

LXM32M

AC servo drive
Product manual
V1.05, 12.2010



Important information

This manual is part of the product.

Carefully read this manual and observe all instructions.

Keep this manual for future reference.

Hand this manual and all other pertinent product documentation over to all users of the product.

Carefully read and observe all safety instructions and the chapter "Before you begin - safety information".

Some products are not available in all countries.

For information on the availability of products, please consult the catalog.

Subject to technical modifications without notice.

All details provided are technical data which do not constitute warranted qualities.

Most of the product designations are registered trademarks of their respective owners, even if this is not explicitly indicated.

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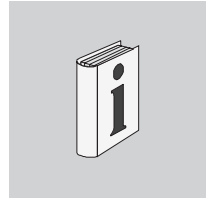
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About this manual



This manual is valid for LXM32M standard products. Chapter 1 "Introduction" lists the type code for this product. The type code allows you to identify whether your product is a standard product or a customized version.

The following manuals belong to this product:

- **Product manual**, describes the technical data, installation, commissioning and the operating modes and functions.
- **Motor manual**, describes the technical characteristics of the motors, including correct installation and commissioning.
- **Module manuals**, descriptions required for using modules.

Source manuals

The latest versions of the manuals can be downloaded from the Internet at:

<http://www.schneider-electric.com>

Source EPLAN Macros

For easier engineering, macro files and product master data are available for download from the Internet at:

<http://www.schneider-electric.com>

Corrections and suggestions

We always try to further optimize our manuals. We welcome your suggestions and corrections.

Please get in touch with us by e-mail:

techcomm@schneider-electric.com.

Work steps

If work steps must be performed consecutively, this sequence of steps is represented as follows:

- Special prerequisites for the following work steps
- Step 1
- ◁ Specific response to this work step
- Step 2

If a response to a work step is indicated, this allows you to verify that the work step has been performed correctly.

Unless otherwise stated, the individual steps must be performed in the specified sequence.

Making work easier

Information on making work easier is highlighted by this symbol:



Sections highlighted this way provide supplementary information on making work easier.

Parameters

In text sections, parameters are shown with the parameter name, for example `_IO_act`. The way parameters are represented in tables is explained in the chapter Parameters. The parameter list is sorted alphabetically by parameter name.

<i>SI units</i>	SI units are the original values. Converted units are shown in brackets behind the original value; they may be rounded. Example: Minimum conductor cross section: 1.5 mm ² (AWG 14)
<i>Inverted signals</i>	Inverted signals are represented by an overline, for example $\overline{\text{STO_A}}$ or $\overline{\text{STO_B}}$.
<i>Logic types</i>	The product supports logic type 1 and logic type 2 for digital signals. Note that most of the wiring examples show the logic type 1. The STO safety function must be wired using the logic type 1.
<i>Glossary</i>	Explanations of special technical terms and abbreviations.
<i>Index</i>	List of keywords with references to the corresponding page numbers.

Further reading

Recommended literature for further reading:

- Ellis, George: Control System Design Guide. Academic Press
- Kuo, Benjamin; Golnaraghi, Farid: Automatic Control Systems. John Wiley & Sons

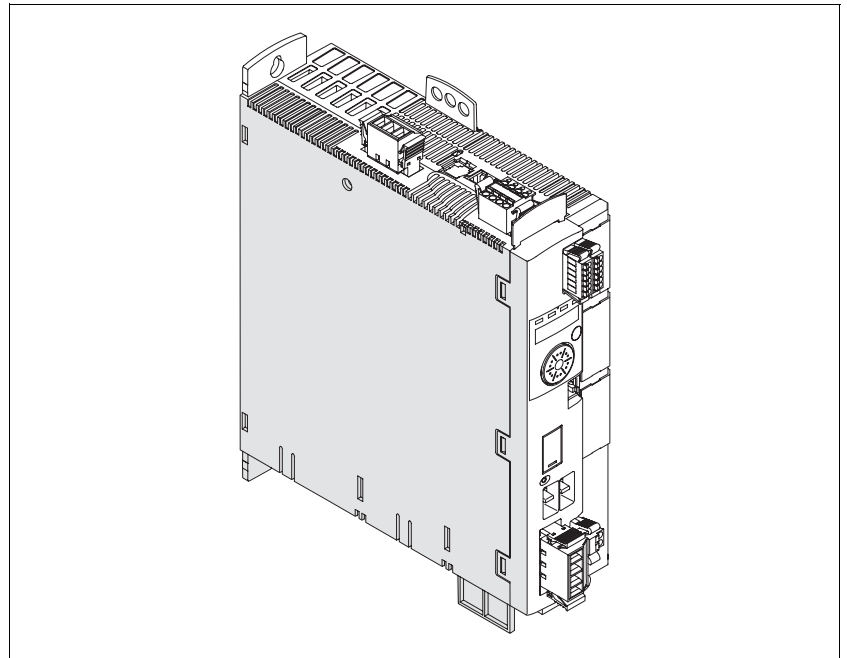
1 Introduction

1

1.1 Device overview

The Lexium 32 product family consists of three servo drive models that cover different application areas. Together with Lexium BMH servo motors or Lexium BSH servo motors as well as a comprehensive range of options and accessories, the drives are ideally suited to implement compact, high-performance drive solutions for a wide range of power requirements.

Lexium servo drive LXM32M This product manual describes the LXM32M servo drive.



Overview of some of the features of the LXM32M servo drive:

- The flexible product can be adapted to a wide variety of tasks by means of numerous modules.
- The available fieldbus modules comprise CANopen/CANmotion, DeviceNet, Profibus DP and EtherNet/IP.
- An encoder module allows you to add a second encoder interface for digital encoders, analog encoders or resolvers.
- A memory card slot is provided for backup and copying of parameters and fast device replacement.
- The safety function "Safe Torque Off" (STO) as per IEC 61800-5-2 is implemented on board. The optional safety module eSM offers additional safety functions.

1.2 Components and interfaces

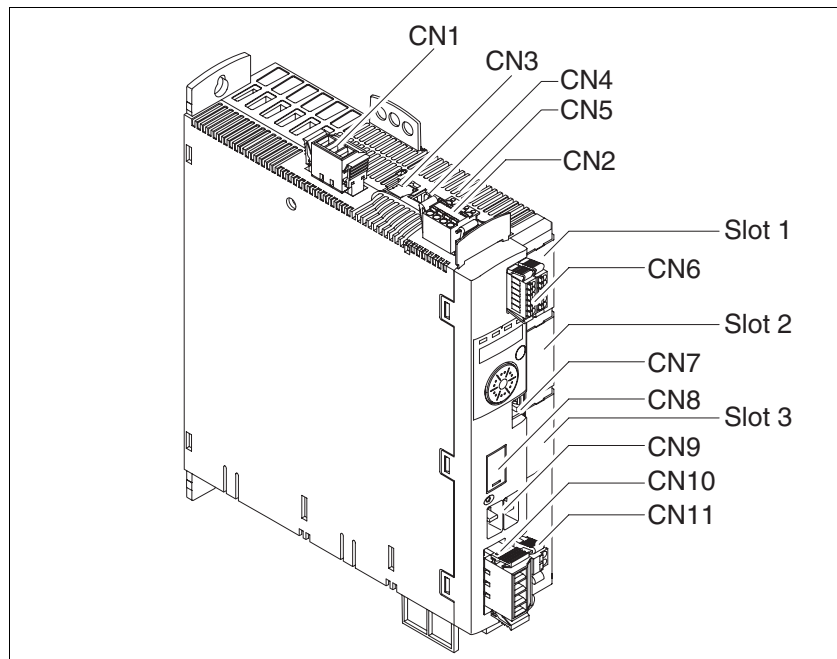


Figure 1.1 Overview of connections

- (1) Integrated HMI
- (CN1) Mains connection (power stage supply)
- (CN2) Connection for
 - 24V controller supply voltage
 - Safety function STO
- (CN3) Motor encoder connection (encoder 1)
- (CN4) Connection for PTO (Pulse Train Out)
 - ESIM (encoder simulation)
- (CN5) Connection for PTI (Pulse Train In)
 - Pulse/direction
 - or -
 - A/B encoder signals
 - or -
 - CW/CCW pulses
- (CN6) Inputs and outputs
 - 6 configurable digital inputs
 - 3 configurable digital outputs
- (CN7) Modbus (commissioning interface)
- (CN8) Connection for external braking resistor
- (CN9) DC bus connection
- (CN10) Motor phases connection
- (CN 11) Motor holding brake connection
- (Slot 1) Slot for safety module
- (Slot 2) Slot for encoder module (encoder 2)
- (Slot 3) Slot for fieldbus module

1.3 Type code

	LXM	32	M	D18	M2	(....)
Product designation LXM - Lexium						
Product type 32 - AC servo drive for one axis						
Interfaces C - Compact Drive with analog inputs and Pulse Train A - Advanced Drive with CANopen fieldbus M - Modular Drive						
Peak current U45 - 4.5A _{rms} U60 - 6A _{rms} U90 - 9A _{rms} D12 - 12A _{rms} D18 - 18A _{rms} D30 - 30A _{rms} D72 - 72A _{rms}						
Power stage supply [V_{ac}] M2 - 1~, 115/200/240V _{ac} 1) N4 - 3~, 208/400/480V _{ac} 1)						
Further options						

1) 208V_{ac} (3*200V_{ac} ... 3*240V_{ac}) DOM >10.05.2010, firmware version >V01.02.00

If you have questions concerning the type code, contact your Schneider Electric sales office. Contact your machine vendor if you have questions concerning customized versions.

Customized version: Position 12 of the type code is an "S". The subsequent number defines the customized version. Example:
LXM32....S123

The device designation is shown on the nameplate.

2 Before you begin - safety information

2

2.1 Qualification of personnel

Only appropriately trained persons who are familiar with and understand the contents of this manual and all other pertinent product documentation are authorized to work on and with this product. In addition, these persons must have received safety training to recognize and avoid hazards involved. These persons must have sufficient technical training, knowledge and experience and be able to foresee and detect potential hazards that may be caused by using the product, by changing the settings and by the mechanical, electrical and electronic equipment of the entire system in which the product is used.

All persons working on and with the product must be fully familiar with all applicable standards, directives, and accident prevention regulations when performing such work.

2.2 Intended use

This product is a drive for 3-phase servo motors and intended for industrial use according to this manual.

The product may only be used in compliance with all applicable safety regulations and directives, the specified requirements and the technical data.

Prior to using the product, you must perform a risk assessment in view of the planned application. Based on the results, the appropriate safety measures must be implemented.

Since the product is used as a component in an entire system, you must ensure the safety of persons by means of the design of this entire system (for example, machine design).

Operate the product only with the specified cables and accessories. Use only genuine accessories and spare parts.

The product must NEVER be operated in explosive atmospheres (hazardous locations, Ex areas).

Any use other than the use explicitly permitted is prohibited and can result in hazards.

Electrical equipment should be installed, operated, serviced, and maintained only by qualified personnel.

2.3 Hazard categories

Safety instructions to the user are highlighted by safety alert symbols in the manual. In addition, labels with symbols and/or instructions are attached to the product that alert you to potential hazards.

Depending on the seriousness of the hazard, the safety instructions are divided into 4 hazard categories.

DANGER

DANGER indicates an imminently hazardous situation, which, if not avoided, **will result** in death or serious injury.

WARNING

WARNING indicates a potentially hazardous situation, which, if not avoided, **can result** in death, serious injury, or equipment damage.

CAUTION

CAUTION indicates a potentially hazardous situation, which, if not avoided, **can result** in injury or equipment damage.

CAUTION

CAUTION used without the safety alert symbol, is used to address practices not related to personal injury (e.g. **can result** in equipment damage).

2.4 Basic information

DANGER

HAZARD OF ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

- Only appropriately trained persons who are familiar with and understand the contents of this manual and all other pertinent product documentation and who have received safety training to recognize and avoid hazards involved are authorized to work on and with this drive system. Installation, adjustment, repair and maintenance must be performed by qualified personnel.
- The system integrator is responsible for compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment.
- Many components of the product, including the printed circuit board, operate with mains voltage. Do not touch. Only use electrically insulated tools.
- Do not touch unshielded components or terminals with voltage present.
- The motor generates voltage when the shaft is rotated. Prior to performing any type of work on the drive system, block the motor shaft to prevent rotation.
- AC voltage can couple voltage to unused conductors in the motor cable. Insulate both ends of unused conductors in the motor cable.
- Do not short across the DC bus terminals or the DC bus capacitors.
- Before performing work on the drive system:
 - Disconnect all power, including external control power that may be present.
 - Place a "DO NOT TURN ON" label on all power switches.
 - Lock all power switches in the open position.
 - **Wait 15 minutes** to allow the DC bus capacitors to discharge. Measure the voltage on the DC bus as per chapter "DC bus voltage measurement" and verify the voltage is $< 42 V_{dc}$. The DC bus LED is not an indicator of the absence of DC bus voltage.
- Install and close all covers before applying voltage.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING**UNEXPECTED MOVEMENT**

Drives may perform unexpected movements because of incorrect wiring, incorrect settings, incorrect data or other errors.

Interference (EMC) may cause unpredictable responses in the system.

- Carefully install the wiring in accordance with the EMC requirements.
- Switch off the voltage at the inputs $\overline{STO_A}$ and $\overline{STO_B}$ to avoid an unexpected start of the motor before switching on and configuring the product.
- Do NOT operate the product with unknown settings or data.
- Perform a comprehensive commissioning test.

Failure to follow these instructions can result in death or serious injury.

⚠ WARNING**LOSS OF CONTROL**

- The designer of any control scheme must consider the potential failure modes of control paths and, for certain critical functions, provide a means to achieve a safe state during and after a path failure. Examples of critical control functions are emergency stop, overtravel stop, power outage and restart.
- Separate or redundant control paths must be provided for critical functions.
- System control paths may include communication links. Consideration must be given to the implication of unanticipated transmission delays or failures of the link.
- Observe all accident prevention regulations and local safety guidelines.¹⁾
- Each implementation of the product must be individually and thoroughly tested for proper operation before being placed into service.

Failure to follow these instructions can result in death or serious injury.

1) For USA: Additional information, refer to NEMA ICS 1.1 (latest edition), "Safety Guidelines for the Application, Installation, and Maintenance of Solid State Control" and to NEMA ICS 7.1 (latest edition), "Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable-Speed Drive Systems".

2.5 DC bus voltage measurement

Disconnect all power prior to starting work on the product.

DANGER

HAZARD OF ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

- Only appropriately trained persons who are familiar with and understand the safety instructions in the chapter "Before you begin - safety information" may perform the measurement.

Failure to follow these instructions will result in death or serious injury.

The DC bus voltage can exceed 800 V_{dc}. Use a properly rated voltage-sensing device for measuring. Procedure:

- ▶ Disconnect the voltage supply to all connections.
- ▶ Wait 15 minutes to allow the DC bus capacitors to discharge.
- ▶ Measure the DC bus voltage between the DC bus terminals to verify that the voltage is < 42 V_{dc}.
- ▶ If the DC bus capacitors do not discharge properly, contact your local Schneider Electric representative. Do not repair or operate the product.

The DC bus LED is not an indicator of the absence of DC bus voltage.

2.6 Functional safety

Using the safety functions integrated in this product requires careful planning. See chapter 5.9 "Safety function STO ("Safe Torque Off")", page 77 for additional information.

An pluggable safety module is available as an accessory; this module provides additional safety functions for the device. See the manual for the module for information on the extended safety functions.

2.7 Standards and terminology

Technical terms, terminology and the corresponding descriptions in this manual are intended to use the terms or definitions of the pertinent standards.

In the area of drive systems, this includes, but is not limited to, terms such as "safety function", "safe state", "fault", "fault reset", "failure", "error", "error message", "warning", "warning message", etc.

Among others, these standards include:

- IEC 61800 series: "Adjustable speed electrical power drive systems"
- IEC 61158 series: "Industrial communication networks - Fieldbus specifications"
- IEC 61784 series: "Industrial communication networks - Profiles"
- IEC 61508 series: "Functional safety of electrical/electronic/programmable electronic safety-related systems"

Also see the glossary at the end of this manual.

3 Technical Data

3

This chapter contains information on the ambient conditions and on the mechanical and electrical properties of the product family and the accessories.

3.1 Ambient conditions

Ambient conditions transportation and storage

The environment during transport and storage must be dry and free from dust. The maximum vibration and shock load must be within the specified limits.

Temperature	[°C]	-25 ... 70
-------------	------	------------

The following relative humidity is permissible during transportation and storage:

Relative humidity (non-condensing)	[%]	<95
------------------------------------	-----	-----

Ambient conditions for operation

The maximum permissible ambient temperature during operation depends on the mounting distances between the devices and on the required power. Observe the pertinent instructions in the chapter 6 "Installation".

Ambient temperature (no icing, non-condensing)	[°C]	0 ... 50
--	------	----------

The following relative humidity is permissible during operation:

Relative humidity (non-condensing)	[%]	5 ... 95
------------------------------------	-----	----------

The installation altitude is defined as altitude above mean sea level.

Installation altitude without derating	[m]	<1000
Installation altitude if all of the following conditions are met: <ul style="list-style-type: none"> • 45 °C max. ambient temperature • Reduction of the continuous power by 1% per 100 m above 1000 m 	[m]	1000 ... 2000
Installation altitude above mean sea level if all of the following conditions are met: <ul style="list-style-type: none"> • 40 °C max. ambient temperature • Reduction of the continuous power by 1% per 100 m above 1000 m • Overvoltages of the supply mains limited to overvoltage category II as per IEC 60664-1 	[m]	2000 ... 3000

Installation site and connection

For operation, the device must be mounted in a closed control cabinet. The device may only be operated with a permanently installed connection.

Pollution degree and degree of protection

Pollution degree		2
Degree of protection		IP 20

Degree of protection when the safety function is used

You must ensure that conductive substances cannot get into the product (pollution degree 2). Conductive substances may cause the safety function to become inoperative.

Vibration and shock

Vibration, sinusoidal		Tested as per IEC 60068-2-6 3.5 mm (from 2 Hz ... 8.4 Hz) 10 m/s ² (from 8.4 Hz ... 200 Hz)
Shock, semi-sinusoidal		Tested as per IEC 60068-2-27 150 m/s ² (for 11 ms)

3.2 Mechanical data

3.2.1 Dimensional drawings

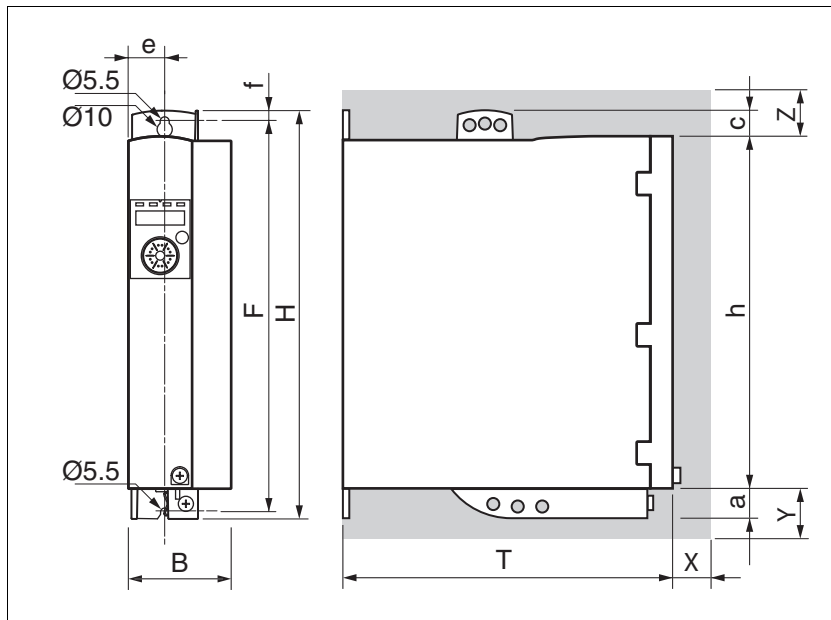


Figure 3.1 Dimensional drawing

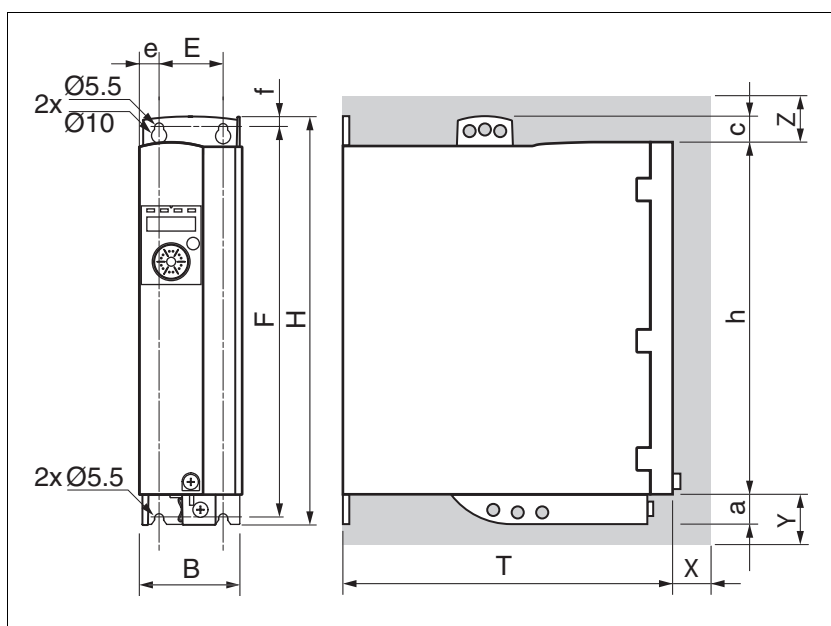


Figure 3.2 Dimensional drawing

LXM32•...		U45•• U60•• U90••	D12•• D18•• D30M2	D30N4	D72••
Figure		Figure 3.1	Figure 3.1	Figure 3.2	Figure 3.2
B	[mm]	68 ±1	68 ±1	68 ±1	108 ±1
T	[mm]	225	225	225	225
H	[mm]	270	270	270	270
e	[mm]	24	24	13	13
E	[mm]	-	-	42	82
F	[mm]	258	258	258	258
f	[mm]	7.5	7.5	7.5	7.5
a	[mm]	20	20	20	24
h	[mm]	230	230	230	230
c	[mm]	20	20	20	20
X required free space	[mm]	60	60	60	60
Y required free space	[mm]	100	100	100	100
Z required free space	[mm]	100	100	100	100
Type of cooling		Convec- tion ¹⁾	Fan 40 mm	Fan 60 mm	Fan 80 mm

1) >1 m/s

The connection cables of the devices are routed to the top and to the bottom. The following distances are required in order to enable sufficient air circulation and cable installation without bends:

- At least 100 mm of free space is required above the device.
- At least 100 mm of free space is required below the device.
- At least 60 mm of free space is required in front of the device. The controls must be accessible.

Mass

LXM32•...		U45••	U60•• U90••	D12•• D18M2	D18N4 D30M2	D30N4	D72N4
Mass	kg	1.7	1.8	1.9	2.1	2.7	4.8

3.3 Electrical Data

The products are intended for industrial use and may only be operated with a permanently installed connection.

3.3.1 Power stage

Mains voltage: range and tolerance

115/230 V _{ac} single-phase	[V _{ac}]	100 -15% ... 120 +10% 200 -15% ... 240 +10%
208/400/480 V _{ac} three-phase ¹⁾	[V _{ac}]	200 -15% ... 240 +10% 380 -15% ... 480 +10%
Frequency	[Hz]	50 -5% ... 60 +5%

1) 208V_{ac} (3*200V_{ac} ... 3*240V_{ac}) DOM >10.05.2010, firmware version >V01.02.00

Transient overvoltages		Overvoltage category III ¹⁾
Rated voltage to ground	[V _{ac}]	300

1) Depends on installation altitude, see chapter 3.1 "Ambient conditions"

Type of mains (type of grounding)

TT mains, TN mains	Permitted
IT mains	Not permitted
Mains with grounded line conductor	Not permitted

Inrush current and leakage current

Inrush current	[A]	<60
Leakage current (as per IEC 60990, figure 3)	[mA]	<30 ¹⁾

1) Measured on mains with grounded neutral point, without external mains filter. If residual current devices are used, note that a 30mA residual current device can trigger at values as low as 15mA. In addition, there is a high-frequency leakage current which is not considered in the measurement. Residual current devices respond differently to this.

Harmonic currents and impedance

The harmonic currents depend on the impedance of the supply mains. This is expressed in terms of the short-circuit current of the supply mains. If the supply mains has a higher short-circuit current than indicated in the Technical Data for the device, use upstream mains reactors. See chapter 12.16 "Mains reactors" for suitable mains reactors.

Monitoring the continuous output current

The continuous output current is monitored by the device. If the continuous output current is permanently exceeded, the device reduces the output current. The continuous output current can flow if the ambient temperature is below 50°C and if the internal braking resistor does not generate heat.

Monitoring the continuous output power

The continuous output power is monitored by the device. If the continuous output power is exceeded, the device reduces the output current.

Peak output current for 1 second

The device can provide the peak output current for 1 second. If the peak output current flows when the motor is at a standstill, the higher load on a single semiconductor switch causes the current limitation to become active earlier than when the motor moves.

PWM frequency power stage The PWM frequency of the power stage is set to a fixed value.

PWM frequency power stage	[kHz]	8
---------------------------	-------	---

Approved motors The following motors can be connected to this device family: BMH, BSH. When selecting, consider the type and amount of the mains voltage and the motor inductance.

Further conditions must be fulfilled if you use the safety module eSM.

If an encoder module is installed, additional motors can be used. The conditions can be found in the corresponding manual for the module.

Please inquire for other motors.

Inductance of motor The permissible minimum inductance and the maximum permissible inductance of the motor to be connected depend on the device type and the nominal mains voltage. See the tables on pages 27 to 31 for the values.

The specified minimum inductance value limits the current ripple of the peak output current. If the inductance value of the connected motor is less than the specified minimum inductance value, this may adversely affect current control and trigger motor phase current monitoring.

3.3.1.1 Data for single-phase devices at 115V_{ac}

LXM32•...		U45M2•...	U90M2•...	D18M2•...	D30M2•...	
Nominal voltage	[V]	115 (1 ~)	115 (1 ~)	115 (1 ~)	115 (1 ~)	
Inrush current limitation	[A]	1.7	3.5	8	16	
Maximum fuse to be connected upstream ¹⁾	[A]	25	25	25	25	
Short-circuit current rating (SCCR)	[kA]	5	5	5	5	
Continuous output current	[A _{rms}]	1.5	3	6	10	
Peak output current (for 1 s)	[A _{rms}]	3	6	10	15	
Minimum inductance motor (phase/phase)	[mH]	5.5	3	1.4	0.8	
Values without mains reactor						
Nominal power ²⁾	[kW]	0.15	0.3	0.5	0.8	
Input current at nominal power and nominal voltage ²⁾	[A _{rms}]	2.9	5.4	8.5	12.9	
Total harmonic distortion THD of the input current ²⁾	[%]	173	159	147	135	
Power dissipation ³⁾	[W]	7	15	28	33	
Maximum inrush current ⁴⁾	[A]	111	161	203	231	
Time for maximum inrush current	[ms]	0.8	1.0	1.2	1.4	
Values with mains reactor						
Mains reactor	[mH]	5	2	2	2	
Nominal power	[kW]	0.2	0.4	0.8	0.8	
Input current at nominal power and nominal voltage	[A _{rms}]	2.6	5.2	9.9	9.9	
Total harmonic distortion THD of the input current	[%]	85	90	74	72	
Power dissipation ³⁾	[W]	8	16	32	33	
Maximum inrush current ⁴⁾	[A]	22	48	56	61	
Time for maximum inrush current	[ms]	3.3	3.1	3.5	3.7	

1) Fuses: Circuit breakers with B or C characteristic; see 3.4 "Conditions for UL 508C and CSA" for UL and CSA.

Lower ratings are permissible. The fuse must be rated in such a way that the fuse does not trip at the specified input current.

2) At a mains impedance corresponding to a short-circuit current of the supply mains of 1 kA

3) Condition: internal braking resistor not active; value at nominal current, nominal voltage and nominal power; value approximately proportional with output current

4) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time

3.3.1.2 Data for single-phase devices at 230V_{ac}

LXM32•...		U45M2•...	U90M2•...	D18M2•...	D30M2•...	
Nominal voltage	[V]	230 (1 ~)	230 (1 ~)	230 (1 ~)	230 (1 ~)	
Inrush current limitation	[A]	3.5	6.9	16	33	
Maximum fuse to be connected upstream ¹⁾	[A]	25	25	25	25	
Short-circuit current rating (SCCR)	[kA]	5	5	5	5	
Continuous output current	[A _{rms}]	1.5	3	6	10	
Peak output current (for 1 s)	[A _{rms}]	4.5	9	18	30	
Minimum inductance motor (phase/phase)	[mH]	5.5	3	1.4	0.8	
Values without mains reactor						
Nominal power ²⁾	[kW]	0.3	0.5	1.0	1.6	
Input current at nominal power and nominal voltage ²⁾	[A _{rms}]	2.9	4.5	8.4	12.7	
Total harmonic distortion THD of the input current ²⁾	[%]	181	166	148	135	
Power dissipation ³⁾	[W]	10	18	34	38	
Maximum inrush current ⁴⁾	[A]	142	197	240	270	
Time for maximum inrush current	[ms]	1.1	1.5	1.8	2.1	
Values with mains reactor						
Mains reactor	[mH]	5	2	2	2	
Nominal power	[kW]	0.5	0.9	1.6	2.2	
Input current at nominal power and nominal voltage	[A _{rms}]	3.4	6.3	10.6	14.1	
Total harmonic distortion THD of the input current	[%]	100	107	93	86	
Power dissipation ³⁾	[W]	11	20	38	42	
Maximum inrush current ⁴⁾	[A]	42	90	106	116	
Time for maximum inrush current	[ms]	3.5	3.2	3.6	4.0	

1) Fuses: Circuit breakers with B or C characteristic; see 3.4 "Conditions for UL 508C and CSA" for UL and CSA.

Lower ratings are permissible. The fuse must be rated in such a way that the fuse does not trip at the specified input current.

2) At a mains impedance corresponding to a short-circuit current of the supply mains of 1 kA

3) Condition: internal braking resistor not active; value at nominal current, nominal voltage and nominal power; value approximately proportional with output current

4) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time

3.3.1.3 Data for three-phase devices at 208V_{ac}¹

LXM32•...		U60N4•...	D12N4•...	D18N4•...	D30N4•...	D72N4•...
Nominal voltage	[V]	208 (3 ~)	208 (3 ~)	208 (3 ~)	208 (3 ~)	208 (3 ~)
Inrush current limitation	[A]	2.2	4.9	10	10	29
Maximum fuse to be connected upstream ¹⁾	[A]	30/32	30/32	30/32	30/32	30/32
Short-circuit current rating (SCCR)	[kA]	5	5	5	5	
Continuous output current	[A _{rms}]	1.5	3	6	10	24
Peak output current (for 1 s)	[A _{rms}]	6	12	18	30	72
Minimum inductance motor (phase/phase)	[mH]	8.5	4.5	3	1.7	0.7
Values without mains reactor						
Nominal power	[kW]	0.35	0.7	1.2	2.0	5
Input current at nominal power and nominal voltage	[A _{rms}]	1.8	3.6	6.2	9.8	21.9
Total harmonic distortion THD of the input current	[%]	132	136	140	128	106
Power dissipation without mains reactor ²⁾	[W]	13	26	48	81	204
Maximum inrush current ³⁾	[A]	60	180	276	341	500
Time for maximum inrush current	[ms]	0.5	0.7	0.9	1.1	1.5
Values with mains reactor						
Mains reactor	[mH]	2	2	1	1	1
Nominal power	[kW]	0.4	0.8	1.5	2.6	6.5
Input current at nominal power and nominal voltage	[A _{rms}]	1.7	3.1	6.0	9.2	21.1
Total harmonic distortion THD of the input current	[%]	97	79	78	59	34
Power dissipation ²⁾	[W]	13	27	51	86	218
Maximum inrush current ³⁾	[A]	19	55	104	126	155
Time for maximum inrush current	[ms]	1.9	2.6	2.6	3.0	3.6

1) Fuses: Circuit breakers with B or C characteristic; see 3.4 "Conditions for UL 508C and CSA" for UL and CSA.

Specification 30/32A: the maximum permissible value for UL is 30A

Lower ratings are permissible. The fuse must be rated in such a way that the fuse does not trip at the specified input current.

2) Condition: internal braking resistor not active; value at nominal current, nominal voltage and nominal power; value approximately proportional with output current

3) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time

1. 208V_{ac} (3*200V_{ac} ... 3*240V_{ac}) DOM >10.05.2010, firmware version >V01.02.00

3.3.1.4 Data for three-phase devices at 400V_{ac}

LXM32•...		U60N4•...	D12N4•...	D18N4•...	D30N4•...	D72N4•...
Nominal voltage	[V]	400 (3 ~)	400 (3 ~)	400 (3 ~)	400 (3 ~)	400 (3 ~)
Inrush current limitation	[A]	4.3	9.4	19	19	57
Maximum fuse to be connected upstream ¹⁾	[A]	30/32	30/32	30/32	30/32	30/32
Short-circuit current rating (SCCR)	[kA]	5	5	5	5	
Continuous output current	[A _{rms}]	1.5	3	6	10	24
Peak output current (for 1 s)	[A _{rms}]	6	12	18	30	72
Minimum inductance motor (phase/phase)	[mH]	8.5	4.5	3	1.7	0.7
Values without mains reactor						
Nominal power	[kW]	0.4	0.9	1.8	3.0	7
Input current at nominal power and nominal voltage	[A _{rms}]	1.4	2.9	5.2	8.3	17.3
Total harmonic distortion THD of the input current	[%]	191	177	161	148	126
Power dissipation ²⁾	[W]	17	37	68	115	283
Maximum inrush current ³⁾	[A]	90	131	201	248	359
Time for maximum inrush current	[ms]	0.5	0.7	0.9	1.1	1.4
Values with mains reactor						
Mains reactor	[mH]	2	2	1	1	1
Nominal power	[kW]	0.8	1.6	3.3	5.6	13
Input current at nominal power and nominal voltage	[A _{rms}]	1.8	3.4	6.9	11.1	22.5
Total harmonic distortion THD of the input current	[%]	108	90	90	77	45
Power dissipation ²⁾	[W]	19	40	74	125	308
Maximum inrush current ³⁾	[A]	28	36	75	87	112
Time for maximum inrush current	[ms]	1.9	2.3	2.3	2.6	3.0

1) Fuses: Circuit breakers with B or C characteristic; see 3.4 "Conditions for UL 508C and CSA" for UL and CSA.

Specification 30/32A: the maximum permissible value for UL is 30A

Lower ratings are permissible. The fuse must be rated in such a way that the fuse does not trip at the specified input current.

2) Condition: internal braking resistor not active; value at nominal current, nominal voltage and nominal power; value approximately proportional with output current

3) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time

3.3.1.5 Data for three-phase devices at 480V_{ac}

LXM32•...		U60N4•...	D12N4•...	D18N4•...	D30N4•...	D72N4•...
Nominal voltage	[V]	480 (3 ~)	480 (3 ~)	480 (3 ~)	480 (3 ~)	480 (3 ~)
Inrush current limitation	[A]	5.1	11.3	23	23	68
Maximum fuse to be connected upstream ¹⁾	[A]	30/32	30/32	30/32	30/32	30/32
Short-circuit current rating (SCCR)	[kA]	5	5	5	5	
Continuous output current	[A _{rms}]	1.5	3	6	10	24
Peak output current (for 1 s)	[A _{rms}]	6	12	18	30	72
Minimum inductance motor (phase/phase)	[mH]	8.5	4.5	3	1.7	0.7
Values without mains reactor						
Nominal power	[kW]	0.4	0.9	1.8	3.0	7
Input current at nominal power and nominal voltage	[A _{rms}]	1.2	2.4	4.5	7.0	14.6
Total harmonic distortion THD of the input current	[%]	201	182	165	152	129
Power dissipation ²⁾	[W]	20	42	76	129	315
Maximum inrush current ³⁾	[A]	129	188	286	350	504
Time for maximum inrush current	[ms]	0.6	0.7	1.0	1.2	1.6
Values with mains reactor						
Mains reactor	[mH]	2	2	1	1	1
Nominal power	[kW]	0.8	1.6	3.3	5.6	13
Input current at nominal power and nominal voltage	[A _{rms}]	1.6	2.9	6.0	9.6	19.5
Total harmonic distortion THD of the input current	[%]	116	98	98	85	55
Power dissipation ²⁾	[W]	21	44	82	137	341
Maximum inrush current ³⁾	[A]	43	57	116	137	177
Time for maximum inrush current	[ms]	1.9	2.4	2.4	2.7	3.2

1) Fuses: Circuit breakers with B or C characteristic; see 3.4 "Conditions for UL 508C and CSA" for UL and CSA.

Specification 30/32A: the maximum permissible value for UL is 30A

Lower ratings are permissible. The fuse must be rated in such a way that the fuse does not trip at the specified input current.

2) Condition: internal braking resistor not active; value at nominal current, nominal voltage and nominal power; value approximately proportional with output current

3) Extreme case, off/on pulse before the inrush current limitation responds, see next line for maximum time

3.3.1.6 Peak output currents

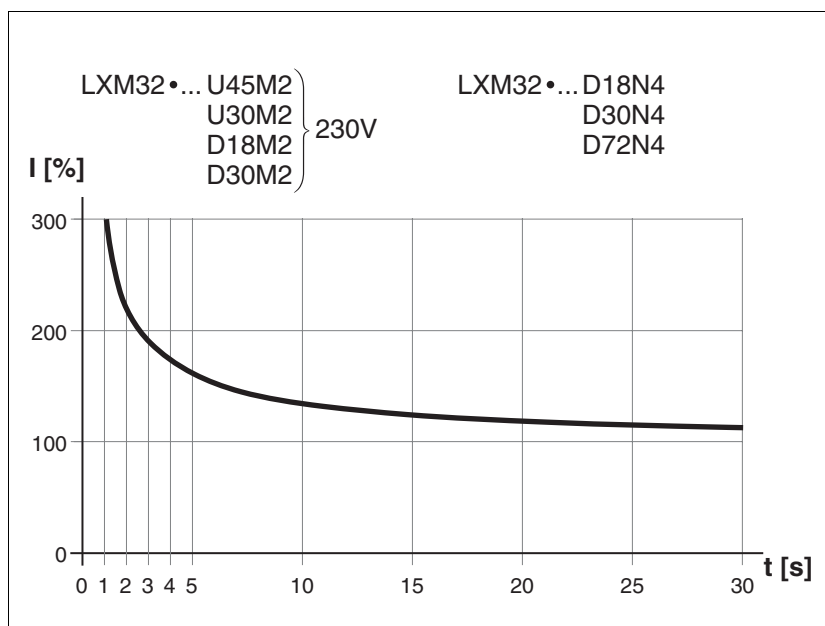


Figure 3.3 Peak output current over time (with reference to the continuous output current)

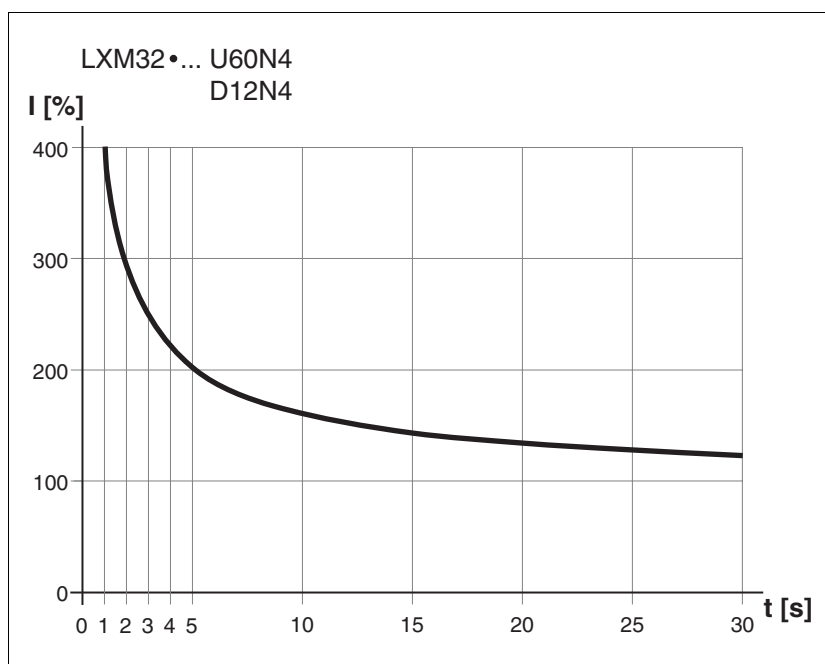


Figure 3.4 Peak output current over time (with reference to the continuous output current)

3.3.1.7 DC bus data for single-phase devices

LXM32•... (1 ~)		U45M2		U90M2		D18M2		D30M2			
Nominal voltage (1 ~)	[V]	115	230	115	230	115	230	115	230		
Nominal voltage DC bus	[V]	163	325	163	325	163	325	163	325		
Undervoltage limit	[V]	55	130	55	130	55	130	55	130		
Voltage limit: activation of Quick Stop	[V]	60	140	60	140	60	140	60	140		
Overvoltage limit	[V]	450	450	450	450	450	450	450	450		
Maximum continuous power via DC bus	[kW]	0.2	0.5	0.4	0.9	0.8	1.6	0.8	2.2		
Maximum continuous current via DC bus	[A]	1.5	1.5	3.2	3.2	6.0	6.0	10.0	10.0		

3.3.1.8 DC bus data for three-phase devices

LXM32•... (3 ~)		U60N4		D12N4		D18N4		D30N4		D72N4	
Nominal voltage (3 ~) ¹⁾	[V]	208		208		208		208		208	
Nominal voltage DC bus	[V]	294		294		294		294		294	
Undervoltage limit	[V]	150		150		150		150		150	
Voltage limit: activation of Quick Stop	[V]	160		160		160		160		160	
Overvoltage limit	[V]	820		820		820		820		820	
Maximum continuous power via DC bus	[kW]	0.4		0.8		1.7		2.8		6.5	
Maximum continuous current via DC bus	[A]	1.5		3.2		6.0		10.0		22.0	

1) 208V_{ac} (3*200V_{ac} ... 3*240V_{ac}) DOM >10.05.2010, firmware version >V01.02.00

LXM32•... (3 ~)		U60N4		D12N4		D18N4		D30N4		D72N4	
Nominal voltage (3 ~)	[V]	400	480	400	480	400	480	400	480	400	480
Nominal voltage DC bus	[V]	566	679	566	679	566	679	566	679	566	679
Undervoltage limit	[V]	350	350	350	350	350	350	350	350	350	350
Voltage limit: activation of Quick Stop	[V]	360	360	360	360	360	360	360	360	360	360
Overvoltage limit	[V]	820	820	820	820	820	820	820	820	820	820
Maximum continuous power via DC bus	[kW]	0.8	0.8	1.6	1.6	3.3	3.3	5.6	5.6	13.0	13.0
Maximum continuous current via DC bus	[A]	1.5	1.5	3.2	3.2	6.0	6.0	10.0	10.0	22.0	22.0

3.3.2 Controller supply voltage 24V

24V supply The +24VDC controller supply voltage must meet the requirements of IEC 61131-2 (PELV standard power supply unit):

Input voltage	[V _{dc}]	24 V -15% / +20% ¹⁾
Input current (without load)	[A]	≤1 ²⁾
Residual ripple		<5%
Inrush current		Charging current for capacitor C=1.8 mF

1) For connection of motors without holding brake; see figure below for motors with holding brake.

2) Input current: holding brake not considered.

If a motor with holding brake is connected, the 24 V_{dc} controller supply voltage must be adjusted according to the connected motor and the motor cable length. Refer to the figure below for the voltage that must be available at CN2 for releasing the holding brake. The voltage tolerance is ±5%.

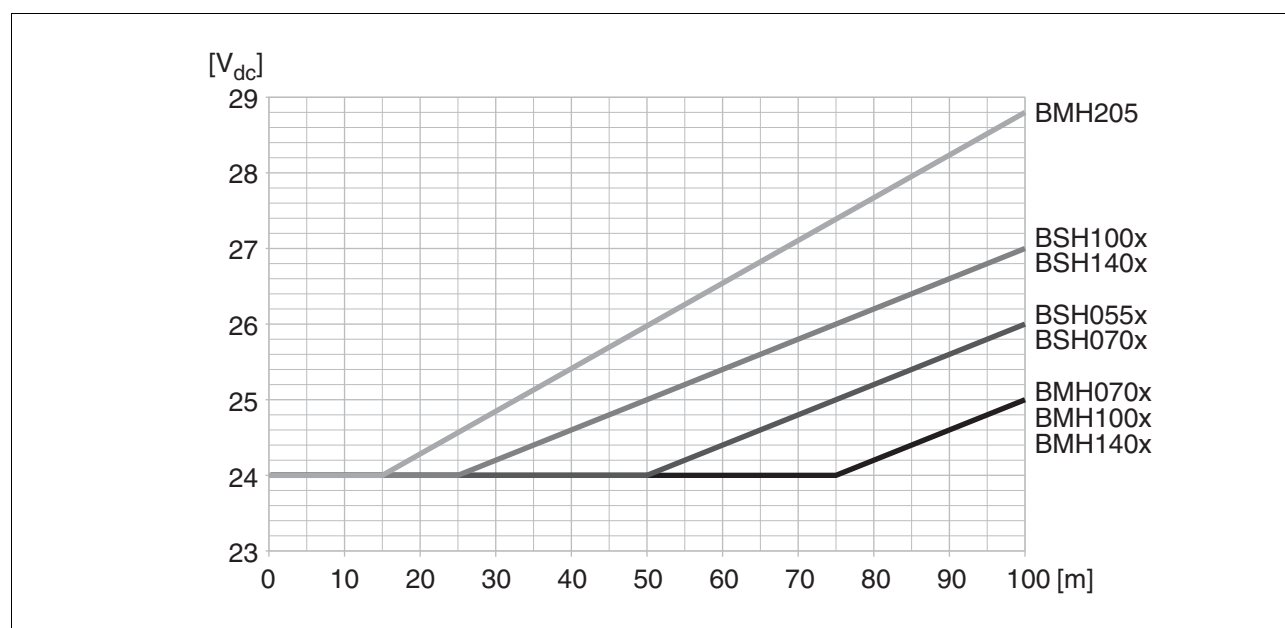


Figure 3.5 The controller supply voltage depends on the motor and the motor cable length.

3.3.3 Signals

The digital inputs and outputs of this product can be wired for logic type 1 or logic type 2.

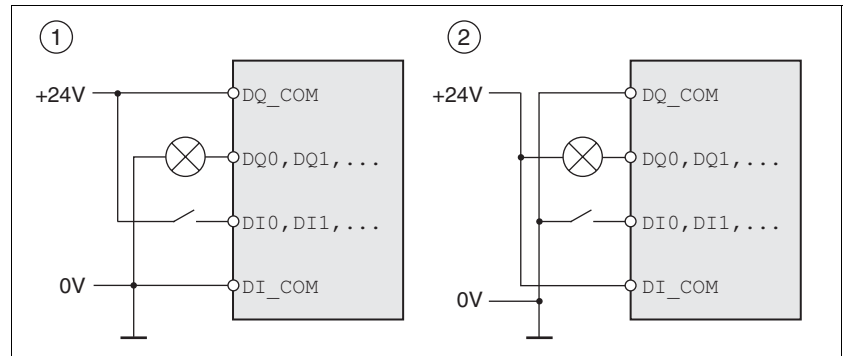


Figure 3.6 Logic type

Logic type	Active state
(1) Logic type 1	Output supplies current (Source) Current flows to the input
(2) Logic type 2	Output draws current (Sink) Current flows from the input

Signal inputs are protected against reverse polarity, outputs are short-circuit protected. The inputs and outputs are galvanically isolated.

Digital input signals 24 V

When wired as logic type 1, the levels of the opto-isolated inputs DI• comply with IEC 61131-2, type 1.

Level 0 with logic type 1 (U_{low})	[V _{dc}]	-3 ... +5
Level 1 with logic type 1 (U_{high})	[V _{dc}]	+15 ... +30
Input current (typical)	[mA]	5
Debounce time ¹⁾	[ms]	1.5

1) Adjustable via parameter (sampling period 250µs)

Capture input signals 24 V

When wired as "logic type 1", the levels of the opto-isolated inputs Cap• comply with IEC 61131-2, type 1.

Level 0 with logic type 1 (U_{low})	[V _{dc}]	-3 ... +5
Level 1 with logic type 1 (U_{high})	[V _{dc}]	+15 ... +30
Input current (typical)	[mA]	5
Debounce time CAP1 and CAP2	[µs]	2
Jitter CAP1 and CAP2	[µs]	<2

Input signals safety function STO

Level 0 with logic type 1 (U_{low})	[V _{dc}]	-3 ... +5
Level 1 with logic type 1 (U_{high})	[V _{dc}]	+15 ... +30
Input current (typical)	[mA]	5
Debounce time $\overline{STO_A}$ and $\overline{STO_B}$	[ms]	>1
Detection of signal differences between $\overline{STO_A}$ and $\overline{STO_B}$	[s]	>1
Response time of safety function STO	[ms]	≤10

24 V output signals

The levels of the digital 24 V output signals DQ• comply with IEC 61131-2.

Output voltage	[V]	≤30
Maximum switching current	[mA]	≤100
Voltage drop at 100 mA load	[V]	≤3

Encoder signals

The encoder signals comply with the Stegmann Hiperface specification.

Output voltage for encoder		+10V / 100mA
SIN/COS input signal voltage range		1V _{pp} with 2.5V offset, 0.5V _{pp} at 100kHz
Input resistance	[Ω]	120

The output voltage is short-circuit protected and overload protected.
The transmission protocol is half duplex as per RS 485.

3.3.3.1 Output PTO (CN4)

5 V signals are available at the PTO (Pulse Train Out, CN4) output. Depending on parameter `PTO_mode`, these signals are ESIM signals (encoder simulation) or directly transmitted PTI input signals (P/D signals, A/B signals, CW/CCW signals). The PTO output signals can be used as PTI input signals for another device. The PTO output signals have 5 V, even if the PTI input signal is a 24 V signal.

The signal level corresponds to RS422. Due to the input current of the optocoupler in the input circuit, a parallel connection of a driver output to several devices is not permitted.

The basic resolution of the encoder simulation at quadruple resolution is 4096 increments per revolution in the case of rotary motors.

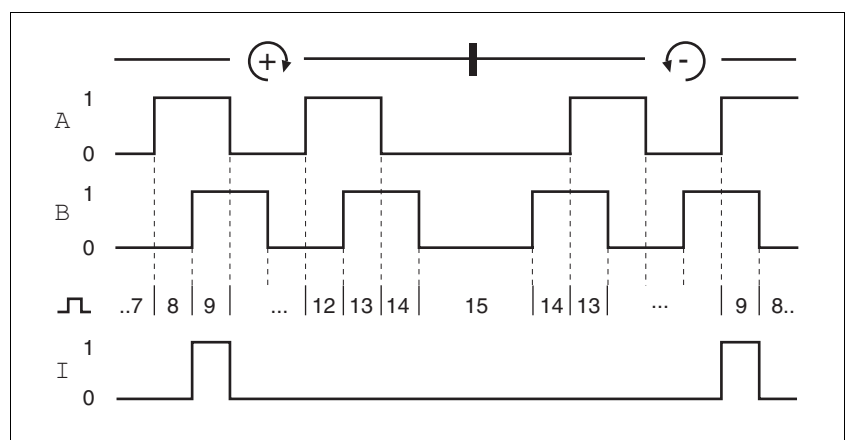


Figure 3.7 Time chart with A, B and index pulse signal, counting forwards and backwards

Output signal PTO

The PTO output signals comply with the RS422 interface specification.

Logic level		As per RS422 ¹⁾
Output frequency per signal	[kHz]	≤500
Motor increments per second	[Inc/s]	≤1.6 * 10 ⁶

1) Due to the input current of the optocoupler in the input circuit, a parallel connection of a driver output to several devices is not permitted.

3.3.3.2 Input PTI (CN5)

⚠ WARNING**UNEXPECTED MOVEMENT**

Incorrect or interfered signals as reference values can cause unexpected movements.

- Use shielded twisted-pair cables.
- If possible, operate the interface with push-pull signals.
- Do not use signals without push-pull in critical applications or in environments subject to interference.
- Do not use signals without push-pull in the case of cable lengths of more than 3 m and limit the frequency to 50 kHz

Failure to follow these instructions can result in death, serious injury or equipment damage.

5 V signals or 24 V signals can be connected to the PTI (Pulse Train In) input.

Signals can be connected:

- A/B signals (ENC_A/ENC_B)
- P/D signals (PULSE/DIR)
- CW/CCW signals (CW/CCW)

See also chapter 6.2.11 "Connection PTI (CN5, Pulse Train In)", page 118.

Signal input circuits PTI

The way the inputs are wired affects the maximum permissible input frequency and the maximum permissible line length:

Input circuit	Maximum input frequency	Maximum line length
RS422, see Figure 3.8 left	1 MHz	100 m
Push pull, see Figure 3.8 center	0.2 MHz	10 m
Open collector, see Figure 3.8 right	0.01 MHz	1 m

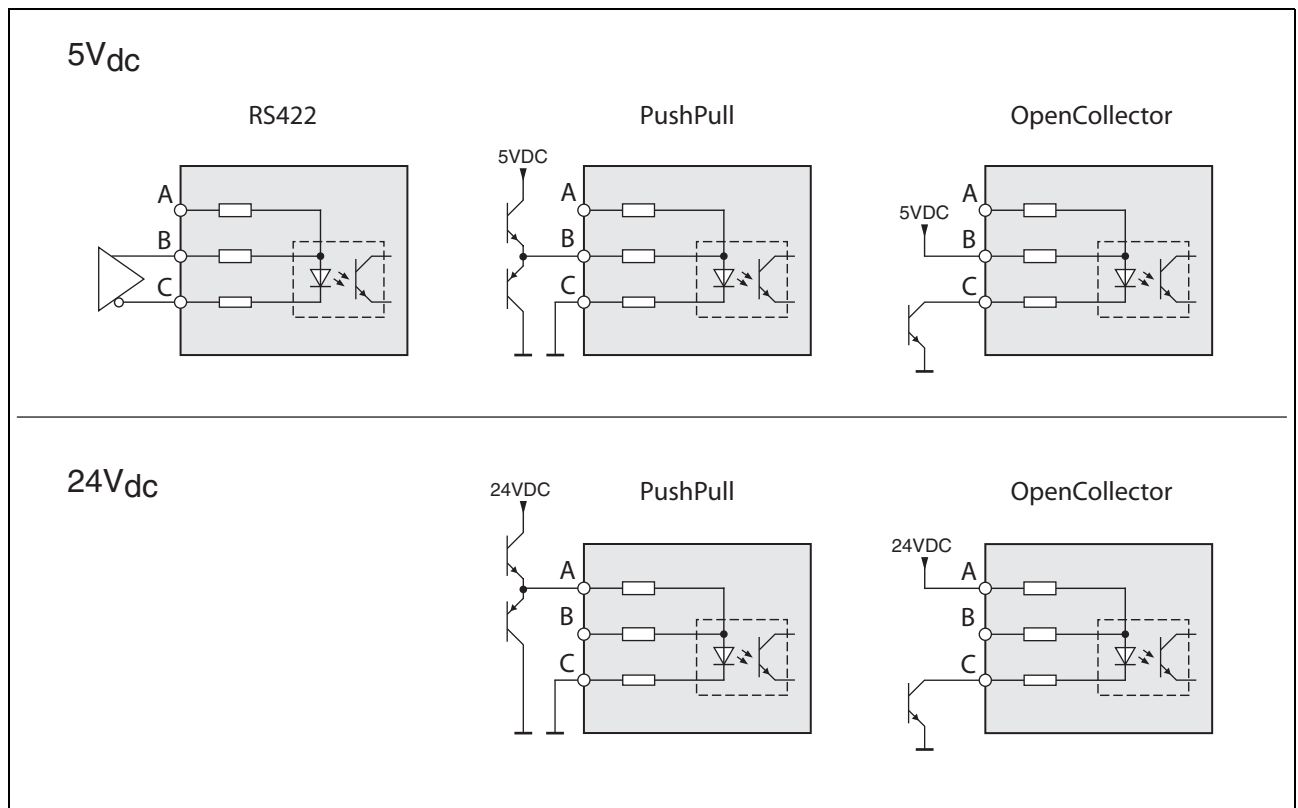


Figure 3.8 Signal input circuits: RS422, Push Pull and Open Collector

Input	Pin ¹⁾	RS422 ²⁾	5V	24V
A	Pin 7	Reserved	Reserved	PULSE (24) ENC_A (24) CW (24)
	Pin 8	Reserved	Reserved	DIR (24) ENC_B (24) CCW (24)
B	Pin 1	PULSE (5) ENC_A (5) CW (5)	PULSE (5) ENC_A (5) CW (5)	Reserved
	Pin 4	DIR (5) ENC_B (5) CCW (5)	DIR (5) ENC_B (5) CCW (5)	Reserved
C	Pin 2	$\overline{\text{PULSE}}$ $\overline{\text{ENC_A}}$ $\overline{\text{CW}}$	$\overline{\text{PULSE}}$ $\overline{\text{ENC_A}}$ $\overline{\text{CW}}$	$\overline{\text{PULSE}}$ $\overline{\text{ENC_A}}$ $\overline{\text{CW}}$
	Pin 5	$\overline{\text{DIR}}$ $\overline{\text{ENC_B}}$ $\overline{\text{CCW}}$	$\overline{\text{DIR}}$ $\overline{\text{ENC_B}}$ $\overline{\text{CCW}}$	$\overline{\text{DIR}}$ $\overline{\text{ENC_B}}$ $\overline{\text{CCW}}$

1) Observe the different pairing in the case of twisted pair:

Pin 1 / pin 2 and pin 4 / pin 5 for RS422 and 5V;
pin 7 / pin 2 and pin 8 / pin 5 for 24V

2) Due to the input current of the optocoupler in the input circuit, a parallel connection of a driver output to several devices is not permitted.

Function A/B signals External A/B signals can be supplied via the PTI input as reference values in operating mode Electronic Gear.

Signal	Value	Function
Signal A before signal B		Movement in positive direction
Signal B before signal A		Movement in negative direction

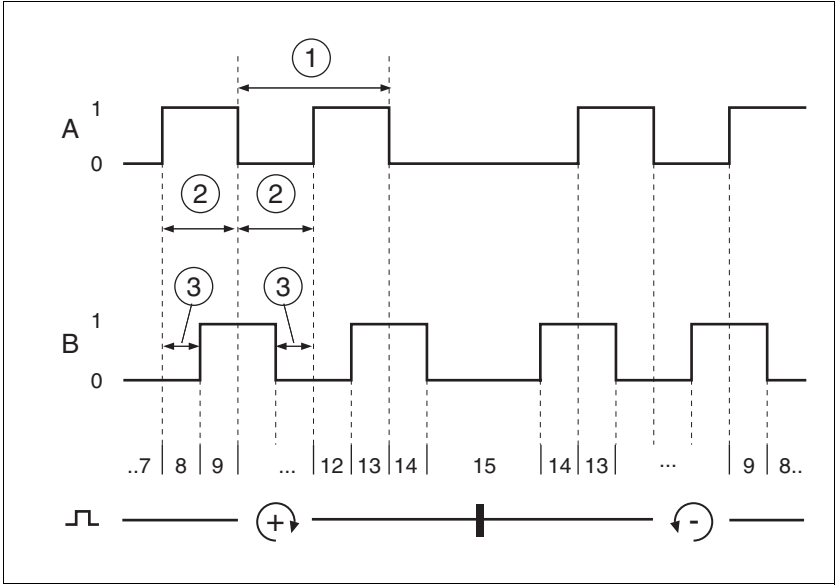


Figure 3.9 Time chart with A/B signal, counting forwards and backwards

Times for pulse/direction	Minimum value	
Cycle duration A, B	1 μs	(1)
Pulse duration	0.4 μs	(2)
Lead time (A, B)	200 ns	(3)

Function P/D External P/D signals can be supplied via the PTI input as reference values in the operating mode Electronic Gear.

The motor performs a movement in the case of a rising edge of the PULSE signal. The direction is controlled with the DIR signal.

Signal	Value	Function
PULSE	0 -> 1	Motor movement
DIR	0 / open	Positive direction

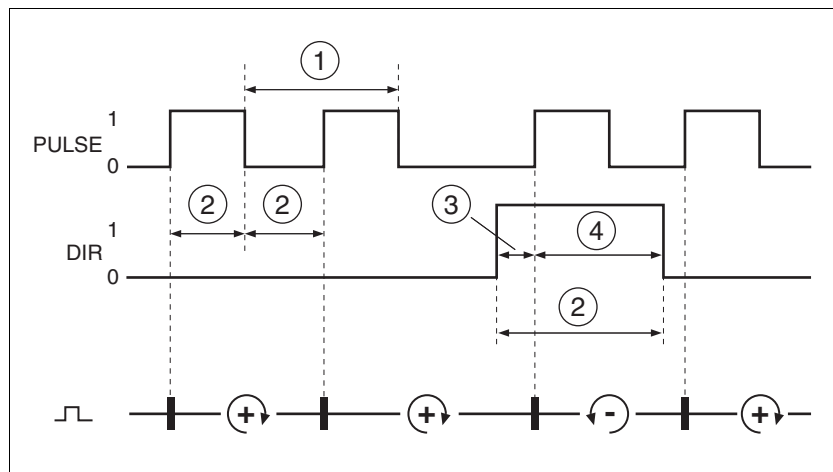


Figure 3.10 Time chart with pulse/direction signal

Times for pulse/direction	Minimum value	
Cycle duration (pulse)	1 μ s	(1)
Pulse duration (pulse)	0.4 μ s	(2)
Lead time (Dir-Pulse)	0 μ s	(3)
Hold time (Pulse-Dir)	0.4 μ s	(4)

Function CW/CCW External CW/CCW signals can be supplied via the PTI input as reference values in operating mode Electronic Gear.

The motor performs a movement in positive direction the case of a rising edge of the CW signal. The motor performs a movement in negative direction the case of a rising edge of the CCW signal.

Signal	Value	Function
CW	0 -> 1	Movement in positive direction
CCW	0 -> 1	Movement in negative direction

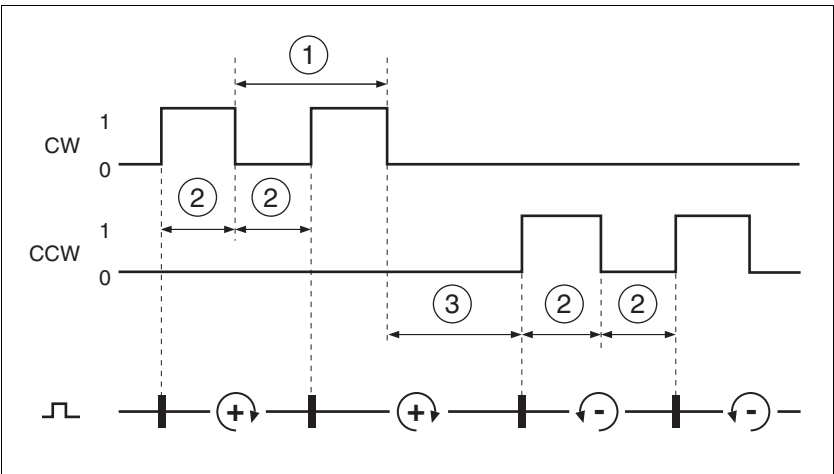


Figure 3.11 Time chart with "CW/CCW"

Times for pulse/direction	Minimum value	
Cycle duration CW, CCW	1 μ s	(1)
Pulse duration	0.4 μ s	(2)
Lead time (CW-CCW, CCW-CW)	0 μ s	(3)

3.3.4 Functional safety

Data for maintenance plan and safety calculations

Use the following data of the STO safety function for your maintenance plan and the safety calculations:

Lifetime (IEC 61508)	Years	20
SFF (IEC 61508) Safe Failure Fraction	[%]	80
HFT (IEC 61508) Hardware Fault Tolerance Type A subsystem		1
Safety integrity level IEC 61508 IEC 62061		SIL3 SILCL3
PFH (IEC 61508) Probability of Dangerous Hardware Failure per Hour	[1/h] (FIT)	$1 \cdot 10^{-9}$ (1)
PL (ISO 13849-1) Performance Level		e (category 3)
MTTF _d (ISO 13849-1) Mean Time to Dangerous Failure	Years	1400
DC (ISO 13849-1) Diagnostic Coverage	[%]	90

The data for the safety module eSM can be found in the product manual for the safety module.

3.3.5 Braking resistor

The device has an internal braking resistor. If the internal braking resistor is insufficient for the dynamics of the application, one or more external braking resistors must be used.

The resistance values for external braking resistors must not be below the specified minimum resistance. If an external braking resistor is activated by means of the appropriate parameter, the internal braking resistor is deactivated.

Further information on the subject	Page
Rating the external braking resistor	106
Mounting the external braking resistor (accessory)	92
Electrical installation of the braking resistor (accessory)	106
Setting the braking resistor parameters	170
Order data for external braking resistors (accessory)	569

LXM32•...		U45M2	U90M2	D18M2	D30M2	
Resistance value of internal braking resistor	[Ω]	94	47	20	10	
Continuous power internal braking resistor P_{PR}	[W]	10	20	40	60	
Peak energy E_{CR}	[Ws]	82	166	330	550	
External braking resistor minimum	[Ω]	68	36	20	12	
External braking resistor maximum ¹⁾	[Ω]	110	55	27	16	
Maximum continuous power external braking resistor	[W]	200	400	600	800	
Parameter DCbus_compat = 0 (default value)						
Switch-on voltage braking resistor	[V]	430	430	430	430	
Capacitance	[μF]	390	780	1170	1560	
Energy absorption of internal capacitors E_{var} at nominal voltage 115 V +10%	[Ws]	30	60	89	119	
Energy absorption of internal capacitors E_{var} at nominal voltage 200 V +10%	[Ws]	17	34	52	69	
Energy absorption of internal capacitors E_{var} at nominal voltage 230 V +10%	[Ws]	11	22	33	44	
Parameter DCbus_compat = 1 (reduced switch-on voltage)						
Switch-on voltage braking resistor	[V]	395	395	395	395	
Capacitance	[μF]	390	780	1170	1560	
Energy absorption of internal capacitors E_{var} at nominal voltage 115 V +10%	[Ws]	24	48	73	97	
Energy absorption of internal capacitors E_{var} at nominal voltage 200 V +10%	[Ws]	12	23	35	46	
Energy absorption of internal capacitors E_{var} at nominal voltage 230 V +10%	[Ws]	5	11	16	22	

1) The maximum specified braking resistor can derate the peak power of the device. Depending on the application, it is possible to use a higher ohm resistor.

Table 3.1 Data braking resistor for single-phase devices

See chapter 3.3.1.7 "DC bus data for single-phase devices", page 33 for the DC bus data.

LXM32•...		U60N4	D12N4	D18N4	D30N4	D72N4
Resistance value of internal braking resistor	[Ω]	132	60	30	30	10
Continuous power internal braking resistor P_{PR}	[W]	20	40	60	100	150
Peak energy E_{CR}	[Ws]	200	400	600	1000	2400
External braking resistor minimum	[Ω]	100	47	33	15	8
External braking resistor maximum ¹⁾	[Ω]	145	73	50	30	12
Maximum continuous power external braking resistor	[W]	200	500	800	1500	3000
Parameter DCbus_compat ²⁾						
Switch-on voltage	[V]	780	780	780	780	780
Capacitance	[μF]	110	195	390	560	1120
Energy absorption of internal capacitors E_{var} at nominal voltage 208 V +10% ³⁾	[Ws]	28	49	98	141	282
Energy absorption of internal capacitors E_{var} at nominal voltage 380 V +10%	[Ws]	14	25	50	73	145
Energy absorption of internal capacitors E_{var} at nominal voltage 400 V +10%	[Ws]	12	22	43	62	124
Energy absorption of internal capacitors E_{var} at nominal voltage 480 V +10%	[Ws]	3	5	10	14	28

1) The maximum specified braking resistor can derate the peak power of the device. Depending on the application, it is possible to use a higher ohm resistor.

2) Parameter DCbus_compat has no effect in the case of three-phase devices.

3) 208V_{ac} (3*200V_{ac} ... 3*240V_{ac}) DOM >10.05.2010, software version >V01.02.00

Table 3.2 Data braking resistor for three-phase devices

See chapter 3.3.1.8 "DC bus data for three-phase devices", page 33 for the DC bus data.

3.3.5.1 External braking resistors (accessories)

VW3A760...		1Rxx ¹⁾	2Rxx	3Rxx	4Rxx ¹⁾	5Rxx	6Rxx	7Rxx ¹⁾
Resistance	[Ω]	10	27	27	27	72	72	72
Continuous power	[W]	400	100	200	400	100	200	400
Maximum time in braking at 115 V / 230 V	[s]	0.72	0.552	1.08	2.64	1.44	3.72	9.6
Peak power at 115 V / 230 V	[kW]	18.5	6.8	6.8	6.8	2.6	2.6	2.6
Maximum peak energy at 115 V / 230 V	[Ws]	13300	3800	7400	18100	3700	9600	24700
Maximum time in braking at 400 V	[s]	0.12	0.084	0.216	0.504	0.3	0.78	1.92
Peak power at 400V	[kW]	60.8	22.5	22.5	22.5	8.5	8.5	8.5
Maximum peak energy at 400 V	[Ws]	7300	1900	4900	11400	2500	6600	16200
Degree of protection		IP65	IP65	IP65	IP65	IP65	IP65	IP65
UL approval (file no.)			E233422	E233422		E233422	E233422	

1) Resistors with a continuous power of 400 W are NOT UL/CSA-approved.

VW3A77...		04	05					
Resistance	[Ω]	15	10					
Continuous power	[W]	2500	2500					
Maximum time in braking at 115 V / 230 V	[s]	3.5	1.98					
Peak power at 115 V / 230 V	[kW]	18.5	12.3					
Maximum peak energy at 115 V / 230 V	[Ws]	43100	36500					
Maximum time in braking at 400 V	[s]	0.65	0.37					
Peak power at 400V	[kW]	60.8	40.6					
Maximum peak energy at 400 V	[Ws]	26500	22500					
Degree of protection		IP20	IP20					
UL approval (file no.)		E221095	E221095					

3.3.6 Internal mains filter

Further information on the subject	Page
Engineering information external mains filters (accessory)	68
Mounting the external mains filter (accessory)	92
Electrical installation of external mains filters (accessory)	109
Order data external mains filters (accessory)	578

Limit values This product meets the EMC requirements according to the standard IEC 61800-3 if the measures described in this manual are implemented during installation.

If the selected composition is not designed for category C1, note the following:

⚠ WARNING
HIGH-FREQUENCY INTERFERENCE In a residential environment this product may cause high-frequency interference that require interference suppression. Failure to follow these instructions can result in death or serious injury.

Emission The following limit values for interference are complied with if the installation is EMC-compliant and if the cables offered as accessories are used.

LXM32•	Conducted interference	Radiated emission
•••M2 up to a motor cable length of 10 m	Category C2	Category C3
•••M2 motor cable length of 10 m to 20 m	Category C3	Category C3
•••M2 motor cable length of more than 20 m	Not permitted	Not permitted
•••N4 up to a motor cable length of 20 m	Category C3	Category C3
•••N4 motor cable length of more than 20 m	Not permitted	Not permitted

External mains filters must be used if longer motor cables are used. See page 49 for the technical data of the external mains filters available as accessories.

3.3.7 External mains filters (accessories)

If external mains filters are used, the system integrator and/or machine owner/operator is responsible for complying with the EMC directives.

Further information on the subject	Page
Engineering information external mains filters (accessory)	68
Mounting the external mains filter (accessory)	92
Electrical installation of external mains filters (accessory)	109
Order data external mains filters (accessory)	578

Emission The specified limit values are complied with if the external mains filters available as accessories are used.

The following limit values for interference are complied with if the installation is EMC-compliant and if the cables offered as accessories are used.

LXM32•	Conducted interference	Radiated emission
•••M2 up to a motor cable length of 20 m	Category C1	Category C3
•••M2 motor cable length of 20 m to 50 m	Category C2	Category C3
•••M2 motor cable length of 50 m to 100 m	Category C3	Category C3
•••M2 motor cable length of more than 100 m	Not permitted	Not permitted
•••N4 up to a motor cable length of 20 m	Category C1	Category C3
•••N4 motor cable length of 20 m to 50 m	Category C2	Category C3
•••N4 motor cable length of 50 m to 100 m	Category C3	Category C3
•••N4 motor cable length of more than 100 m	Not permitted	Not permitted

Common external mains filter Several device can be connected to a common external mains filter. Pre-requisites:

- Single-phase devices may only be connected to single-phase mains filters; three-phase devices may only be connected to three-phase devices.
- The total input current of the connected devices must be smaller than or equal to the permissible nominal current of the mains filter.

Assignment of external mains filters
to device type

Device type 1 ~	Order number mains filter
LXM32•U45M2 (230 V, 1.5 A, 1 ~)	VW3A4420 (9 A, 1 ~)
LXM32•U90M2 (230 V, 3 A, 1 ~)	VW3A4420 (9 A, 1 ~)
LXM32•D18M2 (230 V, 6 A, 1 ~)	VW3A4421 (16 A, 1 ~)
LXM32•D30M2 (230 V, 10 A, 1 ~)	VW3A4421 (16 A, 1 ~)

Device type 3 ~	Order number mains filter
LXM32•U60N4 (480 V, 1.5 A, 3 ~)	VW3A4422 (15 A, 3 ~)
LXM32•D12N4 (480 V, 3 A, 3 ~)	VW3A4422 (15 A, 3 ~)
LXM32•D18N4 (480 V, 6 A, 3 ~)	VW3A4422 (15 A, 3 ~)
LXM32•D30N4 (480 V, 10 A, 3 ~)	VW3A4422 (15 A, 3 ~)
LXM32•D72N4 (480 V, 24 A, 3 ~)	VW3A4423 (25 A, 3 ~)

3.3.8 Mains reactor (accessory)

Mains reactor Mains reactors must be connected upstream if the supply mains does not meet the requirements in terms of mains impedance. High current harmonics result in considerable load on the DC bus capacitors. Mains reactors reduce harmonics in the mains supply. The load on the DC bus capacitors has a decisive impact on the service life of the devices.

A higher continuous power of the device is an additional benefit of using an upstream mains reactor.

Further information on the subject	Page
Engineering information mains reactor (accessory)	67
Mounting the mains reactor (accessory)	92
Electrical installation of the mains reactor (accessory)	109
Order data mains reactor (accessory)	578

3.4 Conditions for UL 508C and CSA

If the product is used to comply with UL 508C or CSA, the following conditions must also be met:

Ambient temperature during operation

Surrounding air temperature	[°C]	0 ... +50
-----------------------------	------	-----------

Fuses Use class J fuses as per UL 248-4.

Maximum fuse rating of fuse to be connected upstream for LXM32...M2	[A]	25
Maximum fuse rating of fuse to be connected upstream for LXM32...N4	[A]	30

Wiring Use at least 60/75 °C copper conductors.

400/480 V three-phase devices 400/480 V three-phase devices may only be operated via 480Y/277Vac mains.

Overvoltage category In the case of single-phase devices, a Schneider Electric surge protective device TVS230XR40 and in the case of three-phase devices, a Schneider Electric surge protective device TVS4XW100C or a UL-listed surge protective device with the following designation must be available in all phases of the mains connection of the drive in the final installation:

UL Category Code VZCA

Type 1 or 2

Operating Voltage 240V for 1-phase systems and 480Y/277V for 3-phase systems

Voltage Protection Rating (VPR) max. 4000V

Nominal Discharge Current Rating (In) min. 3kA



3.5 Certifications

Product certifications:

Certified by	Assigned number
TÜV Nord	SAS-192/2008TB-1
UL	E153659
CSA	2320425

3.6 Declaration of conformity

The following declaration of conformity is applicable if the product is used under the specified conditions and with the cables listed in the Accessories chapter.

 SCHNEIDER ELECTRIC MOTION DEUTSCHLAND GmbH Breslauer Str. 7 D-77933 Lahr	
<u>EC DECLARATION OF CONFORMITY</u> <u>YEAR 2010</u>	
<input checked="" type="checkbox"/> according to EC Directive on Machinery 2006/42/EC <input checked="" type="checkbox"/> according to EC Directive EMC 2004/108/EC <input checked="" type="checkbox"/> according to EC Directive Low Voltage 2006/95/EC	
We hereby declare that the products listed below meet the requirements of the EC Directives indicated with respect to design, construction and version distributed by us. This declaration becomes invalid in the case of any modification to the products not authorized by us.	
Designation:	AC Servo drive including modules
Type:	LXM32Axxxxx, LXM32Cxxxxx, LXM32Mxxxxx, VW3A3607, VW3A3608, VW3A3616, VW3A3618, VW3M3301, VW3M3401, VW3M3402, VW3M3403, VW3M3501
Applied harmonized standards, especially:	EN ISO 13849-1:2008, Performance Level "e" EN 61508:2001, SIL 3 EN 61800-5-1:2007 EN 61800-3:2004, second environment
Applied national standards and technical specifications, especially:	UL 508C CSA C22.2 No. 14-10 Product documentation
<div style="text-align: center;"> Schneider Electric Motion Deutschland GmbH Postfach 11 80 • D-77901 Lahr Breslauer Str. 7 • D-77933 Lahr </div>	
Company stamp:	
Date/Signature:	23 September 2010 
Name/Department:	Wolfgang Brandstätter/Development

3.7 TÜV certificate for functional safety



4 Basics

4

4.1 Functional safety

Automation and safety engineering are two areas that were completely separated in the past but recently have become more and more integrated. Engineering and installation of complex automation solutions are greatly simplified by integrated safety functions.

Usually, the safety engineering requirements depend on the application. The level of the requirements results from the risk and the hazard potential arising from the specific application.

Integrated safety function "Safe Torque Off" STO

The integrated safety function STO (IEC 61800-5-2) allows for a category 0 stop as per IEC 60204-1 without external power contactors. It is not necessary to interrupt the supply voltage for a category 0 stop. This reduces the system costs and the response times.

IEC 61508 standard

The standard IEC 61508 "Functional safety of electrical/electronic/programmable electronic safety-related systems" covers the safety-related function. Instead of a single component, an entire function chain (for example, from a sensor through the logical processing units to the actuator) is considered as a unit. This function chain must meet the requirements of the specific safety integrity level as a whole. Systems and components that can be used in various applications for safety tasks with comparable risk levels can be developed on this basis.

SIL, Safety Integrity Level

The standard IEC 61508 defines 4 safety integrity levels (SIL) for safety functions. SIL1 is the lowest level and SIL4 is the highest level. A hazard and risk analysis serves as a basis for determining the required safety integrity level. This is used to decide whether the relevant function chain is to be considered as a safety function and which hazard potential it must cover.

PFH, Probability of a dangerous hardware failure per hour

To maintain the safety function, the IEC 61508 standard requires various levels of measures for avoiding and controlling faults, depending on the required SIL. All components of a safety function must be subjected to a probability assessment to evaluate the effectiveness of the measures implemented for controlling faults. This assessment determines the PFH (probability of a dangerous failure per hour) for a safety system. This is the probability per hour that a safety system fails in a hazardous manner and the safety function cannot be correctly executed. Depending on the SIL, the PFH must not exceed certain values for the entire safety system. The individual PFH values of a function chain are added. The result must not exceed the maximum value specified in the standard.

SIL	PFH at high demand or continuous demand
4	$\geq 10^{-9} \dots < 10^{-8}$
3	$\geq 10^{-8} \dots < 10^{-7}$
2	$\geq 10^{-7} \dots < 10^{-6}$
1	$\geq 10^{-6} \dots < 10^{-5}$

HFT and SFF Depending on the SIL for the safety system, the IEC 61508 standard requires a specific hardware fault tolerance HFT in connection with a specific proportion of safe failures SFF (safe failure fraction). The hardware fault tolerance is the ability of a system to execute the required safety function in spite of the presence of one or more hardware faults. The SFF of a system is defined as the ratio of the rate of safe failures to the total failure rate of the system. According to IEC 61508, the maximum achievable SIL of a system is partly determined by the hardware fault tolerance HFT and the safe failure fraction SFF of the system.

IEC 61508 distinguishes two types of subsystems (type A subsystem, type B subsystem). These types are specified on the basis of criteria which the standard defines for the safety-relevant components.

SFF	HFT type A subsystem				HFT type B subsystem			
	0	1	2		0	1	2	
< 60%	SIL1	SIL2	SIL3		---	SIL1	SIL2	
60% ... <90%	SIL2	SIL3	SIL4		SIL1	SIL2	SIL3	
90% ... < 99%	SIL3	SIL4	SIL4		SIL2	SIL3	SIL4	
≥99%	SIL3	SIL4	SIL4		SIL3	SIL4	SIL4	

Fault avoidance measures Systematic errors in the specifications, in the hardware and the software, usage faults and maintenance faults of the safety system must be avoided to the maximum degree possible. To meet these requirements, IEC 61508 specifies a number of measures for fault avoidance that must be implemented depending on the required SIL. These measures for fault avoidance must cover the entire life cycle of the safety system, i.e. from design to decommissioning of the system.

5 Engineering

5

This chapter contains information on the application of the product that is vital in the design phase.

Subject	Page
5.1 "Electromagnetic compatibility, EMC"	58
5.2 "Cables"	62
5.3 "Residual current device"	65
5.4 "Operation in an IT mains"	65
5.5 "Parallel connection DC bus"	66
5.6 "Mains reactor"	67
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5.10 "Logic type"	82
5.11 "Monitoring functions"	83
5.12 "Configurable inputs and outputs"	83

5.1 Electromagnetic compatibility, EMC

⚠ WARNING

SIGNAL AND DEVICE INTERFERENCE

Signal interference can cause unexpected responses of device.

- Install the wiring in accordance with the EMC requirements.
- Verify compliance with the EMC requirements.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Limit values

This product meets the EMC requirements according to the standard IEC 61800-3 if the measures described in this manual are implemented during installation.

If the selected composition is not designed for category C1, note the following:

⚠ WARNING

HIGH-FREQUENCY INTERFERENCE

In a residential environment this product may cause high-frequency interference that require interference suppression.

Failure to follow these instructions can result in death or serious injury.

An EMC-compliant design is required to meet the specified limit values. Note the following requirements:

Control cabinet design

EMC measures	Objective
Use galvanised or chrome-plated mounting plates, make large contact surface connections for metal parts, remove paint from contact surfaces	Good conductivity due to two-dimensional contacts
Ground the control cabinet, door and mounting plate with ground straps or ground wires with a cross section greater than 10 mm ² (AWG 6).	Reduces emissions.
Fit switching devices such as contactors, relays or solenoid valves with interference suppression units or arc suppressors (for example, diodes, varistors, RC circuits).	Reduces mutual interference
Install power and control components separately.	Reduces mutual interference

Shielded cables

EMC measures	Objective
Connect large surface areas of cable shields, use cable clamps and ground straps.	Reduces emissions.
Use cable clamps to connect a large surface area of the shields of all shielded cables to the mounting plate at the control cabinet entry.	Reduces emissions.
Ground shields of digital signal wires at both ends by connecting them to a large surface or via conductive connector housings.	Reduces interference affecting the signal wires, reduces emissions
Ground the shields of analog signal wires directly at the device (signal input); insulate the shield at the other cable end or ground it via a capacitor (for example, 10 nF).	Reduces ground loops due to low-frequency interference.
Use only shielded motor cables with copper braid and a coverage of at least 85%, ground a large surface area of the shield at both ends.	Diverts interference currents in a controlled way, reduces emissions.

Cable installation

EMC measures	Objective
Do not route fieldbus cables and signal wires in a single cable duct together with lines with DC and AC voltages of more than 60 V. (Fieldbus cables, signal lines and analog lines may be in the same cable duct) Recommendation: Use separate cable ducts at least 20 cm apart.	Reduces mutual interference
Keep cables as short as possible. Do not install unnecessary cable loops, use short cables from the central grounding point in the control cabinet to the external ground connection.	Reduces capacitive and inductive interference.
Use equipotential bonding conductors in systems with - wide-area installations - different voltage supplies - networking across several buildings	Reduces current in the cable shield, reduces emissions.
Use equipotential bonding conductors with fine wires	Diverts high-frequency interference currents.
If motor and machine are not conductively connected, for example by an insulated flange or a connection without surface contact, you must ground the motor with a ground wire > 10 mm ² (AWG 6) or a ground strap.	Reduces emissions, increases immunity.
Use twisted pair for 24 V _{dc} signals.	Reduces interference affecting the signal cables, reduces emissions.

Power supply

EMC measures	Objective
Operate product on mains with grounded neutral point.	Enables effectiveness of mains filter.
Surge arrester if there is a risk of overvoltage.	Reduces the risk of damage caused by overvoltage.

Motor and encoder cables

Motor and encoder cables are especially critical in terms of EMC. Use only pre-assembled cables (see chapter 12 "Accessories and spare parts") or cables that comply with the specifications (see chapter 5.2 "Cables", page 62) and implement the EMC measures described below.

EMC measures	Objective
Do not install switching elements in motor cables or encoder cables.	Reduces interference.
Route the motor cable at a distance of at least 20 cm from the signal cable or use shielding plates between the motor cable and signal cable.	Reduces mutual interference
For long lines, use equipotential bonding conductors.	Reduces current in the cable shield.
Route the motor cable and encoder cable without cutting them. ¹⁾	Reduces emission.

1) If a cable has to be cut for the installation, it has to be connected with shield connections and a metal housing at the point of the cut.

Additional measures for EMC improvement

An EMC-compliant design is required to meet the specified limit values. Depending on the application, better results can be achieved with the following measures:

EMC measures	Objective
Upstream mains reactors	Reduces mains harmonics, prolongs product service life.
Upstream external mains filters	Improves the EMC limit values.
Particularly EMC-compliant design, e.g. in an enclosed control cabinet with 15 dB shielding attenuation of radiated interference	Improves the EMC limit values.

5.2 Cables

Suitability of the cables Cables must not be twisted, stretched, crushed or bent. Use only cables that comply with the cable specification. Consider the following in determining suitability of the cables:

- Suitable for drag chain applications
- Temperature range
- Chemical resistance
- Outdoor installation
- Underground installation

Shield connections In terms of shield connection, there are the following possibilities:

- Motor cable: The motor cable shield is fastened in the shield clamp at the bottom of the device.
- Other cables: The shields are connected to the shield connection at the bottom of the device.
- Alternative: Shield connection via shield clamp and rail, for example.

Equipotential bonding conductors Potential differences can result in excessive currents on the cable shields. Use equipotential bonding conductors to reduce currents on the cable shields.

The equipotential bonding conductor must be rated for the maximum current flowing. Practical experience has shown that the following conductor cross sections can be used:

- 16 mm² (AWG 4) for equipotential bonding conductors up to a length of 200 m
- 20 mm² (AWG 4) for equipotential bonding conductors with a length of more than 200 m

Cable guides The device features cable guides at the top and at the bottom. The cable guides do not provide strain relief. The cable guide at the bottom of the device can be used as a shield connection.

NOTE: The upper cable guide is not a shield connection.

5.2.1 Overview of the required cables

The properties of the required cables are listed in the table below. Use pre-assembled cables to reduce the risk of wiring errors. Pre-assembled cables can be found in chapter 12 "Accessories and spare parts", page 569. If the product is used to comply with the requirements as per UL 508C, the conditions specified in chapter 3.4 "Conditions for UL 508C and CSA", page 51, must be met.

