generator ramp-down time (→ 2.4)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>600.0</td>
<td>s</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

During ramp-down, the setpoint is reduced from the maximum permissible actual speed to zero.

Note:
- Max. permissible actual speed for synchronous motors: Minimum from 1.1 (1.05 from SW 7.1 onwards with "SIMODRIVE 611 universal HR/HRS", resolver) x P1400 and P1147
- Max. permissible actual speed for induction motors: Minimum from P1146 and P1147
- Max. permissible actual speed for linear motors: From P1147
  refer to the index entry "Ramp-function generator"

### 1259 Torque/power reduction mot./gen. (ARM SRM) (→ 3.7)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines if the torque/power de-rating or force/power de-rating depends on whether the drive is motoring/generating.

- Bit 0: Torque / power reduction, only when motoring
- Bit 0 = 1: Reduction is only effective when motoring
- Bit 0 = 0: Reduction is effective when motoring and regenerating
- Bit 1: Motoring / regenerating limiting dependent on Nset
  - Bit 1 = 1: The torque limits when motoring are used if the product of torque and speed setpoint is positive and the speed setpoint is not equal to 0
  - Bit 1 = 0: The torque limits when motoring are used if the product of torque and speed actual value is positive or the absolute speed actual value is less than 10 RPM

P1259 valid for input via PROFIBUS and analog input.

Note: refer to the index entry "Torque/power reduction"
1260  i2t limiting, limit current, power section S6  
Min  Standard  Max  Unit  Data type  Effective
25.0  100.0  100.0  %  FloatingPoint  immed.

... for the i2t power section limiting, it defines the limiting characteristic referred to i-S6.

Note:
I-S6 = P1109 (limiting power section current S6) x P1099 (limiting factor, power section currents)
refer to the index entry "i2t power section limiting"

1261  i2t limiting, rated current power section current  
Min  Standard  Max  Unit  Data type  Effective
25.0  100.0  100.0  %  FloatingPoint  immed. (ARM)
25.0  110.0  110.0  %  FloatingPoint  immed. (SRM SLM)

... for the i2t power section limiting, it defines the limiting characteristic referred to i-n.

Note:
i-n = P1111 (rated power section current) x P1099 (limiting factor, power section currents)
refer to the index entry "i2t power section limiting"

1262  i2t time in limiting  
Min  Standard  Max  Unit  Data type  Effective
-  -  -  s  FloatingPoint  RO

... for the i2t power section limit, this is used to display the time during which the power section
is being limited.

Note:
The parameter is reset for value overflow and for POWER ON.
refer to the index entry "i2t power section limiting"

1263  i2t actual limiting factor  
Min  Standard  Max  Unit  Data type  Effective
-  -  -  %  FloatingPoint  RO

... for the i2t power section limit, this is used to display the actual current limit referred to i-max.

Note:
i-max = P1108 (limiting power section current) x P1099 (limiting factor, power section currents)
refer to the index entry "i2t power section limiting"

1264  i2t actual utilization factor  
Min  Standard  Max  Unit  Data type  Effective
-  -  -  %  FloatingPoint  RO

... is used for the i2t power section limiting to display the actual utilization. The difference to 100
% specifies how much reserve is available. The current limit is reduced for a utilization of 100%.

Note:
refer to the index entry "i2t power section limiting"

1265  Thermal motor model configuration  
Min  Standard  Max  Unit  Data type  Effective
0  0  3  Hex  Unsigned16  PO

... defines the configuration for the thermal motor model.

Bit 0  Activate thermal motor model
Bit 0 = 1  Thermal motor model activated
Bit 0 = 0  Thermal motor model not activated
Bit 1  Evaluate thermal motor model
Bit 1 = 1  No KTY evaluation (pure current monitoring)
Bit 1 = 0  Evaluation with KTY temperature sensor activated
**A.1 Parameter list**

---

**1266 Thermal motor utilization**  
\[\text{(}\rightarrow 11.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is used to diagnose the thermal motor utilization.

The parameter indicates the thermal utilization of the motor as a percentage.
In so doing, the computation model refers to the maximum permissible motor temperature (P1607) and the shutdown threshold temperature, thermal motor model (P1288).
When commissioning, the value in P1607/P1288 is preassigned depending on the specific motor.
If it is changed then the response of the thermal motor model also changes.
Fault 613 is signaled for a thermal motor utilization > 100 %.

**1268 Winding time constant**  
\[\text{(}\rightarrow 11.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>5000</td>
<td>s</td>
<td>Floating Point</td>
<td>PO</td>
</tr>
</tbody>
</table>

... is used to enter the winding time constants.
The motor manufacturer must specify the specific motor characteristic quantity.
It is required for the thermal motor model (P1265).

**1269 Thermal motor utilization alarm threshold**  
\[\text{(}\rightarrow 11.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>80</td>
<td>100</td>
<td>%</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... outputs alarm 814 if the thermal motor utilization P1266 is greater than the thermal motor utilization alarm threshold P1269 and the time monitoring is started in P1603.
Alarm 614 is output if the timer stage has expired without in the meantime the threshold of the thermal motor utilization having been fallen below.

Note:
Also refer to P1603 and P1288.

**1270 Speed range suppression, lower value**  
\[\text{(}\rightarrow 11.1\text{)}\]

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

... defines the lower value of the speed range suppression. The speed range suppression function prevents the drive from operating under steady-steady conditions at speeds in a range limited by the lower and upper speed.

**1271 Speed range suppression, upper value**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

... defines the upper value of the speed range suppression. The speed range suppression function prevents the drive from operating under steady-steady conditions at speeds in a range limited by the lower and upper speed.
1288  Shutdown threshold, thermal motor model  
(-> 12.2)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>180</td>
<td>220</td>
<td>°C</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the shutdown threshold of the thermal motor model (P1607 applies up to SW 12.1).

When commissioning, the value in P1288 is pre-assigned depending on the specific motor.

Note:
If P1288 is set < P1607, the value from P1607 is used as the shutdown threshold of the thermal motor model.

see also P1265, P1266, P1268, P1269 or P1607.

1400  Rated motor speed (ARM SRM) 
Rated motor velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>1450.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>PO (ARM)</td>
<td></td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>PO (SLM)</td>
<td></td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>PO (SRM)</td>
<td></td>
</tr>
</tbody>
</table>

1401:8  Speed for max. useful motor speed (ARM SRM) 
Velocity for max. useful motor velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-100000.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>immed. (SLM)</td>
<td></td>
</tr>
<tr>
<td>-100000.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>immed. (SRM ARM)</td>
<td></td>
</tr>
</tbody>
</table>

The parameter specifies the maximum useful motor speed and the useful motor velocity in closed-loop speed controlled operation, and represents the setpoint for P0618.

Note:
The maximum useful motor speed, set via P1401:8, is not exceeded, independent of whether the setpoint is entered via terminal or PROFIBUS.

refer to the index entry "speed-controlled operation"

1403  Creep speed pulse suppression (ARM SRM) 
creep speed, pulse suppression (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>6.0</td>
<td>7200.0</td>
<td>rpm</td>
<td>PO (ARM)</td>
<td></td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>7200.0</td>
<td>m/min</td>
<td>PO (SLM)</td>
<td></td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>7200.0</td>
<td>rpm</td>
<td>PO (SRM)</td>
<td></td>
</tr>
</tbody>
</table>

After the controller enable is withdrawn (e.g. via terminal or when a fault occurs) the drive brakes along its torque limit.

If the absolute speed actual value or the absolute velocity value falls below the specified shut-
down speed or creep speed, during the power-off sequence, the pulse enable is withdrawn, and
the drive "coasts down".

The pulses are previously cancelled if the timer stage, set in P1404 has expired. When the
ramp-function generator is active, the timer stage only starts to run when a speed setpoint of
zero is reached at the ramp-function generator output.

0   P1403 is inactive, pulses are exclusively canceled via P1404

Note:
The functionality of P1403 is required if an overshoot when reaching zero speed – after with-
drawing the control enable – is to be suppressed.

The pulse suppression control via P1403 and P1404 is ineffective when the motor holding brake is activated (P0850 = 1)
### 1404 Timer pulse suppression

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>5000.0</td>
<td>8388607.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>8388607.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

After the controller enable has been withdrawn and after this delay, the gating pulses of the power transistors are canceled on the drive side. If the ramp-function generator is active, the delay only starts when zero speed setpoint has been reached at the ramp-function generator output.

**Note:**
The pulses will be canceled beforehand, if the threshold, set in P1403, is fallen short off. The pulse suppression control via P1403 and P1404 is ineffective when the motor holding brake is activated (P0850 = 1)

### 1405:8 Monitoring speed, motor (ARM SRM)  
Monitoring velocity, motor (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>100.0</td>
<td>110.0</td>
<td>110.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Percentage input of the maximum permissible setpoint referred to P1401.

**Note:**
If the setpoint is exceeded, the value in P1405 is used as limit.

### 1407:8 Speed controller P gain (ARM SRM)  
Velocity controller P gain (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2000.0</td>
<td>999999.0</td>
<td>Ns/m</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.3</td>
<td>999999.0</td>
<td>Nm*s/rad</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
</tbody>
</table>

**Note:** refer to the index entry "Speed controller optimization"

### 1408:8 P gain, upper adaption speed (ARM SRM)  
P gain, upper adaption velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>2000.0</td>
<td>999999.0</td>
<td>Ns/m</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.3</td>
<td>999999.0</td>
<td>Nm*s/rad</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

**Note:** Refer under the index entry "Speed controller adaption"

### 1409:8 Speed controller reset time (ARM SRM)  
Velocity controller reset time (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:** refer to the index entry "Speed controller optimization"

### 1410:8 Integral action time, upper adaption speed (ARM SRM)  
Integral action time, upper adaption velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>10.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:** Refer under the index entry "Speed controller adaption"

### 1411 Lower adaptation speed (ARM SRM)  
Lower adaption velocity, motor (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

**Note:** Refer under the index entry "Speed controller adaption"
1412 Upper adaptation speed (ARM SRM)
Upper adaption speed, motor (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Refer under the index entry "Speed controller adaption"

1413 Select speed controller adaptation (ARM SRM)
Select velocity control adaption (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

Note: Refer under the index entry "Speed controller adaption"

1414:8 Natural frequency, reference model speed (ARM SRM)
Natural frequency, reference model velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The reference model is described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

1415:8 Damping, reference model speed (ARM SRM)
Damping, reference model velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.5</td>
<td>1.0</td>
<td>5.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The reference model is described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

1416 Balancing, reference model, speed (ARM SRM)
Balancing, reference model, velocity (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
The reference model is described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

1417:8 n_x for 'n_act < n_x' signal

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>120.0</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>6000.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

The threshold speed or the threshold velocity (SLM) for the output signal "n_act < n_x" is defined using this parameter.

1418:8 n_min for 'n_act < n_min' signal

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.3</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>5.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

The threshold speed or the threshold velocity (SLM) for the output signal "n_act < n_min" is defined using this parameter.
1421:8 **Time constant, integrator feedback (n controller)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The integrator of the speed controller is re-parameterized via a feedback element to a PT1 filter (1st order lowpass characteristics). The PT1 filter time constant can be set via P1421.

The following is valid:

P1421 < 1.0 ---> the PT1 filter is not active, the pure integrator is effective

P1421 >= 1.0 ---> the PT1 filter is active and has replaced the pure integrator

Applications:

Movement at zero setpoint with a dominant stiction can be suppressed but with the disadvantage that a setpoint-actual value difference remains. This can result in, for example, an oscillation of a position-controlled axis at standstill (stick-slip effect) or overshoot with micrometer steps.

Prevents excessive stress for axes which are mechanically rigidly coupled (e.g. for synchronous spindles, master-slave axes).

1426:8 **Toler.bandwidth f.'n_set = n_act' signal**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>1.0</td>
<td>10000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>20.0</td>
<td>10000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

The tolerance bandwidth for the "n_set = n_act" output signal is defined using this parameter.

1427 **Delay time 'n_set = n_act' signal**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>200.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter defines the time which is started if the speed actual value or the velocity actual value (SLM) has reached the tolerance bandwidth around the setpoint.

The time is used for the output signal "Ramp-function generator ended" and for the output signal "n_set = n_act".

Note: refer to the index entry "Output signal ramp-up completed" or "Output signal n_set is equal to n_act"

1428:8 **Threshold torque M_x (ARM SRM)\nThreshold force F_x (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>90.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The threshold torque or the threshold force (SLM) for the output signal "M < M_x" is defined using this parameter.

Note: refer to the index entry "Output signal M less than M_x"

1429 **Delay time 'M < M_x' signal (ARM SRM)\nDelay time 'F < F_x' signal (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>800.0</td>
<td>1000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter defines the time after which the evaluation for the output signal "M < M_x" is started after run-up.

Note: refer to the index entry "Output signal M less than M_x"

1451:8 **P gain speed controller AM**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.3</td>
<td>9999.999</td>
<td>Nm*s/rad</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the P gain of the speed controller is set in IM operation (operation without encoder).
### 1453:8 Reset time speed controller AM

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>140.0</td>
<td>6000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... the integral action time of the speed controller in IM operation (operation without encoder).

### 1458 Current setpoint, controlled range IM

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>90.0</td>
<td>150.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Current setpoint for the currentfrequency open-loop control referred to the rated motor current.

### 1459 Torque smoothing time constant IM

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>4.0</td>
<td>100.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Torque setpoint smoothing (initial rounding-off).

### 1465 Switching speed MSD/AM

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100000.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Threshold speed for the changeover from the MSD to induction motor (IM) control.

### 1466 Changeover speed, open-loop/closed-loop control IM (ARM SRM)

**Changeover velocity closed-loop/open-loop control IM (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>3.000000</td>
<td>20.000000</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed.   (SLM)</td>
</tr>
<tr>
<td>5.0</td>
<td>300.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed.   (SRM ARM)</td>
</tr>
</tbody>
</table>

**MSD:**
Threshold speed for changing over between closed-loop and open-loop control for induction motor operation.

**Note:**
When accelerating, condition P1466 >= 150 RPM is checked. If this is not the case, then fault 722 is signaled.

**FD,SLM:**
If the electrical brake has been enabled (P1049 = 1) if the encoder fails and there is no encoder information, then the axis is braked down to the changeover speed/velocity saved in parameter P1466. The pulses are then inhibited and the motor coasts down.
If the motor speed/velocity at the instant that the encoder fails is below the changeover speed/velocity defined in P1466, then the pulses are immediately inhibited and the motor coasts down.

**Note**
The following criteria apply when using the function “Electrical braking when the encoder fails”:
Rotating motor: P1466 > 40000 / P1114
Linear motor: P1466 > 1386 / P1114
If this limit is incorrectly parameterized, then fault message 722 is output “changeover speed/velocity too low.”

### 1467 BERO pulse number

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td></td>
<td>10</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the BERO pulse number per motor revolution (e.g. BERO senses 7 fan wheel blades per revolution -> P1467 = 7).
A value >= 1 activates the speed monitoring function with BERO.
1468   BERO shutdown threshold  
Min  Standard  Max  Unit  Data type  Effective
0    0         65535  -  Unsigned16  immed.

... defines the BERO shutdown threshold, speed monitoring. For a higher speed, Alarm 718 "BERO shutdown threshold exceeded" is output and the drive is stopped.

1469   BERO speed actual value  
Min  Standard  Max  Unit  Data type  Effective
-    -         -    -  Unsigned16  RO

... displays the absolute value of the actual BERO speed actual value.

1490   Activate equalization controller  
Min  Standard  Max  Unit  Data type  Effective
0    0         3    -  Unsigned16  PO

... can activate the anti-backlash controller (equalization controller).
0   no source or no equalization controller
1   active, source is terminal 24/20
2   active, source is the adjacent drive (double-axis module)
3   Active, PROFIBUS is the source (slave deadtime active, from SW 13.1)

1491   P gain equalization controller  
Min  Standard  Max  Unit  Data type  Effective
0.0  0.1       10000.0  rad/s/Nm  FloatingPoint  immed.

Recommended setting, equalization controller: Vp equalization controller (P1491) = 0.5 / Vp speed controller (P1407)

1492   Integral action time equalization controller  
Min  Standard  Max  Unit  Data type  Effective
0.0  20.0      8000.0  ms  FloatingPoint  immed. (ARM)
0.0  10.0      8000.0  ms  FloatingPoint  immed. (SRM SLM)

Recommended setting, equalization controller: TN equalization controller (P1491) = 10 x TN speed controller (P1409)

1493   Pre-tensioning torque, equalization controller (ARM SRM)  
Pre-tensioning force, equalization controller (SLM)  
Min  Standard  Max  Unit  Data type  Effective
-200.0  0.0     200.0  N  FloatingPoint  immed. (SLM)
-200.0  0.0     200.0  Nm FloatingPoint  immed. (SRM ARM)

... specifies a pre-tensioning torque (or pre-tensioning force (SLM)) which acts with a switch-in delay via a PT1 element (P1494).

1494   Time constant, pre-tensioning torque, equalization contr. (ARM SRM)  
Time constant, pre-tensioning force, equalization contr. (SLM)  
Min  Standard  Max  Unit  Data type  Effective
1.0   1.0      1000.0  ms  FloatingPoint  immed.

... enters the time constant for the PT1 element which ensures a soft, gentle increase of the pre-tensioning torque (P1493) when activating the equalization controller.
1495 Torque weighting, equalization controller - master (ARM SRM)  
(- > 7.1)
Force weighting equalization controller - master (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-100.0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... enters a weighting for the torque setpoint (or force for the force setpoint (SLM)) of the master axis for the equalization controller.