	Max. length [m]	Min. cross section [mm ²] (AWG)	Shielded, both ends grounded	Twisted pair	PELV
Controller supply voltage	–	0.75 (AWG 18)			Required
STO safety function ¹⁾	–	0.75 (AWG 18)	¹⁾		Required
Power stage supply voltage	–	– ²⁾			
Motor phases	– ³⁾	– ⁴⁾	Required		
External braking resistor	3	As power stage supply voltage	Required		
Motor encoder	100	6*0.14 mm ² and 2*0.34 mm ² (6*AWG 24 and 2*AWG 20)	Required	Required	Required
A/B signals	100	0.25 (AWG 22)	Required	Required	Required
PULSE / DIR signals	100	0.14 (AWG 24)	Required	Required	Required
CW/CCW signals	100	0.14 (AWG 24)	Required	Required	Required
ESIM	100	0.14 (AWG 24)	Required	Required	Required
Digital inputs / outputs	30	0.14 (AWG 24)			Required
PC, commissioning interface	20	0.14 (AWG 24)	Required	Required	Required

1) Note the installation requirements (protected cable installation), see page 78.

2) See 6.2.8 "Connection of power stage supply voltage (CN1)"

3) Length depends on the required limit values for conducted interference.

4) See 6.2.4 "Connecting the motor phases (CN 10, motor)"

Table 5.1 Cable specifications

Motor cable and encoder cable

Motor cables		Style 20234
Motor cable outside diameter	mm	VW3M5•01: 12 ± 0.2 VW3M5•02: 14 ± 0.3 VW3M5•03: 16.3 ± 0.3
Permissible voltage motor cable	V _{ac}	600 (UL and CSA)
Encoder cables		Style 20233
Encoder cable outside diameter	mm	VW3M8••2: 6.8 ± 0.2
Temperature range	°C	-40 ... +90 (fixed) -20 ... +80 (moving)
Permissible bending radius		4 x diameter (fixed) 7.5 x diameter (moving)
Cable diameter	mm	VW3M5•01R•••: 12 ± 0.2 VW3M5•02R•••: 14 ± 0.3 VW3M5•03R•••: 16.3 ± 0.3
Cable jacket		Oil-resistant PUR
Shield		Shield braiding
Shield braiding coverage	%	≥85

Table 5.2 Data of the motor cable and encoder cable available as accessories

The motor cables and encoder cables are suitable for drag chain applications; they are available in various lengths. See page 569 for the versions available as accessories.

5.3 Residual current device

⚠ WARNING

THIS PRODUCT MAY CAUSE DIRECT CURRENT IN THE PROTECTIVE GROUND CONDUCTOR

If a residual current device (RCD) is used, conditions must be observed.

Failure to follow these instructions can result in death or serious injury.

Conditions for use of residual current device

Where the installation regulations require upstream protection against direct or indirect contact by means of a residual current device (RCD) or a residual current monitor (RCM), a residual current device of "type A" can be used for a single-phase drive with connection between N and L. In other cases, a "type B" RCD must be used.

Note the following:

- Filtering of high-frequency currents.
- Delayed triggering to avoid triggering as a result of capacitance which may be present when the unit is switched on. 30 mA residual current devices rarely have a delay. Use a residual current device which is not sensitive to unintentional triggering (for example, residual current devices with increased immunity).

Use residual current devices that meet the following conditions:

- For single-phase devices, type A: Residual current devices of series s.i (super-immunized, Schneider Electric).
- For three-phase devices, type B: sensitive to all current types with approval for frequency inverters.

When using residual current devices, consider the leakage currents of connected consumers.

5.4 Operation in an IT mains

The device is intended for operation in a TT/TN mains. The device is not suitable for operation in an IT mains.

A transformer grounded at the output turns a TT/TN mains into an IT mains. The device may be connected to this mains.

See chapter 3.3.1 "Power stage", page 25 for the approved mains types.

5.5 Parallel connection DC bus

⚠ WARNING

DESTRUCTION OF SYSTEM COMPONENTS AND LOSS OF CONTROL

Incorrect use of a parallel connection of the DC bus may destroy the drive systems immediately or after a delay.

- Note the requirements concerning the use of a parallel DC bus connection.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Function principle

If several devices use the DC bus jointly, this results in energy savings. If one device decelerates, a different device can use the generated braking energy via the DC bus. This energy does not have to be taken from the mains supply and there is no need to waste it by transforming it into heat in the braking resistor.

Several devices can share a common braking resistor. This can reduce the power of the braking resistor and improve the deceleration performance without a braking resistor.

Requirements for use

The requirements and limit values for parallel connection of multiple LXM32 via the DC bus can be found on the Internet in the form of Application Note MNA01M001.

5.6 Mains reactor

Mains reactor A mains reactor must be used under the following conditions:

- Operation via supply mains with low impedance (short-circuit current of supply mains greater than specified in chapter 3 "Technical Data", page 25).
- If the nominal power of the drive is insufficient without mains reactor.
- In the case of high demands concerning the service life of the drive (for example, 24 h continuous operation).
- In the case of operation with supply mains with reactive current compensation systems.
- For improvement of the power factor at the mains input and for reduction of mains harmonics.

A mains reactor can be used for several devices. Use a mains reactor with a properly rated current.

Low-impedance supply mains cause high current harmonics at the mains input. High current harmonics result in considerable load on the DC bus capacitors. The load on the DC bus capacitors has a decisive impact on the service life of the devices.

Further information on the subject	Page
Technical data mains reactor (accessory)	50
Mounting the mains reactor (accessory)	92
Electrical installation of the mains reactor (accessory)	109
Order data mains reactor (accessory)	578

5.7 Mains filter

Limit values This product meets the EMC requirements according to the standard IEC 61800-3 if the measures described in this manual are implemented during installation.

If the selected composition is not designed for category C1, note the following:

⚠ WARNING
HIGH-FREQUENCY INTERFERENCE In a residential environment this product may cause high-frequency interference that require interference suppression. Failure to follow these instructions can result in death or serious injury.

See chapter Technical Data, page 48, for the category the device complies with.

Better values can be achieved depending on the device and the application and as well as the design, for example, in the case of installation in an enclosed control cabinet with at least 15db shielding attenuation.

The drives have an integrated mains filter.

An additional external mains filter is required in the case of long motor cables. When using external mains filters, verify compliance with all applicable EMC directives.

If the external mains filters offered in chapter 12.17 "External mains filters" are used, the limit values specified in chapter 3.3.7 "External mains filters (accessories)", page 49, are met.

Further information on the subject	Page
Technical data external mains filters (accessory)	49
Mounting the external mains filter (accessory)	92
Electrical installation of external mains filters (accessory)	109
Order data external mains filters (accessory)	578

5.7.1 Deactivating the Y capacitors

The ground connections of the internal Y capacitors can be disconnected (deactivation). Usually, it is not required to deactivate the ground connection of the Y capacitors.

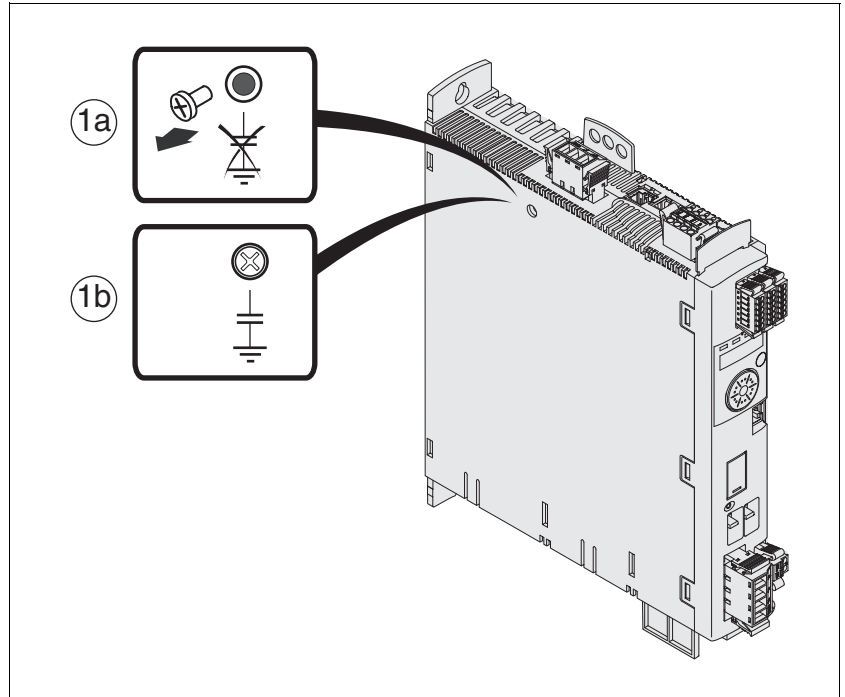


Figure 5.2 Screw for deactivating/activating the internal Y capacitors

To deactivate the Y capacitors, remove the screw, see Figure 5.2. Keep this screw so you can re-activate the Y capacitors, if required.

NOTE: The EMC limit values specified no longer apply if the Y capacitors are deactivated.

5.8 Rating the braking resistor

DANGER

FIRE HAZARD CAUSED BY EXTERNAL DRIVING FORCES ACTING ON MOTOR

If external driving forces acting on the motor cause excessively high currents to be regenerated and supplied back to the drive, this may cause overheating and fire of the drive.

- Verify that no energy is supplied to the driving motor after an error of error classes 3 or 4.

Failure to follow these instructions will result in death or serious injury.

WARNING

MOTOR WITHOUT BRAKING EFFECT

An insufficient braking resistor causes overvoltage on the DC bus and switches off the power stage. The motor is no longer actively decelerated.

- Verify that the braking resistor has a sufficient rating.
- Check the parameter settings for the braking resistor.
- Check the I^2t value under the most critical condition by performing a test run. The device switches off at an I^2t value of 100%.
- When performing the calculation and the test run, take into account the fact that the DC bus capacitors can absorb less braking energy at higher mains voltages.

Failure to follow these instructions can result in death, serious injury or equipment damage.

WARNING

HOT SURFACES

The braking resistor may heat up to over 250°C (480°F) during operation.

- Avoid contact with the hot braking resistor.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of the braking resistor.
- Provide for good heat dissipation.
- Check the temperature of the braking resistor under the most critical condition by performing a test run.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Braking resistors are required for dynamic applications. During deceleration, the kinetic energy is transformed into electrical energy in the motor. The electrical energy increases the DC bus voltage. The braking resistor is activated when the defined threshold value is exceeded. The braking resistor transforms electrical energy into heat. If highly dynamic deceleration is required, the braking resistor must be well adapted to the system.

Further information on the subject	Page
Technical data 3.3.5 "Braking resistor"	44
Mounting the "External braking resistor" (accessory)	92
Electrical installation: 6.2.7 "Braking resistor connection (CN8, Braking Resistor)" (accessory)	106
Setting the braking resistor parameters	170
5.5 "Parallel connection DC bus"	66
Order data for external braking resistors (accessory)	569

5.8.1 Internal braking resistor

A braking resistor is integrated in the drive to absorb braking energy. The device is shipped with the internal braking resistor active.

5.8.2 External braking resistor

An external braking resistor is required for applications in which the motor must be decelerated quickly and the internal braking resistor cannot absorb the excess braking energy.

Monitoring The device monitors the power of the braking resistor. The load on the braking resistor can be read out.
The connection of the external braking resistor is short-circuit protected. There is no protection in the case of a ground fault.

Selection of the external braking resistor

The rating of an external braking resistor depends on the required peak power and continuous power with which the braking resistor can be operated.

The resistance value R [Ω] is derived from the required peak power and the DC bus voltage.

$R = U^2 / P_{\max}$	U : Switching threshold [V] P _{max} : Peek power [W] R: Resistance [Ohm]
----------------------	--

Figure 5.3 Calculating the resistance R of an external braking resistor

If 2 or more braking resistors are connected to one drive, note the following criteria:

- The braking resistors must be connected in parallel or in series so the required resistance is reached. Only connect resistors with identical resistance in parallel in order to evenly distribute the load to all braking resistors.
- The total resistance of all external braking resistors connected to one drive must not fall below a lower limit, see chapter 3.3.5 "Braking resistor".
- The continuous power of the network of connected braking resistors must be calculated. The result must be greater than or equal to the actually required continuous power.

Use only resistors that are specified as braking resistors. For suitable braking resistors, see Accessories, page 577.

Connection of braking resistor

A parameter is used to switch between the internal and an external braking resistor. Test the function of the braking resistor under realistic conditions during commissioning, see page 151.

Braking resistors with degree of protection IP65 may be installed outside the control cabinet in an appropriate environment.

The external braking resistors listed in the Accessories chapter are shipped with an information sheet that provides details on installation.

For information on the function and the electrical installation, see page 70.



Wire ferrules: If you use wire ferrules, use only wire ferrules with collars for these connection terminals.

5.8.3 Rating information

	<p>To rate the braking resistor, calculate the proportion contributing to absorbing braking energy.</p> <p>An external braking resistor is required if the kinetic energy that must be absorbed exceeds the total of the internal proportions, including the internal braking resistor.</p>
<i>Internal energy absorption</i>	<p>Braking energy is absorbed internally by the following mechanisms:</p> <ul style="list-style-type: none"> • DC bus capacitor E_{var} • Internal braking resistor E_I • Electrical losses of the drive E_{el} • Mechanical losses of the drive E_{mech} <p>The energy E_{var} is the square difference between the voltage before the deceleration process and the response threshold.</p> <p>The voltage prior to the deceleration process depends on the mains voltage. The energy absorption by the DC bus capacitors is lowest when the mains voltage is highest. In the calculation, use the values for the highest mains voltage.</p>
<i>Internal braking resistor</i>	<p>Two characteristic values determine the energy absorption of the internal braking resistor.</p> <ul style="list-style-type: none"> • The continuous power P_{PR} is the amount of energy that can be continuously absorbed without overloading the braking resistor. • The maximum energy E_{CR} limits the maximum short-term power that can be absorbed. <p>If the continuous power was exceeded for a specific time, the braking resistor must remain without load for a corresponding period.</p> <p>The characteristic values P_{PR} and E_{CR} of the internal braking resistor can be found on page 44.</p>
<i>Electrical losses E_{el}</i>	<p>The electrical losses E_{el} of the drive system can be estimated on the basis of the peak power of the drive. The maximum power dissipation is approximately 10% of the peak power at a typical efficiency of 90%. If the current during deceleration is lower, the power dissipation is reduced accordingly.</p>
<i>Mechanical losses E_{mech}</i>	<p>The mechanical losses result from friction during operation of the system. Mechanical losses are negligible if the time required by the system to coast to a stop without a driving force is considerably longer than the time required to decelerate the system. The mechanical losses can be calculated from the load torque and the velocity from which the motor is to stop.</p>

Example Deceleration of a rotary motor with the following data:

- Initial speed of rotation: $n = 4000 \text{ min}^{-1}$
- Rotor inertia: $J_R = 4 \text{ kgcm}^2$
- Load inertia: $J_L = 6 \text{ kgcm}^2$

Calculation of the energy to be absorbed:

$$E_B = 1/2 * J * (2 * \pi * n * 1/60)^2$$

to 88 Ws

Electrical and mechanical losses are ignored.

In this example, the DC bus capacitors absorb 23 Ws (the value depends on the device type, see chapter 3 "Technical Data").

The internal braking resistor must absorb the remaining 65 Ws. It can absorb a pulse of 80 Ws. If the load is decelerated once, the internal braking resistor is sufficient.

If the deceleration process is repeated cyclically, the continuous output must be considered. If the cycle time is longer than the ratio of the energy to be absorbed E_B and the continuous power P_{PR} , the internal braking resistor is sufficient. If the system decelerates more frequently, the internal braking resistor is not sufficient.

In the example, the ratio E_B/P_{PR} is 1.3 s. If the cycle time is shorter, an external braking resistor is required.

Rating the external braking resistor

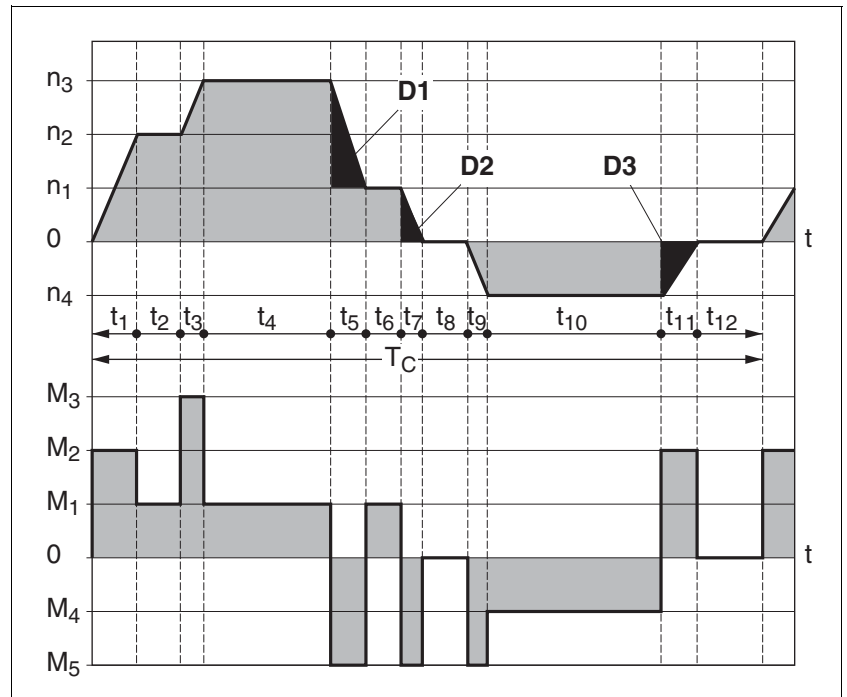


Figure 5.4 Characteristic curves for rating the braking resistor

These two characteristics are also used for the rating the motor. The segments of the characteristic curves in which the motor decelerates are designated by (D_i); these segments must be considered.

Calculation of the energy at constant deceleration:

The total inertia (J_t) must be known.

J_t with:

$$J_t = J_m + J_c$$

J_m: Motor inertia with or without holding brake

J_c: Load inertia

The energy for each deceleration segment is calculated as follows:

$$E_i = \frac{1}{2} J_t \cdot \omega_i^2 = \frac{1}{2} J_t \cdot \left[\frac{2\pi n_i}{60} \right]^2$$

Calculation for the segments (D₁) ... (D₃):

$$E_1 = \frac{1}{2} J_t \cdot \left[\frac{2\pi(n_3 - n_1)}{60} \right]^2$$

$$E_2 = \frac{1}{2} J_t \cdot \left[\frac{2\pi n_1}{60} \right]^2$$

Units: E_i in Ws (wattseconds), J_t in kgm², ω in rad and n_i in min⁻¹.

See the technical data for the energy absorption E_{var} of the devices (without consideration of an internal or external braking resistor).

In the next calculation steps, only consider those segments D_i , whose energy E_i exceeds the energy absorption of the device (see chapter 3.3 "Electrical Data"). These excess energies E_{Di} must be diverted by means of the braking resistor (internal or external).

E_{Di} is calculated using the following formula:

$$E_{Di} = E_i - E_{var} \text{ (in Ws)}$$

The continuous power P_c is calculated for each machine cycle:

$$P_c = \frac{\sum E_{Di}}{\text{Cycletime}}$$

Units: P_c in [W], E_{Di} in [Ws] and cycle time T in [s]

The selection is made in two steps:

- The maximum energy during deceleration must be less than the peak energy that the braking resistor can absorb: $(E_{Di}) < (E_{Cr})$. In addition, the continuous power of the internal braking resistor must not be exceeded: $(P_c) < (P_{Pr})$. If these conditions are met, then the internal braking resistor is sufficient.
- If one of the conditions is not met, you must use an external braking resistor. The braking resistor must be rated in such a way that the conditions are met. The resistance of the braking resistor must be between the specified minimum and maximum values, since otherwise the load can no longer be decelerated or the product might be destroyed.

For order data for the external braking resistors, see chapter Accessories, page 578.

5.9 Safety function STO ("Safe Torque Off")

See chapter 55 for information on using the IEC 61508 standard.

5.9.1 Definitions

<i>Safety function STO (IEC 61800-5-2)</i>	The safety function STO ("Safe Torque Off") shuts off the motor torque safely. It is not necessary to interrupt the supply voltage. There is no monitoring for standstill.
<i>Category 0 stop (IEC 60204-1)</i>	Stopping by immediate removal of power to the machine actuators (i.e. an uncontrolled stop).
<i>Category 1 stop (IEC 60204-1)</i>	Controlled stop with power available to the machine actuators to achieve the stop. Power is not interrupted until the stop is achieved.

5.9.2 Function

The STO safety function integrated into the product can be used to implement an "EMERGENCY STOP" (IEC 60204-1) for category 0 stops. With an additional, approved EMERGENCY STOP safety relay module, it is also possible to implement category 1 stops.

<i>Function principle</i>	<p>The STO safety function is triggered via 2 redundant inputs. The circuits of the two inputs must be separate so that there are two channels.</p> <p>The switching process must be simultaneous for both inputs (offset <1s). The power stage is disabled and an error message is generated. The motor can no longer generate torque and coasts down without braking. A restart is possible after resetting the error message with a "Fault Reset".</p> <p>The power stage is disabled and an error message is generated if only one of the two inputs is switched off or if the time offset is too great. This error message can only be reset by switching off the product.</p>
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5.9.3 Requirements for using the safety function

⚠ DANGER**ELECTRIC SHOCK CAUSED BY INCORRECT USE**

The safety function STO (Safe Torque Off) does not cause electric isolation. The DC bus voltage is still present.

- Turn off the mains voltage using an appropriate switch to achieve a voltage-free condition.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING**LOSS OF SAFETY FUNCTION**

Incorrect usage may cause a hazard due to the loss of the safety function.

- Observe the requirements for using the safety function.

Failure to follow these instructions can result in death or serious injury.

The inputs for the STO safety function (inputs $\overline{\text{STO_A}}$ and $\overline{\text{STO_B}}$) are permanently set to logic type 1.

Category 0 stop During a category 0 stop, the motor coasts down in an uncontrolled way. If access to the machine coasting down involves a hazard (results of the hazard and risk analysis), you must take appropriate measures.

Category 1 stop A controlled stop must be triggered with a category 1 stop. The controlled stop is not monitored by the drive system. In the case of power outage or an error, a controlled stop is impossible. Final shutoff of the motor is achieved by switching off the two inputs of the STO safety function. The shutoff is usually controlled by a standard EMERGENCY STOP safety relay module with a safe time delay.

Behavior of holding brake Triggering the STO safety function means that the delay time for motors with holding brake is not effective. The motor cannot generate holding torque to bridge the time to application of the holding brake. Check whether additional measures have to be taken; for example, this may cause the load of vertical axes to lower.

Vertical axes, external forces If external forces act on the motor (vertical axis) and an unwanted movement, for example caused by gravity, could cause a hazard, the motor must not be operated without additional measures for fall protection.

Unintended restart To avoid unintended restart of the motor after restoration of power (for example, after power outage), the parameter `IO_AutoEnable` must be set to "off". Note that a master controller must not trigger an unintended restart.

Degree of protection when the safety function is used You must ensure that conductive substances cannot get into the product (pollution degree 2). Conductive substances may cause the safety function to become inoperative.

Protected cable installation

If short circuits and cross circuits can be expected in connection with safety-related signals and if they are not detected by upstream devices, protected cable installation as per ISO 13849-2 is required.

In the case of an unprotected cable installation, the two signals (both channels) of a safety function may be connected to external voltage if a cable is damaged. If the two channels are connected to external voltage, the safety function is no longer operative.

Data for maintenance plan and safety calculations

Use the following data of the STO safety function for your maintenance plan and the safety calculations:

Lifetime (IEC 61508)	Years	20
SFF (IEC 61508) Safe Failure Fraction	[%]	80
HFT (IEC 61508) Hardware Fault Tolerance Type A subsystem		1
Safety integrity level IEC 61508 IEC 62061		SIL3 SILCL3
PFH (IEC 61508) Probability of Dangerous Hardware Failure per Hour	[1/h] (FIT)	$1 \cdot 10^{-9}$ (1)
PL (ISO 13849-1) Performance Level		e (category 3)
MTTF _d (ISO 13849-1) Mean Time to Dangerous Failure	Years	1400
DC (ISO 13849-1) Diagnostic Coverage	[%]	90

The data for the safety module eSM can be found in the product manual for the safety module.

Hazard and risk analysis

As a system integrator you must conduct a hazard and risk analysis of the entire system. The results must be taken into account in the application of the safety function.

The type of circuit resulting from the analysis may differ from the following application examples. Additional safety components may be required. The results of the hazard and risk analysis have priority.

5.9.4 Application examples STO

Example of category 0 stop Use without EMERGENCY STOP safety relay module, category 0 stop.

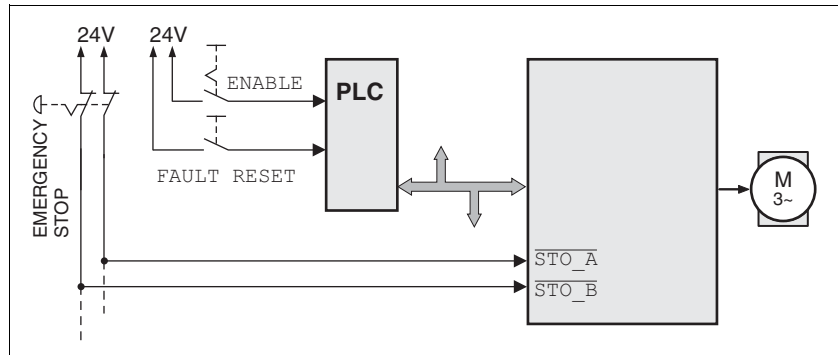


Figure 5.5 Example of category 0 stop

An EMERGENCY STOP is requested. This request leads to a category 0 stop

- The power stage is immediately disabled via the inputs $\overline{\text{STO_A}}$ and $\overline{\text{STO_B}}$ of the STO safety function. Power can no longer be supplied to the motor. If the motor has not yet stopped at this point in time, it coasts down in an uncontrolled way (uncontrolled stop).

Example of category 1 stop Application with EMERGENCY STOP safety relay module, category 1 stop.

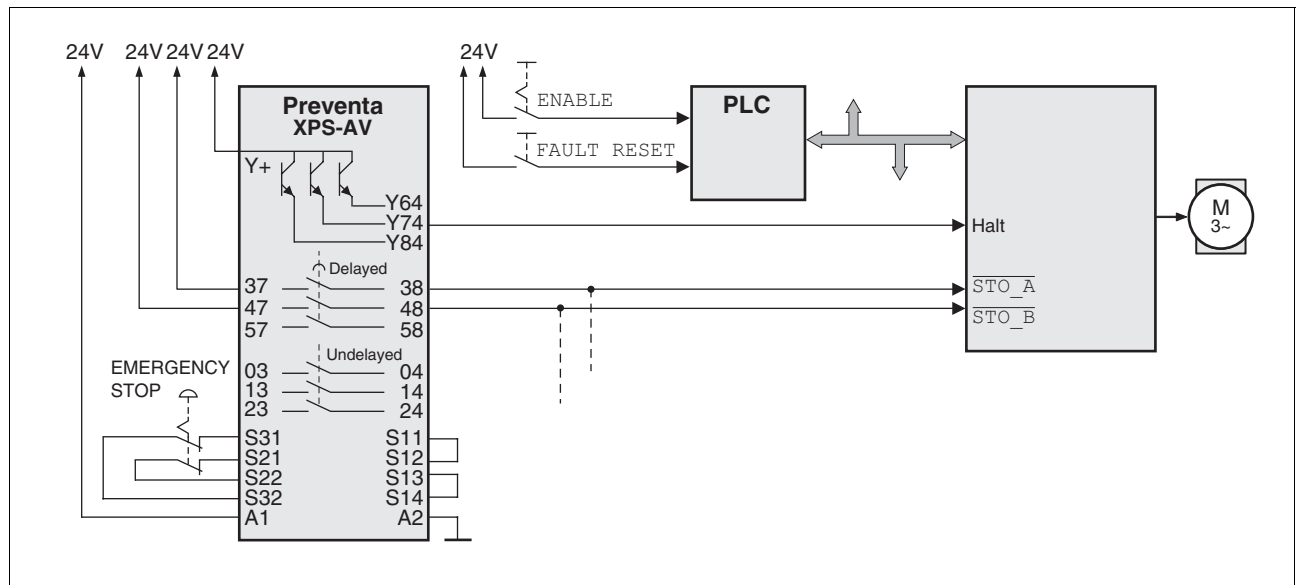


Figure 5.6 Example of category 1 stop with external Preventa XPS-AV EMERGENCY STOP safety relay module

An EMERGENCY STOP is requested. This request leads to a category 1 stop

- The function "Halt" is immediately started (undelayed) via the input HALT (single-channel, not monitored). Any active movement is decelerated via the adjusted ramp.
- The power stage is disabled via the inputs STO_A and STO_B of the STO safety function after the delay time set in the EMERGENCY STOP safety relay module has elapsed. Power can no longer be supplied to the motor. If the motor has not yet stopped when the delay time has elapsed, it coasts down in an uncontrolled way (uncontrolled stop).

NOTE: The specified minimum current and the permissible maximum current of the relay outputs of the EMERGENCY STOP safety relay module must be observed.

5.10 Logic type

⚠ WARNING

UNINTENDED OPERATION

If logic type 2 is used, a ground fault of a signal is detected as an On state.

- Use great care in wiring to exclude the possibility of ground faults.

Failure to follow these instructions can result in death, serious injury or equipment damage.

The digital inputs and outputs of this product can be wired for logic type 1 or logic type 2.

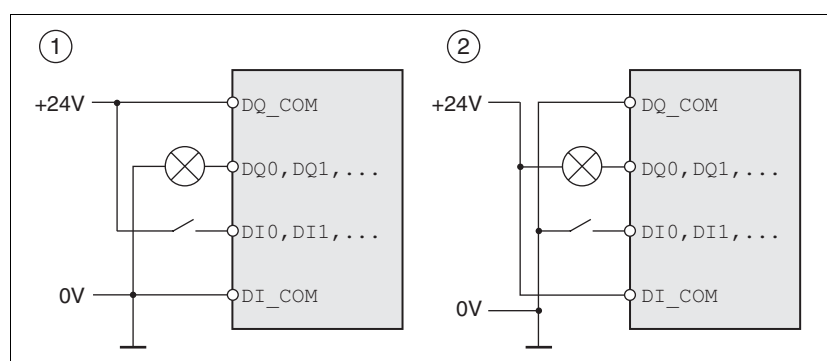


Figure 5.7 Logic type

Logic type	Active state
(1) Logic type 1	Output supplies current (Source) Current flows to the input
(2) Logic type 2	Output draws current (Sink) Current flows from the input

Signal inputs are protected against reverse polarity, outputs are short-circuit protected. The inputs and outputs are galvanically isolated.

The logic type is determined by the way $\overline{DI_COM}$ and $\overline{DQ_COM}$ are wired, see Figure 5.7. The logic type affects wiring and control of the sensors; therefore, you should determine the required value in the engineering phase in view of the application.

Special case: Safety function STO

The inputs for the STO safety function (inputs $\overline{STO_A}$ and $\overline{STO_B}$) are permanently set to logic type 1.

5.11 Monitoring functions

The monitoring functions in the product can help to guard the system and reduce the risks involved in a system misoperation. These monitoring functions may not be used to protect persons.

The following monitoring functions are available:

Monitoring	Task
Data connection	Error response if the link becomes inoperative
Limit switch signals	Monitors for permissible movement range
Position deviation	Monitors for difference between actual position and reference position
Motor overload	Monitors for excessively high current in the motor phases
Overvoltage and undervoltage	Monitors for overvoltage and undervoltage of the power stage supply and the DC bus
Overtemperature	Monitors the device for overtemperature
I^2t limitation	Power limitation in the case of overloads for the motor, the output current, the output power and the braking resistor.
Commutation	Plausibility check of motor acceleration and effective torque
Mains phases	Monitoring for missing mains phases
Short circuit / ground fault	Monitors for short circuit between motor phase and motor phase and between motor phase and ground

For a description of the monitoring functions, see chapter 8.8 "Functions for monitoring movements".

5.12 Configurable inputs and outputs

WARNING

LOSS OF CONTROL

The use of limit switches can provide some protection against hazards (for example, collision with mechanical stop caused by incorrect reference values).

- If possible, use the limit switches.
- Verify correct connection of the limit switches.
- Verify the correct installation of the limit switches. The limit switches must be mounted in a position far enough away from the mechanical stop to allow for an adequate stopping distance.
- You must release the limit switches before you can use them.
- Verify the correct function of the limit switches.

Failure to follow these instructions can result in death, serious injury or equipment damage.

This product has digital inputs and outputs that can be configured. The inputs and outputs have a defined standard assignment depending on the operating mode. This assignment can be adapted to the requirements of the customer's installation. See chapter 8.6.2 "Setting the digital signal inputs and signal outputs" for additional information.

6 Installation

6

An engineering phase is mandatory prior to mechanical and electrical installation. See chapter 5 "Engineering", page 57, for basic information.

⚠ WARNING

LOSS OF CONTROL

- The designer of any control scheme must consider the potential failure modes of control paths and, for certain critical functions, provide a means to achieve a safe state during and after a path failure. Examples of critical control functions are emergency stop, overtravel stop, power outage and restart.
- Separate or redundant control paths must be provided for critical functions.
- System control paths may include communication links. Consideration must be given to the implication of unanticipated transmission delays or failures of the link.
- Observe all accident prevention regulations and local safety guidelines.¹⁾
- Each implementation of the product must be individually and thoroughly tested for proper operation before being placed into service.

Failure to follow these instructions can result in death or serious injury.

¹⁾ For USA: Additional information, refer to NEMA ICS 1.1 (latest edition), "Safety Guidelines for the Application, Installation, and Maintenance of Solid State Control" and to NEMA ICS 7.1 (latest edition), "Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable-Speed Drive Systems".

6.1 Mechanical installation

DANGER

ELECTRIC SHOCK CAUSED BY FOREIGN OBJECTS OR DAMAGE

Conductive foreign objects in the product or damage may cause parasitic voltage.

- Do not use damaged products.
- Keep foreign objects such as chips, screws or wire clippings from getting into the product.

Failure to follow these instructions will result in death or serious injury.

WARNING

LOSS OF SAFETY FUNCTION CAUSED BY FOREIGN OBJECTS

Conductive foreign objects, dust or liquids may cause safety functions to become inoperative.

- Do not use the a safety function unless you have protected the system against contamination by conductive substances.

Failure to follow these instructions can result in death or serious injury.

WARNING

HOT SURFACES

The heat sink at the product may heat up to over 100°C (212°F) during operation.

- Avoid contact with the hot heat sink.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity.
- Consider the measures for heat dissipation described.

Failure to follow these instructions can result in death or serious injury.

6.1.1 Installing and removing modules

CAUTION

DESTRUCTION DUE TO ESD

Electrostatic discharge (ESD) can cause immediate or later destruction of the module or the device.

- Use suitable ESD measures (IEC 61340-5-2) when handling the module.
- Do not touch any internal components.

Failure to follow these instructions can result in equipment damage.

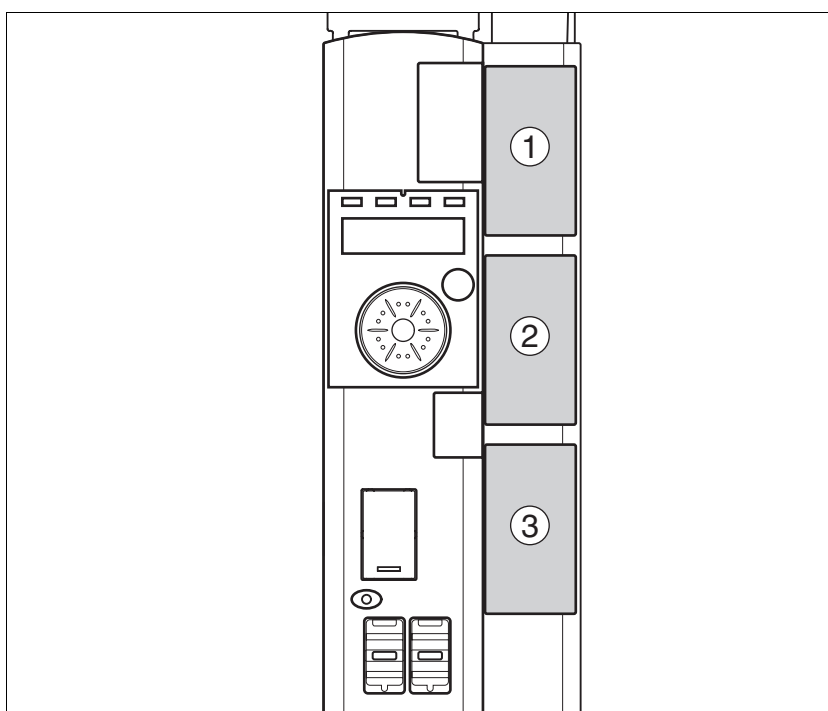


Figure 6.1 Module slots (slot 1 ... slot 3)

The device has 3 module slots. The module slots are designed for the following modules. See also chapter .

Slot 1	Safety module eSM I/O module IOM1
Slot 2	Encoder module RSR (resolver interface) Encoder module DIG (digital interface) Encoder module ANA (analog interface)
Slot 3	Fieldbus module CANopen (module identification CAN) Fieldbus module Profibus DP (module identification PDP) Fieldbus module DeviceNet (module identification DNT) Fieldbus module EtherNet/IP (module identification ETH) Fieldbus module EtherCAT (module identification ECT)



Do not install the safety module eSM until you have commissioned the drive.

Plugging a modul into a slot

Procedure for plugging in a module:

- Disconnect all power (power stage supply voltage and controller supply voltage) before plugging in or removing a module. Verify that no voltage is present (safety instructions).
- ▶ Fully read and understand the product manual as well as the manual for the module prior to installing the module.
- ▶ Verify that the order number on the nameplate of the module corresponds to the specification in the manual for the module.
- ▶ Note and record the serial number, revision and DOM shown on the nameplate of the module and the nameplate of the device.
- ▶ Remove the cover from the module slot and keep the cover.
- ▶ Check the module for visible damage. Do not install damaged modules.
- ▶ Plug the module into the appropriate slot until the snap-in lock snaps in.

Information on wiring can be found in the chapter "Installation" of the manual for the module.

- ▶ Fasten the connection cable to the cable guide of the device.

Various settings must be made the next time the device is switched on. See the chapter Commissioning of the manual for the module for details on these settings.

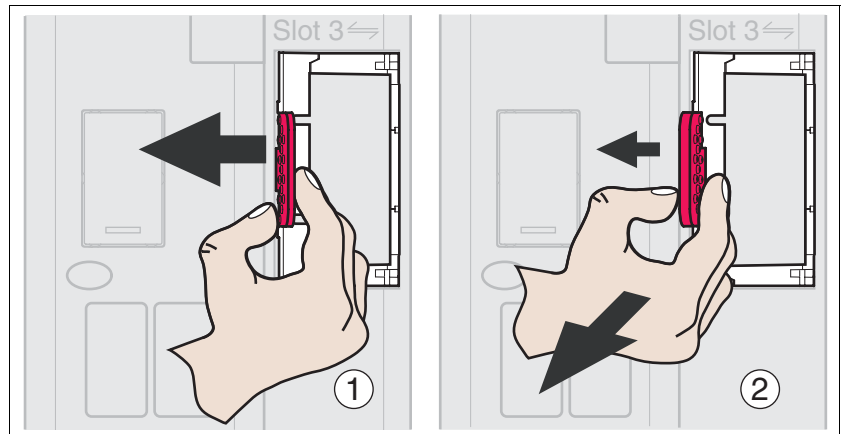
Removing a module from a slot

Figure 6.2 Removing a module from a slot, in this example from slot 3

Procedure for removing a module from a slot of the device:

- Disconnect all power (power stage supply voltage and controller supply voltage) before plugging in or removing a module. Verify that no voltage is present (safety instructions).
- ▶ Label the connection cables. Remove the wiring of the module.
- ▶ Push the snap-in lock of the module to the left (1) and pull out the module at the snap-in lock (2) while holding it to the left.
- ▶ Close the module slot with the cover.

The next time the device is switched on, it signal a different hardware. See chapter 10.3.3 "Acknowledging a module replacement", page 360 for additional information.

6.1.2 Mounting the device

Attaching a label with safety instructions

- ▶ Select the label suitable for the target country. Observe the safety regulations in the target country.
- ▶ Attach the label to the front of the device so that it is clearly visible.

Control cabinet

The control cabinet must have a sufficient size so that all devices and components can be permanently installed and wired in compliance with the EMC requirements.

The ventilation of the control cabinet must be sufficient to remove the heat generated by all devices and components operated in the control cabinet.

Mounting distances, ventilation

When selecting the position of the device in the control cabinet, note the following:

- Mount the device in a vertical position ($\pm 10^\circ$). This is required for cooling the device.
- Adhere to the minimum installation distances for required cooling. Avoid heat accumulations.
- Do not mount the device close to heat sources.
- Do not mount the device on flammable materials.
- The heated airflow from other devices and components must not heat up the air used for cooling the device.
- If the thermal limits are exceeded during operation, the drive switches off (overtemperature).
- Comply with the specifications in chapter 6.1.3 "Mounting mains filter, mains reactor and braking resistor", page 92, for mounting additional components (external mains filters, mains reactor, external braking resistor).

The connection cables of the devices are routed to the top and to the bottom. The minimum distances must be adhered to for air circulation and cable installation.

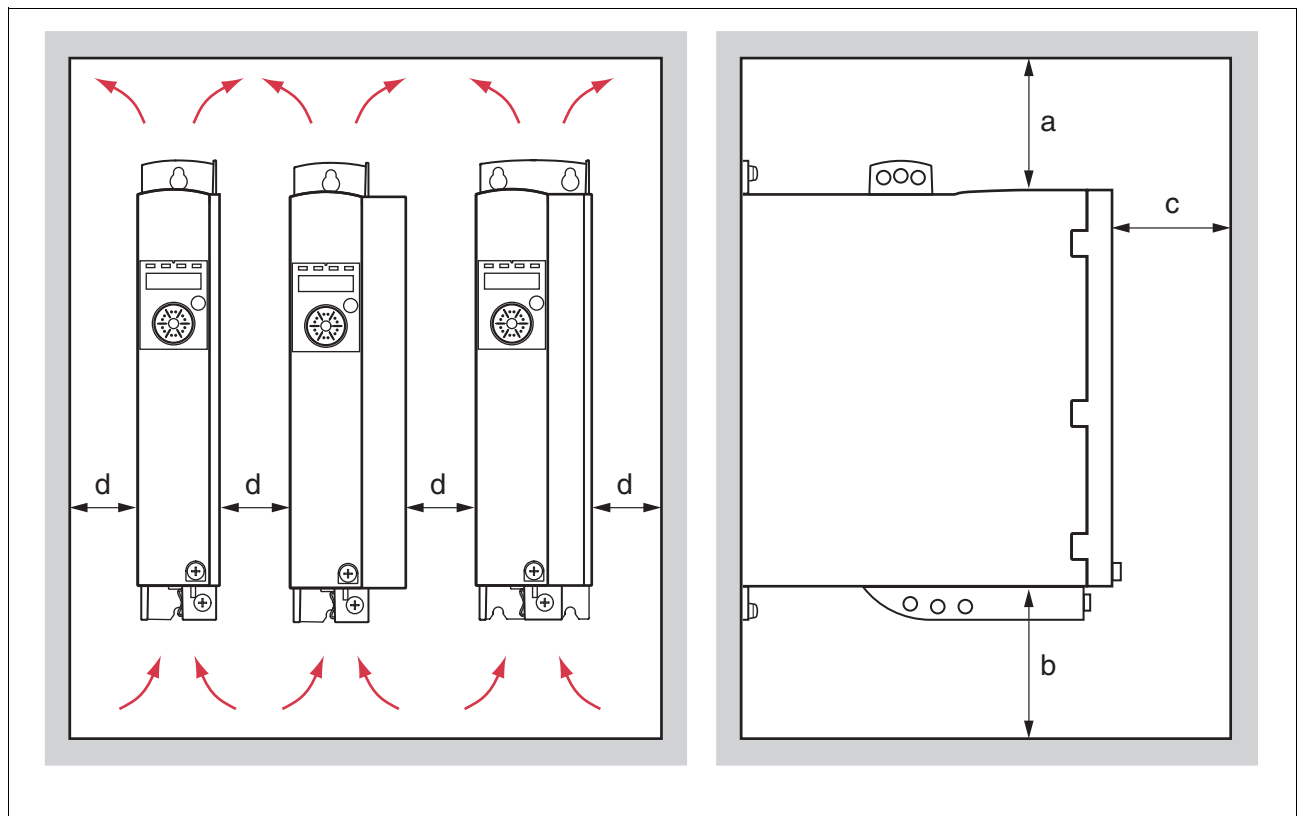


Figure 6.3 Mounting distances and air circulation

Distance	
$a \geq 100 \text{ mm}$ ($a \geq 40 \text{ in.}$)	Free space above the device
$b \geq 100 \text{ mm}$ ($b \geq 40 \text{ in.}$)	Free space below the device
$c \geq 60 \text{ mm}$ ($c \geq 23.5 \text{ in.}$)	Free space in front of the device
$d \geq 0 \text{ mm}$ ($d \geq 0 \text{ in.}$)	Space between devices for ambient temperature during operation: $0^\circ\text{C} \dots +50^\circ\text{C}$ ($32^\circ\text{F} \dots 122^\circ\text{F}$)

Mounting the device

See chapter 3.2.1 "Dimensional drawings", page 23 for the dimensions of the mounting holes.

NOTE: Painted surfaces have an insulating effect. Before mounting the device to a painted mounting plate, remove all paint across a large area of the mounting points until the metal is completely bare.

- Note the ambient conditions in chapter 3 "Technical Data", page 21.
- Mount the device in a vertical position ($\pm 10^\circ$).

6.1.3 Mounting mains filter, mains reactor and braking resistor

External mains filter The drives have an integrated mains filter.

An additional external mains filter is required in the case of long motor cables. When using external mains filters, verify compliance with all applicable EMC directives.

Further information on the subject	Page
Technical data external mains filters (accessory)	49
Engineering information external mains filters (accessory)	67
Electrical installation of external mains filters (accessory)	109
Order data external mains filters (accessory)	528

► Mount the external mains filter above the device.

Mains reactor A mains reactor must be used under specific conditions as outlined in chapter 5.6 "Mains reactor", page 67. The mains reactor is shipped with an information sheet that provides details on mounting. Information on the electrical installation can be found in chapter 6.2.8 "Connection of power stage supply voltage (CN1)", page 109.

If you install a mains reactor, the power provided by the device is increased, see chapter 3.3.1 "Power stage", page 25. Increased power is only available if the corresponding parameter is set during commissioning.

Further information on the subject	Page
Technical data mains reactor (accessory)	50
Engineering information mains reactor (accessory)	67
Electrical installation of the mains reactor (accessory)	109
Order data mains reactor (accessory)	528

*External braking resistor***⚠ WARNING****HOT SURFACES**

The braking resistor may heat up to over 250°C (480°F) during operation.

- Avoid contact with the hot braking resistor.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of the braking resistor.
- Provide for good heat dissipation.
- Check the temperature of the braking resistor under the most critical condition by performing a test run.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Braking resistors with degree of protection IP65 may be installed outside the control cabinet in an appropriate environment.

The external braking resistors listed in the Accessories chapter are shipped with an information sheet that provides details on installation.

Further information on the subject	Page
Technical data braking resistor	44
Mounting the external braking resistor (accessory)	92
Electrical installation of the braking resistor (accessory)	106
Setting the braking resistor parameters	166
Order data for external braking resistors (accessory)	

6.2 Electrical installation

⚠ DANGER

ELECTRIC SHOCK CAUSED BY FOREIGN OBJECTS OR DAMAGE

Conductive foreign objects in the product or damage may cause parasitic voltage.

- Do not use damaged products.
- Keep foreign objects such as chips, screws or wire clippings from getting into the product.

Failure to follow these instructions will result in death or serious injury.

⚠ DANGER

ELECTRIC SHOCK CAUSED BY INSUFFICIENT GROUNDING

Insufficient grounding causes the hazard of electric shocks.

- Ground the drive system before applying voltage.
- Do not use conduits as protective ground conductors; use a protective ground conductor inside the conduit.
- The cross section of the protective ground conductor must comply with the applicable standards.
- Ground the cable shields at both ends; however, the shields are not protective ground conductors.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING

THIS PRODUCT MAY CAUSE DIRECT CURRENT IN THE PROTECTIVE GROUND CONDUCTOR

If a residual current device (RCD) is used, conditions must be observed.

Failure to follow these instructions can result in death or serious injury.

See chapter 5.3 "Residual current device", page 65 for conditions for using a residual current device.

Logic types

The product supports logic type 1 and logic type 2 for digital signals. Note that most of the wiring examples show the logic type 1. The STO safety function must be wired using the logic type 1.

6.2.1 Overview of procedure

- Take into account the information provided in chapter 5 "Engineering". The selected settings affect the entire installation.
- The entire installation procedure must be performed without voltage present.

Sequence of installation steps:

Connection	Connection to	Page
Ground connection	Grounding screw	97
Motor phases	CN10	98
Holding brake	CN11	104
DC bus connection	CN9	105
External braking resistor	CN8	106
Power stage supply	CN1	109
Motor encoder (encoder 1)	CN3	114
PTO: Encoder simulation ESIM	CN4	116
PTI: Pulse/Direction P/D	CN5	118
PTI: A/B signals	CN5	118
PTI: CW/CCW	CN5	118
Safety function STO	CN2	121
24 V controller supply voltage	CN2	121
Digital inputs / outputs	CN6	
Commissioning interface (PC)	CN7	126
Installation of modules	Slot 1 ... slot 3	87

Table 6.1 Installation overview

Finally, verify proper installation.

6.2.2 Connection overview

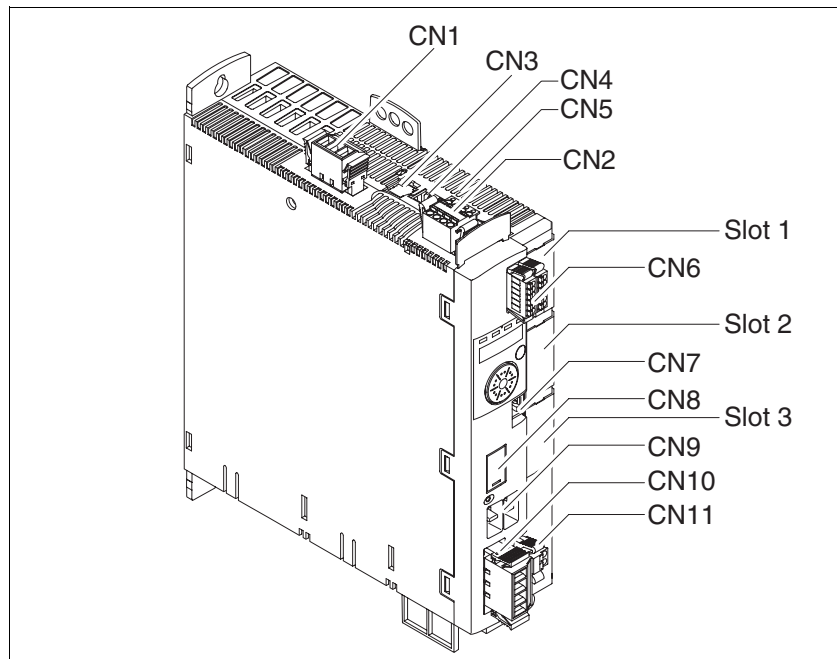


Figure 6.4 Overview of the signal connections

Connection	Assignment
CN1	Power stage supply
CN2	24 controller supply voltage and STO safety function
CN3	Motor encoder (encoder 1)
CN4	PTO (encoder simulation ESIM)
CN5	PTI (A/B signals, P/D-Signale, CW/CCW signals)
CN6	Digital inputs/outputs
CN7	Modbus (commissioning interface)
CN8	External braking resistor
CN9	DC bus connection for parallel operation
CN10	Motor phases
CN11	Holding brake
Slot 1	Safety module or I/O module
Slot 2	Encoder module (encoder 2)
Slot 3	Fieldbus module

Table 6.2 Assignment of the signal connections

6.2.3 Connection grounding screw

⚠ DANGER

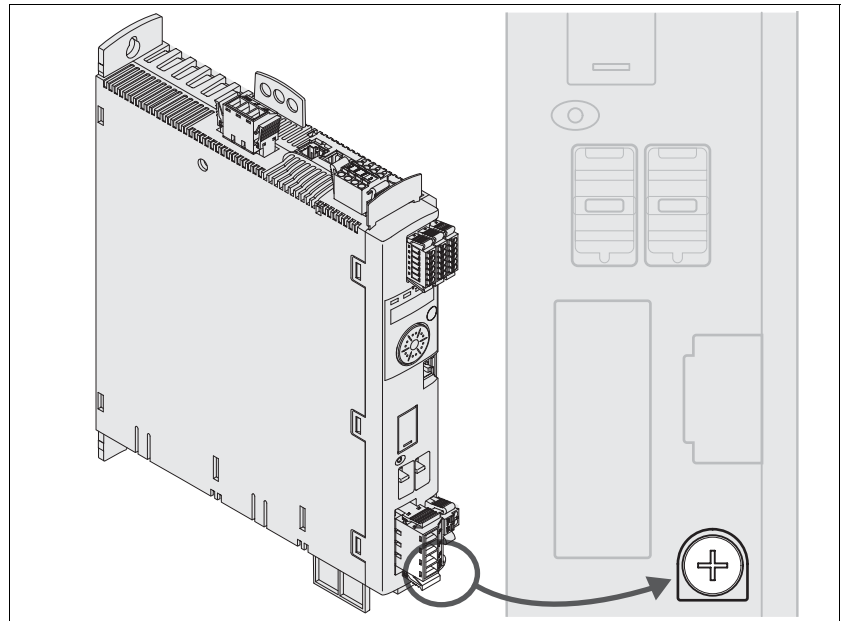
ELECTRIC SHOCK CAUSED BY INSUFFICIENT GROUNDING

This drive system has an increased leakage current > 3.5 mA.

- Use a protective ground conductor at with least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals. Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment.

Failure to follow these instructions will result in death or serious injury.

The central grounding screw of the product is located at the bottom of the front side.



- Connect the ground connection of the device to the central ground point of the system.

LXM32•...		
Tightening torque for terminal screws	[Nm] ([lb.in])	5.5 (48.7)

6.2.4 Connecting the motor phases (CN 10, motor)

⚠ DANGER**ELECTRIC SHOCK**

High voltages at the motor connection may occur unexpectedly.

- The motor generates voltage when the shaft is rotated. Prior to performing any type of work on the drive system, block the motor shaft to prevent rotation.
- AC voltage can couple voltage to unused conductors in the motor cable. Insulate both ends of unused conductors in the motor cable.
- The system integrator is responsible for compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment. Supplement the motor cable grounding conductor with an additional protective ground conductor to the motor housing.

Failure to follow these instructions will result in death or serious injury.

⚠ DANGER**ELECTRIC SHOCK CAUSED BY INSUFFICIENT ISOLATION**

If third-party motors are used, insufficient isolation may allow hazardous voltages to reach the PELV circuit.

- Verify protective separation between the temperature sensor and the motor phases.
- Verify that the signals at the encoder connection meet the PELV requirements.
- Verify protective separation between the brake voltage in the motor and the motor cable on the one hand and the motor phases on the other hand.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING**UNEXPECTED MOVEMENT**

Drive systems may perform unexpected movements because of incorrect connection or other errors.

- Operate the device with approved motors only. Even if motors are similar, different adjustment of the encoder system may be a source of hazards.
- Even if the connectors for power connection and encoder match mechanically, this does NOT imply that they may be used.

Failure to follow these instructions can result in death, serious injury or equipment damage.



Route the cables from the motor and the encoder to the device (start at the motor). Due to the pre-assembled connectors, this direction is often faster and easier.

Cable specifications See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	Required, both ends grounded
Twisted Pair:	-
PELV:	The wires for the holding brake must be PELV-compliant.
Cable composition:	3 wires for motor phases 2 wires for holding brake Cross section: The conductors must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.
Maximum cable length:	Depends on the required limit values for conducted interference, see chapter 3.3.6 "Internal mains filter", page 48, and chapter 3.3.7 "External mains filters (accessories)", page 49.
Special features:	Contains wires for the holding brake

Note the following information:

- You may only connect the original motor cable (with two wires for the holding brake).
 - The wires for the holding brake must also be connected to the device at connection CN11 in the case of motors without holding brakes. At the motor end, connect the wires to the appropriate pins for the holding brake; the cable can then be used for motors with or without holding brake. If you do not connect the wires at the motor end, you must isolate each wire individually (inductive voltages).
 - Observe the polarity of the holding brake voltage.
 - The voltage for the holding brake depends on the controller supply voltage (PELV). Observe the tolerance for the controller voltage and the specified voltage for the holding brake.
- Use pre-assembled cables (page 519) to reduce the risk of wiring errors.

Properties of connection terminals
CN10

The terminals are approved for fine wire conductors and rigid conductors. Observe the maximum permissible connection cross section. Take into account the fact that wire ferrules increase the conductor cross section. Carefully insert the conductors for maximum current capacity and vibration resistance.

LXM32•U45••, LXM32•U60••, LXM32•U90••, LXM32•D12••, LXM32•D18••, LXM32•D30••		
Connection cross section	[mm ²]	0.75 ... 5.3 (AWG 18 ... AWG 10)
Tightening torque for terminal screws	[Nm] ([lb.in])	0.68 (6.0)
Stripping length	[mm]	6 ... 7

LXM32•D72N4		
Connection cross section	[mm ²]	0.75 ... 10 (AWG 18 ... AWG 8)
Tightening torque for terminal screws	[Nm] ([lb.in])	1.81 (16.0)
Stripping length	[mm]	8 ... 9

Assembling cables Note the dimensions specified when assembling cables.

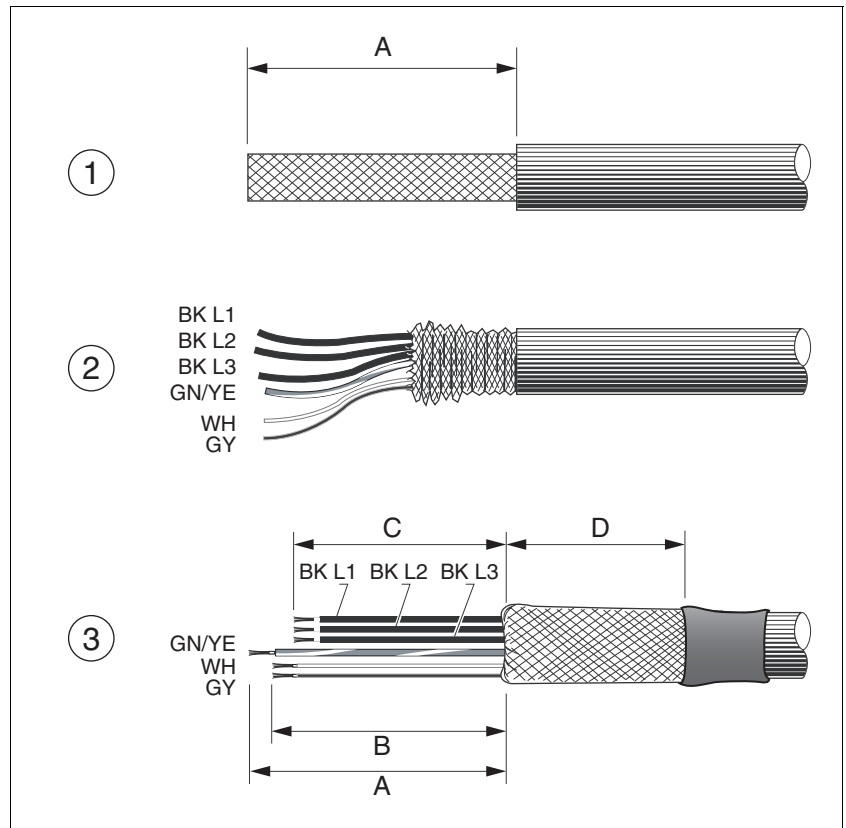


Figure 6.5 Steps (1-3) for assembling the motor cable

LXM32•...		
A	mm	140
B	mm	135
C	mm	130
D	mm	50

- (1) Strip the cable jacket; length A, see table.
- (2) Slide the shield braiding back over the cable jacket. The effective shield must have at least length D for connection to the shield clamp.
- (3) Secure the shield braiding with heat shrink tube. Note that a large surface area of the shield braiding must be connected to the EMC shield clamp.
Shorten the wires for the holding brake to length B and the three wires for the motor phases to length C. The protective ground conductor has length A.
Connect the the wires for the holding brake to the device even in the case of motors without holding brakes (inductive voltage). See also chapter 6.2.5 "Holding brake connection (CN11, Brake)", page 104.

Observe the maximum permissible connection cross section. Take into account the fact that wire ferrules increase the conductor cross section.

Monitoring The device monitor the motor phases for:

- Short circuit between the motor phases
- Short circuit between the motor phases and ground

Short circuits between the motor phases and the DC bus, the braking resistor or the holding brake wires are not detected.

Wiring diagram motor

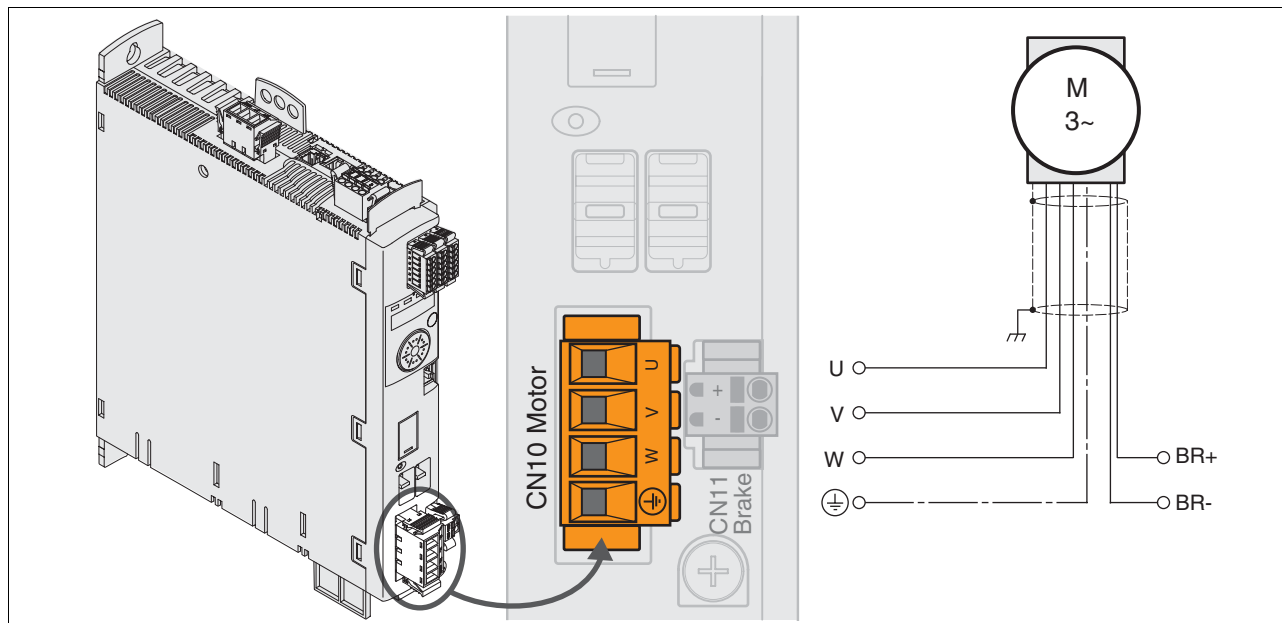


Figure 6.6 Wiring diagram motor with holding brake

Connection	Meaning	Color
U	Motor phase	Black L1 (BK)
V	Motor phase	Black L2 (BK)
W	Motor phase	Black L3 (BK)
PE	Protective ground conductor	Green/yellow (GN/YE)
BR+	Holding brake +	White (WH) or black 5 (BK)
BR-	Holding brake -	Gray (GR) or black 6 (BK)

- Connecting the motor cable*
- ▶ Note the EMC requirements for the motor cables, see page 58.
 - ▶ Connect the motor phases and protective ground conductor to CN10. Verify that the connections U, V, W and PE (ground) match at the motor and the device.
 - ▶ Note the tightening torque specified for the terminal screws.
 - ▶ Connect the white wire or the black wire with the label 5 to connection BR+ of CN11.
Connect the gray wire or the black wire with the label 6 to connection BR- of CN11 (see also page 104).
 - ▶ Verify that the connector locks snap in properly at the housing.
 - ▶ Connect the cable shield to the shield clamp (large surface area contact).

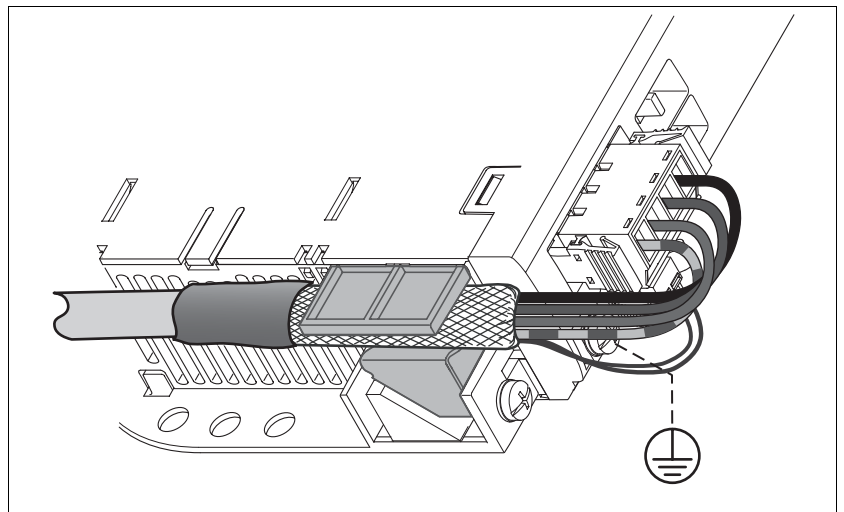


Figure 6.7 Shield clamp motor cable

6.2.5 Holding brake connection (CN11, Brake)

⚠ DANGER**ELECTRIC SHOCK**

High voltages at the motor connection may occur unexpectedly.

- The motor generates voltage when the shaft is rotated. Prior to performing any type of work on the drive system, block the motor shaft to prevent rotation.
- AC voltage can couple voltage to unused conductors in the motor cable. Insulate both ends of unused conductors in the motor cable.
- The system integrator is responsible for compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment. Supplement the motor cable grounding conductor with an additional protective ground conductor to the motor housing.

Failure to follow these instructions will result in death or serious injury.

The optional holding brake of a motor is connected to connection CN11. The integrated holding brake controller releases the holding brake when the power stage is enabled. When the power stage is disabled, the holding brake is re-applied.

The wires must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.

Note the following information:

- You may only connect the original motor cable (with two wires for the holding brake).
- The wires for the holding brake must be connected to the device via connection CN11 even in the case of motors without holding brakes (inductive voltage). The other end of the wires must be isolated or, as in the case of pre-assembled cables, connected to the appropriate pins of the connector at the motor end.
- Observe the polarity of the holding brake voltage.
- The voltage for the holding brake depends on the controller supply voltage (PELV). Observe the tolerance for the controller voltage and the specified voltage for the holding brake.

Properties of spring terminal CN11

LXM32•...		
Maximum terminal current	[A]	1.7
Connection cross section	[mm ²]	0.75 ... 2.5 (AWG 18 ... AWG 14)
Stripping length	[mm]	12 ... 13

The terminals are approved for fine wire conductors and rigid conductors. Observe the maximum permissible connection cross section. Take into account the fact that wire ferrules increase the conductor cross section. Carefully insert the conductors for maximum current capacity and vibration resistance.

Wiring diagram of holding brake

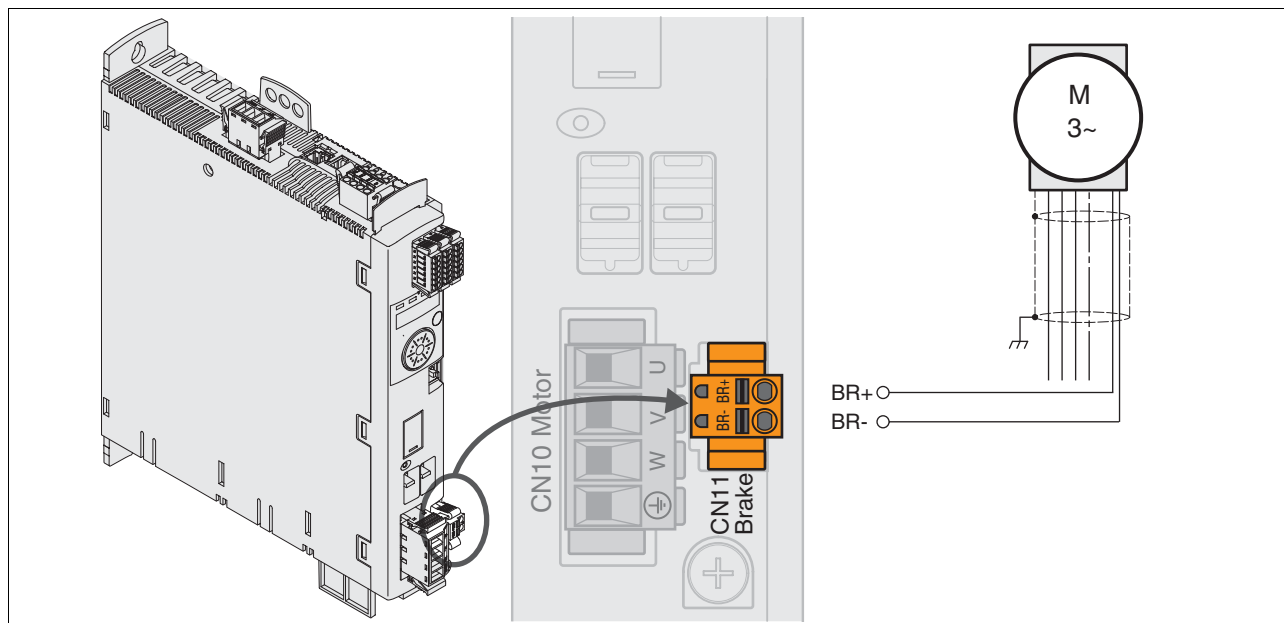


Figure 6.8 Wiring diagram motor with holding brake

Connection	Meaning	Color
U	Motor phase	Black L1 (BK)
V	Motor phase	Black L2 (BK)
W	Motor phase	Black L3 (BK)
PE	Protective ground conductor	Green/yellow (GN/YE)
BR+	Holding brake +	White (WH) or black 5 (BK)
BR-	Holding brake -	Gray (GR) or black 6 (BK)

Cable assembly, wiring and connection are described in chapter 6.2.4 "Connecting the motor phases (CN 10, motor)", page 98.

- Verify that the connector locks snap in properly at the housing.

6.2.6 Connecting the DC bus (CN9, DC bus)

⚠ WARNING**DESTRUCTION OF SYSTEM COMPONENTS AND LOSS OF CONTROL**

Incorrect use of a parallel connection of the DC bus may destroy the drive systems immediately or after a delay.

- Note the requirements concerning the use of a parallel DC bus connection.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Requirements for use

The requirements and limit values for parallel connection of multiple LXM32 via the DC bus can be found on the Internet in the form of Application Note MNA01M001.

6.2.7 Braking resistor connection (CN8, Braking Resistor)

⚠ WARNING

MOTOR WITHOUT BRAKING EFFECT

An insufficient braking resistor causes overvoltage on the DC bus and switches off the power stage. The motor is no longer actively decelerated.

- Verify that the braking resistor has a sufficient rating.
- Check the parameter settings for the braking resistor.
- Check the I^2t value under the most critical condition by performing a test run. The device switches off at an I^2t value of 100%.
- When performing the calculation and the test run, take into account the fact that the DC bus capacitors can absorb less braking energy at higher mains voltages.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Further information on the subject	Page
Technical data braking resistor	44
Rating the braking resistor	69
Mounting the external braking resistor (accessory)	92
Setting the braking resistor parameters	166
Order data for external braking resistors (accessory)	519

6.2.7.1 Internal braking resistor

A braking resistor is integrated in the device to absorb braking energy. The device is shipped with the internal braking resistor active.

6.2.7.2 External braking resistor

An external braking resistor is required for applications in which the motor must be decelerated quickly and the internal braking resistor cannot absorb the excess braking energy.

Selection and rating of the external braking resistor are described in chapter 5.8 "Rating the braking resistor", page 69. For suitable braking resistors, see chapter 12 "Accessories and spare parts", page 527.

Cable specifications See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	Required, both ends grounded
Twisted Pair:	-
PELV:	-
Cable composition:	Minimum conductor cross section: Same cross section as power stage supply voltage, see page 109. The conductors must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.
Maximum cable length:	3 m
Special features:	Temperature resistance

The braking resistors recommended in chapter 12 "Accessories and spare parts" have a 3-wire, temperature-resistant cable with a length of 0.75 m to 3 m.

Properties of the connection terminals

LXM32•...		
Connection cross section	[mm ²]	0.75 ... 3.3 (AWG 18 ... AWG 12)
Tightening torque for terminal screws	[Nm]([lb.in])	0.51 (4.5)
Stripping length	[mm]	10 ... 11

The terminals are approved for fine wire conductors and rigid conductors. Observe the maximum permissible connection cross section. Take into account the fact that wire ferrules increase the conductor cross section.



Wire ferrules: If you use wire ferrules, use only wire ferrules with collars for these connection terminals.

Wiring diagram

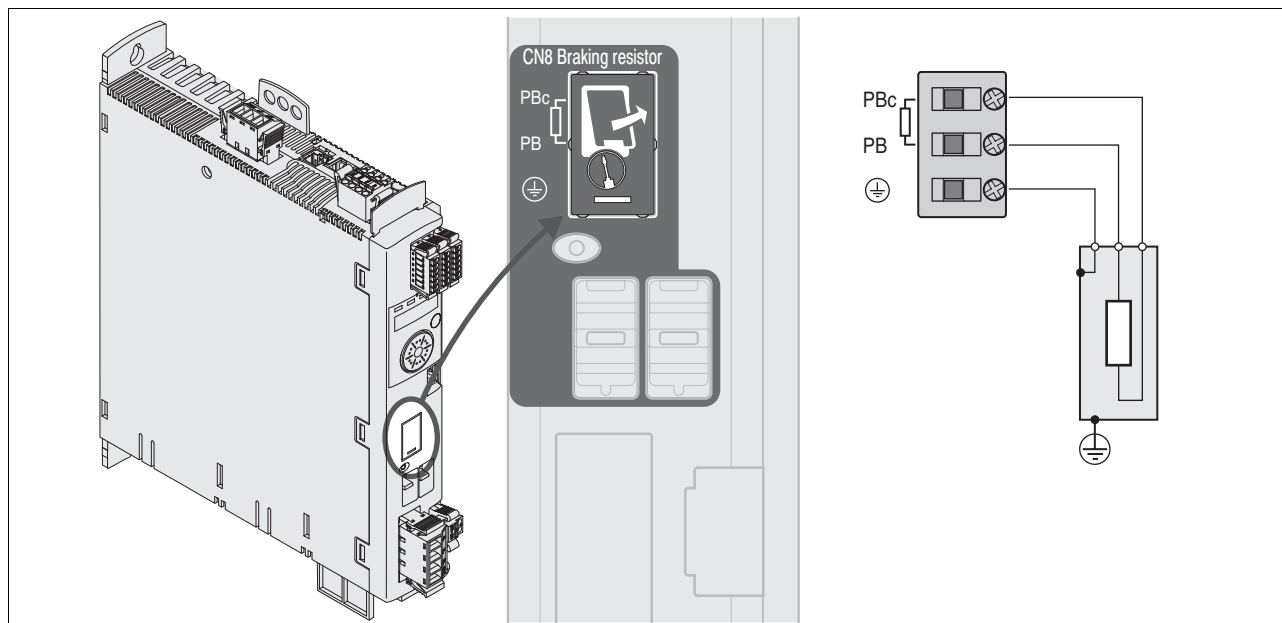


Figure 6.9 Wiring diagram external braking resistor

Connecting the external braking resistor

- ▶ Switch off all supply voltages. Observe the safety instructions concerning electrical installation.
- ▶ Verify that no voltages are present (safety instructions).
- ▶ Remove the cover from the connection.
- ▶ Ground the ground connection (PE) of the braking resistor.
- ▶ Connect the external braking resistor to the device, see Figure 6.9. Note the tightening torque specified for the terminal screws.
- ▶ Connect the cable shield to the shield connection at the bottom of the device (large surface area contact).

The parameter `RESint_ext` is used to switch between the internal and an external braking resistor. The parameter settings for the braking resistor can be found in chapter 7.6.10 "Setting the braking resistor parameters", page 166. Verify that the selected external braking resistor is really connected. Test the function of the braking resistor under realistic conditions during commissioning, see chapter 7.6.10 "Setting the braking resistor parameters", page 166.

6.2.8 Connection of power stage supply voltage (CN1)

⚠ DANGER

ELECTRIC SHOCK CAUSED BY INSUFFICIENT GROUNDING

This drive system has an increased leakage current > 3.5 mA.

- Use a protective ground conductor at with least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals. Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING

INSUFFICIENT PROTECTION AGAINST OVERCURRENTS

- Use the external fuses specified in "Technical data".
- Do not connect the product to a supply mains whose short-circuit current rating (SCCR) exceeds the permissible value specified in the chapter "Technical Data".

Failure to follow these instructions can result in death, serious injury or equipment damage.

CAUTION

DESTRUCTION DUE TO INCORRECT MAINS VOLTAGE

Incorrect mains voltage may destroy the product.

- Before switching on and configuring the product, verify that it is approved for the mains voltage.

Failure to follow these instructions can result in equipment damage.

The products are intended for industrial use and may only be operated with a permanently installed connection.

Prior to connecting the device, check the approved mains types, see chapter 3.3.1 "Power stage", page 25.

Cable specifications

Verify the suitability of the cables, see page 62, and the EMC-compliant connection, see page 58.

Shield:	-
Twisted Pair:	-
PELV:	-
Cable composition:	The conductors must have a sufficiently large cross section so that the fuse at the mains connection can trip if required.
Maximum cable length:	-
Special features:	-

*Properties of connection terminals
CN1*

LXM32•U45••, LXM32•U60••, LXM32•U90••, LXM32•D12••, LXM32•D18••, LXM32•D30••		
Connection cross section	[mm ²]	0.75 ... 5.3 (AWG 18 ... AWG 10)
Tightening torque for terminal screws	[Nm] ([lb.in])	0.68 (6.0)
Stripping length	[mm]	6 ... 7

LXM32•D72N4		
Connection cross section	[mm ²]	0.75 ... 10 (AWG 18 ... AWG 8)
Tightening torque for terminal screws	[Nm] ([lb.in])	1.81 (16.0)
Stripping length	[mm]	8 ... 9

The terminals are approved for fine wire conductors and rigid conductors. Observe the maximum permissible connection cross section. Take into account the fact that wire ferrules increase the conductor cross section. Carefully insert the conductors for maximum current capacity and vibration resistance.

*Prerequisites for connecting the
power stage supply voltage*

Note the following information:

- Three-phase devices may only be connected and operated via three phases.
- Use upstream mains fuses. See chapter 3.3.1 "Power stage", page 25 for recommended ratings and fuse types.
- Observe the EMC requirements. If necessary, use surge arresters, mains filters and mains reactors, see page 67.
- If you use an external mains filter, the mains cable must be shielded and grounded at both ends if the length between the external mains filter and the device exceeds 200 mm.
- See page 21 for a UL-compliant design.
- Due to high leakage currents, use a protective ground conductor at with least 10 mm² (AWG 6) or two protective ground conductors with the cross section of the conductors supplying the power terminals. Verify compliance with all local and national electrical code requirements as well as all other applicable regulations with respect to grounding of all equipment.

Accessories: Mains reactor and external mains filter

Note the information on the following accessories: mains reactor and external mains filter.

Further information on the subject	Page
Technical data mains reactor (accessory)	50
Engineering information mains reactor (accessory)	67
Mounting the mains reactor (accessory)	92
Order data mains reactor (accessory)	528

Further information on the subject	Page
Technical data external mains filters (accessory)	49
Engineering information external mains filters (accessory)	67
Mounting the external mains filter (accessory)	92
Order data external mains filters (accessory)	528

Connecting a single-phase device

Figure 6.10 shows an overview for the connection of the power stage supply voltage for a single-phase device. The figure also shows the wiring of an external mains filter and a mains reactor which are available as accessories.

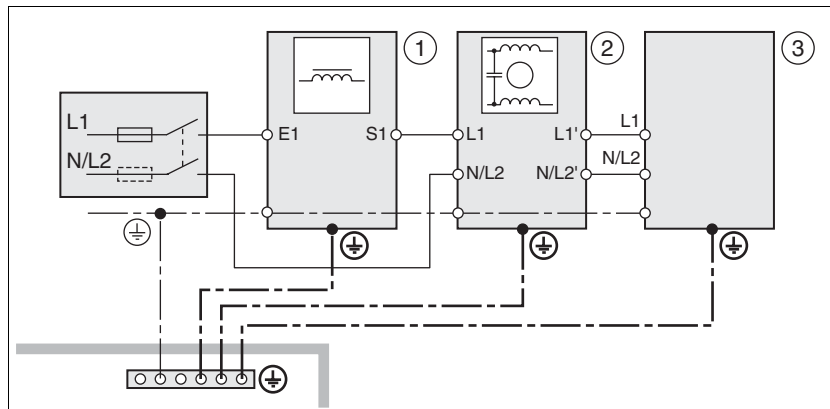


Figure 6.10 Overview power stage supply voltage for single-phase device

- (1) Mains reactor (accessory)
- (2) External mains filter (accessory)
- (3) Drives

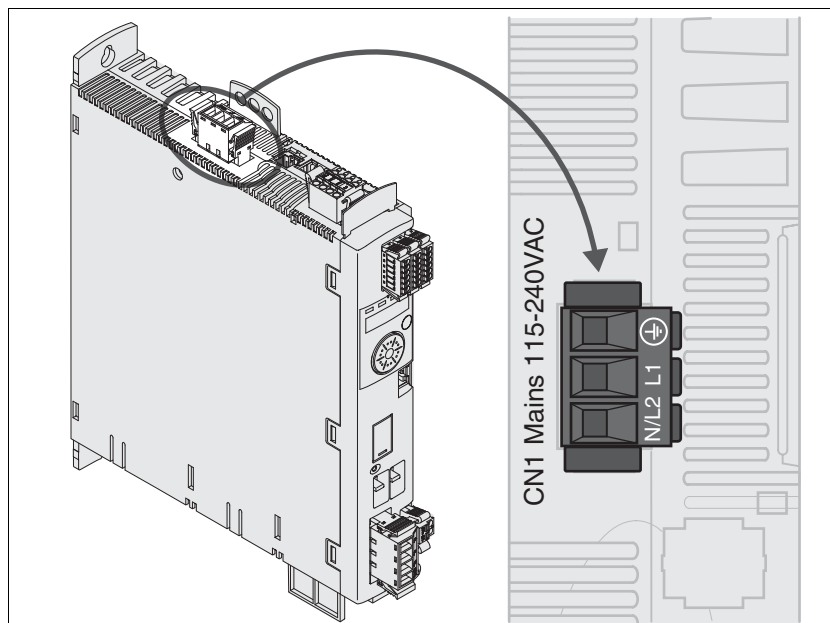


Figure 6.11 Wiring diagram power stage supply voltage for single-phase device.

- Verify the type of mains. See chapter , page for the approved mains types.
- Connect the mains cable (Figure 6.11). Note the tightening torque specified for the terminal screws.
- Verify that the connector locks snap in properly at the housing.

Connecting a three-phase device

Figure 6.12 shows an overview for the connection of the power stage supply voltage for a three-phase device. The figure also shows the wiring of an external mains filter and a mains reactor which are available as accessories.

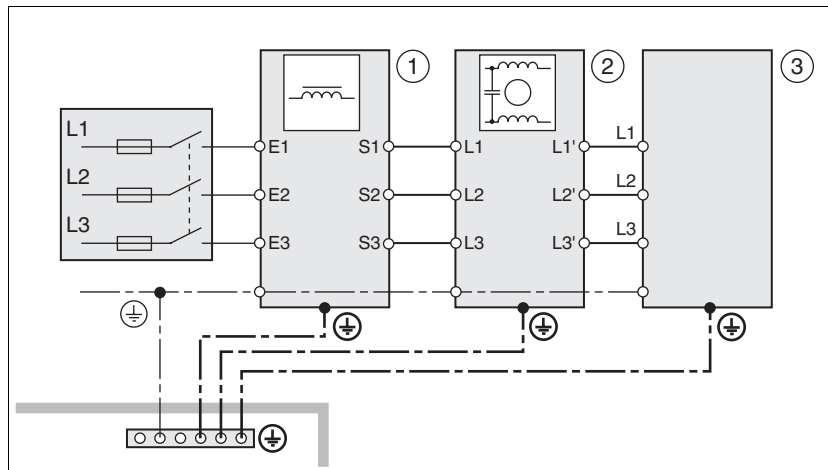


Figure 6.12 Wiring diagram, power stage supply voltage for three-phase device

- (1) Mains reactor (accessory)
- (2) External mains filter (accessory)
- (3) Drives

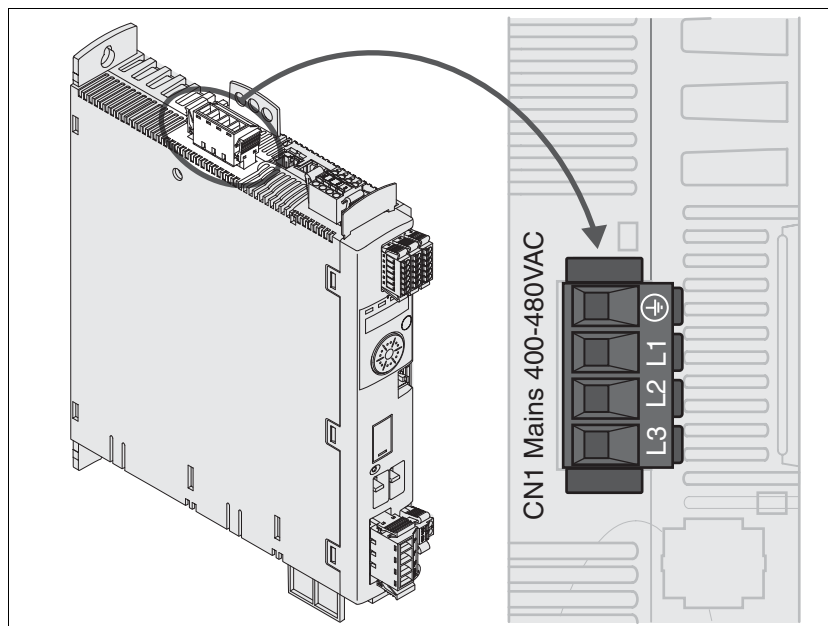


Figure 6.13 Wiring diagram power stage supply voltage for three-phase device

- Verify the type of mains. See chapter 3.3.1 "Power stage", page 25 for the approved mains types.
- Connect the mains cable (Figure 6.13). Note the tightening torque specified for the terminal screws.
- Verify that the connector locks snap in properly at the housing.