1496 Torque weighting, equalization controller - slave (ARM SRM)  
(- > 7.1)
Force weighting equalization controller - slave (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>100.0</td>
<td>100.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... enters a weighting for the torque setpoint (or force for the force setpoint (SLM)) of the slave axis for the equalization controller.

1500:8 No. of speed setpoint filters (ARM SRM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the number of speed setpoint filters.
The filter type (bandstop or low pass PT1/PT2) is set using P1501:8.
0 No speed setpoint filter active
1 Filter 1 active
2 Filters 1 and 2 active

Note:
If filter 1 is parameterized as low pass filter (PT1 or PT2, P1501:8), then it can be enabled/disabled using the input signal "first speed setpoint filter off". When parameterized as bandstop filter, the input signal has no effect.
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2
### 1501:8 Type of speed setpoint filter (ARM SRM)
#### Type of velocity setpoint filter (SLM)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Filter 1: Low pass/bandstop</th>
<th>Filter 2: Low pass/bandstop</th>
<th>Filter 1: Low pass PT1/PT2</th>
<th>Filter 2: Low pass PT1/PT2</th>
<th>Bit 8</th>
<th>Bit 9</th>
<th>Bit 15</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Bandstop (filter parameters: P1514:8, P1515:8, P1516:8)</td>
<td>Bandstop (filter parameters: P1517:8, P1518:8, P1519:8)</td>
<td>PT1 low pass (filter parameter: P1502:8)</td>
<td>PT1 low pass (filter parameter: P1503:8)</td>
<td>1</td>
<td>1</td>
<td>Z transformation</td>
</tr>
<tr>
<td>1</td>
<td>Low pass (filter parameters: P1502:8, P1506:8, P1507:8)</td>
<td>Lowpass (filter parameters: P1503:8, P1508:8, P1509:8)</td>
<td>PT2 low pass (filter parameters: P1506:8, P1507:8)</td>
<td>PT2 low pass (filter parameter: P1508:8, P1509:8)</td>
<td>0</td>
<td>0</td>
<td>Bilinear transformation</td>
</tr>
</tbody>
</table>

**Note:**
Before parameterizing the filter type, the appropriate filter parameters must be assigned.
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1502:8 Time constant, speed setpoint filter 1 (ARM SRM)
#### Time constant, velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Time constant, speed setpoint filter 1</th>
<th>Time constant, velocity setpoint filter 1</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Standard 0.0</td>
<td>Standard 0.0</td>
</tr>
</tbody>
</table>

**Note:**
The filter can be switched out/switched in via the "First speed setpoint filter off" input signal.
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1503:8 Time constant, speed setpoint filter 2 (ARM SRM)
#### Time constant, velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Time constant, speed setpoint filter 2</th>
<th>Time constant, velocity setpoint filter 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Standard 0.0</td>
<td>Standard 0.0</td>
</tr>
</tbody>
</table>

**Note:**
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1506:8 Natural frequency, speed setpoint filter 1 (ARM SRM)
#### Natural frequency, velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Bit</th>
<th>Natural frequency, speed setpoint filter 1</th>
<th>Natural frequency, velocity setpoint filter 1</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Standard 10.0</td>
<td>Standard 10.0</td>
</tr>
</tbody>
</table>

**Note:**
The filter can be switched out/switched in via the "First speed setpoint filter off" input signal.
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2
### 1507:8  Damping, speed setpoint filter 1 (ARM SRM)
Damping, velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.2</td>
<td>0.7</td>
<td>5.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
The filter can be switched out/switched in via the "First speed setpoint filter off" input signal.
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1508:8  Natural frequency, speed setpoint filter 2 (ARM SRM)
Natural frequency, velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>10.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1509:8  Damping, speed setpoint filter 2 (ARM SRM)
Damping, velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.2</td>
<td>0.7</td>
<td>5.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1514:8  Blocking frequency, speed setpoint filter 1 (ARM SRM)
Blocking frequency, velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>3500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1515:8  Bandwidth, speed setpoint filter 1 (ARM SRM)
Bandwidth, velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2

### 1516:8  Numerator, bandwidth speed setpoint filter 1 (ARM SRM)
Numerator, bandwidth velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
The speed setpoint filters are described in:
References: /FBA/, Description of Functions, Drive Functions, Section DD2
### Parameter List

**1517:8** Blocking frequency, speed setpoint filter 2 (ARM SRM)  
Blocking frequency, velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>3500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**  
The speed setpoint filters are described in:  
References: /FBA/, Description of Functions, Drive Functions, Section DD2

**1518:8** Bandwidth, speed setpoint filter 2 (ARM SRM)  
Bandwidth, velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.0</td>
<td>500.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**  
The speed setpoint filters are described in:  
References: /FBA/, Description of Functions, Drive Functions, Section DD2

**1519:8** Numerator, bandwidth speed setpoint filter 2 (ARM SRM)  
Numerator, bandwidth velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>7999.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**  
The speed setpoint filters are described in:  
References: /FBA/, Description of Functions, Drive Functions, Section DD2

**1520:8** Bandstop natural frequency, speed setpoint filter 1 (ARM SRM)  
Bandstop natural frequency velocity setpoint filter 1 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>141.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**  
The speed setpoint filters are described in:  
References: /FBA/, Description of Functions, Drive Functions, Section DD2

**1521:8** Bandstop natural frequency, speed setpoint filter 2 (ARM SRM)  
Bandstop natural frequency, velocity setpoint filter 2 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.0</td>
<td>100.0</td>
<td>141.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**  
The speed setpoint filters are described in:  
References: /FBA/, Description of Functions, Drive Functions, Section DD2
1522  **Time constant, speed actual value filter (PT1) (ARM SRM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>ms</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Encoder with sin/cos 1 Vpp: Default corresponding to the appropriate encoder
- Single absolute value encoder (EQI, 16 pulses/revolution): 1 ms
- Single absolute value encoder (EQI, 32 pulses/revolution): 1 ms
- Toothed-wheel encoder (SIZAG 2, 256/512 pulses/revolution): 1 ms
- Absolute encoder for SRM (SH28/36, 512 pulses/revolution): 1 ms
- Absolute value encoder (EQN, 2048 pulses/revolution): 0 ms
- Incremental encoder (ERN, 2048 pulses/revolution): 0 ms

Note: refer to the index entry "Encoder adaptation"

Resolver: Default, 12 bit resolution
- ARM: 2 ms
- SRM/SLM: 0.8 ms

Default, 14 bit resolution
- ARM: 2 ms
- SRM/SLM: 0.2 ms

1523  **Time constant, speed actual value filter (PT1) RLI (SRM)**

(- > 9.1)

**Time constant, velocity actual value filter (PT1) RLI (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Time constant of the speed actual value filtering during the rotor position identification routine, traversing 3
- <0.05 ms: internally, P1522 is used for the calculation
- >=0.05 ms: internally, P1523 is used for the calculation

Note: Pre-assignment (default) refer to P1522
1560 APC mode (ARM SRM)

--- 10.1 ---

**APC mode (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>7FF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the selection of functions for APC (active oscillation damping).

The direct measuring system must be selected and parameterized for APC. Further, P1562 must be correctly pre-assigned.

Bit 0 to bit 4 reserved

<table>
<thead>
<tr>
<th>Bit 5</th>
<th>Activation from APC</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 5 = 0:</td>
<td>APC is deactivated</td>
</tr>
<tr>
<td>Bit 5 = 1:</td>
<td>APC is activated</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 6</th>
<th>Reserved</th>
</tr>
</thead>
</table>

<table>
<thead>
<tr>
<th>Bit 7</th>
<th>Select the input for the 2nd cascade APC</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 7 = 0:</td>
<td>Input 2nd cascade APC is the acceleration of the direct measuring system</td>
</tr>
<tr>
<td>Bit 7 = 1:</td>
<td>Input 2nd cascade APC is just the same as for the 1st cascade APC</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 8</th>
<th>Filter input APC from the function generator</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 8 = 0:</td>
<td>Filter input APC from selected measured values</td>
</tr>
<tr>
<td>Bit 8 = 1:</td>
<td>Filter input APC is the speed setpoint of the function generator (for measuring purposes)</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 9</th>
<th>Do not connect filter output APC</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 9 = 0:</td>
<td>Filter output is connected when APC is activated</td>
</tr>
<tr>
<td>Bit 9 = 1:</td>
<td>Filter output is not connected (for measuring purposes)</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 10</th>
<th>Input 1st cascade APC</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 10 = 0:</td>
<td>Input 1st cascade APC is the acceleration of the direct measuring system</td>
</tr>
<tr>
<td>Bit 10 = 1:</td>
<td>Input 1st cascade APC is the speed of the direct measuring system minus speed setpoint</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 11</th>
<th>Closed-loop speed control with direct measuring system (pulse decoupling)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 11 = 0:</td>
<td>Closed-loop speed control with motor measuring system</td>
</tr>
<tr>
<td>Bit 11 = 1:</td>
<td>Closed-loop speed control with direct measuring system (bit 5 must also be set!)</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 12</th>
<th>Reserved</th>
</tr>
</thead>
</table>

<table>
<thead>
<tr>
<th>Bit 13</th>
<th>Disable APC 1st cascade</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 13 = 0:</td>
<td>1st cascade is active</td>
</tr>
<tr>
<td>Bit 13 = 1:</td>
<td>1st cascade is disabled</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Bit 14</th>
<th>Disable APC 2nd cascade</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 14 = 0:</td>
<td>2nd cascade is active</td>
</tr>
<tr>
<td>Bit 14 = 1:</td>
<td>2nd cascade is disabled</td>
</tr>
</tbody>
</table>

Bit 15 reserved
### 1562 Ratio between the motor and DM (ARM SRM)  
\[ (-\rightarrow 10.1) \]
**Ratio between the motor and DM (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1000000.0</td>
<td>1.000000</td>
<td>1000000.0</td>
<td>-</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the input to convert the motor measuring system to a direct measuring system.

The factor is entered with which, for uniform, consistent motion, the pulse frequency of the direct measuring system must be multiplied in order to obtain the pulse frequency of the motor measuring system. In this case, the resolution differences of the measuring system are included as also a possibly existing gearbox or measuring gearbox.

A different direction of rotation is taken into account with a negative sign.

**Example 1:**
Rotating motor 2048 pulses/revolution with ballscrew, spindle pitch 10 mm/revolution, direct measuring system with 20 \( \mu \text{m} \) grid division (lattice pitch).

\[
(10 \text{ mm/revolution})/(20 \mu \text{m}) = 500 \text{ pulses of the direct measuring system per motor revolution}
\]

\[ P_{1562} = 2048/500 = 4.096 \]

**Example 2:**
Rotating motor 2048 pulses/revolution, load connected through a gearbox with a ratio 25:1, direct measuring system with 8192 pulses/revolution at the load side.

\[ 8192/25 \text{ pulses of the direct measuring system per motor revolution} \]

\[ P_{1565} = 2048 \times 25/8192 = 6.25 \]

**Example 3:**
Rotating motor, 2048 pulses/revolution with a load directly coupled to the shaft and a direct measuring system at the load, 1024 pulses/revolution.

\[ 1024 \text{ pulses of the direct measuring system per motor revolution} \]

\[ P_{1562} = 2048/1024 = 2.0 \]

### 1564:8 Derivative action time, load speed controller (ARM SRM)  
\[ (-\rightarrow 10.1) \]
**Derivative action time, load velocity controller (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1000.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the derivative action time setting of the 1st cascade APC.

**Note:**
When selecting \( P_{1560} \) bit 10 = 1 (input APC is a speed actual value), \( P_{1564} \) has no units.

### 1567:8 Derivative action time, load speed controller 2 (ARM SRM)  
\[ (-\rightarrow 10.1) \]
**Derivative action time, load velocity controller 2 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1000.0</td>
<td>0.0</td>
<td>1000.0</td>
<td>ms</td>
<td>FloatingPoint</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the derivative action time setting of the 2nd cascade APC.

**Note:**
When selecting \( P_{1560} \) bit 10 = 1 (input APC is a speed actual value), \( P_{1564} \) has no units.
1569 Sub-sampling, acceleration filter (ARM SRM)  
Sub-sampling, acceleration filter (SLM)  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>64</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... sets the sub-sampling factor setting for the 1st and 2nd cascades of the acceleration filter (filters 1, 2, 4 and 5) for APC.

Value 1 means no sub-sampling.

For filters with a low blocking frequency, sub-sampling should be used.

The following recommendation applies: Blocking frequency * sampling time * P1569 should be greater than 1/160. This can be ensured using the sub-sampling factor.

The 3rd filter is also effective in the speed controller clock cycle and can be used to interpolate the sub-sampled filter.

All of the filters can be de-activated by suitably parameterizing them (e.g. using the pre-assignment values). There is no switch to disable individual filters.

1570:8 Type, acceleration filter (ARM SRM)  
Type, acceleration filter (SLM)  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1B1F</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the type of the 2nd speed setpoint filter

Bit 0 Filter 1: Low pass/bandstop
Bit 0 = 1: Bandstop (filter parameters: P1572:8, P1573:8, P1574:8, P1575:8)
Bit 0 = 0: Lowpass (filter parameters: P1571:8, P1572:8, P1573:8)
Bit 1 Filter 2: Low pass/bandstop
Bit 1 = 1: Bandstop (filter parameters: P1577:8, P1578:8, P1579:8, P1580:8)
Bit 1 = 0: Lowpass (filter parameters: P1576:8, P1577:8, P1578:8)
Bit 2 Filter 3: Lowpass/bandstop
Bit 2 = 1: Bandstop (filter parameters: P1581:8, P1582:8, P1583:8, P1584:8)
Bit 2 = 0: Lowpass (filter parameters: P1581:8, P1582:8)
Bit 3 Filter 4: Lowpass/bandstop
Bit 3 = 1: Bandstop (filter parameters: P1586:8, P1587:8, P1588:8, P1589:8)
Bit 3 = 0: Lowpass filter (Filter parameters: P1585:8, P1586:8, P1587:8)
Bit 4 Filter 5: Lowpass/bandstop
Bit 4 = 1: Bandstop (filter parameters: P1591:8, P1592:8, P1593:8, P1594:8)
Bit 4 = 0: Lowpass (filter parameters: P1590:8, P1591:8, P1592:8)
Bit 8 Filter 1: Low pass PT1/PT2
Bit 8 = 1: PT1 lowpass (filter parameter: P1571:8)
Bit 8 = 0: PT2 lowpass (filter parameters: P1572:8, P1573:8)
Bit 9 Filter 2: Low pass PT1/PT2
Bit 9 = 1: PT1 lowpass (filter parameter: P1576:8)
Bit 9 = 0: PT2 lowpass (filter parameters: P1577:8, P1578:8)
Bit 11 Filter 4: Lowpass PT1/PT2
Bit 11 = 1: PT1 lowpass (filter parameter: P1585:8)
Bit 11 = 0: PT2 lowpass (filter parameters: P1586:8, P1587:8)
Bit 12 Filter 5: Lowpass PT1/PT2
Bit 12 = 1: PT1 lowpass (filter parameter: P1590:8)
Bit 12 = 0: PT2 lowpass (filter parameters: P1591:8, P1592:8)

Note:
The 3rd filter cannot be implemented as PT1.

Before parameterizing the filter type, the appropriate filter parameters must be assigned.
### A.1 Parameter list

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
<th>Range</th>
<th>Default</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1571:8</td>
<td>Time constant, acceleration filter 1 (ARM SRM)</td>
<td>(- -&gt; 10.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1572:8</td>
<td>Denominator natural frequency acceleration filter 1 (ARM SRM)</td>
<td>(- -&gt; 10.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1573:8</td>
<td>Denominator damping, acceleration filter 1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1574:8</td>
<td>Numerator natural frequency, acceleration filter 1 (ARM SRM)</td>
<td>(- -&gt; 10.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1575:8</td>
<td>Numerator damping, acceleration filter 1 (ARM SRM)</td>
<td>(- -&gt; 10.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1576:8</td>
<td>Time constant, acceleration filter 2 (ARM SRM)</td>
<td>(- -&gt; 10.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>1577:8</td>
<td>Denominator natural frequency acceleration filter 2 (ARM SRM)</td>
<td>(- -&gt; 10.1)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

---

... defines the time constant setting for the 1st acceleration filter (1st cascade) for APC.

The time constant is only effective if in P1570, bit 0 is set to 0 and bit 8 is set to 1.

... defines the denominator natural frequency setting for the 1st acceleration filter (1st cascade) for APC.

... defines the numerator natural frequency setting for the 1st acceleration filter (1st cascade).

The numerator settings are only effective if in P1570, bit 0 is set to 1.

... defines the numerator damping setting for the 1st acceleration filter (1st cascade) for APC.

... defines the numerator damping setting for the 1st acceleration filter (1st cascade) for APC.

... defines the time constant setting for the 2nd acceleration filter (1st cascade).

The time constant is only effective if in P1570, bit 1 is set to 0 and bit 9 is set to 1.

... defines the denominator natural frequency setting for the 2nd acceleration filter (1st cascade) for APC.
### 1578:8 Denominator damping, acceleration filter 2 (ARM SRM)  
(\(\rightarrow 10.1\))

**Denominator damping, acceleration filter 2 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator damping setting for the 2nd acceleration filter (1st cascade) for APC.

### 1579:8 Numerator natural frequency, acceleration filter 2 (ARM SRM)  
(\(\rightarrow 10.1\))

**Numerator natural frequency, acceleration filter 2 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator natural frequency setting for the 2nd acceleration filter (1st cascade). The numerator settings are only effective if in P1570, bit 1 is set to 1.

### 1580:8 Numerator damping, acceleration filter 2 (ARM SRM)  
(\(\rightarrow 10.1\))

**Numerator damping, acceleration filter 2 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator damping setting for the 2nd acceleration filter (1st cascade) for APC. The numerator settings are only effective if in P1570, bit 1 is set to 1.

### 1581:8 Denominator natural frequency acceleration filter 3 (ARM SRM)  
(\(\rightarrow 10.1\))

**Denominator natural frequency acceleration filter 3 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator natural frequency setting for the 3rd acceleration filter (1st and 2nd cascades) for APC.

### 1582:8 Denominator damping, acceleration filter 3 (ARM SRM)  
(\(\rightarrow 10.1\))

**Denominator damping, acceleration filter 3 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator damping setting for the 3rd acceleration filter (1st and 2nd cascades) for APC.

### 1583:8 Numerator natural frequency, acceleration filter 3 (ARM SRM)  
(\(\rightarrow 10.1\))

**Numerator natural frequency, acceleration filter 3 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator natural frequency setting for the 3rd acceleration filter (1st and 2nd cascades). The numerator settings are only effective if in P1570, bit 2 is set to 1.
1584:8  **Numerator damping, acceleration filter 3 (ARM SRM)**  (→ 10.1)
**Numerator damping, acceleration filter 3 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td></td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator damping setting for the 3rd acceleration filter (1st and 2nd cascade) for APC.
The numerator settings are only effective if in P1570, bit 2 is set to 1.

1585:8  **Time constant, acceleration filter 4 (ARM SRM)**  (→ 10.1)
**Time constant, acceleration filter 4 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>1.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the time constant setting for the 4th acceleration filter (2nd cascade).
The time constant is only effective if in P1570, bit 3 is set to 0 and bit 11 is set to 1.

1586:8  **Denominator natural frequency acceleration filter 4 (ARM SRM)**
(→ 10.1)
**Denominator natural frequency acceleration filter 4 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator natural frequency setting for the 4th acceleration filter (2nd cascade) for APC.

1587:8  **Denominator damping, acceleration filter 4 (ARM SRM)**
(→ 10.1)
**Denominator damping, acceleration filter 4 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td></td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator damping setting for the 4th acceleration filter (2nd cascade) for APC.

1588:8  **Numerator natural frequency, acceleration filter 4 (ARM SRM)**
(→ 10.1)
**Numerator natural frequency, acceleration filter 4 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator natural frequency setting for the 4th acceleration filter (2nd cascade).
The numerator settings are only effective if in P1570, bit 3 is set to 1.

1589:8  **Numerator damping, acceleration filter 4 (ARM SRM)**  (→ 10.1)
**Numerator damping, acceleration filter 4 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td></td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator damping setting for the 4th acceleration filter (2nd cascade) for APC.
The numerator settings are only effective if in P1570, bit 3 is set to 1.

1590:8  **Time constant, acceleration filter 5 (ARM SRM)**  (→ 10.1)
**Time constant, acceleration filter 5 (SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>1.0</td>
<td>500.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the time constant setting for the 5th acceleration filter (2nd cascade) for APC.
The time constant is only effective if in P1570, bit 4 is set to 0 and bit 12 is set to 1.
1591:8 Denominator natural frequency acceleration filter 5 (ARM SRM)  
$\rightarrow$ 10.1

1591:8 Denominator natural frequency acceleration filter 5 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator natural frequency setting for the 5th acceleration filter (2nd cascade) for APC.

1592:8 Denominator damping, acceleration filter 5 (ARM SRM)  
$\rightarrow$ 10.1

1592:8 Denominator damping, acceleration filter 5 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the denominator damping setting for the 5th acceleration filter (2nd cascade) for APC.

1593:8 Numerator natural frequency, acceleration filter 5 (ARM SRM)  
$\rightarrow$ 10.1

1593:8 Numerator natural frequency, acceleration filter 5 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.0</td>
<td>2000.0</td>
<td>8000.0</td>
<td>Hz</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator natural frequency setting for the 5th acceleration filter (2nd cascade). The numerator settings are only effective if in P1570, bit 4 is set to 1.

1594:8 Numerator damping, acceleration filter 5 (ARM SRM)  
$\rightarrow$ 10.1

1594:8 Numerator damping, acceleration filter 5 (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.7</td>
<td>10.0</td>
<td>-</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the numerator damping setting for the 5th acceleration filter (2nd cascade) for APC. The numerator settings are only effective if in P1570, bit 4 is set to 1.

1600 Suppressible faults 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>7FFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The following faults can be suppressed using these bits.

Bit 4 measuring circuit, motor measuring system (fault 504)

Bit 5 monitoring absolute track (fault 505)

Bit 7 synchronizing error, rotor position (fault 507)

Bit 8 zero mark monitoring, motor measuring system (fault 508)

Bit 9 converter limiting frequency too high (fault 509)

Bit 12 Measuring circuit, direct measuring system (Fault 512)

Bit 13 Monitoring, absolute track, direct measuring system (fault 513)

Bit 14 Zero mark monitoring, direct measuring system (fault 514)

Note:

When suppressing the zero mark monitoring with P1600.8 or P1600.14, only faults 508 or 514 are suppressed; however, the internal monitoring functions still remain active.

Bit $x = \text{"1"} \rightarrow$ Fault is suppressed, i.e. de-activated

Bit $x = \text{"0"} \rightarrow$ Fault is activated
1601  Suppressible faults 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The following faults can be suppressed using these bits:

Bit 1  AD conversion error, terminal 56/14 or terminal 24/20 (fault 601)
Bit 5  Position controller output limited (fault 605)
Bit 6  flux controller at its limit (fault 606)
Bit 7  current controller at its limit (fault 607)
Bit 8  speed controller at its limit (fault 608)
Bit 9  Encoder limiting frequency exceeded (fault 609)
Bit 13 Immediate shutdown for motor overtemperature (P1607) (fault 613)
Bit 14 delayed shutdown for motor overtemperature (P1602 and P1603) (fault 614)
Bit 15 Direct measuring system, encoder limiting frequency exceeded (fault 615)

Note:
Bit x = "1" --> Fault is suppressed, i.e. de-activated
Bit x = "0" --> Fault is activated

1602  Alarm threshold, motor overtemperature

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>120</td>
<td>200</td>
<td>°C</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the thermal steady-state permissible motor temperature and is appropriately pre-assigned when the motor code is entered.

Note:
When this temperature alarm threshold is exceeded, "only" an appropriate alarm is output which disappears when the temperature threshold is fallen short off.
If the overtemperature condition remains longer than the time set in P1603, then this results in fault 614.
The monitoring function can be enabled/disabled via P1601.14.
The temperature monitoring functions with/without pre-alarm (P1602 + P1603 or P1607) are not mutually restricted, i.e. P1607 < P1602 is permissible.
Refer under the index entry "Monitoring functions"

1603  Motor temperature alarm timer

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>240</td>
<td>600</td>
<td>s</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

When the temperature alarm threshold (P1602) is exceeded, this timer is started. If the timer expires, and the temperature has not fallen below alarm threshold, fault 614 is output.

Note:
The monitoring function can be enabled/disabled via P1601.14.
Refer under the index entry "Monitoring functions"

1604  DC link undervoltage warning threshold

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>200</td>
<td>680</td>
<td>V(pk)</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the alarm threshold for the DC link monitoring.
The output signal "V_DC link > V_x (P1604)" (DC link voltage greater than the DC link undervoltage alarm threshold) is set if the DC link voltage is greater than the alarm threshold that has been set.

Note:
The output terminal signals can be inverted via parameter P0699 "Inversion, output terminal signals".
### 1605 Timer n controller at stop

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>20.0</td>
<td>200.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies how long the speed controller or velocity controller output can be at its limit without fault 608 being output.

**Important:**
If P1605 < P1404, then regenerative braking can be exited with fault 608, whereby the drive then "coasts down".

**Note:** refer to the index entry "Monitoring functions"

### 1606 Threshold n controller at stop

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>30.0</td>
<td>10000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (ARM)</td>
</tr>
<tr>
<td>0.0</td>
<td>500.0</td>
<td>10000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>90000.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

... specifies up to which speed or velocity the torque setpoint or force setpoint monitoring is active, i.e. up to this value, fault 608 can be output (speed controller at the endstop).

**Note:**
For PE spindles (P1015 = 1 and P1172 = 0), the standard assignment is the same as for ARM (30.0 rpm).

**Refer under index entry "Monitoring functions"**

### 1607 Shutdown limit motor temperature

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>155</td>
<td>200</td>
<td>°C</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the shutdown limit for the motor temperature monitoring without pre-alarm.

When this temperature threshold is exceeded, the drive is shut down, the pulses canceled and fault 613 output.

**Note:**
The monitoring function can be enabled/disabled via P1601.13.
The temperature monitoring functions with/without pre-alarm (P1602 + P1603 or P1607) are not mutually restricted, i.e. P1607 < P1602 is permissible.

Refer under the index entry "Monitoring functions"
Also refer under the index entry "Thermal motor model"

### 1608 Fixed temperature

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>200</td>
<td>°C</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

If a value > 0 is entered, then the rotor resistor is adapted, temperature-dependent, with this fixed temperature.

**Note:**
The measured temperature is then no longer monitored and parameters 1602, 1603 and 1607 are then no longer effective.

A fixed temperature can, e.g. be required, if a motor does not have a temperature sensor. Thus, e.g. the temperature monitoring of linear motors is disabled for the case where the monitoring is realized via an external PLC.

Refer under the index entry "Monitoring functions"
1609  PTC temperature sensor  \((\rightarrow 11.1)\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the sensor type to measure the motor temperature.

Bit 0  Sensor type
Bit 0 = 0  KTY temperature sensor (standard)
Bit 0 = 1  PTC temperature sensor

1610  Diagnostic functions

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>3</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO    ((\text{ARM}))</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>PO    ((\text{SRM SLM}))</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1611  Response threshold \(dn/dt\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>300</td>
<td>1600</td>
<td>%</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1612  Shutdown response, faults 1  \((\rightarrow 3.3)\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8FB2</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.    ((\text{ARM}))</td>
</tr>
<tr>
<td>0</td>
<td>FB2</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.    ((\text{SRM SLM}))</td>
</tr>
</tbody>
</table>

... defines how the system responds to the listed faults.

Bit 1  Measuring circuit fault, absolute current (fault 501)
Bit 4  Measuring circuit fault, motor measuring system (fault 504)
Bit 5  Measuring circuit fault, motor measuring system, absolute track (fault 505)
Bit 7  synchronizing error, rotor position (fault 507)
Bit 8  zero mark monitoring, motor measuring system (fault 508)
Bit 9  Drive converter limiting frequency exceeded (fault 509)
Bit 10 Positive feedback detected (fault 510)
Bit 11 Ground fault detected (fault 511)
Bit 12 Measuring circuit error, direct measuring system (fault 512)
Bit 13 Measuring circuit fault, direct measuring system absolute track (fault 513)
Bit 14 Zero mark monitoring, direct measuring system (fault 514)
Bit 15 Heatsink temperature exceeded (fault 515)

Note:

Bit \(x = "1" \rightarrow \text{STOP 1 is executed (internal pulse cancellation)}\)
Bit \(x = "0" \rightarrow \text{STOP II is executed (internal controller inhibit)}\)
If bit 1 is disabled, then this can destroy the power module (SIMODRIVE 611).
1613 Shutdown response, faults 2

<table>
<thead>
<tr>
<th>Bit</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>AD conversion error, terminal 56/14 or terminal 24/20 (fault 601)</td>
</tr>
<tr>
<td>1</td>
<td>Open-loop torque controlled operation w/o encoder not permissible (fault 602)</td>
</tr>
<tr>
<td>2</td>
<td>Changeover to a non-parameterized motor data set (fault 603)</td>
</tr>
<tr>
<td>3</td>
<td>Position controller output limited (fault 605)</td>
</tr>
<tr>
<td>4</td>
<td>Flux controller output limited (fault 606)</td>
</tr>
<tr>
<td>5</td>
<td>Current controller output limited (fault 607)</td>
</tr>
<tr>
<td>6</td>
<td>Speed controller output limited (fault 608)</td>
</tr>
<tr>
<td>7</td>
<td>Encoder limiting frequency exceeded (fault 609)</td>
</tr>
<tr>
<td>8</td>
<td>Rotor position identification has failed (fault 610)</td>
</tr>
<tr>
<td>9</td>
<td>Illegal motion during rotor position identification (fault 611)</td>
</tr>
<tr>
<td>10</td>
<td>Illegal current during rotor position identification (fault 612)</td>
</tr>
<tr>
<td>11</td>
<td>Shutdown limit, motor overtemperature (P1607) exceeded (fault 613)</td>
</tr>
<tr>
<td>12</td>
<td>Delayed shutdown for motor overtemperature (P1602 and P1603) (fault 614)</td>
</tr>
<tr>
<td>13</td>
<td>Direct measuring system, encoder limiting frequency exceeded (fault 615)</td>
</tr>
<tr>
<td>14</td>
<td>DC link undervoltage (Fault 616)</td>
</tr>
<tr>
<td>15</td>
<td>DC link overvoltage (Fault 617)</td>
</tr>
</tbody>
</table>

Note:
- Bit x = "1" --> STOP 1 is executed (internal pulse cancellation)
- Bit x = "0" --> STOP II is executed (internal controller inhibit)

1615 Tolerance rotational accuracy monitor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.2</td>
<td>100.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>2.0</td>
<td>100.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1616 Diagnosis, actual speed value

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

When continuously increased by several increments, there is an increased noise level (the speed actual value is faulty).
1620  Bits for variable signaling function

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>F</td>
<td></td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the behavior of variable message function.

- Bit 0: Variable message function
  - Bit 0 = 1: active
  - Bit 0 = 0: inactive
- Bit 1: Segment, variable message function
  - Bit 1 = 1: Address space Y
  - Bit 1 = 0: Address space X
- Bit 2: Comparison, signed
  - Bit 2 = 1: Comparison with sign
  - Bit 2 = 0: Comparison without sign
- Bit 3: Variable is a double word
  - Bit 3 = 1: Variable is a double word
  - Bit 3 = 0: Variable is a single word

Note:
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"

1621  Signal number, variable signaling function

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>530</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"

1622  Address, variable signaling function

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"

1623  Threshold, variable signaling function

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>F4143E00</td>
<td>0</td>
<td>BEBC200</td>
<td>Hex</td>
<td>Integer32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"

1624  Hysteresis, variable signaling function

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>BEBC200</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note:
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"
1625 **Pull-in delay, variable signaling function**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>10000</td>
<td>ms</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"

1626 **Drop-out delay, variable signaling function**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>10000</td>
<td>ms</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

**Note:**
Parameterize "variable message function" in the selection box with SimoCom U.
Refer under the index entry "Variable message function"

1645 **Incorrect orientation timer, direction monitoring (SRM SLM) (\(\rightarrow 11.1\))**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>12.0</td>
<td>12.0</td>
<td>10000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

... defines how long the current controller may remain at the same end stop while the acceleration/velocity and torque/force have different directions.
After this time has expired fault 510 "positive feedback detected" is initiated.

1646 **Threshold, disable direction monitoring (SRM SLM) (\(\rightarrow 11.1\))**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>0.2</td>
<td>100000.0</td>
<td>m/min</td>
<td>Floating Point</td>
<td>immed. (SLM)</td>
</tr>
<tr>
<td>0.0</td>
<td>20.0</td>
<td>100000.0</td>
<td>rpm</td>
<td>Floating Point</td>
<td>immed. (SRM)</td>
</tr>
</tbody>
</table>

... specifies from which speed/velocity the direction monitoring is disabled.
If this limit is exceeded and in so doing incorrect orientation does not occur, the monitoring is disabled. After ramping-up and after de-selecting the parking axis, the monitoring is re-enabled.

1650 **Diagnostics control**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFF</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... allows the diagnostic functions to be configured.

Bit 0  Min/max memory
Bit 0 = 1 Enable the "Min/Max memory" function
Bit 0 = 0 Disable the "min/max memory" function
Bit 1  Segment, min/max memory
Bit 1 = 1 Segment Y: (min/max memory)
Bit 1 = 0 Segment X: (Min/Max memory)
Bit 2  Comparison, signed
Bit 2 = 1 Comparison signed (min/max memory)
Bit 2 = 0 Comparison unsigned (absolute value)(Min/Max memory)
Bit 15 Cyclically display the parameter number
Bit 15 = 1 Cyclic display is inactive
Bit 15 = 0 Cyclic display is active (seven-segment display)
While a parameter value is being displayed, the associated parameter number or subparameter number is displayed every 10 seconds for one second.
### 1651 Signal number, min/max memory

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>530</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Refer under the index entry "signal selection list for analog output"

Note: Internal Siemens

### 1652 Memory location min/max memory

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1653 Minimum value Min/Max memory

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

Displays the min. value in the min/max memory.

Note: Internal Siemens

### 1654 Maximum value Min/Max memory

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

Displays the max. value in the min/max memory.

Note: Internal Siemens

### 1655 Segment memory location monitor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Select the segment for the monitor function.

0 Segment X: (Monitor)
1 Segment Y: (Monitor)

Note: Internal Siemens

### 1656 Address memory location monitor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Select the address for the monitor function.

Note: Internal Siemens

### 1657 Value display monitor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

Displays the contents of the address in P1655/P1656.