6.2.9 Connecting the motor encoder (CN3)

Function and encoder type The motor encoder is a Hiperface encoder integrated in the motor. It provides the device with information on the motor position (analog and digital).

Note the information on approved motors, see chapter 3.3 "Electrical Data".

Cable specifications See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	Required, both ends grounded
Twisted Pair:	Required
PELV:	Required
Cable composition:	6*0.14 mm ² + 2*0.34 mm ² (6*AWG 24 + 2*AWG 20)
Maximum cable length:	100 m
Special features:	Fieldbus cables are not suitable for connecting encoders.

Wiring diagram

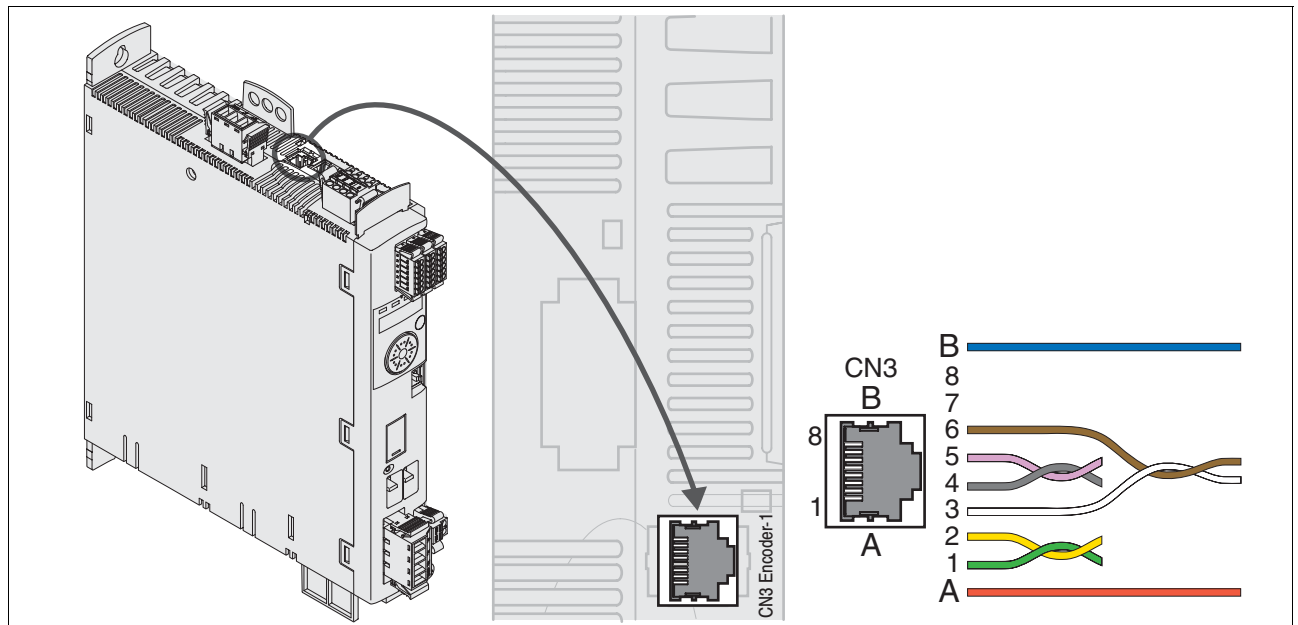


Figure 6.14 Wiring diagram motor encoder

Pin	Signal	Motor, pin	Pair	Meaning	I/O
1	COS+	9	2	Cosine signal	I
2	REFCOS	5	2	Reference for cosine signal	I
3	SIN+	8	3	Sine signal	I
6	REFSIN	4	3	Reference for sine signal	I
4	Data	6	1	Receive data, transmit data	I/O
5	$\overline{\text{Data}}$	7	1	Receive data and transmit data, inverted	I/O
7	reserved		4	Not assigned	
8	reserved		4	Not assigned	
A	ENC+10V_OUT	10	5	Encoder supply	O
B	ENC_0V	11	5	Reference potential for encoder supply	
	SHLD			Shield	

Connecting the motor encoder

- Verify that wiring, cables and connected interface meet the PELV requirements.
- Note the EMC requirements for encoder cables, page 58. Use equipotential bonding conductors for equipotential bonding.
- Connect the connector to CN3, Encoder -1.
- Verify that the connector locks snap in properly at the housing.



Route the cables from the motor and the encoder to the device (start at the motor). Due to the pre-assembled connectors, this direction is often faster and easier.

6.2.10 Connection PTO (CN4, Pulse Train Out)

5 V signals are available at the PTO (Pulse Train Out, CN4) output. Depending on parameter `PTO_mode`, these signals are ESIM signals (encoder simulation) or logically fed through PTI input signals (P/D signals, A/B signals, CW/CCW signals). The PTO output signals can be used as PTI input signals for another device. The signal level corresponds to RS422, see chapter 3.3.3.1 "Output PTO (CN4)", page 37. The PTO output supplies 5 V signals, even if the PTI input signal is a 24 V signal.

Cable specifications See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	Required, both ends grounded
Twisted Pair:	Required
PELV:	Required
Cable composition:	8*0.14 mm ² (8*AWG 24)
Maximum cable length:	100 m
Special features:	-

- Use equipotential bonding conductors, see page .
- Use pre-assembled cables (page) to reduce the risk of wiring errors.

Wiring diagram

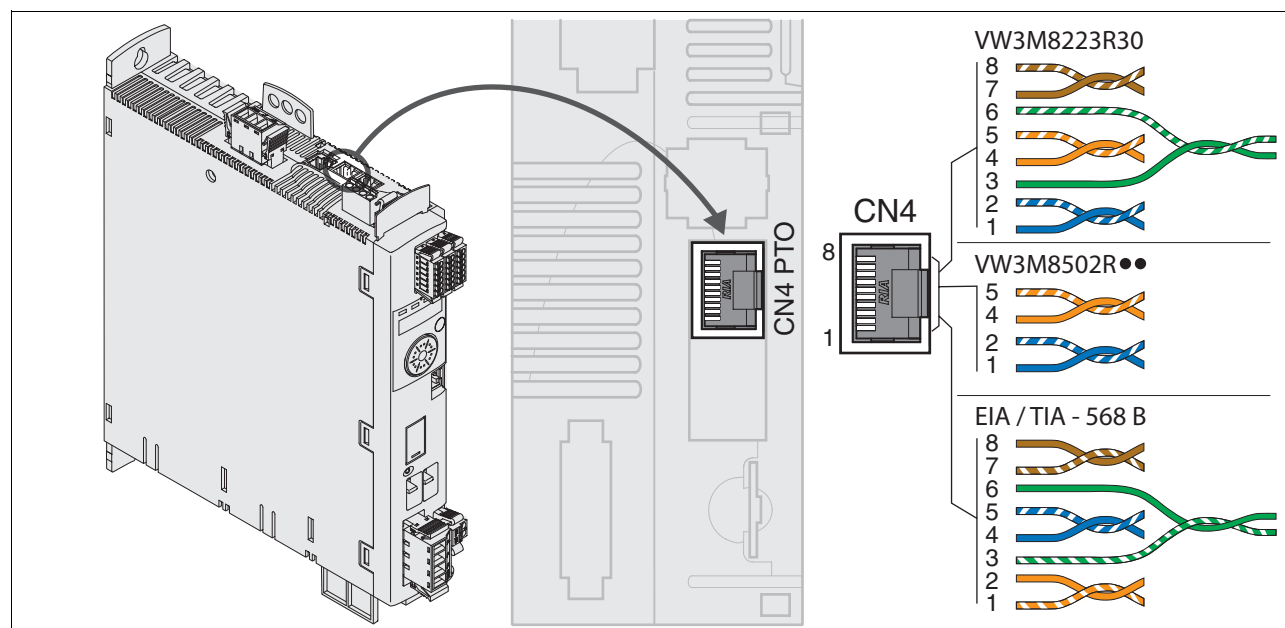


Figure 6.15 Wiring diagram Pulse Train Out (PTO)

PTO: ESIM signals

Pin	Signal	Pair	Meaning	I/O
1	ESIM_A	2	ESIM channel A	O (5 V)
2	$\overline{\text{ESIM_A}}$	2	ESIM channel A, inverted	O (5 V)
4	ESIM_B	1	ESIM channel B	O (5 V)
5	$\overline{\text{ESIM_B}}$	1	ESIM channel B, inverted	O (5 V)
3	ESIM_I	3	ESIM index pulse	O (5 V)
6	$\overline{\text{ESIM_I}}$	3	ESIM index pulse, inverted	O (5 V)
7		4	Reference potential	
8		4	Reference potential	

*PTO: logically fed through signals
PTI signals*

At the PTO output, the PTI input signals can be made available again to control a subsequent device (daisy chain). Depending on the input signal, the output signal can be of type P/D signal, A/B signal or CW/CCW signal. The PTO output supplies 5 V signals.

Pin	P/D signal ¹⁾	A/B signal ²⁾	CW/CCW signal ³⁾	Pair	Meaning	I/O
1	PULSE (5)	ENC_A (5)	CW (5)	2	See PTI connection, pin 1	O (5 V)
2	$\overline{\text{PULSE}}$	$\overline{\text{ENC_A}}$	$\overline{\text{CW}}$	2	See PTI connection, pin 2	O (5 V)
4	DIR (5)	ENC_B (5)	CCW (5)	1	See PTI connection, pin 4	O (5 V)
5	$\overline{\text{DIR}}$	$\overline{\text{ENC_B}}$	$\overline{\text{CCW}}$	1	See PTI connection, pin 5	O (5 V)

1) See page 119

2) See page 119

3) See page 119

Connecting PTO

- Connect the connector to CN4. If you do not use a pre-assembled cable, verify correct pin assignment.
- Verify that the connector locks snap in properly at the housing.

6.2.11 Connection PTI (CN5, Pulse Train In)

P/D (pulse/direction), A/B signals or CW/CCW signals can be connected to the PTI connection (Pulse Train In, CN5).

It is possible to connect 5 V signals or 24 V signals, see chapter 3.3.3.2 "Input PTI (CN5)", page 38. Pin assignments and cables are different.

▲ WARNING

UNEXPECTED MOVEMENT

Incorrect or interfered signals as reference values can cause unexpected movements.

- Use shielded twisted-pair cables.
- If possible, operate the interface with push-pull signals.
- Do not use signals without push-pull in critical applications or in environments subject to interference.
- Do not use signals without push-pull in the case of cable lengths of more than 3 m and limit the frequency to 50 kHz

Failure to follow these instructions can result in death, serious injury or equipment damage.

Cable specifications PTI

See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	Required, both ends grounded
Twisted Pair:	Required
PELV:	Required
Minimum conductor cross section:	0.14 mm ² (AWG 24)
Maximum cable length:	100 m with RS422 10 m with push-pull 1 m with open collector
Special features:	-

- Use equipotential bonding conductors, see page 62.
- Use pre-assembled cables (page 526) to reduce the risk of wiring errors.

6.2.11.1 Connection assignment PTI 5 V

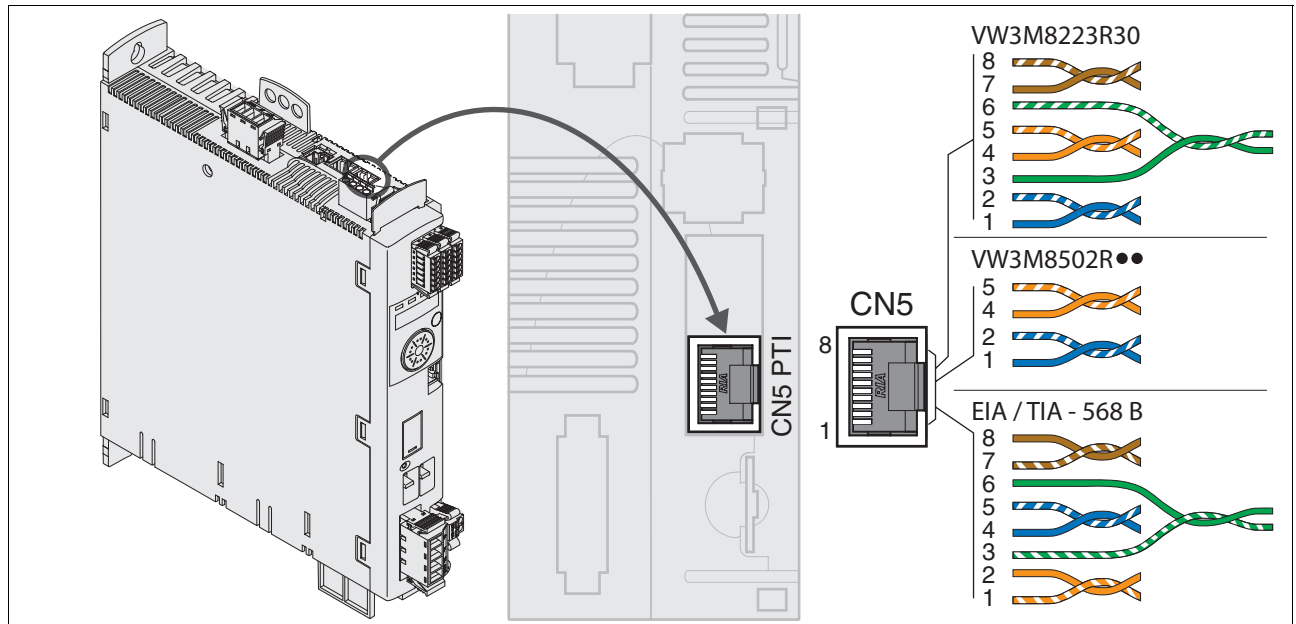


Figure 6.16 Wiring diagram Pulse Train In (PTI) 5 V

P/D signals 5 V

Pin	Signal	Pair	Meaning	I/O
1	PULSE (5)	2	Pulse 5V	I (5 V)
2	$\overline{\text{PULSE}}$	2	Pulse, inverted	I (5 V)
4	DIR (5)	1	Direction 5V	I (5 V)
5	$\overline{\text{DIR}}$	1	Direction, inverted	I (5 V)

A/B signals 5 V

Pin	Signal	Pair	Meaning	I/O
1	ENC_A (5)	2	Encoder channel A 5V	I (5 V)
2	$\overline{\text{ENC_A}}$	2	Encoder channel A, inverted	I (5 V)
4	ENC_B (5)	1	Encoder channel B 5V	I (5 V)
5	$\overline{\text{ENC_B}}$	1	Encoder channel B, inverted	I (5 V)

CW/CCW signals 5 V

Pin	Signal	Pair	Meaning	I/O
1	CW (5)	2	Pulse positive 5V	I (5 V)
2	$\overline{\text{CW}}$	2	Pulse positive, inverted	I (5 V)
4	CCW (5)	1	Pulse negative 5V	I (5 V)
5	$\overline{\text{CCW}}$	1	Pulse negative, inverted	I (5 V)

Connecting Pulse Train IN (PTI) 5 V

- Connect the connector to CN5. If you do not use a pre-assembled cable, verify correct pin assignment.
- Verify that the connector locks snap in properly at the housing.

6.2.11.2 Connection assignment PTI 24 V

Note that the wire pairs for 24 V signals require assignments different from those for 5 V signals. Use a cable that complies with the cable specifications and assemble it as shown below.

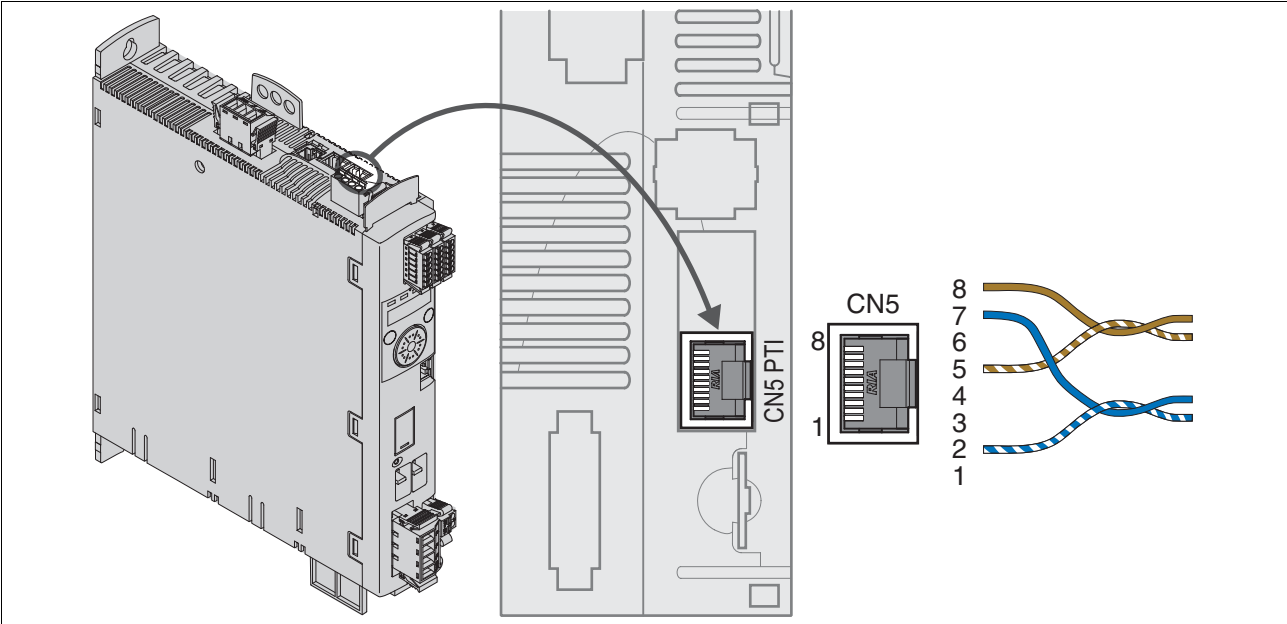


Figure 6.17 Wiring diagram Pulse Train In (PTI) 24 V

P/D signals 24 V

Pin	Signal	Pair	Meaning	I/O
7	PULSE (24)	A	Pulse 24V	I (24 V)
2	$\overline{\text{PULSE}}$	A	Pulse, inverted	I (24 V)
8	DIR (24)	B	Direction 24V	I (24 V)
5	$\overline{\text{DIR}}$	B	Direction, inverted	I (24 V)

A/B signals 24 V

Pin	Signal	Pair	Meaning	I/O
7	ENC_A (24)	A	Encoder channel A 24V	I (24 V)
2	$\overline{\text{ENC_A}}$	A	Encoder channel A, inverted	I (24 V)
8	ENC_B (24)	B	Encoder channel B 24V	I (24 V)
5	$\overline{\text{ENC_B}}$	B	Encoder channel B, inverted	I (24 V)

CW/CCW signals 24 V

Pin	Signal	Pair	Meaning	I/O
7	CW (24)	A	Pulse positive 24V	I (24 V)
2	$\overline{\text{CW}}$	A	Pulse positive, inverted	I (24 V)
8	CCW (24)	B	Pulse negative 24V	I (24 V)
5	$\overline{\text{CCW}}$	B	Pulse negative, inverted	I (24 V)

Connecting Pulse Train In (PTI)
24 V

- Connect the connector to CN5. Verify correct pin assignment and correct pairing.
- Verify that the connector locks snap in properly at the housing.

6.2.12 Connection the controller supply voltage and STO (CN2, DC Supply and STO)

⚠ DANGER

ELECTRIC SHOCK CAUSED BY INCORRECT POWER SUPPLY UNIT

The +24VDC supply voltage is connected with many exposed signal connections in the drive system.

- Use a power supply unit that meets the PELV (Protective Extra Low Voltage) requirements.
- Connect the negative output of the power supply unit to PE (ground).

Failure to follow these instructions will result in death or serious injury.

CAUTION

DAMAGE TO CONTACTS

The connection for the controller supply voltage at the product does not have an inrush current limitation. If the voltage is switched on by means of switching of contacts, damage to the contacts or contact welding may result.

- Use a power supply unit that limits the peak value of the output current to a value permissible for the contact.
- Switch the power input of the power supply unit instead of the output voltage.

Failure to follow these instructions can result in equipment damage.

Safety function STO

⚠ WARNING

LOSS OF SAFETY FUNCTION

Incorrect usage may cause a hazard due to the loss of the safety function.

- Observe the requirements for using the safety function.

Failure to follow these instructions can result in death or serious injury.

Information on the signals of the STO safety function can be found in chapter 5.9 "Safety function STO ("Safe Torque Off")". If the safety function is NOT required, the inputs `STO_A` and `STO_B` must be connected to +24VDC.

Cable specifications CN2 See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	- 1)
Twisted Pair:	-
PELV:	Required
Minimum conductor cross section:	0.75 mm ² (AWG 18)
Maximum cable length:	100 m
Special features:	-

1) See 5.9.3 "Requirements for using the safety function"

Properties of spring terminal CN2

LXM32•...		
Maximum terminal current	[A]	16 1)
Connection cross section	[mm ²]	0.5 ... 2.5 (AWG 20 ... AWG 14)
Stripping length	[mm]	12 ... 13

1) Note the maximum permissible terminal current when connecting several devices.

The terminals are approved for fine wire conductors and rigid conductors. Observe the maximum permissible connection cross section. Take into account the fact that wire ferrules increase the conductor cross section. Carefully insert the conductors for maximum current capacity and vibration resistance.

Permissible terminal current of controller supply voltage

- Connection CN2, pins 3 and 7 as well as CN2, pins 4 and 8 (see Figure 6.18) can be used as 24V/0V connections for additional consumers.¹ Note the maximum permissible terminal current ("Properties of spring terminal CN2").
- The voltage at the holding brake output depends on the controller supply voltage. Note that the current of the holding brake also flows via this terminal.
- As long as the controller supply voltage is switched on, the position of the motor will remain the same, even if the power stage supply voltage is switched off.

1. In the connector, the following pins are connected: pin 1 to pin 5, pin 2 to pin 6, pin 3 to pin 7 and pin 4 to pin 8.

Wiring diagram

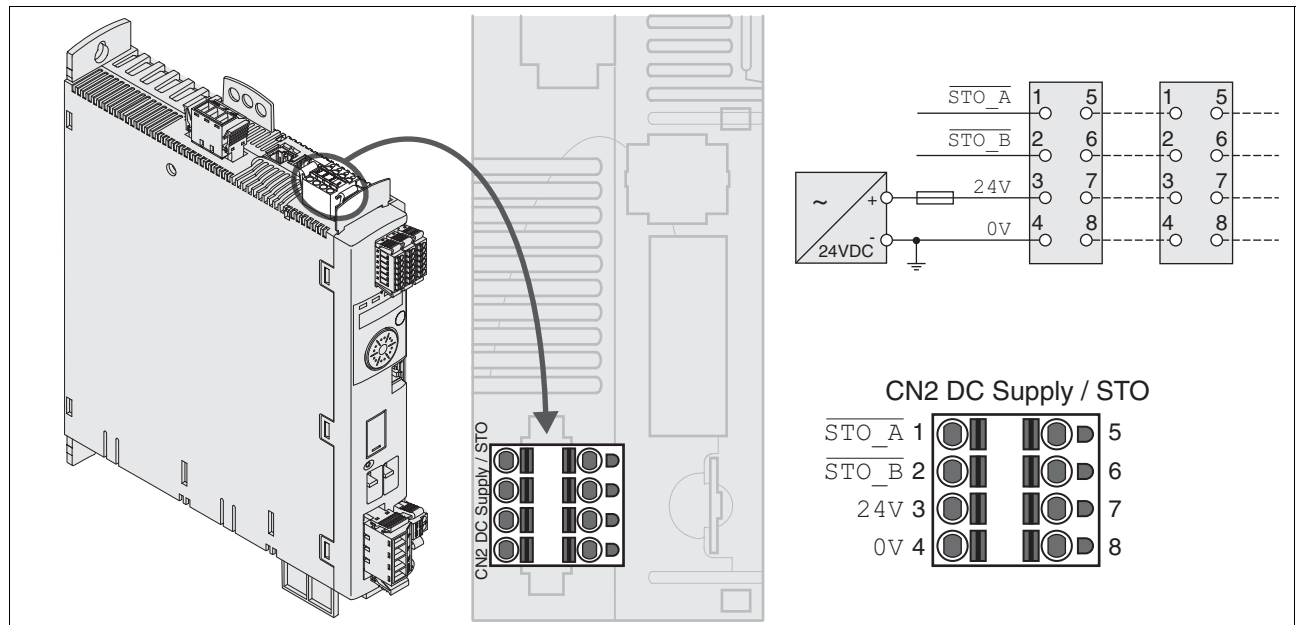


Figure 6.18 Wiring diagram controller supply voltage

Pin	Signal	Meaning
1, 5	$\overline{\text{STO_A}}$	Safety function STO: Dual-channel connection, connection A
2, 6	$\overline{\text{STO_B}}$	Safety function STO: Dual-channel connection, connection B
3, 7	+24 VDC	24 V controller supply voltage
4, 8	0VDC	Reference potential for 24 V controller supply voltage; Reference potential for STO

Connecting the safety function STO

- ▶ Verify that wiring, cables and connected interfaces meet the PELV requirements.
- ▶ Connect the safety function in accordance with the specifications in chapter 5.9 "Safety function STO ("Safe Torque Off")", page 75.

Connecting the controller supply voltage

- ▶ Verify that wiring, cables and connected interfaces meet the PELV requirements.
- ▶ Route the controller supply voltage from a power supply unit (PELV) to the device.
- ▶ Ground the negative output at the power supply unit.
- ▶ Note the maximum permissible terminal current when connecting several devices.
- ▶ Verify that the connector locks snap in properly at the housing.

6.2.13 Connecting the digital inputs/outputs (CN6)

The device has configurable inputs and configurable outputs. The standard assignment and the configurable assignment depends on the selected operating mode. For more information, see chapter 8.5.3 "Setting the digital signal inputs and signal outputs".

Cable specifications See chapter for information on the cables.

Shield:	-
Twisted Pair:	-
PELV:	Required
Cable composition:	0.25 mm ² , (AWG 22)
Maximum cable length:	30 m
Special features:	

Properties of spring terminal CN6

LXM32•...		
Connection cross section	[mm ²]	0.2 ... 1.0 (AWG 24 ... AWG 16)
Stripping length	[mm]	10

Wiring diagram

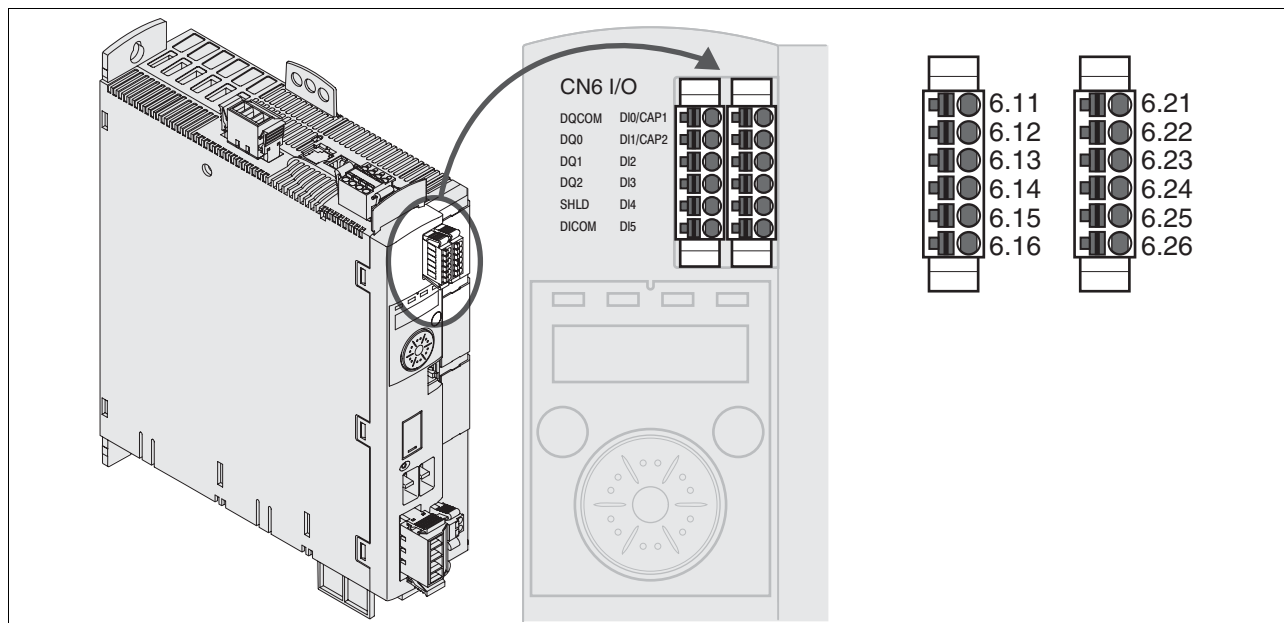


Figure 6.19 Wiring diagram, digital inputs/outputs

Pin	Signal	1)	Meaning	I/O
CN6.11	DQ_COM		Reference potential digital outputs	
CN6.12	DQ0		Digital output 0	O (24 V)
CN6.13	DQ1	X	Digital output 1	O (24 V)
CN6.14	DQ2		Digital output 2	O (24 V)
CN6.15	SHLD		Shield connection	
CN6.16	DI_COM		Reference potential digital inputs	

1) Connector coding, X=coding

Pin	Signal	1)	Meaning	I/O
CN6.21	DI0 / CAP1		Digital input 0 / Capture input 1	I (24 V)
CN6.22	DI1 / CAP2	X	Digital input 1 / Capture input 2	I (24 V)
CN6.23	DI2		Digital input 2	I (24 V)
CN6.24	DI3		Digital input 3	I (24 V)
CN6.25	DI4		Digital input 4	I (24 V)
CN6.26	DI5		Digital input 5	I (24 V)
	DI_COM		Reference potential digital inputs: CN6.16	

1) Connector coding, X=coding



The connectors are coded. Verify correct assignment when connecting them.

The configuration and the standard assignment of the inputs and outputs are described in chapter .

Connecting the digital inputs/outputs

- ▶ Wire the digital connections to CN6.
- ▶ Ground the shield to pin 6.15.
- ▶ Verify that the connector locks snap in properly at the housing.

6.2.14 Connection of PC with commissioning software CN7)

CAUTION

DAMAGE TO PC

If this commissioning interface at the product is directly connected to a Gigabit Ethernet interface at the PC, the PC interface may be destroyed.

- Never directly connect an Ethernet interface to the commissioning interface of this product.

Failure to follow these instructions can result in equipment damage.

Cable specifications

See chapter 5.2 "Cables", page 62 for information on the cables.

Shield:	Required, both ends grounded
Twisted Pair:	Required
PELV:	Required
Cable composition:	8*0.25 mm ² , (8*AWG 22)
Maximum cable length:	100 m
Special features:	-

Connecting a PC

A PC with commissioning software can be connected for commissioning. The PC is connected via a bidirectional USB/RS485 converter, see chapter Accessories, page 519.

Wiring diagram

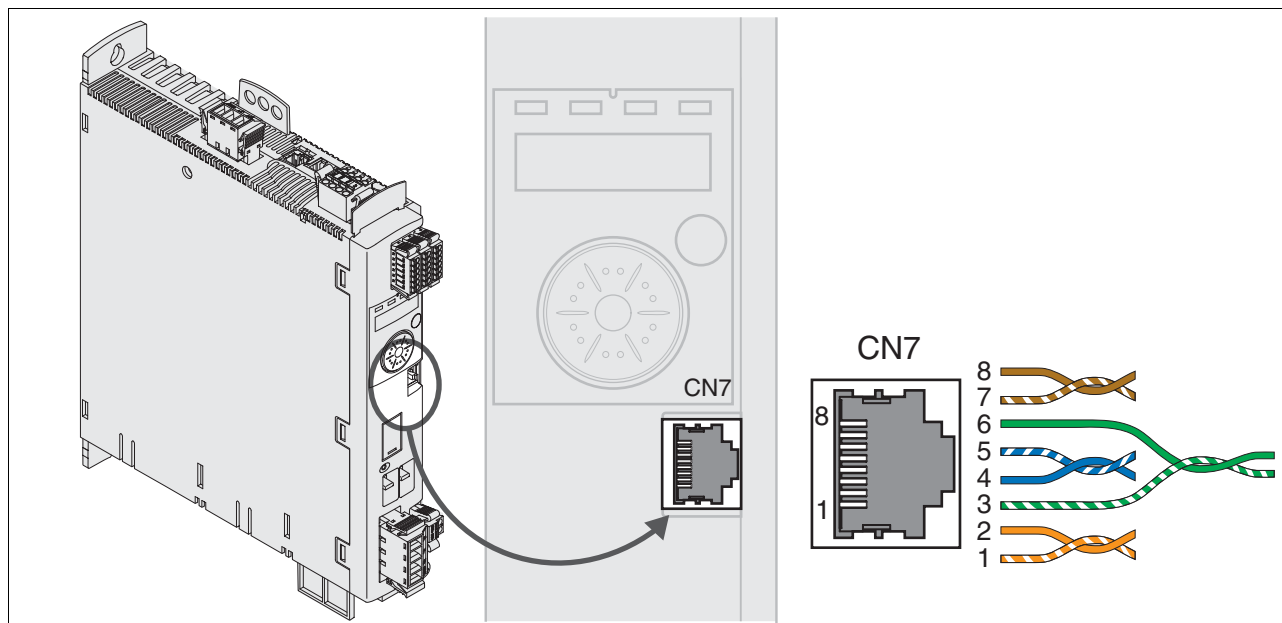


Figure 6.20 Wiring diagram PC with commissioning software

Pin	Signal	Meaning	I/O
1	reserved	Reserved	-
2	reserved	Reserved	-
3	reserved	Reserved	-
6	reserved	Reserved	-
4	MOD_D1	Bidirectional transmit/receive signal	RS485 level
5	MOD_D0	Bidirectional transmit/receive signal, inverted	RS485 level
7	MOD+10V_OUT	10 V power supply, max. 100 mA	O
8	MOD_0V	Reference potential to MOD+10V_OUT	

- Verify that the connector locks snap in properly at the housing.

6.2.15 Modules

The mechanical installation of modules is described in chapter 6.1.1 "Installing and removing modules" on page 87.

The electrical installation of the module is described in the corresponding manual for the module.

6.3 Checking installation

Verify proper installation:

- ▶ Check the mechanical installation of the entire drive system:
 - Does the installation meet the specified distance requirements?
 - Did you tighten all fastening screws with the specified tightening torque?
- ▶ Check the electrical connections and the cabling:
 - Did you connect all protective ground conductors?
 - Do all fuses have the correct rating; are the fuses of the specified type?
 - Did you connect both ends of all live cables or insulate them (no exposed cable ends)?
 - Did you properly connect and install all cables and connectors?
 - Are the mechanical locks of the connectors correct and effective?
 - Did you properly connect the signal wires?
 - Are the required shield connections EMC-compliant?
 - Did you take all measures for EMC compliance?
- ▶ Verify that all covers and seals of the control cabinet are properly installed to meet the required degree of protection.

7 Commissioning

7

This chapter describes how to commission the product.

7.1 Basic information



An alphabetically sorted overview of the parameters can be found in the chapter "Parameters". The use and the function of some parameters are explained in more detail in this chapter.

⚠ DANGER

ELECTRIC SHOCK CAUSED BY INCORRECT USE

The safety function STO (Safe Torque Off) does not cause electric isolation. The DC bus voltage is still present.

- Turn off the mains voltage using an appropriate switch to achieve a voltage-free condition.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING

UNINTENDED BEHAVIOR

The behavior of the drive system is governed by numerous stored data or settings. Unsuitable settings or data may trigger unexpected movements or responses to signals and disable monitoring functions.

- Do NOT operate the drive system with unknown settings or data.
- Verify that the stored data and settings are correct.
- When commissioning, carefully run tests for all operating states and potential error situations.
- Verify the functions after replacing the product and also after making changes to the settings or data.
- Only start the system if there are no persons or obstructions in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.

⚠ WARNING**MOTOR WITHOUT BRAKING EFFECT**

If power outage, functions or errors cause the power stage to be switched off, the motor is no longer decelerated in a controlled way and may cause damage.

- Verify the mechanical situation.
- If necessary, use a cushioned mechanical stop or a suitable holding brake.

Failure to follow these instructions can result in death, serious injury or equipment damage.

⚠ WARNING**UNEXPECTED MOVEMENT**

When the drive is operated for the first time, there is a risk of unexpected movements caused by possible wiring errors or unsuitable parameters.

- Run initial tests without coupled loads.
- Verify that a functioning button for emergency stop is within reach.
- Anticipate movements in the incorrect direction or oscillation of the drive.
- Only start the system if there are no persons or obstructions in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.

⚠ WARNING**HOT SURFACES**

The heat sink at the product may heat up to over 100°C (212°F) during operation.

- Avoid contact with the hot heat sink.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity.
- Consider the measures for heat dissipation described.

Failure to follow these instructions can result in death or serious injury.

7.2 Overview

7.2.1 Commissioning steps

You must also re-commission an already configured device if you want to use it under changed operating conditions.

To be done

6.3 "Checking installation"
7.6 "Commissioning procedure"
7.6.1 ""First Setup""
7.6.2 "Operating state (state diagram)"
7.6.3 "Setting basic parameters and limit values"
7.6.4 "Digital inputs / outputs"
7.6.5 "Testing the signals of the limit switches"
7.6.6 "Testing the safety function STO"
7.6.7 "Holding brake"
7.6.8 "Checking the direction of movement"
7.6.9 "Setting parameters for encoder"
7.6.10 "Setting the braking resistor parameters"
7.6.11 "Autotuning the device"
7.6.12 "Enhanced settings for autotuning"

7.2.2 Commissioning tools

Overview The following tools can be used for commissioning, parameterization and diagnostics:

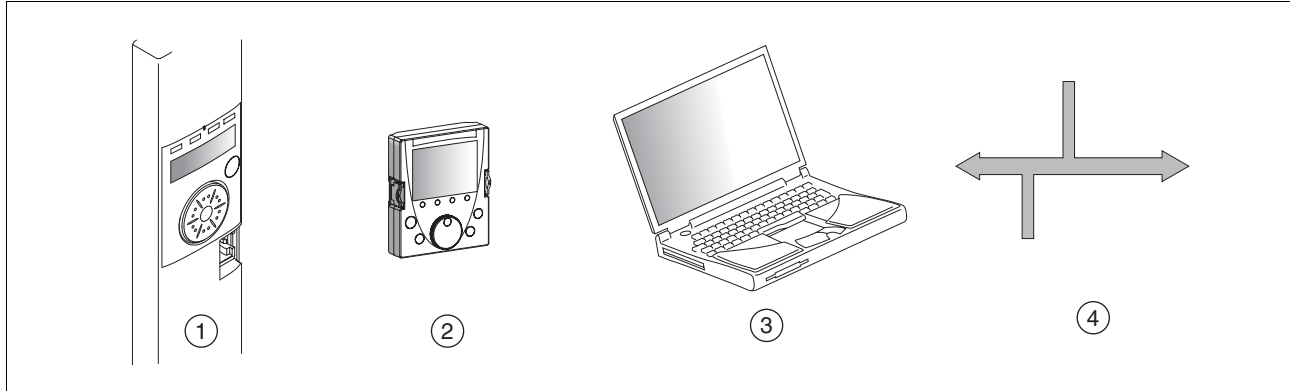


Figure 7.1 Commissioning tools

- (1) Integrated HMI
- (2) External graphic display terminal
- (3) PC with commissioning software
- (4) Fieldbus



Access to all parameters is only possible with the commissioning software or via the fieldbus.

Device settings can be duplicated. Stored device settings can be transferred to a device of the same type. Duplicating the device settings can be used if multiple devices are to have the same settings, for example, when devices are replaced.

7.3 Integrated HMI

The device allows you to edit parameters, start the operating mode Jog or perform autotuning via the integrated Human-Machine Interface (HMI). Diagnostics information (such as parameter values or error numbers) can also be displayed.

The individual sections on commissioning and operation include information on whether a function can be carried out via the integrated HMI or whether the commissioning software must be used.

Overview

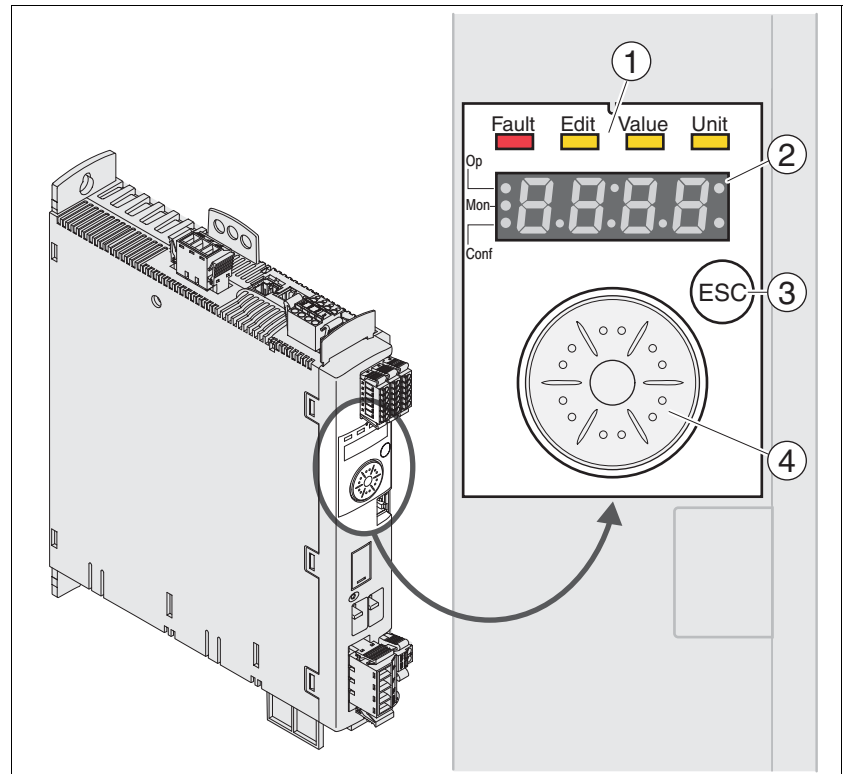


Figure 7.2 Controls at the integrated HMI

- (1) Status LEDs
- (2) 7-segment display
- (3) ESC key
- (4) Navigation button

7.3.1 Indication and operation

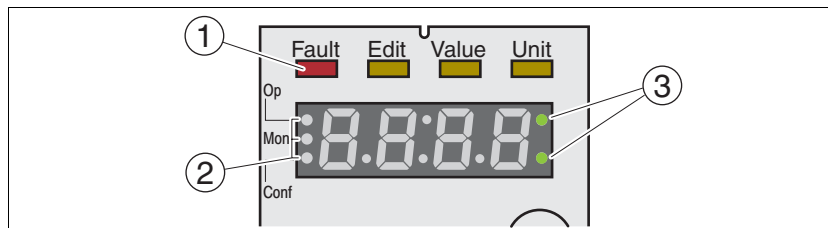
Overview Status LEDs and a 4-digit 7-segment display indicate the device status, menu designation, parameter codes, status codes and error numbers. By turning the navigation button, you can select menu levels and parameters and increment or decrement values. To confirm a selection, press the navigation button.

The ESC (Escape) button allows you to exit parameters and menus. If values are displayed, the ESC button lets you return to the last saved value.

Character set on the HMI The following table shows the assignment of the characters to the symbols displayed by the 4-digit 7-segment display.

A	B	C	D	E	F	G	H	I	J	K	L	M	N	O	P	Q	R
R	b	c	d	E	F	G	h	i	j	K	L	M	n	o	P	q	r
S	T	U	V	W	X	Y	Z	1	2	3	4	5	6	7	8	9	0
S	t	u	v	w	x	y	z	1	2	3	4	5	6	7	8	9	0
!	?	%	()	+	-	_	<	=	>	"	'	^	/	\	°	μ
°	°	'	[]	+	-	_	<	=	>	"	'	^	/	\	°	μ

Indication of the device status



(1) Four status LEDs are located above the 7-segment display:

Fault	Edit	Value	Unit	Meaning
Lights, red				Operating state Fault
	Lights yellow	Lights yellow		Parameter value can be edited
		Lights yellow		Value of the parameter
			Lights yellow	Unit of the selected parameter

(2) Three status LEDs for identification of the menu levels:

LED	Meaning
Op	Operation
Mon	Monitoring
Conf	Configuration

(3) Flashing dots indicate a warning, for example, if a limit value has been exceeded.

Navigation button The navigation button can be turned and pressed. There are two types of pressing: short pressing (≤ 1 s) and long pressing (≥ 3 s).

Turn the navigation button to do the following:

- Go to the next or previous menu
- Go to the next or previous parameter
- Increment or decrement values

Briefly **press** the navigation button to do the following:

- Call the selected menu
- Call the selected parameter
- Save the current value to the EEPROM

Hold down the navigation button to do the following:

- Display a description of the selected parameter
- Display the unit of the selected parameter

Access channels The product can be addressed via different access channels. See chapter 8.1 "Access channels" for additional information.

7.3.2 Menu structure

Overview The integrated HMI is menu-driven. The following illustration shows the top level of the menu structure.

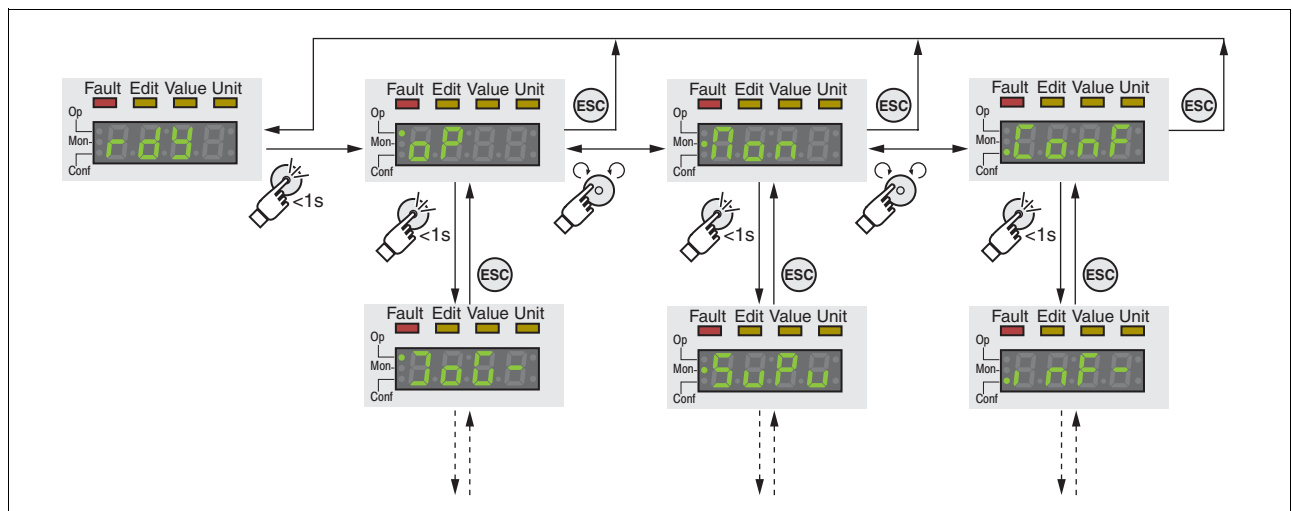
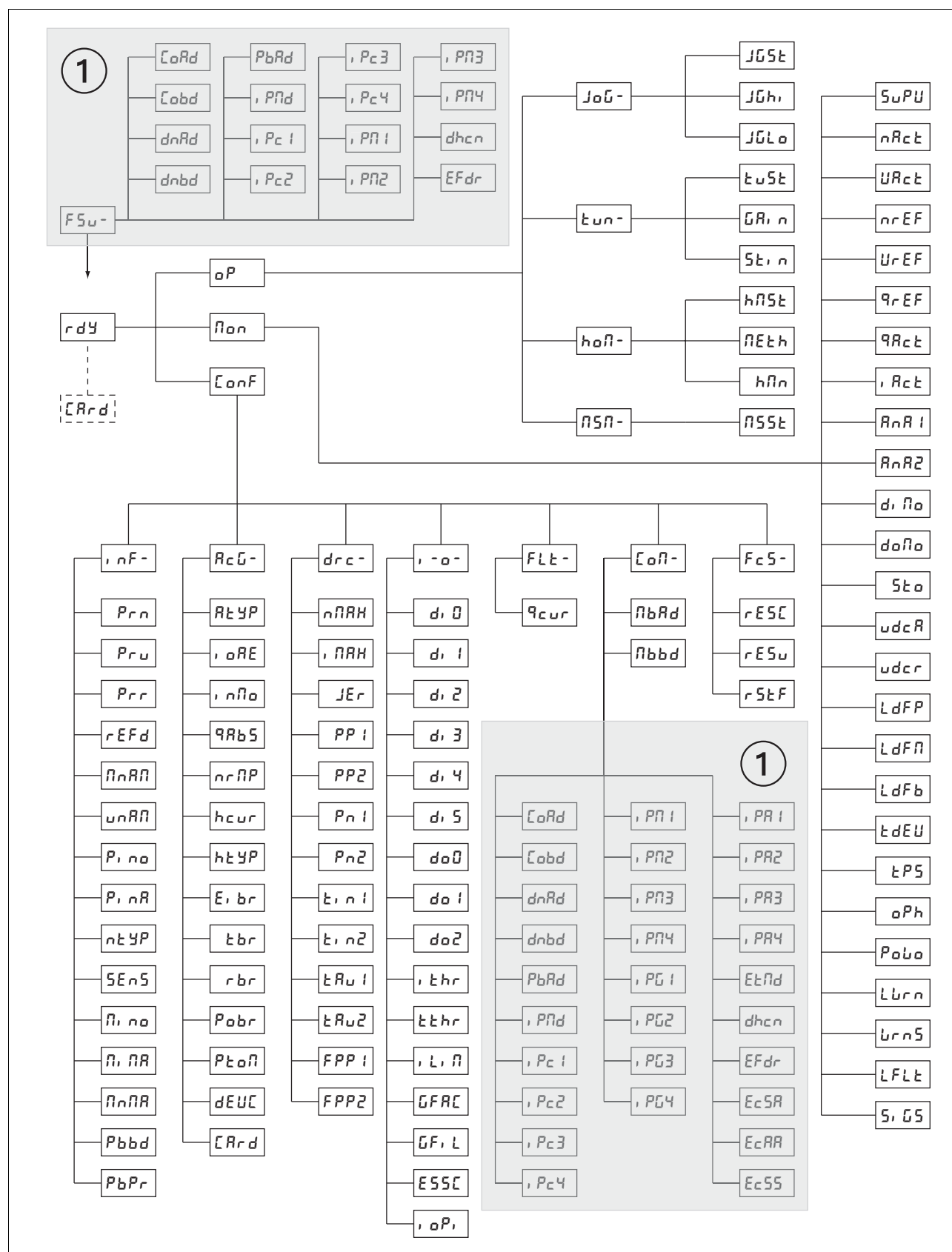


Figure 7.3 HMI menu structure

The level below the top level contains the parameters belonging to the respective menu items. To facilitate access, the parameter tables also specify the menu path, for example $oP \rightarrow Jog-$.



HMI menu <i>F5u-</i>	Description
<i>F5u-</i>	First setup (F irst S etup)
<i>CanAd</i>	CANopen address (node address)
<i>Canbd</i>	CANopen baud rate
<i>dnAd</i>	DeviceNet node address (MAC ID)
<i>dnbd</i>	DeviceNet Baud rate
<i>PbAd</i>	Profibus address
<i>, Pn1</i>	Type of obtaining IP address
<i>, Pc1</i>	IP address Ethernet module, byte 1
<i>, Pc2</i>	IP address Ethernet module, byte 2
<i>, Pc3</i>	IP address Ethernet module, byte 3
<i>, Pc4</i>	IP address Ethernet module, byte 4
<i>, Pn1</i>	IP address subnet mask, byte 1
<i>, Pn2</i>	IP address subnet mask, byte 2
<i>, Pn3</i>	IP address subnet mask, byte 3
<i>, Pn4</i>	IP address subnet mask, byte 4
<i>dhcn</i>	User application name HMI, part 4
<i>EFdr</i>	FDR service

HMI menu <i>oP</i>	Description
<i>oP</i>	Operating mode (O peration)
<i>JoG-</i>	Operating mode Jog
<i>tun-</i>	Autotuning
<i>homi-</i>	Operating mode Homing
<i>nsn-</i>	Operating mode Motion Sequence

HMI menu <i>JoG-</i>	Description
<i>JoG-</i>	Operating mode Jog
<i>JGSt</i>	Start operating mode Jog
<i>JGh_v</i>	Velocity for fast movement
<i>JGL_o</i>	Velocity for slow movement

HMI menu <i>tun-</i>	Description
<i>tun-</i>	Autotuning
<i>tust</i>	Start autotuning
<i>GR_v</i>	Global gain factor (affects parameter set 1)
<i>St_v</i>	Direction of movement for Autotuning

HMI menu <i>homi-</i>	Description
<i>homi-</i>	Operating mode Homing
<i>hns_t</i>	Start operating mode Homing
<i>NEth</i>	Preferred homing method
<i>hvn</i>	Target velocity for searching the switch

HMI menu <i>MSn-</i>	Description
<i>MSn-</i>	Operating mode Motion Sequence
<i>MSSt</i>	Start operating mode Motion Sequence

HMI menu <i>Mon</i>	Description
<i>Mon</i>	Monitoring (M onitoring)
<i>SpU</i>	HMI display when motor moves
<i>nRct</i>	Actual speed of rotation
<i>URct</i>	Actual velocity
<i>nrEF</i>	Reference speed of rotation
<i>UrEF</i>	Reference velocity
<i>qrEF</i>	Reference motor current (q component, generating torque)
<i>qRct</i>	Actual motor current (q component, generating torque)
<i>i Rct</i>	Total motor current
<i>AnR1</i>	Analog 1: Value of input voltage
<i>AnR2</i>	Analog 2: Value of input voltage
<i>di No</i>	Status of digital inputs
<i>doNo</i>	Status of digital outputs
<i>Sto</i>	Status of the inputs for the safety function STO
<i>udcR</i>	Voltage at DC bus
<i>udcr</i>	Degree of utilization of DC bus voltage
<i>LdFP</i>	Current load of power stage
<i>LdFN</i>	Current load of motor
<i>LdFb</i>	Current load on braking resistor
<i>tdEU</i>	Current device temperature
<i>tPS</i>	Current power stage temperature
<i>oPh</i>	Operating hours counter
<i>PolO</i>	Number of power on cycles
<i>Lbrn</i>	Number of last warning (error class 0)
<i>brnS</i>	Saved warnings, bit-coded
<i>LFLt</i>	Error causing a stop (error classes 1 to 4)
<i>Si GS</i>	Saved status of monitoring signals

HMI menu <i>Conf</i>	Description
<i>Conf</i>	Configuration (C onfiguration)
<i>i nF-</i>	Information/Identification (IN formation / Identification)
<i>RcU-</i>	Axis configuration (A xis C onfiguration)
<i>drC-</i>	Device configuration (DR ive C onfiguration)
<i>i -o-</i>	Configurable inputs/outputs (In Out)
<i>FLt-</i>	Error indication
<i>Com-</i>	Communication (COM munication)
<i>FcS-</i>	Restore factory settings (default values) (FACT ory S ettings)

HMI menu <i>i n F -</i>	Description
<i>i n F -</i>	Information/Identification (IN formation / Identification)
<i>P r n</i>	Firmware program number
<i>P r v</i>	Firmware version number
<i>P r r</i>	Firmware revision number
<i>r E F d</i>	Product Name
<i>l n R l</i>	Type
<i>u n R l</i>	User application name
<i>P i n o</i>	Nominal current of power stage
<i>P i n R</i>	Maximum current of power stage
<i>n t y P</i>	Motor type
<i>S E n S</i>	Encoder type of motor
<i>l i n o</i>	Nominal current of motor
<i>l i n R</i>	Maximum current of motor
<i>l n n R</i>	Maximum permissible speed of rotation/velocity of motor
<i>P b b d</i>	Profibus baud rate
<i>P b P r</i>	Profibus drive profile

HMI menu <i>R c G -</i>	Description
<i>R c G -</i>	Axis configuration (Axis Configuration)
<i>R t y P</i>	Activation of Modulo
<i>i o R E</i>	Enabling the power stage at PowerOn
<i>i n l o</i>	Inversion of direction of movement
<i>q R b S</i>	Simulation of absolute position at power cycling
<i>n r n P</i>	Maximum velocity of the motion profile for velocity
<i>h c u r</i>	Current value for Halt
<i>h t y P</i>	Halt option code
<i>E i b r</i>	Selection of internal or external braking resistor
<i>t b r</i>	Maximum permissible activation duration of external braking resistor
<i>r b r</i>	Resistance value of external braking resistor
<i>P o b r</i>	Nominal power of external braking resistor
<i>P t o l</i>	Type of usage of PTO interface
<i>d E U C</i>	Specification of the control mode
<i>E R r d</i>	Memory card management

HMI menu <i>d r C -</i>	Description
<i>d r C -</i>	Device configuration (DR ive C onfiguration)
<i>n n R H</i>	Velocity limitation
<i>i n R H</i>	Current limitation
<i>J E r</i>	Jerk limitation of the motion profile for velocity
<i>P P 1</i>	Position controller P gain
<i>P P 2</i>	Position controller P gain
<i>P n 1</i>	Velocity controller P gain

HMI menu <i>drL-</i>	Description
<i>Pn2</i>	Velocity controller P gain
<i>t_i n1</i>	Velocity controller integral action time
<i>t_i n2</i>	Velocity controller integral action time
<i>tR_u1</i>	Filter time constant of reference velocity value filter
<i>tR_u2</i>	Filter time constant of reference velocity value filter
<i>FPP1</i>	Velocity feed-forward control
<i>FPP2</i>	Velocity feed-forward control

HMI menu <i>i-o-</i>	Description
<i>i-o-</i>	Configurable inputs/outputs (In Out)
<i>di0</i>	Function Input DI0
<i>di1</i>	Function Input DI1
<i>di2</i>	Function Input DI2
<i>di3</i>	Function Input DI3
<i>di4</i>	Function Input DI4
<i>di5</i>	Function Input DI5
<i>do0</i>	Function Output DQ0
<i>do1</i>	Function Output DQ1
<i>do2</i>	Function Output DQ2
<i>i-thr</i>	Monitoring of threshold value for current
<i>t-thr</i>	Monitoring of time window
<i>i-L_n</i>	Current limitation via input
<i>GFRC</i>	Selection of special gear ratios
<i>GF₁L</i>	Activation of jerk filter processing
<i>ESSc</i>	Resolution of encoder simulation
<i>i-oP_i</i>	Selection of signal type for PTI interface

HMI menu <i>FLt-</i>	Description
<i>FLt-</i>	Error indication
<i>q_{cur}</i>	Current value for Quick Stop

HMI menu <i>CoP-</i>	Description
<i>CoP-</i>	Communication (COM munication)
<i>nbAd</i>	Modbus address
<i>nbBd</i>	Modbus Baud rate
<i>CoAd</i>	CANopen address (node address)
<i>CoBd</i>	CANopen baud rate
<i>dnAd</i>	DeviceNet node address (MAC ID)
<i>dnBd</i>	DeviceNet Baud rate
<i>PbAd</i>	Profibus address
<i>i-PNd</i>	Type of obtaining IP address
<i>i-Pc1</i>	IP address Ethernet module, byte 1

HMI menu <i>CoP</i> -	Description
<i>Pc2</i>	IP address Ethernet module, byte 2
<i>Pc3</i>	IP address Ethernet module, byte 3
<i>Pc4</i>	IP address Ethernet module, byte 4
<i>Pn1</i>	IP address subnet mask, byte 1
<i>Pn2</i>	IP address subnet mask, byte 2
<i>Pn3</i>	IP address subnet mask, byte 3
<i>Pn4</i>	IP address subnet mask, byte 4
<i>Pg1</i>	IP address gateway, byte 1
<i>Pg2</i>	IP address gateway, byte 2
<i>Pg3</i>	IP address gateway, byte 3
<i>Pg4</i>	IP address gateway, byte 4
<i>PR1</i>	Current IP address Ethernet module, byte 1
<i>PR2</i>	Current IP address Ethernet module, byte 2
<i>PR3</i>	Current IP address Ethernet module, byte 3
<i>PR4</i>	Current IP address Ethernet module, byte 4
<i>EtPd</i>	Protocol
<i>dhcn</i>	User application name HMI, part 4
<i>EFdr</i>	FDR service
<i>EcSR</i>	Second EtherCAT address
<i>EcRR</i>	EtherCAT address
<i>EcSS</i>	EtherCAT slave state

HMI menu <i>Fc5</i> -	Description
<i>Fc5-</i>	Restore factory settings (default values) (Factory Settings)
<i>rESc</i>	Reset controller parameters
<i>rESu</i>	Reset user parameters
<i>rStF</i>	Restore factory settings (default values)

7.3.3 Making settings

Displaying and setting parameters

The figure below shows an example of displaying a parameter (second level) and entering or selecting a parameter value (third level).

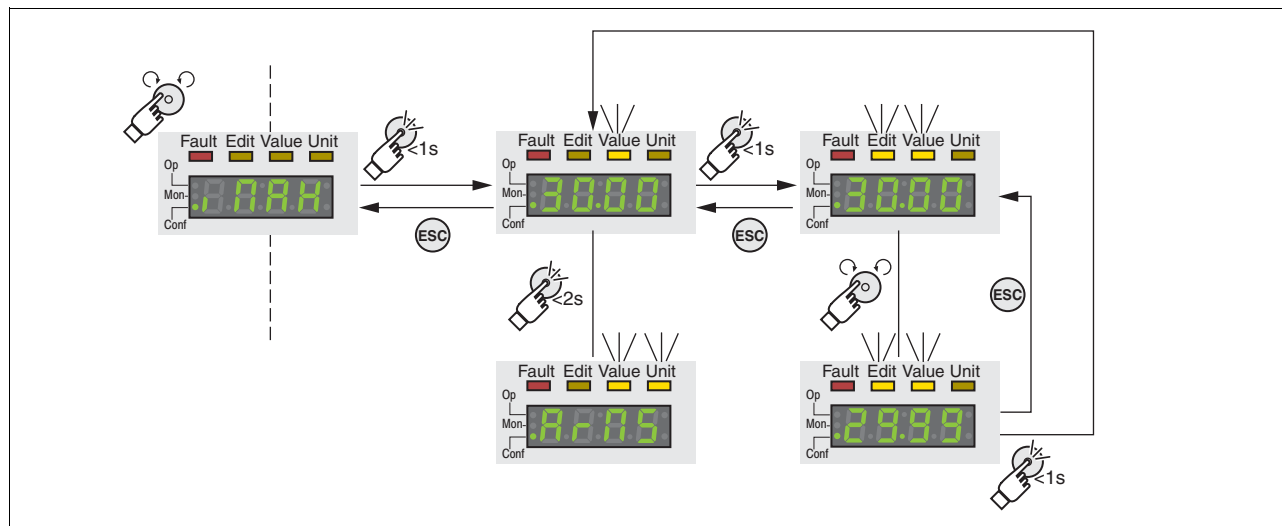


Figure 7.5 Integrated HMI, example of setting a parameter

- The parameter i_{PRH} (i_{Max}) is shown on the 7-segment display, see Figure 7.5.
 - Press the navigation button for a longer period of time to display a parameter description.
 - ◄ The parameter description is displayed in the form of horizontally scrolling text.
 - Briefly press the navigation button to display the current value of the selected parameter.
 - ◄ The Value status LED lights up and the current parameter value is displayed.
 - Press the navigation button for a longer period of time to display the unit of the current parameter value.
 - ◄ As long as the navigation button is held down, the status LEDs Value and Unit light. The unit of the current parameter value is displayed. Once you release the navigation button, the current parameter value is displayed again and the status LED Value lights.
 - Briefly press the navigation button to activate the Edit mode which allows you to modify parameter values.
 - ◄ The Edit and Value status LEDs light up and the current parameter value is displayed.
 - Turn the navigation button to change the value. The increments and the limit value for each parameter are pre-defined.
 - ◄ The Edit and Value status LEDs light and the selected parameter value is displayed.
 - Briefly press the navigation button to save the changed parameter value.
- If you do not want to save the changed parameter value, press the ESC button to cancel. The display returns to the original value.
- ◄ The displayed parameter value flashes once; the changed parameter value is written to the EEPROM.

- Press ESC to return to the menu

Setting the 7-segment display

By default, the current operating state is displayed by the 4-digit 7-segment display, see page 193. You can set the following via the menu item *dr c - / SuPU*:

- *StRt* displays the current operating state
- *URct* displays the current velocity of the motor
- *IRct* displays the current motor current

A change only becomes active when the power stage is disabled.

7.4 External graphic display terminal

The external graphic display terminal is only designed for commissioning drives.

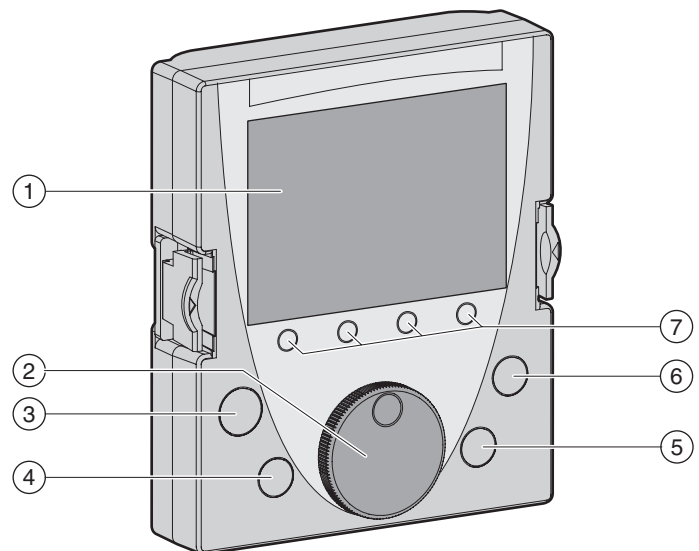


Figure 7.6 External graphic display terminal

- | | |
|-----|-------------------------|
| (1) | Display |
| (2) | Navigation button |
| (3) | STOP/RESET key |
| (4) | RUN key |
| (5) | FWD/REV key |
| (6) | ESC key |
| (7) | Function keys F1 ... F4 |

Depending on the firmware version of the external graphic display terminal, the information may be represented differently. Use the latest firmware version.



If you have any questions please contact your sales office. Your sales office staff will be happy to give you the name of a customer service office in your area.

7.4.1 Display and controls

Display (1) The display is subdivided into 5 areas.

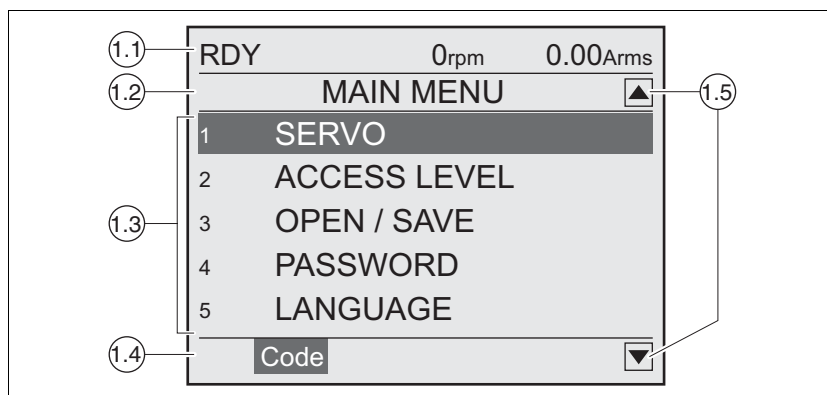


Figure 7.7 Display of the graphic display terminal (example shows English language)

- (1.1) Status information of the drive
- (1.2) Menu bar
- (1.3) Data field
- (1.4) Function bar
- (1.5) Navigation

Status information of the drive (1.1) This line displays the current operating state, the actual velocity and the motor current. If an error occurs, the error number is displayed instead of the operating state.

Menu bar (1.2) The menu bar displays the name of the current menu.

Data field (1.3) The following information can be displayed and values entered in the data field:

- Submenus
- Operating mode
- Parameters and parameter values
- State of movement
- Error messages

Function bar (1.4) The function bar displays the name of the function that is triggered when you press the corresponding function key. Example: Pressing the F1 function key displays the "Code". If you press F1, the HMI name of the displayed parameter is shown.

Navigation (1.5) Arrows indicate that additional information is available that can be displayed by scrolling.

Navigation button (2) By turning the navigation button, you can select menu levels and parameters and increment or decrement values. To confirm a selection, press the navigation button.

Key STOP/RESET (3) The key STOP/RESET stops a movement by means of a Quick Stop.

Key RUN (4) The key RUN allows you to start a movement.

Key FWD/REV (5) The key FWD/REV allows you to reverse the direction of movement.

Key ESC (6) The ESC (Escape) button allows you to exit parameters and menus or cancel a movement. If values are displayed, the ESC key lets you return to the last saved value.

Function keys F1 ... F4 (7) The assignment of the function keys F1 F4 depends on the context. The function bar displays the name of the function triggered when the corresponding function key is pressed.

7.4.2 Connecting the external graphic display terminal to LXM32

The external graphic display terminal is an accessory for the drive, see chapter 12.1 "Commissioning tools", page 519. The external graphic display terminal is connected to CN7 (commissioning interface). Only use the cable shipped with the external graphic display terminal to connect it. If the external graphic display terminal is connected to LXM32, the integrated HMI is deactivated. The integrated HMI shows *d*, *SP* (Display).

7.4.3 Using the external graphic display terminal

The following 2 examples show you how to use the external graphic display terminal.

Example 'Setting the Language'

In this example, you set the desired language for the external graphic display terminal. The drive must have been fully installed and the supply voltage must be on.

- The external graphic display terminal has been connected to CN7 and the main menu is displayed.
- ▶ Rotate the navigation button until item 5 (LANGUAGE) is highlighted.
- ▶ Press the navigation button to confirm the selection.
- ◁ The menu bar shows the selected function (5 LANGUAGE). The data field displays the selected value, in this case the selected language.
- ▶ Press the navigation button to change the value.
- ◁ The menu bar displays the selected function "Language". The supported languages are shown in the data field.
- ▶ Turn the navigation button to select the desired language.
- ◁ The currently active language is highlighted by a check.
- ▶ Press the navigation button to confirm the selected value.
- ◁ The menu bar displays the selected function "Language". The selected language is shown in the data field.
- ▶ Press ESC to return to the main menu.
- ◁ The main menu is displayed in the selected language.

Example 'Using Operating Mode Jog'

This example starts a movement in the operating mode Jog. The drive must have been fully installed. Commission the drive as per chapter 7.6 "Commissioning procedure". The following procedure corresponds to chapter 7.6.8 "Checking the direction of movement".

- The external graphic display terminal has been connected to CN7 and the main menu is displayed. The desired language has been set.
- ▶ Rotate the navigation button until item 1 (SERVO) is highlighted.
- ▶ Press the navigation button to confirm the selection.
- ◁ The menu bar shows the selected function (1 SERVO). The data field displays the submenu of the selected function (1 SERVO).
- ▶ Rotate the navigation button until item 1.4 (OPERATION) is highlighted and press the navigation button to confirm the selection.
- ◁ The menu bar shows the selected function (1.4 OPERATION). The data field displays the supported operating modes in a submenu.
- ▶ Rotate the navigation button until item 1.4.1 (JOG) is highlighted and press the navigation button to confirm the selection.
- ◁ The menu bar shows the selected function (1.4.1 JOG). The data field displays "Op. mode Jog" and the parameters and parameter values for the operating mode
- ▶ Rotate the navigation button until the item "Op. mode Jog" is highlighted and press the navigation button to confirm the selection.
- ◁ The data field displays "JOG →" (Jog, slow movement in positive direction).
- ▶ Rotate the navigation button to change the (slow: →, ← fast: →→, ←←) and the direction of movement (positive direction of movement: →, →→, negative direction of movement: ←, ←←). You can also use the FWD/REV key to change the direction of movement.
- ▶ Press the navigation button or the RUN key to enable the power stage.
- ▶ Press the navigation button or the RUN key to start a movement.
- ◁ The movement continues as long as you hold down the navigation button / the RUN key or until you press the STOP/RESET key. You can neither change the velocity nor the direction of movement during the movement.
- ▶ To stop the movement, press the STOP/RESET key or release the navigation button / the RUN key.
- ▶ Press the ESC key to disable the power stage.
- ◁ Power stage is disabled.
- ▶ Press ESC 3 times to return to the main menu.
- ◁ Each time you press ESC you go back by one menu level.

7.5 Commissioning software

The commissioning software has a graphic user interface and is used for commissioning, diagnostics and testing settings.

- Tuning of the controller parameters via a graphical user interface
- Comprehensive set of diagnostics tools for optimization and maintenance
- Long-term recording for evaluation of the performance
- Testing the input and output signals
- Tracking signals on the screen
- Archiving of device settings and recordings with export function for further processing in other applications

See page 121 for details on connecting a PC to the device.

Online help

The commissioning software offers help functions, which can be accessed via "? - Help Topics" or by pressing the F1 key.

7.6 Commissioning procedure

WARNING

UNINTENDED BEHAVIOR

The behavior of the drive system is governed by numerous stored data or settings. Unsuitable settings or data may trigger unexpected movements or responses to signals and disable monitoring functions.

- Do NOT operate the drive system with unknown settings or data.
- Verify that the stored data and settings are correct.
- When commissioning, carefully run tests for all operating states and potential error situations.
- Verify the functions after replacing the product and also after making changes to the settings or data.
- Only start the system if there are no persons or obstructions in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.

WARNING

UNINTENDED BEHAVIOR CAUSED BY ACCESS CONTROL

Improper use of access control may cause commands to be triggered or blocked.

- Verify that no unintended behavior is caused as a result of enabling or disabling exclusive access.
- Verify that impermissible access is blocked.
- Verify that required access is available.

Failure to follow these instructions can result in death, serious injury or equipment damage.

7.6.1 "First Setup"

	A "First Setup" is required when the controller supply voltage is switched on for the first time or after the factory settings have been restored.
<i>Duplicating device settings</i>	A memory card or the commissioning software allows you duplicate device settings. See chapter 7.9 "Duplicating existing device settings", page 194 for additional information.
<i>Automatic reading of the motor data record</i>	<p>When the device is switched on and if an encoder is connected to CN3, the device automatically reads the electronic nameplate from the Hiperface encoder. The record is checked and written to the EEPROM.</p> <p>The record contains technical information on the motor such as nominal torque and peak torque, nominal current, nominal velocity and number of pole pairs. The record cannot be changed by the user. Without this information, the device is not ready for operation.</p>
<i>Manual adjustment of the motor parameters</i>	If the motor encoder is not connected to CN3, the motor parameters must be adjusted manually. Note the information in the manual for the encoder modules.
<i>Preparation</i>	If the device is not to be commissioned exclusively via the HMI, a PC with the commissioning software must be connected.
<i>Switching on the device</i>	<ul style="list-style-type: none"> ■ The power stage supply voltage is switched off. ▶ Disconnect the product from the the fieldbus during commissioning in order to avoid conflicts by simultaneous access. ▶ Switch on the controller supply voltage. ◁ The device goes through an initialization routine, all LEDs are tested, all segments of the 7-segment display and the status LEDs light up. <p>If a memory card is in the the slot of the device, the message <code>Err d</code> is displayed by the 7-segment display for a short period of time. This indicates that a memory card has been detected. If the message <code>Err d</code> is permanently displayed by the 7-segment display, there are differences between the content of the memory card and the parameter values stored in the device. See chapter 7.8 "Memory Card", page 191 for additional information.</p> <p>After initialization and if one or more modules are plugged in, you must make additional settings depending on the module(s). Make these settings as described in the appropriate manuals for the modules.</p>
<i>Restarting the device</i>	A restart of the device is required for the changes to become effective. After the restart, the device is ready for operation. The device is in the operating mode Jog. See chapter 8.3 "Operating modes", page 199 for changing operating modes.
<i>Further steps</i>	<ul style="list-style-type: none"> ▶ Attach a label to the device that contains information for servicing the device such as fieldbus type and fieldbus address. ▶ Make the settings described below for commissioning.

7.6.2 Operating state (state diagram)

After switching on and when an operating mode is started, the product goes through a number of operating states.

The state diagram (state machine) shows the relationships between the operating states and the state transitions.

The operating states are monitored and influenced by internal monitoring functions and system functions such as temperature monitoring or current monitoring.

Graphical representation The state diagram is represented as a flow chart.

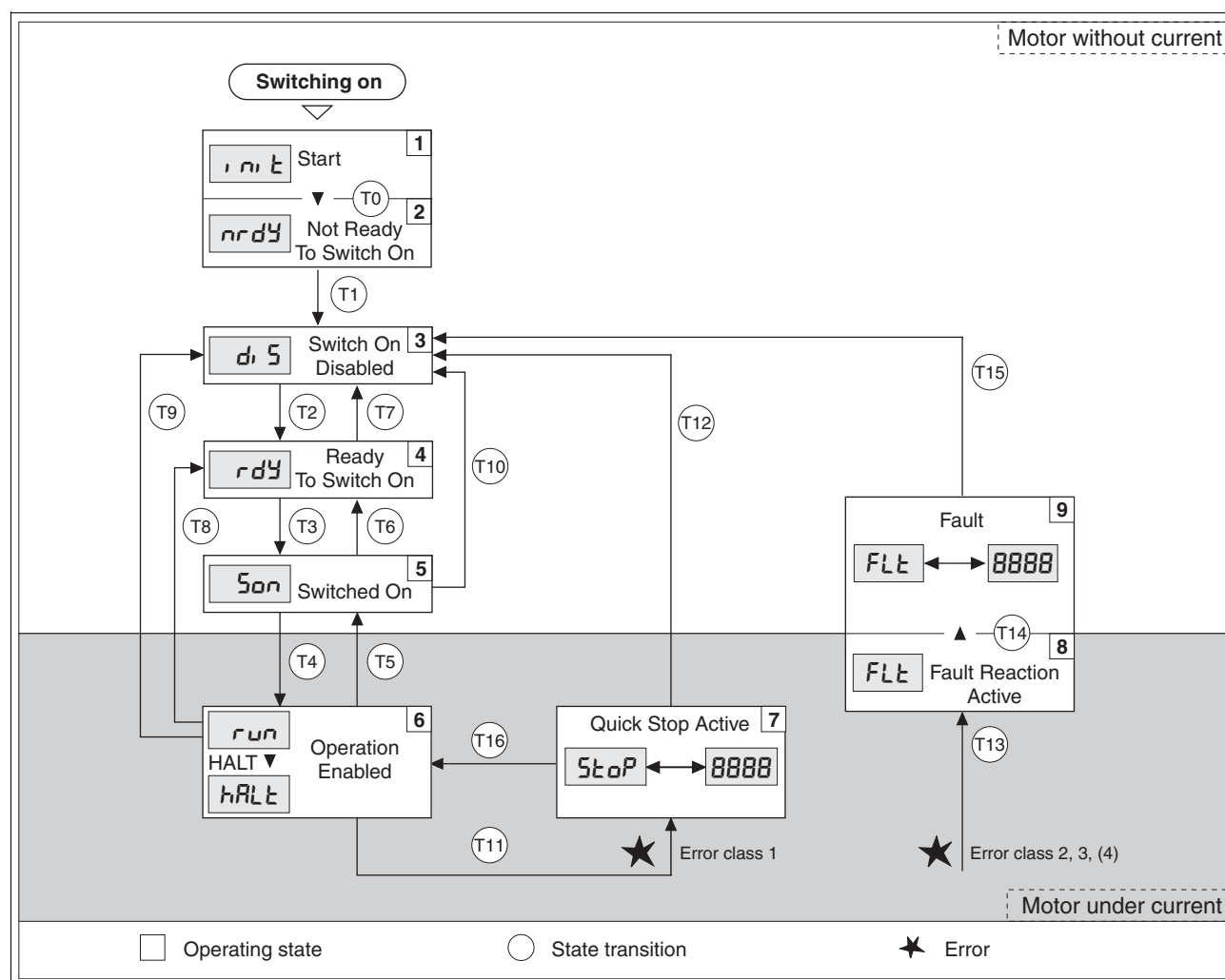


Figure 7.8 State diagram

Operating states and state transitions

See page 193 for detailed information on operating states and state transitions.

7.6.3 Setting basic parameters and limit values



Prepare a list with the parameters required for the functions used.

Controller parameter sets

This device allows you to use two controller parameter sets. It is possible to switch from one set of controller parameters to the other during operation. The active controller parameter set is selected with the parameter CTRL_SelParSet.

The corresponding parameters are CTRL1_xx for the first controller parameter set and CTRL2_xx for the second controller parameter set. The following descriptions use the notation CTRL1_xx (CTRL2_xx) if there are no functional differences between the two controller parameter sets.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_SelParSet	Selection of controller parameter set (non-persistent) Coding see parameter: CTRL_PwrUpParSet Changed settings become active immediately.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3011:19 _h Modbus 4402 Profibus 4402 CIP 117.1.25
_CTRL_ActParSet	Active controller parameter set Value 1: Controller parameter set 1 is active Value 2: Controller parameter set 2 is active A controller parameter set is active after the time for the parameter switching (CTRL_ParChgTime) has elapsed.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3011:17 _h Modbus 4398 Profibus 4398 CIP 117.1.23
CTRL_ParChgTime	Period of time for parameter switching In the case of parameter set switching, the values of the following parameters are changed gradually: - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAUref - CTRL_TAUiref - CTRL_KFPp Such a parameter switching can be caused by - change of the active controller parameter set - change of the global gain - change of any of the parameters listed above - switching off the integral term of the velocity controller Changed settings become active immediately.	ms 0 0 2000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:14 _h Modbus 4392 Profibus 4392 CIP 117.1.20

Setting limit values

Suitable limit values must be determined and calculated on the basis of the system and motor data. As long as the motor is operated without loads, the default settings do not need to be changed.

Current limitation The maximum motor current can be set with the parameter CTRL_I_max.

The maximum current for the "Quick Stop" function can be limited with the parameter LIM_I_maxQSTP and for the "Halt" function with the parameter LIM_I_maxHalt.

- Use the parameter CTRL_I_max to set the maximum motor current.
- Use the parameter LIM_I_maxQSTP to set the maximum motor current for the "Quick Stop" function.
- Use the parameter LIM_I_maxHalt to set the maximum motor current for the "Halt" function.

The motor can be decelerated via a deceleration ramp or the maximum current for the functions "Quick Stop" and "Halt".

The device limits the maximum permissible current on the basis of the motor data and the device data. Even if the value entered for the maximum current in the parameter CTRL_I_max is too high, the value is limited.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_I_max EonF → drE- , nRH	<p>Current limitation</p> <p>During operation, the actual current limit is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - CTRL_I_max - M_I_max - PA_I_max - Current limitation via digital input <p>Limitations caused by I2t monitoring are also taken into account.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	<p>A_{rms}</p> <p>0.00</p> <p>-</p> <p>300.00</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3011:C_h</p> <p>Modbus 4376</p> <p>Profibus 4376</p> <p>CIP 117.1.12</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_I_maxQSTP [onF → FLt - qcur	<p>Current value for Quick Stop</p> <p>This value is only limited by the minimum/maximum value range (no limitation of this value by motor/power stage).</p> <p>In the case of a Quick Stop, the actual current limit ($I_{\text{max_actual}}$) is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - LIM_I_maxQSTP - M_I_max - PA_I_max <p>Further current reductions caused by I2t monitoring are also taken into account during a Quick Stop.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	<p>A_{rms}</p> <p>-</p> <p>-</p> <p>-</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3011:D_h</p> <p>Modbus 4378</p> <p>Profibus 4378</p> <p>CIP 117.1.13</p>
LIM_I_maxHalt [onF → RLG - hcur	<p>Current value for Halt</p> <p>This value is only limited by the minimum/maximum value range (no limitation of this value by motor/power stage).</p> <p>In the case of a Halt, the actual current limit ($I_{\text{max_actual}}$) is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - LIM_I_maxHalt - M_I_max - PA_I_max <p>Further current reductions caused by I2t monitoring are also taken into account during a Halt.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	<p>A_{rms}</p> <p>-</p> <p>-</p> <p>-</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3011:E_h</p> <p>Modbus 4380</p> <p>Profibus 4380</p> <p>CIP 117.1.14</p>

Velocity limitation The parameter CTRL_v_max can be used to limit the maximum velocity.

- Use the parameter CTRL_v_max to set the maximum velocity of the motor.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_v_max CONF → drC - nPRH	<p>Velocity limitation</p> <p>During operation, the actual velocity limit is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - CTRL_v_max - M_n_max - Velocity limitation via digital input <p>Changed settings become active immediately.</p>	usr_v 1 13200 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3011:10 _h Modbus 4384 Profibus 4384 CIP 117.1.16

7.6.4 Digital inputs / outputs

The device has configurable inputs and configurable outputs. The standard assignment and the configurable assignment depends on the selected operating mode. For more information, see chapter 8.5.3 "Setting the digital signal inputs and signal outputs".

The signal states of the digital inputs and outputs can be displayed on the HMI and displayed and modified using the commissioning software.

Integrated HMI The signal states can be displayed on the integrated HMI, but they cannot be modified.

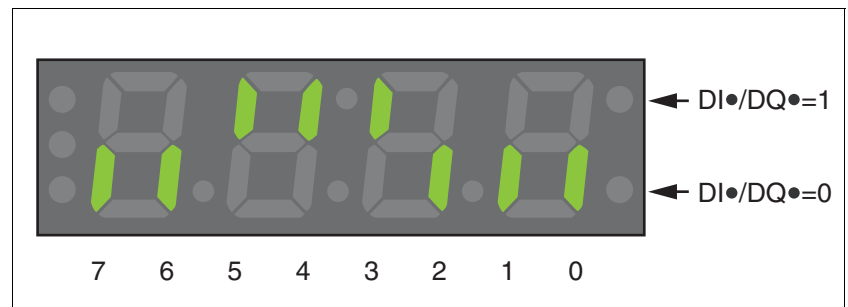


Figure 7.9 Integrated HMI, displaying the signal state of the digital inputs (DI) and outputs (DQ)

Inputs (parameter `_IO_DI_act`):

► Open the menu item `-Eing / d, E`.

◁ The digital inputs are displayed in a bit-coded way.

Bit	Signal	I/O
0	DI0	I
1	DI1	I
2	DI2	I
3	DI3	I
4	DI4	I
5	DI5	I
6	-	-
7	-	-

The parameter `_IO_DI_act` does not display the states of the inputs of the STO safety function. Use the parameter `_IO_STO_act` to visualize the states of the inputs of the STO safety function.

Outputs (parameter `_IO_DQ_act`):

► Open the menu item *-Παλ / δαΠα*.

◁ The digital outputs are displayed in a bit-coded way.

Bit	Signal	I/O
0	DQ0	O
1	DQ1	O
2	DQ2	O
3	-	-
4	-	-
5	-	-
6	-	-
7	-	-

Fieldbus The current signal states are contained in the parameter `_IO_act` in a bit-coded way. The values "1" and "0" correspond to the current signal state of the input or output.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_IO_act</code>	Physical status of the digital inputs and outputs Low byte: Bit 0: DI0 Bit 1: DI1 Bit 2: DI2 Bit 3: DI3 Bit 4: DI4 Bit 5: DI5 High byte: Bit 8: DQ0 Bit 9: DQ1 Bit 10: DQ2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3008:1 _h Modbus 2050 Profibus 2050 CIP 108.1.1
<code>_IO_DI_act</code> <i>flon</i> <i>di flo</i>	Status of digital inputs Bit assignments: Bit 0: DI0 Bit 1: DI1 Bit 2: DI2 Bit 3: DI3 Bit 4: DI4 Bit 5: DI5	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3008:F _h Modbus 2078 Profibus 2078 CIP 108.1.15
<code>_IO_DQ_act</code> <i>flon</i> <i>do flo</i>	Status of digital outputs Bit assignments: Bit 0: DQ0 Bit 1: DQ1 Bit 2: DQ2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3008:10 _h Modbus 2080 Profibus 2080 CIP 108.1.16
<code>_IO_STO_act</code> <i>flon</i> <i>sto</i>	Status of the inputs for the safety function STO Coding of the individual signals: Bit 0: STO_A Bit 1: STO_B	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3008:26 _h Modbus 2124 Profibus 2124 CIP 108.1.38

7.6.5 Testing the signals of the limit switches

⚠ WARNING**LOSS OF CONTROL**

The use of limit switches can provide some protection against hazards (for example, collision with mechanical stop caused by incorrect reference values).