Note: Internal Siemens

### 1658 Value input monitor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1659 Value acceptance monitor

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td></td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens
1690  Memory test event counter
Min  Standard  Max  Unit  Data type  Effective
0   0         FFFF  -    Unsigned16  immed.
Note: Internal Siemens

1691  Memory test last address
Min  Standard  Max  Unit  Data type  Effective
0   0         FFFFF  Hex  Unsigned32  immed.
Note: Internal Siemens

1692  Memory test setpoint
Min  Standard  Max  Unit  Data type  Effective
0   0         FFFFF  Hex  Unsigned32  immed.
Note: Internal Siemens

1693  Memory test actual value
Min  Standard  Max  Unit  Data type  Effective
0   0         FFFFF  Hex  Unsigned32  immed.
Note: Internal Siemens

1694  Memory test actual value
Min  Standard  Max  Unit  Data type  Effective
0   0         FFFFF  Hex  Unsigned32  immed.
Note: Internal Siemens

1701  DC link voltage
Min  Standard  Max  Unit  Data type  Effective
-   -         -     V(pk)  Unsigned16  RO
... is used for continuous display (measurement) of the DC link voltage.
Note:
If a value > 0 V is in P1161 (fixed DC link voltage), then this display is not valid.
The DC link voltage is centrally measured at the NE module. This means that the DC link con-
nection to the drive modules cannot be checked using P1701.

1703  Lead time, motor measuring system conversion
Min  Standard  Max  Unit  Data type  Effective
-   -         -     µs     Unsigned16  RO
Note: Internal Siemens

1705  Voltage setpoint (rms)
Min  Standard  Max  Unit  Data type  Effective
-   -         -     V(RMS)  Floating Point  RO
Displays the phase-to-phase voltage.

1708  Torque-generating current Iq
Min  Standard  Max  Unit  Data type  Effective
-   -         -     %     Floating Point  RO
... displays the torque-generating current Iq RMS.
Note:
The display of the torque generating current actual value is smoothed using a PT1 filter
(P1250).
The smoothed current actual value is displayed as an absolute percentage, where 100 % corre-
sponds to the maximum power module current (e. g. for an 18/36 A power module -->
100 % = 36 A RMS).
### 1709 Significance, voltage representation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td></td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1710 Significance, current representation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>μA(pk)</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1711 Significance, speed representation (ARM SRM) Significance, velocity representation (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>m/min</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>rpm</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1712 Significance, rotor flux representation (ARM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>μVs</td>
<td>Floating Point</td>
<td>RO (ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1713 Significance torque representation (ARM SRM) Significance, force representation (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>μN</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>μNm</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1715 Limit, thermal motor utilization

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1716 Torque setpoint (ARM SRM) Force setpoint (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>N</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Nm</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

... displays the actual torque setpoint or force setpoint (SLM).

Note:
The torque/force setpoint display is smoothed using a PT1 filter (P1252).

### 1717 Limiting factor for torque/power (ARM SRM) Limiting factor for force/power (SLM)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Floating Point</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the actual limiting factor for torque/power or force/power (SLM).

Note:
refer to the index entry "Torque/power reduction"
1718 Torque-generating current $I_q$ (A) (-> 3.1)
Min Standard Max Unit Data type Effective
- - - A(rms) Floating Point RO
... displays the torque-generating current $I_q$ as RMS value.
Note: The display of the torque generating current actual value is smoothed using a PT1 filter (P1250).

1719 Actual absolute current (rms)
Min Standard Max Unit Data type Effective
- - - A(rms) Floating Point RO
Displays the motor phase current RMS.

1723 Diagnosis, ramp-up time
Min Standard Max Unit Data type Effective
- - - ms Unsigned16 RO
Note: Internal Siemens

1724 Diagnosis, rotational accuracy monitor
Min Standard Max Unit Data type Effective
- - - Unsigned16 RO
Note: Internal Siemens

1725 Normalization of torque setpoint (ARM SRM) (-> 2.4)
Normalization of force setpoint (SLM)
Min Standard Max Unit Data type Effective
- - - N Floating Point RO (SLM)
- - - Nm Floating Point RO (SRM ARM)
... specifies the reference value for the status word Msoll for PROFIBUS.
The following applies before SW 4.1: The value corresponds to 800% of the rated motor torque.
From SW 4.1 the following applies: The value corresponds to $P0882 \times$ rated motor torque.

1726 Calculated jerk time (-> 3.1)
Min Standard Max Unit Data type Effective
- - - ms Floating Point RO
... displays the calculated jerk time which is currently effective.
Note: refer to the index entry "Jerk limitation"

1729 Actual rotor position (electrical) (-> 3.3)
Min Standard Max Unit Data type Effective
- - - Degree Floating Point RO
... displays the actual electrical rotor position.

1731 Image ZK1_PO register
Min Standard Max Unit Data type Effective
- - - Hex Unsigned16 RO
Note: Internal Siemens

1732 Image ZK1_RES register
Min Standard Max Unit Data type Effective
- - - Hex Unsigned16 RO
Note: Internal Siemens
### 1733  NPFK diagnosis counter

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1734  Diagnostics, rotor position identification (SRM SLM)  
(\(\rightarrow 3.3\))

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Integer16</td>
<td>RO(SRM SLM)</td>
</tr>
</tbody>
</table>

...indicates the result of the last rotor position identification. When a fault condition occurs, negative values indicate the fault cause.

- **0** Function was not selected or was not exited
- **1, 2** Function was successfully executed (saturation-based technique)
- **3** Function was successfully executed (motion-based traversing, from SW 6.1)

**Error codes**

- **-1** Measurement has not provided any significant result
  - Remedy: Increase current (P1019)
- **-2** Current was not able to be reduced again in time during the measurement
  - Remedy: Check armature inductance (P1116) and if required, increase
- **-3** The motor moved during the measurement more than permitted in P1020
  - Remedy: Increase permissible rotation (P1020) or reduce current (P1019)
- **-4** Current rise is too low, the motor is possibly not correctly connected
  - Remedy: Check motor terminals
- **-5** The current limit of the motor or the power module was exceeded
  - Remedy: Check current limits or reduce armature inductance (P1116)
- **-6** Longest permissible time RLI exceeded. Within the permissible time, no continuous rotor position value was achieved (from SW 6.1).
  - Remedy: refer under the index entry "Rotor position identification"
    ---> "Parameterization for motion-based traversing"
- **-7** No clear rotor position found. It appears that the motor cannot be freely moved (e.g. it is locked, at its end stop).
  - Remedy: refer under the index entry "Rotor position identification"
    ---> "Parameterization for motion-based traversing"

**Note:**

refer to P1736 or under the index entry "Rotor position identification", "PE spindle" or "Linear motor"

### 1735  Processor utilization

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

...continuously displays (online) the processor utilization and provides information about the available computation time reserves of the processor.

The processor utilization is essentially dependent on the number of axes, operating mode and cycle setting.

- **P1735 > 90 %**
  - If, after start-up (optimization), this is displayed as "normal status", then there is a high danger that if additional computation time-intensive functions are selected, the processor will be overloaded (e.g. measuring function).
  - Note:
    - If processor utilization is too high it can be reduced by increasing the clock cycles (refer to the index entry "cycles").
    - **P1735 < 90 %**
    - From experience, there are no problems here, so that later (e.g. when troubleshooting), supplementary functions (e.g. measuring functions, trace functions) can be temporarily activated.
1736  **Test, rotor position identification (SRM SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td></td>
<td>Unsigned16</td>
<td>immed. (SRM SLM)</td>
</tr>
</tbody>
</table>

To check the rotor position identification, using this test function, the difference between the calculated rotor position angle, and that currently used by the control, can be determined.

Bit 0 = 1: The rotor position identification test has been activated (either directly here or through the activated plausibility monitoring encoder – P1011[10] = 1).

Bit 0 = 0: The test has been completed (initial state)

Bit 23 The rotor position identification is also started even when the brake control is activated.

Start for the encoder plausibility monitoring (this cannot be set). When the encoder plausibility monitoring is activated bit 0 and bit 23 are set (from SW 10.1).

Note:
refer under the index entry "Rotor position identification", "PE spindle" or "Linear motor"

1737  **Difference, rotor position identification (SRM SLM)**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Degree</td>
<td>Floating Point</td>
<td>RO (SRM SLM)</td>
</tr>
</tbody>
</table>

Note:
also refer for P1736 and under the index entry "PE spindle" or "linear motor"
The rotor position identification is described in:
References: /FBA/, Description of Functions, Drive Functions, Section DM1

1738  **No. of data backup operations in the FEPROM**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1739  **You must save in the FEPROM**

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays that at least one parameter was written into and the value was not yet saved in the non-volatile memory (FEPROM).

1 Must be saved in the FEPROM because parameters have been changed
0 Need not be saved in the FEPROM

1740  **Significance, abs. speed act. value representation (fine) (ARM SRM)**

<table>
<thead>
<tr>
<th>Min Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>m/min</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>rpm</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1741  **Significance, utilization representation (fine)**

<table>
<thead>
<tr>
<th>Min Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>%</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens
1742 **Significance, torque setpoint representation (fine) (ARM SRM)**  
**Significance, force setpoint representation (fine) (SLM)**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>μN</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>μNm</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1743 **Significance, velocity representation**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>c*MSR/min</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>c*MSR/min</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1744 **Weighting, velocity representation, external**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>c*MSR/min</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>c*MSR/min</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1745 **Weighting following error representation DSC**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>mm</td>
<td>Floating Point</td>
<td>RO (SLM)</td>
</tr>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Degree</td>
<td>Floating Point</td>
<td>RO (SRM ARM)</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

1781:17 **Setpoint source, process data PROFIBUS**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates the source of the process data received via PROFIBUS.  
The high byte includes a reference to the source device (0xFF for the master, DP address for a Publisher) and the low byte, the offset within the telegram (Counting in bytes, starting with 1).  
The following is valid:  
P1781:0 Number of valid entries  
P1781:1 Source of process data 1 (STW1)  
P1781:2 Source of process data 2 (PZD2), etc.  
Note: refer to the index entry "Process data"

1782:17 **Target offset PROFIBUS process data**  

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates which offset the process data have in the telegrams sent to the master or the subscribers via the PROFIBUS (Counting in bytes, starting with 1).  
The following is valid:  
P1782:0 Number of valid entries  
P1782:1 Target offset, process data 1 (ZSW1)  
P1782:2 Target offset, process data 2 (PZD2), etc.  
Note: refer to the index entry "Process data"
### 1783:97 PROFIBUS parameterization data received

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of the parameterizing data received from the DP slave.

The sub-parameter

- with index 0 contains the number of valid bytes of the parameterization frame
  
  \(= 0 \implies \) no parameterizing data available

- with index 1, the 1st byte includes the parameterizing data

- with index 2, the 2nd byte includes the parameterizing data, etc.

### 1784:97 PROFIBUS configuration data received

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of the configuration data received by the DP slave.

The sub-parameter

- with index 0 contains the number of valid bytes of the configuration frame
  
  \(= 0 \implies \) no configuration data available

- with index 1, the 1st byte includes the configuration data

- with index 2, the 2nd byte includes the configuration data, etc.

### 1785:13 Expanded PROFIBUS diagnostics

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>RO</td>
</tr>
</tbody>
</table>

... contains diagnostic information for PROFIBUS operation. For the individual indices of P1785, the following applies:

- :0 Error, master sign-of-life since POWER ON
- :1 Clock cycle-synchronous operation selected
- :2 Interpolation clock cycle (Tïïï) in \(\mu s\)
- :3 Position controller clock cycle (Tïï) in \(\mu s\)
- :4 Master application cycle time (Tmapc) in \(\mu s\)
- :5 DP cycle time (Tdp) in \(\mu s\)
- :6 Data Exchange time (Tdx) in \(\mu s\)
- :7 Instant of the setpoint sensing (To) in \(\mu s\)
- :8 Instant of the actual value sensing (Ti) in \(\mu s\)
- :9 PLL window (Tpllw) in 1/12 \(\mu s\)
- :10 PLL delay time (Tplld) in 1/12 \(\mu s\)
- :11 External slave-to-slave communication links
- :12 Internal slave-to-slave communication links

### 1786:5 PKW data received, PROFIBUS

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of the PKW data received by the DP slave.

The sub-parameter

- with index 0 contains the number of valid words
  
  \(= 0 \implies \) no PKW data available

- \(= 4 \implies \) PKW data available

- with index 1 of the PKE word (PKE: Parameter identification)

- with index 2 of the IND word (IND: Sub-index, sub-parameter number, array index)

- with index 3 of the most significant PWE word (PWE: Parameter value)

- with index 4 of the least-significant PWE word

Note: refer to the index entry "PKW area"
### 1787:5  PKW data sent, PROFIBUS  
\(\rightarrow 2.4\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of the PKW data sent to the DP master.

The sub-parameter

- with index 0 contains the number of valid words
  - \(= 0 \rightarrow \) no PKW data available
  - \(= 4 \rightarrow \) PKW data available

- with index 1 of the PKE word (PKE: Parameter identification)

With index 2 - the IND word (IND: Subindex, sub-parameter number, array index)

- with index 3 of the most significant PWE word (PWE: Parameter value)

- with index 4 of the least-significant PWE word

Note: refer to the index entry "PKW area"

### 1788:17  Processed data received via PROFIBUS

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of the process data received from the DP slave (control words).

The sub-parameter

- with index 0 - contains the number of valid words,
- with index 1, the process data 1 (control word 1), with index 2, the process data 2 (PZD2), ...

Note: refer to the index entry "Process data"

### 1789:17  Process data sent via PROFIBUS

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Hex</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... is an image of the process data sent to the DP master (status words).

The sub-parameter

- with index 0 - contains the number of valid words,
- with index 1, process data 1 (status word 1), with index 2, process data 2 (PZD2), ...

Note: refer to the index entry "Process data"

### 1790  Meas. circ. type indirect meas. system

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Integer16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays which measuring system type is used.

0 Encoder with sin/cos 1 Vpp signals
7 TTL encoder (new basic module HR)
11 Encoder with sin/cos 1 Vpp voltage signals with a higher resolution
13 Resolver with higher resolution (14 bit)
14 Resolver (12 bit)
16 EnDat encoder (absolute value encoder)
27 EnDat encoder (absolute value encoder) with higher incremental track resolution

### 1792  Active measuring system  
\(\rightarrow 3.3\)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned16</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates the measuring system which the drive control uses.

0 No measuring system
1 Motor measuring system
2 Direct measuring system
### 1794 Option module (PROFIBUS): Version initial program loader

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates which version of the initializer is on the option module.
Example: P1794 = 10104 --> V01.01.04 is available

### 1795 Option module (PROFIBUS): Version firmware

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the firmware version on the option module.
Example: P1795 = 10104 --> V01.01.04 is available

### 1796 Initializer version

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays which version of the initializer is available on the memory module.
Example: P1796 = 10104 --> V01.01.04 is available

### 1797 Module initial program loader version

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... indicates which version of the module initial program loader is available in the control module.
Example: P1797 = 10101 --> V01.01.01 is available

### 1798 Firmware date

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

Internal Siemens
... displays when the firmware release (P1799) was generated.
Note: yyyyymmdd --> yyyy = year, mm = month, dd = day

### 1799 Firmware version

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>Unsigned32</td>
<td>RO</td>
</tr>
</tbody>
</table>

... displays the firmware version on the memory module.
Example: P1799 = 10103 --> V01.01.03 is available

### 1800 Function generator control

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-40</td>
<td>0</td>
<td>2</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Refer under the index entry "Function generator control"

### 1804 Function generator operating mode

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>3</td>
<td>5</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Refer under index entry "Function generator operating mode"

### 1805 Function generator curve shape

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>5</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies, which waveform of the function generator should be output.
### 1806 Start-up function amplitude

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1600.0</td>
<td>5.0</td>
<td>1600.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the amplitude of the function generation signal to be output. The unit depends on P1804.

1. Unit is referred to P1103 (rated motor current)
2. Unit is referred to P1400 (rated motor speed)

### 1807 Start-up function offset

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1600.0</td>
<td>0.0</td>
<td>1600.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the offset of the function generator signal to be output. The unit depends on P1804.

1. Unit is referred to P1103 (rated motor current)
2. Unit is referred to P1400 (rated motor speed)

Note:
For P1804 = 2 (operating mode "disturbing torque"), the offset does not act on the current setpoint, but on the speed setpoint in order to bypass the effects of backlash.

### 1808 Function generator limitation

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>100.0</td>
<td>1600.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the limit of the function generator signal to be output. The unit depends on P1804.

1. Unit is referred to P1103 (rated motor current)
2. Unit is referred to P1400 (rated motor speed)

Note:
The limit is effective, symmetrically around the zero point.
For P1804 = 2 (operating mode "Disturbing torque") the limit only acts on the current setpoint, however, not on the speed setpoint (=offset).

### 1809 Function generator 2nd amplitude (staircase)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1600.0</td>
<td>7.0</td>
<td>1600.0</td>
<td>%</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the 2nd amplitude for the "Staircase" waveform of the function generator signal to be output. The unit depends on P1804.

1. Unit is referred to P1103 (rated motor current)
2. Unit is referred to P1400 (rated motor speed)

### 1810 Function generator period

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1000</td>
<td>65535</td>
<td>ms</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the period of the function generator signal to be output.

### 1811 Function generator, pulse width (squarewave)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>500</td>
<td>65535</td>
<td>ms</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the pulse width for the "squarewave" waveform of the function generator signal to be output.

### 1812 Start-up function, bandwidth (FFT)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Datatype</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>4000</td>
<td>8000</td>
<td>Hz</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the bandwidth in PRBS operation (only for P1805 = 4, PRBS).
1813  Start-up function, ramp-up time to P1400

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0</td>
<td>32.0</td>
<td>100000.0</td>
<td>ms</td>
<td>Floating Point</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... specifies the time in which the drive accelerates or brakes to the required speed. In this case, the parameter refers to P1400 (rated speed).

1814  Measuring function meas. type

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>11</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the index entry "Measuring function"

1815  Measuring function meas. period (step change)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>100</td>
<td>2000</td>
<td>ms</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the index entry "Measuring function"

1816  Measuring function settling time

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>100</td>
<td>65535</td>
<td>ms</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the index entry "Measuring function"

1817  Measuring function no. of averaging ops. (FFT)

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>16</td>
<td>1000</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: refer to the index entry "Measuring function"

1820  Signal number test socket 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>6</td>
<td>530</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter defines which signal is output via test socket 1. The signal number from the signal selection list for analog outputs must be entered. Note: refer to the index entry "Test sockets"

1821  Shift factor test socket 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>6</td>
<td>47</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

... defines the shift factor, with which the analog signal is manipulated. An 8 bit window of the 24/48 bit signal can be represented via the test socket, thus, the shift factor must be used to define which window of the internal 24/48 bits is to be displayed.

1822  Offset test socket 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

The parameter specifies the offset value which is added to the 8-bit output signal. Note: refer to the index entry "Test sockets"

1823  Segment address test socket 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens
### 1824 Offset address test socket 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1826 Status test socket 1

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

This parameter determines the status of test socket 1 for this drive.

0  test socket is inactive
1  test socket is active

As always only one drive can output one value at a test socket, when changing the parameter in one drive, the parameter in the other drive is appropriately changed.

Note:
On a 2-axis module, the test sockets are pre-set as follows after the first start-up:

Drive A: Test socket 1 = active (P1826 = 1) and test socket 2 = inactive (P1836 = 0)
Drive B: Test socket 1 = inactive (P1826 = 0) and test socket 2 = active (P1836 = 1)
(refer to the index entry "Test sockets")

### 1830 Signal number test socket 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>14</td>
<td>530</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Description, refer to that for P1820.

### 1831 Shift factor test socket 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>12</td>
<td>47</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Description, refer to that for P1821.

### 1832 Offset test socket 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>-128</td>
<td>0</td>
<td>127</td>
<td>-</td>
<td>Integer16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Description, refer to that for P1822.

### 1833 Segment address test socket 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1834 Offset address test socket 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>FFFFFF</td>
<td>Hex</td>
<td>Unsigned32</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Note: Internal Siemens

### 1836 Status test socket 2

<table>
<thead>
<tr>
<th>Min</th>
<th>Standard</th>
<th>Max</th>
<th>Unit</th>
<th>Data type</th>
<th>Effective</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-</td>
<td>Unsigned16</td>
<td>immed.</td>
</tr>
</tbody>
</table>

Description, refer to that for P1826.
### A.2 Power module list

A power module is defined by its Order No. (MLFB) and internally by its code number.

#### Table A-1 Power module Order No. and code

<table>
<thead>
<tr>
<th>Order No. (MLFB)</th>
<th>Power module code</th>
<th>No. of axes</th>
<th>Transistor current [A(pk)]</th>
<th>Motor(^1) Motor(^1)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>P1106</td>
<td></td>
<td></td>
<td>(I_{n/\text{max}}) [A(rms)]</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0HAx</td>
<td>1</td>
<td>1/2</td>
<td>8</td>
<td>3/6</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0AAx</td>
<td>2</td>
<td>1/2</td>
<td>15</td>
<td>5/10</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0BAx</td>
<td>4</td>
<td>1/2</td>
<td>25</td>
<td>9/18</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0CAx</td>
<td>6</td>
<td>1/2</td>
<td>50</td>
<td>18/36</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0DAx</td>
<td>7</td>
<td>1</td>
<td>80</td>
<td>28/56</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0LAx</td>
<td>13(^2)</td>
<td>1</td>
<td>108</td>
<td>42/64</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0GAx</td>
<td>8(^2)</td>
<td>1</td>
<td>120</td>
<td>42/64</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0EAx</td>
<td>9</td>
<td>1</td>
<td>160</td>
<td>56/112</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0FAx</td>
<td>10</td>
<td>1</td>
<td>200</td>
<td>70/140</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0JAx</td>
<td>11(^2)</td>
<td>1</td>
<td>300</td>
<td>100/150 (from SW 12.2)</td>
</tr>
<tr>
<td>6SN112x-1Ax0x-0KAx</td>
<td>12</td>
<td>1</td>
<td>400</td>
<td>140/210</td>
</tr>
</tbody>
</table>

**Note:**
- rms: rms value
- pk: Peak value
- x: Space retainer for the Order No.
- \(I_n\): Continuous current
- \(I_{s6}\): Current for max. 4 min. for S6 load duty cycle
- \(I_{\text{max}}\): Peak current

1) At higher pulse frequencies (P1100) \(I_n, I_{\text{max}}\) and \(I_{s6}\) must be reduced to protect the power module.

The following applies before SW 2.4:
- The display using P1108, P1109 and P1111 depends on the pulse frequency.
- The reduction factor is already calculated into this parameter.
- The displayed values only correspond to the values in the table for the standard setting of the pulse frequency (P1100).

The following applies from SW 2.4:
- The display using P1108, P1109 and P1111 corresponds to the values in this table.
- The limiting factor is displayed in P1099 (limiting factor, power module currents).

Example:
- P1111 = 9 A, P1099 = 80 % - - - > reduced rated current \(I_n = 9 A\) • 80 % = 7.2 A

2) from SW 8.2
Reader’s note
Additional information about the power modules can be found in

Reference: /PJU/ SIMODRIVE 611, Configuration Manual, Drive Converters Chapter “Power modules”

\[ \text{\textit{i}^2t power module limiting (from SW 3.1)} \]

This limit protects the power module from continuous overload.

The power module current is limited according to a characteristic if the drive converter operates for an excessive time above the permissible load limit. The load limit is set per parameter.

The limit is removed step-by-step if the power module is no longer being operated above the load limit.

\[ \text{Note:} \]

\[ i_{\text{max}} = P1108 \text{ (current limit, power module)} \times P1099 \text{ (limit factor, power module currents)} \]

\[ i_{\text{S6}} = P1109 \text{ (current limit, power module S6)} \times P1099 \text{ (limit factor, power module currents)} \]

\[ i_{\text{n}} = P1111 \text{ (rated current, power module)} \times P1099 \text{ (limit factor, power module currents)} \]

Fig. A-2  Behavior when operation is continued at the current limit
The following signals are available for the "i^2t power module limit" function:

- Output terminal signal ----> function number 37
  (power module current not limited)
- PROFIBUS status signal ----> MeldW.10
  (power module current not limited)

The following parameters are available for the "i^2t power module limiting" function:

- Parameters which have to be set:
  - P1260  i^2t limiting, limit current power module S6
  - P1261  i^2t limiting, rated power module current
  These parameters are preset to protect the power module. It may be possible to protect the motor against continuous overload by reducing the parameter values.

- Parameters used for diagnostics:
  - P1262  i^2t time in limiting
  - P1263  actual i^2t limit factor
  - P1264  i^2t actual utilization factor (from SW 4.1)

Interrelationship between parameters:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Constant</th>
<th>Running</th>
</tr>
</thead>
<tbody>
<tr>
<td>P1262</td>
<td>100 %</td>
<td>&lt;100 %</td>
</tr>
<tr>
<td>P1263</td>
<td>&lt;100 %</td>
<td>100 %</td>
</tr>
</tbody>
</table>

---> Limiting?  No  Yes
A.3 List of motors

Reader’s note
General information about the motors can be found in
Reference: SIMODRIVE 611/MASTERDRIVES MC
Configuration Manuals
/PJAL/ General Part for Synchronous Motors
/ASAL/ General Part for Asynchronous Motors

A.3.1 List of the rotating synchronous motors

Reader’s note
Information about the motors can be found in
Reference: SIMODRIVE 611/MASTERDRIVES MC
Configuration Manuals
/PFK6/ AC Servomotors 1FK6
/PFK7/ Synchronous Motors 1FK7
/PFT6/ Synchronous Motors 1FT6
/PFT7/ Synchronous Motors 1FT7
SINAMICS_1PH8_Configuration Manual
/PH8S/ Main Spindle Motors 1PH8

Motor code for rotating synchronous motors (SRM)

Table A-2 Motor code for rotating synchronous motors (SRM)

<table>
<thead>
<tr>
<th>Order No. (MLFB)</th>
<th>Motor code P1102</th>
<th>$n_{\text{rated}}$ [RPM]</th>
<th>$M_0$ (100 K) [Nm]</th>
<th>$I_0$ (100 K) [A(rms)]</th>
</tr>
</thead>
<tbody>
<tr>
<td>1FK6032-6AK7x-xxxx</td>
<td>2401</td>
<td>6000</td>
<td>1.1</td>
<td>1.70</td>
</tr>
<tr>
<td>1FK6033-7AK7x-xxxx</td>
<td>2315</td>
<td>6000</td>
<td>1.3</td>
<td>2.20</td>
</tr>
<tr>
<td>1FK6040-6AK7x-xxxx</td>
<td>2402</td>
<td>6000</td>
<td>1.6</td>
<td>2.80</td>
</tr>
<tr>
<td>1FK6042-6AF7x-xxxx</td>
<td>2201</td>
<td>3000</td>
<td>3.2</td>
<td>2.80</td>
</tr>
<tr>
<td>1FK6043-7AH7x-xxxx</td>
<td>2311</td>
<td>4500</td>
<td>3.1</td>
<td>4.50</td>
</tr>
<tr>
<td>1FK6045-7AK7x-xxxx</td>
<td>2314</td>
<td>6000</td>
<td>3.1</td>
<td>6.40</td>
</tr>
<tr>
<td>1FK6044-7AF7x-xxxx</td>
<td>2211</td>
<td>3000</td>
<td>4.0</td>
<td>4.50</td>
</tr>
<tr>
<td>1FK6044-7AH7x-xxxx</td>
<td>2312</td>
<td>4500</td>
<td>4.0</td>
<td>6.30</td>
</tr>
<tr>
<td>1FK6060-6AF7x-xxxx</td>
<td>2202</td>
<td>3000</td>
<td>6.0</td>
<td>4.30</td>
</tr>
</tbody>
</table>
### Table A-2  Motor code for rotating synchronous motors (SRM), continued

<table>
<thead>
<tr>
<th>Order No. (MLFB)</th>
<th>Motor code</th>
<th>( n_{\text{rated}} ) [RPM]</th>
<th>( M_0 ) (100 K) [Nm]</th>
<th>( I_0 ) (100 K) [A(rms)]</th>
</tr>
</thead>
<tbody>
<tr>
<td>1FK6061-7AF7x-xxxx</td>
<td>2212</td>
<td>3000</td>
<td>6.4</td>
<td>6.10</td>
</tr>
<tr>
<td>1FK6061-7AH7x-xxxx</td>
<td>2313</td>
<td>4500</td>
<td>6.4</td>
<td>8.00</td>
</tr>
<tr>
<td>1FK6063-6AF7x-xxxx</td>
<td>2203</td>
<td>3000</td>
<td>11.0</td>
<td>7.90</td>
</tr>
<tr>
<td>1FK6064-7AF7x-xxxx</td>
<td>2213</td>
<td>3000</td>
<td>12.0</td>
<td>11.00</td>
</tr>
<tr>
<td>1FK6064-7AH7x-xxxx</td>
<td>2214</td>
<td>4500</td>
<td>12.0</td>
<td>15.00</td>
</tr>
<tr>
<td>1FK6080-6AF7x-xxxx</td>
<td>2204</td>
<td>3000</td>
<td>8.0</td>
<td>5.80</td>
</tr>
<tr>
<td>1FK6082-7AF7x-xxxx</td>
<td>2215</td>
<td>3000</td>
<td>14.0</td>
<td>10.60</td>
</tr>
<tr>
<td>1FK6083-6AF7x-xxxx</td>
<td>2205</td>
<td>3000</td>
<td>16.0</td>
<td>10.40</td>
</tr>
<tr>
<td>1FK6085-7AF7x-xxxx</td>
<td>2216</td>
<td>3000</td>
<td>22.0</td>
<td>22.50</td>
</tr>
<tr>
<td>1FK6100-8AF7x-xxxx</td>
<td>2206</td>
<td>3000</td>
<td>18.0</td>
<td>12.20</td>
</tr>
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### Table A-2  Motor code for rotating synchronous motors (SRM), continued

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# Table A-2 Motor code for rotating synchronous motors (SRM), continued

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### Table A-2  Motor code for rotating synchronous motors (SRM), continued

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Table A-2  Motor code for rotating synchronous motors (SRM), continued

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Table A-2  Motor code for rotating synchronous motors (SRM), continued

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### Table A-2  Motor code for rotating synchronous motors (SRM), continued

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<td>( I_0 ) (100 K) [A(rms)]</td>
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Unlisted motors

2000   -   -   -

Note:

x: Space retainer for the Order No.
### Parameters for unlisted motors (SRM)

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<td>Motor pole pair number</td>
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<td>Upper current limit, current controller adaptation</td>
<td>%</td>
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<td>Factor, current controller adaptation</td>
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A.3.2 List of permanent-magnet synchronous motors with field weakening (1FE1, 2SP1, PE spindle)

Reader’s note
Information about the motors can be found in
Reference: SIMODRIVE 611 Configuration Manual
/PJFE/ AC Motors for Main Spindle Drives
Synchronous Built-In Motors 1FE1
/PMS/ ECS Motor Spindle 2SP1

Motor code for permanent-magnet synchronous motors with field weakening

Table A-4 Motor code for 1FE1/2SP1 motors (PE spindle)

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## Table A-4  Motor code for 1FE1/2SP1 motors (PE spindle), continued

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<th>( n_{\text{rated}} ) [RPM]</th>
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Table A-4  Motor code for 1FE1/2SP1 motors (PE spindle), continued

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<th>Motor code</th>
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<th>( n_{\text{rated}} )</th>
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Table A-4  Motor code for 1FE1/2SP1 motors (PE spindle), continued

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### Table A-4  Motor code for 1FE1/2SP1 motors (PE spindle), continued

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<th>Motor code</th>
<th>( n_{\text{max}} ) [RPM]</th>
<th>( n_{\text{rated}} ) [RPM]</th>
<th>( M_0 ) ( (100 \text{ K}) ) [Nm]</th>
<th>( I_{\text{rated}} ) ( (100 \text{ K}) ) [A(rms)]</th>
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<td>135.0</td>
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<td>1FE1125-4WN11-xxxx</td>
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<td>12500</td>
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</table>

**Unlisted motors**

1999  -  -  -  -

**Note:** x Space retainer for the Order No.
### Parameters for unlisted motors (PE spindle)

Table A-5 Unlisted motor: Parameters for permanent-magnet synchronous motors with field weakening

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Unit</th>
<th>Value</th>
</tr>
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<tbody>
<tr>
<td>1015</td>
<td>Activate PE-MSD</td>
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<tr>
<td></td>
<td>1 = activated, 0 = de-activated</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1102</td>
<td>Motor code number</td>
<td></td>
<td>1999</td>
</tr>
<tr>
<td>1103</td>
<td>Rated motor current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1104</td>
<td>Maximum motor current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1112</td>
<td>Motor pole pair number</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1113</td>
<td>Torque constant</td>
<td>Nm/A</td>
<td></td>
</tr>
<tr>
<td>1114</td>
<td>Voltage constant</td>
<td>V(rms)</td>
<td></td>
</tr>
<tr>
<td>1115</td>
<td>Armature resistance (phase value)</td>
<td>Ω</td>
<td></td>
</tr>
<tr>
<td>1116</td>
<td>Armature inductance</td>
<td>mH</td>
<td></td>
</tr>
<tr>
<td>1117</td>
<td>Motor moment of inertia</td>
<td>kgm²</td>
<td></td>
</tr>
<tr>
<td>1118</td>
<td>Motor standstill current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1122</td>
<td>Motor limiting current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1128</td>
<td>Optimum load angle (from SW 3.3)</td>
<td>Degrees.</td>
<td></td>
</tr>
<tr>
<td>1136</td>
<td>Motor locked-rotor current</td>
<td>A(rms)</td>
<td></td>
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<tr>
<td>1142</td>
<td>Speed at the start of field weakening</td>
<td>RPM</td>
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<tr>
<td>1145</td>
<td>Stall torque reduction factor</td>
<td>%</td>
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<td>1146</td>
<td>Maximum motor speed</td>
<td>RPM</td>
<td></td>
</tr>
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<td>1149</td>
<td>Reluctance torque constant (from SW 3.3)</td>
<td>mH</td>
<td></td>
</tr>
<tr>
<td>1180</td>
<td>Lower current limit, current controller adaptation</td>
<td>%</td>
<td></td>
</tr>
<tr>
<td>1181</td>
<td>Upper current limit, current controller adaptation</td>
<td>%</td>
<td></td>
</tr>
<tr>
<td>1182</td>
<td>Factor, current controller adaptation</td>
<td>%</td>
<td></td>
</tr>
<tr>
<td>1400</td>
<td>Rated motor speed</td>
<td>RPM</td>
<td></td>
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A.3.3 List of permanent-magnet synchronous motors without field weakening, built-in torque motors (1FW6, from SW 6.1)

Reader’s note
Information about the motors can be found in
Reference: SIMODRIVE 611 Configuration Manual /PJTM/ Built-In Torque Motors 1FW6

Motor code for permanent-magnet synchronous motors without field weakening (1FW6)

Table A-6 Motor code for 1FW6 motors (built-in torque motors)

<table>
<thead>
<tr>
<th>Order No. (MLFB)</th>
<th>Motor code</th>
<th>( n_{\text{max}} ) [RPM]</th>
<th>( n_{\text{rated}} ) [RPM]</th>
<th>( M_0 ) (100 K) [Nm]</th>
<th>( I_{\text{rated}} ) (100 K) [A(rms)]</th>
</tr>
</thead>
<tbody>
<tr>
<td>1FW6090-0xx05-0Fxx</td>
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<td>1100</td>
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<td></td>
<td>1100</td>
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<td>119.0</td>
<td>8.2</td>
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<tr>
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<td>10.0</td>
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<td>166.0</td>
<td>16.0</td>
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<td>1100</td>
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<td>238.0</td>
<td>16.0</td>
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<td>1100</td>
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<td>357.0</td>
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Table A-6  Motor code for 1FW6 motors (built-in torque motors), continued

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<th>( n_{\text{rated}} ) [RPM]</th>
<th>( M_0 ) (100 K) [Nm]</th>
<th>( I_{\text{rated}} ) (100 K) [A(rms)]</th>
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### Table A-6  Motor code for 1FW6 motors (built-in torque motors), continued

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<th>( I_{\text{rated}} ) (100 K) [A(rms)]</th>
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Table A-6  Motor code for 1FW6 motors (built-in torque motors), continued

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<th>Order No. (MLFB)</th>
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<th>(n_{\text{max}})</th>
<th>(n_{\text{rated}})</th>
<th>(M_0) (100 K)</th>
<th>(I_{\text{rated}}) (100 K)</th>
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Note:
x: Space retainer for the Order No.