- If possible, use the limit switches.
- Verify correct connection of the limit switches.
- Verify the correct installation of the limit switches. The limit switches must be mounted in a position far enough away from the mechanical stop to allow for an adequate stopping distance.
- You must release the limit switches before you can use them.
- Verify the correct function of the limit switches.

Failure to follow these instructions can result in death, serious injury or equipment damage.

► Set up the limit switches in such a way as to keep the motor from overtraveling the limit switches.

► Trigger the limit switches manually.

◁ The HMI displays an error message.

Parameters can be used to release the limit switches and to set the evaluation to active 0 or active 1, see page 314.



If possible, use normally closed contacts so that a wire break can be signaled as an error.

7.6.6 Testing the safety function STO

Operation with STO If you want to use the STO safety function, carry out the following steps:

- Power stage supply is switched off.
Controller supply voltage is switched off.
- ▶ Verify that the inputs $\overline{\text{STO_A}}$ and $\overline{\text{STO_B}}$ are isolated from each other. The two signals must not be electrically connected.
- Power stage supply voltage is switched on.
Controller supply voltage is switched on.
- ▶ To avoid unintended restart after restoration of power, the parameter `IO_AutoEnable` must be set to "off". Verify that the parameter `IO_AutoEnable` is set to "off" (HMI: `conf → RCU → oRE`).
- ▶ Start the operating mode Jog (without motor movement) (see page 200).
- ▶ Trigger the STO safety function. $\overline{\text{STO_A}}$ and $\overline{\text{STO_B}}$ must be switched off simultaneously.
- ◁ The power stage is disabled and error message 1300 is generated. (NOTE: Error message 1301 indicates a wiring error.)
- ▶ Check the behavior of the drive when errors are present.
- ▶ Document all tests of the safety function in your acceptance certificate.

Operation without STO If you do not want to use the STO safety function:

- ▶ Verify that the inputs $\overline{\text{STO_A}}$ and $\overline{\text{STO_B}}$ are connected to +24VDC.

7.6.7 Holding brake

Holding brake The holding brake in the motor has the task of holding the current motor position when the power stage is disabled, even if external forces act (for example, in the case of a vertical axis). The holding brake is not a safety function.

The signals of the holding brake meet the PELV requirements.

Adjustable parameters The electronic nameplate of the motor contains the delay for releasing and the delay applying the holding brake. It is possible to parameterize an additional time delay for releasing the holding brake (BRK_AddT_release) and an additional time delay for applying (BRK_AddT_apply) the holding brake.

Time delay for releasing the holding brake The time delay for releasing the holding brake stored in the electronic nameplate depends on the motor type.

The parameter BRK_AddT_release allows you to add an additional time delay. The power stage is enabled (Operation Enabled) after the entire delay time has passed.

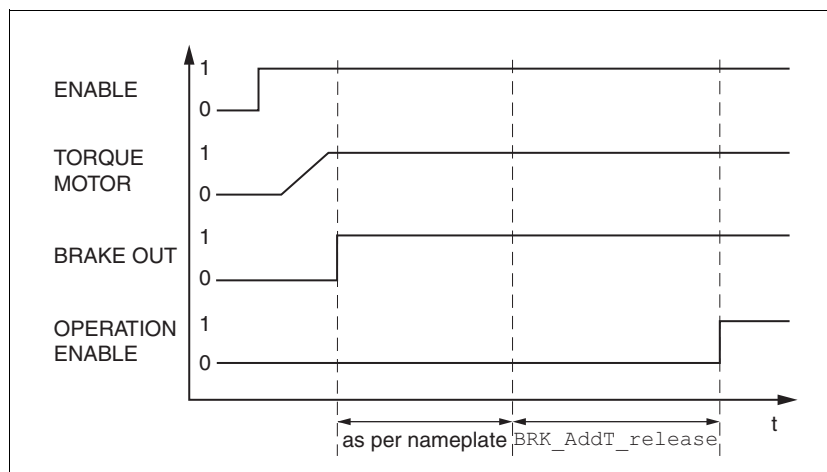


Figure 7.10 Releasing the holding brake

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
BRK_AddT_release	<p>Additional time delay for releasing the holding brake</p> <p>The overall time delay for releasing the holding brake is the time delay from the electronic nameplate of the motor and the additional time delay in this parameter.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	ms 0 0 400	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3005:7 _h Modbus 1294 Profibus 1294 CIP 105.1.7

Time delay for applying the holding brake

When the power stage is disabled, the holding brake is applied. However, current continues to be applied to the motor for the period of time corresponding to the time delay for applying the holding brake.

The time delay for applying the holding brake stored in the electronic nameplate depends on the motor type.

The parameter `BRK_AddT_apply` allows you to add an additional time delay. Current continues to be applied to the motor until the entire delay time has passed.

NOTE: Triggering the STO safety function means that the time delay for motors with holding brake is not effective. The motor cannot generate holding torque to bridge the time to application of the holding brake. Check whether additional measures have to be taken; for example, this may cause the load of vertical axes to lower.

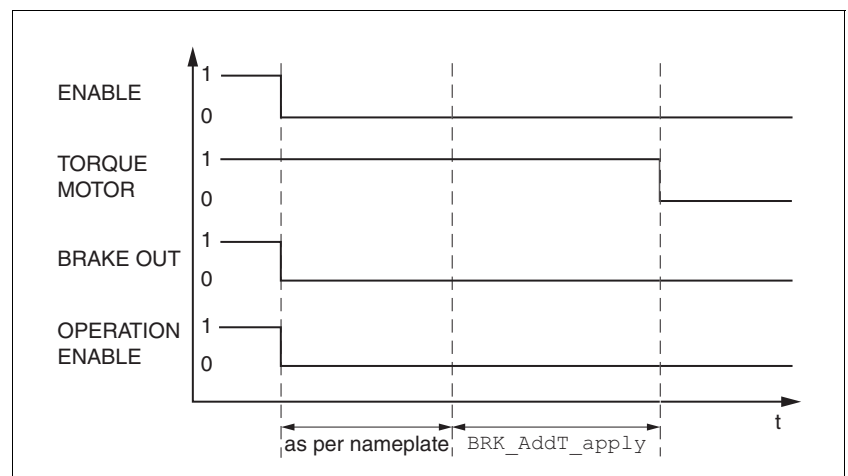


Figure 7.11 Applying the holding brake

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>BRK_AddT_apply</code>	<p>Additional time delay for applying the holding brake</p> <p>The overall time delay for applying the holding brake is the time delay from the electronic nameplate of the motor and the additional time delay in this parameter.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	<p>ms</p> <p>0</p> <p>0</p> <p>1000</p>	<p>INT16</p> <p>INT16</p> <p>INT16</p> <p>INT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3005:8_h</p> <p>Modbus 1296</p> <p>Profibus 1296</p> <p>CIP 105.1.8</p>

7.6.7.1 Checking the holding brake

⚠ WARNING**UNEXPECTED MOVEMENT**

Releasing the holding brake may cause an unexpected movement in the system, for example if vertical axes are used.

- Take appropriate measures to avoid damage caused by the falling loads.
- Only run the test if there are no persons or obstacles in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Checking the holding brake

- The device is in operating state "Ready to switch on" and the parameters for the holding brake must have been set.
- ▶ Start the operating mode Jog (HMI: $\alpha P \rightarrow J\alpha G \rightarrow JGSt$).
- ◁ The power stage is enabled and the holding brake released. The HMI displays $JG-$.
- ▶ Press the navigation button and hold it down.
- ◁ As long as the navigation button is held down, the motor moves.
- ▶ Press ESC.
- ◁ The holding brake is applied. The power stage is disabled.

7.6.8 Checking the direction of movement

⚠ WARNING

UNEXPECTED MOVEMENT CAUSED BY INTERCHANGED MOTOR PHASES

Interchanging motor phases results in unexpected movements with fast acceleration.

- If required, use the parameter `POSdirOfRotat` for reversing the direction.
- Do not interchange the motor phases.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Direction of movement

Movements are made in positive or in negative directions. In the case of a rotary motors, direction of movement is defined in accordance with IEC 61800-7-204: Positive direction is when the motor shaft rotates clockwise as you look at the end of the protruding motor shaft.

Checking the direction of movement

▶ Start the operating mode Jog. (HMI: `OP→JOG→JOGt`)

◁ The HMI displays `JG-`.

Movement in positive direction:

▶ Press the navigation button and hold it down.

◁ A movement is made in positive direction.

Movement in negative direction:

▶ Turn the navigation button until the HMI displays `-JG`.

▶ Press the navigation button and hold it down.

◁ A movement is made in negative direction.

Changing the direction of movement

If the expected direction of movement and the actual direction of movement are not identical, you can invert the direction of movement.

- Inversion of direction of movement is off:
Movements are made in positive direction with positive target values.
- Inversion of direction of movement is on:
Movements are made in positive direction with negative target values.

The parameter `InvertDirOfMove` allows you to invert the direction of movement.

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Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
InvertDirOfMove [onF → RCU- info	<p>Inversion of direction of movement</p> <p>0 / Inversion Off / off: Inversion of direction of movement is off</p> <p>1 / Inversion On / on: Inversion of direction of movement is on</p> <p>The limit switch which is reached with a movement in positive direction must be connected to the positive limit switch input and vice versa.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:Ch Modbus 1560 Profibus 1560 CIP 106.1.12

7.6.9 Setting parameters for encoder

Setting an absolute position When starting up, the device reads the absolute position of the motor from the encoder. The current absolute position can be read with the parameter `_p_absENC`.

When the motor is at a standstill, the new absolute position of the motor can be set to the current mechanical motor position with the parameter `ENC1_adjustment`. The value can be set with the power stage enabled or disabled. Setting the absolute position also shifts the position of the index pulse of the encoder and the index pulse of the encoder simulation.

The absolute position of an encoder at encoder 2 (modules can be adjusted via the parameter `ENC2_adjustment`).

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_p_absENC</code>	<p>Absolute position with reference to the encoder range</p> <p>This value corresponds to the modulo position of the absolute encoder range. The value is no longer valid if the gear ratio of machine encoder and motor encoder is changed. A restart is required in such a case.</p>	<p>usr_p</p> <p>-</p> <p>-</p> <p>-</p>	<p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>R/-</p> <p>-</p> <p>-</p>	<p>CANopen 301E:F_n</p> <p>Modbus 7710</p> <p>Profibus 7710</p> <p>CIP 130.1.15</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENC1_adjustment	<p>Adjustment of absolute position of encoder 1</p> <p>The value range depends on the encoder type.</p> <p>Singleturn encoder: 0 ... max_pos_usr/rev. - 1</p> <p>Singleturn encoder (shifted with parameter ShiftEncWorkRang): -(max_pos_usr/rev)/2 ... (max_pos_usr/rev.) / 2 - 1</p> <p>Multiturn encoder: 0 ... (4096 * max_pos_usr/rev.) - 1</p> <p>Multiturn encoder (shifted with parameter ShiftEncWorkRang): -2048 * max_pos_usr/rev ... (2048 * max_pos_usr/rev.) - 1</p> <p>max_pos_usr/rev.: Maximum user-defined position for one encoder turn. This value is 16384 with the default scaling.</p> <p>NOTE: * If processing is to be performed with inversion of the direction of movement, this must be set before the encoder position is adjusted. * After the write access, a wait time of at least 1 second is required before the drive is switched off. * Changing this value also changes the position of the virtual index pulse and the index pulse for the encoder simulation.</p> <p>Changed settings become active the next time the product is switched on.</p>	usr_p - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 3005:16 _h Modbus 1324 Profibus 1324 CIP 105.1.22

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENC2_adjustment	<p>Adjustment of absolute position of encoder 2</p> <p>The value range depends on the encoder type at the physical port ENC2.</p> <p>ENC2_adjustment can only be changed if ENC_abs_source = Encoder 2.</p> <p>Singleturn encoder: 0 ... max_pos_usr/rev. - 1</p> <p>Singleturn encoder (shifted with parameter ShiftEncWorkRang): -(max_pos_usr/rev)/2 ... (max_pos_usr/rev.) / 2 - 1</p> <p>Multiturn encoder: 0 ... (revolutions * max_pos_usr/rev.) - 1</p> <p>Multiturn encoder (shifted with parameter ShiftEncWorkRang): -(revolutions * max_pos_usr/rev)/2 ... (revolutions * max_pos_usr/rev.) / 2 - 1</p> <p>max_pos_usr/rev.: Maximum user-defined position for one encoder turn. This value is 16384 with the default scaling.</p> <p>NOTE: * If processing is to be performed with inversion of the direction of movement, this must be set before the encoder position is adjusted. * After the write access, the parameter values has to be saved to the EEPROM and the drive has to be switched off, before the change becomes active. * Changing this value also changes the position of the virtual index pulse and the index pulse for the encoder simulation.</p> <p>Changed settings become active the next time the product is switched on.</p>	usr_p - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 3005:24 _h Modbus 1352 Profibus 1352 CIP 105.1.36



If you have replaced the device, you must check the absolute position of the motor. If there is a deviation or if you replace the motor, you must set the absolute position once again.

Singleturn encoder

In the case of a singleturn encoder, you can shift the position of the index pulse of the encoder by setting a new absolute position. If the position value is 0, the index pulse is defined at the current mechanical motor position.

This also changes the position of the index pulse of the encoder simulation.

Multiturn encoder

If a rotary motor with multiturn encoder performs a movement from 0 into negative direction, there is an underrun of the absolute position of the multiturn encoder. However, the actual position in the drive keeps counting forward and delivers a negative position value. After switching off and on, the actual position of the drive no longer corresponds to the negative position value, but to the absolute position of the encoder (a position of -10 revolutions prior to switching off becomes an absolute position of 4086 revolutions after switching on again).

The parameter `ShiftEncWorkRang` lets you specify whether the working range continues to comprise 0...4096 revolutions or whether the working range comprises -2048...+2048 revolutions.

`ShiftEncWorkRang = 0`: The working range is defined as 0 ... 4096 revolutions.

`ShiftEncWorkRang = 1`: The working range is defined as -2048 ... 2048 revolutions. With a typical application (positive and negative movements), the working range of the motor is in the continuous range of the encoder.

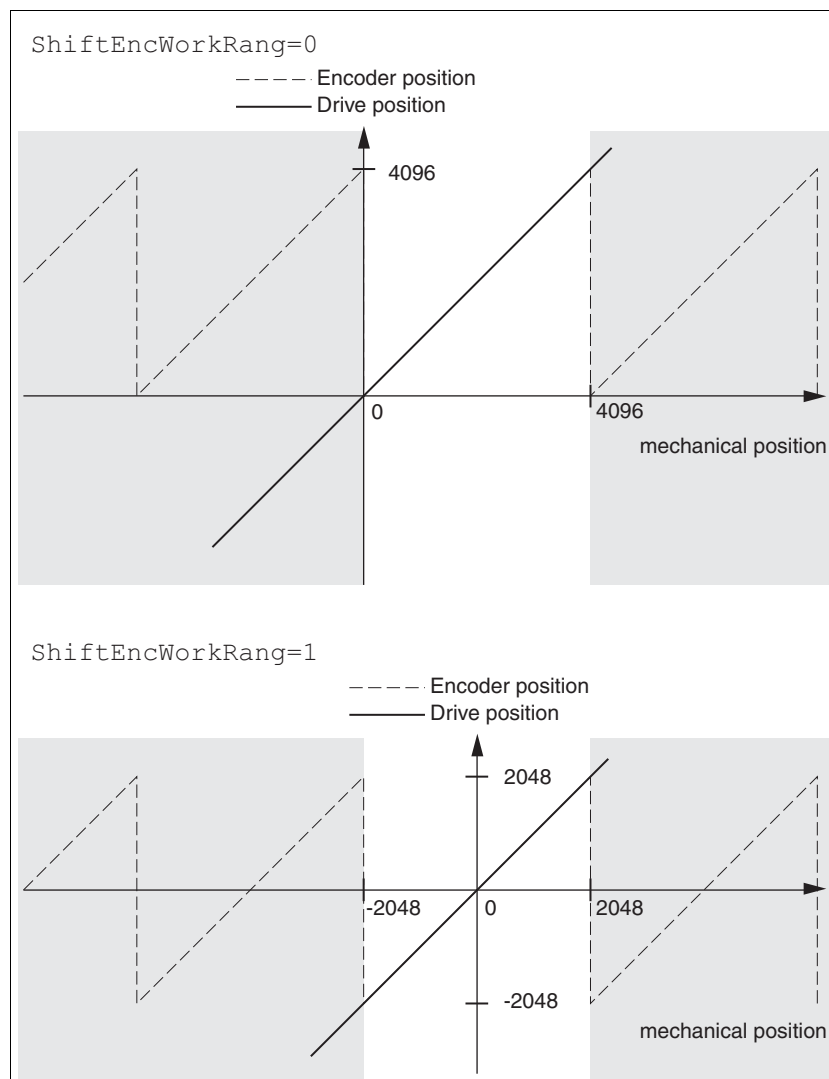


Figure 7.12 Position values of multiturn encoder

- Set the absolute position at the mechanical limit to a position value >0.

This achieves that the mechanical working range will be in the continuous range of the encoder.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ShiftEncWorkRang	<p>Shifting of the encoder working range</p> <p>0 / Off: Shifting off 1 / On: Shifting on</p> <p>Value 0: Position values are between 0 ... 4096 revolutions.</p> <p>Value 1: Position values are between -2048 ... 2048 revolutions.</p> <p>After activating the shifting function, the position range of a multiturn encoder is shifted for half of the range. Example for the position range of a multiturn encoder with 4096 revolutions.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:21 _h Modbus 1346 Profibus 1346 CIP 105.1.33

7.6.10 Setting the braking resistor parameters

⚠ WARNING**MOTOR WITHOUT BRAKING EFFECT**

An insufficient braking resistor causes overvoltage on the DC bus and switches off the power stage. The motor is no longer actively decelerated.

- Verify that the braking resistor has a sufficient rating.
- Check the parameter settings for the braking resistor.
- Check the I^2t value under the most critical condition by performing a test run. The device switches off at an I^2t value of 100%.
- When performing the calculation and the test run, take into account the fact that the DC bus capacitors can absorb less braking energy at higher mains voltages.

Failure to follow these instructions can result in death, serious injury or equipment damage.

⚠ WARNING**HOT SURFACES**

The braking resistor may heat up to over 250°C (480°F) during operation.

- Avoid contact with the hot braking resistor.
- Do not allow flammable or heat-sensitive parts in the immediate vicinity of the braking resistor.
- Provide for good heat dissipation.
- Check the temperature of the braking resistor under the most critical condition by performing a test run.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Further information on braking resistors	Page
Technical data braking resistor	44
Rating the braking resistor	69
Mounting the external braking resistor	90
Electrical installation of the braking resistor	103
Order data for external braking resistors	519

- Check the parameter `RESint_ext`. If you have connected an external braking resistor, you must set the parameter to "external".
- If you have connected an external braking resistor, (value of the parameter `RESint_ext` is set to "external"), you must assign the appropriate values to the parameters `RESext_P`, `RESext_R` and `RESext_ton`. Verify that the selected external braking resistor is really connected.
- Test the function of the braking resistor under realistic, worst case conditions.

If the regenerated power becomes greater than the power that can be absorbed by the braking resistor, an error message is generated and the power stage is disabled.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>RESint_ext</code> [onF → REG- E, br	Selection of internal or external braking resistor 0 / Internal Braking Resistor / r_{int} : Internal braking resistor 1 / External Braking Resistor / r_{ext} : External braking resistor Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:9 _h Modbus 1298 Profibus 1298 CIP 105.1.9
<code>RESext_P</code> [onF → REG- Pabr	Nominal power of external braking resistor Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	W 1 10 32767	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:12 _h Modbus 1316 Profibus 1316 CIP 105.1.18
<code>RESext_R</code> [onF → REG- rbr	Resistance value of external braking resistor The minimum value depends on the power stage. In increments of 0.01 Ω . Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	Ω - 100.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:13 _h Modbus 1318 Profibus 1318 CIP 105.1.19

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RESext_ton CONF → REG- tbr	Maximum permissible switch-on time of external braking resistor Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	ms 1 1 30000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:11 _h Modbus 1314 Profibus 1314 CIP 105.1.17

7.6.11 Autotuning the device

There are three ways of tuning the drive control loops:

- Easy Tuning: Automatic - autotuning without user intervention. For most applications, autotuning yields good, highly dynamic results.
- Comfort Tuning: Semi-automatic - autotuning with user intervention. Parameters for direction and parameters for damping can be set by the user.
- Manual: The user can set and tune the control loop parameters manually. Expert mode.

Autotuning

Autotuning determines the friction torque as a constantly acting load torque and considers it in the calculation of the moment of inertia of the entire system.

External factors such as a load at the motor are considered. Autotuning optimizes the settings of the control loop parameters; see chapter 7.7 "Controller optimization with step response".

Autotuning also supports typical vertical axes.

⚠ WARNING

UNEXPECTED MOVEMENT

Autotuning moves the motor in order to tune the control loops. Incorrect parameters may cause unexpected movements or the loss of monitoring functions.

- Check the parameters `AT_dir` and `AT_dis_usr` (`AT_dis`). The distance required for the deceleration ramp must also be taken into account.
- Verify that the parameter `LIM_I_maxQSTP` for Quick Stop is correctly set.
- If possible, use the limit switches.
- Verify that a functioning button for emergency stop is within reach.
- Verify that the system is free and ready for the movement before starting the function.

Failure to follow these instructions can result in death, serious injury or equipment damage.

During autotuning, the motor is activated and small movements are made. Noise development and mechanical oscillations of the system are normal.

If you want to perform Easy Tuning, no additional parameters need to be set. If you want to perform Comfort Tuning, set the parameters `AT_dir`, `AT_dis_usr` (`AT_dis`) and `AT_mechanics` to meet the requirements of your system.

The parameter `AT_Start` is used to selected between Easy Tuning and Comfort Tuning. When the value is written, autotuning also starts.

- Start autotuning via the commissioning software.

It is also possible to start autotuning via the HMI.

HMI: `oP → t_u n → t_u 5 t`

- Save the new settings to the EEPROM via the commissioning software.

The product features 2 controller parameter sets that can be parameterized separately. The values for the controller parameters determined during autotuning are stored in controller parameter set 1.

If you have started autotuning via the HMI, press the navigation button to save the new values to the EEPROM.

If autotuning cancels with an error message, the default values are used. Change the mechanical position and restart autotuning. If you want to verify the plausibility of the calculated values, you can have them displayed; see chapter 7.6.12 "Enhanced settings for autotuning", page 176.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
AT_dir <code>oP → t_u n -</code> <code>5 t, n</code>	Direction of movement for Autotuning 1 / Positive Negative Home / Pnh: Positive direction first, then negative direction with return to initial position 2 / Negative Positive Home / nPh: Negative direction first, then positive direction with return to initial position 3 / Positive Home / P-h: Positive direction only with return to initial position 4 / Positive / P--: Positive direction only without return to initial position 5 / Negative Home / n-h: Negative direction only with return to initial position 6 / Negative / n--: Negative direction only without return to initial position Changed settings become active the next time the motor moves.	- 1 1 6	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302F:4 _h Modbus 12040 Profibus 12040 CIP 147.1.4
AT_dis_usr	Movement range for Autotuning Range within which the control parameters are automatically optimized. The range is entered with reference to the current position. NOTE: In the case of "Movement in one direction only" (Parameter AT_dir), the specified range is used for each optimization step. The actual movement typically corresponds to 20 times the value, but it is not limited. The minimum value, the factory setting and the maximum value depend on the scaling factor. Available as of firmware version V01.03 Changed settings become active the next time the motor moves.	usr_p 1 32768 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 302F:12 _h Modbus 12068 Profibus 12068 CIP 147.1.18

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
AT_dis	<p>Movement range for Autotuning</p> <p>Range within which the control parameters are automatically optimized. The range is entered with reference to the current position.</p> <p>NOTE: In the case of "Movement in one direction only" (Parameter AT_dir), the specified range is used for each optimization step. The actual movement typically corresponds to 20 times the value, but it is not limited.</p> <p>The parameter AT_dis_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.1 revolution.</p> <p>Changed settings become active the next time the motor moves.</p>	<p>revolution</p> <p>1.0</p> <p>2.0</p> <p>999.9</p>	<p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 302F:3_h</p> <p>Modbus 12038</p> <p>Profibus 12038</p> <p>CIP 147.1.3</p>
AT_mechanical	<p>Type of coupling of the system</p> <p>1 / Direct Coupling: Direct coupling</p> <p>2 / Belt Axis: Belt axis</p> <p>3 / Spindle Axis: Spindle axis</p> <p>Changed settings become active the next time the motor moves.</p>	<p>-</p> <p>1</p> <p>2</p> <p>3</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 302F:E_h</p> <p>Modbus 12060</p> <p>Profibus 12060</p> <p>CIP 147.1.14</p>
AT_start	<p>Autotuning start</p> <p>Value 0: Terminate</p> <p>Value 1: Activate EasyTuning</p> <p>Value 2: Activate ComfortTuning</p> <p>Changed settings become active immediately.</p>	<p>-</p> <p>0</p> <p>-</p> <p>2</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 302F:1_h</p> <p>Modbus 12034</p> <p>Profibus 12034</p> <p>CIP 147.1.1</p>

7.6.12 Enhanced settings for autotuning

The following parameters allow you to monitor and influence autotuning.

The parameters `AT_state` and `AT_progress` allow you to monitor the progress (in percent) and the status of autotuning.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_AT_state</code>	Autotuning status Bit assignments: Bits 0 ... 10: Last processing step Bit 13: <code>auto_tune_process</code> Bit 14: <code>auto_tune_end</code> Bit 15: <code>auto_tune_err</code>	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302F:2 _h Modbus 12036 Profibus 12036 CIP 147.1.2
<code>_AT_progress</code>	Progress of Autotuning	% 0 0 100	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302F:B _h Modbus 12054 Profibus 12054 CIP 147.1.11

If, in a test run, you want to check the effects of harder or softer settings of the controller parameters on your system, you can write the parameter `CTRL_GlobGain` to modify the settings determined during autotuning. The parameter `_AT_J` allows you to read the moment of inertia of the entire system calculated during autotuning.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_GlobGain $\sigma P \rightarrow t_{un-}$ GR, n	<p>Global gain factor (affects parameter set 1)</p> <p>The global gain factor affects the following parameters of controller parameter set 1:</p> <ul style="list-style-type: none"> - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAUref <p>The global gain factor is set to 100%</p> <ul style="list-style-type: none"> - if the controller parameters are set to default - at the end of the Autotuning process - if the controller parameter set 2 is copied to set 1 via the parameter CTRL_ParSetCopy <p>NOTE: If a full configuration is transmitted via the fieldbus, the value for CTRL_GlobGain must be transmitted prior to the values of the controller parameters CTRL_KPn, CTRL_TNn, CTRL_KPp and CTRL_TAUref. If CTRL_GlobGain is changed during a configuration transmission, CTRL_KPn, CTRL_TNn, CTRL_KPp and CTRL_TAUref must also be part of the configuration.</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p>	% 5.0 100.0 1000.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:15 _h Modbus 4394 Profibus 4394 CIP 117.1.21
_AT_M_friction	<p>Friction torque of the system</p> <p>Is determined during Autotuning.</p> <p>In increments of 0.01 A_{rms}.</p>	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302F:7 _h Modbus 12046 Profibus 12046 CIP 147.1.7
_AT_M_load	<p>Constant load torque</p> <p>Is determined during Autotuning.</p> <p>In increments of 0.01 A_{rms}.</p>	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 302F:8 _h Modbus 12048 Profibus 12048 CIP 147.1.8
_AT_J	<p>Moment of inertia of the complete system</p> <p>Is automatically calculated during Autotuning.</p> <p>In increments of 0.1 kg cm².</p>	kg cm ² 0.1 0.1 6553.5	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 302F:C _h Modbus 12056 Profibus 12056 CIP 147.1.12

The parameter `AT_wait` lets you set a waiting time between the individual autotuning steps. Setting a waiting time is only useful in the case of a low-rigidity coupling, in particular so if the next autotuning step (changing the hardness) is already performed while the system is still settling.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
AT_wait	Waiting time between Autotuning steps Changed settings become active the next time the motor moves.	ms 300 500 10000	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302F:9 _h Modbus 12050 Profibus 12050 CIP 147.1.9

7.7 Controller optimization with step response

7.7.1 Controller structure

The controller structure corresponds to the classical cascaded closed loop with current controller, velocity controller and position controller. In addition, the reference value of the velocity controller can be smoothed via a filter.

The controllers are tuned one after the other from the "inside" to the "outside" in the following sequence: current control, velocity control, position control. The superimposed control loop remains off.

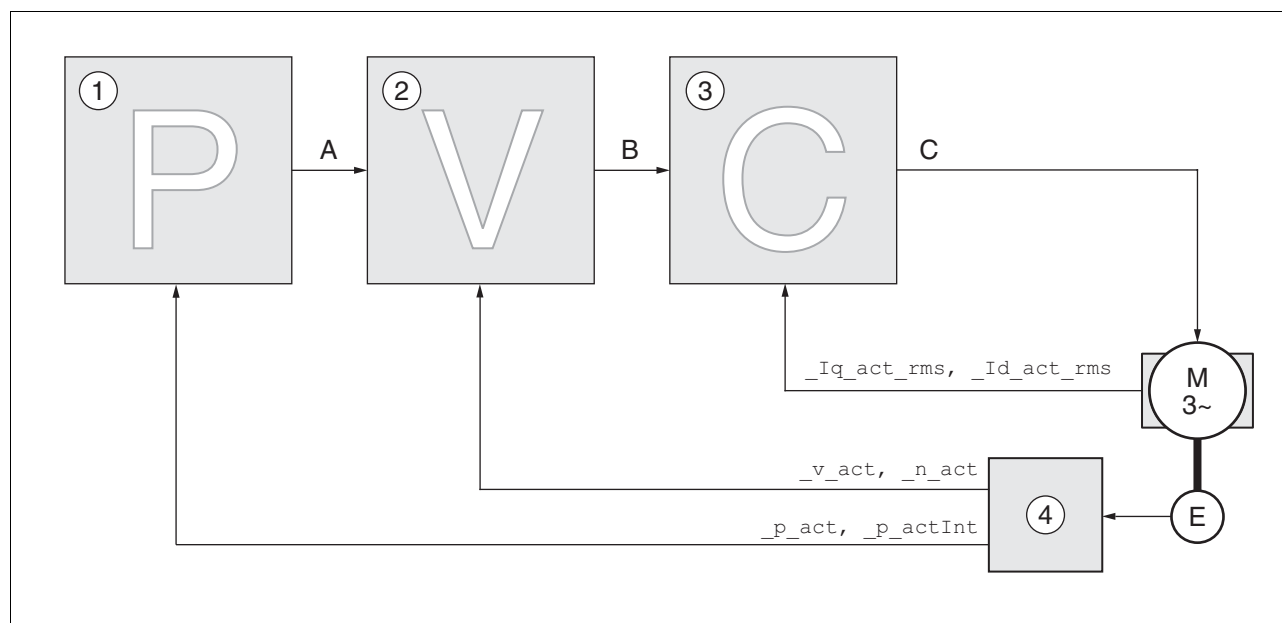


Figure 7.13 Controller structure

- (1) Position controller
- (2) Velocity controller
- (3) Current controller
- (4) Encoder evaluation

See chapter 8.5.5 "Setting the controller parameters" for a detailed description of the controller structure.

Current controller The current controller determines the torque of the motor. The current controller is automatically optimally tuned with the stored motor data.

Velocity controller The velocity controller controls the motor velocity by varying the motor current depending on the load situation. The velocity controller has a decisive influence on the dynamic response of the drive. The dynamics of the velocity controller depend on:

- Moment of inertia of the drive and the controlled system
- Power of the motor
- Stiffness and elasticity of the elements in the flow of forces
- Backlash of the drive elements
- Friction

Position controller The position controller reduces the difference between the reference position and the actual position of the motor (position deviation) to a minimum. When the motor is at a standstill, the position deviation is close to zero in the case of a well-tuned position controller.

An optimized velocity control loop is a prerequisite for good amplification of the position controller.

7.7.2 Optimization

The drive optimization function matches the device to the application conditions. The following options are available:

- Selecting control loops. Superimposed control loops are automatically deactivated.
- Defining reference value signals: signal type, amplitude, frequency and starting point
- Testing control performance with the signal generator.
- Recording the control performance on screen and evaluating it with the commissioning software.

Setting reference value signals ► Start controller optimization with the commissioning software.
 ► Set the following values for the reference value signal:

- Signal type: Step "positive"
 - Amplitude: 100 1/min
 - Cycle duration: 100 ms
 - Number of repetitions: 1
- Start recording



Only the signal types "Step" and "Square" allow you to determine the entire dynamic behavior of a control loop. The manual shows signal paths for the signal type "Step".

- Entering controller values* The optimization steps described on the following pages require you to enter control loop parameters and test their effect by triggering a step function.
- A step function is triggered as soon as you start recording in the commissioning software.
- You can enter controller values for optimization in the parameters window in the "Control" group.
- Controller parameter sets* This device allows you to use two controller parameter sets. It is possible to switch from one set of controller parameters to the other during operation. The active controller parameter set is selected with the parameter CTRL_SelParSet.
- The corresponding parameters are CTRL1_xx for the first controller parameter set and CTRL2_xx for the second controller parameter set. The following descriptions use the notation CTRL1_xx (CTRL2_xx) if there are no functional differences between the two controller parameter sets.

7.7.3 Optimizing the velocity controller

Optimum settings of complex mechanical control systems require hands-on experience with controller tuning. This includes the ability to calculate control loop parameters and to apply identification procedures.

Less complex mechanical systems can often be successfully optimized by means of experimental adjustment using the aperiodic limit method. The following parameters are used for this:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_KPn [onF → dr[- Pn1	Velocity controller P gain The default value is calculated on the basis of the motor parameters. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.0001 A/min ⁻¹ . Changed settings become active immediately.	A/min ⁻¹ 0.0001 - 1.2700	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:1 _h Modbus 4610 Profibus 4610 CIP 118.1.1
CTRL2_KPn [onF → dr[- Pn2	Velocity controller P gain The default value is calculated on the basis of the motor parameters. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.0001 A/min ⁻¹ . Changed settings become active immediately.	A/min ⁻¹ 0.0001 - 1.2700	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:1 _h Modbus 4866 Profibus 4866 CIP 119.1.1
CTRL1_TNn [onF → dr[- tn1	Velocity controller integral action time The default value is calculated on the basis of CTRL_TAUiref. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 - 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:2 _h Modbus 4612 Profibus 4612 CIP 118.1.2
CTRL2_TNn [onF → dr[- tn2	Velocity controller integral action time The default value is calculated on the basis of CTRL_TAUiref. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 - 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:2 _h Modbus 4868 Profibus 4868 CIP 119.1.2

Check and optimize the calculated values in a second step, as described on page 187.

Determining the mechanical system of the system

To assess and optimize the transient response behavior of your system, group its mechanical system into one of the following two categories.

- System with rigid mechanical system
- System with a less rigid mechanical system

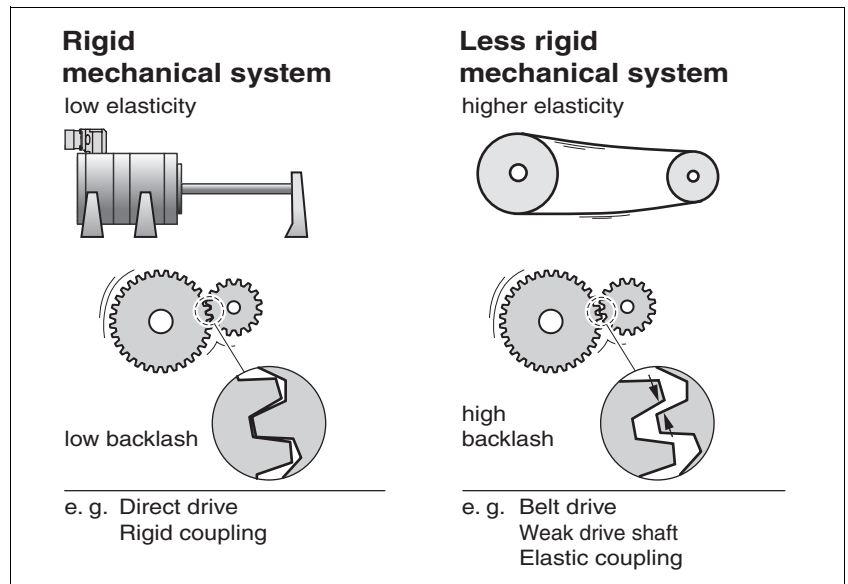


Figure 7.14 Rigid and less rigid mechanical systems

- Couple the motor and the mechanical system
- If you use limit switches: verify the function of the limit switches after installation of the motor.

Switching of the reference value filter of the velocity controller

The reference value filter of the velocity controller allows you to improve the transient response at optimized velocity control. The reference value filter must be switched off for the first setup of the velocity controller.

- Deactivate the reference value filter of the velocity controller. Set the parameter CTRL1_TAUnref (CTRL2_TAUnref) to the lower limit value "0".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_TAUnref [onF → dr[- tRu1	Filter time constant of the reference velocity value filter This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 9.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:4 _h Modbus 4616 Profibus 4616 CIP 118.1.4
CTRL2_TAUnref [onF → dr[- tRu2	Filter time constant of the reference velocity value filter This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 9.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:4 _h Modbus 4872 Profibus 4872 CIP 119.1.4

NOTE: The procedure for optimization of the settings is only a suggestion. It is the responsibility of the user to decide whether the method is suitable for the actual application.

Determining controller parameter values for rigid mechanical systems

In the case of a rigid mechanical system, adjusting the control performance on the basis of the table is possible if:

- the moment of inertia of the load and of the motor are known and
- the moment of inertia of the load and of the motor are constant

The P gain CTRL_KPn and the integral action time CTRL_TNn depend on:

- J_L : moment of inertia of the load
- J_M : moment of inertia of the motor

- Determine the controller parameter values using Table 7.1:

	$J_L = J_M$		$J_L = 5 * J_M$		$J_L = 10 * J_M$	
J_L [kgcm ²]	KPn	TNn	KPn	TNn	KPn	TNn
1	0.0125	8	0.008	12	0.007	16
2	0.0250	8	0.015	12	0.014	16
5	0.0625	8	0.038	12	0.034	16
10	0.125	8	0.075	12	0.069	16
20	0.25	8	0.15	12	0.138	16

Table 7.1 Determining controller values

Determining controller parameter values for rigid mechanical systems

For optimization purposes, determine the P gain of the velocity controller at which the controller adjusts velocity `_v_act` as quickly as possible without overshooting.

- Set the integral action time `CTRL1_TNn` (`CTRL2_TNn`) to infinite (= 327.67 ms).

If a load torque acts on the motor when the motor is at a standstill, the integral action time must not exceed a value that causes uncontrolled change of the motor position.



If the motor is subject to loads when it is at a standstill, setting the integral action time to "infinite" may cause position deviations. Reduce the integral action time if the deviation is unacceptable in your application. However, reducing the integral action time can adversely affect optimization results.

⚠ WARNING

UNEXPECTED MOVEMENT

The step function moves the motor at constant velocity until the specified time has expired.

- Verify that the selected values for velocity and time do not exceed the available distance.
- If possible, use limit switches.
- Verify that a functioning button for emergency stop is within reach.
- Verify that the system is free and ready for the movement before starting the function.

Failure to follow these instructions can result in death, serious injury or equipment damage.

- Initiate a step function.
- After the first test, check the maximum amplitude for the reference value for the current `_Iq_ref`.

Set the amplitude of the reference value just high enough so the reference value for the current `_Iq_ref` remains below the maximum value `CTRL_I_max`. On the other hand, the value selected should not be too low, otherwise friction effects of the mechanical system will determine the performance of the control loop.

- Trigger another step function if you had to modify `_v_ref` and check the amplitude of `_Iq_ref`.
- Increase or decrease the P gain in small increments until `_v_act` is obtained as fast as possible. The following diagram shows the required transient response on the left. Overshooting - as shown on the right - is reduced by reducing `CTRL1_KPn` (`CTRL2_KPn`).

Differences between `_v_ref` and `_v_act` result from setting `CTRL1_TNn` (`CTRL2_TNn`) to "Infinite".

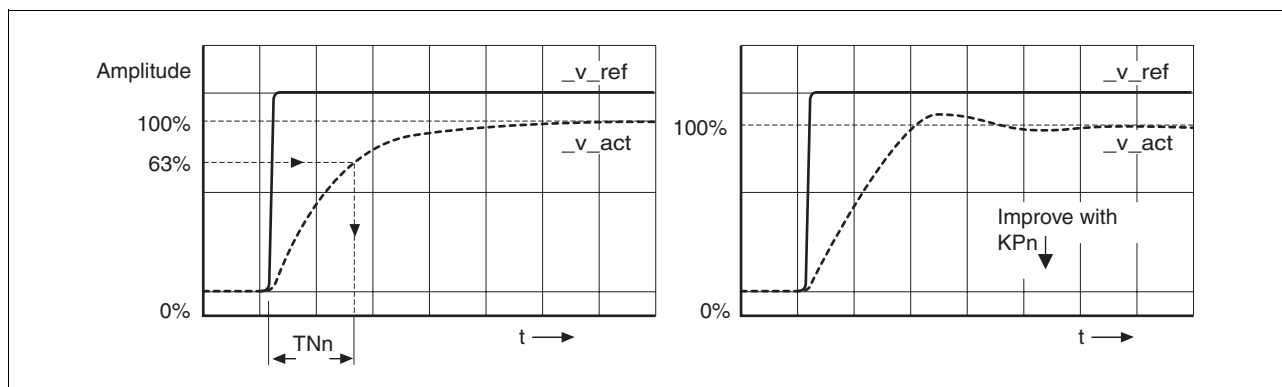


Figure 7.15 Determining "TNn" for the aperiodic limit



In the case of drive systems in which oscillations occur before the aperiodic limit is reached, the P gain "KPn" must be reduced until oscillations can no longer be detected. This occurs frequently in the case of linear axes with a toothed belt drive.

Graphic determination of the 63% value

Graphically determine the point at which the actual velocity `_v_act` reaches 63% of the final value. The integral action time `CTRL1_TNn` (`CTRL2_TNn`) then results as a value on the time axis. The commissioning software supports you with the evaluation:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_TAUiref	Filter time constant of the reference current value filter This parameter is switched gradually over the time defined in <code>CTRL_ParChgTime</code> . In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.50 4.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:5 _h Modbus 4618 Profibus 4618 CIP 118.1.5
CTRL2_TAUiref	Filter time constant of the reference current value filter This parameter is switched gradually over the time defined in <code>CTRL_ParChgTime</code> . In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.50 4.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:5 _h Modbus 4874 Profibus 4874 CIP 119.1.5

7.7.4 Checking and optimizing default settings

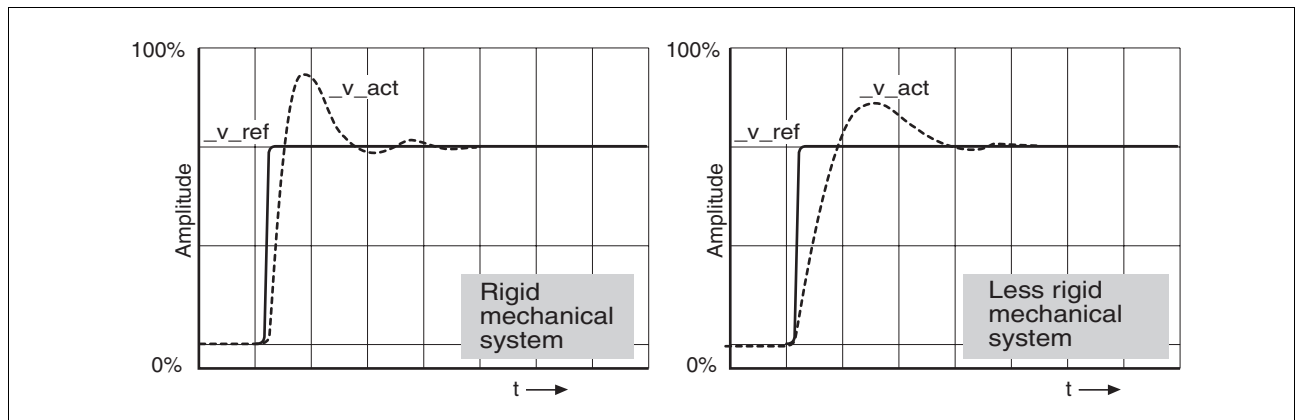


Figure 7.16 Step responses with good control performance

The controller is properly set when the step response is approximately identical to the signal shown. Good control performance is characterized by

- Fast transient response
- Overshooting up to a maximum of 40%, 20% is recommended.

If the control performance does not correspond to the curve shown, change `CTRL_KPn` in increments of about 10% and then trigger another step function:

- If the control is too slow: Use a higher `CTRL1_KPn` (`CTRL2_KPn`) value.
- If the control tends to oscillate: Use a lower `CTRL1_KPn` (`CTRL2_KPn`) value.

Oscillation ringing is characterized by continuous acceleration and deceleration of the motor.

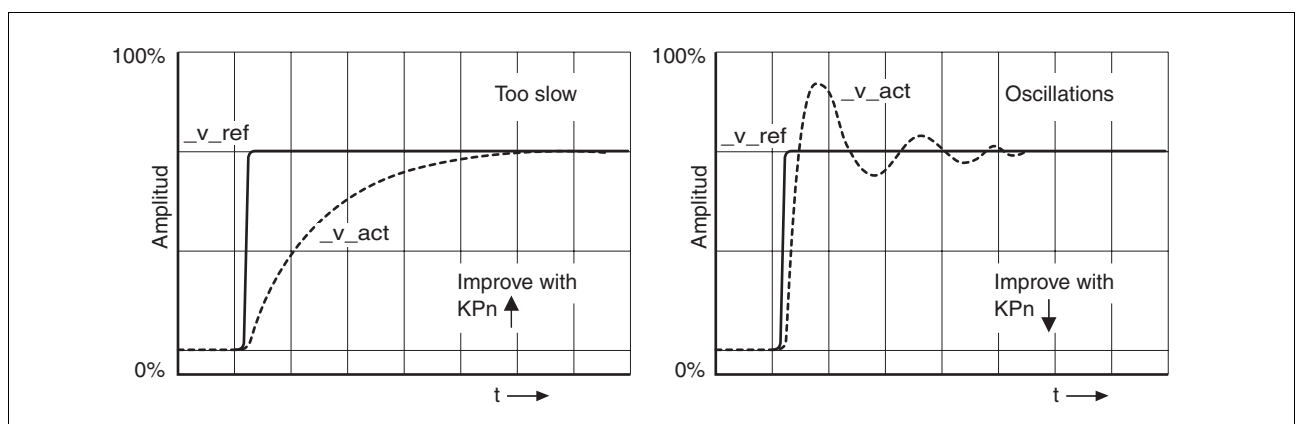


Figure 7.17 Optimizing insufficient velocity controller settings



If the controller performance remains unsatisfactory in spite of optimization, contact your local sales representative.

7.7.5 Optimizing the position controller

Optimization requires good control dynamics in the subordinate velocity control circuit.

When tuning the position controller, you must optimize the P gain CTRL1_KPp (CTRL2_KPp) in two limits:

- CTRL1_KPp (CTRL2_KPp) too high: Overshooting of the mechanical system, instability of the closed-loop control
- CTRL1_KPp (CTRL2_KPp) too low: High position deviation

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_KPp [onF → dr[- PP1	Position controller P gain The default value is calculated. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 1/s. Changed settings become active immediately.	1/s 2.0 - 900.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:3 _h Modbus 4614 Profibus 4614 CIP 118.1.3
CTRL2_KPp [onF → dr[- PP2	Position controller P gain The default value is calculated. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 1/s. Changed settings become active immediately.	1/s 2.0 - 900.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:3 _h Modbus 4870 Profibus 4870 CIP 119.1.3

WARNING

UNEXPECTED MOVEMENT

The step function moves the motor at constant velocity until the specified time has expired.

- Verify that the selected values for velocity and time do not exceed the available distance.
- If possible, use limit switches.
- Verify that a functioning button for emergency stop is within reach.
- Verify that the system is free and ready for the movement before starting the function.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Setting the reference value signal ► Select Position Controller as the reference value in the commissioning software.

► Set the reference signal:

- Signal type: "Step"
- For rotary motors: Set the amplitude to approx. 1/10 motor revolution.

The amplitude is entered in user-defined units. With the default scaling, the resolution is 16384 usr per motor revolution.

Selecting the recording signals ► Select the values in the box General Recording Parameters:

- Reference position of position controller $_p_refusr$ ($_p_ref$)
- Actual position of position controller $_p_actusr$ ($_p_act$)
- Actual velocity $_v_act$
- Current motor current $_Iq_ref$

Controller values for the position controller can be changed in the same parameter group that you already used for the velocity controller.

Optimizing the position controller value

- Trigger a step function with the default controller values.
- After the first test, check the values achieved for $_n_act$ and $_Iq_ref$ for current and velocity control. The values must not reach the current and velocity limitation range.

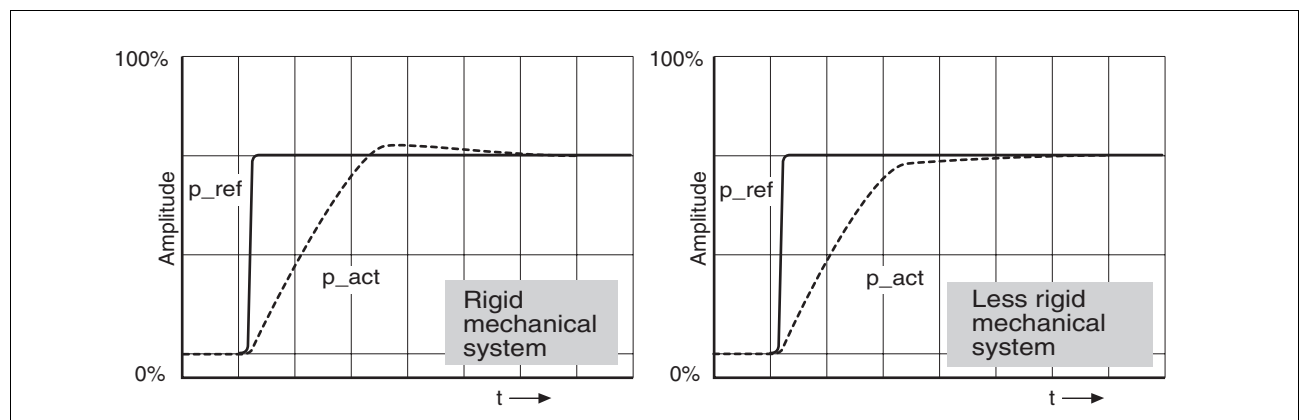


Figure 7.18 Step responses of a position controller with good control performance

The setting of the p gain `CTRL1_KPp` (`CTRL2_KPp`) is optimal if the reference value is reached rapidly and with little or no overshooting.

If the control performance does not correspond to the curve shown, change the P gain `CTRL1_KPp` (`CTRL2_KPp`) in increments of approximately 10% and trigger another step function.

- If the control tends to oscillate: Use a lower KPp value.
- If the actual value is too slow reaching the reference value: Use a higher KPp value.

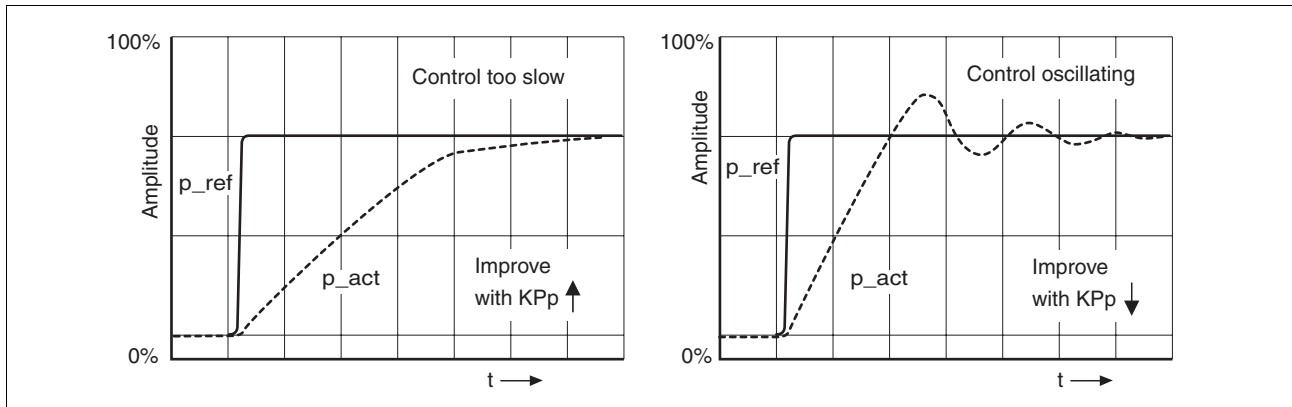


Figure 7.19 Optimizing inadequate position controller settings

7.8 Memory Card

The device features a slot for a memory card. The parameters stored on the memory card can be transferred to other devices. If a device is replaced, a new device of the same type can be operated with identical parameters.

NOTE: The contents of the memory card is only compared to the parameters stored in the device when the device is switched on.

If the parameters on the memory card and in the device are identical, the 7-segment display briefly shows **Err-d** during start-up.

The parameters of the safety module require special treatment. See the module manual of the safety module for additional information.

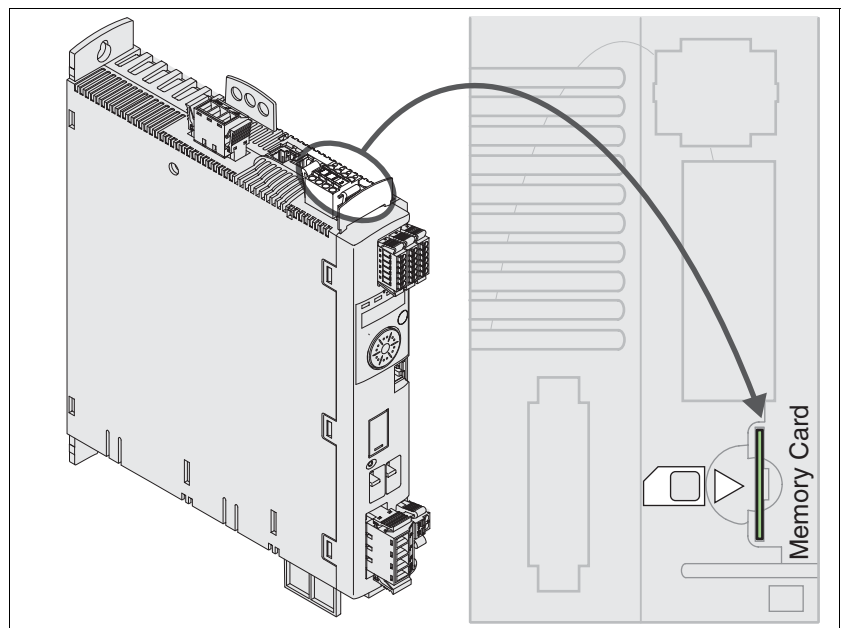


Figure 7.20 Slot for memory card

Note the following:

- Use only genuine accessory memory cards.
- Do not touch the gold contacts.
- The insert/remove cycles of the memory card are limited.
- The memory card can remain in the device.

Inserting a memory card

- The controller supply voltage is switched off.
- Insert the memory card into the device with the gold contacts face down; the slanted corner must be face to the mounting plate.
- Switch on the controller supply voltage.

Observe the 7-segment display during the initialization of the device:

CR-d is displayed	
CR-d is displayed for a short period of time during initialization of the device.	Memory card detected, no user intervention required. The parameter values stored in the device and the contents of the memory card are identical.
CR-d is displayed permanently.	Memory card detected, user intervention required. See chapter 7.8.1 "Data exchange with the memory card", page 193. The parameter values stored in the device and the contents of the memory card are different or the memory card has been removed.
CR-d is not displayed.	No memory card detected. Switch off the controller supply voltage. Verify that the memory card has been properly inserted (contacts, slanted corner).

7.8.1 Data exchange with the memory card

Copying data or ignoring the memory card (Errd, Ignr, ctoad, dtoc)

If there are differences between the parameters on the memory card and the parameters stored in the device, the device stops after initialization and displays **Errd**.

- The 7-segment display shows **Errd**.
- Press the navigation button.
 - ◁ The 7-segment display shows the last setting, for example **Ignr**.
- Briefly press the navigation button to activate the Edit mode.
 - ◁ The 7-segment display continues to display the last setting, the Edit LED lights.
- Select one of the following using the navigation button¹:
 - **Ignr** ignores the memory card.
 - **ctoad** transfers the data from the memory card to the device.
 - **dtoc** transfers the data from the device to the memory card.
- ◁ The device switches to operating state 4 Ready To Switch On.

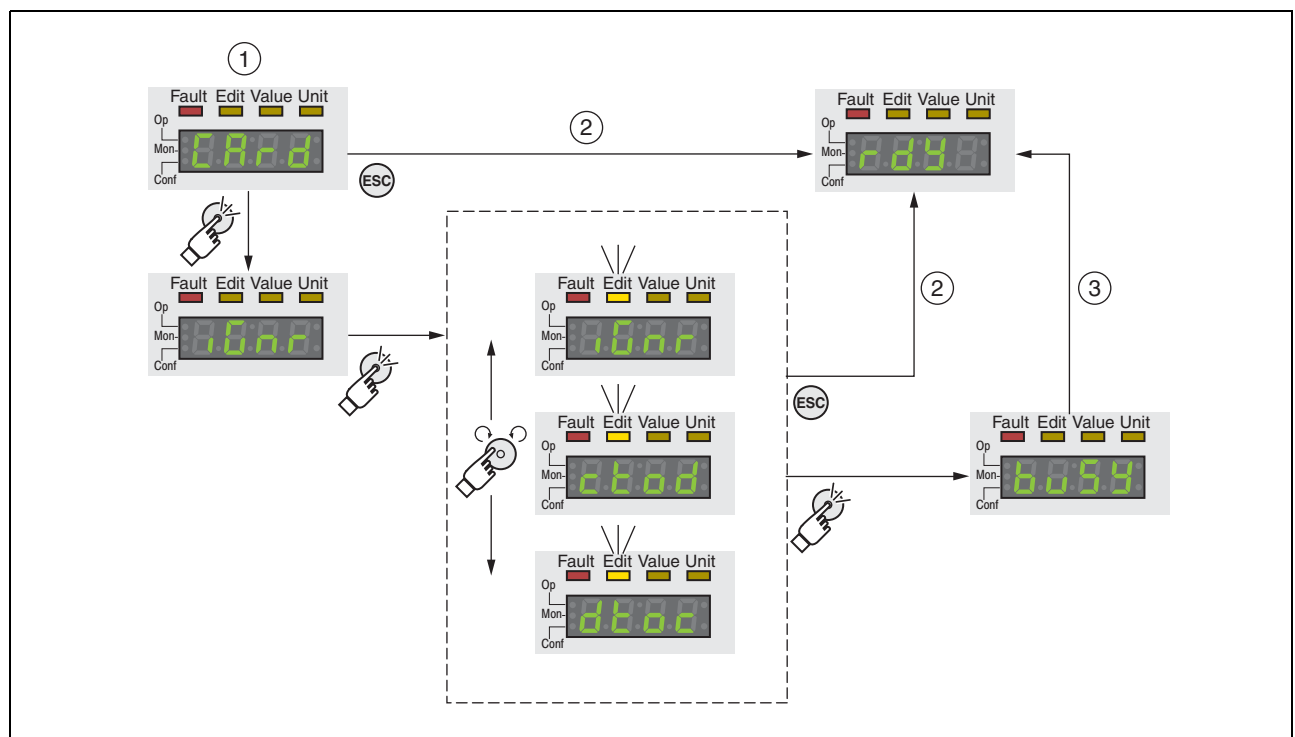


Figure 7.21 Memory card via integrated HMI

- (1) Data on the memory card and in the device are different: The device displays **Errd** and waits for user intervention.
- (2) Transition to operating state 4 Ready To Switch On (memory card is ignored).
- (3) Transfer of data (**ctoad** = card to device, **dtoc** = device to card) and transition to operating state 4 Ready To Switch On.

1. Options may be limited

*Memory card has been removed
(Err 55)*

If you removed the memory card, the device displays Err 55 after initialization. If you confirm this, the display shows n. 55. After you have confirmed this warning, the product switches to the operating state 4 Ready To Switch On..

*Write protection for memory card
(Err, EnPr, di Pr, Pr o t)*

It is possible to write-protect the memory card for LXM 32 (Pr o t). For example, you may want to write-protect memory cards used for regular duplication of device data.

To write-protect the memory card, select Conf - RCU-Err on the HMI.

Selection	Meaning
EnPr	Write protection on (Pr o t)
di Pr	Write protection off

Memory cards can also be write-protected via the commissioning software.

7.9 Duplicating existing device settings

Application and advantage

- Multiple devices are to have the same settings, for example, when devices are replaced.

Prerequisites

Device type, motor type and device firmware must be identical.
Tools for duplication:

- Memory card
- Commissioning software (for Windows)

The controller supply voltage must be switched on at the device.

Duplication using a memory card

Device settings can be stored on a memory card (accessories). The stored device settings can be copied to a device of the same type. Note that the fieldbus address and the settings for the monitoring functions are copied along with this information. See chapter 7.8 "Memory Card", page 191 for additional information.

*Duplication using the
commissioning software*

The commissioning software installed on a PC can save the settings of a device in the form of a configuration file. The stored device settings can be copied to a device of the same type. Note that the fieldbus address and the settings for the monitoring functions are copied along with this information. See the manual for the commissioning software or the on-line help for additional information.

8 Operation

8

The chapter "Operation" describes the basic operating states, operating modes and functions of the device.

⚠ WARNING

UNINTENDED BEHAVIOR

The behavior of the drive system is governed by numerous stored data or settings. Unsuitable settings or data may trigger unexpected movements or responses to signals and disable monitoring functions.

- Do NOT operate the drive system with unknown settings or data.
- Verify that the stored data and settings are correct.
- When commissioning, carefully run tests for all operating states and potential error situations.
- Verify the functions after replacing the product and also after making changes to the settings or data.
- Only start the system if there are no persons or obstructions in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Access channels

8.1 "Access channels"

Control mode

8.2 "Control mode"

Operating states

8.3 "Operating states"

8.3.1 "State diagram"

8.3.2 "State transitions"

8.3.3 "Indication of the operating state"

8.3.4 "Changing the operating state"

Operating modes

8.4 "Operating modes"
8.4.1 "Starting the operating mode"
8.4.2 "Changing the operating mode"
8.4.3 "Operating mode Jog"
8.4.4 "Operating mode Electronic Gear"
8.4.5 "Operating mode Profile Torque"
8.4.6 "Operating mode Profile Velocity"
8.4.7 "Operating mode Profile Position"
8.4.8 "Operating mode Interpolated Position"
8.4.9 "Operating mode Homing"
8.4.10 "Operating mode Motion Sequence"

Movement range

8.5 "Movement range"
8.5.1 "Zero point of the movement range"
8.5.2 "Scaling"
8.5.3 "Movement beyond the movement range"
8.5.4 "Setting a modulo range"

Extended settings

8.6 "Extended settings"
8.6.1 "Setting the PTO interface"
8.6.2 "Setting the digital signal inputs and signal outputs"
8.6.3 "Setting the motion profile for the velocity"
8.6.4 "Setting the controller parameters"
8.6.5 "Settings of parameter _DCOMstatus"

Functions for target value processing

8.7 "Functions for target value processing"
8.7.1 "Stop movement with Halt"
8.7.2 "Stopping a movement with Quick Stop"
8.7.3 "Inverting the analog signal inputs"
8.7.4 "Limitation of the velocity via signal inputs"
8.7.5 "Limitation of the current via signal inputs"
8.7.6 "Jerk limitation"
8.7.7 "Zero Clamp"
8.7.8 "Setting a signal output via parameter"
8.7.9 "Starting a movement via a signal input"
8.7.10 "Position capture via signal input"

Functions for monitoring movements

8.8 "Functions for monitoring movements"
8.8.1 "Limit switches"
8.8.2 "Reference switch"
8.8.3 "Software limit switches"
8.8.4 "Load-dependent position deviation (following error)"
8.8.5 "Motor standstill"
8.8.6 "Torque window"
8.8.7 "Velocity window"
8.8.8 "Standstill window"
8.8.9 "Position register"
8.8.10 "Position deviation window"
8.8.11 "Velocity deviation window"
8.8.12 "Velocity threshold value"
8.8.13 "Current threshold value"

Functions for monitoring internal device signals

8.9 "Functions for monitoring internal device signals"
8.9.1 "Temperature monitoring"
8.9.2 "Monitoring load and overload (I2T monitoring)"
8.9.3 "Commutation monitoring"
8.9.4 "Monitoring of mains phases"
8.9.5 "Ground fault monitoring"

8.1 Access channels

⚠ WARNING

UNINTENDED BEHAVIOR CAUSED BY ACCESS CONTROL

Improper use of access control may cause commands to be triggered or blocked.

- Verify that no unintended behavior is caused as a result of enabling or disabling exclusive access.
- Verify that impermissible access is blocked.
- Verify that required access is available.

Failure to follow these instructions can result in death, serious injury or equipment damage.

The product can be addressed via different access channels. Access channels are:

- Integrated HMI
- Fieldbus
- Commissioning software
- Digital input signals

If several access channels are active at the same time, this may lead to unintended behavior. Access control can be used to limit access to a particular access channel.

The product offers 2 different possibilities of access control.

- Non-exclusive access
- Exclusive access via an access channel

When the product is switched on, there is no exclusive access via an access channel.

Only one access channel can have exclusive access to the product. An exclusive access can be provided via different access channels:

- Via the integrated HMI:

The operating mode Jog or Autotuning can be started via the HMI.

- Via a fieldbus:

Exclusive access is provided to a fieldbus by blocking all other access channels with the parameter `AccessLock`.

- Via the commissioning software:

The commissioning software receives exclusive access via the switch "Exclusive access" in position "On".

The signal input functions "Halt", "Fault Reset", "Enable", "Positive Limit Switch (LIMP)", "Negative Limit Switch (LIMN)" and "Reference Switch (REF)" as well as the signals of the safety function STO (`STO_A` and `STO_B`) are effective during exclusive access.

Access to the product via the HMI (writing parameters) can be revoked by means of the parameter `HMIlocked`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
AccessLock	<p>Locking other access channels</p> <p>Value 0: Allow control via other access channels Value 1: Lock control via other access channels</p> <p>Example: The access channel is used by the fieldbus. In this case, control via the commissioning software or the HMI is not possible.</p> <p>The access channel can only be locked after the current operating mode has terminated.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3001:E _h Modbus 284 Profibus 284 CIP 101.1.14
HMIlocked	<p>Lock HMI</p> <p>0 / Not Locked / \negLoc: HMI not locked 1 / Locked / Loc: HMI locked</p> <p>The following functions can no longer be started when the HMI is locked:</p> <ul style="list-style-type: none"> - Parameter change - Jog - Autotuning - Fault Reset <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303A:1 _h Modbus 14850 Profibus 14850 CIP 158.1.1

8.2 Control mode

The control mode determines whether the operating states are changed and the operating modes started and changed via the signal inputs or via the fieldbus.

In local control mode, the operating states are changed and the operating modes started and changed via the digital signal inputs.

In fieldbus control mode, the operating states are changed and the operating modes started and changed via the fieldbus.

Availability The following table provides an overview of the operating modes available in the different control modes.

Operating mode	Local control mode	Fieldbus control mode
Jog	Available ¹⁾	Available
Electronic Gear	Available ¹⁾	Available
Profile Torque	Available ^{1) 2)}	Available
Profile Velocity	Available ^{1) 2)}	Available
Profile Position	Not available	Available
Interpolated Position	Not available	Available
Homing	Not available	Available
Motion Sequence	Available	Available

1) Available as of firmware version $\geq V01.08$

2) Only possible with IOM1 module

Setting the control mode The parameter `DEVcmdinterf` lets you set the control mode.

► Set the desired control mode with the parameter `DEVcmdinterf`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>DEVcmdinterf</code> <code>CONF → REG- nonE</code> <code>dEUC</code>	Specification of the control mode 1 / Local Control Mode / \square : Local control mode 2 / Fieldbus Control Mode / $Fb5$: Fieldbus control mode Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:1 _h Modbus 1282 Profibus 1282 CIP 105.1.1

8.3 Operating states

8.3.1 State diagram

After switching on and when an operating mode is started, the product goes through a number of operating states.

The state diagram (state machine) shows the relationships between the operating states and the state transitions.

The operating states are monitored and influenced by internal monitoring functions and system functions such as temperature monitoring or current monitoring.

Graphical representation The state diagram is represented as a flow chart.

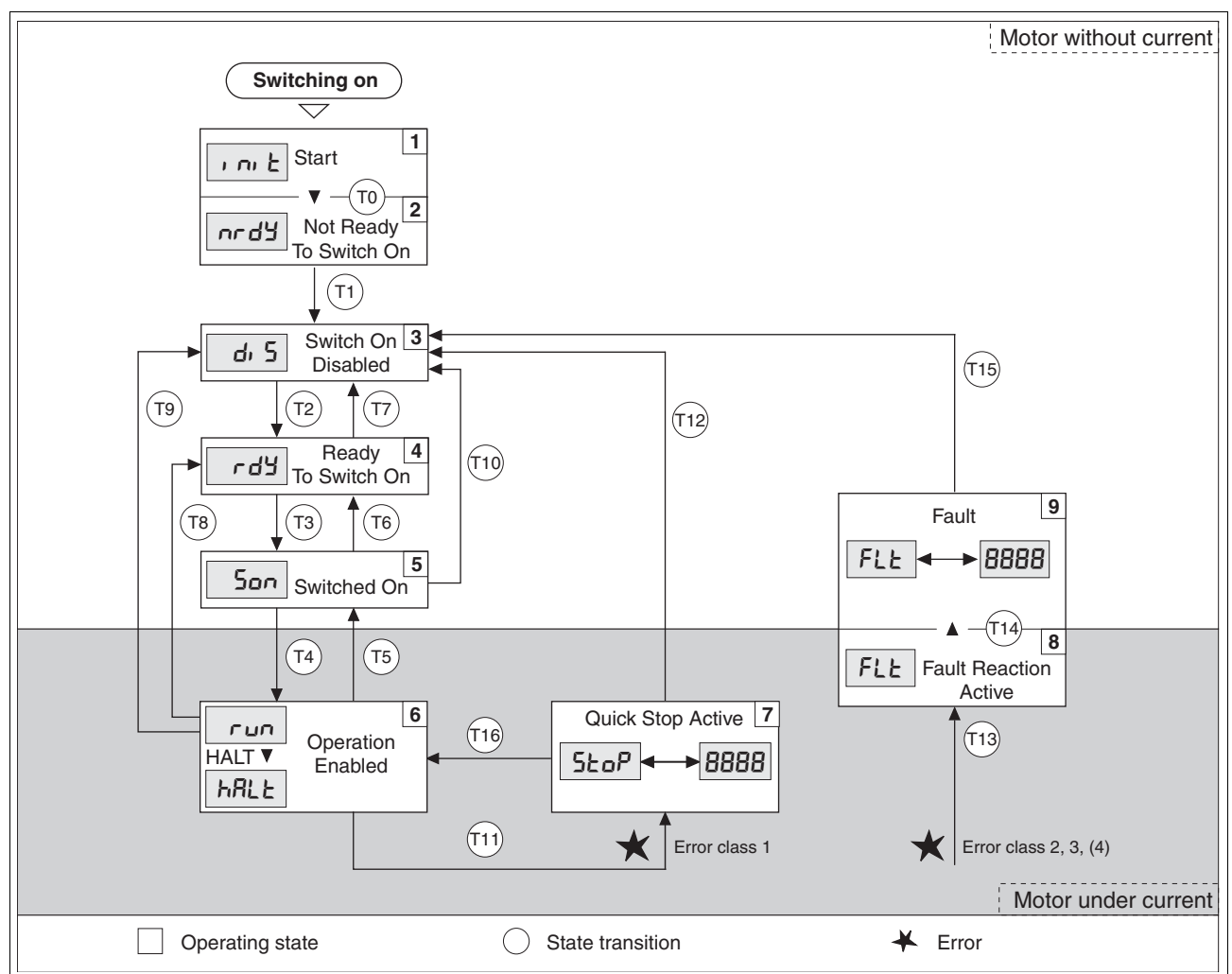


Figure 8.1 State diagram

Operating states

Operating state	Description
1 Start	Controller supply voltage switched on Electronics are initialized
2 Not Ready To Switch On	The power stage is not ready to switch on
3 Switch On Disabled	Impossible to enable the power stage
4 Ready To Switch On	The power stage is ready to switch on.
5 Switched On	Power stage is switched on
6 Operation Enabled	Power stage is enabled Selected operating mode is active
7 Quick Stop Active	"Quick Stop" is being executed
8 Fault Reaction Active	Error response is active
9 Fault	Error response terminated Power stage is disabled

Error class The product triggers an error response if an error occurs. Depending upon the severity of the error, the device responds in accordance with one of the following error classes:

Error class	Response	Meaning
0	Warning	A monitoring function has detected a problem. No interruption of the movement.
1	"Quick Stop"	Motor stops with "Quick Stop", the power stage remains enabled.
2	"Quick Stop" with switch-off	Motor stops with "Quick Stop", the power stage is disabled after standstill has been achieved.
3	Fatal error	The power stage is immediately disabled without stopping the motor first.
4	Uncontrolled operation	The power stage is immediately disabled without stopping the motor first. The error can only be reset by switching off the product.

Error response The state transition T13 (error class 2, 3 or 4) initiates an error response as soon as an internal occurrence signals an error to which the device must react.

Error class	State from -> to	Response
2	x -> 8	Stop movement with "Quick Stop" Holding brake is applied Power stage is disabled
3, 4 or Safety function STO	x -> 8 -> 9	Power stage is disabled immediately, even if "Quick Stop" is still active.

An error can be triggered by a temperature sensor, for example. The product cancels the running movement and performs an error response, for example stopping with "Quick Stop" or disabling the power stage. Subsequently, the operating state changes to **9** Fault.

To exit the **9** Fault operating state, the cause of the error must be remedied and a Fault Reset must be executed.

Resetting an error message A "Fault Reset" resets an error message.



In the event of a "Quick Stop" triggered by an error of class 1 (operating state 7 Quick Stop Active), a "Fault Reset" causes a direct transition to operating state 6 Operation Enabled.

8.3.2 State transitions

State transition	Operating state	Condition / event ¹⁾	Response
T0	1 -> 2	<ul style="list-style-type: none"> Device electronics successfully initialized 	
T1	2 -> 3	<ul style="list-style-type: none"> Parameter successfully initialized 	
T2	3 -> 4	<ul style="list-style-type: none"> No undervoltage Encoder successfully checked Actual velocity: <1000 min⁻¹ STO signals = +24V Fieldbus command: Shutdown ²⁾ 	
T3	4 -> 5	<ul style="list-style-type: none"> Request for enabling the power stage Fieldbus command: Switch On or Enable Operation 	
T4	5 -> 6	<ul style="list-style-type: none"> Automatic transition Fieldbus command: Enable Operation 	Power stage is enabled User-defined parameters are checked Holding brake is released (if available)
T5	6 -> 5	<ul style="list-style-type: none"> Fieldbus command: Disable Operation 	Motion command is canceled with "Halt" Holding brake is applied Power stage disabled
T6	5 -> 4	<ul style="list-style-type: none"> Fieldbus command: Shutdown 	
T7	4 -> 3	<ul style="list-style-type: none"> Undervoltage STO signals = 0V Actual velocity: >1000 min⁻¹ (for example by external driving force) Fieldbus command: Disable Voltage 	-
T8	6 -> 4	<ul style="list-style-type: none"> Fieldbus command: Shutdown 	Power stage is immediately disabled.
T9	6 -> 3	<ul style="list-style-type: none"> Request for disabling the power stage Fieldbus command: Disable Voltage 	Power stage is immediately disabled.
T10	5 -> 3	<ul style="list-style-type: none"> Request for disabling the power stage Fieldbus command: Disable Voltage 	
T11	6 -> 7	<ul style="list-style-type: none"> Error of error class 1 Fieldbus command: Quick Stop 	Motion command is canceled with "Quick Stop".
T12	7 -> 3	<ul style="list-style-type: none"> Request for disabling the power stage Fieldbus command: Disable Voltage 	Power stage is disabled immediately, even if "Quick Stop" is still active.
T13	x -> 8	<ul style="list-style-type: none"> Error of error classes 2, 3 or 4 	Error response is carried out, see "Error Response"
T14	8 -> 9	<ul style="list-style-type: none"> Error response terminated (error class 2) Error of error classes 3 or 4 	

State transition	Operating state	Condition / event ¹⁾	Response
T15	9-> 3	<ul style="list-style-type: none"> Function: "Fault Reset" 	Error is reset (cause of error must be corrected).
T16	7 -> 6	<ul style="list-style-type: none"> Function: "Fault reset" Fieldbus command: Enable Operation ³⁾ 	

- 1) In order to trigger a state transition it is sufficient if one condition is met
2) Only required with fieldbus CANopen and parameter DCOMcompatib= 1
3) Possible only if operating state was triggered via the fieldbus

8.3.3 Indication of the operating state

Information on the operating state is available via the HMI and the signal outputs

The table below provides an overview.

Operating state	HMI	"No fault" ¹⁾	"Active" ²⁾
1 Start	start	0	0
2 Not Ready To Switch On	nr dy	0	0
3 Switch On Disabled	di s	0	0
4 Ready To Switch On	rd y	1	0
5 Switched On	son	1	0
6 Operation Enabled	run	1	1
7 Quick Stop Active	stop	0	0
8 Fault Reaction Active	FLt	0	0
9 Fault	FLt	0	0

1) The signal output function is factory setting for DQ0

2) The signal output function is the factory setting for DQ1

Descriptions of how to indicate the operating states via a fieldbus can be found in the fieldbus manual.

8.3.4 Changing the operating state

8.3.4.1 HMI

An error message can be reset via the HMI.

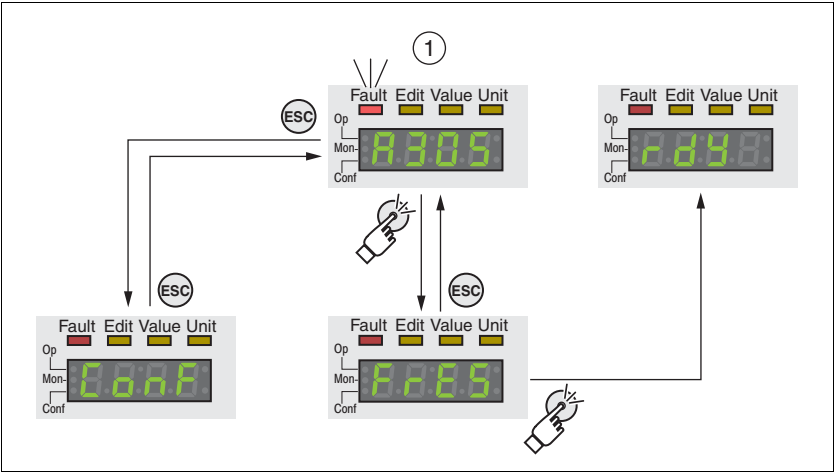


Figure 8.2 Reseting an error message

In the case of an error of error class 1, resetting the error message causes a transition from operating state 7 Quick Stop Active back to operating state 6 Operation Enabled.

In the case of an error of error classes 2 or 3, resetting the error message causes a transition from operating state 9 Fault back to operating state 3 Switch On Disable.

8.3.4.2 Signal inputs

The operating states can only be changed via the signal inputs in local control mode.

Signal input function "Enable"

The power stage is enabled by means of the signal input function "Enable".

"Enable"	State transition
Rising edge	Enable power stage T3
Falling edge	Disable power stage T9 and T12

The signal input function "Enable" is the factory setting for DI0.

Signal input function "Fault Reset"

The signal input function "Fault Reset" is used to reset an error message.

"Fault Reset"	State transition
Rising edge	Resetting an error message T15 and T16

The signal input function "Fault Reset" is the factory setting for DI1.

8.3.4.3 Fieldbus

The operating states can only be changed via the fieldbus in fieldbus control mode.

Descriptions of how to change the operating states via a fieldbus can be found in the fieldbus manual.

8.4 Operating modes

8.4.1 Starting the operating mode

In local control mode, the parameter `IOdefaultMode` is used to set the desired operating mode.

The selected operating mode is starting by enabling the power stage.

► Set the operating mode with the parameter `IOdefaultMode`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IOdefaultMode</code> [onF] → [ELG-] , on-1	<p>Operating mode</p> <p>0 / None / none: None 1 / Profile Torque / TorQ: Profile Torque 2 / Profile Velocity / VELP: Profile Velocity 3 / Electronic Gear / GEAR: Electronic Gear 5 / Jog / Jog: Jog 6 / Motion Sequence / MotS: Motion Sequence</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:3 _h Modbus 1286 Profibus 1286 CIP 105.1.3

In fieldbus control mode, the desired operating mode is set via the fieldbus.

Descriptions of how to start and change operating modes via the fieldbus can be found in the fieldbus manual.

8.4.2 Changing the operating mode

The operating mode can be changed after the current operating mode has been terminated.

In addition, it is also possible to change the operating mode during a running movement; however, this is only possible in certain operating modes.

Changing the operating mode during a movement

You can switch between the following operating modes during a running movement.

- Jog
- Electronic Gear
- Profile Torque
- Profile Velocity
- Profile Position

The operating mode can be changed while the motor is at a standstill or while the motor is not at a standstill, depending on the new operating mode.

Operating mode to be changed to	Motor standstill
Jog	With motor standstill
Electronic Gear (position synchronization)	With motor standstill
Electronic Gear (velocity synchronization)	Without motor standstill
Profile Torque	Without motor standstill
Profile Velocity	Without motor standstill
Profile Position ¹⁾	Depends on the setting in parameter .PP_OpmChgType

1) Firmware version <V01.04: Only with motor standstill

The motor is decelerated to a standstill via the ramp set in the parameter LIM_HaltReaction, see chapter 8.7.1 "Stop movement with Halt".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PP_OpmChgType	Change to operating mode Profile Position during movements 0 / WithStandStill: Change with standstill 1 / OnTheFly: Change without standstill Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3023:9 _h Modbus 8978 Profibus 8978 CIP 135.1.9

Changing the operating mode via signal input

In local control mode, the signal input function "Operating Mode Switch" is available.

It allows you to switch via a signal input from the operating mode set in the `IOdefaultMode` to the operating mode set in the parameter `IO_ModeSwitch`.

To switch between two operating modes, you must parameterize the signal input function "Operating Mode Switch", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IO_ModeSwitch</code> <i>CONF → REG- mode</i>	Operating mode for signal input function Operating Mode Switch 0 / None / none : None 1 / Profile Torque / Torq : Profile Torque 2 / Profile Velocity / VELP : Profile Velocity 3 / Electronic Gear / GEAR : Electronic Gear Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2F _h Modbus 1630 Profibus 1630 CIP 106.1.47

8.4.3 Operating mode Jog

Availability See chapter 8.2 "Control mode".

Description In the operating mode Jog, a movement is made from the actual motor position in the desired direction.

A movement can be made using one of 2 methods:

- Continuous movement
- Step movement

In addition, the product features 2 parameterizable velocities.

Continuous movement As long as the signal for the direction ("Jog Positive" or "Jog Negative") is available, a movement is made in the desired direction.

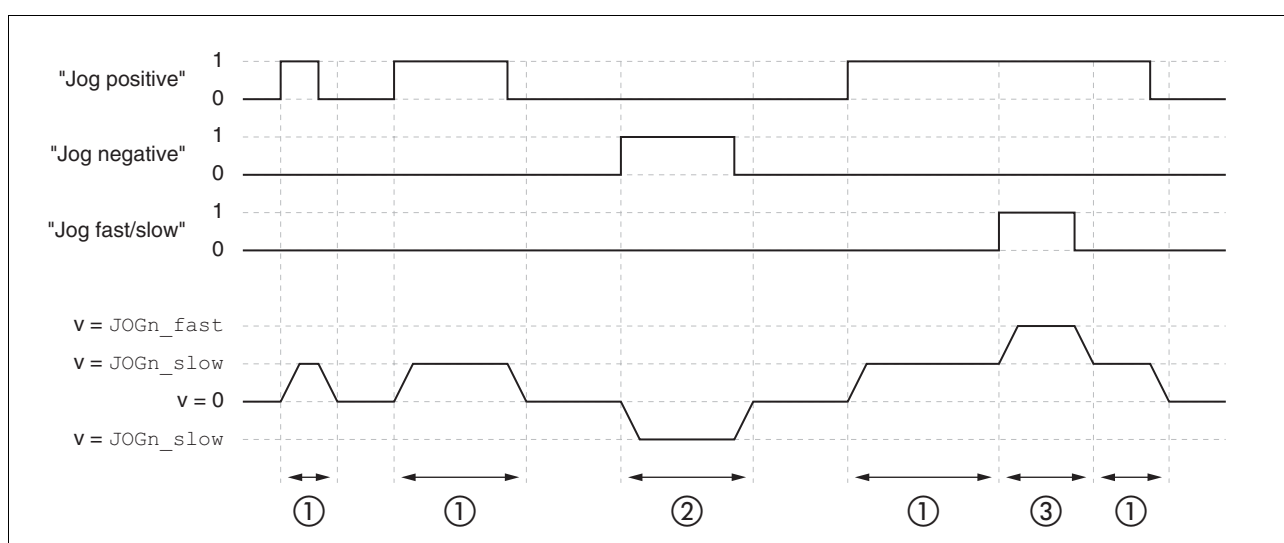


Figure 8.3 Continuous movement

- (1) Slow movement in positive direction
- (2) Slow movement in negative direction
- (3) Fast movement in positive direction

Step movement If the signal for the direction ("Jog Positive" or "Jog Negative") is available, a movement with a parameterizable number of user-defined units is made in the desired direction. After this movement, the motor stops for a defined time. Then a continuous movement is made in the desired direction.