Parameters for third-party motors (1FW6)

Table A-7  Unlisted motor: Parameters for permanent-magnet synchronous motors without field weakening

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<td>A(rms)</td>
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<td>Motor pole pair number</td>
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<td>1113</td>
<td>Torque constant</td>
<td>Nm/A</td>
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<td>Voltage constant</td>
<td>V(rms)</td>
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<td>Armature resistance (phase value)</td>
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<td>Armature inductance</td>
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<td>Motor standstill current</td>
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<td>Motor limiting current</td>
<td>A(rms)</td>
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<td>1128</td>
<td>Optimum load angle</td>
<td>Degrees.</td>
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<td>1136</td>
<td>Motor locked-rotor current</td>
<td>A(rms)</td>
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<td>Speed at the start of field weakening</td>
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<td>1145</td>
<td>Stall torque reduction factor</td>
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<td>1146</td>
<td>Maximum motor speed</td>
<td>RPM</td>
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<td>1180</td>
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<td>Upper current limit, current controller adaptation</td>
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<td>Factor, current controller adaptation</td>
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<td>RPM</td>
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A.3.4 List of linear synchronous motors

Reader’s note
Information about the motors can be found in
Reference: SIMODRIVE 611 Linear Motor 1FN
Configuration Manual
- 1FN1 motors
- 1FN3-type peak-load motors
- Continuous Load Motors of the 1FN3 Product
Family

Motor code for
linear synchronous
motors (SLM)

Table A-8 Motor code for linear synchronous motors (SLM)

<table>
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<th>Order No. (MLFB)</th>
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Table A-8  Motor code for linear synchronous motors (SLM), continued

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Table A-8  Motor code for linear synchronous motors (SLM), continued

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Table A-8  Motor code for linear synchronous motors (SLM), continued

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<th>( F_{\text{max}} ) [N]</th>
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### Table A-8  Motor code for linear synchronous motors (SLM), continued

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<th>( F_{\text{max}} ) [N]</th>
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**Note:**
- \( x \): Space retainer for the Order No.
- 2 • 1FN ...: There are two motors, connected in parallel to a power module.
The following applies for 2 "identical" linear motors connected in parallel:

The value for the individual motor is handled, as specified in column "2 (parallel)" thus obtaining the value for the parallel circuit.

### Table A-9  Parameters for unlisted motors (SLM)

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<td>I₀</td>
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**Danger**

It is only permissible to connect temperature sensor cables with PELV or SELV voltage (refer to EN 60204–1 Chapter 6.4)
### A.3.5 List of induction motors

**Reader’s note**
Information about the motors can be found in

**Reference:**
- SIMODRIVE 611 Configuration Manuals
  - /APH2/ AC Induction Motors 1PH2
  - /APH4/ Induction Motors 1PH4
  - /APH7/ Induction Motors 1PH7
  - /PPM/ Hollow–Shaft Motors for Main Spindle Drives
    - 1PM6/1PM4

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**Motor code for rotating induction motors (ARM)**

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### Table A-10  Motor code for rotating induction motors (ARM), continued

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### Table A-10  Motor code for rotating induction motors (ARM), continued

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## Table A-10  Motor code for rotating induction motors (ARM), continued

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### Table A-10  Motor code for rotating induction motors (ARM), continued

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<td>1PM4101-xxF8x (L37)-D</td>
<td>639</td>
<td>4000</td>
<td>3.7</td>
<td>13.5</td>
</tr>
<tr>
<td>1PM4101-xxF8x (L37)-Y</td>
<td>638</td>
<td>1500</td>
<td>3.7</td>
<td>13.0</td>
</tr>
<tr>
<td>1PM4101-xxF8x-xxxx-D</td>
<td>601</td>
<td>4000</td>
<td>3.7</td>
<td>13.5</td>
</tr>
</tbody>
</table>
Table A-10  Motor code for rotating induction motors (ARM), continued

<table>
<thead>
<tr>
<th>Order No. (MLFB)</th>
<th>Motor code</th>
<th>( n_{\text{rated}} ) [RPM]</th>
<th>( P_{\text{rated}} ) [kW]</th>
<th>( I_{\text{rated}} ) [A(rms)]</th>
</tr>
</thead>
<tbody>
<tr>
<td>1PM4101-xxF8x-xxxx-Y</td>
<td>600</td>
<td>1500</td>
<td>3.7</td>
<td>13.0</td>
</tr>
<tr>
<td>1PM4101-xxW2x (L37)</td>
<td>640</td>
<td>1500</td>
<td>5.0</td>
<td>18.0</td>
</tr>
<tr>
<td>1PM4101-xxW2x-xxxx</td>
<td>620</td>
<td>1500</td>
<td>5.0</td>
<td>18.0</td>
</tr>
<tr>
<td>1PM4105-xxF8x (L37)-D</td>
<td>633</td>
<td>4000</td>
<td>7.5</td>
<td>24.0</td>
</tr>
<tr>
<td>1PM4105-xxF8x (L37)-Y</td>
<td>632</td>
<td>1500</td>
<td>7.5</td>
<td>23.0</td>
</tr>
<tr>
<td>1PM4105-xxF8x-xxxx-D</td>
<td>603</td>
<td>4000</td>
<td>7.5</td>
<td>24.0</td>
</tr>
<tr>
<td>1PM4105-xxF8x-xxxx-Y</td>
<td>602</td>
<td>1500</td>
<td>7.5</td>
<td>23.0</td>
</tr>
<tr>
<td>1PM4105-xxW2x (L37)</td>
<td>641</td>
<td>1500</td>
<td>11.0</td>
<td>38.0</td>
</tr>
<tr>
<td>1PM4105-xxW2x-xxxx</td>
<td>621</td>
<td>1500</td>
<td>11.0</td>
<td>38.0</td>
</tr>
<tr>
<td>1PM4133-xxF8x (L37)-D</td>
<td>634</td>
<td>4000</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM4133-xxF8x (L37)-Y</td>
<td>635</td>
<td>1500</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM4133-xxF8x-xxxx-D</td>
<td>605</td>
<td>4000</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM4133-xxF8x-xxxx-Y</td>
<td>604</td>
<td>1500</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM4133-xxW2x (L37)</td>
<td>642</td>
<td>1500</td>
<td>15.0</td>
<td>55.0</td>
</tr>
<tr>
<td>1PM4133-xxW2x-xxxx</td>
<td>618</td>
<td>1500</td>
<td>15.0</td>
<td>55.0</td>
</tr>
<tr>
<td>1PM4137-xxF8x (L37)-D</td>
<td>637</td>
<td>4000</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM4137-xxF8x-xxxx-D</td>
<td>607</td>
<td>4000</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM4137-xxF8x-xxxx-Y</td>
<td>606</td>
<td>1500</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM4137-xxW2x (L37)</td>
<td>643</td>
<td>1500</td>
<td>27.0</td>
<td>85.0</td>
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<tr>
<td>1PM4137-xxW2x-xxxx</td>
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<td>1500</td>
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<tr>
<td>1PM6101-xxF8x-(L37)-D</td>
<td>623</td>
<td>4000</td>
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<td>13.5</td>
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<td>1PM6101-xxF8x-(L37)-Y</td>
<td>622</td>
<td>1500</td>
<td>3.7</td>
<td>13.0</td>
</tr>
<tr>
<td>1PM6101-xxF8x-xxxx-D</td>
<td>609</td>
<td>4000</td>
<td>3.7</td>
<td>13.5</td>
</tr>
<tr>
<td>1PM6101-xxF8x-xxxx-Y</td>
<td>608</td>
<td>1500</td>
<td>3.7</td>
<td>13.0</td>
</tr>
<tr>
<td>1PM6105-xxF8x (L37)-D</td>
<td>625</td>
<td>4000</td>
<td>7.5</td>
<td>24.0</td>
</tr>
<tr>
<td>1PM6105-xxF8x (L37)-Y</td>
<td>624</td>
<td>1500</td>
<td>7.5</td>
<td>23.0</td>
</tr>
<tr>
<td>1PM6105-xxF8x-xxxx-D</td>
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<td>4000</td>
<td>7.5</td>
<td>24.0</td>
</tr>
<tr>
<td>1PM6105-xxF8x-xxxx-Y</td>
<td>610</td>
<td>1500</td>
<td>7.5</td>
<td>23.0</td>
</tr>
<tr>
<td>1PM6107-xxF8x-xxxx-D</td>
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<td>4000</td>
<td>9.0</td>
<td>30.0</td>
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<tr>
<td>1PM6107-xxF8x-xxxx-Y</td>
<td>644</td>
<td>1500</td>
<td>9.0</td>
<td>28.0</td>
</tr>
<tr>
<td>1PM6133-xxF8x (L37)-D</td>
<td>627</td>
<td>4000</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM6133-xxF8x (L37)-Y</td>
<td>626</td>
<td>1500</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM6133-xxF8x-xxxx-D</td>
<td>613</td>
<td>4000</td>
<td>11.0</td>
<td>41.0</td>
</tr>
<tr>
<td>1PM6133-xxF8x-xxxx-Y</td>
<td>612</td>
<td>1500</td>
<td>11.0</td>
<td>41.0</td>
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### Table A-10  Motor code for rotating induction motors (ARM), continued

<table>
<thead>
<tr>
<th>Order No. (MLFB)</th>
<th>Motor code</th>
<th>(n_{\text{rated}}) [RPM]</th>
<th>(P_{\text{rated}}) [kW]</th>
<th>(I_{\text{rated}}) [A(rms)]</th>
</tr>
</thead>
<tbody>
<tr>
<td>1PM6137-xxF8x (L37)-D</td>
<td>629</td>
<td>4000</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM6137-xxF8x (L37)-Y</td>
<td>628</td>
<td>1500</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM6137-xxF8x-xxxx-D</td>
<td>615</td>
<td>4000</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM6137-xxF8x-xxxx-Y</td>
<td>614</td>
<td>1500</td>
<td>18.5</td>
<td>56.0</td>
</tr>
<tr>
<td>1PM6138-xxF8x (L37)-D</td>
<td>630</td>
<td>4000</td>
<td>22.0</td>
<td>57.0</td>
</tr>
<tr>
<td>1PM6138-xxF8x (L37)-Y</td>
<td>631</td>
<td>1500</td>
<td>22.0</td>
<td>58.0</td>
</tr>
<tr>
<td>1PM6138-xxF8x-xxxx-D</td>
<td>617</td>
<td>4000</td>
<td>22.0</td>
<td>57.0</td>
</tr>
<tr>
<td>1PM6138-xxF8x-xxxx-Y</td>
<td>616</td>
<td>1500</td>
<td>22.0</td>
<td>58.0</td>
</tr>
<tr>
<td>2SP1253-8xAxx-0xxx-D</td>
<td>340</td>
<td>4000</td>
<td>13.2</td>
<td>29.0</td>
</tr>
<tr>
<td>2SP1253-8xAxx-0xxx-Y</td>
<td>341</td>
<td>1800</td>
<td>13.2</td>
<td>28.0</td>
</tr>
<tr>
<td>2SP1253-8xAxx-1xxx-D</td>
<td>343</td>
<td>4000</td>
<td>13.2</td>
<td>29.0</td>
</tr>
<tr>
<td>2SP1253-8xAxx-1xxx-Y</td>
<td>342</td>
<td>1800</td>
<td>13.2</td>
<td>28.0</td>
</tr>
<tr>
<td>2SP1255-8xAxx-0xxx-D</td>
<td>345</td>
<td>1800</td>
<td>11.7</td>
<td>28.0</td>
</tr>
<tr>
<td>2SP1255-8xAxx-0xxx-Y</td>
<td>344</td>
<td>800</td>
<td>11.7</td>
<td>30.0</td>
</tr>
<tr>
<td>2SP1255-8xAxx-1xxx-D</td>
<td>346</td>
<td>1800</td>
<td>11.7</td>
<td>28.0</td>
</tr>
<tr>
<td>2SP1255-8xAxx-1xxx-Y</td>
<td>347</td>
<td>800</td>
<td>11.7</td>
<td>30.0</td>
</tr>
<tr>
<td>DMR160.80.6RIF-Y</td>
<td>212</td>
<td>200</td>
<td>12.6</td>
<td>60.0</td>
</tr>
<tr>
<td>DMR160.80.6RIF-D</td>
<td>213</td>
<td>200</td>
<td>12.6</td>
<td>60.0</td>
</tr>
<tr>
<td>Unlisted motors</td>
<td>99</td>
<td>-</td>
<td>-</td>
<td>-</td>
</tr>
</tbody>
</table>

**Note:**
- \(x\): Space retainer for the Order No.
### Parameters for unlisted motors (ARM)

#### Table A-11 Parameters for unlisted motors (ARM)

<table>
<thead>
<tr>
<th>No.</th>
<th>Parameter</th>
<th>Unit</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>1102</td>
<td>Motor code</td>
<td>-</td>
<td>99</td>
</tr>
<tr>
<td>1103</td>
<td>Rated motor current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1117</td>
<td>Motor moment of inertia</td>
<td>kgm²</td>
<td></td>
</tr>
<tr>
<td>1119</td>
<td>Inductance of the series reactor</td>
<td>mH</td>
<td></td>
</tr>
<tr>
<td>1129</td>
<td>cos phi power factor</td>
<td>-</td>
<td></td>
</tr>
<tr>
<td>1130</td>
<td>Rated motor power</td>
<td>kW</td>
<td></td>
</tr>
<tr>
<td>1132</td>
<td>Rated motor voltage</td>
<td>V</td>
<td></td>
</tr>
<tr>
<td>1134</td>
<td>Rated motor frequency</td>
<td>Hz</td>
<td></td>
</tr>
<tr>
<td>1135</td>
<td>Motor no-load voltage</td>
<td>V</td>
<td></td>
</tr>
<tr>
<td>1136</td>
<td>Motor no-load current</td>
<td>A(rms)</td>
<td></td>
</tr>
<tr>
<td>1137</td>
<td>Stator resistance, cold</td>
<td>Ω</td>
<td></td>
</tr>
<tr>
<td>1138</td>
<td>Rotor resistance, cold</td>
<td>Ω</td>
<td></td>
</tr>
<tr>
<td>1139</td>
<td>Stator leakage reactance</td>
<td>Ω</td>
<td></td>
</tr>
<tr>
<td>1140</td>
<td>Rotor leakage reactance</td>
<td>Ω</td>
<td></td>
</tr>
<tr>
<td>1141</td>
<td>Magnetizing reactance</td>
<td>Ω</td>
<td></td>
</tr>
<tr>
<td>1142</td>
<td>Speed at the start of field weakening</td>
<td>RPM</td>
<td></td>
</tr>
<tr>
<td>1146</td>
<td>Maximum motor speed</td>
<td>RPM</td>
<td></td>
</tr>
<tr>
<td>1288</td>
<td>Shutdown threshold, thermal motor model</td>
<td>°C</td>
<td></td>
</tr>
<tr>
<td>1400</td>
<td>Rated motor speed</td>
<td>RPM</td>
<td></td>
</tr>
<tr>
<td>1602</td>
<td>Warning threshold, motor overtemperature</td>
<td>°C</td>
<td></td>
</tr>
</tbody>
</table>
A.4 Encoder list

A.4.1 Encoder code

The motor encoder being used is identified by its encoder code in P1006.
If encoder systems are used, which are not marketed by SIEMENS (third-party encoder, encoder code = 99), then additional parameters must be “manually” set corresponding to the measuring system manufacturer’s data (refer to Table A-12).
### Table A-12 Encoder code for motor encoders

<table>
<thead>
<tr>
<th>Rough classification</th>
<th>Encoder code P1006</th>
<th>Motor The Order No. (MLFB) defines the encoder code</th>
<th>Encoder</th>
<th>Additional parameters</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Incremental encoder</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Installation</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>1</td>
<td>1PH4xxx-xxxxx-xNxx&lt;sup&gt;1)&lt;/sup&gt; 1PH6xxx-xxxxx-xNxx 1PH7xxx-xxxxx-xNxx</td>
<td>ERN 1381/ERN 1387&lt;sup&gt;2)&lt;/sup&gt;</td>
<td>Voltage signals sin/cos 1Vpp 2048 pulses/revolution</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>2</td>
<td>1FT6xxx-xxxxx-xAxx 1FK6xxx-xxxxx-xAxx</td>
<td>ERN 1387&lt;sup&gt;2)&lt;/sup&gt;</td>
<td>Voltage signals sin/cos 1Vpp 2048 pulses/revolution C/D track</td>
</tr>
<tr>
<td><strong>Incremental encoder</strong></td>
<td></td>
<td></td>
<td></td>
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<tr>
<td>mounted</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>30</td>
<td>1PH2 1FE1</td>
<td>SIZAG 2</td>
<td>6FX2001–8RA03–1B/–1C/–1F&lt;sup&gt;3)&lt;/sup&gt;</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Voltage signals sin/cos 1Vpp 256 pulses/revolution</td>
</tr>
<tr>
<td></td>
<td>31</td>
<td>1PH2 1FE1</td>
<td>SIZAG 2</td>
<td>6FX2001–8RA03–1D/–1E/–1G&lt;sup&gt;3)&lt;/sup&gt;</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Voltage signals sin/cos 1Vpp 512 pulses/revolution</td>
</tr>
<tr>
<td></td>
<td>32</td>
<td>1PH2 1FE1</td>
<td>SIMAG H</td>
<td>6FX2001–6RB01–4xx&lt;sup&gt;3)&lt;/sup&gt;</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Voltage signals sin/cos 1Vpp 256 pulses/revolution</td>
</tr>
<tr>
<td></td>
<td>33</td>
<td>1PH2 1FE1</td>
<td>SIMAG H</td>
<td>6FX2001–6RB01–5xx&lt;sup&gt;3)&lt;/sup&gt;</td>
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<td></td>
<td></td>
<td></td>
<td>Voltage signals sin/cos 1Vpp 400 pulses/revolution</td>
</tr>
<tr>
<td></td>
<td>34</td>
<td>1PH2 1FE1</td>
<td>SIMAG H</td>
<td>6FX2001–6RB01–6xx&lt;sup&gt;3)&lt;/sup&gt;</td>
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<td></td>
<td></td>
<td></td>
<td>Voltage signals sin/cos 1Vpp 512 pulses/revolution</td>
</tr>
<tr>
<td><strong>Absolute encoder</strong></td>
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</tr>
<tr>
<td>Installation</td>
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<td></td>
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<tr>
<td></td>
<td>10</td>
<td>1FT6xxx-xxxxx-xExx 1FK6xxx-xxxxx-xExx</td>
<td>EQN 1325&lt;sup&gt;2)&lt;/sup&gt;</td>
<td>Voltage signals sin/cos 1Vpp EnDat, 2048 pulses/revolution, 4096 revolutions which can be differentiated between</td>
</tr>
<tr>
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<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>15&lt;sup&gt;1)&lt;/sup&gt;</td>
<td>1FK6xxx-xxxxx-xGxx</td>
<td>EQI 1324&lt;sup&gt;2)&lt;/sup&gt;</td>
<td>Voltage signals sin/cos 1Vpp EnDat, 32 pulses/revolution, 4096 revolutions which can be differentiated between</td>
</tr>
<tr>
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<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>70&lt;sup&gt;1)&lt;/sup&gt;</td>
<td>1FK702x-xxxxx-xJxx 1FK703x-xxxxx-xJxx</td>
<td>EQI 1125&lt;sup&gt;2)&lt;/sup&gt;</td>
<td>Voltage signals sin/cos 1Vpp EnDat, 16 pulses/revolution, 4096 revolutions which can be differentiated between</td>
</tr>
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### Table A-12  Encoder code for motor encoders, continued

<table>
<thead>
<tr>
<th>Rough classification</th>
<th>Encoder code P1006</th>
<th>Motor The Order No. (MLFB) defines the encoder code</th>
<th>Encoder</th>
<th>Additional parameters</th>
</tr>
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<tr>
<td><strong>Resolver</strong></td>
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<td></td>
<td></td>
<td></td>
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<tr>
<td>Incremental encoder</td>
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<td>1FT6xxx-xxxx-xxTxx 1FK6xxx-xxxx-xxTxx</td>
<td>Resolver 2p (1-speed)</td>
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</tr>
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<td>Installation</td>
<td>21</td>
<td>1FT6xxx-4xxxx-xxSxx Special design</td>
<td>Resolver 4p (2-speed)</td>
<td>-</td>
</tr>
<tr>
<td></td>
<td>22</td>
<td>1FT6xxx-6xxxx-xxSxx Special design</td>
<td>Resolver 6p (3-speed)</td>
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<tr>
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<td>23</td>
<td>1FT6xxx-8xxxx-xxSxx Special design</td>
<td>Resolver 8p (4-speed)</td>
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<td><strong>Linear encoders</strong></td>
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<tr>
<td>absolute</td>
<td>80</td>
<td>(from SW 9.1)</td>
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<td>LC 182²</td>
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<tr>
<td><strong>Without encoder</strong></td>
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<td>1LAx</td>
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<td>-</td>
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<tr>
<td><strong>Unlisted encoder</strong></td>
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<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with sin/cos 1Vpp</td>
<td></td>
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<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Unlisted encoder</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>with TTL signal⁴</td>
<td></td>
<td></td>
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<td></td>
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<tr>
<td></td>
<td></td>
<td></td>
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<td></td>
</tr>
<tr>
<td><strong>Special cases</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Unlisted resolver</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>99</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>Linear encoders</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Absolute</td>
<td>1FN1</td>
<td></td>
<td>e.g. LS 186/LS 484²</td>
<td>P1024 P1027</td>
</tr>
<tr>
<td></td>
<td>1FN3</td>
<td></td>
<td>e.g. LC 181¹</td>
<td>P1024 P1027</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>e.g. ERA 780C/RON 785C²</td>
<td>P1027 P1037 P1050 P1051 P1052 P1053</td>
</tr>
<tr>
<td><strong>Distance-coded measuring system</strong></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

1) x: Space retainer for the Order No.
2) Heidenhain is the manufacturer.
3) Order No. (MLFB) of the measuring wheel, as this is decisive for the number of pulses/revolution.
4) Only with control board, Order No. 6SN1118-□NH01-0AA□, from SW 8.1
A.4.2 Encoder adaptation

Encoder types

The following encoder types are supported:

- Incremental encoder with sin/cos 1Vpp
- Absolute value encoder with EnDat protocol and incremental tracks with sin/cos 1Vpp
- Resolver with pole pair numbers 1 to 6 and 1 to 64 from SW 7.1 with "SIMODRIVE 611 universal HR/HRS"
- Incremental encoders with TTL signal from SW 8.1 mounted on induction motors – only with "SIMODRIVE 611 universal HR/HRS" (Order No. 6SN1118-□NH01-0AA□)

Note

From SW 9.2:
Linear scales with resolution <100 nm can also be used as motor measuring system (indirect measuring system)!

Recommended encoder signals for fault-free operation with sin/cos 1 Vpp

The following encoder signals are recommended for fault-free operation:

- For track signals A+, A−, B+, B−, C+, C−, D+ and D−

![Signal characteristics for track signals A+, A−, B+, B−, C+, C−, D+ and D−](image)
- For zero pulse/reference signal R+ and R-

Fig. A-4  Signal characteristics for zero pulse/reference signal R+ and R-

Use of other encoder signals can trigger encoder signal monitoring. In particular, the lower signal level for reference signals R+ and R- must be carefully observed.

Resolution, resolver

From SW 6.1 for "SIMODRIVE 611 universal HR/HRS", it is possible to set the resolver resolution.

- Resolver resolution: 14 bits
  - P1011.2 = 1 (indirect measuring system)
  - P1030.2 = 1 (direct measuring system)

- Resolver resolution: 12 bits
  - P1011.2 = 0 (indirect measuring system)
  - P1030.2 = 0 (direct measuring system)
Note

After the resolver resolution has been changed from 12 bit to 14 bit, the resolution of several signals at analog output (X441, P0625/P0633) or at the test sockets DAU (P1820/P1830) also change. The signals involved are those signals whose normalization refers to the speed (P1711). These are the following signals:

- Speed actual value, motor (SRM, ARM)
- Speed setpoint (SRM, ARM)
- Speed setpoint, reference model (SRM, ARM)
- Absolute speed actual value (SRM, ARM)
- Speed setpoint at terminals 56.x/14.x, 24.x/20.x (SRM, ARM)
- Speed setpoint from PROFIBUS PPO (SRM, ARM)
- Speed correction value (SRM, ARM)
- Position controller output (SRM, ARM)
- Pre-controlled speed (SRM, ARM)
- DSC pre-controlled speed, motor (from SW 4.1)
- Equalization controller output (from SW 7.1)

Do you want the original resolution:
- Restore the original resolver resolution (P1011.2) or
- Adapt the shift factor, analog outputs P0627/P0634 or test sockets (DAU) P1821/1831 (+2 or -2)

Fault message 749 (from SW 7.1) is output, if the following conditions are not fulfilled:

- A 14-bit resolution was set for "SIMODRIVE 611 universal" ---＞ only a 12-bit resolution is possible
- Synchronous motor (SRM): .orientation
  ---＞ (max. encoder frequency/resolver pole pair number • 60 • 0.98) > P1147
- Induction motor (ARM): orientation
  ---＞ (max. encoder frequency/resolver pole pair number • 60 • 0.98) > min (P1146, P1465)
- Max. encoder frequency:
  ---＞ 12 bit: 432 Hz
  ---＞ 14 bits: 108 Hz

Note

If P1146, P1147 or P1465 are changed during operation so that the set limits are exceeded, then fault message 749 is output.

If the condition .orientation is not violated, then when the system is re-commissioned, the 14-bit resolution is preset and the speed actual value smoothing (P1522) is selected.

If the resolver resolution is manually changed, then it is also necessary to change the presetting of P1522 (refer to the parameter list Attachment A.1).
A.4 Encoder list

Parameterizing an indirect measuring system

An indirect measuring system is commissioned by entering a code number into P1006. If an encoder is used which is not saved in the firmware, then the data according to Table 4-14 must be entered.

Refer to the parameter overview Chapter A.1 for the significance of parameters P1005, P1021, P1022 and P1024.

Parameterizing a direct measuring system

For "SIMODRIVE 611 universal" when a direct measuring system is used, it must be appropriately parameterized.

The direct measuring system is commissioned by entering a code number into P1036. If an encoder is used which is not saved in the firmware, then the data according to Table 4-14 must be entered and P1036 set to 99.
### Parameters for unlisted encoders

Table A-13  Unlisted encoders: Which data are required for which encoder type?

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Name</th>
<th>Encoder pulse number</th>
<th>Absolute encoder (EnDat-SS)</th>
<th>Linear measuring system</th>
<th>Transmission rate</th>
<th>Multiturn resolution, abs. encoder</th>
<th>Single-turn resolution, abs. encoder</th>
<th>Grid spacing</th>
</tr>
</thead>
<tbody>
<tr>
<td>for indirect measuring system (IM)</td>
<td></td>
<td>P1005</td>
<td>P1027.3</td>
<td>P1027.4</td>
<td>P1027.14/15</td>
<td>P1021</td>
<td>P1022</td>
<td>P1024</td>
</tr>
<tr>
<td>for direct measuring system (DM) (from SW 3.3)</td>
<td></td>
<td>P1007</td>
<td>P1037.3</td>
<td>P1037.4</td>
<td>P1037.14/15</td>
<td>P1031</td>
<td>P1032</td>
<td>P1034</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Encoder type</th>
<th>Incremental</th>
<th>Rotary</th>
<th>Linear</th>
<th>-</th>
<th>0</th>
<th>1</th>
<th>x</th>
<th>-</th>
<th>-</th>
<th>-</th>
<th>x</th>
</tr>
</thead>
<tbody>
<tr>
<td>Encoder (EnDat)</td>
<td>Absolute</td>
<td>A</td>
<td>0</td>
<td>x</td>
<td>A</td>
<td>A</td>
<td>-</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Linear</td>
<td>A</td>
<td>1</td>
<td>1</td>
<td>x</td>
<td>-</td>
<td>A</td>
<td>-</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- x: Input required
- : No input required
- A: Display
- 0 or 1: The parameter bit must be set like this
- For an absolute value encoder (P1037.3 = 1), the drive can automatically detect the protocol being used (EnDat).

**Reader’s note**

Additional information on encoder systems is provided in:

**Reference:** /PJU/ SIMODRIVE 611,
Configuration Manual, Drive Converters
Chapter "Indirect and direct position sensing"
Space for your notes

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______________________________________________________________________
## List of Abbreviations

<table>
<thead>
<tr>
<th>Abbreviation</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ABS</td>
<td>Absolute</td>
</tr>
<tr>
<td>ADC</td>
<td>Analog-to-digital converter</td>
</tr>
<tr>
<td>AIE</td>
<td>Angular incremental encoder</td>
</tr>
<tr>
<td>AO</td>
<td>Analog output</td>
</tr>
<tr>
<td>ARM</td>
<td>Rotating induction motor</td>
</tr>
<tr>
<td>ASCII</td>
<td>American Standard Code for Information Interchange</td>
</tr>
<tr>
<td>Being prepared</td>
<td>Being prepared: This feature is presently not available</td>
</tr>
<tr>
<td>CE</td>
<td>Controller enable</td>
</tr>
<tr>
<td>ChkCfg</td>
<td>Abbreviation for the configuration telegram (Check Config.): this is sent from the master to the slave when establishing the bus</td>
</tr>
<tr>
<td>COM</td>
<td>Communications module</td>
</tr>
<tr>
<td>CPU</td>
<td>Central Processing Unit</td>
</tr>
<tr>
<td>CTS</td>
<td>Clear To Send: Signal that it is clear to send for serial data interfaces</td>
</tr>
<tr>
<td>DAC</td>
<td>Digital-to-analog converter</td>
</tr>
<tr>
<td>DM</td>
<td>Direct measuring system (encoder 2)</td>
</tr>
<tr>
<td>DP</td>
<td>Distributed Periphery (I/O)</td>
</tr>
<tr>
<td>DPC31</td>
<td>DP controller with integrated 8031 core</td>
</tr>
<tr>
<td>DPMC1, DPMC2</td>
<td>DP master, Class 1 or Class 2</td>
</tr>
<tr>
<td>DPR</td>
<td>Dual port RAM</td>
</tr>
<tr>
<td>DRAM</td>
<td>Dynamic memory (non-buffered)</td>
</tr>
<tr>
<td>DRF</td>
<td>Differential Resolver Function</td>
</tr>
<tr>
<td>DRIVE ES Basic</td>
<td>Software, which is linked in to the HW Config engineering tool of SIMATIC S7 for a special slave.</td>
</tr>
<tr>
<td>DSC</td>
<td>Dynamic servo control</td>
</tr>
<tr>
<td>DSP</td>
<td>Digital Signal Processor</td>
</tr>
<tr>
<td>DSR</td>
<td>Data Send Ready: Signals that data is ready to be sent from the serial data interfaces</td>
</tr>
<tr>
<td>DXB</td>
<td>Data eXchange Broadcast: DXB request is a task (request) which initiates a slave (publisher) to send its actual values as broadcast</td>
</tr>
</tbody>
</table>
### List of Abbreviations

**EGB**
Modules/components that can be destroyed by electrostatic discharge

**EMC**
Electromagnetic compatibility

**EMK**
Electromotive force

**EnDat**
Encoder-Data-Interface: Bidirectional synchronous-serial interface

**Note:**
The abbreviation EnDat refers to the descriptions provided in the FBU for EnDat 2.1 encoders from Heidenhain. EnDat 2.2 encoders with incremental interface are supported in the EnDat 2.1 mode.