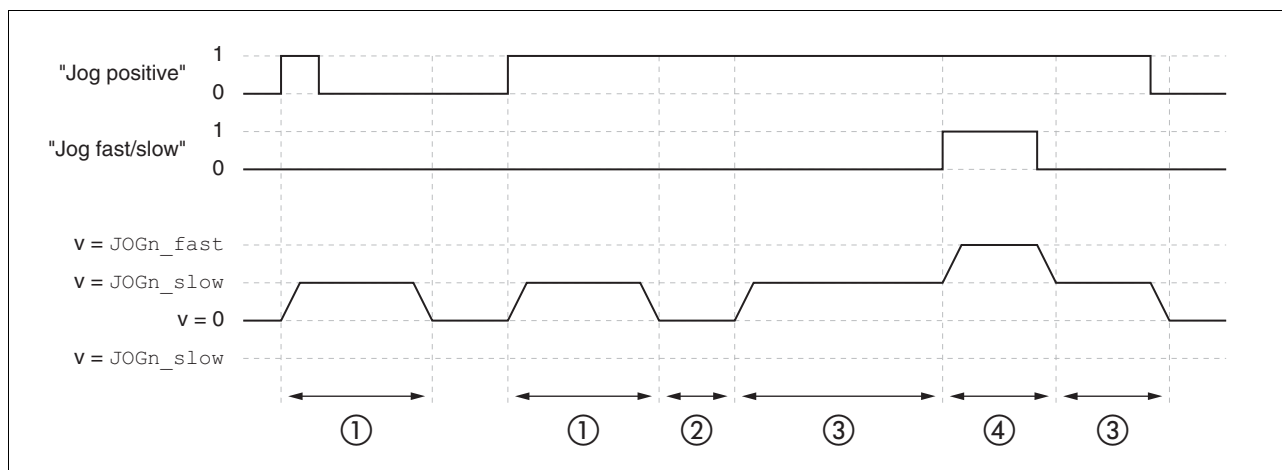


Figure 8.4 Step movement

- (1) Slow movement in positive direction with a parameterizable number of user-defined units $JOGstep$
- (2) Waiting time $JOGtime$
- (3) Slow continuous movement in positive direction
- (4) Fast continuous movement in positive direction

Starting the operating mode

In local control mode, the operating mode must first have been selected, see chapter 8.4.1 "Starting the operating mode". After the power stage is enabled, the operating mode is started automatically.

The power stage is enabled via the signal inputs, see chapter 8.3 "Operating states". The table below provides an overview of the factory settings of the signal inputs:

Signal input	Signal input function
DI0	"Enable" Enable and disable the power stage
DI1	"Fault Reset" Resetting an error message
DI2	"Positive Limit Switch (LIMP)" See chapter 8.8.1 "Limit switches"
DI3	"Negative Limit Switch (LIMN)" See chapter 8.8.1 "Limit switches"
DI4	"Jog Negative" Operating mode Jog: Movement in negative direction
DI5	"Jog Positive" Operating mode Jog: Movement in positive direction

The factory settings of the signal inputs depend on the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In the case of fieldbus control mode, the operating mode is started via the fieldbus. See the fieldbus manual for a description.

Integrated HMI

It is also possible to start the operating mode via the HMI. Calling $\rightarrow \text{OP} \rightarrow \text{JOG} \rightarrow \text{JOG}$ enables the power stage and starts the operating mode.

The method Continuous Movement is controlled via the HMI.

Turn the navigation button to select one of 4 types of movement:

- JOG^+ : slow movement in positive direction
- JOG^- : fast movement in positive direction
- $-\text{JOG}^+$: slow movement in negative direction
- $-\text{JOG}^-$: fast movement in negative direction

Press the navigation button to start the movement.

Terminating the operating mode

In local control mode, the operating mode is automatically terminated by disabling the power stage.

In fieldbus control mode, the operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages In local control mode, information on the operating state and the current movement is available via signal outputs.

In fieldbus control mode, information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	With local control mode: "In Position Deviation Window" See chapter 8.8.10 "Position deviation window" With fieldbus control mode: "Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

The factory settings of the signal outputs depend on the selected control mode and the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.3.1 Parameterization

Overview The illustration below provides an overview of the parameters that can be adjusted in local control mode.

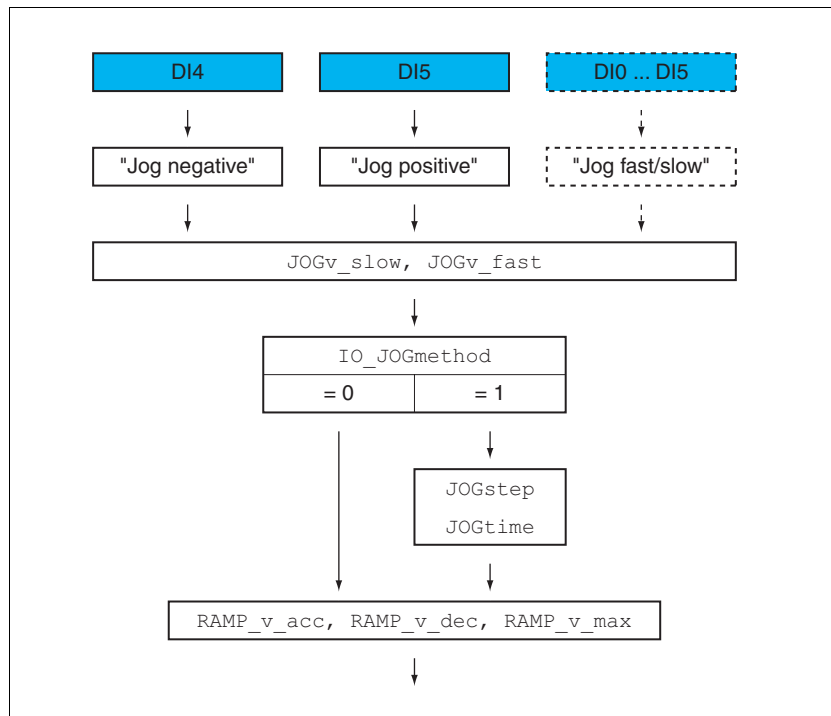


Figure 8.5 Overview of adjustable parameters

The illustration below provides an overview of the parameters that can be adjusted in fieldbus control mode.

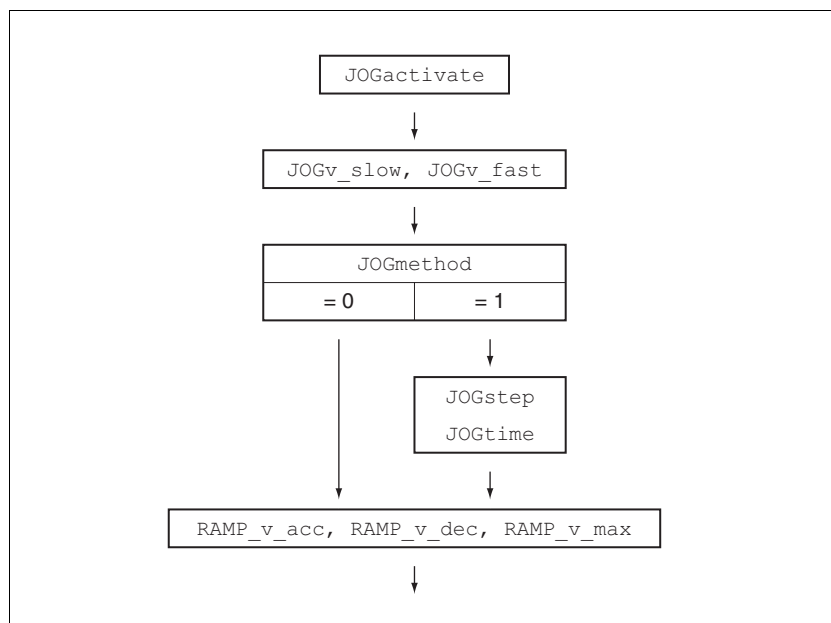


Figure 8.6 Overview of adjustable parameters

Velocities 2 parameterizable velocities are available.

- Set the desired values with the parameters JOGv_slow and JOGv_fast.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
JOGv_slow OP → JOG- JUL O	Velocity for slow movement The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active immediately.	usr_v 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3029:4 _h Modbus 10504 Profibus 10504 CIP 141.1.4
JOGv_fast OP → JOG- JUL h	Velocity for fast movement The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active immediately.	usr_v 1 180 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3029:5 _h Modbus 10506 Profibus 10506 CIP 141.1.5

Switching between velocities In local control mode, the signal input function "Jog Fast/Slow" is available. It allows you to switch between the two velocities via a signal input.

To switch between the two velocities, you must parameterize the signal input function "Jog Fast/Slow", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

Selection of the method In local control mode, the parameter IO_JOGmethod is used to set the method.

- Set the desired method with the parameter IO_JOGmethod.

In fieldbus control mode, the parameter JOGmethod is used to set the method.

- Set the desired method with the parameter JOGmethod.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IO_JOGmethod CONF → REG- IOJG	Selection of jog method 0 / Continuous Movement / continuous: Jog with continuous movement 1 / Step Movement / step: Jog with step movement Changed settings become active the next time the motor moves.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:18 _h Modbus 1328 Profibus 1328 CIP 105.1.24
JOGmethod	Selection of jog method 0 / Continuous Movement / continuous: Jog with continuous movement 1 / Step Movement / step: Jog with step movement Changed settings become active immediately.	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3029:3 _h Modbus 10502 Profibus 10502 CIP 141.1.3

Setting the step movement The parameters JOGstep and JOGtime are used to set the parameterizable number of user-defined units and the time for which the motor is stopped.

- Set the desired values with the parameters JOGstep and JOGtime.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
JOGstep	Distance for step movement Changed settings become active the next time the motor moves.	usr_p 1 20 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3029:7 _h Modbus 10510 Profibus 10510 CIP 141.1.7
JOGtime	Wait time for step movement Changed settings become active the next time the motor moves.	ms 1 500 32767	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3029:8 _h Modbus 10512 Profibus 10512 CIP 141.1.8

Changing the motion profile for the velocity It is possible to change the parameterization of the motion profile for the velocity, see chapter 8.6.3 "Setting the motion profile for the velocity".

8.4.3.2 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.6 "Jerk limitation"
- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.4 "Load-dependent position deviation (following error)"
- Chapter 8.8.5 "Motor standstill"
- Chapter 8.8.8 "Standstill window"

This function is only available for a step movement.

- Chapter 8.8.9 "Position register"
- Chapter 8.8.10 "Position deviation window"
- Chapter 8.8.11 "Velocity deviation window"
- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.4.4 Operating mode Electronic Gear

Availability See chapter 8.2 "Control mode".

Description In the operating mode Electronic Gear, movements are carried out according to externally supplied reference value signals. A new position value is calculated on the basis of these reference value signals plus an adjustable gear ratio. The reference value signals can be A/B signals, P/D signals or CW/CCW signals.

A movement can be made using one of 3 methods:

- Position synchronization without compensation movement

In the case of position synchronization without compensation movement, the movement is made synchronously (position synchronicity) with the supplied reference value signals. Reference value signals supplied during an interruption caused by Halt or by an error of error class 1 are not considered.

- Position synchronization with compensation movement

In the case of position synchronization with compensation movement, the movement is made synchronously (position synchronicity) with the supplied reference value signals. Reference value signals supplied during an interruption caused by Halt or by an error of error class 1 are considered and compensated for.

- Velocity synchronization

In the case of velocity synchronization, the movement is made synchronously (velocity synchronicity) with the supplied reference value signals.

Internal units The position value for the movement depends on the internal units.
The internal units are 131072 increments per revolution.

Starting the operating mode

In local control mode, the operating mode must first have been selected, see chapter 8.4.1 "Starting the operating mode". After the power stage is enabled, the operating mode is started automatically.

The power stage is enabled via the signal inputs, see chapter 8.3 "Operating states". The table below provides an overview of the factory settings of the signal inputs:

Signal input	Signal input function
DI0	"Enable" Enable and disable the power stage
DI1	"Fault Reset" Resetting an error message
DI2	"Positive Limit Switch (LIMP)" See chapter 8.8.1 "Limit switches"
DI3	"Negative Limit Switch (LIMN)" See chapter 8.8.1 "Limit switches"
DI4	"Gear Ratio Switch" Switch between 2 parameterizable gear ratios
DI5	"Halt" See chapter 8.7.1 "Stop movement with Halt"

The factory settings of the signal inputs depend on the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In the case of fieldbus control mode, the operating mode is started via the fieldbus. See the fieldbus manual for a description.

Terminating the operating mode

In local control mode, the operating mode is automatically terminated by disabling the power stage.

In fieldbus control mode, the operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages In local control mode, information on the operating state and the current movement is available via signal outputs.

In fieldbus control mode, information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	With local control mode: "In Position Deviation Window" See chapter 8.8.10 "Position deviation window" With fieldbus control mode: "Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

The factory settings of the signal outputs depend on the selected control mode and the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.4.1 Parameterization

Overview The illustration below provides an overview of the parameters that can be adjusted in local control mode.

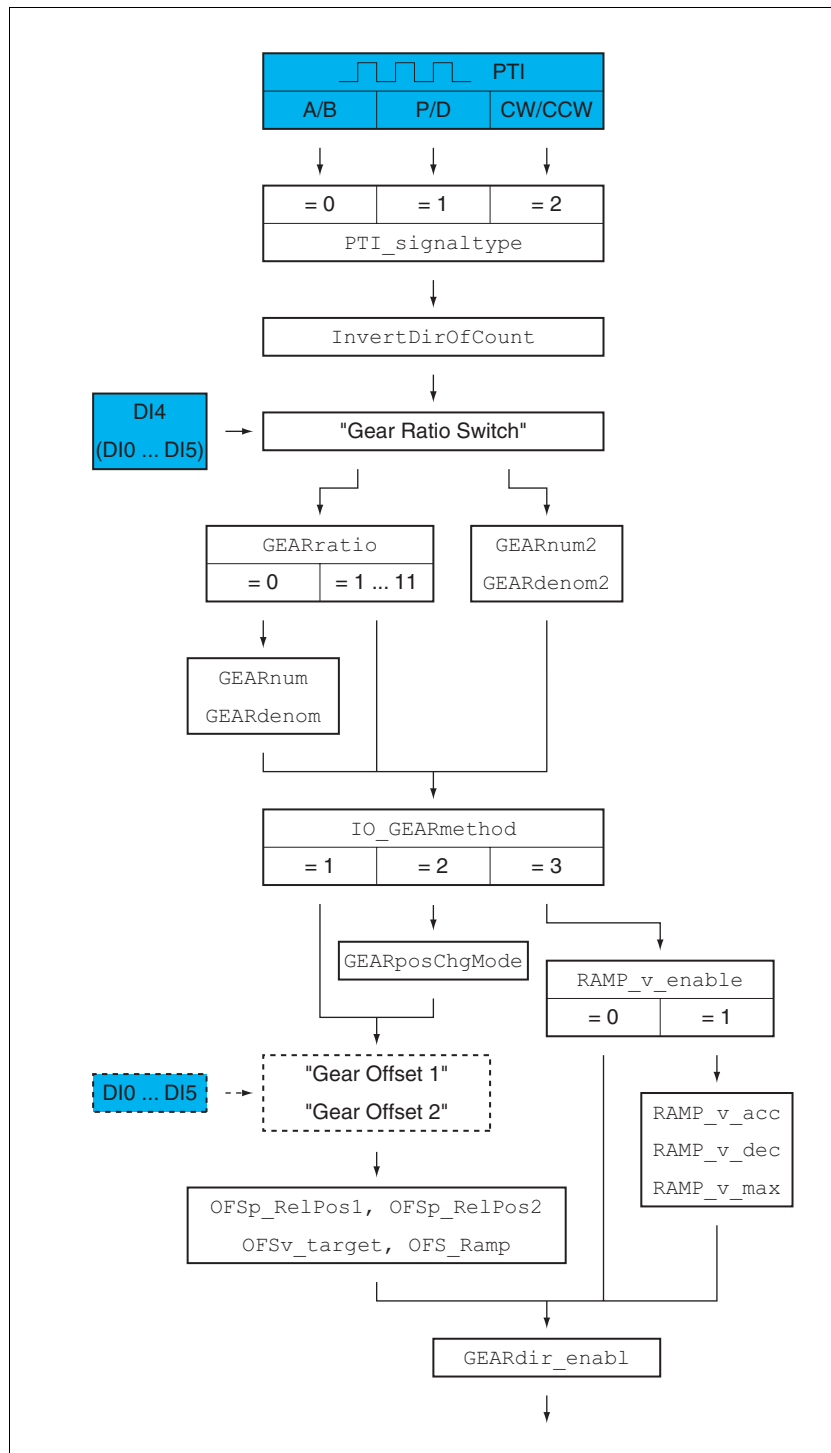


Figure 8.7 Overview of adjustable parameters

The illustration below provides an overview of the parameters that can be adjusted in fieldbus control mode.

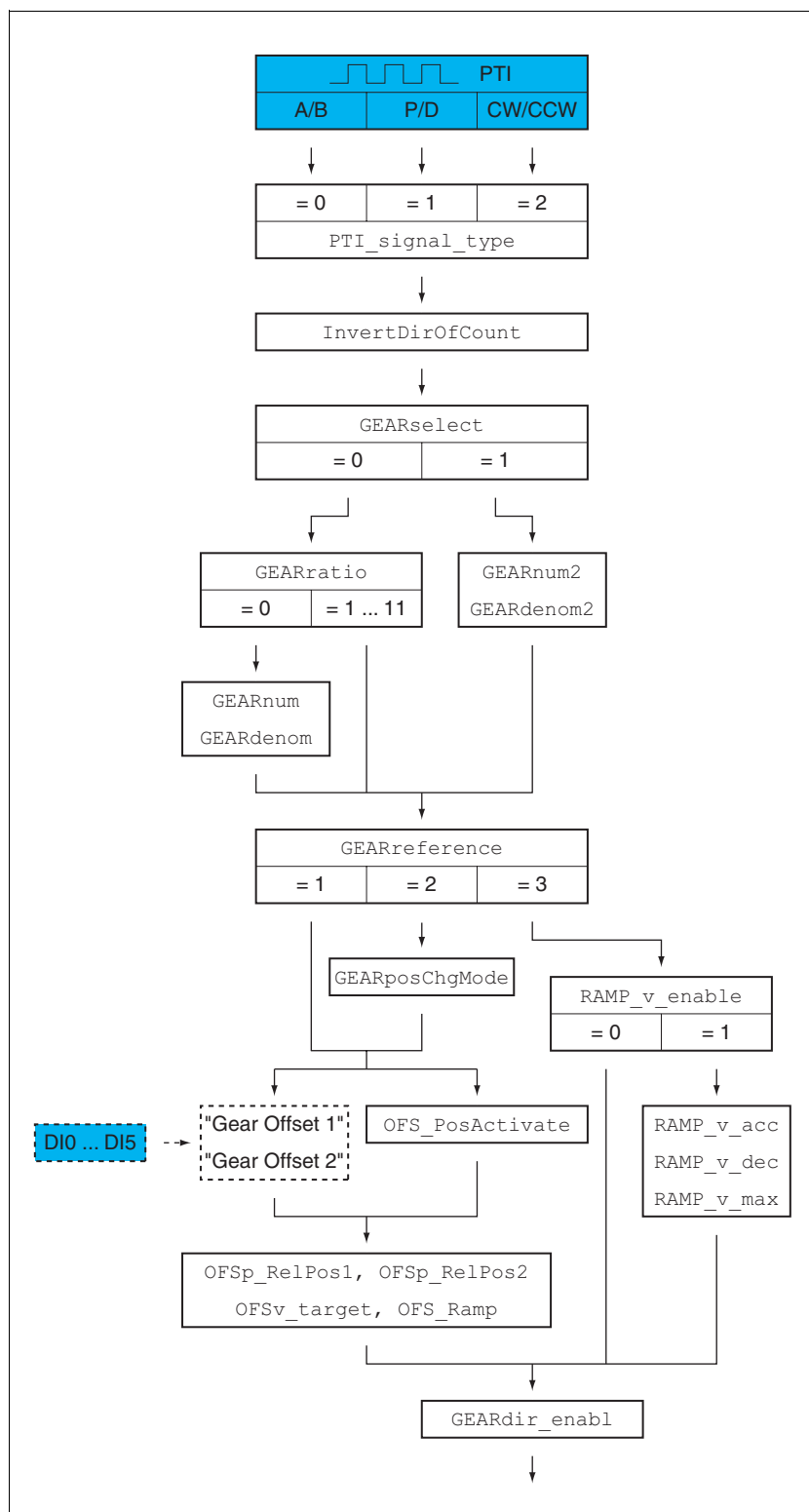


Figure 8.8 Overview of adjustable parameters

Type of reference signals A/B signals, P/D signals or CW/CCW signals can be connected to the PTI connection (Pulse Train In, CN5).

- Set the type of reference value signal with the `PTI_signal_type` parameter.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>PTI_signal_type</code> [onF →, -o- oP,	Selection of signal type for PTI interface 0 / A/B Signals / <i>Rb</i> : Signals ENC_A and ENC_B (quadruple evaluation) 1 / P/D Signals / <i>Pd</i> : Signals PULSE and DIR 2 / CW/CCW Signals / <i>clcc</i> : Signals CW and CCW Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:2 _h Modbus 1284 Profibus 1284 CIP 105.1.2

Inverting the reference value signals The direction of counting of the reference value signals at the PTI interface can be inverted by means of the parameter `InvertDirOfCount`.

- Activate or deactivate inversion of the direction of counting by means of the parameter `InvertDirOfCount`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>InvertDirOf- Count</code>	Inversion of direction of counting at PTI interface 0 / Inversion Off : Inversion of direction of counting is off 1 / Inversion On : Inversion of direction of counting is on Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:7 _h Modbus 2062 Profibus 2062 CIP 108.1.7

Gear ratio The gear ratio is the ratio of the number of motor increments and the number of externally supplied reference increments.

$$\text{Gear factor} = \frac{\text{Motor increments}}{\text{Reference increments}} = \frac{\text{Gear factor numerator}}{\text{Gear factor denominator}}$$

In local control mode, the signal input function "Gear Ratio Switch" allows you to switch between 2 parameterizable gear ratios during operation.

In fieldbus control mode, the parameter `GEARselect` allows you to switch between 2 parameterizable gear ratios during operation.

The parameter `GEARratio` allows you to set a predefined gear ratio. It is also possible to set a parameterizable gear ratio.

The parameterizable gear ratio is defined with the parameters `GEARnum` and `GEARdenom`. A negative numerator value reverses the motor's direction of movement.

- Set the desired gear ratio with the parameters `GEARratio`, `GEARnum`, `GEARdenom`, `GEARnum2` and `GEARdenom2`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>GEARratio</code> <code>Conf → 1-0-</code> <code>GFRC</code>	Selection of special gear ratios 0 / Gear Factor / FRct: Usage of gear ratio adjusted with <code>GEARnum</code> / <code>GEARdenom</code> 1 / 200 / 200: 200 2 / 400 / 400: 400 3 / 500 / 500: 500 4 / 1000 / 1000: 1000 5 / 2000 / 2000: 2000 6 / 4000 / 4000: 4000 7 / 5000 / 5000: 5000 8 / 10000 / 10000: 10000 9 / 4096 / 4096: 4096 10 / 8192 / 8192: 8192 11 / 16384 / 16384: 16384 A change of the reference value by the specified value causes one motor revolution. Changed settings become active immediately.	- 0 0 11	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:6 _h Modbus 9740 Profibus 9740 CIP 138.1.6
<code>GEARselect</code>	Gear ratio selection Switches between two gear ratios: Value 0: Use gear ratio defined by parameter <code>GEARratio</code> Value 1: Use gear ratio from parameters <code>GEARnum2</code> / <code>GEARdenom2</code> Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3026:E _h Modbus 9756 Profibus 9756 CIP 138.1.14

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
GEARnum	Numerator of gear ratio GEARnum ----- = Gear ratio GEARdenom The new gear ratio is applied when the numerator value is supplied. Changed settings become active immediately.	- -2147483648 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:4 _h Modbus 9736 Profibus 9736 CIP 138.1.4
GEARdenom	Denominator of gear ratio See description GEARnum	- 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:3 _h Modbus 9734 Profibus 9734 CIP 138.1.3
GEARnum2	Numerator of gear ratio number 2 GEARnum2 ----- = Gear ratio GEARdenom2 The new gear ratio is applied when the numerator value is supplied. Changed settings become active immediately.	- -2147483648 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:D _h Modbus 9754 Profibus 9754 CIP 138.1.13
GEARdenom2	Denominator of gear ratio number 2 See description GEARnum	- 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:C _h Modbus 9752 Profibus 9752 CIP 138.1.12

Selection of the method The methods specifies the way the movement is to be performed.

- In local control mode, set the desired method with the parameter IO_GEARmethod.
- In fieldbus control mode, set the desired method with the parameter GEARreference.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IO_GEARmethod [onF → RCU- , on	<p>Processing mode for operating mode Electronic Gear</p> <p>1 / Position Synchronization Immediate / P_{on} I: Position synchronization without compensation movement</p> <p>2 / Position Synchronization Compensated / P_{on} C: Position synchronization with compensation movement</p> <p>3 / Velocity Synchronization / UEL_o: Velocity synchronization</p> <p>Changed settings become active the next time the motor moves.</p>	- 1 1 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:17 _h Modbus 1326 Profibus 1326 CIP 105.1.23
GEARreference	<p>Processing mode for operating mode Electronic Gear</p> <p>0 / Deactivated: Deactivated</p> <p>1 / Position Synchronization Immediate: Position synchronization without compensation movement</p> <p>2 / Position Synchronization Compensated: Position synchronization with compensation movement</p> <p>3 / Velocity Synchronization: Velocity synchronization</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 301B:12 _h Modbus 6948 Profibus 6948 CIP 127.1.18

Position change with power stage disabled

If the method "Synchronization With Compensation Movement" is selected, the parameter `GEARposChgMode` determines the way changes to the motor position and to the reference value signals are handled with disabled power stage.

Position changes can be ignored or taken into account during a transition to operating state **6** Operation Enabled.

- Off: Position changes with disabled power stage are ignored.
- On: Position changes with disabled power stage are taken into account.

Position changes between starting the operating mode and the subsequent enabling of the power stage are not taken into account.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
GEARposChgMode	<p>Consideration of position changes with inactive power stage</p> <p>0 / Off: Position changes in states with inactive power stage are discarded.</p> <p>1 / On: Position changes in states with inactive power stage are considered.</p> <p>This setting has an effect only if gear processing is started in the mode 'Synchronization with compensation movement'.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:B _n Modbus 9750 Profibus 9750 CIP 138.1.11

Offset movement

The offset movement allows you to perform a movement with a parameterizable number of increments.

Offset movements are only available for the methods "Position Synchronization Without Compensation Movement" and "Position Synchronization With Compensation Movement".

2 parameterizable offset positions are available. The parameters `OFSp_RelPos1` and `OFSp_RelPos2` are used to set the offset positions.

In local control mode, an offset movement is started via a signal input.

In fieldbus control mode, an offset movement is started via a signal input or via the fieldbus.

To start offset movements via the signal input, you must first parameterize the signal input functions "Gear Offset 1" and "Gear Offset 2", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

The velocity and the acceleration for the offset movement are set via the parameters `OFSpv_target` and `OFSp_Ramp`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
OFSp_RelPos1	Relative offset position 1 for offset movement Changed settings become active immediately.	Inc -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3027:8 _h Modbus 10000 Profibus 10000 CIP 139.1.8
OFSp_RelPos2	Relative offset position 2 for offset movement Changed settings become active immediately.	Inc -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3027:A _h Modbus 10004 Profibus 10004 CIP 139.1.10
OFS_PosActivate	Offset movement with relative offset position This parameter starts an offset movement with one the relative offset positions specified by means of the parameters OFSp_RelPos1 and OFSp_RelPos2. Value 0: No offset movement Value 1: Start offset movement with relative offset position 1 (OFSp_RelPos1) Value 2: Start offset movement with relative offset position 2 (OFSp_RelPos2) Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3027:B _h Modbus 10006 Profibus 10006 CIP 139.1.11
OFSv_target	Target velocity for offset movement The maximum possible value is 5000 if the user-defined scaling factor of the velocity scaling is 1. This applies to all user-defined scaling factors. Example: If the user-defined scaling factor of the velocity scaling is 2 (ScaleVELnum = 2, ScaleVELdenom = 1), the maximum possible value is 2500. Changed settings become active immediately.	usr_v 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3027:4 _h Modbus 9992 Profibus 9992 CIP 139.1.4
OFS_Ramp	Acceleration and deceleration for offset movement Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3027:6 _h Modbus 9996 Profibus 9996 CIP 139.1.6

Changing the motion profile for the velocity

If the method "Velocity Synchronization" is selected, the motion profile for the velocity can be changed.

It is possible to change the parameterization of the motion profile for the velocity, see chapter 8.6.3 "Setting the motion profile for the velocity".

Release of direction Release of direction allows you to limit movements to positive or negative direction. Release of direction is set with the parameter GEARdir_enabl.

- Set the desired directions of movement with the parameter GEARdir_enabl.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
GEARdir_enabl	<p>Enabled movement direction of gear processing</p> <p>1 / Positive: Positive direction 2 / Negative: Negative direction 3 / Both: Both directions</p> <p>This allows you to activate a return movement lock function.</p> <p>Changed settings become active immediately.</p>	- 1 3 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:5 _h Modbus 9738 Profibus 9738 CIP 138.1.5

8.4.4.2 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.6 "Jerk limitation"

This function is only available for the methods "Position Synchronization Without Compensation Movement" and "Position Synchronization With Compensation Movement".

- Chapter 8.7.7 "Zero Clamp"

This function is only available with the method "Velocity Synchronization".

- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.4 "Load-dependent position deviation (following error)"

This function is only available for the methods "Position Synchronization Without Compensation Movement" and "Position Synchronization With Compensation Movement".

- Chapter 8.8.5 "Motor standstill"
- Chapter 8.8.7 "Velocity window"

This function is only available with the method "Velocity Synchronization".

- Chapter 8.8.9 "Position register"
- Chapter 8.8.10 "Position deviation window"

This function is only available for the methods "Position Synchronization Without Compensation Movement" and "Position Synchronization With Compensation Movement".

- Chapter 8.8.11 "Velocity deviation window"

This function is only available with the method "Velocity Synchronization".

- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.4.5 Operating mode Profile Torque

⚠ WARNING

EXCESSIVELY HIGH VELOCITY DUE TO INCORRECT LIMIT VALUE

Without a proper limit value, the motor can reach a very high velocity in this operating mode.

- Check the parameterized velocity limitation.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Availability See chapter 8.2 "Control mode".

Description In the operating mode Profile Torque, a movement is made with a desired target torque.

Starting the operating mode In local control mode, the operating mode must first have been selected, see chapter 8.4.1 "Starting the operating mode". After the power stage is enabled, the operating mode is started automatically.

The power stage is enabled via the signal inputs, see chapter 8.3 "Operating states". The table below provides an overview of the factory settings of the signal inputs:

Signal input	Signal input function
DI0	"Enable" Enable and disable the power stage
DI1	"Fault Reset" Resetting an error message
DI2	"Operating Mode Switch" See chapter 8.4.2 "Changing the operating mode"
DI3	"Velocity Limitation" See chapter 8.7.4 "Limitation of the velocity via signal inputs"
DI4	"Current Limitation" See chapter 8.7.5 "Limitation of the current via signal inputs"
DI5	"Halt" See chapter 8.7.1 "Stop movement with Halt"

The factory settings of the signal inputs depend on the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In the case of fieldbus control mode, the operating mode is started via the fieldbus. See the fieldbus manual for a description.

Terminating the operating mode In local control mode, the operating mode is automatically terminated by disabling the power stage.

In fieldbus control mode, the operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages In local control mode, information on the operating state and the current movement is available via signal outputs.

In fieldbus control mode, information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	With local control mode: "Current Threshold Reached" See chapter 8.8.13 "Current threshold value" With fieldbus control mode: "Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

The factory settings of the signal outputs depend on the selected control mode and the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.5.1 Parameterization

Overview The illustration below provides an overview of the parameters that can be adjusted in local control mode.

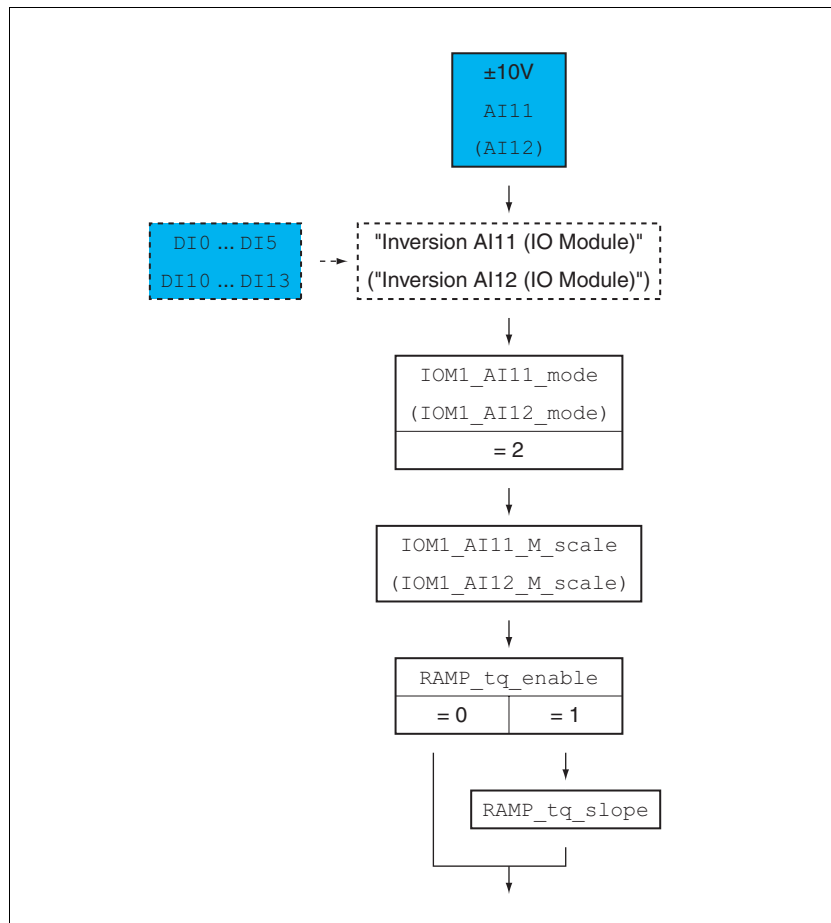


Figure 8.9 Overview of adjustable parameters

The illustration below provides an overview of the parameters that can be adjusted in fieldbus control mode.

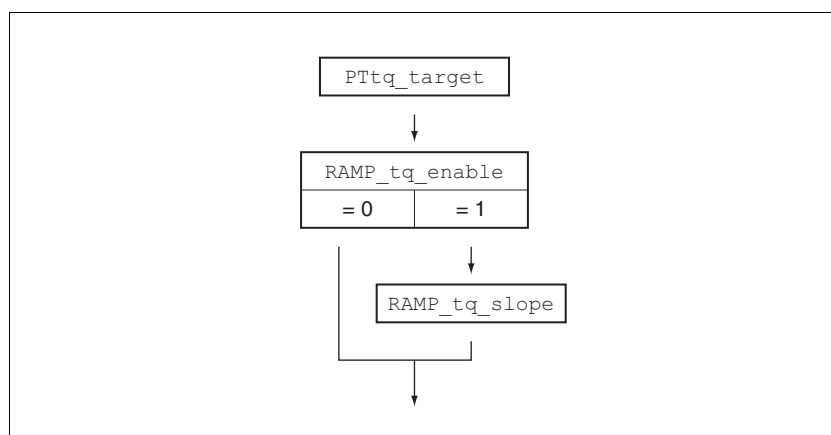


Figure 8.10 Overview of adjustable parameters

Setting the type of usage In local control mode, the parameters IOM1_AI11_mode and IOM1_AI12_mode let you select the type of usage of the analog signal inputs.

- If you do not want to use the analog signal input, set the parameter AI1 to IOM1_AI11_mode the value "Target Torque".

If you do not want to use the analog signal input, set the parameter AI2 to IOM1_AI12_mode the value "Target Torque".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI11_mode [onF →, -o- R i1u	<p>IOM1 Type of usage of AI11</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Ltr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 1 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:E _h Modbus 20252 Profibus 20252 CIP 179.1.14
IOM1_AI12_mode [onF →, -o- R i2u	<p>IOM1 Type of usage of AI12</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Ltr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:13 _h Modbus 20262 Profibus 20262 CIP 179.1.19

Setting the target torque

In local control mode, the parameters `IOM1_AI11_M_scale` and `IOM1_AI12_M_scale` are used to set the target torque for a voltage value of +10V.

- If you want to use the analog signal input AI11, use the parameter `IOM1_AI11_M_scale` to set the desired target torque for a voltage value of +10V.

If you want to use the analog signal input AI12, use the parameter `IOM1_AI12_M_scale` to set the desired target torque for a voltage value of +10V.

In fieldbus control mode, the parameter `PTtq_target` is used to set the target torque.

- Set the desired target torque with the parameter `PTtq_target`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IOM1_AI11_M_scale</code> [onF →, -o- t i l t	IOM1 Target torque at 10 V in operating mode Profile Torque of AI11 100.0 % correspond to the continuous stall torque <code>_M_M_0</code> . By using a negative sign, you can invert the evaluation of the analog signal. In increments of 0.1 %. Changed settings become active immediately. Available as of software version V01.06.00.	% -3000.0 100.0 3000.0	INT16 INT16 INT16 INT16 R/W per. -	CANopen 304F:12 _h Modbus 20260 Profibus 20260 CIP 179.1.18
<code>IOM1_AI12_M_scale</code> [onF →, -o- t i 2,	IOM1 Target torque at 10 V in operating mode Profile Torque of AI12 100.0 % correspond to the continuous stall torque <code>_M_M_0</code> . By using a negative sign, you can invert the evaluation of the analog signal. In increments of 0.1 %. Changed settings become active immediately. Available as of software version V01.06.00.	% -3000.0 100.0 3000.0	INT16 INT16 INT16 INT16 R/W per. -	CANopen 304F:17 _h Modbus 20270 Profibus 20270 CIP 179.1.23
<code>PTtq_target</code>	Target torque for operating mode Profile Torque 100.0 % correspond to the continuous stall torque <code>_M_M_0</code> . In increments of 0.1 %. Changed settings become active immediately.	% -3000.0 0.0 3000.0	INT16 INT16 INT16 INT16 R/W - -	CANopen 6071:0 _h Modbus 6944 Profibus 6944 CIP 127.1.16

Changing the motion profile for the torque It is possible to change the parameterization of the motion profile for the torque.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RAMP_tq_enable	<p>Activation of the motion profile for torque</p> <p>0 / Profile Off: Profile off 1 / Profile On: Profile on</p> <p>The motion profile for torque can be activated or deactivated for the operating mode Profile Torque. In all other operating modes, the motion profile for torque is inactive.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2C _h Modbus 1624 Profibus 1624 CIP 106.1.44
RAMP_tq_slope	<p>Slope setting of the motion profile for torque</p> <p>100.0 % correspond to the continuous stall torque _M_M_0.</p> <p>In increments of 0.1 %/s.</p> <p>Changed settings become active immediately.</p>	%/s 0.1 10000.0 3000000.0	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6087:0 _h Modbus 1620 Profibus 1620 CIP 106.1.42

8.4.5.2 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.5 "Motor standstill"
- Chapter 8.8.6 "Torque window"
- Chapter 8.8.9 "Position register"
- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.4.6 Operating mode Profile Velocity

Availability See chapter 8.2 "Control mode".

Description In the operating mode Profile Velocity, a movement is made with a desired target velocity.

Starting the operating mode In local control mode, the operating mode must first have been selected, see chapter 8.4.1 "Starting the operating mode". After the power stage is enabled, the operating mode is started automatically.

The power stage is enabled via the signal inputs, see chapter 8.3 "Operating states". The table below provides an overview of the factory settings of the signal inputs:

Signal input	Signal input function
DI0	"Enable" Enable and disable the power stage
DI1	"Fault Reset" Resetting an error message
DI2	"Operating Mode Switch" See chapter 8.4.2 "Changing the operating mode"
DI3	"Velocity Limitation" See chapter 8.7.4 "Limitation of the velocity via signal inputs"
DI4	"Zero Clamp" See chapter 8.7.7 "Zero Clamp"
DI5	"Halt" See chapter 8.7.1 "Stop movement with Halt"

The factory settings of the signal inputs depend on the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In the case of fieldbus control mode, the operating mode is started via the fieldbus. See the fieldbus manual for a description.

Terminating the operating mode In local control mode, the operating mode is automatically terminated by disabling the power stage.

In fieldbus control mode, the operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages In local control mode, information on the operating state and the current movement is available via signal outputs.

In fieldbus control mode, information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	With local control mode: "In Velocity Deviation Window" See chapter 8.8.11 "Velocity deviation window" With fieldbus control mode: "Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

The factory settings of the signal outputs depend on the selected control mode and the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.6.1 Parameterization

Overview The illustration below provides an overview of the parameters that can be adjusted in local control mode.

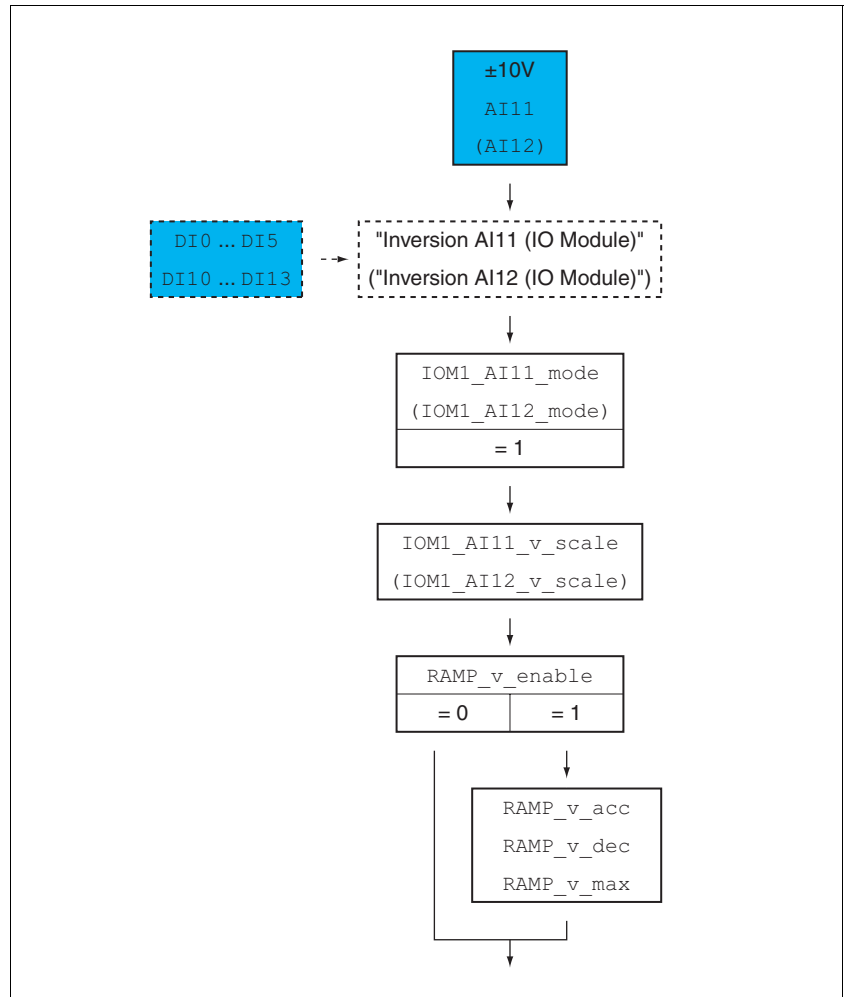


Figure 8.11 Overview of adjustable parameters

The illustration below provides an overview of the parameters that can be adjusted in fieldbus control mode.

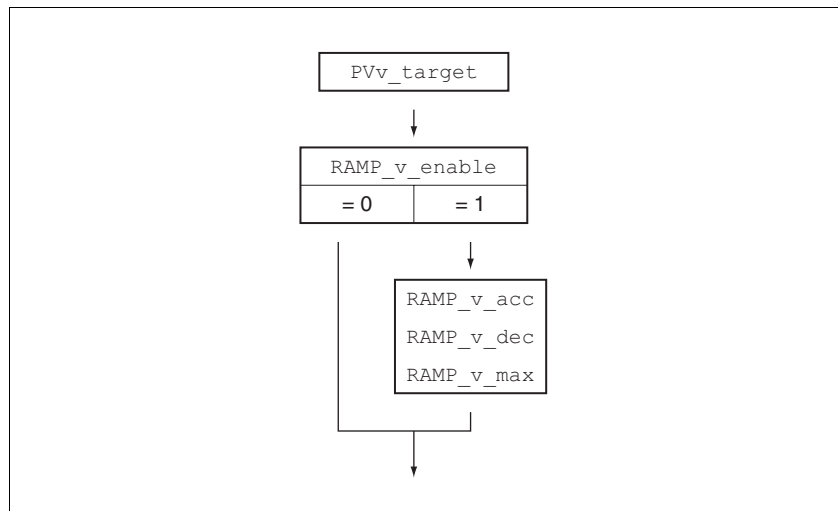


Figure 8.12 Overview of adjustable parameters

Setting the type of usage In local control mode, the parameters IOM1_AI11_mode and IOM1_AI12_mode let you select the type of usage of the analog signal inputs.

- If you do not want to use the analog signal input, set the parameter AI1 to IOM1_AI11_mode the value "Target Velocity".

If you do not want to use the analog signal input, set the parameter AI2 to IOM1_AI12_mode the value "Target Velocity".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI11_mode [onF →, -o- R11u	<p>IOM1 Type of usage of AI11</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / LTr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 1 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:E _h Modbus 20252 Profibus 20252 CIP 179.1.14
IOM1_AI12_mode [onF →, -o- R12u	<p>IOM1 Type of usage of AI12</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / LTr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:13 _h Modbus 20262 Profibus 20262 CIP 179.1.19

Setting the target velocity

In local control mode, the parameters `IOM1_AI11_v_scale` and `IOM1_AI12_v_scale` are used to set the target velocity for a voltage value of +10 V.

- If you want to use the analog signal input AI11, use the parameter `IOM1_AI11_v_scale` to set the desired target velocity for a voltage value of +10V.

If you want to use the analog signal input AI12, use the parameter `IOM1_AI12_v_scale` to set the desired target velocity for a voltage value of +10V.

In fieldbus control mode, the parameter `PVv_target` is used to set the target velocity.

- Set the target velocity with the parameter `PVv_target`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IOM1_AI11_v_scale</code>	<p>IOM1 Target velocity at 10 V in operating mode Profile Velocity of AI11</p> <p>The maximum velocity is limited to the setting in <code>CTRL_v_max</code>.</p> <p>By using a negative sign, you can invert the evaluation of the analog signal.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	<p>usr_v</p> <p>-2147483648</p> <p>6000</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:11_h</p> <p>Modbus 20258</p> <p>Profibus 20258</p> <p>CIP 179.1.17</p>
<code>IOM1_AI12_v_scale</code>	<p>IOM1 Target velocity at 10 V in operating mode Profile Velocity of AI12</p> <p>The maximum velocity is limited to the setting in <code>CTRL_v_max</code>.</p> <p>By using a negative sign, you can invert the evaluation of the analog signal.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	<p>usr_v</p> <p>-2147483648</p> <p>6000</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:16_h</p> <p>Modbus 20268</p> <p>Profibus 20268</p> <p>CIP 179.1.22</p>
<code>PVv_target</code>	<p>Target velocity for operating mode Profile Velocity</p> <p>The target velocity is limited to the setting in <code>CTRL_v_max</code> and <code>RAMP_v_max</code>.</p> <p>Changed settings become active immediately.</p>	<p>usr_v</p> <p>-</p> <p>0</p> <p>-</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 60FF:0_h</p> <p>Modbus 6938</p> <p>Profibus 6938</p> <p>CIP 127.1.13</p>

Changing the motion profile for the velocity

It is possible to change the parameterization of the motion profile for the velocity, see chapter 8.6.3 "Setting the motion profile for the velocity".

8.4.6.2 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.8.5 "Motor standstill"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.7 "Zero Clamp"
- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.7 "Velocity window"
- Chapter 8.8.9 "Position register"
- Chapter 8.8.11 "Velocity deviation window"
- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.4.7 Operating mode Profile Position

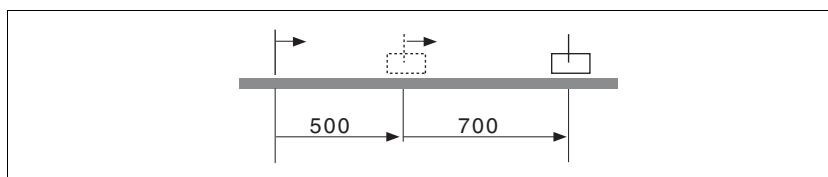
Availability See chapter 8.2 "Control mode".

Description In the operating mode Profile Position, a movement to a desired target position is performed.

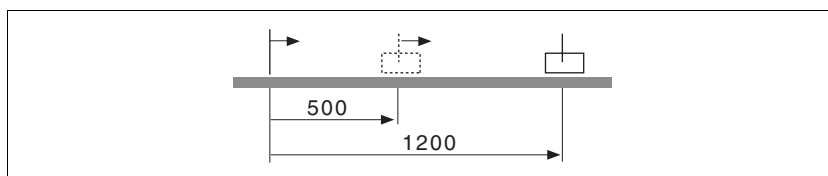
A movement can be made using one of 2 methods:

- Relative movement
- Absolute movement

Relative movement In the case of a relative movement, the movement is relative with reference to the previous target position or the current motor position.



Absolute movement In the case of an absolute movement, the movement is absolute with reference to the zero point.



A zero point must be defined with the operating mode Homing prior to the first absolute movement.

Starting the operating mode The operating mode is started via the fieldbus. See the fieldbus manual for a description.

Terminating the operating mode The operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages Information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	"Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

It is possible to change the factory settings of the signal outputs, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.7.1 Parameterization

Overview The illustration below provides an overview of the adjustable parameters.

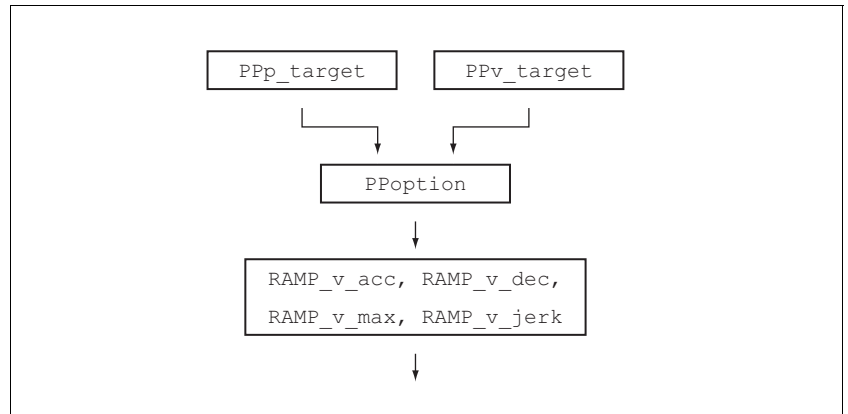


Figure 8.13 Overview of adjustable parameters

Target position The parameter `PPp_target` allows you to enter the target position.

- Set the desired target position with the parameter `PPp_target`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PPp_target	Target position for operating mode Profile Position Minimum/maximum values depend on: - Scaling factor - Software limit switches (if they are activated) Changed settings become active immediately.	usr_p - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 607A:0 _h Modbus 6940 Profibus 6940 CIP 127.1.14

Target velocity The parameter `PPv_target` allows you to set the target velocity.

- Set the target velocity with the parameter `PPv_target`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PPv_target	Target velocity for operating mode Profile Position The target velocity is limited to the setting in <code>CTRL_v_max</code> and <code>RAMP_v_max</code> . Changed settings become active the next time the motor moves.	usr_v 1 60 -	UINT32 UINT32 UINT32 UINT32 R/W - -	CANopen 6081:0 _h Modbus 6942 Profibus 6942 CIP 127.1.15

Selection of the method The parameter `PPoption` allows you to set the method for a relative movement.

- Set the desired method for a relative movement with the parameter `PPoption`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PPoption	Options for operating mode Profile Position Determines the reference position for relative positioning: 0: Relative with reference to the previous target position of the profile generator 1: Not supported 2: Relative with reference to the actual position of the motor Changed settings become active the next time the motor moves.	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 60F2:0h Modbus 6960 Profibus 6960 CIP 127.1.24

Changing the motion profile for the velocity

It is possible to change the parameterization of the motion profile for the velocity, see chapter 8.6.3 "Setting the motion profile for the velocity".

8.4.7.2 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.6 "Jerk limitation"
- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.9 "Starting a movement via a signal input"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.4 "Load-dependent position deviation (following error)"
- Chapter 8.8.5 "Motor standstill"
- Chapter 8.8.8 "Standstill window"
- Chapter 8.8.9 "Position register"
- Chapter 8.8.10 "Position deviation window"
- Chapter 8.8.11 "Velocity deviation window"
- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.4.8 Operating mode Interpolated Position

Availability Available as of firmware version \geq V01.08.

The operating mode is only possible with the CAN fieldbus.

Description In the operating mode Interpolated Position, movements are made to cyclically set reference positions.

The monitoring functions Heartbeat and Node Guarding cannot be used in this operating mode.

- Check cyclical reception of PDOs at the PLC in order to detect an interruption of the connection.

The reference positions are transmitted synchronously with each cycle.
The cycle time of a cycle can be set from 1 ... 20 ms.

The movement to the reference positions starts with the SYNC signal.

The drive performs an internal fine interpolation with a raster of 250 μs .

The illustration below provides an overview:

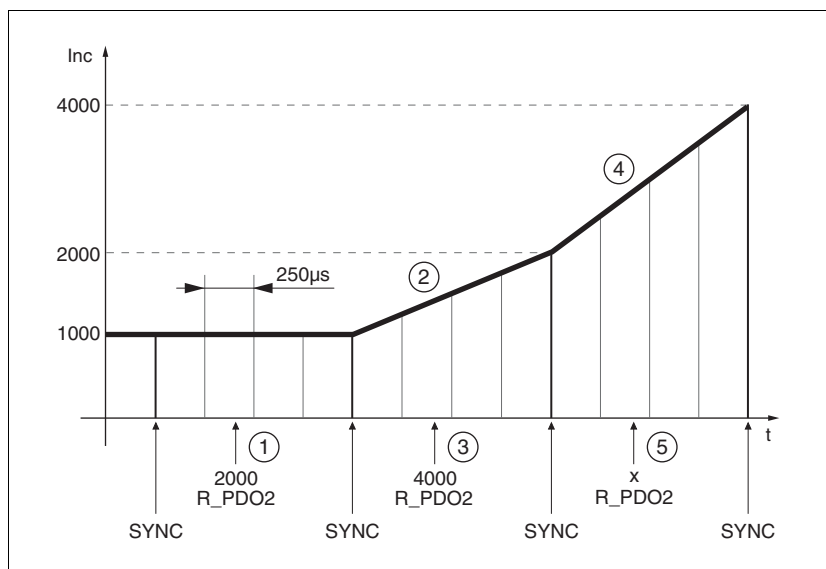


Figure 8.14 Overview

- (1) Transmission of first reference position (example)
- (2) Movement to first reference position
- (3) Transmission of second reference position (example)
- (4) Movement to second reference position
- (5) Transmission of next reference position (example)

Starting the operating mode The operating mode is started via the fieldbus. See the fieldbus manual for a description.

<i>Terminating the operating mode</i>	The operating mode is terminated via the fieldbus. See the fieldbus manual for a description.
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Status messages Information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	"Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

It is possible to change the factory settings of the signal outputs, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.8.1 Parameterization

Cycle time The cycle time is set via the parameters `IP_IntTimPerVal` and `IP_IntTimInd`.

The cycle time depends on the following factors:

- Number of drives
- Baud rate
- Time of the minimum data packets per cycle:
 - SYNC
 - R_PDO2, T_PDO2
 - EMCY (This time must be reserved.)
- Optionally the time of the additional data packets per cycle:
 - R_SDO and T_SDO
The PLC must make sure that the number of requests (R_SDO) and the cycle time match. The response (T_SDO) is transmitted with the next cycle.
 - n_{PDO} - additional R_PDO und T_PDO:
R_PDO1, T_PDO1, R_PDO3, T_PDO3, R_PDO4 and T_PDO4

The table below shows the typical values for the individual data packets, depending on the baud rate:

Data packets	Size in bytes	1 Mbit	500 kbit	250 kbit
R_PDO2	6	0.114 ms	0.228 ms	0.456 ms
T_PDO2	6	0.114 ms	0.228 ms	0.456 ms
SYNC	0	0.067 ms	0.134 ms	0.268 ms
EMCY	8	0.13 ms	0.26 ms	0.52 ms
R_PDOx	8	0.13 ms	0.26 ms	0.52 ms
T_PDOx	8	0.13 ms	0.26 ms	0.52 ms
R_SDO and T_SDO	16	0.26 ms	0.52 ms	1.040 ms

Table 8.1 Data packets and baud rate

In the case of one drive, the minimum cycle time is calculated as follows:

$$t_{\text{cycle}} = \text{SYNC} + R_{\text{PDO2}} + T_{\text{PDO2}} + \text{EMCY} + \text{SDO} + n_{\text{PDO}}$$

The following table shows t_{cycle} depending on the baud rate and the number of additional PDOs n_{PDO} , based on one drive:

Baud rate	Number of additional PDOs (n_{PDO})	Minimum cycle time in ms
1 Mbit	0	1
	1	1
	2	1
	3	2
	4	2
	5	2
	6	2
500 kbit	0	2
	1	2
	2	2
	3	2
	4	3
	5	3
	6	3
250 kbit	0	3
	1	3
	2	4
	3	4
	4	5
	5	5
	6	6

Table 8.2 Minimum cycle time

Cycle time in seconds: $IP_IntTimPerVal * 10^{IP_IntTimInd}$

- Set the desired cycle time with the parameters `IP_IntTimPerVal` and `IP_IntTimInd`.

Valid cycle times are 1 ... 20 ms in increments of 1 ms.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IP_IntTimPerVal</code>	Interpolation time period value Available as of software version V01.08.	s 0 1 255	UINT8 UINT16 UINT16 UINT16 R/W - -	CANopen 60C2:1 _h Modbus 7000 Profibus 7000 CIP 127.1.44
<code>IP_IntTimInd</code>	Interpolation time index Available as of software version V01.08.	- -128 -3 63	INT8 INT16 INT16 INT16 R/W - -	CANopen 60C2:2 _h Modbus 7002 Profibus 7002 CIP 127.1.45

Synchronization mechanism The synchronization mechanism must be activated for the operating mode Interpolated Position.

The synchronization mechanism is activated via the parameter `SyncMechStart` = 2.

The parameter `SyncMechTol` is used to set a synchronization tolerance. The value of the parameter `SyncMechTol` is internally multiplied by 250 µs. For example, a value of 4 corresponds to a tolerance of 1 ms.

The status of the synchronizations mechanism can be read by means of the parameter `SyncMechStatus`.

- Activate the synchronization mechanism by means of the parameter `SyncMechStart`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>SyncMechStart</code>	Activation of synchronization mechanism Value 0: Deactivate synchronization mechanism Value 1: Activate synchronization mechanism (CANmotion). Value 2: Activate synchronization mechanism, standard CANopen mechanism. The cycle time of the synchronization signal is derived from the parameters <code>intTimPerVal</code> and <code>intTimInd</code> . Changed settings become active immediately.	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3022:5 _h Modbus 8714 Profibus 8714 CIP 134.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
SyncMechTol	<p>Synchronization tolerance</p> <p>This parameter is used to increase the synchronization tolerance in the operating mode Interpolated Position. The value is applied when the synchronization mechanism is activated via the parameter SyncMechStart.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.08.</p>	- 1 1 20	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3022:4 _h Modbus 8712 Profibus 8712 CIP 134.1.4
SyncMechStatus	<p>Status of synchronization mechanism</p> <p>Status of synchronization mechanism: Value 1: Synchronization mechanism of drive is inactive. Value 32: Drive is synchronizing with external sync signal. Value 64: Drive is synchronized with external sync signal.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3022:6 _h Modbus 8716 Profibus 8716 CIP 134.1.6

Reference position The parameter IPp_target cyclically transmits a reference value.

- Set the desired reference value with the parameter IPp_target.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IPp_target	<p>Position reference value for operating mode Interpolated Position</p> <p>Available as of software version V01.08.</p>	- -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 60C1:1 _h Modbus 7004 Profibus 7004 CIP 127.1.46

8.4.9 Operating mode Homing

Availability See chapter 8.2 "Control mode".

Description In the operating mode Homing, a movement is performed to a defined position. This position is defined as the reference point.

The reference point also defines the zero point. The zero point is the point of reference for absolute movements in the operating modes Profile Position and Motion Sequence.

A movement can be made using different methods:

- Reference movement to a limit switch

In the case of a reference movement to a limit switch, a movement to the negative limit switch or the positive limit switch is performed. When the limit switch is reached, the motor is stopped and a movement is made back to the switching point of the limit switch.

From the switching point of the limit switch, a movement is made to the next index pulse of the motor or to a parameterizable distance from the switching point.

The position of the index pulse or the position of the parameterizable distance from the switching point is the reference point.

- Reference movement to the reference switch

In the case of a reference movement to the reference switch, a movement to the reference switch is performed.

When the reference switch is reached, the motor is stopped and a movement is made back to the switching point of the reference switch.

From the switching point of the reference switch, a movement is made to the next index pulse of the motor or to a parameterizable distance from the switching point.

The position of the index pulse or the position of the parameterizable distance from the switching point is the reference point.

- Reference movement to the index pulse

In the case of a reference movement to the index pulse, a movement is made from the actual position to the next index pulse. The position of the index pulse is the reference point.

- Position setting

In the case of position setting, the current motor position is set to a desired position value.

A reference movement must be completed for the new zero point to be valid. If the reference movement is interrupted, it must be started again.



Motors with multiturn encoder deliver a valid zero point after they are switched on.

Starting the operating mode

The operating mode is started via the fieldbus. See the fieldbus manual for a description.

Terminating the operating mode

The operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages Information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	"No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled
DQ1	"Active" Signals the operating state 6 Operation Enabled
DQ2	"Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"

It is possible to change the factory settings of the signal outputs, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.9.1 Parameterization

Overview The illustration below provides an overview of the adjustable parameters.

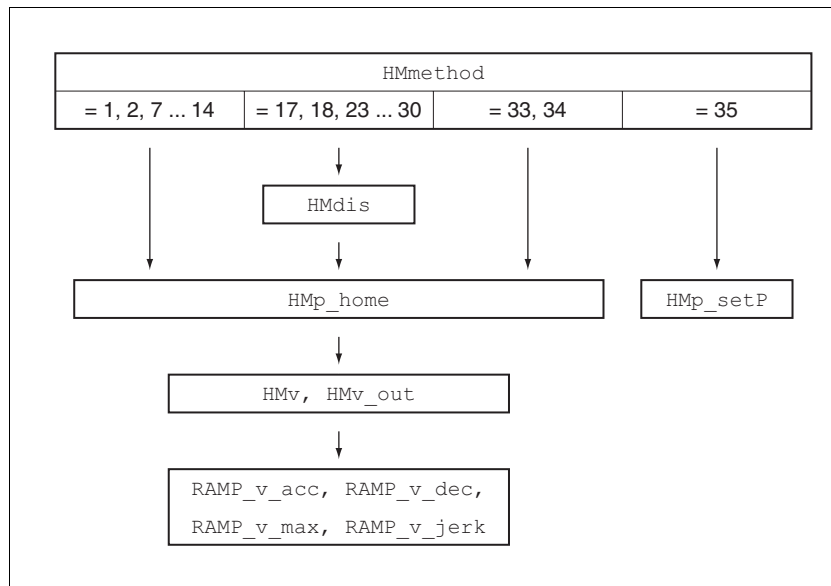


Figure 8.15 Overview of adjustable parameters

Setting limit switches and reference switches

The limit switches and reference switches must be set to meet the requirements, see chapter 8.8.1 "Limit switches" and chapter 8.8.2 "Reference switch".

Selection of the method

The operating mode Homing establishes an absolute position reference between the motor position and a defined axis position. There are various Homing methods which can be selected via the parameter HMmethod.

The HMprefmethod parameter is used to save the preferred method to the EEPROM (persistent). When the preferred method has been set in this parameter, the method is performed during homing even after the device is switched off and on. The value to be entered corresponds to the value in the HMmethod parameter.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMmethod	<p>Homing method</p> <p>1: LIMN with index pulse 2: LIMP with index pulse 7: REF+ with index pulse, inv., outside 8: REF+ with index pulse, inv., inside 9: REF+ with index pulse, not inv., inside 10: REF+ with index pulse, not inv., outside 11: REF- with index pulse, inv., outside 12: REF- with index pulse, inv., inside 13: REF- with index pulse, not inv., inside 14: REF- with index pulse, not inv., outside 17: LIMN 18: LIMP 23: REF+, inv., outside 24: REF+, inv., inside 25: REF+, not inv., inside 26: REF+, not inv., outside 27: REF-, inv., outside 28: REF-, inv., inside 29: REF-, not inv., inside 30: REF-, not inv., outside 33: Index pulse neg. direction 34: Index pulse pos. direction 35: Position setting</p> <p>Abbreviations: REF+: Search movement in pos. direction REF-: Search movement in neg. direction inv.: Invert direction in switch not inv.: Direction not inverted in switch outside: Index pulse / distance outside switch inside: Index pulse / distance inside switch</p> <p>Changed settings become active immediately.</p>	- 1 18 35	INT8 INT16 INT16 INT16 R/W - -	CANopen 6098:0 _h Modbus 6936 Profibus 6936 CIP 127.1.12
HMprefmethod OP → hOP- NEth	<p>Preferred homing method</p> <p>Changed settings become active immediately.</p>	- 1 18 35	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3028:A _h Modbus 10260 Profibus 10260 CIP 140.1.10

Setting the distance from the switching point

A distance to the switching point of the limit switch or the reference switch must be parameterized for a reference movement with index pulse. The parameter **HMdis** lets you set the distance to the switching limit switch or the reference switch.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMdis	Distance from switching point The distance from the switching point is defined as the reference point. The parameter is only effective during a reference movement without index pulse. Changed settings become active the next time the motor moves.	usr_p 1 200 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:7 _h Modbus 10254 Profibus 10254 CIP 140.1.7

Defining the zero point

The parameter **HMp_home** is used to specify a desired position value, which is set at the reference point after a successful reference movement. The desired position value at the reference point defines the zero point.

NOTE: If the value 0 is used, the zero point corresponds to the reference point.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMp_home	Position at reference point After a successful reference movement, this position is automatically set at the reference point. Changed settings become active the next time the motor moves.	usr_p -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:B _h Modbus 10262 Profibus 10262 CIP 140.1.11

Setting monitoring The parameters `HMoutdis` and `HMSrchdis` allow you to activate monitoring of the limit switches and the reference switch.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMoutdis	<p>Maximum distance for search for switching point</p> <p>0: Monitoring of distance inactive >0: Maximum distance</p> <p>After detection of the switch, the drive starts to search for the defined switching point. If the defined switching point is not found within the distance defined here, the reference movement is canceled with an error.</p> <p>Changed settings become active the next time the motor moves.</p>	<p>usr_p</p> <p>0</p> <p>0</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3028:6_h</p> <p>Modbus 10252</p> <p>Profibus 10252</p> <p>CIP 140.1.6</p>
HMSrchdis	<p>Maximum search distance after overtravel of switch</p> <p>0: Search distance monitoring disabled >0: Search distance</p> <p>The switch must be activated again within this search distance, otherwise the reference movement is canceled.</p> <p>Changed settings become active the next time the motor moves.</p>	<p>usr_p</p> <p>0</p> <p>0</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3028:D_h</p> <p>Modbus 10266</p> <p>Profibus 10266</p> <p>CIP 140.1.13</p>

Reading out the position distance The position distance between the switching point and index pulse can be read out with the following parameters.

The distance between the switching point and the index pulse must be >0.05 revolutions for reproducible reference movements with index pulse.

If the index pulse is too close to the switching point, the limit switch or reference switch can be moved mechanically.

Otherwise the position of the index pulse can be moved with the parameter `ENC_pabsusr`, see Chapter 7.6.9 "Setting parameters for encoder".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_HMdisREFtoIDX_usr</code>	Distance from switching point to index pulse It allows to check the distance between the index pulse and the switching point and serves as a criterion for determining whether the reference movement with index pulse can be reproduced. Available as of firmware version V01.03	<code>usr_p</code> -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/- - -	CANopen 3028:F _h Modbus 10270 Profibus 10270 CIP 140.1.15
<code>_HMdisREFtoIDX</code>	Distance from switching point to index pulse It allows to check the distance between the index pulse and the switching point and serves as a criterion for determining whether the reference movement with index pulse can be reproduced. The parameter <code>_HMdisREFtoIDX_usr</code> allows you to enter the value in user-defined units. In increments of 0.0001 revolution.	revolution - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 3028:C _h Modbus 10264 Profibus 10264 CIP 140.1.12

Setting velocities The parameters `HMv` and `HMv_out` are used to set the velocities for searching the switch and for moving away from the switch.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>HMv</code> <code>OP → hofn-hfn</code>	Target velocity for searching the switch The adjustable value is internally limited to the current parameter setting in <code>RAMP_v_max</code> . Changed settings become active the next time the motor moves.	<code>usr_v</code> 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6099:1 _h Modbus 10248 Profibus 10248 CIP 140.1.4
<code>HMv_out</code>	Target velocity for moving away from switch The adjustable value is internally limited to the current parameter setting in <code>RAMP_v_max</code> . Changed settings become active the next time the motor moves.	<code>usr_v</code> 1 6 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6099:2 _h Modbus 10250 Profibus 10250 CIP 140.1.5

Changing the motion profile for the velocity It is possible to change the parameterization of the motion profile for the velocity, see chapter 8.6.3 "Setting the motion profile for the velocity".

8.4.9.2 Reference movement to a limit switch

The illustration below shows a reference movement to a limit switch

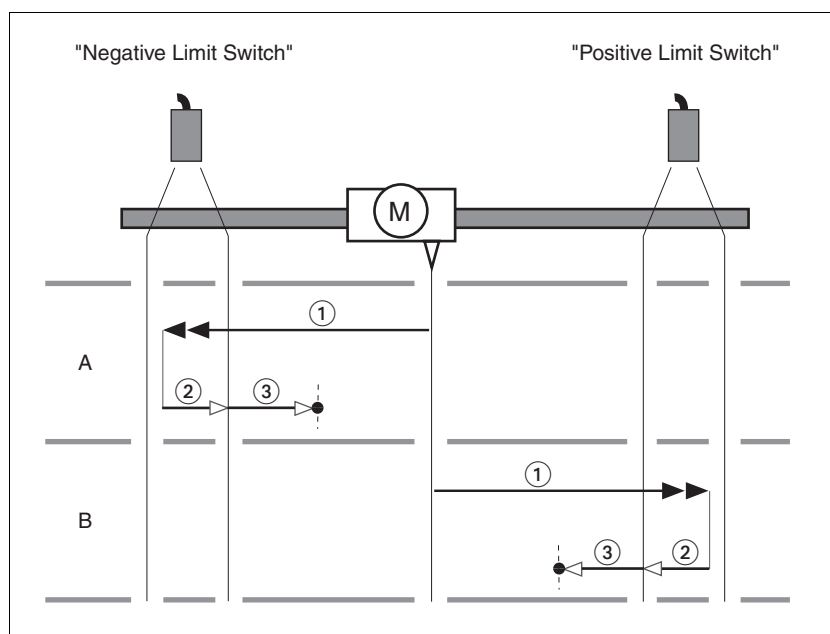


Figure 8.16 Reference movement to a limit switch

- (1) Movement to limit switch at velocity HMv
- (2) Movement to the switching point of the limit switch at velocity HMv_{out}
- (3) Movement to index pulse or movement to a distance from the switching point at velocity HMv_{out}

Type A Method 1: Movement to the index pulse.

Method 17: Movement to distance from switching point.

Type B Method 2: Movement to the index pulse.

Method 18: Movement to distance from switching point.

8.4.9.3 Reference movement to the reference switch in positive direction

The illustration below shows a reference movement to the reference switch in positive direction

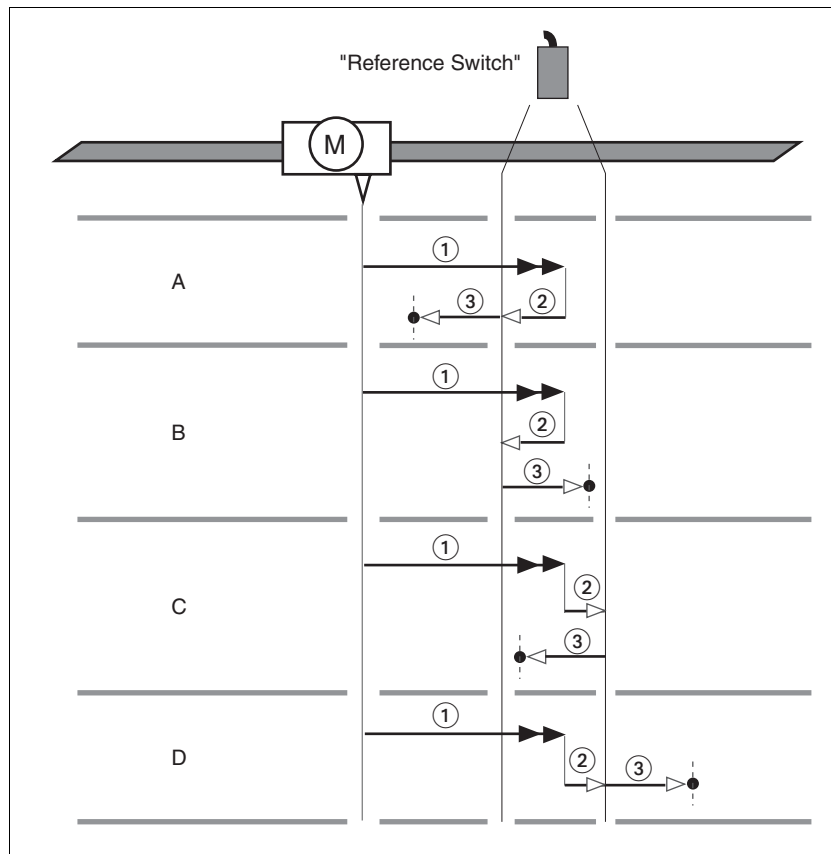


Figure 8.17 Reference movement to the reference switch in positive direction

- (1) Movement to reference switch at velocity HMv
- (2) Movement to the switching point of the reference switch at velocity HMv_{out}
- (3) Movement to index pulse or movement to a distance from the switching point at velocity HMv_{out}

- Type A* Method 7: Movement to the index pulse.
Method 23: Movement to distance from switching point.
- Type B* Method 8: Movement to the index pulse.
Method 24: Movement to distance from switching point.
- Type C* Method 9: Movement to the index pulse.
Method 25: Movement to distance from switching point.
- Type D* Method 10: Movement to the index pulse.
Method 26: Movement to distance from switching point.

8.4.9.4 Reference movement to the reference switch in negative direction

The illustration below shows a reference movement to the reference switch in negative direction

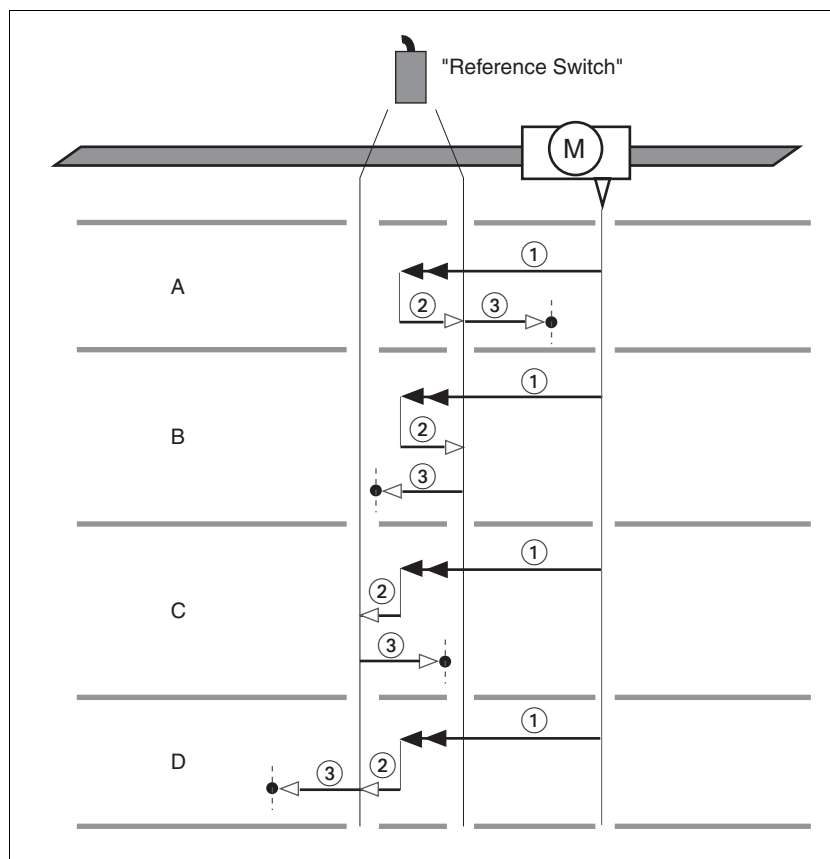


Figure 8.18 Reference movement to the reference switch in negative direction

- (1) Movement to reference switch at velocity HMv
- (2) Movement to the switching point of the reference switch at velocity HMv_{out}
- (3) Movement to index pulse or movement to a distance from the switching point at velocity HMv_{out}

Type A Method 11: Movement to the index pulse.

Method 27: Movement to distance from switching point.

Type B Method 12: Movement to the index pulse.

Method 28: Movement to distance from switching point.

Type C Method 13: Movement to the index pulse.

Method 29: Movement to distance from switching point.

Type D Method 14: Movement to the index pulse.

Method 30: Movement to distance from switching point.

8.4.9.5 Reference movement to the index pulse

The illustration below shows a reference movement to the index pulse

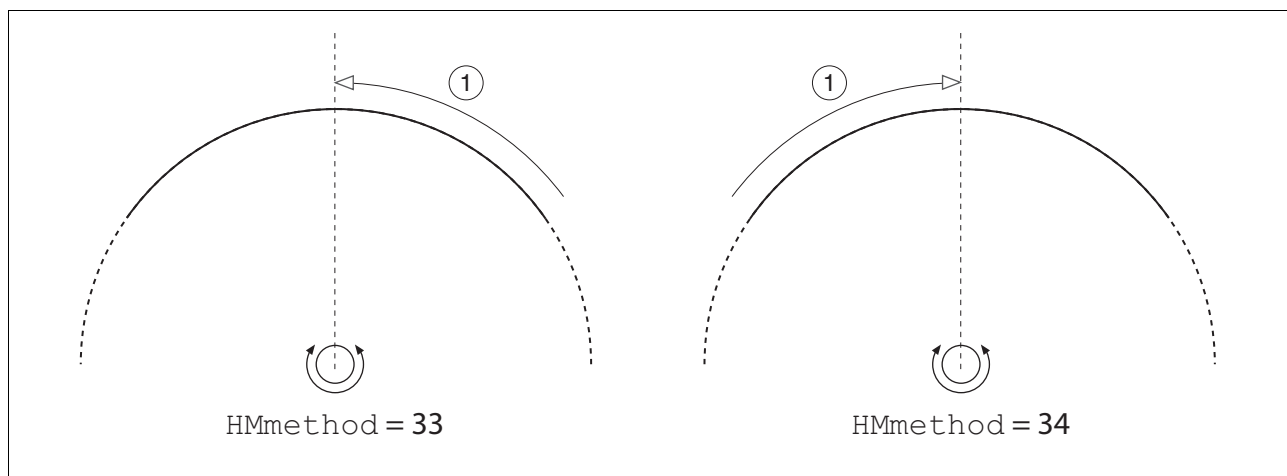


Figure 8.19 Reference movement to the index pulse

(1) Movement to index pulse at velocity HMv_{out}

8.4.9.6 Position setting

Description By means of position setting, the current motor position is set to the position value in parameter `HMP_setP`. This also defines the zero point.

Position setting is only possible when the motor is at a standstill. Any active position deviation remains active and can still be compensated by the position controller after position setting.

Setting the position for position setting

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMP_setP	Position for Position Setting Position for operating mode Homing, method 35. Changed settings become active immediately.	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W - -	CANopen 301B:16 _h Modbus 6956 Profibus 6956 CIP 127.1.22

Example

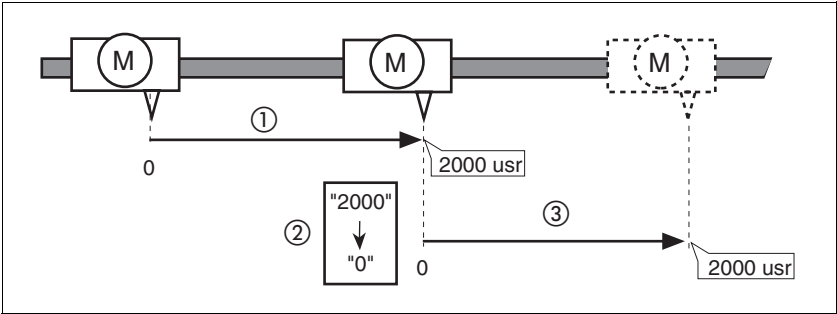


Figure 8.20 Positioning by 4000 usr units with position setting

- (1) The motor is positioned by 2000 `usr_p`.
- (2) By means of position setting to 0, the current motor position is set to position value 0 which, at the same time, defines a new zero point.
- (3) When a new movement by 2000 `usr_p` is triggered, the new target position is 2000 `usr_p`.

8.4.9.7 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.6 "Jerk limitation"
- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.2 "Reference switch"
- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.4 "Load-dependent position deviation (following error)"
- Chapter 8.8.5 "Motor standstill"
- Chapter 8.8.8 "Standstill window"
- Chapter 8.8.9 "Position register"
- Chapter 8.8.10 "Position deviation window"
- Chapter 8.8.11 "Velocity deviation window"
- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.4.10 Operating mode Motion Sequence

Availability Available as of firmware version $\geq V01.01$.

Description In the operating mode Motion Sequence, movements are performed via parameterizable data sets.

A parameterizable data set contains settings on the type of movement, the appropriate target values and the setting for the subsequent data set.

These parameterizable data sets can be started individually or as a sequence.

The data sets are parameterized via the commissioning software.

Types of movements The following types of movements are available:

- Absolute movement, additive movement or relative movement
- Movement at a specific velocity
- Homing the motor (reference movement or position setting)
- Repetition of a given sequence

Number of data sets The product provides 32 parameterizable data sets.

Starting the operating mode In local control mode, the operating mode must first have been selected, see chapter 8.4.1 "Starting the operating mode". After the power stage is enabled, the operating mode is started automatically.

The power stage is enabled via the signal inputs, see chapter 8.3 "Operating states". The table below provides an overview of the factory settings of the signal inputs:

Signal input	Signal input function
DI0	"Enable" Enable and disable the power stage
DI1	"Reference Switch (REF)" See chapter 8.8.2 "Reference switch"
DI2	"Positive Limit Switch (LIMP)" See chapter 8.8.1 "Limit switches"
DI3	"Negative Limit Switch (LIMN)" See chapter 8.8.1 "Limit switches"
DI4	"Start Motion Sequence" Start sequence
DI5	"Data Set Select" Select data set number

The factory settings of the signal inputs depend on the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In the case of fieldbus control mode, the operating mode is started via the fieldbus. See the fieldbus manual for a description.

Terminating the operating mode In local control mode, the operating mode is automatically terminated by disabling the power stage.

In fieldbus control mode, the operating mode is terminated via the fieldbus. See the fieldbus manual for a description.

Status messages In local control mode, information on the operating state and the current movement is available via signal outputs.

In fieldbus control mode, information on the operating state and the current movement is available via the fieldbus and the signal outputs.

Descriptions on obtaining information on the operating state and the current movement can be found in the fieldbus manual.

The table below provides an overview of the signal outputs:

Signal output	Signal output function
DQ0	<p>With local control mode: "Motion Sequence: Start Acknowledge" Signals the end of a sequence</p> <p>With fieldbus control mode: "No Fault" Signals the operating states 4 Ready To Switch On, 5 Switched On and 6 Operation Enabled</p>
DQ1	<p>"Active" Signals the operating state 6 Operation Enabled</p>
DQ2	<p>With local control mode: "Motion Sequence: Done" Signals that a new movement can be started</p> <p>With fieldbus control mode: "Freely Available" See chapter 8.7.8 "Setting a signal output via parameter"</p>

The factory settings of the signal outputs depend on the selected control mode and the selected operating mode; it can be adapted, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.4.10.1 Starting a movement

In local control mode, a movement is started via the digital signal inputs.

In fieldbus control mode, a movement is started via the fieldbus. See the fieldbus manual for a description.

Start of a data set A movement can be started in one of two ways:

- Start of a data set with sequence

The selected data set is started. If a subsequent data set has been defined, the subsequent data set started once the transition condition is met.

- Start of a data set without sequence

The selected data set is started. If a subsequent data set has been defined, the subsequent data set is not started.

Start of a data set with sequence In local control mode, the following signal input functions are required to start a data set with sequence:

Signal input function	Description
"Start Motion Sequence" Factory setting for DI4	The set data set is started. A data set is set via the signal input functions "Data Set Select" and "Data Set Bit 1" ... "Data Set Bit 3". If a subsequent data set has been defined in the data set, the subsequent data set is executed once the transition condition is met.
"Data Set Select" Factory setting for DI5	The signal input function "Data Set Select" is used to set the selected data set. A data set is selected with the signal input functions "Data Set Bit 1" ... "Data Set Bit 3". If the signal input functions "Data Set Bit 1" ... "Data Set Bit 3" are not set to any of the signal inputs, data set 0 is selected with the signal input function "Data Set Select".
"Data Set Bit 0" ... "Data Set Bit 3" Adjustable for signal inputs DI0 ... DI5	The signal input functions "Data Set Bit 1" ... "Data Set Bit 3" are used to select a data set in a bit-coded way. The selected data set must be set with the signal input function "Data Set Select".

Start of a data set without sequence

In local control mode, the following signal input functions are required to start a data set without sequence:

Signal input function	Description
"Start Single Data Set" The signal input function must be set.	The set data set is started. A data set is set via the signal input functions "Data Set Bit 1" ... "Data Set Bit 3". If a subsequent data set has been defined in the data set, the subsequent data set is executed once the transition condition is met.
"Data Set Bit 0" ... "Data Set Bit 3" Adjustable for signal inputs DI0 ... DI5	The signal input functions "Data Set Bit 1" ... "Data Set Bit 3" are used to set a data set in a bit-coded way. The selected data set is immediately set; it does not need to be set with the signal input function "Data Set Select".

Start conditions for the start of a data set with sequence

A start condition is defined for starting a data set with sequence. The start conditions can be set with the parameter MSM_CondSequ.

- Set the desired start condition for the start of a data set with sequence with the parameter MSM_CondSequ.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MSM_CondSequ	Start condition for the start of a sequence via a signal input 0 / Rising Edge: Rising edge 1 / Falling Edge: Falling edge 2 / 1-level: 1 level 3 / 0-level: 0 level The start condition defines the way the start request is to be processed. This setting is used for the first start after activation of the operating mode. Changed settings become active the next time the motor moves.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:8 _h Modbus 11536 Profibus 11536 CIP 145.1.8

8.4.10.2 Structure of a data set

Data set type, settings and type of transition

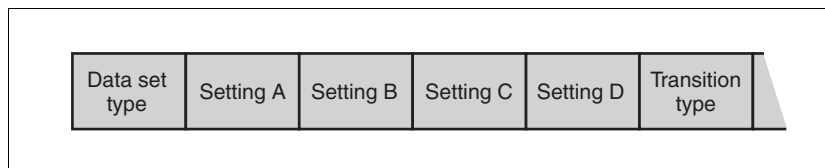


Figure 8.21 Structure of a data set

Data set type	Setting A	Setting B	Setting C	Setting D	Transition type
"Move Absolute" Movement to an absolute position value	Acceleration Unit: usr_a	Velocity Unit: usr_v	Absolute target position Unit: usr_p	Deceleration Unit: usr_a	<ul style="list-style-type: none"> No Transition Abort And Go Next Buffer And Start Next Blending Previous Blending Next
"Move Additive" Movement that is added to current target position	Acceleration Unit: usr_a	Velocity Unit: usr_v	Added target position Unit: usr_p	Deceleration Unit: usr_a	<ul style="list-style-type: none"> No Transition Abort And Go Next Buffer And Start Next
"Reference Movement" Reference movement	Homing method Unit: Value of parameter HMmethod	Desired position value at reference point Unit: usr_p	-	-	<ul style="list-style-type: none"> No Transition Buffer And Start Next
"Position Setting" Position setting	Position for position setting Unit: usr_p	-	-	-	<ul style="list-style-type: none"> No Transition Buffer And Start Next
"Repeat" Repeat part of a sequence	Number of repetitions	Number of the data set at which the repetition is to be started	-	-	<ul style="list-style-type: none"> No Transition Buffer And Start Next
"Move Relative" Relative movement with reference to current motor position	Acceleration Unit: usr_a	Velocity Unit: usr_v	Relative target position Unit: usr_p	Deceleration Unit: usr_a	<ul style="list-style-type: none"> No Transition Abort And Go Next Buffer And Start Next
"Move Velocity" Movement at a specific velocity	Acceleration Unit: usr_a	Velocity Unit: usr_v	Direction of movement Value 0: Positive Value 1: Negative Value 2: Current direction of movement	Deceleration Unit: usr_a	<ul style="list-style-type: none"> Abort And Go Next

- Transition type* Transition type is used to set the type of transition to the subsequent data set. The following types of transitions are possible:
- **No Transition**
No further data set is started upon successful completion of the movement.
 - **Abort And Go Next**
If the transition condition is met, the current movement is aborted and the subsequent data set started.
Transition condition 1 is considered for the transition.
 - **Buffer And Start Next**
Upon successful completion of the movement and if the transition condition is met, the subsequent data set is started.
Transition condition 1 and transition condition 2 are considered for the transition.
 - **Blending Previous / Blending Next**
(data set type Move Absolute only)
The velocity is adapted to the velocity of the subsequent data set until the target position is reached or when it has been reached.
The transition is performed without consideration of a transition condition.

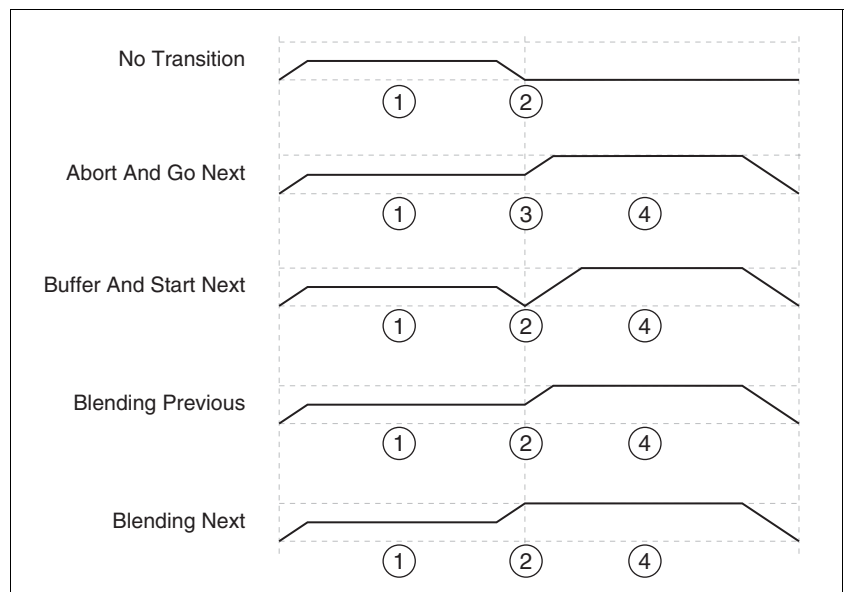


Figure 8.22 Transition type

- (1) First data set.
- (2) Target position of data set reached.
- (3) First transition condition met, the first data set is terminated and the next data set is started.
- (4) Next data set.

NOTE: Some transition types are not available with some types of data sets.

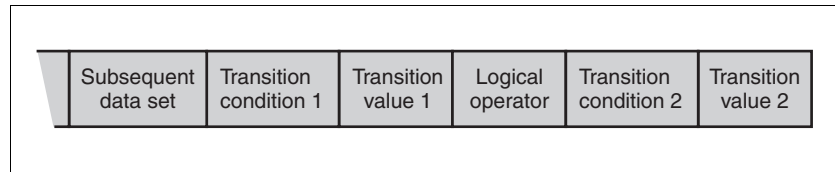
Subsequent data set and transition conditions

Figure 8.23 Structure of a data set

- Subsequent data set* Subsequent data set defines the data set to be started next.
- Transition condition 1* Transition condition 1 is used to set the first transition condition. The following transition conditions are possible:
- Continue Without Condition
No condition for a transition. The subsequent data set is started directly. Any second transition condition is without effect.
 - Wait Time
The condition for a transition is a waiting time.
 - Start Request Edge
The condition for a transition is an edge at the signal input.
 - Start Request Level
The condition for a transition is a level at the signal input.
- Transition value 1* Transition value 1 is used to set the value for the first transition condition. The meaning depends on the selected transition condition.
- In the case of transition condition Continue Without Condition
 - No meaning
 - In the case of transition condition Waiting Time
 - Value 0 ... 30000: Waiting time of 0 ... 30000 ms
 - In the case of transition condition Start Request Edge
 - Value 0: Rising edge
 - Value 1: Falling edge
 - Value 4: Rising or falling edge
 - In the case of transition condition Start Request Level
 - Value 2: 1 level
 - Value 3: 0 level
- Logical operator* Logical operator is used to logically link transition condition 1 and transition condition 2. The following logical operators are available:
- None
No operator (transition condition 2 has no effect)
 - AND
Logical AND
 - OR
Logical OR

Transition condition 2 Transition condition 2 is used to set the second transition condition. The following transition conditions are possible:

- Continue Without Condition
No condition for a transition. The subsequent data set is started directly.
- Start Request Edge
The condition for a transition is an edge at the signal input.
If an edge is selected and logically linked to a waiting time, the edge is not evaluated until the waiting time has elapsed.
- Start Request Level
The condition for a transition is a level at the signal input.

Transition value 2 Transition value 2 is used to set the value for the second transition condition. The meaning depends on the selected transition condition.

- In the case of transition condition Continue Without Condition
 - No meaning
- In the case of transition condition Start Request Edge
 - Value 0: Rising edge
 - Value 1: Falling edge
 - Value 4: Rising or falling edge
- In the case of transition condition Start Request Level
 - Value 2: 1 level
 - Value 3: 0 level

8.4.10.3 Additional settings

The following functions can be used for target value processing:

- Chapter 8.7.1 "Stop movement with Halt"
- Chapter 8.7.2 "Stopping a movement with Quick Stop"
- Chapter 8.7.4 "Limitation of the velocity via signal inputs"
- Chapter 8.7.5 "Limitation of the current via signal inputs"
- Chapter 8.7.6 "Jerk limitation"

This function is only available for the data set types Move Absolute, Move Relative, Reference Movement and Move Additive.

- Chapter 8.7.7 "Zero Clamp"

This function is only available for data set type Move Velocity.

- Chapter 8.7.8 "Setting a signal output via parameter"
- Chapter 8.7.10 "Position capture via signal input"

The following functions can be used for monitoring the movement:

- Chapter 8.8.1 "Limit switches"
- Chapter 8.8.2 "Reference switch"

This function is only available for data set type Reference Movement.

- Chapter 8.8.3 "Software limit switches"
- Chapter 8.8.4 "Load-dependent position deviation (following error)"

This function is only available for the data set types Move Absolute, Move Relative, Reference Movement and Move Additive.

- Chapter 8.8.5 "Motor standstill"
- Chapter 8.8.8 "Standstill window"

This function is only available for the data set types Move Absolute, Move Relative, Reference Movement and Move Additive.

- Chapter 8.8.9 "Position register"

This function is only available for fieldbus control mode.

- Chapter 8.8.10 "Position deviation window"

This function is only available for the data set types Move Absolute, Move Relative, Reference Movement and Move Additive.

- Chapter 8.8.11 "Velocity deviation window"
- Chapter 8.8.12 "Velocity threshold value"
- Chapter 8.8.13 "Current threshold value"

8.5 Movement range

The movement range is the maximum possible range within which a movement can be made to any position.

The actual position of the motor is the position in the movement range.

The figure below shows the movement range in user-defined units with the factory scaling.

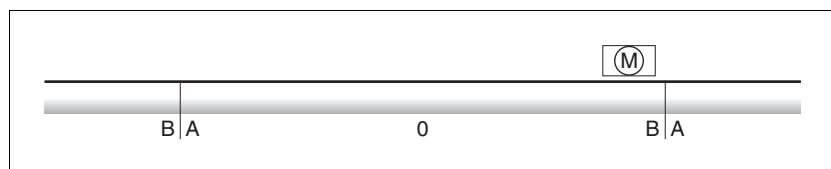


Figure 8.24 Movement range

(A) -268435456 user-defined units (usr_p)

(B) 268435455 user-defined units (usr_p)

Availability The movement range is relevant in the following operating modes:

- Jog
- Profile Position
- Homing
- Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)

8.5.1 Zero point of the movement range

The zero point of the movement range is the point of reference for absolute movements in the operating modes Profile Position and Motion Sequence.

Valid zero point The zero point of the movement range is set by means of a reference movement or by position setting.

A reference movement and position setting can be performed in the operating modes Homing and Motion Sequence.

In the case of a movement beyond the movement range (for example, a relative movement), the reference point is lost and the zero point becomes invalid.

8.5.2 Scaling

⚠ WARNING**UNEXPECTED MOVEMENT CAUSED BY CHANGED SCALING**

Changing the scaling changes the effect of the values in user-defined units. The same user-defined units cause different movements when the scaling is changed.

- Note that scaling affects all relationships between the user-defined units and the movements.
- Check the parameters with user-defined units.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Scaling converts user-defined units into internal units of the device, and vice versa.

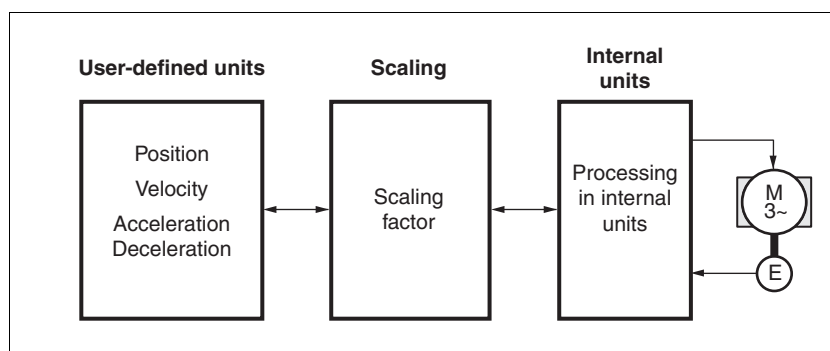


Figure 8.25 Scaling

User-defined units User-defined units are values for positions, velocities, acceleration and deceleration; they have the following units:

- usr_p for positions
- usr_v for velocities
- usr_a for acceleration and deceleration

Scaling factor The scaling factor is the relationship between the motor movement and the required user-defined units. When specifying the scaling factor, note that numerator and denominator can only be integer values.

Commissioning software As of firmware version $\geq V01.04$, you can adjust the scaling via the commissioning software. The parameters with user-defined units are automatically checked and adjusted.

8.5.2.1 Configuration of position scaling

Position scaling is the relationship between the number of motor revolutions and the required user-defined units [usr_p].

Scaling factor Position scaling is specified by means of scaling factor:

In the case of a rotary motor, the scaling factor is calculated as shown below:

$$\frac{\text{Number of revolutions of the motor}}{\text{Number of user-defined units [usr_p]}}$$

Figure 8.26 Scaling factor of position scaling

The scaling factor is set using the parameters POSscaleNum and POSscaleDenom. A new scaling factor is activated when you specify the numerator value.

Factory setting The following factory settings are used:

- 1 motor revolution corresponds to 16384 user-defined units

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ScalePOSnum	Position scaling: Numerator Specification of the scaling factor: Motor revolutions ----- User-defined units [usr_p] A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	revolution 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:8 _h Modbus 1552 Profibus 1552 CIP 106.1.8
ScalePOSdenom	Position scaling: Denominator Refer to numerator (ScalePOSnum) for a description. A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled.	usr_p 1 16384 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:7 _h Modbus 1550 Profibus 1550 CIP 106.1.7

8.5.2.2 Configuration of velocity scaling

Velocity scaling is the relationship between the number of motor revolutions per minute and the required user-defined units [usr_v].

Scaling factor Velocity scaling is specified by means of scaling factor:

In the case of a rotary motor, the scaling factor is calculated as shown below:

$$\frac{\text{Number of revolutions of the motor per minute}}{\text{Number of user-defined units [usr_v]}}$$

Figure 8.27 Scaling factor of velocity scaling

Factory setting The following factory settings are used:

- 1 motor revolution per minute corresponds to 1 user-defined unit

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ScaleVELnum	Velocity scaling: Numerator Specification of the scaling factor: Speed of rotation of motor [min ⁻¹] ----- User-defined units [usr_v] A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	min ⁻¹ 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:22 _h Modbus 1604 Profibus 1604 CIP 106.1.34
ScaleVELdenom	Velocity scaling: Denominator Refer to numerator (ScaleVELnum) for a description. A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled.	usr_v 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:21 _h Modbus 1602 Profibus 1602 CIP 106.1.33

8.5.2.3 Configuration of ramp scaling

Ramp scaling is the relationship between the change in velocity and the required user-defined units [usr_a].

Scaling factor Ramp scaling is specified by means of scaling factor:

$$\frac{\text{Velocity change per second}}{\text{Number of user-defined units [usr_a]}}$$

Figure 8.28 Scaling factor of ramp scaling

Factory setting The following factory settings are used:

- A change of 1 motor revolution per minute per second corresponds to 1 user-defined unit.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ScaleRAMPnum	Ramp scaling: Numerator Setting can only be changed if power stage is disabled. Changed settings become active immediately.	min ⁻¹ /s 1 1 2147483647	INT32 INT32 INT32 R/W per. -	CANopen 3006:31 _h Modbus 1634 Profibus 1634 CIP 106.1.49
ScaleRAMPdenom	Ramp scaling: Denominator Refer to numerator (ScaleRAMPnum) for a description. A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled.	usr_a 1 1 2147483647	INT32 INT32 INT32 R/W per. -	CANopen 3006:30 _h Modbus 1632 Profibus 1632 CIP 106.1.48

8.5.3 Movement beyond the movement range

The behavior in the case of a movement beyond the movement range depends on the operating mode and the type of movement.

The following behavior is possible:

- In the case of a movement beyond the movement range, the movement range restarts.
- In the case of a movement with a target position outside of the movement range, position setting to 0 is performed before the movement is started.

As of firmware version $\geq V01.04$, you can use the parameter `PP_ModeRangeLim` to set the behavior.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PP_ModeRangeLim	<p>Absolute movement beyond movement range</p> <p>0 / NoAbsMoveAllowed: Absolute movement beyond movement range is not possible</p> <p>1 / AbsMoveAllowed: Absolute movement beyond movement range is possible</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3023:7 _h Modbus 8974 Profibus 8974 CIP 135.1.7

8.5.3.1 Behavior for operating mode Jog

Continuous movement Behavior for continuous movement beyond the movement range:

- The movement range restarts.

Step movement Behavior for step movement beyond the movement range:

- In the case of firmware version $\geq V01.04$ and setting via parameter `PP_ModeRangeLim = 1`:

The movement range restarts.

- In the case of firmware version $< V01.04$:

Internal position setting to 0.

8.5.3.2 Behavior for operating mode Profile Position

Relative movement Behavior for relative movement beyond the movement range:

- In the case of firmware version $\geq V01.04$ and setting via parameter `PP_ModeRangeLim = 1`:

The movement range restarts.

A relative movement is possible when the motor is at a standstill and during movements

- In the case of firmware version $< V01.04$:

Internal position setting to 0.

A relative movement is only possible when the motor is at a standstill.

Absolute movement Behavior for absolute movement:

- In the case of firmware version $\geq V01.04$ and setting via parameter `PP_ModeRangeLim = 1`:

A relative movement beyond the movement range is possible.

- In the case of firmware version $< V01.04$:

An absolute movement is made within the movement range. An relative movement beyond the movement range is not possible.

Example:

Actual position: 268435000 user-defined units (usr_p)

Target position absolute: -268435000 user-defined units (usr_p)

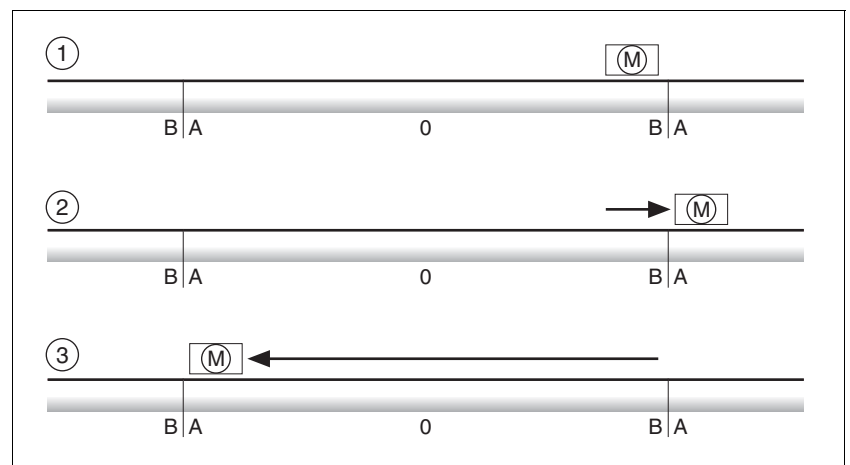


Figure 8.29 Absolute movement

- (A) -268435456 user-defined units (usr_p)
- (B) 268435455 user-defined units (usr_p)
- (1) Actual position: 268435000 user-defined units
- (2) Absolute movement to -268435000 user-defined units
Parameter `PP_ModeRangeLim = 1`
- (3) Absolute movement to -268435000 user-defined units
Parameter `PP_ModeRangeLim = 0`

8.5.3.3 Behavior for operating mode Motion Sequence

Move Relative and Move Additive Behavior for movement with Move Relative and Move Additive beyond the movement range:

- In the case of firmware version $\geq V01.04$ and setting via parameter $PP_ModeRangeLim = 1$:
The movement range restarts.
- In the case of firmware version $< V01.04$:
Internal position setting to 0.

Move Absolute Behavior for a movement with Move Absolute:

- In the case of firmware version $\geq V01.04$ and setting via parameter $PP_ModeRangeLim = 1$:
A relative movement beyond the movement range is possible.
- In the case of firmware version $< V01.04$:
An absolute movement is made within the movement range. An relative movement beyond the movement range is not possible.

Example:

Actual position: 268435000 user-defined units (usr_p)

Target position absolute: -268435000 user-defined units (usr_p)

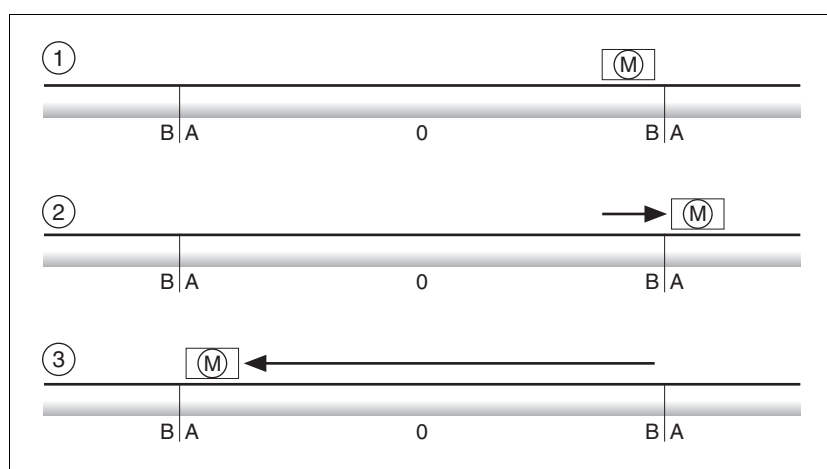


Figure 8.30 Absolute movement

- (A) -268435456 user-defined units (usr_p)
- (B) 268435455 user-defined units (usr_p)
- (1) Actual position: 268435000 user-defined units
- (2) Absolute movement to -268435000 user-defined units
Parameter $PP_ModeRangeLim = 1$
- (3) Absolute movement to -268435000 user-defined units
Parameter $PP_ModeRangeLim = 0$

8.5.4 Setting a modulo range

Availability Available as of firmware version $\geq V01.01$.

Description The modulo range supports applications with repeating arrangements of target positions (such as rotary indexing tables). The target positions are mapped to a parameterizable movement range.

Direction of movement The direction of movement for absolute target positions can be adjusted to meet the requirements of the application.

- Shortest distance
- Positive direction of movement only
- Negative direction of movement only

Multiple modulo range In addition, it is possible to set a multiple modulo range for absolute target positions. A movement with an absolute target position beyond the modulo range is performed in a way as if several modulo ranges had been arranged one after the other.

Example:

- Modulo range
 - Minimum position: 0 usr_p
 - Maximum position: 3600 usr_p
- Actual position: 700 usr_p
- Target positions absolute: 5000 usr_p
- Left: Without multiple modulo range
- Right: With multiple modulo range

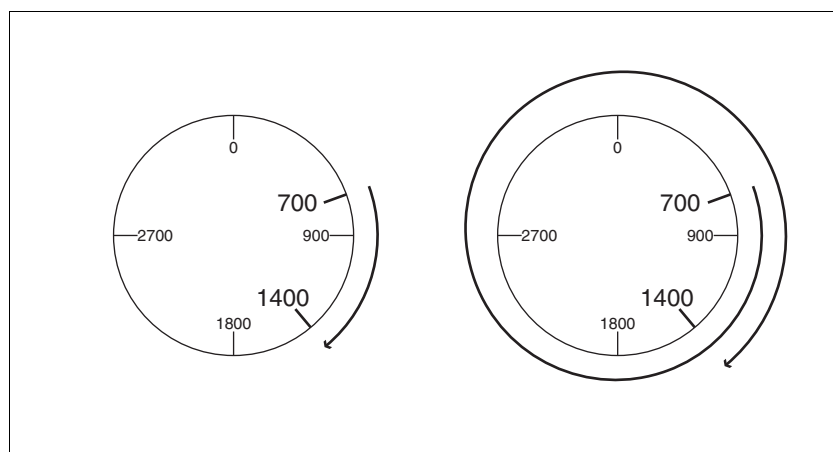


Figure 8.31 Multiple modulo range

8.5.4.1 Parameterization

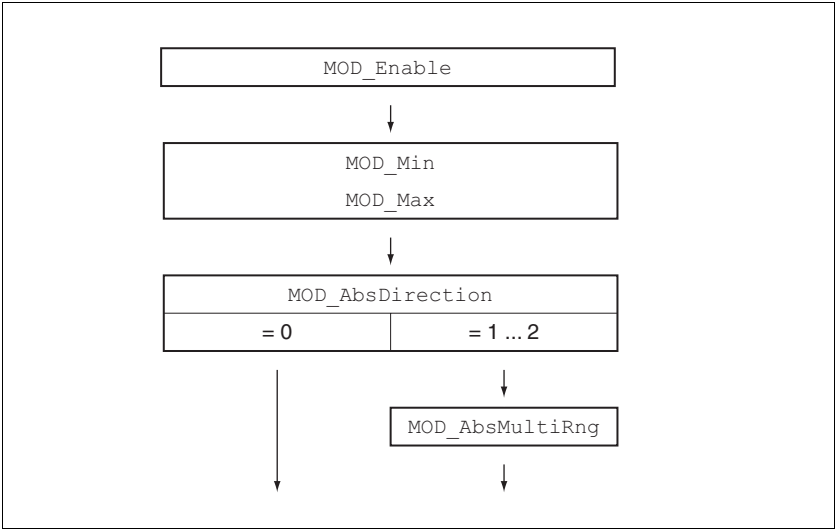


Figure 8.32 Overview of parameters

General Using a modulo range requires the scaling to be adapted. The scaling of the motor must be adapted to the requirements of the application, see chapter 8.5.2 "Scaling".

Activation The modulo range is activated with the parameter MOD_Enable.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MOD_Enable CONF → REG- RESP	Activation of Modulo 0 / Modulo Off / oFF: Modulo is off 1 / Modulo On / on: Modulo is on Activating Modulo does not automatically change the value of other parameters. Before changing this value, verify that the parameter settings for the intended application are correct. NOTE: Modulo must be deactivated for Auto-tuning. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:38 _h Modbus 1648 Profibus 1648 CIP 106.1.56

Modulo range The parameters MOD_Min and MOD_Max can be used to set the modulo range.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MOD_Min	<p>Minimum position of modulo range</p> <p>The minimum position value of the modulo range must be less than the maximum position value of the modulo range. The value must not exceed the maximum possible value of position scaling _ScalePOSmax.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:39 _h Modbus 1650 Profibus 1650 CIP 106.1.57
MOD_Max	<p>Maximum position of modulo range</p> <p>The maximum position value of the modulo range must be greater than the minimum position value of the modulo range. The value must not exceed the maximum possible value of position scaling _ScalePOSmax.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	usr_p - 3600 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:3A _h Modbus 1652 Profibus 1652 CIP 106.1.58

Direction for absolute movements The parameter MOD_AbsDirection lets you set the direction of movement for absolute movements.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MOD_AbsDirection	<p>Direction of absolute movement with Modulo</p> <p>0 / Shortest Distance: Movement with shortest distance 1 / Positive Direction: Movement only in positive direction 2 / Negative Direction: Movement only in negative direction</p> <p>If the parameter is set to 0, the drive calculates the shortest way to the new target position and starts the movement in the corresponding direction. If the distance to the target position is identical in positive and negative directions, the movement takes place in positive direction.</p> <p>Changed settings become active immediately.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:3B _h Modbus 1654 Profibus 1654 CIP 106.1.59

Multiple modulo range for absolute movements The parameter MOD_AbsMultiRng lets you set a multiple modulo range for absolute movements.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MOD_AbsMultiRng	<p>Multiple ranges for absolut movement with Modulo</p> <p>0 / Multiple Ranges Off: Absolute movement in one modulo range</p> <p>1 / Multiple Ranges On: Absolute movement in multiple modulo ranges</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:3C _h Modbus 1656 Profibus 1656 CIP 106.1.60

8.5.4.2 Examples with relative movements

Assumptions The settings below are assumed for the examples.

- Rotary motor
- Position scaling
 - Numerator: 1
 - Denominator: 3600
- Modulo range
 - Minimum position: 0 usr_p
 - Maximum position: 3600 usr_p
- Actual position: 700 usr_p

Example 1 Target positions relative: 500 usr_p and 3300 usr_p

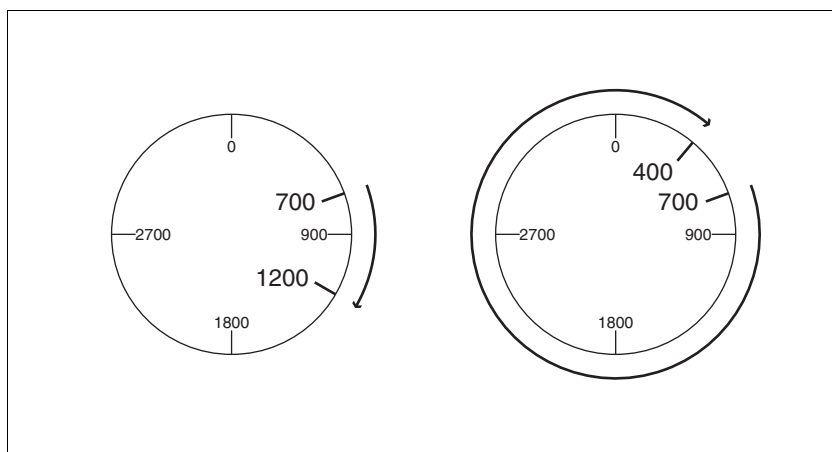


Figure 8.33 Example 1

Example 2 Target positions relative: -500 usr_p and -3300 usr_p

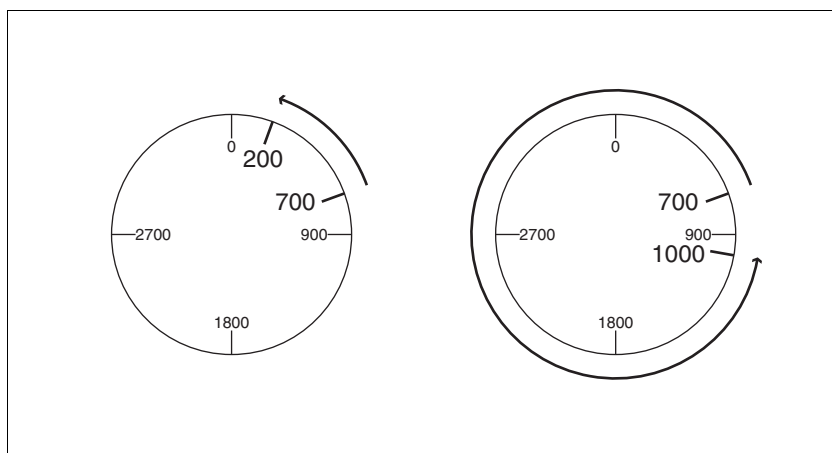


Figure 8.34 Example 2

8.5.4.3 Examples with absolute movements and "Shortest Distance"

Assumptions The settings below are assumed for the examples.

- Rotary motor
- Position scaling
 - Numerator: 1
 - Denominator: 3600
- Modulo range
 - Minimum position: 0 usr_p
 - Maximum position: 3600 usr_p
- Actual position: 700 usr_p

Example 1 Target positions absolute: 1500 usr_p and 5000 usr_p

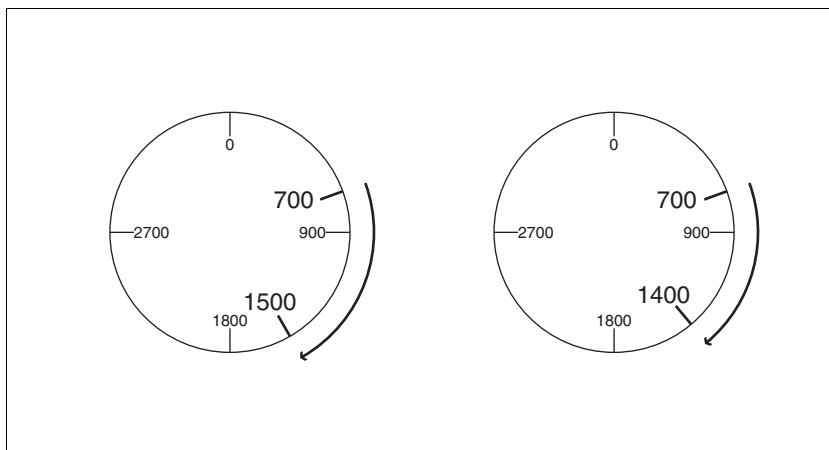


Figure 8.35 Example 1

Example 2 Target positions absolute: 2500 usr_p and 2900 usr_p

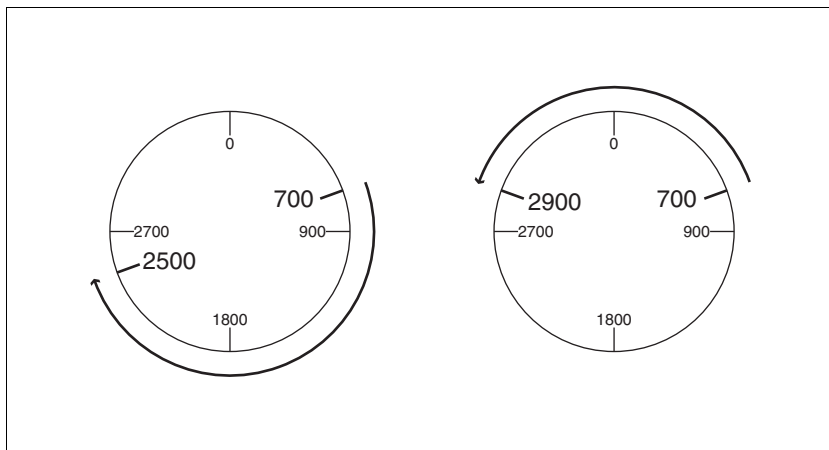


Figure 8.36 Example 2

8.5.4.4 Examples with absolute movements and "Positive Direction"

Assumptions The settings below are assumed for the examples.

- Rotary motor
- Position scaling
 - Numerator: 1
 - Denominator: 3600
- Modulo range
 - Minimum position: 0 usr_p
 - Maximum position: 3600 usr_p
- Actual position: 700 usr_p

Parameter MOD_AbsDirection: Positive Direction

Example 1 Parameter MOD_AbsMultiRng: Off

Target positions absolute: 1500 usr_p and 5000 usr_p

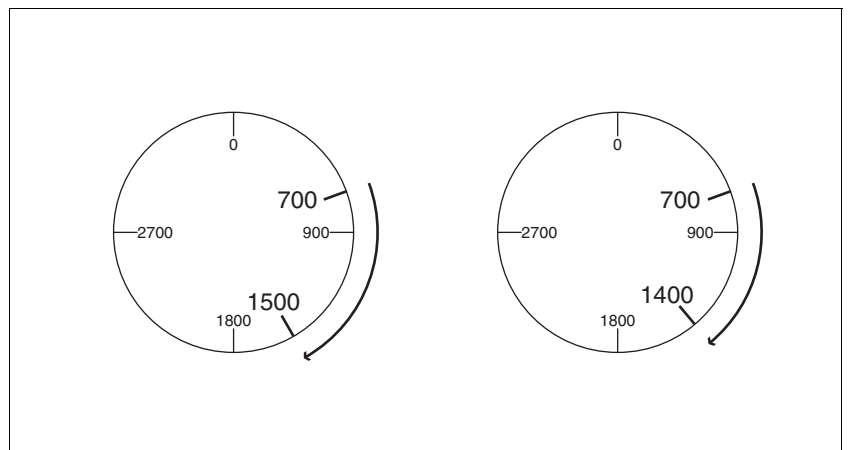


Figure 8.37 Example 1

Example 2 Parameter MOD_AbsMultiRng: On

Target positions absolute: 1500 usr_p and 5000 usr_p

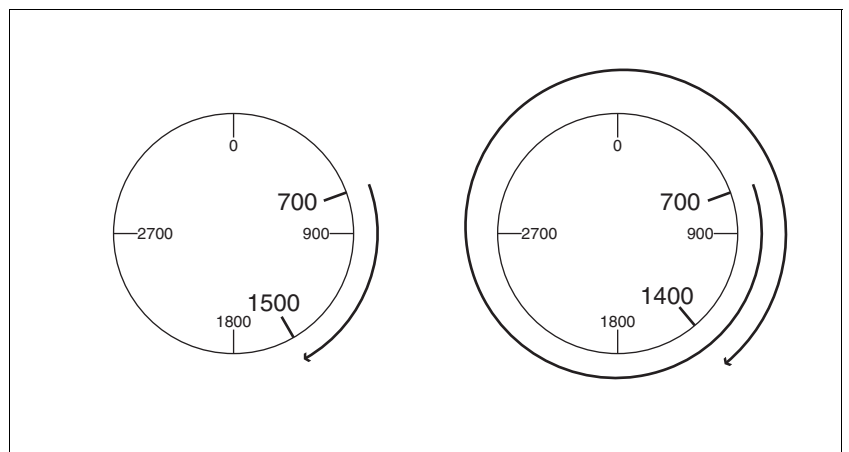


Figure 8.38 Example 2

8.5.4.5 Examples with absolute movements and "Negative Direction"

Assumptions The settings below are assumed for the examples.

- Rotary motor
- Position scaling
 - Numerator: 1
 - Denominator: 3600
- Modulo range
 - Minimum position: 0 usr_p
 - Maximum position: 3600 usr_p
- Actual position: 700 usr_p

Parameter MOD_AbsDirection: Negative Direction

Example 1 Parameter MOD_AbsMultiRng: Off

Target positions absolute: 1500 usr_p and -5000 usr_p

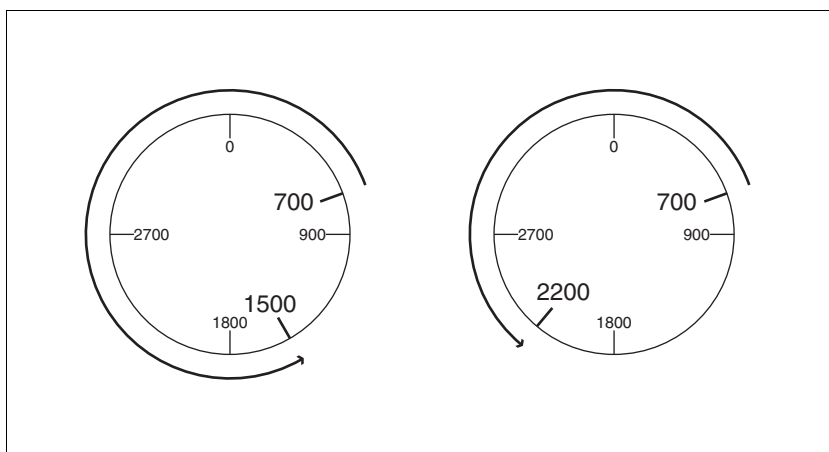


Figure 8.39 Example 1

Example 2 Parameter MOD_AbsMultiRng: On

Target positions absolute: 1500 usr_p and -5000 usr_p

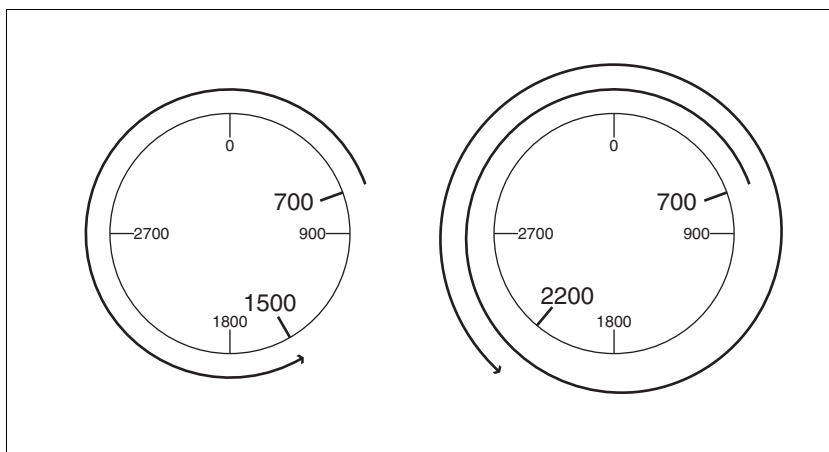


Figure 8.40 Example 2

8.6 Extended settings

8.6.1 Setting the PTO interface

The PTO interface allows you to make reference value signals from the device externally available.

The PTO interface can be used in one of 2 ways.

- Encoder simulation
- PTI signal

The parameter `PTO_mode` lets you set the way the PTO interface is used.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PTO_mode [onF → RCLG- Ptoñ	<p>Type of usage of PTO interface</p> <p>0 / Off / oFF: PTO interface disabled</p> <p>1 / Esim pAct Enc 1 / PEñ1: Encoder simulation based on actual position of encoder 1</p> <p>2 / Esim pRef / PrEF: Encoder simulation based on reference position values (_p_ref)</p> <p>3 / PTI Signal / Pti: Directly the signal from PTI interface</p> <p>4 / Esim pAct Enc 2 / PEñ2: Encoder simulation based on actual position of encoder 2 (module)</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:1F _h Modbus 1342 Profibus 1342 CIP 105.1.31

Encoder simulation The following types of encoder simulation are possible:

- Encoder simulation based on actual position of encoder 1
- Encoder simulation based on the reference position values (_p_ref)
- Encoder simulation based on actual position of encoder 2

The resolution for the encoder simulation is set with the parameter `ESIM_scale`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ESIM_scale [onF → , -o- E55C	<p>Resolution of encoder simulation</p> <p>Resolution defines the number of increments per revolution (AB signal with quadruple evaluation).</p> <p>The index pulse is created once per revolution at an interval where signal A and signal B are high.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	Enclnc 8 4096 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:15 _h Modbus 1322 Profibus 1322 CIP 105.1.21

PTI signal If the PTI signal is selected by means of parameter `PTO_mode`, the signal from the PTI interface is directly made available at the PTO interface.

8.6.2 Setting the digital signal inputs and signal outputs

Different signal functions can be assigned to the digital signal inputs and digital signal outputs.

Depending on the selected control mode and the selected operating mode, different functions are assigned to the digital signal inputs and digital signal outputs.

Current state The parameters `_IO_DI_act` and `_IO_DQ_act` can be used to read the status of the digital signal inputs and the digital signal outputs.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_IO_DI_act</code> <i>flon</i> <i>di flo</i>	Status of digital inputs Bit assignments: Bit 0: DI0 Bit 1: DI1 Bit 2: DI2 Bit 3: DI3 Bit 4: DI4 Bit 5: DI5	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3008:F _h Modbus 2078 Profibus 2078 CIP 108.1.15
<code>_IO_DQ_act</code> <i>flon</i> <i>doflo</i>	Status of digital outputs Bit assignments: Bit 0: DQ0 Bit 1: DQ1 Bit 2: DQ2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3008:10 _h Modbus 2080 Profibus 2080 CIP 108.1.16

Factory settings The table below shows the factory settings of the digital signal inputs in local control mode depending on the selected operating mode:

Signal	Jog	Electronic Gear	Profile Torque	Profile Velocity	Motion Sequence
DI0	Enable	Enable	Enable	Enable	Enable
DI1	Fault Reset	Fault Reset	Fault Reset	Fault Reset	Reference Switch (REF)
DI2	Positive Limit Switch (LIMP)	Positive Limit Switch (LIMP)	Operating Mode Switch	Operating Mode Switch	Positive Limit Switch (LIMP)
DI3	Negative Limit Switch (LIMN)	Negative Limit Switch (LIMN)	Velocity Limitation	Velocity Limitation	Negative Limit Switch (LIMN)
DI4	Jog negative	Gear Ratio Switch	Current Limitation	Zero Clamp	Start Motion Sequence
DI5	Jog positive	Halt	Halt	Halt	Data Set Select

The table below shows the factory settings of the digital signal inputs in fieldbus control mode:

Signal	Signal input function
DI0	Freely Available
DI1	Reference Switch (REF)
DI2	Positive Limit Switch (LIMP)
DI3	Negative Limit Switch (LIMN)
DI4	Freely Available
DI5	Freely Available

The table below shows the factory settings of the digital signal outputs in local control mode depending on the selected operating mode:

Signal	Jog	Electronic Gear	Profile Torque	Profile Velocity	Motion Sequence
DQ0	No Fault	No Fault	No Fault	No Fault	Motion Sequence: Done
DQ1	Active	Active	Active	Active	Active
DQ2	In Position Deviation Window	In Position Deviation Window	Current Threshold Reached	In Velocity Deviation Window	Motion Sequence: Start Acknowledge

The table below shows the factory settings of the digital signal outputs in fieldbus control mode:

Signal	Signal output function
DQ0	No Fault
DQ1	Active
DQ2	Freely Available

8.6.2.1 Configuration of signal inputs

The table below provides an overview of the possible signal input functions for local control mode:

Signal input function	Jog	Electronic Gear	Profile Torque	Profile Velocity	Motion Sequence	Description in chapter
Freely Available	•	•	•	•	•	No function
Fault Reset	•	•	•	•	•	8.3 "Operating states"
Enable	•	•	•	•	•	8.3 "Operating states"
Halt	•	•	•	•	•	8.7.1 "Stop movement with Halt"
Current Limitation	•	•	•	•	•	8.7.5 "Limitation of the current via signal inputs"
Zero Clamp	•	•	•	•	•	8.7.7 "Zero Clamp"
Velocity Limitation	•	•	•	•	•	8.7.4 "Limitation of the velocity via signal inputs"
Jog Positive	•					8.4.3 "Operating mode Jog"
Jog Negative	•					8.4.3 "Operating mode Jog"
Jog Fast/Slow	•					8.4.3 "Operating mode Jog"
Gear Ratio Switch		•				8.4.4 "Operating mode Electronic Gear"
Start Single Data Set					•	8.4.10 "Operating mode Motion Sequence"
Data Set Select					•	8.4.10 "Operating mode Motion Sequence"
Data Set Bit 0					•	8.4.10 "Operating mode Motion Sequence"
Data Set Bit 1					•	8.4.10 "Operating mode Motion Sequence"
Data Set Bit 2					•	8.4.10 "Operating mode Motion Sequence"
Data Set Bit 3					•	8.4.10 "Operating mode Motion Sequence"
Gear Offset 1		•				8.4.4 "Operating mode Electronic Gear"
Gear Offset 2		•				8.4.4 "Operating mode Electronic Gear"
Reference Switch (REF)	•	•	•	•	•	8.8.2 "Reference switch"
Positive Limit Switch (LIMP)	•	•	•	•	•	8.8.1 "Limit switches"
Negative Limit Switch (LIMN)	•	•	•	•	•	8.8.1 "Limit switches"
Switch Controller Parameter Set	•	•	•	•	•	8.6.4.5 "Parameterizable controller parameter"
Operating Mode Switch	•	•	•	•	•	8.4.2 "Changing the operating mode"
Velocity Controller Integral Off	•	•	•	•	•	8.6.4.9 "Deactivating the integral term"
Start Motion Sequence	•	•	•	•	•	8.4.10 "Operating mode Motion Sequence"

Signal input function	Jog	Elec- tronic Gear	Profile Torque	Profile Velocity	Motion Sequence	Description in chapter
Data Set Bit 4					•	8.4.10 "Operating mode Motion Sequence"
Data Set Bit 5					•	8.4.10 "Operating mode Motion Sequence"
Data Set Bit 6					•	8.4.10 "Operating mode Motion Sequence"
Inversion AI11 (IO Module) ¹⁾	•	•	•	•	•	Module manual
Inversion AI12 (IO Module) ¹⁾	•	•	•	•	•	Module manual

1) Analog signal inputs are available with the IOM1 module.

The table below provides an overview of the possible signal input functions for fieldbus control mode:

Signal input function	Description in chapter
Freely Available	No function
Fault Reset	8.3 "Operating states"
Enable	8.3 "Operating states"
Halt	8.7.1 "Stop movement with Halt"
Start Profile Positioning	8.7.9 "Starting a movement via a signal input"
Current Limitation	8.7.5 "Limitation of the current via signal inputs"
Zero Clamp	8.7.7 "Zero Clamp"
Velocity Limitation	8.7.4 "Limitation of the velocity via signal inputs"
Gear Offset 1	8.4.4 "Operating mode Electronic Gear"
Gear Offset 2	8.4.4 "Operating mode Electronic Gear"
Reference Switch (REF)	8.8.2 "Reference switch"
Positive Limit Switch (LIMP)	8.8.1 "Limit switches"
Negative Limit Switch (LIMN)	8.8.1 "Limit switches"
Switch Controller Parameter Set	8.6.4.5 "Parameterizable controller parameter"
Velocity Controller Integral Off	8.6.4.9 "Deactivating the integral term"

The following parameters can be used to parameterize the digital signal inputs:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI0 [onF →, -o- di 0]	Function Input DI0 1 / Freely Available / nonE 2 / Fault Reset / FrE5 3 / Enable / EnAb 4 / Halt / hALt 5 / Start Profile Positioning / SPtP 6 / Current Limitation / iL, n 7 / Zero Clamp / CLnP 8 / Velocity Limitation / VL, n 9 / Jog Positive / JoGP 10 / Jog Negative / JoGn 11 / Jog Fast/Slow / JoGF 12 / Gear Ratio Switch / GrRt 13 / Start Single Data Set / d5tA 14 / Data Set Select / d5EL 15 / Data Set Bit 0 / d5b0 16 / Data Set Bit 1 / d5b1 17 / Data Set Bit 2 / d5b2 18 / Data Set Bit 3 / d5b3 19 / Gear Offset 1 / Gof1 20 / Gear Offset 2 / Gof2 21 / Reference Switch (REF) / rEF 22 / Positive Limit Switch (LIMP) / L, nP 23 / Negative Limit Switch (LIMN) / L, nN 24 / Switch Controller Parameter Set / CLPr 27 / Operating Mode Switch / n5Lt 28 / Velocity Controller Integral Off / tnoF 29 / Start Motion Sequence / 5tM5 35 / Data Set Bit 4 / d5b4 36 / Data Set Bit 5 / d5b5 37 / Data Set Bit 6 / d5b6 38 / Inversion AI11 (IO Module) / R i1 39 / Inversion AI12 (IO Module) / R i2 Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:1 _h Modbus 1794 Profibus 1794 CIP 107.1.1

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI1 [onF →, -o- di, i	Function Input DI1 1 / Freely Available / nonE 2 / Fault Reset / FrE5 3 / Enable / EnAb 4 / Halt / hALt 5 / Start Profile Positioning / SPtP 6 / Current Limitation / i, L, n 7 / Zero Clamp / CLNP 8 / Velocity Limitation / UL, n 9 / Jog Positive / JoGP 10 / Jog Negative / JoGn 11 / Jog Fast/Slow / JoGF 12 / Gear Ratio Switch / GrARt 13 / Start Single Data Set / dStA 14 / Data Set Select / dSEL 15 / Data Set Bit 0 / d5b0 16 / Data Set Bit 1 / d5b1 17 / Data Set Bit 2 / d5b2 18 / Data Set Bit 3 / d5b3 19 / Gear Offset 1 / GOF1 20 / Gear Offset 2 / GOF2 21 / Reference Switch (REF) / rEF 22 / Positive Limit Switch (LIMP) / L, nP 23 / Negative Limit Switch (LIMN) / L, nN 24 / Switch Controller Parameter Set / CLPRr 27 / Operating Mode Switch / nSLt 28 / Velocity Controller Integral Off / EnoF 29 / Start Motion Sequence / Stn5 35 / Data Set Bit 4 / d5b4 36 / Data Set Bit 5 / d5b5 37 / Data Set Bit 6 / d5b6 38 / Inversion AI11 (IO Module) / R i1 39 / Inversion AI12 (IO Module) / R i2 Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:2h Modbus 1796 Profibus 1796 CIP 107.1.2

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI2 [onF →, -o- di, 2	Function Input DI2 1 / Freely Available / nonE 2 / Fault Reset / FrE5 3 / Enable / EnAb 4 / Halt / hALt 5 / Start Profile Positioning / SPtP 6 / Current Limitation / i, L, n 7 / Zero Clamp / CLnP 8 / Velocity Limitation / VL, n 9 / Jog Positive / JoGP 10 / Jog Negative / JoGn 11 / Jog Fast/Slow / JoGF 12 / Gear Ratio Switch / GrRt 13 / Start Single Data Set / d5tA 14 / Data Set Select / d5EL 15 / Data Set Bit 0 / d5b0 16 / Data Set Bit 1 / d5b1 17 / Data Set Bit 2 / d5b2 18 / Data Set Bit 3 / d5b3 19 / Gear Offset 1 / Gof1 20 / Gear Offset 2 / Gof2 21 / Reference Switch (REF) / rEF 22 / Positive Limit Switch (LIMP) / L, nP 23 / Negative Limit Switch (LIMN) / L, nN 24 / Switch Controller Parameter Set / CLPr 27 / Operating Mode Switch / n5Lt 28 / Velocity Controller Integral Off / tnoF 29 / Start Motion Sequence / 5tM5 35 / Data Set Bit 4 / d5b4 36 / Data Set Bit 5 / d5b5 37 / Data Set Bit 6 / d5b6 38 / Inversion AI11 (IO Module) / R i1 39 / Inversion AI12 (IO Module) / R i2 Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:3 _h Modbus 1798 Profibus 1798 CIP 107.1.3

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI3 CONF →, -> di 3	Function Input DI3 1 / Freely Available / none 2 / Fault Reset / FrE5 3 / Enable / EnAb 4 / Halt / hALt 5 / Start Profile Positioning / SPtP 6 / Current Limitation / L, n 7 / Zero Clamp / CLNP 8 / Velocity Limitation / UL, n 9 / Jog Positive / JoGP 10 / Jog Negative / JoGn 11 / Jog Fast/Slow / JoGF 12 / Gear Ratio Switch / GrARt 13 / Start Single Data Set / dStA 14 / Data Set Select / dSEL 15 / Data Set Bit 0 / d5b0 16 / Data Set Bit 1 / d5b1 17 / Data Set Bit 2 / d5b2 18 / Data Set Bit 3 / d5b3 19 / Gear Offset 1 / GOF1 20 / Gear Offset 2 / GOF2 21 / Reference Switch (REF) / rEF 22 / Positive Limit Switch (LIMP) / L, nP 23 / Negative Limit Switch (LIMN) / L, nN 24 / Switch Controller Parameter Set / CPAr 27 / Operating Mode Switch / nSLt 28 / Velocity Controller Integral Off / EnoF 29 / Start Motion Sequence / StnS 35 / Data Set Bit 4 / d5b4 36 / Data Set Bit 5 / d5b5 37 / Data Set Bit 6 / d5b6 38 / Inversion AI11 (IO Module) / R11 39 / Inversion AI12 (IO Module) / R12 Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:4 _h Modbus 1800 Profibus 1800 CIP 107.1.4

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI4 [onF →, -o- di 4	Function Input DI4 1 / Freely Available / nonE 2 / Fault Reset / FrE5 3 / Enable / EnAb 4 / Halt / hALt 5 / Start Profile Positioning / SPtP 6 / Current Limitation / i L, n 7 / Zero Clamp / CLnP 8 / Velocity Limitation / VL, n 9 / Jog Positive / JoGP 10 / Jog Negative / JoGn 11 / Jog Fast/Slow / JoGF 12 / Gear Ratio Switch / GrRt 13 / Start Single Data Set / d5tA 14 / Data Set Select / d5EL 15 / Data Set Bit 0 / d5b0 16 / Data Set Bit 1 / d5b1 17 / Data Set Bit 2 / d5b2 18 / Data Set Bit 3 / d5b3 19 / Gear Offset 1 / Gof1 20 / Gear Offset 2 / Gof2 21 / Reference Switch (REF) / rEF 22 / Positive Limit Switch (LIMP) / L, nP 23 / Negative Limit Switch (LIMN) / L, nN 24 / Switch Controller Parameter Set / CLPr 27 / Operating Mode Switch / n5Lt 28 / Velocity Controller Integral Off / tnoF 29 / Start Motion Sequence / 5tP5 35 / Data Set Bit 4 / d5b4 36 / Data Set Bit 5 / d5b5 37 / Data Set Bit 6 / d5b6 38 / Inversion AI11 (IO Module) / R i1 39 / Inversion AI12 (IO Module) / R i2 Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:5 _h Modbus 1802 Profibus 1802 CIP 107.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI5 CONF →, -> di 5	Function Input DI5 1 / Freely Available / none 2 / Fault Reset / FrE5 3 / Enable / EnAb 4 / Halt / hALt 5 / Start Profile Positioning / SPtP 6 / Current Limitation / L, n 7 / Zero Clamp / CLNP 8 / Velocity Limitation / UL, n 9 / Jog Positive / JoGP 10 / Jog Negative / JoGn 11 / Jog Fast/Slow / JoGF 12 / Gear Ratio Switch / GrARt 13 / Start Single Data Set / dStA 14 / Data Set Select / dSEL 15 / Data Set Bit 0 / d5b0 16 / Data Set Bit 1 / d5b1 17 / Data Set Bit 2 / d5b2 18 / Data Set Bit 3 / d5b3 19 / Gear Offset 1 / GOF1 20 / Gear Offset 2 / GOF2 21 / Reference Switch (REF) / rEF 22 / Positive Limit Switch (LIMP) / L, nP 23 / Negative Limit Switch (LIMN) / L, nN 24 / Switch Controller Parameter Set / CPAr 27 / Operating Mode Switch / nSLt 28 / Velocity Controller Integral Off / EnoF 29 / Start Motion Sequence / StnS 35 / Data Set Bit 4 / d5b4 36 / Data Set Bit 5 / d5b5 37 / Data Set Bit 6 / d5b6 38 / Inversion AI11 (IO Module) / R11 39 / Inversion AI12 (IO Module) / R12 Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:6h Modbus 1804 Profibus 1804 CIP 107.1.6

8.6.2.2 Configuration of the signal outputs

The table below provides an overview of the possible signal output functions in local control mode depending on the selected operating mode:

Signal output function	Jog	Electronic Gear	Profile Torque	Profile Velocity	Motion Sequence	Description in chapter
Freely Available	•	•	•	•	•	8.7.8 "Setting a signal output via parameter"
No Fault	•	•	•	•	•	8.3.3 "Indication of the operating state"
Active	•	•	•	•	•	8.3.3 "Indication of the operating state"
In Position Deviation Window	•	•			•	8.8.10 "Position deviation window"
In Velocity Deviation Window	•	•		•	•	8.8.11 "Velocity deviation window"
Velocity Threshold Reached	•	•	•	•	•	8.8.12 "Velocity threshold value"
Current Threshold Reached	•	•	•	•	•	8.8.13 "Current threshold value"
Halt Acknowledge	•	•	•	•	•	8.7.1 "Stop movement with Halt"
Motion Sequence: Start Acknowledge					•	8.4.10 "Operating mode Motion Sequence"
Motor Standstill	•	•	•	•	•	8.8.5 "Motor standstill"
Selected Error	•	•	•	•	•	8.3.3 "Indication of the operating state"
Drive Referenced (ref_ok)					•	8.4.9 "Operating mode Homing"
Selected Warning	•	•	•	•	•	8.3.3 "Indication of the operating state"
Motion Sequence: Done					•	8.4.10 "Operating mode Motion Sequence"

The table below provides an overview of the possible signal output functions depending in fieldbus control mode:

Signal output function	Description in chapter
Freely Available	8.7.8 "Setting a signal output via parameter"
No Fault	8.3.3 "Indication of the operating state"
Active	8.3.3 "Indication of the operating state"
In Position Deviation Window	8.8.10 "Position deviation window"
In Velocity Deviation Window	8.8.11 "Velocity deviation window"
Velocity Threshold Reached	8.8.12 "Velocity threshold value"
Current Threshold Reached	8.8.13 "Current threshold value"
Halt Acknowledge	8.7.1 "Stop movement with Halt"
Motion Sequence: Start Acknowledge	8.4.10 "Operating mode Motion Sequence"
Motor Standstill	8.8.5 "Motor standstill"
Selected Error	8.3.3 "Indication of the operating state"
Drive Referenced (ref_ok)	8.4.9 "Operating mode Homing"
Selected Warning	8.3.3 "Indication of the operating state"
Motion Sequence: Done	8.4.10 "Operating mode Motion Sequence"
Position Register Channel 1	8.8.9 "Position register"
Position Register Channel 2	8.8.9 "Position register"
Position Register Channel 3	8.8.9 "Position register"
Position Register Channel 4	8.8.9 "Position register"

The following parameters can be used to parameterize the digital signal outputs:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DQ0 [onF →, -o- do0]	<p>Function Output DQ0</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / No Fault / nFLt: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / i n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / i n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / i thr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hRLt: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nStd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFa: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SLrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nSLa: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrC1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrC2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrC3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrC4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:9h Modbus 1810 Profibus 1810 CIP 107.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DQ1 [onF →, -o- do]	<p>Function Output DQ1</p> <p>1 / Freely Available / onF: Available as required</p> <p>2 / No Fault / nFLt: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / i n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / i n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / i thr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALt: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nStd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFo: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nSLd: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrL1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrL2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrL3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrL4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:Ah Modbus 1812 Profibus 1812 CIP 107.1.10

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DQ2 [onF →, -o- do2	<p>Function Output DQ2</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / No Fault / nFLt: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / , n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / , n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / , thr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALt: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nStd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFo: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nScd: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrC1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrC2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrC3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrC4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:B _h Modbus 1814 Profibus 1814 CIP 107.1.11

8.6.3 Setting the motion profile for the velocity

Target position and target velocity are input values specified by the user. A motion profile for the velocity is calculated on the basis of these input values.

The motion profile for the velocity consists of an acceleration, a deceleration and a maximum velocity.

A linear ramp for both directions of movement is available.

Availability The availability of the motion profile for the velocity depends on the operating mode.

In the following operating modes, the motion profile for the velocity is permanently active:

- Jog
- Profile Position
- Homing
- Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)

In the following operating modes, the motion profile for the velocity can be activated and deactivated:

- Electronic Gear (velocity synchronization)
- Profile Velocity
- Motion Sequence (Move Velocity)

In the following operating modes, the motion profile for the velocity is unavailable:

- Electronic Gear (position synchronization)
- Profile Torque
- Interpolated Position

Ramp slope The ramp slope determines the velocity changes of the motor per time unit. The ramp slope can be set for acceleration and deceleration.

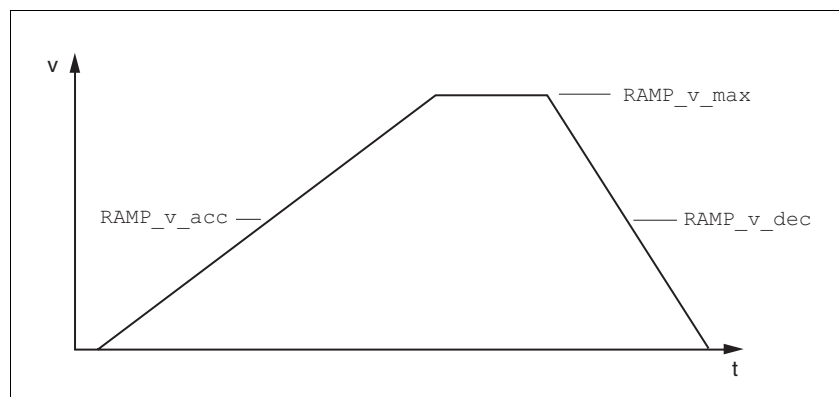


Figure 8.41 Ramp slope

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RAMP_v_enable	<p>Activation of the motion profile for velocity</p> <p>0 / Profile Off: Profile off 1 / Profile On: Profile on</p> <p>The motion profile for velocity can be activated or deactivated for the operating modes Profile Velocity and Electronic Gear (velocity synchronization).</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2B _h Modbus 1622 Profibus 1622 CIP 106.1.43
RAMP_v_max CONF → RCU- rnp	<p>Maximum velocity of the motion profile for velocity</p> <p>If a greater reference speed is set in one of these operating modes, it is automatically limited to RAMP_v_max. This way, commissioning at limited speed is easier to perform.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_v 1 13200 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 607F:0 _h Modbus 1554 Profibus 1554 CIP 106.1.9
RAMP_v_acc	<p>Acceleration of the motion profile for velocity</p> <p>Writing the value 0 has no effect on the parameter.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6083:0 _h Modbus 1556 Profibus 1556 CIP 106.1.10
RAMP_v_dec	<p>Deceleration of the motion profile for velocity</p> <p>The minimum value depends on the operating mode:</p> <p>Operating modes with minimum value 1: Electronic Gear (velocity synchronisation) Profile Velocity Motion Sequence (Move Velocity)</p> <p>Operating modes with minimum value 120: Jog Profile Position Homing Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)</p> <p>Writing the value 0 has no effect on the parameter.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6084:0 _h Modbus 1558 Profibus 1558 CIP 106.1.11

8.6.4 Setting the controller parameters

8.6.4.1 Overview of the controller structure

The illustration below shows an overview of the controller structure.

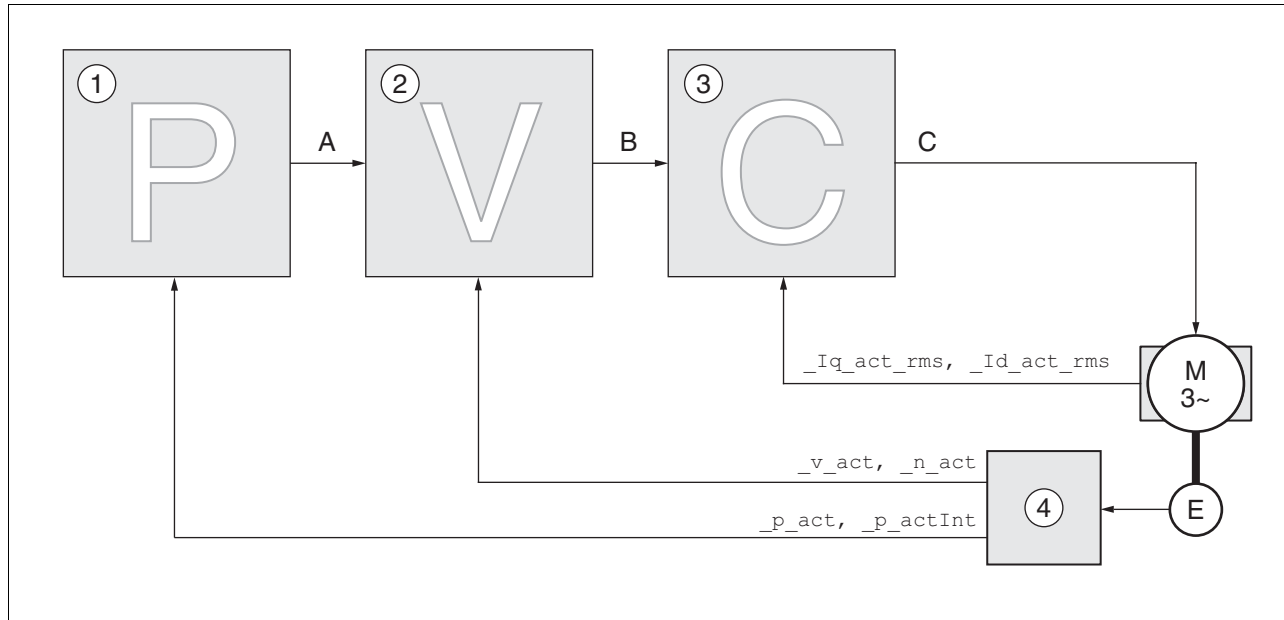


Figure 8.42 Controller structure, overview

- (1) Position controller
- (2) Velocity controller
- (3) Current controller
- (4) Encoder evaluation

Position controller

The position controller reduces the difference between the reference position and the actual position of the motor (position deviation) to a minimum. When the motor is at a standstill, the position deviation is close to zero in the case of a well-tuned position controller.

An optimized velocity control loop is a prerequisite for good amplification of the position controller.

Velocity controller

The velocity controller controls the motor velocity by varying the motor current depending on the load situation. The velocity controller has a decisive influence on the dynamic response of the drive. The dynamics of the velocity controller depend on:

- Moment of inertia of the drive and the controlled system
- Power of the motor
- Stiffness and elasticity of the elements in the flow of forces
- Backlash of the drive elements
- Friction

Current controller

The current controller determines the torque of the motor. The current controller is automatically optimally tuned with the stored motor data.

8.6.4.2 Overview of position controller

The illustration below shows an overview of the position controller.

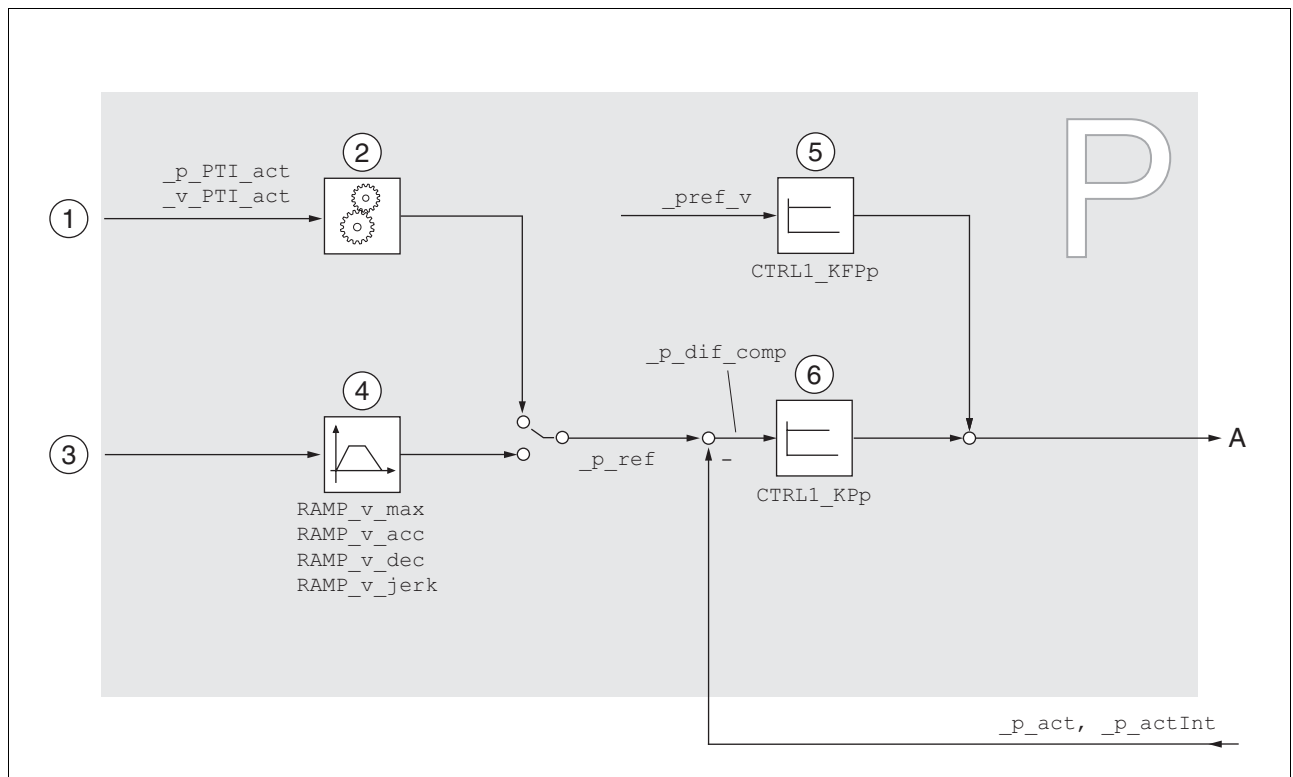


Figure 8.43 Position controller

- (1) Reference value signals for the operating mode Electronic Gear with the methods "Position Synchronization Without Compensation Movement" and "Position Synchronization With Compensation Movement"
- (2) Evaluation of the reference value signal for the operating mode Electronic Gear
- (3) Target values for the operating modes Jog, Profile Position, Homing and Motion Sequence
- (4) Motion profile for the velocity
- (5) Velocity feed-forward control
- (6) Position controller

8.6.4.3 Overview of velocity controller

The illustration below shows an overview of the velocity controller.

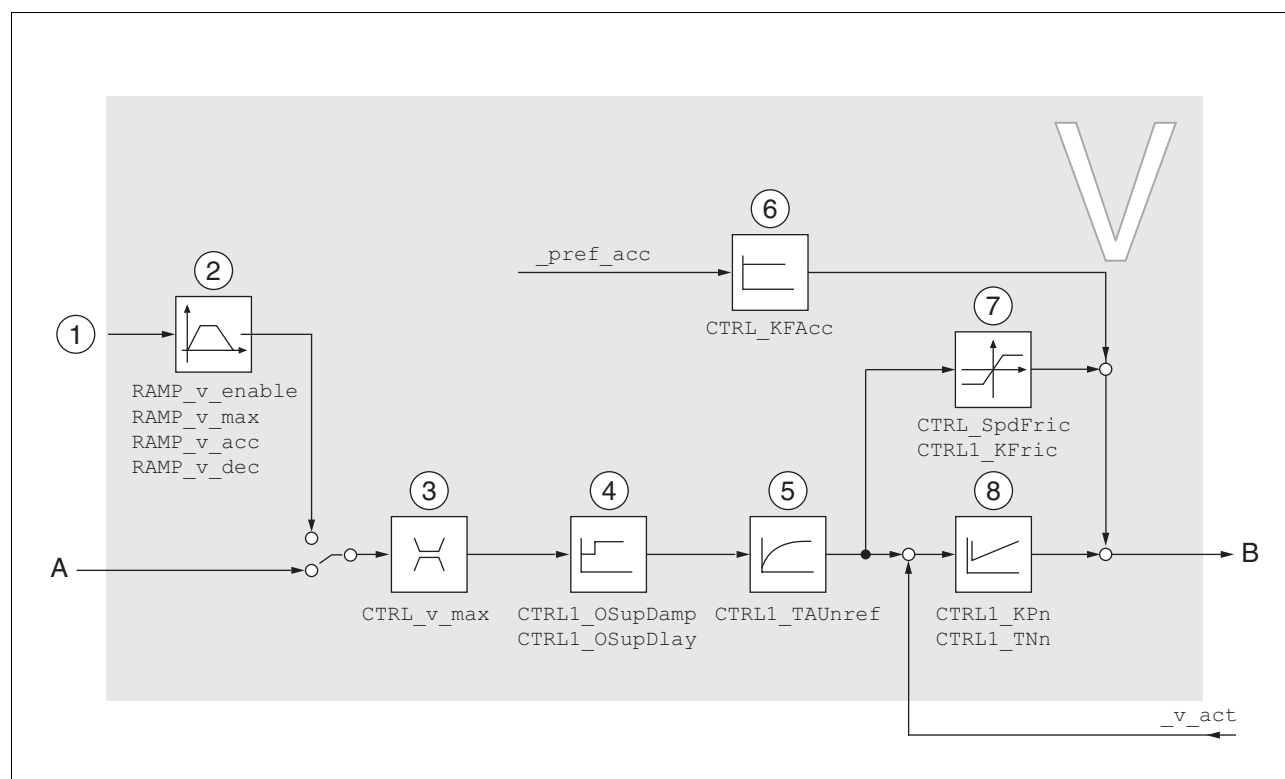


Figure 8.44 Velocity controller

- (1) Reference value signals for the operating mode Electronic Gear with the method "Velocity Synchronization" and target values for the operating mode Profile Velocity
- (2) Motion profile for the velocity
- (3) Velocity limitation
- (4) Overshoot suppression filter (parameter accessible in Expert mode)
- (5) Filter time constant of reference velocity value filter
- (6) Acceleration feed forward control (parameter accessible in Expert mode)
- (7) Friction compensation (parameter accessible in Expert mode)
- (8) Velocity controller

8.6.4.4 Overview of current controller

The illustration below shows an overview of the current controller.

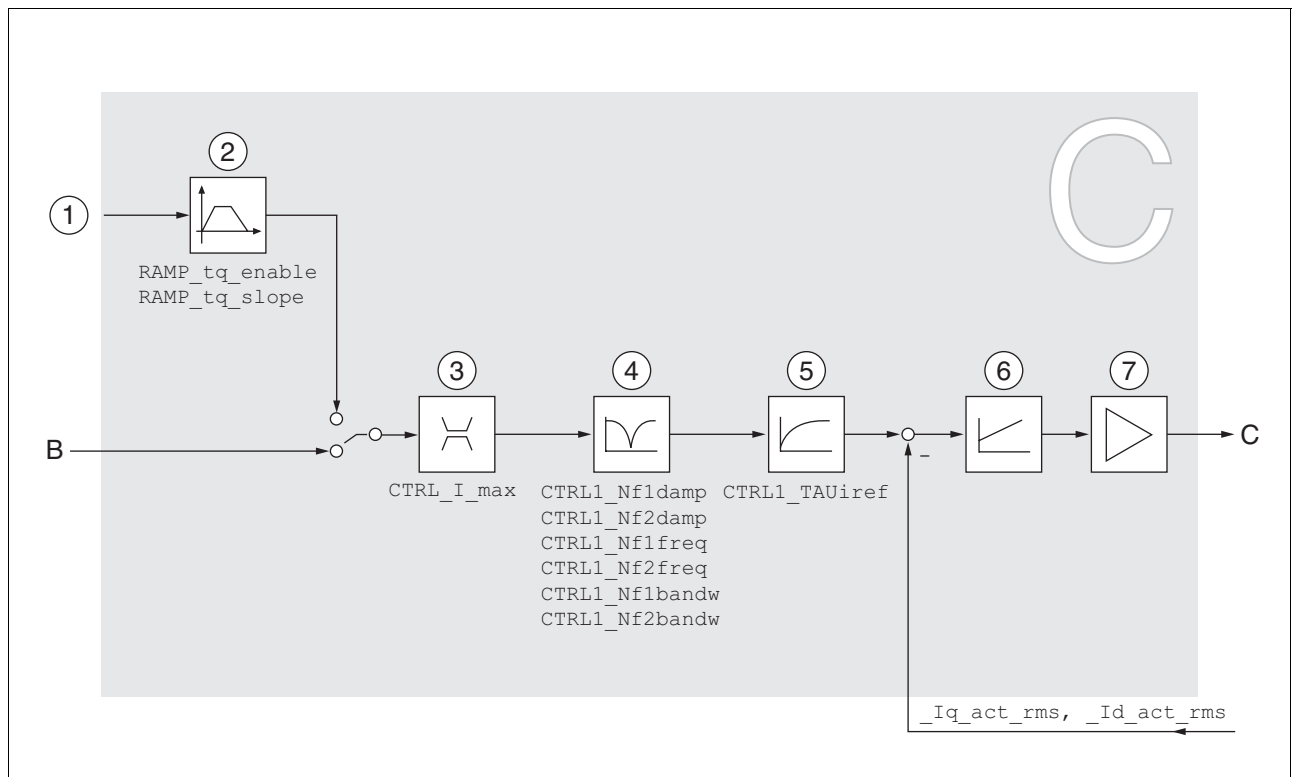


Figure 8.45 Current controller

- (1) Target values for the operating mode Profile Torque
- (2) Motion profile for the torque
- (3) Current limitation
- (4) Notch filter (parameter accessible in Expert mode)
- (5) Filter time constant of the reference current value filter
- (6) Current controller
- (7) Power stage

8.6.4.5 Parameterizable controller parameter

The product features 2 controller parameter sets that can be parameterized separately. The values for the controller parameters determined during autotuning are stored in controller parameter set 1.

Controller parameter set

A controller parameter set consists of freely accessible parameters and parameters which are only accessible in Expert mode.

Controller parameter set 1	Controller parameter set 2
Freely accessible parameters: CTRL1_KPn CTRL1_TNn CTRL1_KPp CTRL1_TAUiref CTRL1_TAUUnref CTRL1_KFPp Parameters only accessible in expert mode: CTRL1_Nf1damp CTRL1_Nf1freq CTRL1_Nf1bandw CTRL1_Nf2damp CTRL1_Nf2freq CTRL1_Nf2bandw CTRL1_Osupdamp CTRL1_Osupdelay CTRL1_Kfric	Freely accessible parameters: CTRL2_KPn CTRL2_TNn CTRL2_KPp CTRL2_TAUiref CTRL2_TAUUnref CTRL2_KFPp Parameters only accessible in expert mode: CTRL2_Nf1damp CTRL2_Nf1freq CTRL2_Nf1bandw CTRL2_Nf2damp CTRL2_Nf2freq CTRL2_Nf2bandw CTRL2_Osupdamp CTRL2_Osupdelay CTRL2_Kfric

See chapters 8.6.4.10 "Controller parameter set 1" and 8.6.4.11 "Controller parameter set 2".

Parameterization

- Selecting a controller parameter set
Select a controller parameter set after switching on.
See chapter 8.6.4.6 "Selecting a controller parameter set".
- Automatically switching between control parameter sets
It is possible to switch between the two controller parameter sets.
See chapter 8.6.4.7 "Automatically switching between control parameter sets".
- Copying a controller parameter set
The values of controller parameter set 1 can be copied to controller parameter set 2.
See chapter 8.6.4.8 "Copying a controller parameter set".
- Deactivating the integral term
The integral term and, by implication, the integral action time, can be switched off via a digital signal input.
See chapter 8.6.4.9 "Deactivating the integral term".

8.6.4.6 Selecting a controller parameter set

The currently active controller parameter set is indicated via the parameter `_CTRL_ActParSet`.

The parameter `CTRL_PwrUpParSet` allows you to set the controller parameter set to be activated after switching on. Alternatively, you can set whether or not the product is to switch automatically between the two controller parameter sets.

The parameter `CTRL_SelParSet` allows you to switch between the two controller parameter sets during operation.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_CTRL_ActParSet</code>	Active controller parameter set Value 1: Controller parameter set 1 is active Value 2: Controller parameter set 2 is active A controller parameter set is active after the time for the parameter switching (<code>CTRL_ParChgTime</code>) has elapsed.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3011:17 _h Modbus 4398 Profibus 4398 CIP 117.1.23
<code>CTRL_PwrUpParSet</code>	Selection of controller parameter set at power up 0 / Switching Condition: The switching condition is used for parameter set switching 1 / Parameter Set 1: Parameter set 1 is used 2 / Parameter Set 2: Parameter set 2 is used The selected value is also written to <code>CTRL_ParSetSel</code> (non-persistent). Changed settings become active immediately.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:18 _h Modbus 4400 Profibus 4400 CIP 117.1.24
<code>CTRL_SelParSet</code>	Selection of controller parameter set (non-persistent) Coding see parameter: <code>CTRL_PwrUpParSet</code> Changed settings become active immediately.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3011:19 _h Modbus 4402 Profibus 4402 CIP 117.1.25

8.6.4.7 Automatically switching between control parameter sets

It is possible to automatically switch between the two controller parameter sets.

The following criteria can be set for switching between the controller parameter sets:

- Digital signal input
- Position deviation window
- Target velocity below parameterizable value
- Actual velocity below parameterizable value

Settings

The illustration below shows an overview of switching between the controller parameter sets.

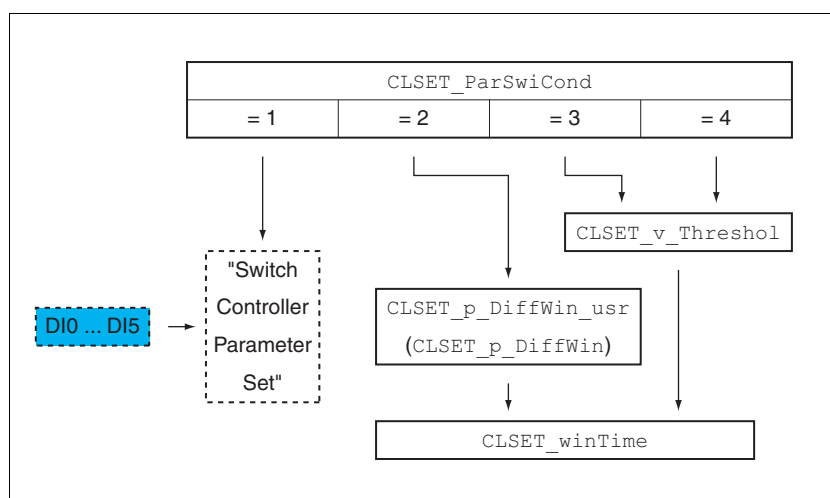


Figure 8.46 Parameters for switching the controller parameter sets

Time chart The freely accessible parameters are changed linearly. This linear change of the values of controller parameter set 1 to the values of controller parameter set 2 takes place during the parameterizable time CTRL_ParChgTime.

The parameters only accessible in Expert mode are directly changed to the values of the other controller parameter set after the parameterizable time CTRL_ParChgTime has passed.

The figure below shows the time chart for switching the controller parameters.

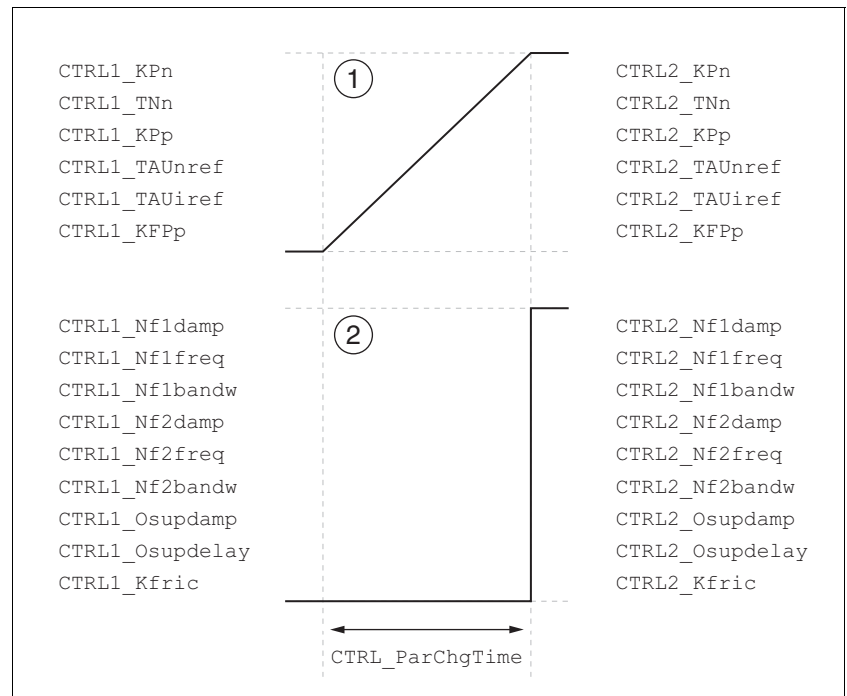


Figure 8.47 Time chart for switching the controller parameter sets

- (1) Freely accessible parameters are changed linearly over time
- (2) Parameters which are only accessible in Expert mode are switched over directly

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CLSET_ParSwiCond	<p>Condition for parameter set switching</p> <p>0 / None Or Digital Input: None or digital input function selected</p> <p>1 / Inside Position Deviation: Inside position deviation (value definition in parameter CLSET_p_DiffWin)</p> <p>2 / Below Reference Velocity: Below reference velocity (value definition in parameter CLSET_v_Threshold)</p> <p>3 / Below Actual Velocity: Below actual velocity (value definition in parameter CLSET_v_Threshold)</p> <p>In the case of parameter set switching, the values of the following parameters are changed gradually:</p> <ul style="list-style-type: none"> - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAUref - CTRL_TAUiref - CTRL_KFPp <p>The following parameters are changed immediately after the time for parameter set switching (CTRL_ParChgTime):</p> <ul style="list-style-type: none"> - CTRL_Nf1damp - CTRL_Nf1freq - CTRL_Nf1bandw - CTRL_Nf2damp - CTRL_Nf2freq - CTRL_Nf2bandw - CTRL_Osupdamp - CTRL_Osupdelay - CTRL_Kfric <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:1A _h Modbus 4404 Profibus 4404 CIP 117.1.26
CLSET_p_DiffWin_usr	<p>Position deviation for parameter set switching</p> <p>If the position deviation of the position controller is less than the value of this parameter, the controller parameter set 2 is used. Otherwise, controller parameter set 1 is used.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor</p> <p>Changed settings become active immediately.</p>	usr_p 0 164 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3011:25 _h Modbus 4426 Profibus 4426 CIP 117.1.37

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CLSET_p_DiffWin	<p>Position deviation for parameter set switching</p> <p>If the position deviation of the position controller is less than the value of this parameter, the controller parameter set 2 is used. Otherwise, controller parameter set 1 is used.</p> <p>The parameter CLSET_p_DiffWin_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	revolution 0.0000 0.0100 2.0000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:1C _h Modbus 4408 Profibus 4408 CIP 117.1.28
CLSET_v_Threshold	<p>Velocity threshold for parameter set switching</p> <p>If the reference velocity or the actual velocity are less than the value of this parameter, the controller parameter set 2 is used. Otherwise, controller parameter set 1 is used.</p> <p>Changed settings become active immediately.</p>	usr_v 0 50 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3011:1D _h Modbus 4410 Profibus 4410 CIP 117.1.29
CLSET_winTime	<p>Time window for parameter set switching</p> <p>Value 0: Window monitoring deactivated. Value >0: Window time for the parameters CLSET_v_Threshold and CLSET_p_DiffWin.</p> <p>Changed settings become active immediately.</p>	ms 0 0 1000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:1B _h Modbus 4406 Profibus 4406 CIP 117.1.27
CTRL_ParChgTime	<p>Period of time for parameter switching</p> <p>In the case of parameter set switching, the values of the following parameters are changed gradually:</p> <ul style="list-style-type: none"> - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAUref - CTRL_TAUiref - CTRL_KFPp <p>Such a parameter switching can be caused by</p> <ul style="list-style-type: none"> - change of the active controller parameter set - change of the global gain - change of any of the parameters listed above - switching off the integral term of the velocity controller <p>Changed settings become active immediately.</p>	ms 0 0 2000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:14 _h Modbus 4392 Profibus 4392 CIP 117.1.20

8.6.4.8 Copying a controller parameter set

The parameter CTRL_ParSetCopy allows you to copy the values of controller parameter set 1 to controller parameter set 2 or the values of controller parameter set 2 to controller parameter set 1.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_ParSetCopy	<p>Controller parameter set copying</p> <p>Value 1: Copy controller parameter set 1 to set 2</p> <p>Value 2: Copy controller parameter set 2 to set 1</p> <p>If parameter set 2 copied to parameter set 1, the parameter CTRL_GlobGain is set to 100%.</p> <p>Changed settings become active immediately.</p>	<p>-</p> <p>0.0</p> <p>-</p> <p>0.2</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 3011:16_h</p> <p>Modbus 4396</p> <p>Profibus 4396</p> <p>CIP 117.1.22</p>

8.6.4.9 Deactivating the integral term

The integral term of the velocity controller can be deactivated via the signal input function "Velocity Controller Integral Off". If the integral term is deactivated, the integral action time of the velocity controller (CTRL1_TNn and CTRL2_TNn) is implicitly and gradually reduced to zero. The time it takes to reduce the value to zero depends on the parameter CTRL_ParChgTime. In the case of vertical axes, the integral term is needed to reduce position deviations during standstill.