**EPROM**
Program memory with permanently written program

**ET200**
Peripheral devices (I/O) from the SIMATIC range which can be coupled via PROFIBUS

**FD**
Feed drive

**FEPROM**
Flash EPROM: Memory which can be read and written into

**FFT**
Fast Fourier Transformation

**FG**
Function generator

**FIPO**
Fine interpolator

**EN+**
Enable voltage +24 V

**EN-**
Reference for the enable voltage

**GC**
Global-Control-Telegramm (Broadcast-Telegramm)

**GSD**
Master device file: describes the features of a DP slave

**HEX**
Abbreviation for a hexadecimal number

**HLG**
Ramp-function generator

**HW**
Hardware

**HWE**
Hardware limit switches

**I**
Input

**I/R**
Infeed/regenerative feedback module

**IBN**
Commissioning

**Id**
Field-generating current

**IF**
Pulse enable

**IM**
Induction motor without encoder (IM operation)

**IM**
Indirect measuring system (motor measuring system)

**IND**
Sub-index, sub-parameter number array index: Part of a PIV

**IPO**
Interpolator

**Iq**
Torque-generating current
<table>
<thead>
<tr>
<th>Abbreviation</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>KL</td>
<td>Terminal</td>
</tr>
<tr>
<td>Kv</td>
<td>Position loop gain (Kv factor)</td>
</tr>
<tr>
<td>LED</td>
<td>Light Emitting Diode</td>
</tr>
<tr>
<td>LSB</td>
<td>Least significant bit</td>
</tr>
<tr>
<td>MAV</td>
<td>Main actual value: Part of the PZD</td>
</tr>
<tr>
<td>MPI</td>
<td>Multi Point Interface: Multi-point serial interface</td>
</tr>
<tr>
<td>MS</td>
<td>Main setpoint: Part of the PZD</td>
</tr>
<tr>
<td>MSB</td>
<td>Most significant bit</td>
</tr>
<tr>
<td>MSCY_C1</td>
<td>Master Slave Cycle Class 1: Cyclic communications between the master (Class 1) and the slave</td>
</tr>
<tr>
<td>MSC</td>
<td>Dimension system grid: Smallest position unit</td>
</tr>
<tr>
<td>MSD</td>
<td>Main spindle drive</td>
</tr>
<tr>
<td>NC</td>
<td>Numerical control</td>
</tr>
<tr>
<td>NE</td>
<td>Line infeed</td>
</tr>
<tr>
<td>NIL</td>
<td>Not in List</td>
</tr>
<tr>
<td>NIST</td>
<td>Actual speed value</td>
</tr>
<tr>
<td>nset</td>
<td>Speed setpoint</td>
</tr>
<tr>
<td>O</td>
<td>Output</td>
</tr>
<tr>
<td>OC</td>
<td>Operating condition</td>
</tr>
<tr>
<td>OLP</td>
<td>Optical Link Plug: Bus connector for fiber-optic cables</td>
</tr>
<tr>
<td>P</td>
<td>Parameter</td>
</tr>
<tr>
<td>PCMCIA</td>
<td>Personal Computer Memory Card International Association</td>
</tr>
<tr>
<td>PD</td>
<td>Process data: Process data section of a PPO</td>
</tr>
<tr>
<td>PEH</td>
<td>Position reached and stop</td>
</tr>
<tr>
<td>PELV</td>
<td>Protective extra low voltage</td>
</tr>
<tr>
<td>PG</td>
<td>Programming device</td>
</tr>
<tr>
<td>PLC</td>
<td>Programmable logic controller</td>
</tr>
<tr>
<td>PIV</td>
<td>Parameter identification value: Parameterizing part of a PPO</td>
</tr>
<tr>
<td>PKE</td>
<td>Parameter identification: Part of a PKW</td>
</tr>
<tr>
<td>PLI</td>
<td>Pole position identification</td>
</tr>
<tr>
<td>PLL</td>
<td>Phase Locked Loop: Module for clock cycle synchronous operation</td>
</tr>
<tr>
<td>PNO</td>
<td>PROFIBUS User Organization</td>
</tr>
<tr>
<td>PO</td>
<td>POWER ON</td>
</tr>
<tr>
<td>Abbreviation</td>
<td>Description</td>
</tr>
<tr>
<td>--------------</td>
<td>-------------</td>
</tr>
<tr>
<td>PosAnw</td>
<td>Position selection</td>
</tr>
<tr>
<td>PosZsw</td>
<td>Positioning status word</td>
</tr>
<tr>
<td>PPO</td>
<td>Parameter process data object: Cyclic data telegram when transferring data with PROFIBUS-DP and the &quot;variable-speed drives&quot; profile</td>
</tr>
<tr>
<td>PRBS</td>
<td>Pseudo Random Binary Signal: White noise</td>
</tr>
<tr>
<td>PROFIBUS</td>
<td>Process field bus: Serial data bus</td>
</tr>
<tr>
<td>PTP</td>
<td>Point To Point</td>
</tr>
<tr>
<td>PWE</td>
<td>Parameter value: Part of a PKW</td>
</tr>
<tr>
<td>PWM</td>
<td>Pulse Width Modulation</td>
</tr>
<tr>
<td>RAM</td>
<td>Random Access Memory, i.e. program memory that can be read and written to</td>
</tr>
<tr>
<td>REL</td>
<td>Relative</td>
</tr>
<tr>
<td>RF</td>
<td>Controller enable</td>
</tr>
<tr>
<td>RLI</td>
<td>Rotor position identification, corresponds to the pole position identification (PLI)</td>
</tr>
<tr>
<td>RO</td>
<td>Read Only</td>
</tr>
<tr>
<td>SERCOS</td>
<td>Standard bus system for drives</td>
</tr>
<tr>
<td>SetPrm</td>
<td>Abbreviation for the parameterizing telegram (set param): this is sent from the master to the slave when establishing the bus</td>
</tr>
<tr>
<td>SF</td>
<td>Shift factor</td>
</tr>
<tr>
<td>SLM</td>
<td>Synchronous linear motor</td>
</tr>
<tr>
<td>SPC3</td>
<td>Siemens PROFIBUS Controller 3</td>
</tr>
<tr>
<td>SRM</td>
<td>Rotating synchronous motor</td>
</tr>
<tr>
<td>SS</td>
<td>Interface</td>
</tr>
<tr>
<td>SSI</td>
<td>Synchronous serial interface</td>
</tr>
<tr>
<td>STS</td>
<td>Gating unit</td>
</tr>
<tr>
<td>STW</td>
<td>Control word: Part of a PZD</td>
</tr>
<tr>
<td>SW</td>
<td>Software</td>
</tr>
<tr>
<td>SWE</td>
<td>Software limit switches</td>
</tr>
<tr>
<td>UI</td>
<td>Uncontrolled infeed</td>
</tr>
<tr>
<td>VDI</td>
<td>Verein Deutscher Ingenieure [Association of German Engineers]</td>
</tr>
<tr>
<td>VPM</td>
<td>VP module, module to limit the DC link voltage when a fault condition occurs (VPM: Voltage Protection Module)</td>
</tr>
<tr>
<td>Vpp</td>
<td>Peak-to-peak voltage</td>
</tr>
<tr>
<td>Abbreviation</td>
<td>Definition</td>
</tr>
<tr>
<td>--------------</td>
<td>-------------------------------------</td>
</tr>
<tr>
<td>WZM</td>
<td>Machine tools</td>
</tr>
<tr>
<td>xact</td>
<td>Actual position value</td>
</tr>
<tr>
<td>xset</td>
<td>Position setpoint value</td>
</tr>
<tr>
<td>ZK</td>
<td>DC link</td>
</tr>
<tr>
<td>ZSW</td>
<td>Status word: Part of a PZD</td>
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</tbody>
</table>
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Products for Totally Integrated Automation and Micro Automation
Catalog ST 70 • 2005
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Order No.: E86 060–K4670–A101–B2–7600 (English)

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Connections & System Components for SIMATIC, SINUMERIK,
MASTERDRIVES and SIMOTION
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Order No.: E86060–K4490–A101–B1–7600 (English)

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ISBN 3-7785-2781-9

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Design, Configuring and
Using PROFIBUS–DP with SIMATIC S7
SIEMENS; Publics MCD Verlag; Josef Weigmann, Gerhard Kilian
Order No.: A19100–L531–B714

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Components on the Fieldbus, Catalog ST PI 1999
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Draft PROFIBUS Profile
Version 3.1.2, September 2004
Version 4.1, May 2006
PROFIBUS User Organization e.V.
Haid-und-Neu-Straße 7
76131 Karlsruhe
Order No. 3.172
Manufacturer/Service Documentation

Note
A list of additional documents, updated on a monthly basis, is available on the Internet for the available languages at:
http://www.siemens.com/motioncontrol
Select "Support" --> "Technical documentation" --> "Ordering documentation" --> "Printed documentation".

/FBU_TE/
SIMODRIVE 611 universal
Mounting Instructions Replacing Spare Parts
Order No.: On request
(07.05 Edition)

/FBU_TEH/
SIMODRIVE 611 universal
Mounting Instructions Replacing Spare Parts HRS
Order No.: On request
(07.05 Edition)

/SP/
SIMODRIVE 611–A/611–D,
SimoPro 3.1
Program for Configuring Machine Tool Drives
Order No.: 6SC6 111–6PC00–0BA
Ordering location: WK Fürth

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Order No.: 6ES7 398–8AA03–8BA0
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/S7HR/
SIMATIC S7-300
Manual: STEP 7, Reference Manuals, V. 3.1
Order No.: 6ES7 810-4CA02-8BR0

(03.97 Edition)

/ET200X/
SIMATIC
Distributed ET 200X
Manual EWA 4NEB 780 6016-01 04
Part of the package with Order No.
6ES7 198-8FA01-8BA0

(05.01 Edition)
Certificates

Note

An excerpt is provided from the certification of the PROFIBUS User Organization e.V. and the certification of the “Safe Standstill” function. The complete certification for the “Safe standstill” function can be found as follows:

Reference: /PJU/ SIMODRIVE 611 Configuration Manual, Drive Converters
Certificate

PROFIBUS Nutzerorganisation e.V. grants to
Siemens AG, A&D MC RD1
Frauenauracher Str. 60, D-91056 Erlangen
the Certificate No.: Z00531 for the PROFIBUS Slave:

Product Name: SIMODRIVE 611U MC, POSMO SI/CA/CD
Revision: V2.5; SW/FW: V11.02.06; HW: 03.00/04.00
GSD: SI02808F.gsd; File Version: 27.02.2008

This certificate confirms that the product has successfully passed the certification tests with the following scope:

- DP-V0 MS0, Sync, Freeze, Fail, Safe
- DP-V1 MS1, Prm_Block, Structure, MS2
- DP-V2 IsoM, Lifesign
- Profile PROFIdrive 3.1.2
- Physical Layer RS485

Test Report Number: 245-9
Authorized Test Laboratory: Siemens AG, Fürth, Germany
Expiry date of Certificate: March 17, 2011

The tests were executed in accordance with the following documents:
"Test Specification for PROFIBUS DP Slaves, Version 3.0 from November 2005" and
"Test Specification for "PROFIdrive profile V3.1.2", Version 1.2, November 2004"

This certificate is granted according to the document "Framework for testing and certification of PROFIBUS products"

Karlsruhe, June 11, 2008

[Signature]

(Official in Charge)

Board of PROFIBUS Nutzerorganisation e. V.

[K. P. Lindner] [Prof. K. Bender]
Fig. D-2 Certificate, "Safe standstill" function (German, Zertifikat Funktion "Sicherer Halt")
Fig. D-3
Certificate, "Safe standstill" function (English)
EC Declaration of Conformity

Note

Attached is an excerpt from the EC Declaration of Conformity for SIMODRIVE 611 universal.

The complete EC Declaration of Conformity can be found as follows:

the Internet: http://www.support.automation.siemens.com under the Product/Order No. 15257461
or at the relevant branch office of the I DT MC group of Siemens AG.

Please observe the following documentation:

Reference: /EMC/ EMC Configuring Guidelines (Order No.: 6FC5297--AD30-0BP)
EG-Konformitätserklärung
EC Declaration of Conformity
No. E002 Version 07/08/15

Hersteller: SIEMENS AG

Anschrift: SIEMENS AG; A&D MC
Address: Fraunhoferstraße 80
91056 Erlangen

Produktbezeichnung: SIMOTION C230-2, P350, D4, CX32, E510

Produktbeschreibung: SIMATIC FM 353, FM 354, FM 357
SIROTEC RCM1D, RCM1P
SIMODRIVE 610, 611, MCU, FM STEPDRIVE, POSMO A / SI / CA / CD
SINAMICS S

Die bezeichneten Produkte stammen in den von uns in Verkehr gebrachten Ausführungen mit den Vorschriften folgender Europäischer Richtlinie überein:
The products described above in the form as delivered is in conformity with the provisions of the following European Directives:


Die Einhaltung dieser Richtlinie setzt einen EMV-gerechten Einbau der Produkte gemäß EMV-Aufbau-
richtlinie (Best. Nr. 6/FC 5297-CAD30-0AP/4) in die Gesamtanlage voraus. Anlagenkonfigurationen, bei der die Einhaltung dieser Richtlinie nachgewiesen wurde, sowie angewandte Normen, siehe:
For keeping the directive, it is required to install the products according to “EMC Mounting regulation” (Order No. 6/FC 5297-CAD30-0AP/3). For details of the system configurations, which meet the requirements of the directives, as well as for the standards applied see:

- Anhang A (Anlagenkonfigurationen) - Annex A (system configurations) : Version 07/04/30
- Anhang B (Komponenten) - Annex B (components) : Version 00/01/14
- Anhang C (Normen) - Annex C (standards) : Version 07/08/15

Erlangen, den 15.08.2007
Siemens AG

R. Müller
Entwicklungleitung

K. Krause
Qualitätsmanagement

Name, Funktion
Name, function

Unterschrift
Signature

Diese Erklärung bescheinigt die Übereinstimmung mit den genannten Richtlinien, stellt jedoch keine Beschaffenheits- und Haltbarkeitsgarantie gemäß § 443 BGB dar. Die Sicherheitsteilweise der mitgelieferten Produktdokumentation sind zu beachten.
This declaration certifies the conformity to the specified directives but contains no condition and durability guarantee to § 443 BGB. The safety instructions in the enclosed documentation shall be considered in detail.

Fig. D-4 EC Declaration of Conformity
Anhang A zur EG-Konformitätserklärung Nr. E002

A17: Typische Anlagenkonfiguration
SIMODRIVE 611 mit Regelungseinschub SIMODRIVE 611U (universal) / SIMATIC FM 357 (SINUMERIK FM NC)

Metallschrank

* bei E/R-Modul und UE-Modul 28kW
** Filter im Modulverband oder separat
*** oder FM NC

- Alle Komponenten, die gemäß Bestellunterlage für den Anlagenverbund von SIMODRIVE 611 zugelassen sind, erfüllen im Verbund die Richtlinie 89/336/EWG
- Normenkonformität siehe Anhang C

Hinweis:
In der Skizze der Anlagenkonfiguration werden nur die grundsätzlichen Maßnahmen zur Einhaltung der Richtlinie 89/336/EWG einer typischen Anlagenkonfiguration aufgezeigt. Zusätzlich, besonders bei Abweichung von dieser Anlagenkonfiguration, sind die Installationshinweise für EMV-gerechten Anlagenaufbau der Produktdokumentation und der EMV-Aufbaurichtlinie (Bestell Nr.: 6FC5297-0AD30-0AP0) zu beachten.
Fig. D-6  Annex A18 to the Declaration of Conformity (excerpt)
Anhang A zur EG-Konformitätserklärung Nr. E002

A21: Typische Anlagenkonfiguration
SIMOTION C230 und C230-2 / SIMODRIVE 611 mit Regelung 611U

1) bei EFR-Modul und UE-Modul 28kW
2) Filter im Modulverband oder separat
3) Bei Verwendung von SIMOTION C230 / C230-2 und Nachfolgekomponenten ist die Anordnung der Komponenten auch außerhalb des Schrankes zulässig (Leitungslänge zwischen Schrank und externen Komponenten < 5m).

- Alle Komponenten, die gemäß Bestellunterlage für den Anlagenverbund von SIMOTION C230 / C230-2 zugelassen sind, erfüllen im Verbund die Richtlinie 89/336/EWG
- Normenkonformität siehe Anhang C

Hinweis:
In der Skizze der Anlagenkonfiguration werden nur die grundsätzlichen Maßnahmen zur Einhaltung der Richtlinie 89/336/EWG einer typischen Anlagenkonfiguration aufgezeigt. Zusätzlich, besonders bei Abweichung von dieser Anlagenkonfiguration, sind die Installationshinweise für EMV-gerechten Anlagenaufbau der Produktdokumentation und der EMV-Aufbaurichtlinie (Bestell Nr.: 6FC5297- AD30-0AP ) zu beachten.
Anhang A zur EG-Konformitätserklärung Nr. E002

A22: Typische Anlagenkonfiguration

SINUMERIK 840Di / SIMODRIVE 611 mit Regelung SIMODRIVE 611U

Metallschrank

Maschinenbett

*) bei E/R-Modul und UE-Modul 28kW
**) Filter im Modulverbund oder separat

- Alle Komponenten, die gemäß Bestellunterlage für den Anlagenverbund von SINUMERIK 840Di und SIMODRIVE 611 mit Regelung 611U zugelassen sind, erfüllen im Verbund die Richtlinie 89/336/EWG
- Normenkonformität siehe Anhang C

Hinweis:

In der Skizze der Anlagenkonfiguration werden nur die grundsätzlichen Maßnahmen zur Einhaltung der Richtlinie 89/336/EWG einer typischen Anlagenkonfiguration aufgezeigt. Zusätzlich, besonders bei Abweichung von dieser Anlagenkonfiguration, sind die Installationshinweise für EMV-gerechten Anlagenaufbau der Produktdokumentation und der EMV-Aufbaurichtlinie (Bestell Nr.: 6FC5297-□ AD30-0AP □) zu beachten.

Fig. D-8 Annex A22 to the Declaration of Conformity (excerpt)
Anhang A zur EG-Konformitätserklärung Nr. E002

A23: Typische Anlagenkonfiguration

SIMOTION P350 / SIMODRIVE 611 mit Regelung SIMODRIVE 611U

Metallschrank

SIMOTION P350

Bedienstatus

E/A Modul ET20

Maschinenbett

Filtenerg.**

SIMODRIVE 611

Nennklemme

Drossel

*) bei E/R-Modul und UE-Modul 28kW

**) Filter im Modulverband oder separat

- Alle Komponenten, die gemäß Bestellunterlage für den Anlagenverbund von SIMOTION P350 zugelassen sind, erfüllen im Verbund die Richtlinie 89/336/EWG
- Normenkonformität siehe Anhang C

Hinweis:

In der Skizze der Anlagenkonfiguration werden nur die grundsätzlichen Maßnahmen zur Einhaltung der Richtlinie 89/336/EWG einer typischen Anlagenkonfiguration aufgezeigt. Zusätzlich, besonders bei Abweichung von dieser Anlagenkonfiguration, sind die Installationshinweise für EMV-gerechten Anlagenaufbau der Produktdokumentation und der EMV-Aufbaurichtlinie (Bestell Nr.: 6FC5297-□AD30-0AP□) zu beachten.
## Appendix C of the EC Declaration of Conformity No. E002

The agreement of the products with the directive of the 2004/108/EU counsel has been validated by testing in accordance with the following product standard and listed Basic Standards.

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Fig. D-10  Annex C to the EC Declaration of Conformity (excerpt)
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