8.6.4.10 Controller parameter set 1

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_KPn [onF → dr[- Pn I	Velocity controller P gain The default value is calculated on the basis of the motor parameters. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.0001 A/min ⁻¹ . Changed settings become active immediately.	A/min ⁻¹ 0.0001 - 1.2700	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:1 _h Modbus 4610 Profibus 4610 CIP 118.1.1
CTRL1_TNn [onF → dr[- t, n I	Velocity controller integral action time The default value is calculated on the basis of CTRL_TAUiref. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 - 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:2 _h Modbus 4612 Profibus 4612 CIP 118.1.2
CTRL1_KPp [onF → dr[- PP I	Position controller P gain The default value is calculated. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 1/s. Changed settings become active immediately.	1/s 2.0 - 900.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:3 _h Modbus 4614 Profibus 4614 CIP 118.1.3
CTRL1_TAUiref	Filter time constant of the reference current value filter This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.50 4.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:5 _h Modbus 4618 Profibus 4618 CIP 118.1.5
CTRL1_TAUhref [onF → dr[- t, Ru I	Filter time constant of the reference velocity value filter This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 9.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:4 _h Modbus 4616 Profibus 4616 CIP 118.1.4
CTRL1_KFPp [onF → dr[- FPP I	Velocity feed-forward This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 200.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:6 _h Modbus 4620 Profibus 4620 CIP 118.1.6

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_Nf1damp	Notch filter 1: Damping In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:8 _h Modbus 4624 Profibus 4624 CIP 118.1.8
CTRL1_Nf1freq	Notch filter 1: Frequency The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:9 _h Modbus 4626 Profibus 4626 CIP 118.1.9
CTRL1_Nf1bandw	Notch filter 1: Bandwidth Definition of bandwidth: 1 - Fb/F0 In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:A _h Modbus 4628 Profibus 4628 CIP 118.1.10
CTRL1_Nf2damp	Notch filter 2: Damping In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:B _h Modbus 4630 Profibus 4630 CIP 118.1.11
CTRL1_Nf2freq	Notch filter 2: Frequency The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:C _h Modbus 4632 Profibus 4632 CIP 118.1.12
CTRL1_Nf2bandw	Notch filter 2: Bandwidth Definition of bandwidth: 1 - Fb/F0 In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:D _h Modbus 4634 Profibus 4634 CIP 118.1.13
CTRL1_Osupdamp	Overshoot suppression filter: Damping The filter is switched off at a value of 0. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 50.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:E _h Modbus 4636 Profibus 4636 CIP 118.1.14
CTRL1_Osupdelay	Overshoot suppression filter: Time delay The filter is switched off at a value of 0. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.00 75.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:F _h Modbus 4638 Profibus 4638 CIP 118.1.15

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_Kfric	Friction compensation: Gain In increments of 0.01 A_{rms} . Changed settings become active immediately.	A_{rms} 0.00 0.00 10.00	UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:10 _h Modbus 4640 Profibus 4640 CIP 118.1.16

8.6.4.11 Controller parameter set 2

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL2_KFPp [onF → dr[- FPP2	Velocity feed-forward This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 200.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:6 _h Modbus 4876 Profibus 4876 CIP 119.1.6
CTRL2_Kfric	Friction compensation: Gain In increments of 0.01 A _{rms} . Changed settings become active immediately.	A _{rms} 0.00 0.00 10.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:10 _h Modbus 4896 Profibus 4896 CIP 119.1.16
CTRL2_KPn [onF → dr[- Pn2	Velocity controller P gain The default value is calculated on the basis of the motor parameters. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.0001 A/min ⁻¹ . Changed settings become active immediately.	A/min ⁻¹ 0.0001 - 1.2700	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:1 _h Modbus 4866 Profibus 4866 CIP 119.1.1
CTRL2_KPp [onF → dr[- PP2	Position controller P gain The default value is calculated. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 1/s. Changed settings become active immediately.	1/s 2.0 - 900.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:3 _h Modbus 4870 Profibus 4870 CIP 119.1.3
CTRL2_Nf1bandw	Notch filter 1: Bandwidth Definition of bandwidth: 1 - Fb/F0 In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:A _h Modbus 4884 Profibus 4884 CIP 119.1.10
CTRL2_Nf1damp	Notch filter 1: Damping In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:8 _h Modbus 4880 Profibus 4880 CIP 119.1.8
CTRL2_Nf1freq	Notch filter 1: Frequency The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:9 _h Modbus 4882 Profibus 4882 CIP 119.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL2_Nf2bandw	Notch filter 2: Bandwidth Definition of bandwidth: $1 - F_b/F_0$ In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:D _h Modbus 4890 Profibus 4890 CIP 119.1.13
CTRL2_Nf2damp	Notch filter 2: Damping In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:B _h Modbus 4886 Profibus 4886 CIP 119.1.11
CTRL2_Nf2freq	Notch filter 2: Frequency The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:C _h Modbus 4888 Profibus 4888 CIP 119.1.12
CTRL2_Osupdamp	Overshoot suppression filter: Damping The filter is switched off at a value of 0. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 50.0	UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:E _h Modbus 4892 Profibus 4892 CIP 119.1.14
CTRL2_Osupdelay	Overshoot suppression filter: Time delay The filter is switched off at a value of 0. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.00 75.00	UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:F _h Modbus 4894 Profibus 4894 CIP 119.1.15
CTRL2_TAUiref	Filter time constant of the reference current value filter This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.50 4.00	UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:5 _h Modbus 4874 Profibus 4874 CIP 119.1.5
CTRL2_TAUiref [onF → dr[- tR _{u2}	Filter time constant of the reference velocity value filter This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 9.00 327.67	UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:4 _h Modbus 4872 Profibus 4872 CIP 119.1.4

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL2_TNn [Ctrl] → [dr] - [t, n]	<p>Velocity controller integral action time</p> <p>The default value is calculated on the basis of CTRL_TAUref.</p> <p>This parameter is switched gradually over the time defined in CTRL_ParChgTime.</p> <p>In increments of 0.01 ms.</p> <p>Changed settings become active immediately.</p>	<p>ms</p> <p>0.00</p> <p>-</p> <p>327.67</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3013:2_h</p> <p>Modbus 4868</p> <p>Profibus 4868</p> <p>CIP 119.1.2</p>

8.6.5 Settings of parameter _DCOMstatus

The meaning of bit 11 of the parameter _DCOMstatus can be set.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_DCOMstatus	DriveCom status word Bits 0 ... 3: Status bits Bit 4: Voltage enabled Bits 5 ... 6: Status bits Bit 7: Warning Bit 8: HALT request active Bit 9: Remote Bit 10: Target reached Bit 11: Internal limit Bit 12: Operating mode-specific Bit 13: x_err Bit 14: x_end Bit 15: ref_ok The meaning of bit 11 can be set via the parameter DS402intLim.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 6041:0 _h Modbus 6916 Profibus 6916 CIP 127.1.2

The meaning of bit 11 can be set via the parameter DS402intLim.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DS402intLim	DS402 status word: Setting for bit 11 (internal limit) 0 / None: Not used (reserved) 1 / Current Below Threshold: Current threshold value 2 / Velocity Below Threshold: Velocity threshold value 3 / In Position Deviation Window: Position deviation window 4 / In Velocity Deviation Window: Velocity deviation window 5 / Position Register Channel 1: Position register channel 1 6 / Position Register Channel 2: Position register channel 2 7 / Position Register Channel 3: Position register channel 3 8 / Position Register Channel 4: Position register channel 4 9 / Hardware Limit Switch: Hardware limit switch 10 / RMAC active or finished: Relative movement after capture is active or finished 11 / Standstill Window: Standstill window Setting for: - bit 11 of the parameter _DCOMstatus and - bit 10 of the parameters _motionStat and _actionStatus Changed settings become active immediately.	- 0 0 11	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 301B:1E _h Modbus 6972 Profibus 6972 CIP 127.1.30

8.7 Functions for target value processing

8.7.1 Stop movement with Halt

With a Halt, the current movement is interrupted; it can be resumed.

A Halt can be triggered via a digital signal input or a fieldbus command.

In order to interrupt a movement via a signal input, you must parameterize the signal input function "Halt", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

The movement can be interrupted with 2 different deceleration types.

- Deceleration via deceleration ramp
- Deceleration via torque ramp

Setting the type of deceleration

The parameter LIM_HaltReaction lets you set the type of deceleration.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_HaltReaction CONF → REG- help	<p>Halt option code</p> <p>1 / Deceleration Ramp / decE: Deceleration ramp</p> <p>3 / Torque Ramp / Torq: Torque ramp</p> <p>Type of deceleration for Halt.</p> <p>Setting of deceleration ramp with parameter RAMP_v_dec.</p> <p>Setting of torque ramp with parameter LIM_I_maxHalt.</p> <p>If a deceleration ramp is already active, the parameter cannot be written.</p> <p>Changed settings become active immediately.</p>	- 1 1 3	INT16 INT16 INT16 INT16 R/W per. -	CANopen 605D:0h Modbus 1582 Profibus 1582 CIP 106.1.23

Setting the deceleration ramp The deceleration ramp is set with the parameter Ramp_v_dec via the motion profile for the velocity, see chapter 8.6.3 "Setting the motion profile for the velocity". The parameter Ramp_v_dec is available in all operating modes.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IO_ModeSwitch [onF → RCU- , onS	Operating mode for signal input function Operating Mode Switch 0 / None / none : None 1 / Profile Torque / Torq : Profile Torque 2 / Profile Velocity / VELP : Profile Velocity 3 / Electronic Gear / GEAR : Electronic Gear Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2F _h Modbus 1630 Profibus 1630 CIP 106.1.47
RAMP_v_dec	Deceleration of the motion profile for velocity The minimum value depends on the operating mode: Operating modes with minimum value 1: Electronic Gear (velocity synchronisation) Profile Velocity Motion Sequence (Move Velocity) Operating modes with minimum value 120: Jog Profile Position Homing Motion Sequence (Move Absolute, Move Realtime, Reference Movement and Move Additive) Writing the value 0 has no effect on the parameter. Changed settings become active the next time the motor moves.	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6084:0 _h Modbus 1558 Profibus 1558 CIP 106.1.11

Setting the torque ramp The parameter LIM_I_maxHalt lets you set the torque ramp.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_I_maxHalt CONF → REG- hcur	<p>Current value for Halt</p> <p>This value is only limited by the minimum/maximum value range (no limitation of this value by motor/power stage).</p> <p>In the case of a Halt, the actual current limit (I_{max_actual}) is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - LIM_I_maxHalt - M_I_max - PA_I_max <p>Further current reductions caused by I_{2t} monitoring are also taken into account during a Halt.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:E _h Modbus 4380 Profibus 4380 CIP 117.1.14

8.7.2 Stopping a movement with Quick Stop

With a Quick Stop, the current movement is stopped.

A Quick Stop can be triggered by an error of error classes 1 or 2 or via a fieldbus command.

The movement can be stopped with 2 different deceleration types.

- Deceleration via deceleration ramp
- Deceleration via torque ramp

In addition, you can set the operating state to switch to after the deceleration.

- Transition to operating state **9** Fault
- Transition to operating state **7** Quick Stop Active

Setting the type of deceleration The parameter LIM_QStopReact lets you set the type of deceleration.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_QStopReact	<p>Quick Stop option code</p> <p>-2 / Torque ramp (Fault): Use torque ramp and transit to operating state 9 Fault</p> <p>-1 / Deceleration Ramp (Fault): Use deceleration ramp and transit to operating state 9 Fault</p> <p>6 / Deceleration ramp (Quick Stop): Use deceleration ramp and remain in operating state 7 Quick Stop</p> <p>7 / Torque ramp (Quick Stop): Use torque ramp and remain in operating state 7 Quick Stop</p> <p>Type of deceleration for Quick Stop.</p> <p>Setting of deceleration ramp with parameter RAMPquickstop.</p> <p>Setting of torque ramp with parameter LIM_I_maxQSTP.</p> <p>If a deceleration ramp is already active, the parameter cannot be written.</p> <p>Changed settings become active immediately.</p>	- -2 6 7	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3006:18 _h Modbus 1584 Profibus 1584 CIP 106.1.24

Setting the deceleration ramp The parameter RAMPquickstop lets you set the deceleration ramp.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RAMPquickstop	<p>Deceleration ramp for Quick Stop</p> <p>Deceleration ramp for a software stop or an error with error class 1 or 2.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_a 1 6000 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:12 _h Modbus 1572 Profibus 1572 CIP 106.1.18

Setting the torque ramp The parameter LIM_I_maxQSTP lets you set the torque ramp.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_I_maxQSTP CONF → FLT - qcur	<p>Current value for Quick Stop</p> <p>This value is only limited by the minimum/maximum value range (no limitation of this value by motor/power stage).</p> <p>In the case of a Quick Stop, the actual current limit (I_{max_actual}) is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - LIM_I_maxQSTP - M_I_max - PA_I_max <p>Further current reductions caused by I_{2t} monitoring are also taken into account during a Quick Stop.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:D _h Modbus 4378 Profibus 4378 CIP 117.1.13

8.7.3 Inverting the analog signal inputs

The evaluation of the analog signal inputs can be inverted via the digital signal inputs.

- The signal input function "Inversion AI11 (I/O module) " inverts the signal evaluation of the analog signal input AI11.
- The signal input function "Inversion AI12 (I/O module) " inverts the signal evaluation of the analog signal input AI12.

In order to invert the signal evaluation of the analog signal inputs, you must parameterize the signal input functions "Inversion AI11 (I/O module)" and "Inversion AI12 (I/O module)", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

Availability Analog signal inputs are available with the IOM1 module.

The signal input functions are available in the following operating modes:

- Profile Torque
- Profile Velocity

8.7.4 Limitation of the velocity via signal inputs

Limitation analog signal input The velocity can be limited via an analog signal input.

Analog signal inputs are available with the IOM1 module.

The parameters IOM1_AI11_mode and IOM1_AI12_mode let you select the type of usage of the analog signal inputs.

- If you do not want to use the analog signal input, set the parameter AI1 to IOM1_AI11_mode the value "Velocity Limitation".

If you do not want to use the analog signal input, set the parameter AI2 to IOM1_AI12_mode the value "Velocity Limitation".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI11_mode [onF →, -o- R11u	<p>IOM1 Type of usage of AI11</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Lr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 1 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:E _h Modbus 20252 Profibus 20252 CIP 179.1.14
IOM1_AI12_mode [onF →, -o- R12u	<p>IOM1 Type of usage of AI12</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Lr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:13 _h Modbus 20262 Profibus 20262 CIP 179.1.19

The parameters `IOM1_AI11_v_max` and `IOM1_AI12_v_max` are used to set the value of the limitation for a voltage value of +10V.

- If you want to use the analog signal input AI11, use the parameter `IOM1_AI11_v_max` to set the value of the limitation for a voltage value of +10V.

If you want to use the analog signal input AI12, use the parameter `IOM1_AI12_v_max` to set the value of the limitation for a voltage value of +10V.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IOM1_AI11_v_max</code>	<p>IOM1 Limitation of velocity at 10 V of AI11</p> <p>The maximum velocity is limited to the setting in <code>CTRL_v_max</code>.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	<p>usr_v</p> <p>1</p> <p>3000</p> <p>2147483647</p>	<p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:10_h</p> <p>Modbus 20256</p> <p>Profibus 20256</p> <p>CIP 179.1.16</p>
<code>IOM1_AI12_v_max</code>	<p>IOM1 Limitation of velocity at 10 V of AI12</p> <p>The maximum velocity is limited to the setting in <code>CTRL_v_max</code>.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	<p>usr_v</p> <p>1</p> <p>3000</p> <p>2147483647</p>	<p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:15_h</p> <p>Modbus 20266</p> <p>Profibus 20266</p> <p>CIP 179.1.21</p>

Limitation via digital signal input The velocity can be limited to a specific value via a digital signal input. The parameter `IO_v_limit` lets you set the velocity limitation.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IO_v_limit</code>	<p>Velocity limitation via input</p> <p>A velocity limitation can be activated via a digital input.</p> <p>NOTE: In operating mode Profile Torque, the minimum velocity is internally limited to 100 min⁻¹.</p> <p>Changed settings become active immediately.</p>	<p>usr_v</p> <p>1</p> <p>10</p> <p>2147483647</p>	<p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3006:1E_h</p> <p>Modbus 1596</p> <p>Profibus 1596</p> <p>CIP 106.1.30</p>

In order to limit the velocity via a digital signal input, you must parameterize the signal input function "Velocity Limitation", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.7.5 Limitation of the current via signal inputs

Limitation analog signal input The current can be limited via an analog signal input.

Analog signal inputs are available with the IOM1 module.

The parameters `IOM1_AI11_mode` and `IOM1_AI12_mode` let you select the type of usage of the analog signal inputs.

- If you do not want to use the analog signal input, set the parameter `AI1` to `IOM1_AI11_mode` the value "Current Limitation".

If you do not want to use the analog signal input, set the parameter `AI2` to `IOM1_AI12_mode` the value "Current Limitation".

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IOM1_AI11_mode</code> <i>Conf → , -a-</i> <i>RI1u</i>	<p>IOM1 Type of usage of AI11</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Lr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 1 4	UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:E _h Modbus 20252 Profibus 20252 CIP 179.1.14
<code>IOM1_AI12_mode</code> <i>Conf → , -a-</i> <i>RI2u</i>	<p>IOM1 Type of usage of AI12</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Lr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 4	UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:13 _h Modbus 20262 Profibus 20262 CIP 179.1.19

The parameters `IOM1_AI11_I_max` and `IOM1_AI12_I_max` are used to set the value of the limitation for a voltage value of +10V.

- If you want to use the analog signal input `AI11`, use the parameter `IOM1_AI11_I_max` to set the value of the limitation for a voltage value of +10V.

If you want to use the analog signal input `AI12`, use the parameter `IOM1_AI12_I_max` to set the value of the limitation for a voltage value of +10V.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI11_I_max CONF → , - L 11	IOM1 Limitation of current at 10 V of AI11 In increments of 0.01 A _{rms} . Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled. Available as of software version V01.06.00.	A _{rms} 0.00 3.00 300.00	UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:F _h Modbus 20254 Profibus 20254 CIP 179.1.15
IOM1_AI12_I_max CONF → , - L 12	IOM1 Limitation of current at 10 V of AI12 In increments of 0.01 A _{rms} . Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled. Available as of software version V01.06.00.	A _{rms} 0.00 3.00 300.00	UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:14 _h Modbus 20264 Profibus 20264 CIP 179.1.20

Limitation via digital signal input The current can be limited to a specific value via a digital signal input.
The parameter IO_I_limit lets you set the current limitation.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IO_I_limit CONF → , - L 11	Current limitation via input A current limit can be activated via a digital input. In increments of 0.01 A _{rms} . Changed settings become active immediately.	A _{rms} 0.00 0.20 300.00	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:27 _h Modbus 1614 Profibus 1614 CIP 106.1.39

In order to limit the current via a digital signal input, you must parameterize the signal input function "Current Limitation", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.7.6 Jerk limitation

Jerk limitation smoothes sudden acceleration changes to allow for smooth transitions with almost no jerking.

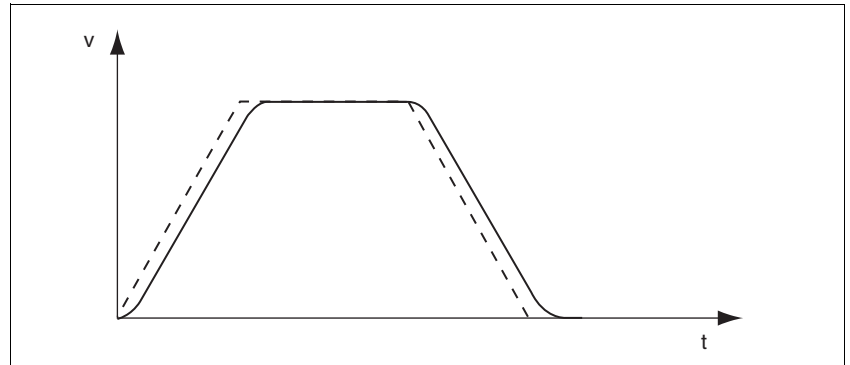


Figure 8.48 Jerk limitation

Availability Jerk limitation is available in the following operating modes.

- Jog
- Electronic Gear (position synchronization)
(firmware version $\geq V01.02$ and parameter `GEARjerklim`)
- Profile Position
- Homing
- Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)

Jerk limitation is activated and set via the parameter `RAMP_v_jerk`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>RAMP_v_jerk</code> [onF → dr[- JEr	<p>Jerk limitation of the motion profile for velocity</p> <p>0 / Off / oFF: Off 1 / 1 / 1: 1 ms 2 / 2 / 2: 2 ms 4 / 4 / 4: 4 ms 8 / 8 / 8: 8 ms 16 / 16 / 16: 16 ms 32 / 32 / 32: 32 ms 64 / 64 / 64: 64 ms 128 / 128 / 128: 128 ms</p> <p>Adjustments can only be made if the operating mode is inactive (<code>x_end=1</code>).</p> <p>Changed settings become active the next time the motor moves.</p>	ms 0 0 128	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:D _h Modbus 1562 Profibus 1562 CIP 106.1.13

Operating mode Electronic Gear Jerk limitation is activated for the operating mode Electronic Gear by means of the parameter GEARjerklim.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
GEARjerklim [onF →, -o- GF, L	<p>Activation of jerk filter processing</p> <p>0 / Off / oFF: Jerk filter deactivated. 1 / PosSyncOn / P_on: Jerk filter active in processing modes with position synchronization.</p> <p>The jerk filter processing time must be activated via parameter RAMP_v_jerk.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.02.05.</p>	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:7 _h Modbus 9742 Profibus 9742 CIP 138.1.7

8.7.7 Zero Clamp

The motor can be stopped via a digital signal input. The velocity of the motor must be below a parameterizable velocity value.

Availability The signal input function "Zero Clamp" is available in the following operating mode:

- Electronic Gear (velocity synchronization)
- Profile Velocity
- Motion Sequence (Move Velocity)

Target velocities in the operating mode Profile Velocity and reference velocities in the operating mode Electronic Gear (Velocity Synchronization) that are below the parameterizable velocity value are interpreted as "Zero".

The signal input function "Zero Clamp" has a hysteresis of 20 %.

The parameter MON_v_zeroclamp lets you set the velocity value.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_v_zeroclamp	<p>Velocity limit for Zero Clamp</p> <p>A Zero Clamp operation is only possible if the reference velocity is below the Zero Clamp velocity limit.</p> <p>Changed settings become active immediately.</p>	usr_v 0 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:28 _h Modbus 1616 Profibus 1616 CIP 106.1.40

In order to stop the motor via a digital signal input, you must parameterize the signal input function "Zero Clamp", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.7.8 Setting a signal output via parameter

The digital signal outputs can be set as required via the fieldbus.

In order to set a digital signal output via the parameter, you must parameterize the signal input function "Freely Available", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

The parameter `IO_DQ_set` lets you set the digital signal outputs.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IO_DQ_set</code>	<p>Setting the digital outputs directly</p> <p>Write access to output bits is only active if the signal pin is available as an output and if the function of the output was set to 'Available as required'.</p> <p>Coding of the individual signals: Bit 0: DQ0 Bit 1: DQ1 Bit 2: DQ2</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3008:11 _h Modbus 2082 Profibus 2082 CIP 108.1.17

8.7.9 Starting a movement via a signal input

The signal input function "Start Profile Positioning" sets the start signal for the movement in the operating mode Profile Position. The positioning movement is then executed when the edge at the digital input rises.

8.7.10 Position capture via signal input

The motor position can be captured when a signal is detected at a Capture input.

Number of Capture inputs The number of Capture inputs depends on the hardware version.

- Hardware version \geq RS03:
3 Capture inputs: DI0/CAP1, DI1/CAP2 and DI2/CAP3
- Hardware version $<$ RS03:
2 Capture inputs: DI0/CAP1 and DI1/CAP2

Selection of the method The motor position can be captured in 2 different ways:

- One-time position capture.
One-time capture means that the position is captured at the first edge.
- Continuous motor position capture
Continuous capture means that the motor position is captured anew at every edge. The previously captured value is lost.

The motor position can be captured when the edge at the Capture input rises or falls.

Accuracy A jitter of 2 μ s results in a capture inaccuracy of approximately 1.6 usr_p at a velocity of 3000 min^{-1} .
 $(3000 \text{ min}^{-1} = (3000 \cdot 16384) / (60 \cdot 10^6) = 0.8 \text{ usr}/\mu\text{s})$
 If the factory settings for scaling are used, 1.6 usr_p correspond to 0.036 °.

The captured motor position is less accurate during the acceleration phase and the deceleration phase.

Status messages The parameter `_CapStatus` indicates the capture status.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_CapStatus	Status of the capture inputs Read access: Bit 0: Position captured via input CAP1 Bit 1: Position captured via input CAP2 Bit 2: Position captured via input CAP3	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300A:1 _h Modbus 2562 Profibus 2562 CIP 110.1.1

Captured position The captured position can be read via the following parameters:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_Cap1Pos	Capture input 1 captured position Captured position at the time of the "capture signal". The captured position is re-calculated after "Position Setting" or "Reference Movement".	usr_p - - -	INT32 INT32 INT32 INT32 R/- -	CANopen 300A:6 _h Modbus 2572 Profibus 2572 CIP 110.1.6
_Cap2Pos	Capture input 2 captured position Captured position at the time of the "capture signal". The captured position is re-calculated after "Position Setting" or "Reference Movement".	usr_p - - -	INT32 INT32 INT32 INT32 R/- -	CANopen 300A:7 _h Modbus 2574 Profibus 2574 CIP 110.1.7
_Cap3Pos	Capture input 3 captured position Captured position at the time of the "capture signal". The captured position is re-calculated after "Position Setting" or "Reference Movement". Available as of hardware version RS03.	usr_p - - -	INT32 INT32 INT32 INT32 R/- -	CANopen 300A:13 _h Modbus 2598 Profibus 2598 CIP 110.1.19
_Cap1Count	Capture input 1 event counter Counts the capture events. The counter is reset when capture input 1 is activated.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 300A:8 _h Modbus 2576 Profibus 2576 CIP 110.1.8
_Cap2Count	Capture input 2 event counter Counts the capture events. The counter is reset when capture input 2 is activated.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 300A:9 _h Modbus 2578 Profibus 2578 CIP 110.1.9
_Cap3Count	Capture input 3 event counter Counts the capture events. The counter is reset when capture input 3 is activated. Available as of hardware version RS03.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 300A:14 _h Modbus 2600 Profibus 2600 CIP 110.1.20

Starting position capture The following parameters let you start position capture.

- Set the desired method with the parameters Cap1Activate and Cap2Activate and Cap3Activate.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
Cap1Activate	<p>Capture input 1 start/stop</p> <p>0 / Capture Stop: Cancel capture function 1 / Capture Once: Start one-time capture 2 / Capture Continuous: Start continuous capture</p> <p>In the case of one-time capture, the function is terminated when the first value is captured. In the case of continuous capture, the function continues to run.</p> <p>Changed settings become active immediately.</p>	- 0 - 2	UINT16 UINT16 UINT16 R/W - -	CANopen 300A:4 _h Modbus 2568 Profibus 2568 CIP 110.1.4
Cap2Activate	<p>Capture input 2 start/stop</p> <p>0 / Capture Stop: Cancel capture function 1 / Capture Once: Start one-time capture 2 / Capture Continuous: Start continuous capture</p> <p>In the case of one-time capture, the function is terminated when the first value is captured. In the case of continuous capture, the function continues to run.</p> <p>Changed settings become active immediately.</p>	- 0 - 2	UINT16 UINT16 UINT16 R/W - -	CANopen 300A:5 _h Modbus 2570 Profibus 2570 CIP 110.1.5
Cap3Activate	<p>Capture input 3 start/stop</p> <p>0 / Capture Stop: Cancel capture function 1 / Capture Once: Start one-time capture 2 / Capture Continuous: Start continuous capture</p> <p>In the case of one-time capture, the function is terminated when the first value is captured. In the case of continuous capture, the function continues to run.</p> <p>Available as of hardware version RS03.</p> <p>Changed settings become active immediately.</p>	- 0 - 2	UINT16 UINT16 UINT16 R/W - -	CANopen 300A:12 _h Modbus 2596 Profibus 2596 CIP 110.1.18

Setting the source The following parameters let you set the source for position capture.

- Set the source for position capture with the parameters Cap1Source, Cap2Source and Cap3Source.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
Cap1Source	Capture input 1 encoder source 0 / Pact Encoder 1: Source for capture input 1 is Pact of encoder 1 1 / Pact Encoder 2: Source for capture input 1 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 R/W - -	CANopen 300A:A _h Modbus 2580 Profibus 2580 CIP 110.1.10
Cap2Source	Capture input 2 encoder source 0 / Pact Encoder 1: Source for capture input 2 is Pact of encoder 1 1 / Pact Encoder 2: Source for capture input 2 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 R/W - -	CANopen 300A:B _h Modbus 2582 Profibus 2582 CIP 110.1.11
Cap3Source	Capture input 3 encoder source 0 / Pact Encoder 1: Source for capture input 3 is Pact of encoder 1 1 / Pact Encoder 2: Source for capture input 3 is Pact of encoder 2 (module) Available as of hardware version RS03. Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 R/W - -	CANopen 300A:15 _h Modbus 2602 Profibus 2602 CIP 110.1.21

Setting the edge The following parameters let you set the edge for position capture.

- Set the desired edge with the parameters Cap1Config, Cap2Config and Cap3Config.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
Cap1Config	Capture input 1 configuration 0 / Falling Edge: Position capture at falling edge 1 / Rising Edge: Position capture at rising edge Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:2 _h Modbus 2564 Profibus 2564 CIP 110.1.2
Cap2Config	Capture input 2 configuration 0 / Falling Edge: Position capture at falling edge 1 / Rising Edge: Position capture at rising edge Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:3 _h Modbus 2566 Profibus 2566 CIP 110.1.3
Cap3Config	Capture input 3 configuration 0 / Falling Edge: Position capture at falling edge 1 / Rising Edge: Position capture at rising edge Available as of hardware version RS03. Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:11 _h Modbus 2594 Profibus 2594 CIP 110.1.17

8.8 Functions for monitoring movements

8.8.1 Limit switches

⚠ WARNING

LOSS OF CONTROL

The use of limit switches can provide some protection against hazards (for example, collision with mechanical stop caused by incorrect reference values).

- If possible, use the limit switches.
- Verify correct connection of the limit switches.
- Verify the correct installation of the limit switches. The limit switches must be mounted in a position far enough away from the mechanical stop to allow for an adequate stopping distance.
- You must release the limit switches before you can use them.
- Verify the correct function of the limit switches.

Failure to follow these instructions can result in death, serious injury or equipment damage.

Limit switches

Movements can be monitored using limit switches. A positive limit switch and a negative limit switch can be used for monitoring.

If the positive or negative limit switch are tripped, the movement stops. An error message is generated and the operating state switches to **7 Quick Stop Active**.

The error message can be reset by means of a "Fault Reset". The operating state switches back to **6 Operation Enabled**.

The movement can continue, however, only in the opposite direction. For example, if the positive limit switch was triggered, further movement is only possible in negative direction. In the case of further movement in positive direction, a new error message is generated and the operating state switches back to **7 Quick Stop Active**.

The parameters `IOsigLIMP` and `IOsigLIMN` are used to set the type of limit switch.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>IOsigLIMP</code>	Signal evaluation for positive limit switch 0 / Inactive: Inactive 1 / Normally closed: Normally closed NC 2 / Normally open: Normally open NO Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:10 _h Modbus 1568 Profibus 1568 CIP 106.1.16
<code>IOsigLIMN</code>	Signal evaluation for negative limit switch 0 / Inactive: Inactive 1 / Normally closed: Normally closed NC 2 / Normally open: Normally open NO Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:F _h Modbus 1566 Profibus 1566 CIP 106.1.15

The signal input functions "Positive Limit Switch" and "Negative Limit Switch" must be parameterized, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".



If possible, use normally closed contacts so that a wire break can be signaled as an error.

8.8.2 Reference switch

The reference switch is only active in the operating mode Homing and in the operating mode Motion Sequence (Reference Movement).

The parameter `IOsigREF` lets you set the type of reference switch.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOsigREF	<p>Signal evaluation for reference switch</p> <p>1 / Normally Closed: Normally closed NC</p> <p>2 / Normally Open: Normally open NO</p> <p>The reference switch is only active while a reference movement to the reference switch is processed.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 1 1 2	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:E _h Modbus 1564 Profibus 1564 CIP 106.1.14

The signal input function "Reference Switch" must be parameterized, see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".



If possible, use normally closed contacts so that a wire break can be signaled as an error.

8.8.3 Software limit switches

The movement range can be limited by software limit switches. The position values of the software limit switches are specified with reference to the zero point. A zero point is defined by means of the operating mode Homing.

The software limit switches are set via the parameters `MON_swLimP` and `MON_swLimN` are activated via the parameter `MON_SW_Limits`.

The determining factor for monitoring the software limit switches is the reference position of the position controller.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>MON_SW_Limits</code>	Monitoring of software limit switches 0 / None: Deactivated 1 / SWLIMP: Activation of software limit switches positive direction 2 / SWLIMN: Activation of software limit switches negative direction 3 / SWLIMP+SWLIMN: Activation of software limit switches both directions Monitoring of software limit switches only works in case of successful homing (<code>ref_ok = 1</code>). Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:3 _h Modbus 1542 Profibus 1542 CIP 106.1.3
<code>MON_swLimP</code>	Positive position limit for software limit switch If a user-defined value entered is outside of the permissible range, the limit switch limits are automatically set to the maximum user-defined value. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	usr_p - 2147483647 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 607D:2 _h Modbus 1544 Profibus 1544 CIP 106.1.4
<code>MON_swLimN</code>	Negative position limit for software limit switch Refer to description 'MON_swLimP' Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	usr_p - -2147483648 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 607D:1 _h Modbus 1546 Profibus 1546 CIP 106.1.5

8.8.4 Load-dependent position deviation (following error)

The load-dependent position deviation is the difference between the reference position and the actual position caused by the load.

Parameters are available to read the load-dependent position deviation during operation and the maximum position deviation reached so far.

The maximum permissible load-dependent position deviation can be parameterized. In addition, you can set the error class for a following error.

Availability Monitoring of the load-dependent position deviation is available in the following operating modes:

- Jog
- Electronic Gear (position synchronization)
- Profile Position
- Homing
- Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)

Reading the position deviation The following parameters let you read the current load-dependent position deviation in user-defined units or revolutions.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_p_dif_load_usr	Current load-dependent position deviation between reference and actual position The load-dependent position deviation is the difference between the reference position and the actual position caused by the load. This value is used for following error monitoring. Available as of firmware version V01.03	usr_p -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:16 _h Modbus 7724 Profibus 7724 CIP 130.1.22
_p_dif_load	Current load-dependent position deviation between reference and actual position The load-dependent position deviation is the difference between the reference position and the actual position caused by the load. This value is used for following error monitoring. The parameter _p_dif_load_usr allows you to enter the value in user-defined units. In increments of 0.0001 revolution.	revolution -214748.3648 - 214748.3647	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:1C _h Modbus 7736 Profibus 7736 CIP 130.1.28

The following parameters let you read the maximum value of the load-dependent position deviation reached so far in user-defined units or revolutions.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_p_dif_load_peak_usr	Maximum value of the load-dependent position deviation This parameter contains the maximum load-dependent position deviation reached so far. A write access resets this value. Available as of firmware version V01.03 Changed settings become active immediately.	usr_p 0 - 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 301E:15 _h Modbus 7722 Profibus 7722 CIP 130.1.21
_p_dif_load_peak	Maximum value of the load-dependent position deviation This parameter contains the maximum load-dependent position deviation reached so far. A write access resets this value. The parameter _p_dif_load_peak_usr allows you to enter the value in user-defined units.. In increments of 0.0001 revolution. Changed settings become active immediately.	revolution 0.0000 - 429496.7295	UINT32 UINT32 UINT32 UINT32 R/W - -	CANopen 301E:1B _h Modbus 7734 Profibus 7734 CIP 130.1.27

Setting the position deviation The following parameter lets you set the warning threshold for the maximum load-dependent position deviation.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_p_dif_warn	Maximum load-dependent position deviation (warning) 100.0 % correspond to the maximum position deviation (following error) as specified by means of parameter MON_p_dif_load. Changed settings become active immediately.	% 0 75 100	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:29 _h Modbus 1618 Profibus 1618 CIP 106.1.41

The following parameters let you set the following error threshold in user-defined units or revolutions for the maximum load-dependent position deviation.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_p_dif_load_usr	<p>Maximum load-dependent position deviation (following error)</p> <p>The load-dependent position deviation is the difference between the reference position and the actual position caused by the load.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active immediately.</p>	usr_p 1 16384 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:3E _h Modbus 1660 Profibus 1660 CIP 106.1.62
MON_p_dif_load	<p>Maximum load-dependent position deviation (following error)</p> <p>The load-dependent position deviation is the difference between the reference position and the actual position caused by the load.</p> <p>The parameter MON_p_dif_load_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	revolution 0.0001 1.0000 200.0000	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6065:0 _h Modbus 1606 Profibus 1606 CIP 106.1.35

Setting the error class The following parameter lets you set the error response to an excessively high load-dependent position deviation (following error).

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ErrorResp_p_dif	<p>Error response to following error</p> <p>1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 1 3 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:B _h Modbus 1302 Profibus 1302 CIP 105.1.11

8.8.5 Motor standstill

It is possible to monitor whether the motor is at a standstill.

At a velocity of $<10 \text{ min}^{-1}$, the motor is at a standstill.

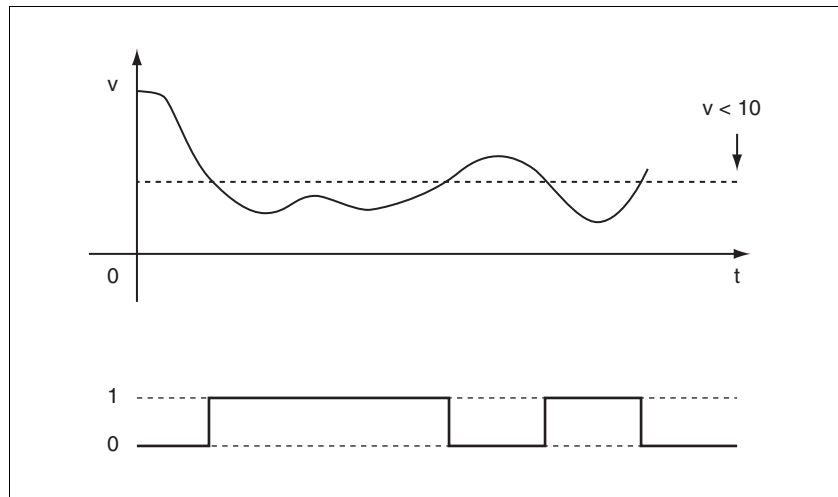


Figure 8.49 Motor standstill

The status is available via a signal output. In order to read the status, you must parameterize the signal output function "Motor Standstill", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

8.8.6 Torque window

The torque window allows you to monitor whether the motor has reached the target torque.

If the difference between the target torque and the current torque remains in the torque window for the time `MON_tq_winTime`, the target torque is considered to have been reached.

Availability The torque window is available in the following operating modes.

- Profile Torque

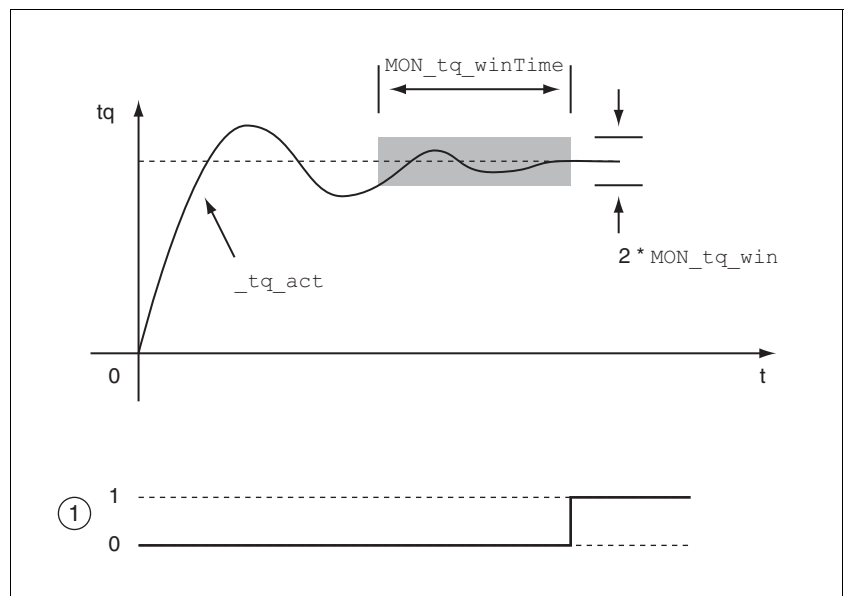


Figure 8.50 Torque window

(1) Target torque reached

The parameters `MON_tq_win` and `MON_tq_winTime` specify the size of the window.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>MON_tq_win</code>	Torque window, permissible deviation The torque window can only be activated in operating mode Profile Torque. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 3.0 3000.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2D _h Modbus 1626 Profibus 1626 CIP 106.1.45
<code>MON_tq_winTime</code>	Torque window, time Value 0: Torque window monitoring deactivated Changing the value causes a restart of torque monitoring. NOTE: Torque window is only used in operating mode Profile Torque. Changed settings become active immediately.	ms 0 0 16383	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2E _h Modbus 1628 Profibus 1628 CIP 106.1.46

8.8.7 Velocity window

The velocity window allows you to monitor whether the motor has reached the target velocity.

If the difference between the target velocity and the current motor velocity remains in the velocity window for the time `MON_v_winTime`, the target velocity is considered to have been reached.

Availability The velocity window is available in the following operating modes.

- Electronic Gear (velocity synchronization)
- Profile Velocity

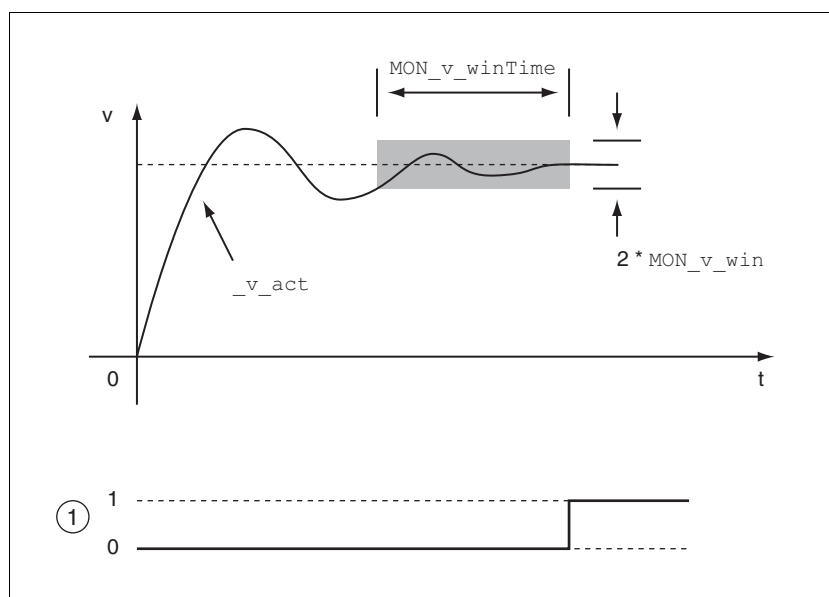


Figure 8.51 Velocity window

(1) Target velocity reached

The parameters `MON_v_win` and `MON_v_winTime` specify the size of the window.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>MON_v_win</code>	Velocity window, permissible deviation Changed settings become active immediately.	usr_v 1 10 2147483647	UINT16 UINT32 UINT32 UINT32 R/W per. -	CANopen 606D:0h Modbus 1576 Profibus 1576 CIP 106.1.20
<code>MON_v_winTime</code>	Velocity window, time Value 0: Velocity window monitoring deactivated Changing the value causes a restart of velocity monitoring. Changed settings become active immediately.	ms 0 0 16383	UINT16 UINT16 UINT16 R/W per. -	CANopen 606E:0h Modbus 1578 Profibus 1578 CIP 106.1.21

8.8.8 Standstill window

The standstill window allows you to monitor whether the motor has reached the target position.

If the difference between the target position and the current motor position remains in the standstill window for the time `MON_p_winTime`, the target position is considered to have been reached.

Availability

The standstill window is available in the following operating modes.

- Jog (step movement)
- Profile Position
- Homing
- Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)

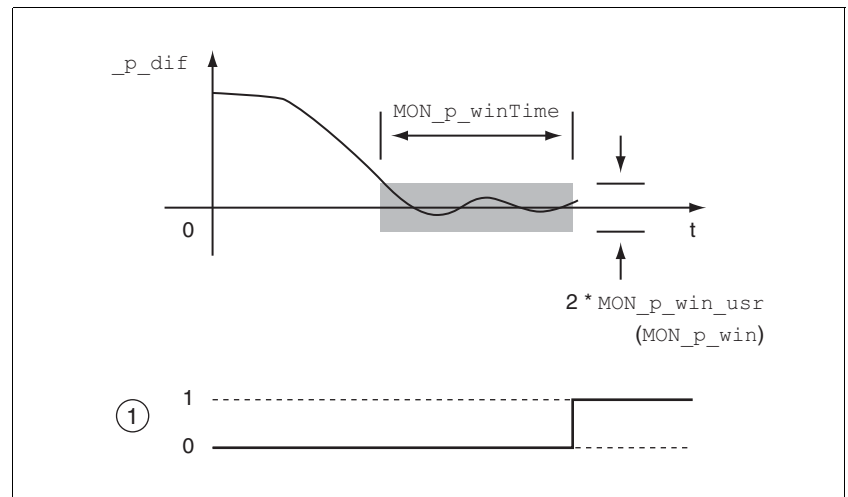


Figure 8.52 Standstill window

(1) Target position reached

The parameters `MON_p_win_usr` (`MON_p_win`) and `MON_p_winTime` specify the size of the window.

The parameter `MON_p_winTout` can be used to set the period of time after which an error is signaled if the standstill window was not reached.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_p_win_usr	Standstill window, permissible control deviation The control deviation for the standstill window time must be within this range for a standstill of the drive to be detected. Processing of the standstill window must be activated via the parameter MON_p_winTime. The minimum value, the factory setting and the maximum value depend on the scaling factor. Changed settings become active immediately.	usr_p 0 16 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:40 _h Modbus 1664 Profibus 1664 CIP 106.1.64
MON_p_win	Standstill window, permissible control deviation The control deviation for the standstill window time must be within this range for a standstill of the drive to be detected. Processing of the standstill window must be activated via the parameter MON_p_winTime. The parameter MON_p_win_usr allows you to enter the value in user-defined units. In increments of 0.0001 revolution. Changed settings become active immediately.	revolution 0.0000 0.0010 3.2767	UINT32 UINT16 UINT16 UINT16 R/W per. -	CANopen 6067:0 _h Modbus 1608 Profibus 1608 CIP 106.1.36
MON_p_winTime	Standstill window, time Value 0: Monitoring of standstill window deactivated Value >0: Time in ms during which the control deviation must be in the standstill window Changed settings become active immediately.	ms 0 0 32767	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 6068:0 _h Modbus 1610 Profibus 1610 CIP 106.1.37
MON_p_winTout	Timeout time for standstill window monitoring Value 0: Timeout monitoring deactivated Value >0: Timeout time in ms Standstill window processing values are set via MON_p_win and MON_p_winTime. Time monitoring starts when the target position (reference position of position controller) is reached or when the profile generator has finished processing. Changed settings become active immediately.	ms 0 0 16000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:26 _h Modbus 1612 Profibus 1612 CIP 106.1.38

8.8.9 Position register

The position register allows you to monitor whether the motor is within a parameterizable position range.

A movement can be monitored using one of 4 methods:

- The motor position is greater than or equal to comparison value A.
- The motor position is less than or equal to comparison value A.
- The motor position is within the range between comparison value A and comparison value B.
- The motor position is outside the range between comparison value A and comparison value B.

Separate channels are available for monitoring.

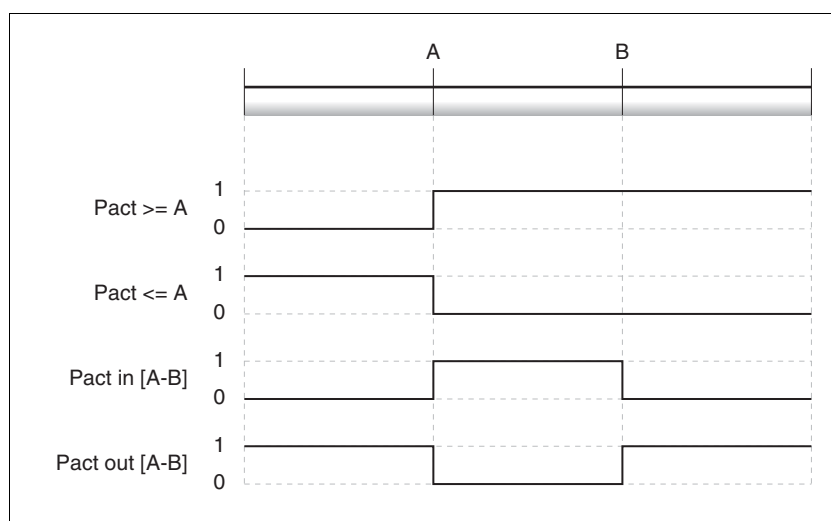


Figure 8.53 Position register

Availability This function is only available for fieldbus control mode.

Number of channels The number of channels depends on the firmware version:

- 4 channels (firmware version \geq V01.04)
- 2 channels (firmware version $<$ V01.04)

Status messages The status of the position register is available via the parameter `_PosRegStatus`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_PosRegStatus</code>	Status of the position register channels Signal state: 0: Comparison criterion not met 1: Comparison criterion met Bit assignments: Bit 0: State of position register channel 1 Bit 1: State of position register channel 2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300B:1 _h Modbus 2818 Profibus 2818 CIP 111.1.1

In addition, the status is available via signal outputs. In order to read the status via signal outputs, you must parameterize the signal output functions "Position Register Channel 1", "Position Register Channel 2", "Position Register Channel 3" and "Position Register Channel 4", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

Starting the position registers The channels of the position registers are started via the following parameters.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>PosReg1Start</code>	Start/stop of position register channel 1 0 / Off (keep last state): Position Register channel 1 is off and status bit keeps last state 1 / On: Position Register channel 1 is on 2 / Off (set state 0): Position Register channel 1 is off and status bit is set to 0 3 / Off (set state 1): Position Register channel 1 is off and status bit is set to 1 Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300B:2 _h Modbus 2820 Profibus 2820 CIP 111.1.2
<code>PosReg2Start</code>	Start/stop of position register channel 2 0 / Off (keep last state): Position Register channel 2 is off and status bit keeps last state 1 / On: Position Register channel 2 is on 2 / Off (set state 0): Position Register channel 2 is off and status bit is set to 0 3 / Off (set state 1): Position Register channel 2 is off and status bit is set to 1 Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300B:3 _h Modbus 2822 Profibus 2822 CIP 111.1.3

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg3Start	Start/stop of position register channel 3 0 / Off (keep last state): Position Register channel 3 is off and status bit keep last state 1 / On: Position Register channel 3 is on 2 / Off (set state 0): Position Register channel 3 is off and status bit is set to 0 3 / Off (set state 1): Position Register channel 3 is off and status bit is set to 1 Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 R/W - -	CANopen 300B:C _h Modbus 2840 Profibus 2840 CIP 111.1.12
PosReg4Start	Start/stop of position register channel 4 0 / Off (keep last state): Position Register channel 4 is off and status bit keeps last state 1 / On: Position Register channel 4 is on 2 / Off (set state 0): Position Register channel 4 is off and status bit is set to 0 3 / Off (set state 1): Position Register channel 4 is off and status bit is set to 1 Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 R/W - -	CANopen 300B:D _h Modbus 2842 Profibus 2842 CIP 111.1.13

Setting the source The source of the comparison criterion is set via the following parameters.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg1Source	Selection of source for position register channel 1 0 / Pact Encoder 1: Source for position register channel 1 is Pact of encoder 1 1 / Pact Encoder 2: Source for position register channel 1 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:6 _h Modbus 2828 Profibus 2828 CIP 111.1.6
PosReg2Source	Selection of source for position register channel 2 0 / Pact Encoder 1: Source for position register channel 2 is Pact of encoder 1 1 / Pact Encoder 2: Source for position register channel 2 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:7 _h Modbus 2830 Profibus 2830 CIP 111.1.7
PosReg3Source	Selection of source for position register channel 3 0 / Pact Encoder 1: Source for position register channel 3 is Pact of encoder 1 1 / Pact Encoder 2: Source for position register channel 3 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:10 _h Modbus 2848 Profibus 2848 CIP 111.1.16

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg4Source	Selection of source for position register channel 4 0 / Pact Encoder 1: Source for position register channel 4 is Pact of encoder 1 1 / Pact Encoder 2: Source for position register channel 4 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:11 _h Modbus 2850 Profibus 2850 CIP 111.1.17

Setting the comparison criterion The comparison criterion is set via the following parameters.

In the case of the comparison criteria "Pact in" and "Pact out", there is a difference between "basic" and "extended".

- Basic: The movement to be performed remains within the movement range.
- Extended: The movement to be performed can extend beyond the movement range.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg1Mode	Selection of comparison criterion for position register channel 1 0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 1 1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 1 2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic) 3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic) 4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended) 5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended) Changed settings become active immediately.	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:4 _h Modbus 2824 Profibus 2824 CIP 111.1.4

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg2Mode	<p>Selection of comparison criterion for position register channel 2</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 2</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 2</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:5 _h Modbus 2826 Profibus 2826 CIP 111.1.5
PosReg3Mode	<p>Selection of comparison criterion for position register channel 3</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 3</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 3</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:E _h Modbus 2844 Profibus 2844 CIP 111.1.14

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg4Mode	<p>Selection of comparison criterion for position register channel 4</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 4</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 4</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:F _h Modbus 2846 Profibus 2846 CIP 111.1.15

Setting comparison values The comparison values are set via the following parameters.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg1ValueA	Comparison value A for position register channel 1	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 300B:8 _h Modbus 2832 Profibus 2832 CIP 111.1.8
PosReg1ValueB	Comparison value B for position register channel 1	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 300B:9 _h Modbus 2834 Profibus 2834 CIP 111.1.9
PosReg2ValueA	Comparison value A for position register channel 2	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 300B:A _h Modbus 2836 Profibus 2836 CIP 111.1.10
PosReg2ValueB	Comparison value B for position register channel 2	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 300B:B _h Modbus 2838 Profibus 2838 CIP 111.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg3ValueA	Comparison value A for position register channel 3	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:12 _h Modbus 2852 Profibus 2852 CIP 111.1.18
PosReg3ValueB	Comparison value B for position register channel 3	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:13 _h Modbus 2854 Profibus 2854 CIP 111.1.19
PosReg4ValueA	Comparison value A for position register channel 4	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:14 _h Modbus 2856 Profibus 2856 CIP 111.1.20
PosReg4ValueB	Comparison value B for position register channel 4	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:15 _h Modbus 2858 Profibus 2858 CIP 111.1.21

8.8.10 Position deviation window

The position deviation window allows you to monitor whether the motor is within a parameterizable position deviation.

The position deviation is the difference between reference position and actual position.

The position deviation window comprises position deviation and monitoring time.

Availability

The position deviation window is available in the following operating modes.

- Jog
- Electronic Gear (position synchronization)
- Profile Position
- Homing
- Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)

Monitoring

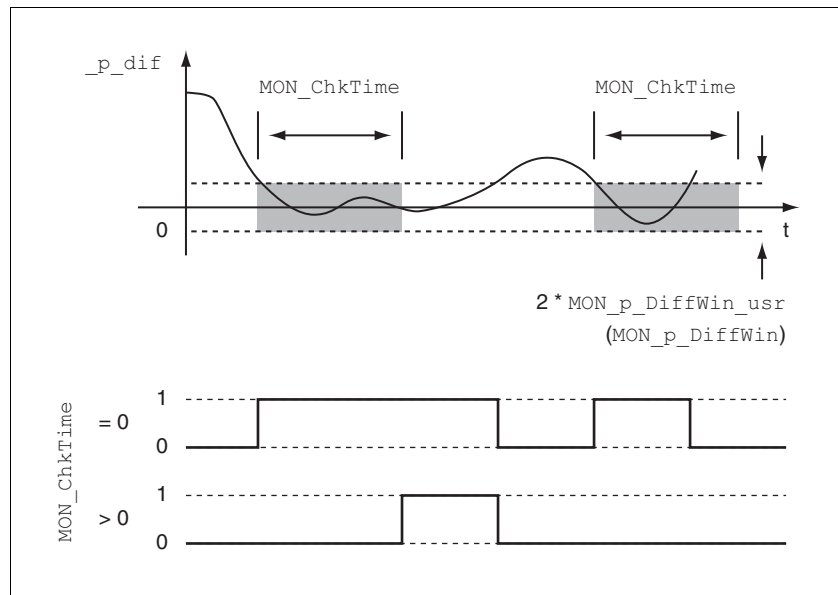


Figure 8.54 Position deviation window

The parameters `MON_p_DiffWin_usr` (`MON_p_DiffWin`) and `MON_ChkTime` specify the size of the window.

Status indication

The status is available via a signal output or via the fieldbus.

In order to read the status via a signal output, you must parameterize the signal output function "In Position Deviation Window", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In order to read the status via the fieldbus, you must set the parameter `DS402intLim` to the value "In Position Deviation Window", see chapter 8.6.5 "Settings of parameter `_DCOMstatus`".



The parameter `MON_ChkTime` acts on the parameters `MON_p_DiffWin_usr` (`MON_p_DiffWin`), `MON_v_DiffWin`, `MON_v_Threshold` and `MON_I_Threshold`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_p_DiffWin_usr	<p>Monitoring of position deviation</p> <p>The system checks whether the drive is within the defined deviation during the period set with MON_ChkTime. The status can be output via a parameterizable output.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active immediately.</p>	usr_p 0 16 2147483647	INT32 INT32 INT32 R/W per. -	CANopen 3006:3F _h Modbus 1662 Profibus 1662 CIP 106.1.63
MON_p_DiffWin	<p>Monitoring of position deviation</p> <p>The system checks whether the drive is within the defined deviation during the period set with MON_ChkTime. The status can be output via a parameterizable output.</p> <p>The parameter MON_p_DiffWin_usr allows you to enter the value in user-defined units. In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	revolution 0.0000 0.0010 0.9999	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:19 _h Modbus 1586 Profibus 1586 CIP 106.1.25
MON_ChkTime [onF →, -o- tthr	<p>Monitoring of time window</p> <p>Adjustment of a time for monitoring of position deviation, speed deviation, speed value and current value. If the monitored value is in the permissible range during the adjusted time, the monitoring function delivers a positive result. The status can be output via a parameterizable output.</p> <p>Changed settings become active immediately.</p>	ms 0 0 9999	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1D _h Modbus 1594 Profibus 1594 CIP 106.1.29

8.8.11 Velocity deviation window

The velocity deviation window allows you to monitor whether the motor is within a parameterizable velocity deviation.

The velocity deviation is the difference between the reference velocity and the actual velocity.

The velocity deviation window comprises velocity deviation and monitoring time.

Availability The velocity deviation window is available in the following operating modes.

- Jog
- Electronic Gear (velocity synchronization)
- Profile Velocity
- Profile Position
- Homing
- Motion Sequence

Monitoring

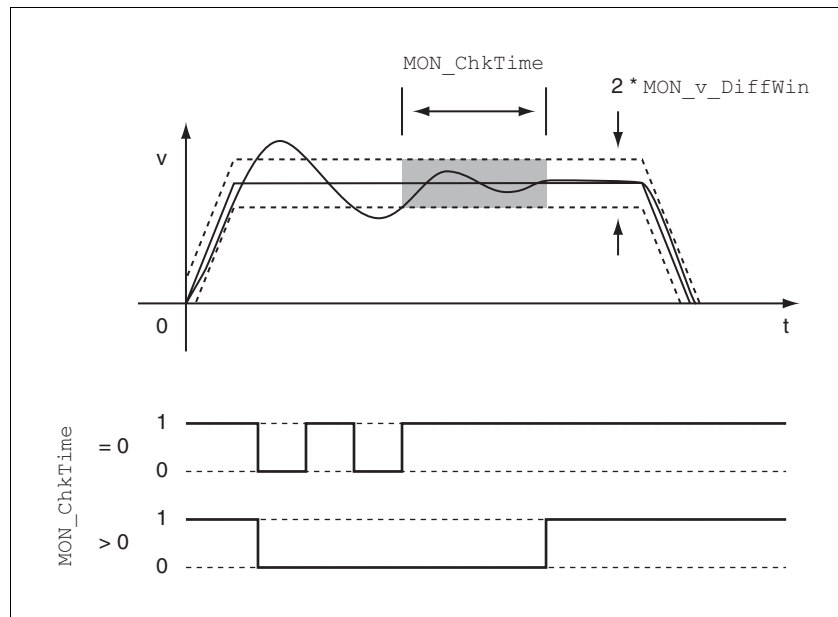


Figure 8.55 Velocity deviation window

The parameters `MON_v_DiffWin` and `MON_ChkTime` specify the size of the window.

Status indication The status is available via a signal output or via the fieldbus.

In order to read the status via a signal output, you must parameterize the signal output function "In Velocity Deviation Window", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In order to read the status via the fieldbus, you must set the parameter `DS402intLim` to the value "In Velocity Deviation Window", see chapter 8.6.5 "Settings of parameter `_DCOMstatus`".



The parameter `MON_ChkTime` acts on the parameters

*`MON_p_DiffWin_usr` (`MON_p_DiffWin`),
`MON_v_DiffWin`, `MON_v_Threshold` and
`MON_I_Threshold`.*

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>MON_v_DiffWin</code>	Monitoring of velocity deviation The system checks whether the drive is within the defined deviation during the period set with <code>MON_ChkTime</code> . The status can be output via a parameterizable output. Changed settings become active immediately.	<code>usr_v</code> 1 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:1A _h Modbus 1588 Profibus 1588 CIP 106.1.26
<code>MON_ChkTime</code> <code>LonF →, -o-</code> <code>tkhr</code>	Monitoring of time window Adjustment of a time for monitoring of position deviation, speed deviation, speed value and current value. If the monitored value is in the permissible range during the adjusted time, the monitoring function delivers a positive result. The status can be output via a parameterizable output. Changed settings become active immediately.	ms 0 0 9999	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1D _h Modbus 1594 Profibus 1594 CIP 106.1.29

8.8.12 Velocity threshold value

The velocity threshold value allows you to monitor whether the current velocity is below a parameterizable velocity value.

The velocity threshold value comprises the velocity and the monitoring time.

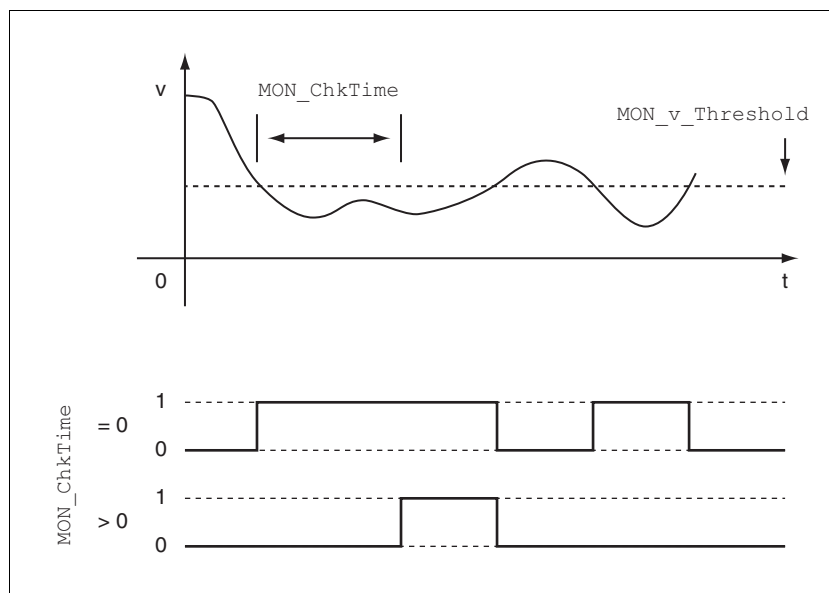
Monitoring

Figure 8.56 Velocity threshold value

The parameters `MON_v_Threshold` and `MON_ChkTime` specify the size of the window.

Status indication

The status is available via a signal output or via the fieldbus.

In order to read the status via a signal output, you must parameterize the signal output function "Velocity Below Threshold", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In order to read the status via the fieldbus, you must set the parameter `DS402intLim` to the value "Velocity Below Threshold", see chapter 8.6.5 "Settings of parameter `_DCOMstatus`".



The parameter `MON_ChkTime` acts on the parameters

*`MON_p_DiffWin_usr` (`MON_p_DiffWin`),
`MON_v_DiffWin`, `MON_v_Threshold` and
`MON_I_Threshold`.*

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>MON_v_Threshold</code>	Monitoring of velocity threshold The system checks whether the drive is below the defined value during the period set with <code>MON_ChkTime</code> . The status can be output via a parameterizable output. Changed settings become active immediately.	<code>usr_v</code> 1 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:1B _n Modbus 1590 Profibus 1590 CIP 106.1.27

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_ChkTime [onF →, -o- t t hr	Monitoring of time window Adjustment of a time for monitoring of position deviation, speed deviation, speed value and current value. If the monitored value is in the permissible range during the adjusted time, the monitoring function delivers a positive result. The status can be output via a parameterizable output. Changed settings become active immediately.	ms 0 0 9999	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1D _h Modbus 1594 Profibus 1594 CIP 106.1.29

8.8.13 Current threshold value

The current threshold value allows you to monitor whether the current motor current is below a parameterizable current value.

The current threshold value comprises the current value and the monitoring time.

Monitoring

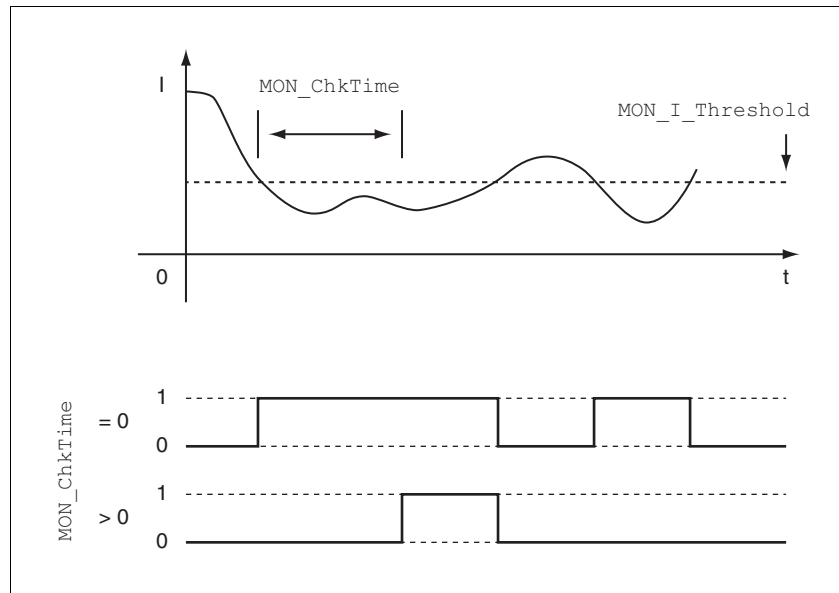


Figure 8.57 Current threshold value

The parameters `MON_I_Threshold` and `MON_ChkTime` specify the size of the window.

Status indication

The status is available via a signal output or via the fieldbus.

In order to read the status via a signal output, you must parameterize the signal output function "Current Below Threshold", see chapter 8.6.2 "Setting the digital signal inputs and signal outputs".

In order to read the status via the fieldbus, you must set the parameter `DS402intLim` to the value "Current Below Threshold", see chapter 8.6.5 "Settings of parameter `_DCOMstatus`".



The parameter `MON_ChkTime` acts on the parameters `MON_p_DiffWin_usr` (`MON_p_DiffWin`), `MON_v_DiffWin`, `MON_v_Threshold` and `MON_I_Threshold`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_I_Threshold [onF →, -o- , t hr	Monitoring of current threshold The system checks whether the drive is below the defined value during the period set with MON_ChkTime. The status can be output via a parameterizable output. The parameter _Iq_act_rms is used as comparison value. In increments of 0.01 A _{rms} . Changed settings become active immediately.	A _{rms} 0.00 0.20 300.00	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1C _h Modbus 1592 Profibus 1592 CIP 106.1.28
MON_ChkTime [onF →, -o- t t hr	Monitoring of time window Adjustment of a time for monitoring of position deviation, speed deviation, speed value and current value. If the monitored value is in the permissible range during the adjusted time, the monitoring function delivers a positive result. The status can be output via a parameterizable output. Changed settings become active immediately.	ms 0 0 9999	UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1D _h Modbus 1594 Profibus 1594 CIP 106.1.29

8.9 Functions for monitoring internal device signals

8.9.1 Temperature monitoring

The power stage temperature the motor temperature are monitored internally.

Power stage temperature The parameters `_PS_T_current` and `_PS_T_max` can be used to read the current temperature and the maximum temperature of the power stage.

The parameter `_PS_T_warn` contains as threshold value for a warning.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_PS_T_current</code> None tPS	Current power stage temperature	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:10 _h Modbus 7200 Profibus 7200 CIP 128.1.16
<code>_PS_T_warn</code>	Temperature warning threshold of power stage	°C - - -	INT16 INT16 INT16 INT16 R/- per. -	CANopen 3010:6 _h Modbus 4108 Profibus 4108 CIP 116.1.6
<code>_PS_T_max</code>	Maximum power stage temperature	°C - - -	INT16 INT16 INT16 INT16 R/- per. -	CANopen 3010:7 _h Modbus 4110 Profibus 4110 CIP 116.1.7

Motor temperature The parameters `_M_T_current` and `_M_T_max` can be used to read the current temperature and the maximum temperature of the motor.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_M_T_current</code>	Current motor temperature No meaningful indication possible for switching temperature sensors (see parameter <code>M_TempType</code> for temperature sensor type)	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:11 _h Modbus 7202 Profibus 7202 CIP 128.1.17
<code>_M_T_max</code>	Maximum temperature of motor	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 300D:10 _h Modbus 3360 Profibus 3360 CIP 113.1.16

8.9.2 Monitoring load and overload (I2T monitoring)

The load is the thermal load on the power stage, the motor and the braking resistor.

Load and overload on the individual components are monitored internally; the values can be read by means of parameters.

Overload starts at a load value of 100 %.

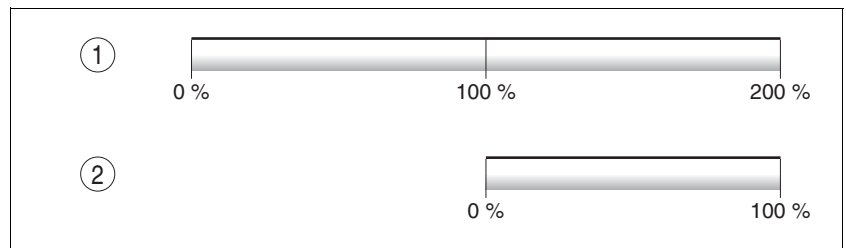


Figure 8.58 Load and overload

- (1) Load
(2) Overload

Load monitoring The current load can be read using the following parameters:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_PS_load <i>n</i> on <i>LdFP</i>	Current load of power stage	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:17 _h Modbus 7214 Profibus 7214 CIP 128.1.23
_M_load <i>n</i> on <i>LdF</i> n	Current load of motor	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:1A _h Modbus 7220 Profibus 7220 CIP 128.1.26
_RES_load <i>n</i> on <i>LdFb</i>	Current load of braking resistor Monitoring of internal and external braking resistor depending on parameter RESint_ext.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:14 _h Modbus 7208 Profibus 7208 CIP 128.1.20

Overload monitoring If the overload persists for an excessive period of time (100 % overload), the current is limited internally.

The current overload and the peak value can be read using the following parameters:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_PS_overload	Current overload of power stage	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:24 _h Modbus 7240 Profibus 7240 CIP 128.1.36
_PS_maxoverload	Maximum value of overload of power stage Maximum overload of power stage during the last 10 seconds.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:18 _h Modbus 7216 Profibus 7216 CIP 128.1.24
_M_overload	Current overload of motor (I _{2t})	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:19 _h Modbus 7218 Profibus 7218 CIP 128.1.25
_M_maxoverload	Maximum value of overload of motor Maximum overload of motor during the last 10 seconds.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:1B _h Modbus 7222 Profibus 7222 CIP 128.1.27
_RES_overload	Current overload of braking resistor (I _{2t}) Monitoring of internal and external braking resistor depending on parameter RESint_ext.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:13 _h Modbus 7206 Profibus 7206 CIP 128.1.19
_RES_maxoverload	Maximum value of overload of braking resistor Maximum overload of braking resistor during the last 10 seconds.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:15 _h Modbus 7210 Profibus 7210 CIP 128.1.21

8.9.3 Commutation monitoring

⚠ WARNING**UNEXPECTED MOVEMENT**

The risk of unexpected movements increases if monitoring functions are deactivated.

- Use the monitoring functions.

Failure to follow these instructions can result in death, serious injury or equipment damage.

The device checks the plausibility of motor acceleration and effective motor torque in order to recognize uncontrolled movements and to suppress them if required. The monitoring function is referred to as commutation monitoring.

If the motor accelerates for a period of more than 5 to 10 ms even though the drive control decelerates the motor with the maximum current set, commutation monitoring signals an uncontrolled motor movement.

The parameter `MON_commutat` lets you deactivate commutation monitoring.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_commutat	Commutation monitoring 0 / Off: Commutation monitoring off 1 / On: Commutation monitoring on Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:5 _h Modbus 1290 Profibus 1290 CIP 105.1.5

8.9.4 Monitoring of mains phases

CAUTION**DESTRUCTION CAUSED BY MISSING MAINS PHASE**

If a mains phase for a three-phase product misses and the monitoring function is deactivated, this can cause overload and destruction of the product.

- Use the monitoring functions.
- Do not operate the product if a mains phase misses.

Failure to follow these instructions can result in equipment damage.

The mains phases are monitored internally.

The parameter `ErrorResp_Flt_AC` lets you set the error response to a missing mains phase for three-phase devices.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>ErrorResp_Flt_AC</code>	<p>Error response to missing mains phase</p> <p>1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 1 2 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:A _h Modbus 1300 Profibus 1300 CIP 105.1.10

If the product is supplied via the DC bus, mains phase monitoring must be set to the mains voltage used.

The type of main phase monitoring is set by means of the parameter `MON_MainsVolt`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_MainsVolt	<p>Detection and monitoring of mains phases</p> <p>0 / Automatic Mains Detection: Automatic detection and monitoring of mains voltage</p> <p>1 / DC-Bus Only (Mains 1~230 V / 3~480 V): DC bus supply only, corresponding to mains voltage 230 V (single-phase) or 480 V (three phases)</p> <p>2 / DC-Bus Only (Mains 1~115 V / 3~208 V): DC bus supply only, corresponding to mains voltage 115 V (single-phase) or 208 V (three phases)</p> <p>3 / Mains 1~230 V / 3~480 V: Mains voltage 230 V (single-phase) or 480 V (three phases)</p> <p>4 / Mains 1~115 V / 3~208 V: Mains voltage 115 V (single-phase) or 208 V (three phases)</p> <p>Value 0: As soon as a mains voltage detected, the device automatically checks whether the mains voltage is 115 V or 230 V in the case of single-phase devices or 208 V or 400/480 V in the case of three-phase devices.</p> <p>Values 1 ... 2: If the device is supplied only via the DC bus, the parameter has to be set to the voltage value corresponding to the mains voltage of the supplying device. There is no mains voltage monitoring.</p> <p>Values 3 ... 4: If the mains voltage is not detected properly during start-up, the mains voltage to be used can be selected manually.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3005:F _h Modbus 1310 Profibus 1310 CIP 105.1.15

8.9.5 Ground fault monitoring

CAUTION**DESTRUCTION CAUSED BY GROUND FAULTS**

If the monitoring function is deactivated, the product may be destroyed by a ground fault.

- Use the monitoring functions.
- Avoid ground faults by wiring the product properly.

Failure to follow these instructions can result in equipment damage.

When the power stage is enabled, the device monitors the motor phases for ground faults.

A ground fault of one or more motor phases is detected. A ground fault of the DC bus or the braking resistor is not detected.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_GroundFault	<p>Ground fault monitoring</p> <p>0 / Off: Ground fault monitoring off 1 / On: Ground fault monitoring on</p> <p>In exceptional cases, deactivation may be necessary, for example: - Long motor cables Deactivate ground fault monitoring if it responds in an unwanted way.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3005:10 _h Modbus 1312 Profibus 1312 CIP 105.1.16

9 Examples

9

9.1 General information

The examples show some typical applications of the product. The examples are intended to provide an overview; they are not exhaustive wiring plans.

Using the safety functions integrated in this product requires careful planning. See chapter 5.9 "Safety function STO ("Safe Torque Off")", page 77 for additional information.

9.2 Example of operation with a module

See the manual for the modules for details on wiring.

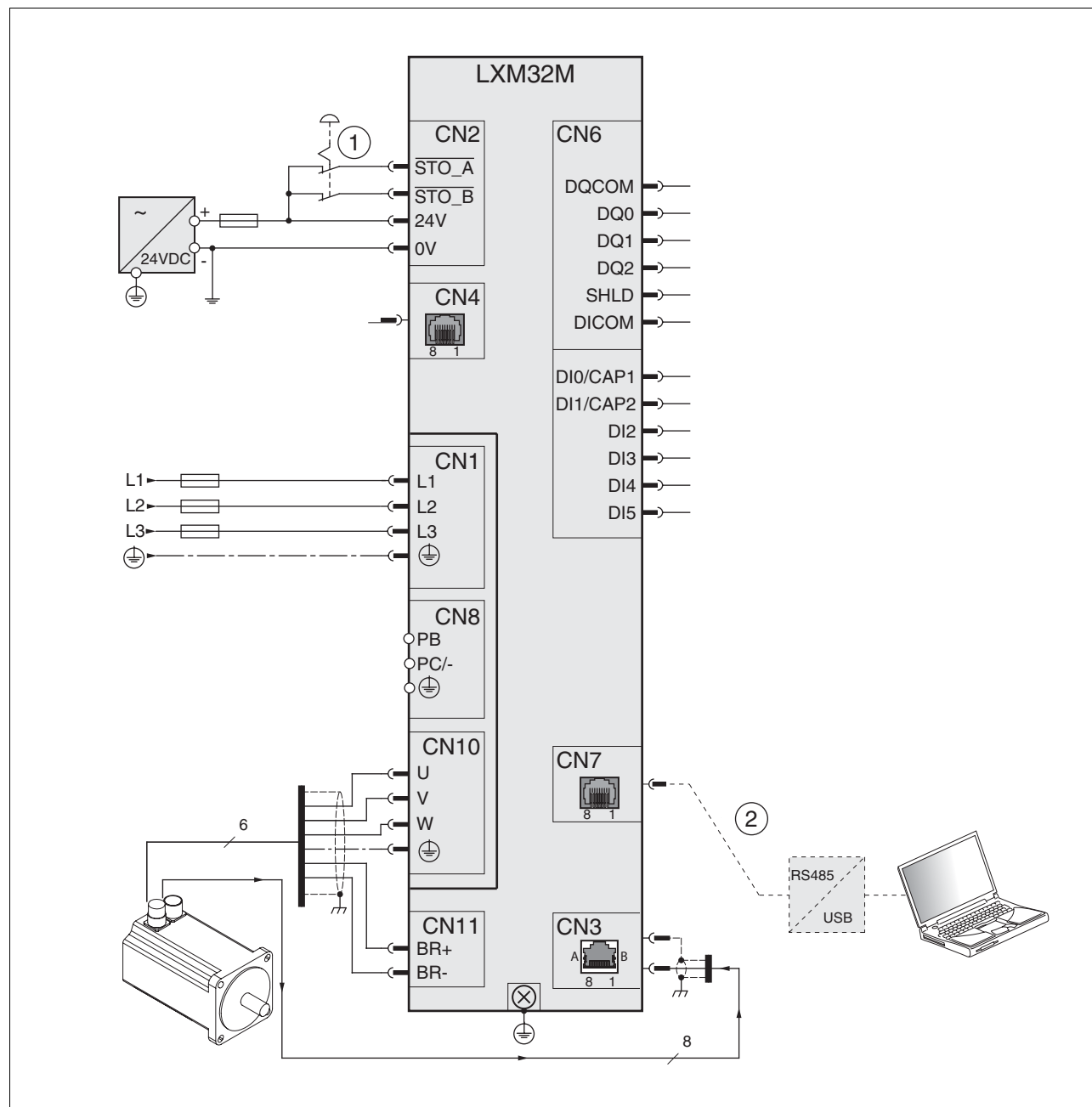


Figure 9.1 Wiring example

- (1) EMERGENCY STOP
- (2) Commissioning accessories

10 Diagnostics and troubleshooting

10

This chapter describes the various types of diagnostics and provides troubleshooting assistance.

10.1 Status request/status indication

Information on the product status is provided by:

- Integrated HMI
- Commissioning software
- Fieldbus
- Status LEDs (see the manuals for the modules)

The error memory also contains a history of the last 10 errors.

Meaning of a warning message

A warning alerts to a problem that was detected by a monitoring function. The cause of a warning must be remedied.

A warning belongs to error class 0 and does not cause a transition of the operating state.

Meaning of an error message

An error is a deviation from the required value or state. Errors are subdivided into different error classes.

Error class

The product triggers an error response if an error occurs. Depending upon the severity of the error, the device responds in accordance with one of the following error classes:

Error class	Response	Meaning
0	Warning	A monitoring function has detected a problem. No interruption of the movement.
1	"Quick Stop"	Motor stops with "Quick Stop", the power stage remains enabled.
2	"Quick Stop" with switch-off	Motor stops with "Quick Stop", the power stage is disabled after standstill has been achieved.
3	Fatal error	The power stage is immediately disabled without stopping the motor first.
4	Uncontrolled operation	The power stage is immediately disabled without stopping the motor first. The error can only be reset by switching off the product.

10.1.1 Diagnostics via the integrated HMI

The following illustration shows the status LEDs and the 7-segment display of the integrated HMI

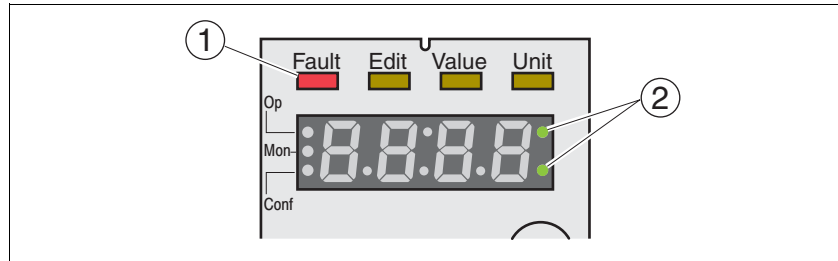


Figure 10.1 Status indication via the integrated HMI

<i>Status LED "Fault"</i>	If the drive is in the operating state Fault, the "Fault" (1) status LED lights.
<i>7-segment display</i>	The 7-segment display provides the user with information.
<i>Warning messages</i>	If there are warnings (error class 0), the two dots to the right of the 7-segment display (2) flash. Warnings are not directly displayed on the 7-segment display in the form of an error number, but must be explicitly queried by the user. See chapter 10.3.1 "Reading and acknowledging warnings", page 388 for additional information.
<i>Error numbers</i>	Error numbers of errors belonging to error classes 1 to 4 on the one hand and the current operating state on the other hand are displayed alternately by the 7-segment display. See chapter 10.3.2 "Reading and acknowledging errors", page 389 for information on acknowledging errors via the integrated HMI. The meanings of the error numbers can be found in chapter 10.4.2 "Table of warnings and errors by range", page 394.

Messages on the integrated HMI

The table below provides an overview of the messages that can be displayed on the integrated HMI.

Message	Description
\overline{ERRd}	Data on the memory card differs from data in the product. See chapter 7.8.1 "Data exchange with the memory card", page 193 for information on how to proceed.
$d. 5$	The product is in the operating state 3 Switch On Disabled. There is no DC bus voltage or the inputs $\overline{STO_A}$ and $\overline{STO_B}$ have no current.
$d. 5P$	An external HMI is connected. The integrated HMI has no function.
FLt	The display alternately shows FLt (FLT) and a 4-digit error number. See chapter 10.4.2 "Table of warnings and errors by range", page 394 for the meaning of the error number.
$F5u$	Perform a First Setup. See chapter 7.6 "Commissioning procedure", page 148.
$hRLt$	The motor is stopped, the power stage is enabled.
$flot$	A new motor was detected. See chapter 10.3.4 "Acknowledging a motor change", page 391 for replacing a motor.
$nr dY$	The product is not ready to switch on (operating state: 2 Not Ready To Switch On).
$Pr ot$	Parts of the integrated HMI were locked with the parameter $HMIlocked$.
rdY	The power stage is ready to switch on.
run	The product operates with the operating mode set.
$SLt ! \dots SLt 3$	The device has detected a different equipment with modules. See chapter 10.3.3 "Acknowledging a module replacement", page 390 for replacing modules.
$StoP$	The display alternately shows $StoP$ (STOP) and a 4-digit error number. See chapter 10.4.2 "Table of warnings and errors by range" for the meaning of the error number.
$uLoU$	Controller supply voltage during initialization not high enough.
$BBBB$	Undervoltage controller supply voltage.

Table 10.1 Table of the messages at the HMI

In addition to the messages as listed in Table 10.1, the integrated HMI displays information on the following:

- Error numbers (see chapter 10.4.2 "Table of warnings and errors by range", page 394)
- Menu labels (see chapter 7.3.2 "Menu structure", page 135)
- Parameter names (see chapter 11 "Parameters", page 427)
- Parameter values (for example, maximum current i_{RMH} (IMAX))

10.1.2 Diagnostics via the commissioning software

See the information provided with the commissioning software for details on how to display the device state via the commissioning software.

10.1.3 Diagnostics via the fieldbus

For further information on the fieldbus, see the fieldbus manual.

10.2 Error memory

General The error memory is an error history of the last 10 errors; it is not cleared even if the product is switched off. The error memory allows you to read and evaluate past events.

The following information on the events is stored:

- Error class
- Error number
- Motor current
- Number of switch-on cycles
- Additional error information (for example, parameter numbers)
- Product temperature
- Power stage temperature
- Time the error occurred (with reference to operating hours counter)
- DC bus voltage
- Velocity
- Number of Enable cycles after switch-on
- Time from Enable until occurrence of the error

The stored information relates to the situation at the point in time the error occurred.

10.2.1 Reading the error memory via the fieldbus

The following parameters allow you to manage the error memory:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ERR_clear	Clear error memory Value 1: Delete all entries in the error memory The clearing process is completed if a 0 is returned after a read access. Changed settings become active immediately.	- 0 - 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 303B:4 _h Modbus 15112 Profibus 15112 CIP 159.1.4
ERR_reset	Reset error memory read pointer Value 1: Set error memory read pointer to oldest error entry. Changed settings become active immediately.	- 0 - 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 303B:5 _h Modbus 15114 Profibus 15114 CIP 159.1.5

The error memory can only be read sequentially. The parameter `ERR_reset` must be used to reset the read pointer. Then the first error entry can be read. The read pointer is automatically set to the next entry. A new read access delivers the next error entry. If the error number 0 is returned, there is no additional error entry.

Position of the entry	Meaning
1	First error entry (oldest message).
2	Second error entry (later message).
...	...
10	Tenth error entry. In the case of ten error entries, the most recent message is contained here.

An error entry consists of several pieces of information which can be read using different parameters. When you read an error entry, the error number must be read first with the parameter `_ERR_number`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_ERR_class	Error class Value 0: Warning (no response) Value 1: Error (Quick Stop -> state 7) Value 2: Error (Quick Stop -> state 8, 9) Value 3: Fatal error (state 9, can be acknowledged) Value 4: Fatal error (state 9, cannot be acknowledged)	- 0 - 4	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:2 _h Modbus 15364 Profibus 15364 CIP 160.1.2

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_ERR_number	Error number Reading this parameter copies the entire error entry (error class, time of occurrence of error, ...) to an intermediate memory from which all elements of the error can then be read. In addition, the read pointer of the error memory is automatically set to the next error entry.	- 0 - 65535	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:1 _h Modbus 15362 Profibus 15362 CIP 160.1.1
_ERR_motor_I	Motor current at error time In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:9 _h Modbus 15378 Profibus 15378 CIP 160.1.9
_ERR_powerOn non Power	Number of power on cycles	- 0 - 4294967295	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 303C:2 _h Modbus 15108 Profibus 15108 CIP 159.1.2
_ERR_qual	Error additional information This entry contains additional information on the error, depending on the error number. Example: a parameter address	- 0 - 65535	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:4 _h Modbus 15368 Profibus 15368 CIP 160.1.4
_ERR_temp_dev	Temperature of device at error time	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 303C:B _h Modbus 15382 Profibus 15382 CIP 160.1.11
_ERR_temp_ps	Temperature of power stage at error time	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 303C:A _h Modbus 15380 Profibus 15380 CIP 160.1.10
_ERR_time	Error time With reference to operating hours counter	s 0 - 536870911	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 303C:3 _h Modbus 15366 Profibus 15366 CIP 160.1.3
_ERR_DCbus	DC bus voltage at error time In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:7 _h Modbus 15374 Profibus 15374 CIP 160.1.7

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_ERR_motor_v	Motor velocity at error time	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 303C:8 _h Modbus 15376 Profibus 15376 CIP 160.1.8
_ERR_enable_cycles	Number of cycles of enabling the power stage at error time Number of cycles of enabling the power stage from the time the power supply (control voltage) was switched on to the time the error occurred.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:5 _h Modbus 15370 Profibus 15370 CIP 160.1.5
_ERR_enable_time	Time between enabling of power stage and occurrence of the error	s - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:6 _h Modbus 15372 Profibus 15372 CIP 160.1.6

10.2.2 Reading the error memory via the commissioning software

See the information provided with the commissioning software for details on how to read the error memory using the commissioning software.

10.3 Special menus at the integrated HMI

The following functions depend on the situation. They are only available in specific contexts.

10.3.1 Reading and acknowledging warnings

Procedure for reading and acknowledging warnings via the integrated HMI:

- A warning is active. The two dots to the right of the 7-segment display flash.
- ▶ Remedy the cause of the warning.
- ▶ Press the navigation button and hold it down.
- ◁ The 7-segment display shows the error number of the warning.
- ▶ Release the navigation button.
- ◁ The 7-segment display shows *FrE5*.
- ▶ Press the navigation button to acknowledge the warning.
- ◁ The 7-segment display returns to the initial state.

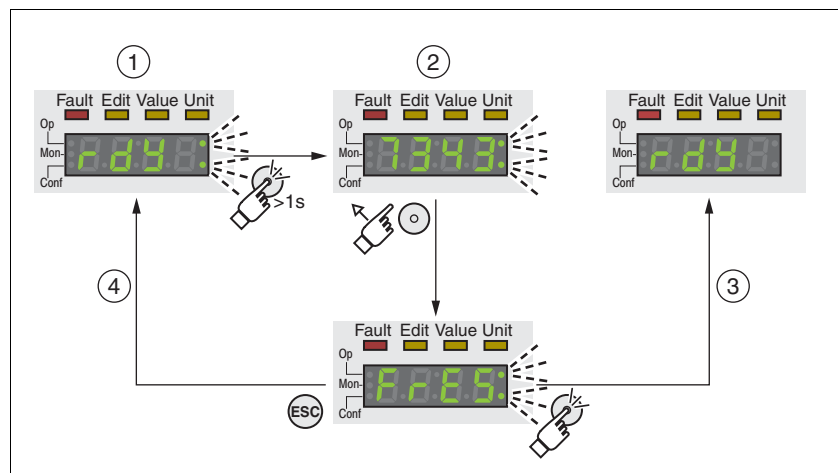


Figure 10.2 Acknowledging warnings via the integrated HMI

- (1) HMI displays a warning
- (2) Error number is displayed
- (3) Resetting the warning
- (4) Canceling, the warning remains in the memory

See chapter 10.4.2 "Table of warnings and errors by range", page 394, for detailed information on the warnings.

10.3.2 Reading and acknowledging errors

Procedure for reading and acknowledging errors via the integrated HMI:

- The LED "Fault" is on. The 7-segment display alternately shows *FLt* and an error number. An error of error classes 2 to 4 has occurred.
- ▶ Remedy the cause of the error.
- ▶ Press the navigation button.
- ◁ The 7-segment display shows *FrE5*.
- ▶ Press the navigation button to acknowledge the error.
- ◁ The product switches to operating state **4** Ready To Switch On.

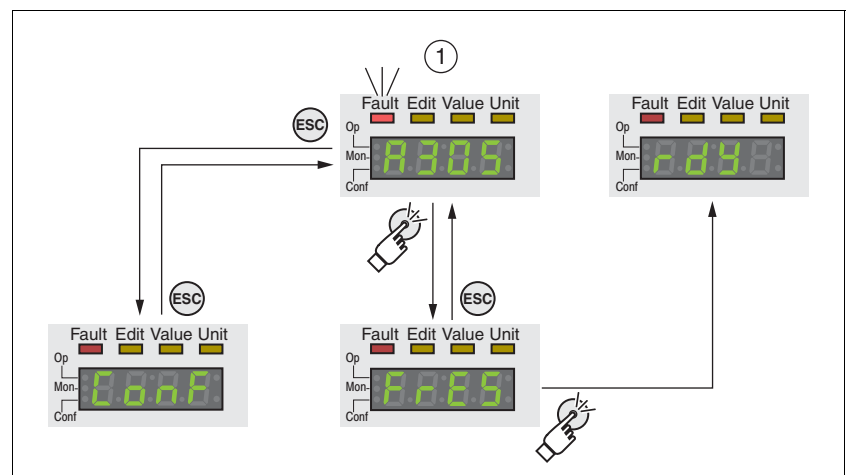


Figure 10.3 Acknowledging errors via the integrated HMI

(1) HMI displays an error with error number

The meanings of the error numbers can be determined using the table in chapter 10.4.2 "Table of warnings and errors by range", page 394.

10.3.3 Acknowledging a module replacement

General Note the information in the manuals for the respective modules.

Slot 1 Please refer to the manual for the safety module for information on replacing a module in slot 1.

Slot 2 and slot 3 The replacement of a module is confirmed via the integrated HMI.

- The 7-segment display shows **SLt2** or **SLt3**.
- Press the navigation button.
- ◁ The 7-segment display shows **SAVE**.
- Press the navigation button to acknowledge. The information on the current module equipment is saved to the EEPROM.
- ◁ The product switches to operating state **4 Ready To Switch On**.

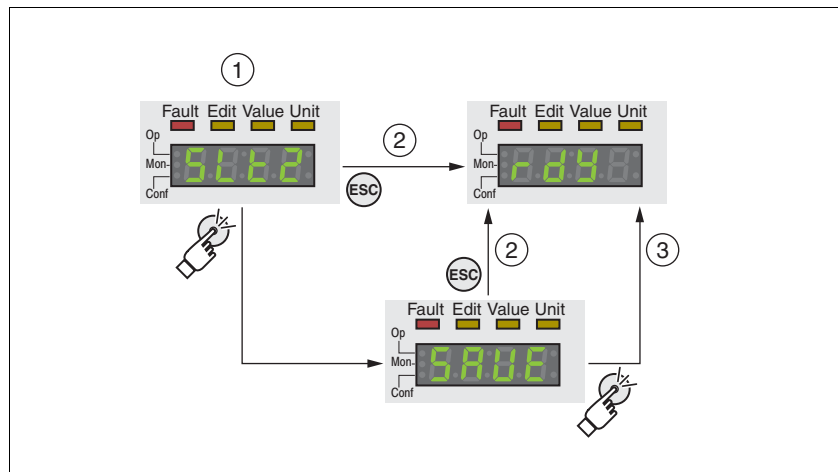


Figure 10.4 Acknowledging a module change via the integrated HMI

- (1) HMI displays that a replacement of a module has been detected.
- (2) Canceling the saving process
- (3) Saving the new equipment with modules and switching to operating state **4 Ready To Switch On**.

10.3.4 Acknowledging a motor change

Procedure for acknowledging a motor change via the integrated HMI:

- The 7-segment display shows *Not*.
- Press the navigation button.
- ◁ The 7-segment display shows *SAVE*.
- Press the navigation button to save the new motor parameters to the EEPROM.
- ◁ The product switches to operating state **4** Ready To Switch On.

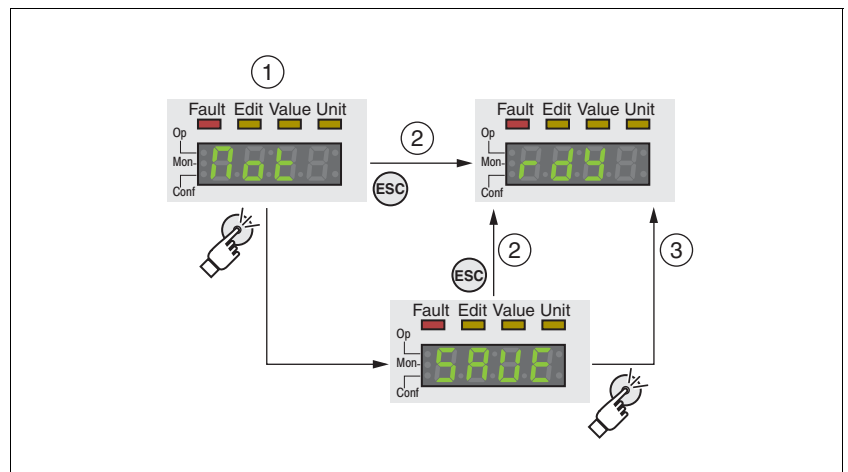


Figure 10.5 Acknowledging a motor change via the integrated HMI

- (1) HMI displays that a replacement of a motor has been detected.
- (2) Canceling the saving process
- (3) Saving the new motor data and switching to operating state **4** Ready To Switch On.

10.4 Troubleshooting

10.4.1 Errors and warnings sorted by error bit

The parameters `_WarnLatched` and `_SigLatched` contain information on warnings and errors.

The error bits of the warnings can be read using the parameter `_WarnLatched`.

The error bits of the errors can be read using the parameter `_SigLatched`.

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_WarnLatched</code> Warn WarnS	<p>Saved warnings, bit-coded</p> <p>Saved warning bits are deleted in the case of a Fault Reset. Bits 10, 13 are deleted automatically.</p> <p>Signal state: 0: Not activated 1: Activated</p> <p>Bit assignments: Bit 0: General warning Bit 1: Reserved Bit 2: Out of range (SW limit switches, tuning) Bit 3: Reserved Bit 4: Active operating mode Bit 5: Commissioning interface (RS485) Bit 6: Integrated fieldbus Bit 7: Reserved Bit 8: Following warning limit reached Bit 9: Reserved Bit 10: Inputs STO_A and/or STO_B Bit 11: Reserved Bit 12: Reserved Bit 13: Low voltage DC bus or mains phase missing Bit 14: Reserved Bit 15: Reserved Bit 16: Integrated encoder interface Bit 17: Temperature of motor high Bit 18: Temperature of power stage high Bit 19: Reserved Bit 20: Memory card Bit 21: Optional fieldbus module Bit 22: Optional encoder module Bit 23: Optional safety module or I/O module Bit 24: Reserved Bit 25: Reserved Bit 26: Reserved Bit 27: Reserved Bit 28: Reserved Bit 29: Braking resistor overload (I^2t) Bit 30: Power stage overload (I^2t) Bit 31: Motor overload (I^2t)</p> <p>Monitoring functions are product-dependent.</p>	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:C _h Modbus 7192 Profibus 7192 CIP 128.1.12

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_SigLatched Non 5, 65	<p>Saved status of monitoring signals</p> <p>Signal state: 0: Not activated 1: Activated</p> <p>Bit assignments: Bit 0: General error Bit 1: Hardware limit switches (LIMP/LIMN/REF) Bit 2: Out of range (software limit switches, tuning) Bit 3: Quick Stop via fieldbus Bit 4: Error in active operating mode Bit 5: Commissioning interface (RS485) Bit 6: Integrated fieldbus Bit 7: Reserved Bit 8: Following error Bit 9: Reserved Bit 10: Inputs STO are 0 Bit 11: Inputs STO different Bit 12: Reserved Bit 13: DC bus voltage low Bit 14: DC bus voltage high Bit 15: Mains phase missing Bit 16: Integrated encoder interface Bit 17: Overtemperature motor Bit 18: Overtemperature power stage Bit 19: Reserved Bit 20: Memory card Bit 21: Optional fieldbus module Bit 22: Optional encoder module Bit 23: Optional safety module or I/O module Bit 24: Reserved Bit 25: Reserved Bit 26: Motor connection Bit 27: Motor overcurrent/short circuit Bit 28: Frequency of reference signal too high Bit 29: EEPROM error Bit 30: System start-up (hardware or parameter) Bit 31: System error (for example, watchdog, internal hardware interface)</p> <p>Monitoring functions are product-dependent.</p>	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:8 _h Modbus 7184 Profibus 7184 CIP 128.1.8

10.4.2 Table of warnings and errors by range

The table below summarizes the error numbers classified by range.

Error number	Range
E 1xxx	General
E 2xxx	Overcurrent
E 3xxx	Voltage
E 4xxx	Temperature
E 5xxx	Hardware
E 6xxx	Software
E 7xxx	Interface, wiring
E Axxx	Motor movement
E Bxxx	Communication

Error number not listed If the error number is not listed in the table below, the firmware version may be newer than the version of the manual or there may be a system error.

- ▶ Verify that you use the correct manual ("About this manual")
- ▶ Verify that the wiring is EMC-compliant (5.1 "Electromagnetic compatibility, EMC")
- ▶ Contact technical support (13.1 "Service address")

List of error numbers The table below provides an overview of the error numbers.

Error number	Error class	Description	Cause	Correctives
E 1100	-	Parameter out of permissible range	The value entered was outside of the permissible value range for this parameter.	The entered value must be within the permissible value range.
E 1101	-	Parameter does not exist	Error signaled by parameter management: Parameter (index) does not exist.	Select a different parameter (index).
E 1102	-	Parameter does not exist	Error signaled by parameter management: Parameter (subindex) does not exist.	Select a different parameter (subindex).
E 1103	-	Parameter write not permissible (READ only)	Write access to read only parameter.	Write only to parameters that are not read-only.
E 1104	-	Write access denied (no access authorization)	Parameter only accessible at expert level.	The write access level expert is required.
E 1106	-	Command not allowed while power stage is active	Command not allowed while the power stage is enabled (operating state Operation Enabled or Quick Stop Active).	Disable the power stage and repeat the command.
E 1107	-	Access via other interface blocked	Access occupied by another channel (for example: Commissioning software is active and fieldbus access was tried at the same time).	Check the channel that blocks the access.

Error number	Error class	Description	Cause	Correctives
E 110B	3	Configuration error (additional info=Modbus register address) Parameter _SigLatched Bit 30	Error detected during parameter check (for example, reference velocity value for operating mode Profile Position is greater than maximum allowed velocity of drive).	Value in additional error information shows the Modbus register address of the parameter where the initialization error was detected.
E 110D	1	Basic configuration of drive required after factory setting	The "First Setup" (FSU) was not run at all or not completed.	Perform a First Setup.
E 110E	-	Parameter changed that requires a restart of the drive	Only displayed by the commissioning software. A parameter modification requires the drive to be switched off and on.	Restart the drive to activate the parameter functionality. See the chapter Parameters for the parameter that requires a restart of the drive.
E 1110	-	Unknown file ID for upload or download	The specific type of device does not support this kind of file.	Verify that you have the correct device type or the correct configuration file.
E 1112	-	Locking of configuration denied	An external tool has tried to lock the configuration of the drive for upload or download. This may not work because another tool had already locked the configuration of the drive or the drive is in an operating state that does not allow locking.	
E 1114	4	Configuration download aborted Parameter _SigLatched Bit 5	During a configuration download, a communication error or an error in the external tool occurred. The configuration was only partially transferred to the drive and might be inconsistent now.	Switch the drive off/on and retry to download the configuration or reset the drive parameters to their factory settings.
E 1118	-	Configuration data incompatible with device	The configuration data contains data from a different device.	Check device type including type of power stage.
E 111B	4	Configuration download error (additional info=Modbus register address)	During a configuration download, one or more configuration values have not been accepted by the drive.	Check whether the configuration file is valid and matches the type and version of the drive. The value in the additional error info shows the Modbus register address of the parameter where the initialization error was detected.
E 111C	1	Not possible to initialize recalculation for scaling	A parameter could not be initialized.	The address of the parameter that caused the error can be read via the parameter _PAR_ScalingError.
E 111D	3	Original state of a parameter after error during recalculation of parameters with user-defined units cannot be restored.	The drive contained an invalid configuration before the recalculation was started. An error occurred during the recalculation.	Switch the drive off and on again. This may help you to identify the affected parameter(s). Change the parameters as required. Verify that the parameter configuration is valid before starting the recalculation procedure.

Error number	Error class	Description	Cause	Correctives
E 111E	1	Not possible to recalculate data record	A data set of the operating mode Motion Sequence could not be recalculated.	The address of the parameter and the number of the data set that caused the error can be read via the parameter <code>_PAR_ScalingError</code> .
E 111F	1	Recalculation not possible.	Invalid scaling factor.	Check whether you really want the selected scaling factor. Try a different scaling factor. Before triggering scaling, reset the parameters with user-defined units.
E 1120	1	Recalculation for scaling not possible	A parameter could not be recalculated.	The address of the parameter that caused the error can be read via the parameter <code>_PAR_ScalingError</code> .
E 1121	-	Incorrect sequence of steps for scaling (fieldbus)	The recalculation has been started prior to the initialization.	The recalculation must be started after the initialization.
E 1122	-	Recalculation for scaling not possible	Recalculation for scaling is already running.	Wait for the running recalculation for scaling to finish.
E 1123	-	Parameter cannot be changed	Recalculation for scaling is running.	Wait for the running recalculation for scaling to finish.
E 1124	1	Timeout during recalculation for scaling	The time between the initialization of the recalculation and the start of the recalculation has been exceeded (30 seconds).	Recalculation must be started within 30 seconds after initialization.
E 1125	1	Scaling not possible	The scaling factors for position, velocity or acceleration/deceleration are beyond internal calculation limits.	Retry with different scaling factors.
E 1300	3	Safety function STO activated (STO_A, STO_B) Parameter <code>_SigLatched</code> Bit 10	The safety function STO was activated in the operating state Operation Enabled.	Check the wiring of the inputs of the STO safety function and reset the error.
E 1301	4	STO_A and STO_B different level Parameter <code>_SigLatched</code> Bit 11	The levels of the inputs STO_A and STO_B were different for more than 1 second.	The drive has to be switched off and the reason fixed (for example, check whether EMERGENCY STOP is active) before it is switched on.
E 1302	0	Safety function STO activated (STO_A, STO_B) Parameter <code>_WarnLatched</code> Bit 10	STO safety function was activated while the power stage was disabled.	The warning is automatically reset once the STO safety function is deactivated.
E 1310	2	Reference signal frequency too high Parameter <code>_SigLatched</code> Bit 28	The frequency of the pulse signal (A/B, Pulse/Direction, CW/CCW) is higher than the allowed value.	Adapt the output pulse frequency of the controller to fit the input specification of the drive. Also adapt the gear ratio in the operating mode Electronic Gear to the application requirements (position accuracy and velocity).
E 1311	-	The selected signal input function or signal output function cannot be configured	The selected signal input function or signal output function cannot be used in the selected operating mode.	Select another function or change the operating mode.

Error number	Error class	Description	Cause	Correctives
E 1312	-	Limit switch or reference switch signal not defined for signal input function	Reference movements require limit switches. These limit switches are not assigned to inputs.	Assign the signal input functions Positive Limit Switch, Negative Limit Switch and Reference Switch.
E 1313	-	Configured debounce time not possible for this signal input function	The signal input function does not support the selected debounce time.	Set the debounce time to a valid value.
E 1314	4	At least two inputs have the same signal input function.	At least two inputs are configured with the same signal input function.	Reconfigure the inputs.
E 1315	0	Frequency of reference value signal is too high (warning). Parameter _WarnLatched Bit 28	The frequency of the pulse signal (A/B, Pulse/Direction, CW/CCW) exceeds the specified working range. Received pulses may be lost.	Adapt the output pulse frequency of the controller to fit the input specification of the drive. Also adapt the gear ratio in the operating mode Electronic Gear to the application requirements (position accuracy and velocity).
E 1316	1	Position capture via signal input currently not possible Parameter _SigLatched Bit 28	Position capture is already being used.	
E 1317	0	Interference at PTI input Parameter _WarnLatched Bit 28	Interfering pulses or impermissible edge transitions (A and B signal simultaneously) have been detected.	Check cable specifications, shielding and EMC.
E 160C	1	Autotuning: Moment of inertia outside permissible range	The load inertia is too high.	Verify that the system can easily be moved. Check the load. Use a differently rated drive.
E 160F	1	Autotuning: Power stage cannot be enabled	Autotuning was not started in the operating state Ready To Switch On.	Start Autotuning when the drive is in the operating state Ready To Switch On.
E 1610	1	Autotuning: Processing stopped	Autotuning process stopped by user command or by drive error (see additional error message in error memory, for example, DC bus undervoltage, limit switches triggered)	Fix the cause of the stop and restart Autotuning.
E 1611	1	System error: Autotuning internal write access	HALT is active and an Autotuning parameter is written. Occurs when Autotuning is started.	
E 1613	1	Autotuning: Maximum permissible movement range exceeded Parameter _SigLatched Bit 2	The motor exceeded the adjusted movement range during Autotuning.	Increase the movement range value or disable range monitoring by setting AT_DIS = 0.
E 1614	-	Autotuning: Already active	Autotuning has been started twice simultaneously or an Autotuning parameter is modified during Autotuning (parameter AT_dis and AT_dir).	Wait for Autotuning to finish before restarting Autotuning.
E 1615	-	Autotuning: This parameter cannot be changed while Autotuning is active	Parameter AT_gain or AT_J are written during Autotuning.	Wait for Autotuning to finish before changing the parameter.

Error number	Error class	Description	Cause	Correctives
E 1617	1	Autotuning: Friction torque or load torque too great	The current limit has been reached (parameter CTRL_I_max).	Verify that the system can easily be moved. Check the load. Use a differently rated drive.
E 1618	1	Autotuning: Optimization aborted	The internal Autotuning sequence has not been finished (following error?).	Note the additional information provided in the error memory.
E 1619	-	Autotuning: The velocity jump height in parameter AT_n_ref is too small	Parameter AT_n_ref < 2 * AT_n_tolerance. Checked only once at the first velocity jump.	Modify the parameter AT_n_ref or AT_n_tolerance to meet the desired condition.
E 1620	1	Autotuning: Load torque too high	Product rating is not suitable for the machine load. Detected machine inertia is too high compared to the inertia of the motor.	Reduce load, check rating.
E 1622	-	Autotuning: Not possible to perform Autotuning	Autotuning can only be performed if no operating mode is active.	Terminate the active operating mode or disable the power stage.
E 1623	1	Autotuning: HALT request has stopped the autotuning process	Autotuning can only be performed if no operating mode is active.	Terminate the active operating mode or disable the power stage.
E 1A01	3	Motor has been changed Parameter _SigLatched Bit 16	Detected motor type is different from previously detected motor.	Confirm the motor change.
E 1B04	2	Resolution of the encoder simulation too high Parameter _SigLatched Bit 30	Parameter CTRL_v_max too small or resolution of the encoder simulation too high.	Reduce the resolution of the encoder simulation or the maximum velocity in parameter CTRL_v_max.
E 1B0C	3	Actual motor velocity too high.		
E 2300	3	Power stage overcurrent Parameter _SigLatched Bit 27	Motor short circuit and disabling of the power stage. Motor phases are inverted.	Check the motor power connection.
E 2301	3	Braking resistor overcurrent Parameter _SigLatched Bit 27	Braking resistor short circuit.	If you use the internal braking resistor, please contact Technical Support. If you use an external braking resistor, check the wiring and the rating of the braking resistor.
E 3100	par.	Mains power supply: Missing mains phase(s) or wrong mains voltage Parameter _SigLatched Bit 15	Missing phase(s) for more than 50ms. Mains voltage is too low. Mains frequency is out of range. Mains voltage and parameter setting of MON_MainsVolt do not match (for example, mains voltage is 230V and MON_MainsVolt is set to 115V).	Verify that the values of the mains power supply network comply with the technical data. Check the settings of the parameter for reduced mains voltage.
E 3200	3	DC bus overvoltage Parameter _SigLatched Bit 14	Excessive regeneration during braking.	Check deceleration ramp, check rating of drive and braking resistor.

Error number	Error class	Description	Cause	Correctives
E 3201	3	DC bus undervoltage (shut-down threshold) Parameter _SigLatched Bit 13	Power supply loss, poor power supply.	Check mains supply.
E 3202	2	DC bus undervoltage (Quick Stop threshold) Parameter _SigLatched Bit 13	Power supply loss, poor power supply.	Check mains supply.
E 3206	0	DC bus undervoltage (warning) Parameter _WarnLatched Bit 13	Power supply loss, poor/incorrect power supply.	Check mains supply.
E 3300	0	Maximum motor voltage is too low for the power stage used	The maximum motor voltage M_U_max is too low. The power stage supply voltage and the maximum motor voltage do not match.	Use a motor with a higher maximum voltage M_U_max. If this warning is ignored, the motor may be damaged.
E 4100	3	Power stage overtemperature Parameter _SigLatched Bit 18	Transistors overtemperature: Ambient temperature is too high, fan is inoperative, dust.	Check the fan, improve the heat dissipation in the cabinet.
E 4101	0	Warning power stage overtemperature Parameter _WarnLatched Bit 18	Transistors overtemperature: Ambient temperature is too high, fan is inoperative, dust.	Check the fan, improve the heat dissipation in the cabinet.
E 4102	0	Power stage overload (I2t) Parameter _WarnLatched Bit 30	The current has exceeded the nominal value for an extended period of time.	Check rating, reduce cycle time.
E 4200	3	Device overtemperature Parameter _SigLatched Bit 18	Board overtemperature: Ambient temperature is too high.	Check fan, improve the heat dissipation in the cabinet.
E 4300	2	Motor overtemperature Parameter _SigLatched Bit 17	Ambient temperature is too high. Duty cycle is too high. Motor not properly mounted (thermal isolation). Motor overload (power losses too high).	Check motor installation: The heat must be dissipated via the mounting surface. Reduce ambient temperature. Provide ventilation.
E 4301	0	Warning motor overtemperature Parameter _WarnLatched Bit 17	Resistance of thermal sensor is too high; overload, ambient temp (see I2t).	Check motor installation: The heat must be dissipated via the mounting surface.
E 4302	0	Motor overload (I2t) Parameter _WarnLatched Bit 31	The current has exceeded the nominal value for an extended period of time.	Verify that the system can easily be moved. Check the load. Use a differently sized motor, if necessary.
E 4402	0	Warning: Braking resistor overload (I2t > 75%) Parameter _WarnLatched Bit 29	The braking resistor has been switched on for such a long period of time that 75% of its overload capability have been exceeded.	The regeneration energy is too high. Possible causes: The external loads are too high, the motor velocity is too high, the deceleration is too fast.

Error number	Error class	Description	Cause	Correctives
E 4403	par.	Braking resistor overload ($I_{2t} > 100\%$)	The braking resistor is switched on for an excessively long period of time.	The regeneration energy is too high. Possible causes: The external loads are too high, the motor velocity is too high, the deceleration is too fast.
E 5101	0	Modbus power supply missing		
E 5102	4	Motor encoder supply voltage Parameter _SigLatched Bit 16	Encoder power supply is not within permissible range of 8V to 12V; there may be a hardware problem.	Replace the device. Contact Technical Support.
E 5200	4	Error at connection to motor encoder Parameter _SigLatched Bit 16	Incorrect encoder cable or cable not connected, EMC.	Check the cable connection and the shield.
E 5201	4	Errors in motor encoder communication Parameter _SigLatched Bit 16	Encoder error message: Communication error detected by the encoder itself.	Check the cable connection and the shield.
E 5202	4	Motor encoder is not supported Parameter _SigLatched Bit 16	Incompatible encoder type is connected.	Use genuine accessories.
E 5204	3	Connection to motor encoder lost Parameter _SigLatched Bit 16	Encoder cable problems (communication has been interrupted).	Check the cable connection.
E 5206	0	Communication error in encoder Parameter _WarnLatched Bit 16	Communication disturbed, EMC.	Check the connection, check the shielding on the EMC plate.
E 5207	1	Function is not supported	The current hardware revision does not support the function.	
E 5302	4	The motor requires a PWM frequency (16kHz) which the power stage does not support.	The connected motor only works with a PWM frequency of 16 kHz (motor nameplate entry). However, the power stage does not support this PWM frequency.	Use a motor that works with a PWM frequency of 8 kHz.
E 544C	4	System error: EEPROM is write-protected Parameter _SigLatched Bit 29		
E 5451	0	System error: No memory card available Parameter _WarnLatched Bit 20		
E 5452	2	System error: Data on memory card and device do not match Parameter _SigLatched Bit 20	Different type of device. Different type of power stage. Data on memory card does not match firmware version of device.	

Error number	Error class	Description	Cause	Correctives
E 5453	2	System error: Incompatible data on the memory card Parameter _SigLatched Bit 20		
E 5455	2	System error: Memory card not formatted Parameter _SigLatched Bit 20		Update memory card via HMI command "dtoc" (drive-to-card).
E 5456	1	System error: Memory card is write-protected Parameter _SigLatched Bit 20	The memory card has been write-protected.	Remove memory card or disable write protection via HMI.
E 5506	1	Error during write access to safety module via fieldbus (additional info = detailed error number)		
E 5600	3	Motor connection phase error Parameter _SigLatched Bit 26	Missing motor phase.	Check connection of motor phases.
E 5603	3	Commutation error Parameter _SigLatched Bit 26	Wiring error of motor cable. Encoder signals are lost or subject to interference. The load torque is greater than the motor torque. The encoder EEPROM contains incorrect data (encoder phase offset is incorrect). Motor is not adjusted.	Check motor phases, check encoder wiring. Check and improve EMC situation, check grounding and shielding. Resize the motor so it can withstand the load torque. Check the motor data. Contact Technical Support.
E 610D	-	Error in selection parameter	Wrong parameter value selected.	Check the value to be written.
E 610E	4	System error: 24 VDC below undervoltage threshold for shutdown		
E 7100	4	System error: Invalid power stage data Parameter _SigLatched Bit 30	Power stage data stored in device is corrupt (wrong CRC), error in internal memory data.	Contact technical support or replace the device.
E 7111	-	Parameter cannot be changed because the external braking resistor is active.	An attempt is made to change one of the parameters RESext_ton, RESext_P or RESext_R even though the external braking resistor is active.	Verify that the external braking resistor is not active if one of the parameters RESext_ton, RESext_P or RESext_R has to be changed.
E 7112	2	No external braking resistor connected	External braking resistor activated (Parameter RESint_ext), but no external resistor is detected.	Check wiring of the external braking resistor. Verify correct resistance.
E 7120	4	Invalid motor data Parameter _SigLatched Bit 16	Motor data is corrupt (wrong CRC).	Contact technical support or replace the motor.
E 7121	2	System error: Errors in motor encoder communication Parameter _SigLatched Bit 16	EMC, detailed information is included in the error memory that contains the error code of the encoder.	Contact technical support.

Error number	Error class	Description	Cause	Correctives
E 7122	4	Invalid motor data Parameter _SigLatched Bit 30	Motor data stored in motor encoder is corrupt, error in internal memory data.	Contact technical support or replace the motor.
E 7124	4	System error: Motor encoder inoperative Parameter _SigLatched Bit 16	Encoder signals internal error.	Contact technical support or replace the motor.
E 712D	4	Electronic motor nameplate not found Parameter _SigLatched Bit 16	Motor data is corrupt (wrong CRC). Motor without electronic motor nameplate (for example, SER motor)	Contact technical support or replace the motor.
E 7133	0	Not possible to write motor configuration		
E 7134	4	Incomplete motor configuration Parameter _SigLatched Bit 16		
E 7137	4	Error during the internal conversion of the motor configuration Parameter _SigLatched Bit 16		
E 7138	4	Parameter of the motor configuration out of permissible range Parameter _SigLatched Bit 16		
E 7139	0	Encoder offset: Data segment in encoder is corrupt.		
E 713A	3	Adjustment value of the encoder of the third party motor has not yet been determined. Parameter _SigLatched Bit 16		
E 7321	3	Timeout reading the absolute position from the encoder Parameter _SigLatched Bit 16	Communication channel (Hiperface) to encoder is subject to interference or motor encoder is inoperative.	Check wiring and shielding of encoder cable or replace motor.
E 7328	4	Motor encoder: Position evaluation error Parameter _SigLatched Bit 16	Position evaluation problem detected by encoder.	Contact technical support or replace the motor.
E 7329	0	Motor encoder: Warning Parameter _WarnLatched Bit 16	EMC, encoder signals internal warning.	Contact technical support or replace the motor.
E 7340	3	Reading of absolute position aborted, number of unsuccessful consecutive attempts too great Parameter _SigLatched Bit 16	Communication channel (Hiperface) to encoder is subject to interference. Encoder (in motor) is inoperative.	Check wiring and shielding of encoder cable, replace motor.

Error number	Error class	Description	Cause	Correctives
E 7341	0	Encoder temperature warning level reached Parameter _WarnLatched Bit 16	The maximum permissible duty cycle is exceeded. The motor was not mounted properly, for example, it is thermally isolated. The motor is blocked or damaged so that more current is used than under normal conditions. The ambient temperature is too high.	Reduce the duty cycle, for example, reduce acceleration. Supply additional cooling, for example, use a fan. Mount the motor in such a way as to increase thermal conductivity. Use a differently rated drive or motor. Replace the motor if it is damaged.
E 7342	2	Encoder temperature limit reached Parameter _SigLatched Bit 16	The maximum permissible duty cycle is exceeded. The motor was not mounted properly, for example, it is thermally isolated. The motor is blocked or damaged so that more current is used than under normal conditions. The ambient temperature is too high.	Reduce the duty cycle, for example, reduce acceleration. Supply additional cooling, for example, use a fan. Mount the motor in such a way as to increase thermal conductivity. Use a differently rated drive or motor. Replace the motor if it is damaged.
E 7343	0	Warning: Absolute position is different from incremental position Parameter _WarnLatched Bit 16	- Encoder is subject to EMC interference. - Motor encoder is inoperative.	Check wiring and shielding of encoder cable, replace motor.
E 7344	3	Absolute position is different from incremental position Parameter _SigLatched Bit 16	- Encoder is subject to EMC interference. - Motor encoder is inoperative.	Check wiring and shielding of encoder cable, replace motor.
E 734C	3	Error with quasi absolute position Parameter _SigLatched Bit 16	The motor shaft may have been moved while the drive was shut down. A quasi absolute position has been detected that is not within the permissible motor shaft deviation range.	If the quasi absolute function is active, only shut down the drive if the motor is at a standstill and do not move the motor shaft when the drive is off.
E 734D	0	Index pulse is not available for the encoder Parameter _WarnLatched Bit 16		
E 7500	0	RS485/Modbus: Overrun error Parameter _WarnLatched Bit 5	EMC; cabling problem.	Check cables.
E 7501	0	RS485/Modbus: Framing error Parameter _WarnLatched Bit 5	EMC; cabling problem.	Check cables.
E 7502	0	RS485/Modbus: Parity error Parameter _WarnLatched Bit 5	EMC; cabling problem.	Check cables.
E 7503	0	RS485/Modbus: Receive error Parameter _WarnLatched Bit 5	EMC; cabling problem.	Check cables.

Error number	Error class	Description	Cause	Correctives
E 7601	4	System error: Unknown type of encoder Parameter _SigLatched Bit 16		
E 7602	4	Configuration error: Encoder module and selected machine encoder type do not match Parameter _SigLatched Bit 16		
E 7603	4	Configuration error: Encoder module and selected motor encoder type do not match Parameter _SigLatched Bit 16		
E 7604	4	Configuration error: Encoder module parameterized, but no module detected Parameter _SigLatched Bit 16		
E 7605	4	Configuration error: No motor encoder type selected for encoder module Parameter _SigLatched Bit 16		
E 7606	4	Configuration error: No machine encoder type selected for encoder module Parameter _SigLatched Bit 16		
E 7607	4	Encoder module cannot be identified Parameter _SigLatched Bit 16	The encoder module is unknown.	Exchange encoder module.
E 7608	4	Encoder module power supply overcurrent Parameter _SigLatched Bit 16	- Short circuit at connector or encoder cable. - Incorrect or inoperative encoder.	
E 7609	4	Encoder not connected to encoder module Parameter _SigLatched Bit 16	Connector not connected to module or connected to motor/encoder. Incorrect or damaged encoder cable.	
E 760A	3	Encoder module in slot 2 missing. Parameter _SigLatched Bit 16	Module has been removed or module is inoperative.	
E 760C	2	Encoder signals that maximum frequency is exceeded Parameter _SigLatched Bit 16	Velocity too high for the encoder.	

Error number	Error class	Description	Cause	Correctives
E 760D	4	Configuration error: Incorrect use of encoder module Parameter _SigLatched Bit 16	Incorrect value in parameter ENC2_usage.	
E 760E	2	Position evaluation error (signal tracking error detected) Parameter _SigLatched Bit 16	Encoder signals subject to EMC interference	Check wiring, cable shield.
E 760F	0	Position evaluation problem (interference detected)	Encoder signals subject to EMC interference	Check wiring, cable shield.
E 7610	0	Resolver: Loss of position tracking, position is inaccurate Parameter _WarnLatched Bit 16	- Motor moves too fast. - Motor acceleration is too fast.	- Reduce speed. - Reduce acceleration. - Reduce resolver resolution. - Adapt resolver excitation frequency.
E 7611	2	Resolver: Signal degradation error, position is inaccurate Parameter _SigLatched Bit 16	Resolver is inoperative. Resolver signals are subject to interference. Resolver cable is too long.	Replace resolver. Check resolver cable, especially cable shield. Additional info bits: D5: Sine/cosine inputs exceed DOS out of range threshold. D4: Sine/cosine inputs exceed DOS mismatch threshold.
E 7612	3	Resolver: Error due to loss of signal, position unreliable Parameter _SigLatched Bit 16	Resolver is inoperative. Resolver wiring is incorrect. Resolver signals are subject to excessive interference. Resolver is unsuitable for drive. Incorrect parameter transformation ratio.	Check resolver cable, especially wiring and shielding. Replace resolver. Additional info bits: D7: Sine/cosine inputs clipped. D6: Sine/cosine inputs below LOS threshold.
E 7613	3	Resolver: Signal communication subject to interference Parameter _SigLatched Bit 16	Resolver signals are subject to interference.	Check resolver cable, especially wiring and shielding.
E 7614	3	Error at resolver power supply. Parameter _SigLatched Bit 16	Resolver is not connected properly.	Check resolver cable.
E 7615	3	System error: Encoder module RES is not ready for position evaluation Parameter _SigLatched Bit 16	EMC problem.	Check resolver cable.
E 7616	3	System error: Resolver timeout Parameter _SigLatched Bit 16	System error	Replace encoder module.
E 7617	1	Resolver velocity is too high Parameter _SigLatched Bit 16	Motor velocity is too high.	Reduce motor velocity.
E 7618	4	Encoder 2 Hall sensor error Parameter _SigLatched Bit 16	Incorrect wiring or damaged cable for Hall signals of encoder 2.	Check encoder cabling.

Error number	Error class	Description	Cause	Correctives
E 7619	4	Error during module - encoder communication Parameter _SigLatched Bit 16	Incorrect encoder wiring or wrong encoder parameter settings (example: parameter ENCDigSSICoding is set incorrectly for SSI encoder).	Check encoder cable, especially wiring and shield. Check encoder parameter settings.
E 761A	0	Warning during module - encoder communication Parameter _WarnLatched Bit 16	Incorrect encoder wiring.	Check encoder cable, especially wiring and shield.
E 761B	4	Connected type of EnDat encoder is not supported Parameter _SigLatched Bit 16	Operation of the EnDat encoder not possible with the entries detected in the encoder nameplate.	Use a supported EnDat encoder.
E 761C	4	Configuration error: Invalid SSI encoder parameter setting Parameter _SigLatched Bit 16	Incorrect values in parameter ENCDigSSIResSgl or ENCDigSSIResMult.	
E 761D	2	Maximum velocity of the encoder is exceeded Parameter _SigLatched Bit 16	Velocity too high for the encoder. In the case of SSI or EnDat2.2, the reason may also be an encoder communication error.	
E 761E	2	Encoder module overtemperature Parameter _SigLatched Bit 16	The ambient temperature is too high.	Improve the heat dissipation in the cabinet.
E 761F	2	Position evaluation error (AB encoder signals) Parameter _SigLatched Bit 16	No sync signal available.	
E 7620	4	Checksum error in EnDat encoder data Parameter _SigLatched Bit 16		
E 7621	1	Runtime compensation was not successful Parameter _SigLatched Bit 16		Check encoder cable, especially wiring and shield.
E 7622	0	Warning: Resolver timeout Parameter _WarnLatched Bit 22	System error.	Replace encoder module
E 7623	0	Absolute encoder signal is not available Parameter _WarnLatched Bit 22	There is no encoder available at the input specified via the parameter ENC_abs_source.	Check wiring, check encoder. Change the value of the parameter ENC_abs_source.
E 7624	0	Not possible to set the absolute position for encoder 2. Parameter _WarnLatched Bit 22	Setting the absolute position via ENC2_setpabs for the encoder at the input for encoder 2 is not possible. If no encoder is connected to the input for encoder 2 input and if ENC2_setpabs is executed, this warning is also generated.	Use an encoder that supports direct setting of the absolute position via ENC2_setpabs.

Error number	Error class	Description	Cause	Correctives
E 7625	0	Not possible to set the absolute position for encoder 1. Parameter _WarnLatched Bit 22	There is no encoder connected to the input for encoder 1.	Connect an encoder to the input for encoder 1 before trying to set the absolute position directly via ENC1_abs_pos.
E 7626	4	Overflow error during encoder scaling Parameter _SigLatched Bit 16	The multiturn resolution of the machine encoder with reference to the motor shaft exceeds the system limits, for example, due to the mechanical gear ratio between machine encoder and motor encoder.	Reduce the number of bits of the multiturn resolution that are used for position evaluation via the parameter ENCDigResMuUsed.
E 7627	4	Configuration error: Invalid BISS encoder parameter setting Parameter _SigLatched Bit 16	Incorrect values in parameters ENCDigBISSResSgl or ENCDigBISSResMult.	
E 7628	0	BISS encoder warn/alarm bit is set Parameter _WarnLatched Bit 16	Device-dependent; alarm bit is used for all types of monitoring such as: - Encoder temperature is too high. - Service life of LED inside encoder exceeded. - Position is unreliable. - etc.	- Cool down encoder. - Clean or replace encoder.
E 7629	3	BISS initialization error Parameter _SigLatched Bit 16		
E 7804	3	eSM module: Insufficient deceleration for Quick Stop Parameter _SigLatched Bit 23	Quick Stop ramp of drive lower than Quick Stop ramp configured for eSM.	Change ramp in eSM or drive.
E 7805	1	eSM module: Error during Safe Operating Stop (SOS) Parameter _SigLatched Bit 23	Motor movement during Safe Operating Stop (SOS).	Keep motor from moving while Safe Operating Stop is active (external forces, loads).
E 7806	1	eSM module: Safely Limited Speed (SLS) exceeded in machine operating mode Setup Mode Parameter _SigLatched Bit 23	Delay for reaching Safely Limited Speed (SLS) too low or deceleration ramp too high.	Increase delay for eSM control of Safely Limited Speed or decrease ramp to reach Safely Limited Speed.
E 780A	2	eSM module: /ESTOP signal for EMERGENCY STOP triggered Parameter _SigLatched Bit 23	EMERGENCY STOP is active.	Reset EMERGENCY STOP.
E 780B	0	eSM module: Not ready for Fault Reset Parameter _WarnLatched Bit 23	eSM is in state Quick Stop Active or Fault Reaction Active or Fault.	Wait until eSM is no longer in state Quick Stop Active or Fault Reaction Active or Fault or reboot the drive.

Error number	Error class	Description	Cause	Correctives
E 780C	0	eSM module: Not ready for eSM Disable Parameter_WarnLatched Bit 23	eSM is in state Operation Enabled.	Wait until eSM is no longer in state Operation Enabled.
E 780F	0	eSM module: Parameter cannot be written in this operating state Parameter_WarnLatched Bit 23	Parameter cannot be written in this eSM state.	Change eSM state to write this parameter.
E 7810	0	eSM module: Incorrect password Parameter_WarnLatched Bit 23	The password that was sent by the configuration tool is not identical to the password stored in the device.	Send the stored password.
E 7811	0	eSM module: Timeout during parameter download (default values loaded) Parameter_WarnLatched Bit 23	Connection problems or EMC.	Check wiring (shield).
E 7813	0	eSM module: Parameter checksum cannot be written in this operating state Parameter_WarnLatched Bit 23	eSM is not ready to be configured.	Use correct password. Reconfigure eSM. Contact technical Support.
E 7814	0	eSM module: Parameter checksum incorrect (default values loaded) Parameter_WarnLatched Bit 23	EMC problems.	Check wiring (shield).
E 7815	0	eSM module: Warning: Under-temperature Parameter_WarnLatched Bit 23	Temperature too low.	
E 7816	0	eSM module: Warning: Over-temperature Parameter_WarnLatched Bit 23	Temperature too high.	Check the ambient conditions. Verify that the flow of air is sufficient (pollution, objects).
E 7818	2	eSM module: System error: ESM5VDC undervoltage Parameter_SigLatched Bit 23	Error in eSM 5V supply.	
E 7819	2	eSM module: Overload outputs channel A Parameter_SigLatched Bit 23	Short circuit or overload.	Check wiring and connected devices.
E 781A	4	eSM module: System error: 5V overvoltage Parameter_SigLatched Bit 23	eSM internal power supply error	
E 781B	4	eSM module: System error: 5V undervoltage Parameter_SigLatched Bit 23	eSM internal power supply error	

Error number	Error class	Description	Cause	Correctives
E 781D	2	eSM module: ESMSTART: Maximum permissible pulse duration exceeded Parameter _SigLatched Bit 23	Pulse duration longer than 4 seconds.	Pulse duration must be less than 4 seconds.
E 7826	0	eSM module: Parameter outside of permissible value range Parameter _WarnLatched Bit 23	Parameter outside of permissible value range.	Check the parameter value.
E 7827	2	eSM module: Parameter checksum error Parameter _SigLatched Bit 23	Saved parameter values are invalid.	Reconfigure the eSM. Contact Technical Support.
E 7829	4	eSM module: Input states channel A and channel B are not identical Parameter _SigLatched Bit 23	Wire break or connected devices are inoperable.	Check wiring and connected devices.
E 782A	2	eSM module: Output states channel A and channel B are not identical Parameter _SigLatched Bit 23	Short circuit to 24V DC. System error.	Check wiring and connected devices. Contact Technical Support.
E 782F	2	eSM module: System error: Error during dynamization of STO signal Parameter _SigLatched Bit 23		
E 7833	0	eSM module: System error: EEPROM incorrect checksum (default values loaded) Parameter _WarnLatched Bit 23	EEPROM error.	
E 7834	0	eSM module: Safety module replaced (default values loaded) Parameter _WarnLatched Bit 23	This safety module has not been configured with this drive. The parameters have been reset to the default values.	Reconfigure the safety module.
E 7835	4	eSM module: Commutation position Parameter _SigLatched Bit 23	Encoder error or error in internal communication with the drive (for example, EMC).	Check EMC. Check encoder connection. Contact Technical Support.
E 7836	4	eSM module: Parameter checksums not identical Parameter _SigLatched Bit 23	Parameter of CPU_A is not identical to parameter of CPU_B. Problem during loading of parameters into eSM module.	Retry loading the parameters into the eSM module. If the problem persists, contact Technical Support.
E 7838	1	eSM module: Safely Limited Speed (SLS) exceeded in machine operating mode Automatic Mode Parameter _SigLatched Bit 23	Drive velocity greater than configured eSM velocity.	Reduce velocity of the drive or check eSM velocity for machine operating mode Automatic Mode.

Error number	Error class	Description	Cause	Correctives
E 7839	2	eSM module: Input ESM-START low instead of high (automatic start) Parameter _SigLatched Bit 23	ESMSTART is configured for automatic start and must be high at start.	Check parameter configuration of ESMSTART. Check wiring of ESMSTART.
E 783A	2	eSM module: Input ESM-START high instead of low (manual start) Parameter _SigLatched Bit 23	ESMSTART is configured for manual start and must be low at start.	Check parameter configuration of ESMSTART. Check wiring of ESMSTART.
E 783B	2	eSM module: Guard door acknowledgment: The acknowledgement signal is available for too long a time. Parameter _SigLatched Bit 23	The acknowledgement signal is available for more than 6 seconds.	The acknowledgement signal must be available for less than 6 seconds.
E 783C	4	eSM module: System error: State of eSM state machines not identical Parameter _SigLatched Bit 23		
E 783F	2	eSM module: Output AUXOUT1 (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 7840	2	eSM module: Output / INTERLOCK_OUT (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 7841	2	eSM module: Output RELAY_OUT_A (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 7842	2	eSM module: Output CCM24V_OUT_A (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 7843	2	eSM module: Output AUXOUT1 (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.
E 7844	2	eSM module: Output / INTERLOCK_OUT (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.

Error number	Error class	Description	Cause	Correctives
E 7845	2	eSM module: Output RELAY_OUT_A (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.
E 7846	2	eSM module: Output CCM24V_OUT_A (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	
E 7848	2	eSM module: System error: Input ESMSTART_A Parameter _SigLatched Bit 23		
E 7849	2	eSM module: System error: Input SETUPENABLE_A Parameter _SigLatched Bit 23		
E 784A	2	eSM module: System error: Input SETUPMODE_A Parameter _SigLatched Bit 23		
E 784B	2	eSM module: System error: Input GUARD_A Parameter _SigLatched Bit 23		
E 784C	2	eSM module: System error: Input GUARD_ACK Parameter _SigLatched Bit 23		
E 784D	2	eSM module: System error: Input /INTERLOCK_IN_A Parameter _SigLatched Bit 23		
E 784E	2	eSM module: System error: Input /ESTOP_A Parameter _SigLatched Bit 23		
E 784F	2	eSM module: System error: Input NOTUSED_A Parameter _SigLatched Bit 23		
E 7850	2	eSM module: Overload outputs channel B Parameter _SigLatched Bit 23	Short circuit or overload.	Check wiring and connected devices.
E 7852	2	eSM module: System error: ResEnc (encoder resolution) is set to 0 Parameter _SigLatched Bit 23		

Error number	Error class	Description	Cause	Correctives
E 7854	2	eSM module: No motor movement for 36 hours Parameter _SigLatched Bit 23	There has not been a minimum motor movement for the last 36 hours.	There should be a minimum motor movement at least once every 36 hours.
E 7857	2	eSM module: Parameter dec_Qstop (minimum deceleration) is set to 0 Parameter _SigLatched Bit 23	Module is not configured.	Download a configuration.
E 7858	2	eSM module: Output AUXOUT2 (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 7859	2	eSM module: Output / INTERLOCK_OUT (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 785A	2	eSM module: Output RELAY_OUT_B (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 785B	2	eSM module: Output CCM24V_OUT_B (cross fault to another output) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to another output.	Check wiring and connected devices.
E 785C	2	eSM module: Output AUXOUT2 (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.
E 785D	2	eSM module: Output / INTERLOCK_OUT (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.
E 785E	2	eSM module: Output RELAY_OUT_B (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.
E 785F	2	eSM module: Output CCM24V_OUT_B (cross fault to 24V) Parameter _SigLatched Bit 23	Cross fault detection detected a cross fault to 24V.	Check wiring and connected devices.
E 7861	2	eSM module: System error: Input ESMSTART_B Parameter _SigLatched Bit 23		

Error number	Error class	Description	Cause	Correctives
E 7862	2	eSM module: System error: Input SETUPENABLE_B Parameter _SigLatched Bit 23		
E 7863	2	eSM module: System error: Input SETUPMODE_B Parameter _SigLatched Bit 23		
E 7864	2	eSM module: System error: Input GUARD_B Parameter _SigLatched Bit 23		
E 7865	2	eSM module: System error: Input GUARD_ACK Parameter _SigLatched Bit 23		
E 7866	2	eSM module: System error: Input /INTERLOCK_IN_B Parameter _SigLatched Bit 23		
E 7867	2	eSM module: System error: Input /ESTOP_B Parameter _SigLatched Bit 23		
E 7868	2	eSM module: System error: Input NOTUSED_B Parameter _SigLatched Bit 23		
E 786A	4	eSM module: Undertempera- ture Parameter _SigLatched Bit 23	Temperature of the eSM too low.	Check ambient conditions.
E 786C	2	eSM module: Overvoltage ESM24VDC Parameter _SigLatched Bit 23	Voltage too high at the ESM24VDC.	Check power supply.
E 786D	4	eSM module: Parameter _SigLatched Bit 23	Temperature too high.	Check the ambient conditions. Verify that the flow of air is sufficient (pollution, objects).
E 7871	3	eSM module: Error during Safe Operating Stop (SOS) after error Parameter _SigLatched Bit 23	Motor movement during Safe Operating Stop (SOS).	
E 7873	1	eSM module: Error during deceleration to Safely Limited Speed (SLS) Parameter _SigLatched Bit 23	Velocity of drive greater than velocity configured for eSM Safely Limited Speed.	Check velocity value and delay time for eSM Safely Limited Speed. Adapt the drive values for ramp and velocity, if necessary.

Error number	Error class	Description	Cause	Correctives
E 7874	2	eSM module: Repeated error during Safe Operating Stop (SOS) Parameter _SigLatched Bit 23		
E 7875	4	eSM module: Repeated error during deceleration for Quick Stop Parameter _SigLatched Bit 23		
E 7876	3	eSM module: /INTERLOCK_IN not high (timeout if t_Relay = 2) Parameter _SigLatched Bit 23		
E 7877	2	eSM module: Input / INTERLOCK_IN is high even though Ignore has been configured Parameter _SigLatched Bit 23		
E 7878	2	eSM module: Velocity for Setup Mode (n_maxRed) higher than velocity for Automatic Mode (n_maxAuto) Parameter _SigLatched Bit 23	Velocity for machine operating mode Setup Mode must not be greater than velocity for machine operating mode Automatic Mode.	Check the velocities for machine operating modes Automatic Mode and Setup Mode and change them as required.
E 7879	4	eSM module: System error: Unknown state of eSM state machine Parameter _SigLatched Bit 23		
E 787A	2	eSM module: ESM24VDC undervoltage Parameter _SigLatched Bit 23	Voltage at the ESM24VDC connector to low.	Check power supply.
E 787F	4	eSM module: Encoder signal error Parameter _SigLatched Bit 23	Encoder error or encoder cable error. Signal evaluation error in drive.	
E 7880	2	eSM module: Unknown service Parameter _SigLatched Bit 23		
E 7881	2	eSM module: Parameter does not exist Parameter _SigLatched Bit 23	Parameter does not exist.	Check the parameter number.
E 7882	4	eSM module: System error: 3_3V overvoltage Parameter _SigLatched Bit 23	Error in internal eSM power supply.	

Error number	Error class	Description	Cause	Correctives
E 7883	4	eSM module: System error: 3_3V undervoltage Parameter _SigLatched Bit 23	Error in internal eSM power supply.	
E 7884	4	eSM module: System error: Temperature sensor Parameter _SigLatched Bit 23	Temperature sensor for CPU_A or CPU_B does not work properly.	
E 7900	4	Error detecting module in fieldbus slot Parameter _SigLatched Bit 21	Fieldbus module not correctly mounted in the slot. Unsupported fieldbus module inserted. Fieldbus module inoperative. EMC problems.	Replace fieldbus module. Improve EMC.
E 7901	4	Unknown type of fieldbus module detected in fieldbus slot Parameter _SigLatched Bit 21	The type of module detected in fieldbus slot is not supported by the drive.	Use supported type of fieldbus module. Refer to manual or catalog.
E 7903	3	Fieldbus module in slot 3 missing Parameter _SigLatched Bit 21	Fieldbus module has been removed or fieldbus module is inoperative.	Confirm or cancel HMI dialog box for fieldbus module replacement. Install a new fieldbus module.
E 7904	0	Parameter access error in fieldbus module	Fieldbus module parameter does not exist or cannot be written.	
E 7905	3	Fieldbus module in slot 3 has been changed. Parameter _SigLatched Bit 21	The fieldbus module has been replaced by another type of fieldbus module.	Confirm the new fieldbus module via the HMI dialog.
E 7A0B	0	I/O module: Temperature has reached warning level Parameter _WarnLatched Bit 23	Device cooling not sufficient. Cooling fan inoperative. Ambient temperature too high.	Check fan and ambient temperature.
E 7A0C	2	I/O module: Temperature has reached error level Parameter _SigLatched Bit 23	Device cooling not sufficient. Cooling fan inoperative. Ambient temperature too high.	Check fan and ambient temperature.
E 7A0D	2	I/O module not available Parameter _SigLatched Bit 23	No I/O module detected when the operating mode Profile Velocity or Profile Torque with reference value via analog input was activated. I/O module has been removed the de device was off.	Plug in the I/O module.
E 7A0E	4	I/O module: Inoperative Parameter _SigLatched Bit 23		
E 7A0F	2	I/O module: Inoperative Parameter _SigLatched Bit 23		

Error number	Error class	Description	Cause	Correctives
E 7A10	4	I/O module: Inoperative Parameter _SigLatched Bit 23		
E 7A11	4	I/O module: Inoperative Parameter _SigLatched Bit 23		
E 7A12	2	I/O module required for velocity or torque limitation via analog input Parameter _SigLatched Bit 23	Velocity or torque limitation via analog input has been activated, but no I/O module has been plugged in.	Plug in the I/O module or deactivate the velocity or torque limitation setting via the analog input
E 7A13	par.	I/O module: Overload or short circuit at analog output Parameter _SigLatched Bit 23	Overload or short circuit at one of the analog outputs.	Check wiring and connected load.
E 8120	0	CANopen: CAN Controller in Error Passive Parameter _WarnLatched Bit 21	Too many error frames have been detected.	Check CAN bus installation.
E 8130	2	CANopen: Heartbeat or Life Guard error Parameter _SigLatched Bit 21	The bus cycle time of the CANopen master is higher than the programmed heartbeat or node guard time.	Check the CANopen configuration, increase the heartbeat or node guard time.
E 8131	0	CANopen: Heartbeat or Life Guard error Parameter _WarnLatched Bit 21		
E 8140	0	CANopen: CAN controller was in 'bus-off', communication is possible again Parameter _WarnLatched Bit 21		
E 8141	2	CANopen: CAN controller is in 'bus-off' Parameter _SigLatched Bit 21	Too many error frames have been detected, CAN devices with different baud rates.	Check CAN bus installation.
E 8142	0	CANopen: CAN controller is in 'bus-off' Parameter _WarnLatched Bit 21	Too many error frames have been detected, CAN devices with different baud rates.	Check CAN bus installation.
E 8281	0	CANopen: RxPDO1 could not be processed Parameter _WarnLatched Bit 21	Error while processing Receive PDO1: PDO1 contains invalid value.	Check RxPDO1 content (application).
E 8282	0	CANopen: RxPDO2 could not be processed Parameter _WarnLatched Bit 21	Error while processing Receive PDO2: PDO2 contains invalid value.	Check RxPDO2 content (application).

Error number	Error class	Description	Cause	Correctives
E 8283	0	CANopen: RxPDO3 could not be processed Parameter _WarnLatched Bit 21	Error while processing Receive PDO3: PDO3 contains invalid value.	Check RxPDO3 content (application).
E 8284	0	CANopen: RxPDO4 could not be processed Parameter _WarnLatched Bit 21	Error while processing Receive PDO4: PDO4 contains invalid value.	Check RxPDO4 content (application)
E 8294	0	CANopen: TxPdo could not be processed Parameter _WarnLatched Bit 21		
E A060	2	Calculated velocity too high for operating mode Electronic Gear Parameter _SigLatched Bit 4	Gear ratio or reference velocity value too high	Reduce the gear ratio or reference velocity.
E A061	2	Position change in reference value for operating mode Electronic Gear too high Parameter _SigLatched Bit 4	Position reference change is too high. Error at signal input for reference value.	Reduce the resolution of the master. Check signal input for reference signal.
E A300	-	Braking procedure after HALT request still active	HALT was removed too soon. New command was sent before motor standstill was reached after a HALT request.	Wait for complete stop before removing HALT signal. Wait until motor has come to a complete standstill.
E A301	-	Drive in operating state Quick Stop Active	Error with error class 1 occurred. Drive stopped with Quick Stop command.	
E A302	1	Stop by positive limit switch Parameter _SigLatched Bit 1	The positive limit switch was activated because movement range was exceeded, misoperation of limit switch or signal disturbance.	Check application. Check limit switch function and connection.
E A303	1	Stop by negative limit switch Parameter _SigLatched Bit 1	The negative limit switch was activated because movement range was exceeded, misoperation of limit switch or signal disturbance.	Check application. Check limit switch function and connection.
E A305	-	Power stage cannot be enabled in the current operating state	Fieldbus: An attempt was made to enable the power stage in the operating state Not Ready To Switch On.	Refer to the state diagram.
E A306	1	Stop by user-initiated software stop Parameter _SigLatched Bit 3	Drive is in operating state Quick Stop Active due to a software stop request. The activation of a new operating mode is not possible, the error code is sent as the response to the activation command.	Clear break condition with command Fault Reset.

Error number	Error class	Description	Cause	Correctives
E A307	-	Interruption by internal software stop	In the operating mode Homing and Jog, the movement is internally interrupted by an internal software stop. The activation of a new operating mode is not possible, the error code is sent as the response to the activation command.	Clear break condition with command Fault Reset.
E A308	-	Drive is in operating state Fault or Fault Reaction Active	Error with error class 2 or higher occurred.	Check error code (HMI or commissioning software), remove error condition and clear error with command Fault Reset.
E A309	-	Drive not in operating state Operation Enabled	A command was sent that requires the drive to be in the operating state Operation Enabled was sent (for example, a command to change the operating mode).	Set drive to operating state Operation Enabled and repeat the command.
E A310	-	Power stage not enabled	Command cannot be used because the power stage is not enabled (operating state Operation Enabled or Quick Stop Active).	Set drive to an operating state in which the power stage is enabled, refer to the state diagram.
E A313	-	Position overtraveled, reference point is therefore no longer defined (ref_ok=0)	The movement range limits were exceeded which resulted in a loss of the reference point. An absolute movement cannot be made before a new reference point is defined.	Define a new reference point by means of the operating mode Homing.
E A314	-	No reference point	Command needs a defined reference point (ref_ok=1).	Define a new reference point by means of the operating mode Homing.
E A315	-	Homing active	Command cannot be used while the operating mode Homing is active.	Wait until reference movement is finished.
E A317	-	Motor is not at a standstill	Command sent which is not allowed when the motor is not at a standstill. For example: - Change of software limit switches - Change of handling of monitoring signals - Setting of reference point - Teach in of data set	Wait until the motor has come to a standstill (x_end = 1).
E A318	-	Operating mode active (x_end=0)	Activation of a new operating mode is not possible while the current operating mode is still active.	Wait until the command in the operating mode has finished (x_end=1) or terminate current operating mode with HALT command.
E A319	1	Manual tuning/Autotuning: Movement out of permissible range Parameter _SigLatched Bit 2	The movement exceeds the parameterized maximum permissible movement range.	Check permissible movement range value and time interval.
E A31A	-	Manual tuning/Autotuning: Amplitude/offset too high	Amplitude plus offset for tuning exceed internal velocity or current limitation.	Choose lower amplitude and offset values.

Error number	Error class	Description	Cause	Correctives
E A31B	-	HALT requested	Command not allowed while a HALT is requested.	Clear HALT request and repeat command.
E A31C	-	Invalid position setting with software limit switch	Value for negative (positive) software limit switch is greater (less) than value for positive (negative) software limit switch.	Set correct position values.
E A31D	-	Velocity range exceeded (parameter CTRL_v_max, M_n_max)	The velocity was set to a value greater than the maximum permissible velocity in parameter CTRL_v_max or M_n_max, whichever is lower.	If the value of parameter M_n_max is greater than the value of parameter CTRL_v_max, increase the value of parameter CTRL_v_max or reduce the velocity value.
E A31E	1	Stop by positive software limit switch Parameter _SigLatched Bit 2	Not possible to execute command because positive software limit switch was overtraveled.	Return to the permissible range.
E A31F	1	Stop by negative software limit switch Parameter _SigLatched Bit 2	Not possible to execute command because negative software limit switch was overtraveled.	Return to the permissible range.
E A320	par.	Following error Parameter _SigLatched Bit 8	External load or acceleration are too high.	Reduce external load or acceleration. Use a differently rated drive, if necessary. Error response can be adjusted via parameter ErrorResp_p_dif.
E A324	1	Error during homing (additional info = detailed error number) Parameter _SigLatched Bit 4	Homing movement was stopped by an error, the detailed reason is indicated by the additional info in the error buffer.	Possible sub error codes: E A325, E A326, E A327, E A328 or E A329.
E A325	1	Limit switch to be approached not enabled Parameter _SigLatched Bit 4	Homing to positive limit switch or negative limit switch is disabled.	Enable limit switch via 'IOsigLimP' or 'IOsigLimN'.
E A326	1	Reference switch not found between positive limit switch and negative limit switch Parameter _SigLatched Bit 4	Reference switch inoperative or not correctly connected.	Check the function and wiring of the reference switch.
E A329	1	More than one signal positive limit switch/negative limit switch/reference switch signal active Parameter _SigLatched Bit 4	Reference switch or limit switch not connected correctly or supply voltage for switches too low.	Check the wiring and 24VDC supply voltage.
E A32A	1	Positive limit switch triggered with negative direction of movement Parameter _SigLatched Bit 4	Start reference movement with negative direction (for example reference movement to negative limit switch) and activate the positive limit switch (switch in opposite direction of movement).	Check correct connection and function of limit switch. Activate a jog movement with negative movement (target limit switch must be connected to the negative limit switch).

Error number	Error class	Description	Cause	Correctives
E A32B	1	Negative limit switch triggered with positive direction of movement Parameter _SigLatched Bit 4	Start reference movement with positive direction (for example reference movement to positive limit switch) and activate the negative limit switch (switch in opposite direction of movement).	Check correct connection and function of limit switch. Activate a jog movement with positive movement (target limit switch must be connected to the positive limit switch).
E A32C	1	Reference switch error (switch signal briefly enabled or switch overtraveled) Parameter _SigLatched Bit 4	Switch signal disturbance. Motor subjected to vibration or shock when stopped after activation of the switch signal.	Check supply voltage, cabling and function of switch. Check motor reaction after stopping and optimize controller settings.
E A32D	1	Positive limit switch error (switch signal briefly enabled or switch overtraveled) Parameter _SigLatched Bit 4	Switch signal disturbance. Motor subjected to vibration or shock when stopped after activation of the switch signal.	Check supply voltage, cabling and function of switch. Check motor reaction after stopping and optimize controller settings.
E A32E	1	Negative limit switch error (switch signal briefly enabled or switch overtraveled) Parameter _SigLatched Bit 4	Switch signal disturbance. Motor subjected to vibration or shock when stopped after activation of the switch signal.	Check supply voltage, cabling and function of switch. Check motor reaction after stopping and optimize controller settings.
E A330	0	Reference movement to index pulse cannot be reproduced. Index pulse is too close to the switch Parameter _WarnLatched Bit 4	The position difference between the index pulse and the switching point is insufficient.	Increase the distance between the index pulse and the switching point. If possible, the distance between the index pulse and the switching point should be a half motor revolution.
E A332	1	Jog error (additional info = detailed error number) Parameter _SigLatched Bit 4	Jog movement was stopped by error.	For additional info, check the detailed error number in the error buffer.
E A334	2	Timeout Standstill Window monitoring	Position deviation after movement greater than standstill window. This may have been caused by an external load.	Check load. Check settings for standstill window (parameter MON_p_win, MON_p_winTime and MON_p_winTout). Optimize controller settings.
E A337	0	Operating mode cannot be continued Parameter _WarnLatched Bit 4	Continuation of interrupted movement in operating mode Profile Position is not possible because another operating mode had been active in the meantime. In the operating mode Motion Sequence, continuation is not possible if a motion blend was interrupted.	Restart the operating mode.
E A33A	0	Reference point is not defined (ref_ok=0) Parameter _WarnLatched Bit 4	No reference point defined by means of operating mode Homing. Reference position lost because the movement range has been left. Motor does not have an absolute encoder.	Use operating mode Homing to define a reference point. Use a motor with an absolute encoder.

Error number	Error class	Description	Cause	Correctives
E A33D	0	Motion blend is already active Parameter _WarnLatched Bit 4	Change of motion blend during the current motion blend (end position of motion blend not yet reached)	Wait for the motion blend to complete before setting the next position.
E A33E	0	No movement activated Parameter _WarnLatched Bit 4	Activation of a motion blend without movement.	Start a movement before the motion blend is activated.
E A33F	0	Position of motion blend movement not in the range of the active movement Parameter _WarnLatched Bit 4	The position of the motion blend is outside of the current movement range.	Check the position of the motion blend and the current movement range.
E A340	1	Error in operating mode Motion Sequence (additional info = detailed error number) Parameter _SigLatched Bit 4	The operating mode Motion Sequence was stopped by an error. Check the error memory for details on the error.	Verify the error by checking the additional error information.
E A341	0	Position of motion blend has already been passed Parameter _WarnLatched Bit 4	The current movement has passed beyond the position of the motion blend.	
E A342	1	Target velocity was not reached at motion blend position. Parameter _SigLatched Bit 4	The position of the motion blend was overtraveled, the target velocity was not reached.	Reduce the ramp velocity so that the target velocity is reached at the position of the motion blend.
E A344	3	Maximum position deviation between motor encoder and machine encoder exceeded Parameter _SigLatched Bit 8	Incorrect or damaged encoder cable. Machine encoder not connected or not supplied correctly. Different counting directions of motor encoder and machine encoder. Wrong setting of resolution factors (numerator or denominator) of machine encoder.	Check encoder connection. Check parameterization of machine encoder.
E A347	0	Threshold for position deviation warning reached Parameter _WarnLatched Bit 8	External load or acceleration are too high.	Reduce external load or acceleration. Threshold can be adjusted via the parameter MON_p_dif_warn.
E A34D	-	The function is not possible when Modulo is active.	The function cannot be executed when Modulo is active.	Deactivate Modulo to use the function.
E A34E	-	Target value for absolute movement not possible with defined modulo range and modulo handling.	If parameter 'MOD_Absolute' is set to: Shortest Distance: Target value is not in defined modulo range. Positive Direction: Target value is less than parameter 'MOD_Min'. Negative Direction: Target value is greater than parameter 'MOD_Max'.	Set a correct target value for absolute movement.

Error number	Error class	Description	Cause	Correctives
E A34F	-	Target position outside of modulo range. Corresponding movement within range performed instead.	The current setting of parameter 'MOD_AbsMultiRng' only allows for a movement within the modulo range.	Change the parameter 'MOD_AbsMultiRng' to allow for movements beyond the modulo range.
E A350	1	Change for jerk filter input position too great Parameter _SigLatched Bit 4	Operating mode Electronic Gear with processing method 'Position synchronization with compensation movement' has been activated which resulted in a position change greater than 0.25 revolutions.	Deactivate jerk filter processing for Electronic Gear or use processing method 'Position synchronization without compensation movement'.
E A351	1	Function cannot be executed with the current position scaling factor Parameter _SigLatched Bit 4	The positions scaling factor is set to a value less than 1 rev/131072usr_p, which is less than the internal resolution. In the operating mode Cyclic Synchronous Position, the resolution is not set to 1 rev/131072usr_p.	Use a different position scaling factor or deactivate the selected function.
E A355	1	Error during relative movement after capture (additional info = detailed error number) Parameter _SigLatched Bit 4	Movement was stopped by error.	Check the error memory or the parameter _LastError_Qual for additional information.
E A356	0	Function Relative Movement After Capture not assigned to a digital input.		Assign the function Relative Movement After Capture to a digital input.
E A357	-	Braking procedure still active	Command is not allowed when a braking procedure is active.	Wait until motor has come to a complete standstill.
E A358	1	Target position overtraveled with function Relative Movement After Capture Parameter _SigLatched Bit 4	Stopping distance too small or velocity too high at the point in time of the capture event.	Reduce the velocity.
E A359	0	Request cannot be processed since the relative movement after capture is still active		
E B100	0	RS485/Modbus: Unknown service Parameter _WarnLatched Bit 5	Unsupported Modbus service was received.	Check application on the Modbus master.
E B101	1	Incorrect I/O data configuration (additional info=Modbus register address) Parameter _SigLatched Bit 21	The I/O data configuration or the Modbus I/O scanning configuration contains an invalid parameter.	Check the configuration of the I/O data.
E B102	1	Fieldbus module: General error Parameter _SigLatched Bit 21		
E B103	2	Fieldbus module: Controlling communication channel has been closed Parameter _SigLatched Bit 21		

Error number	Error class	Description	Cause	Correctives
E B104	2	Fieldbus module: Internal communication error Parameter _SigLatched Bit 21		
E B105	2	Fieldbus module: I/O data timeout Parameter _SigLatched Bit 21		
E B106	2	Fieldbus module: I/O data mapping error Parameter _SigLatched Bit 21		
E B107	4	Fieldbus module: EEPROM error in module Parameter _SigLatched Bit 21		
E B120	2	Cyclic communication: Incorrect cycle time Parameter _SigLatched Bit 21	The drive does not support the configured cycle time or the difference between the measured cycle time and the configured cycle time is too great.	Change the cycle time in the master controller to a cycle time supported by the drive or check synchronization requirements.
E B121	2	Cyclic communication: Synchronization signal missing Parameter _SigLatched Bit 21	Two cycles have passed without a synchronization signal having been received.	Analyze the communication.
E B122	2	Cyclic communication: Incorrect synchronization Parameter _SigLatched Bit 21	One signal was missing and expected second signal was received at an incorrect point in time. The master controller may be unable to provide the required synchronization signals at the current cycle time, for example, due to insufficient computing power.	Analyze the communication or increase the cycle time.
E B123	2	Cyclic communication: The selected cycle time tolerance is too high. Parameter _SigLatched Bit 21	The cycle time tolerance may not exceed one quarter of the set cycle time.	Enter a correct value.
E B200	0	RS485/Modbus: Protocol error Parameter _WarnLatched Bit 5	Logical protocol error: Wrong length or unsupported sub-function.	Check application on the Modbus master.
E B201	2	RS485/Modbus: Node Guarding error Parameter _SigLatched Bit 5	Connection monitoring (parameter MBnode_guard) is ≤ 0 ms and a nodeguard event was detected.	Check application on the Modbus master or change value (set to 0ms or increase the parameter MBnode_guard monitoring time).
E B202	0	RS485/Modbus: Node Guarding warning Parameter _WarnLatched Bit 5	Connection monitoring (parameter MBnode_guard) is ≤ 0 ms and a Node Guarding event was detected.	Check application on the Modbus master or change value (set to 0ms or increase the parameter MBnode_guard monitoring time).

Error number	Error class	Description	Cause	Correctives
E B312	2	Profibus: Clear command with error response Parameter _SigLatched Bit 21	Clear command sent by master, bus error.	Check application.
E B314	2	Profibus: Watchdog error with error response Parameter _SigLatched Bit 21	The bus cycle time of the Profibus master is greater than the programmed watchdog time.	Increase watchdog time in the Profibus master.
E B316	2	Profibus: Communication error with error response Parameter _SigLatched Bit 21	System or bus error, EMC.	Check Profibus connection, shielding.
E B400	2	CANopen: NMT reset with power stage enabled Parameter _SigLatched Bit 21	NMT Reset command is received while drive is in operating state Operation Enabled.	Disable the power stage before sending a NMT reset command.
E B401	2	CANopen: NMT stop with power stage enabled Parameter _SigLatched Bit 21	NMT Stop command is received while drive is in operating state Operation Enabled.	Disable the power stage before sending a NMT Stop command.
E B402	0	CAN PLL active Parameter _WarnLatched Bit 21	An attempt has been made to start the synchronization mechanism even though the synchronization mechanism was already active.	Deactivate the synchronization mechanism.
E B403	2	Excessive Sync period deviation from ideal value Parameter _SigLatched Bit 21	The period time of the SYNC signals is not stable. The deviation is more than 100usec.	The SYNC signals of the motion controller must be more accurate.
E B404	2	Sync signal error Parameter _SigLatched Bit 21	SYNC signal missed more than twice.	Check CAN connection, check motion controller.
E B405	2	Drive could not be adapted to master cycle Parameter _SigLatched Bit 21	The jitter of the SYNC object is too great or the motion bus requirements are not considered.	Check the timing requirements regarding interpolation time period and number of devices.
E B406	0	Baud rate is not supported. Parameter _WarnLatched Bit 21	The configured baud rate is not supported.	Choose one of the following baud rates: 250kB, 500kB, 1000kB.
E B407	0	Drive is not synchronous with master cycle Parameter _WarnLatched Bit 21	The 'Cyclic Synchronous Mode' cannot be activated as long as the drive is not synchronized.	Check motion controller. To be synchronized, the motion controller must cyclically send SYNC signals.
E B600	2	Ethernet: Network overload Parameter _SigLatched Bit 21		
E B601	2	Ethernet: Loss of Ethernet carrier Parameter _SigLatched Bit 21		

Error number	Error class	Description	Cause	Correctives
E B602	2	Ethernet: Duplicate IP address Parameter _SigLatched Bit 21		
E B603	2	Ethernet: No valid IP address Parameter _SigLatched Bit 21		
E B604	0	Ethernet: DHCP/BOOTP Parameter _WarnLatched Bit 21	IP assignment via DHCP/BOOTP unsuccessful. Effort was given up after 2 minutes.	Set up a properly working DHCP or BOOTP server or assign the IP address manually.
E B605	2	Ethernet FDR: Unconfigured error Parameter _SigLatched Bit 21		
E B606	2	Ethernet FDR: Irrecoverable error Parameter _SigLatched Bit 21		
E B607	2	Ethernet: I/O data idle Parameter _SigLatched Bit 21	PLC has been stopped, but I/O data keeps being transmitted.	Disable power stage of connected drives before stopping the PLC.
E B610	2	EtherCAT: Fieldbus watchdog error (additional info = detailed error number) Parameter _SigLatched Bit 21	EtherCAT frames are lost, for example, due to cable errors or master errors.	Verify correct cabling and shielding. Check diagnostics info of EtherCAT master.
E B611	2	EtherCAT: Invalid I/O data (additional info = detailed error number) Parameter _SigLatched Bit 21	Incorrect input data or output data (such as object length, object type)	Check for correct PDO configuration (length, objects, etc.).
E B612	2	EtherCAT: Link lost at input and output port Parameter _SigLatched Bit 21	EtherCAT cable error. Link to connected devices lost.	Check link LEDs. Check cables and verify that the devices connected to input port and output port operate. Use EtherCAT master diagnostics for further troubleshooting.
E B700	0	Drive Profile Lexium: On activation of the profile, no dmControl, refA or refB has been mapped.	dmControl, refA or refB have not been mapped.	dmControl, refA or refB must be mapped.
E B702	1	Information loss too high due to velocity scaling.	Due to the configured velocity scaling, the information loss of the shift factor is too high.	Change the velocity scaling.

11 Parameters

11

This chapter provides an overview of the parameters which can be used for operating the product.

In addition, special parameters for communication via the fieldbus are described in the corresponding fieldbus manual.

⚠ WARNING

UNINTENDED BEHAVIOR CAUSED BY PARAMETERS

The behavior of the drive system is governed by numerous parameters. Unsuitable parameter values can trigger unintended movements or signals or deactivate monitoring functions.

- Never change a parameter unless you understand its meaning.
- Only start the system if there are no persons or obstructions in the hazardous area.
- When commissioning, carefully run tests for all operating states and potential fault situations.

Failure to follow these instructions can result in death, serious injury or equipment damage.

11.1 Representation of the parameters

The way parameters are shown provides information required for unique identification, the default values and the properties of a parameter.

Structure of the parameter representation:

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
Example_Name [onF → , nF- Prn	Short description (cross reference) Selection values 1 / Selection value 1 / AbC 1: Explanation 1 2 / Selection value 2 / AbC 2: Explanation 2 Description and details	A _{pk} 0.00 3.00 300.00	UINT32 R/W per. -	Fieldbus 1234:5 _h

Parameter name The parameter name uniquely identifies a parameter.

HMI menu HMI menu shows the sequence of menus and commands to access the parameter via the HMI.

<i>Description</i>	<p>Short description (cross reference) The short description contains information on the parameter and a cross reference to the page that describes the use of the parameter.</p> <p>Selection values In the case of parameters which offer a selection of settings, the value to be entered via the fieldbus and the designation of the value for input via the commissioning software and the HMI are specified. 1 = Value via fieldbus Selection value1 = Selection value via commissioning software Abc 1 = Selection value via HMI</p> <p>Further description and details Provides further information on the parameter.</p>
<i>Unit</i>	The unit of the value.
<i>Minimum value</i>	The minimum value which can be entered.
<i>Factory setting</i>	Factory settings when the product is shipped
<i>Maximum value</i>	The maximum value which can be entered.
<i>Data type</i>	If the minimum and the maximum values are not explicitly indicated, the valid range of values is determined by the data type.

Data type	Byte	Minumum value	Maximum value
INT8	1 Byte / 8 Bit	-128	127
UINT8	1 Byte / 8 Bit	0	255
INT16	2 Byte / 16 Bit	-32768	32767
UINT16	2 Byte / 16 Bit	0	65535
INT32	4 Byte / 32 Bit	-2147483648	2147483647
UINT32	4 Byte / 32 Bit	0	4294967295

<i>R/W</i>	<p>Indicates read and/or write values</p> <p>"R/" values can only be read "R/W" values can be read and written.</p>
<i>Persistent</i>	<p>"per." indicates whether the value of the parameter is persistent, i.e. whether it remains in the memory after the device is switched off .</p> <p>When a value is entered via the HMI, the device stores the value of the parameter automatically each time it is changed.</p> <p>When changing a value via commissioning software or fieldbus, the user must explicitly store the changed value in the persistent memory.</p> <p>NOTE: Parameters for the safety module eSM are modified using the commissioning software. The parameter values are saved persistently after transfer. Explicit saving to the persistent memory is not required in the case of the eSM module.</p>

11.1.1 Decimal numbers for fieldbus

Entering values Please note that parameter values are entered via the fieldbus without a decimal point. All decimal places must be entered.

Input examples:

Value	Commissioning software	Fieldbus
20	20	20
5.0	5.0	50
23.57	23.57	2357
1.000	1.000	1000

11.2 List of parameters

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_AccessInfo	Current access channel Low byte: Value 0: Used by channel in high byte Value 1: Exclusively used by channel in high byte High byte: Current assignment of access channel Value 0: Reserved Value 1: I/O Value 2: HMI Value 3: Modbus RS485 Value 4: Fieldbus main channel Values 5 ... 12: Modbus TCP, CANopen second SDO or Profibus master class 2 Values 13 ... 28: Ethernet/IP explicit channels	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3001:C _h Modbus 280 Profibus 280 CIP 101.1.12
_actionStatus	Action word Signal state: 0: Not activated 1: Activated Bit 0: Warning (error class 0) Bit 1: Error class 1 Bit 2: Error class 2 Bit 3: Error class 3 Bit 4: Error class 4 Bit 5: Reserved Bit 6: Motor is at standstill ($_n_act < 9$) Bit 7: Motor movement in positive direction Bit 8: Motor movement in negative direction Bit 9: Can be mapped via parameter DPLintLim Bit 10: Can be mapped via parameter DS402intLim Bit 11: Profile generator idle (reference velocity is 0) Bit 12: Profile generator decelerates Bit 13: Profile generator accelerates Bit 14: Profile generator moves at constant speed Bit 15: Reserved	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:4 _h Modbus 7176 Profibus 7176 CIP 128.1.4
_AT_J	Moment of inertia of the complete system (177) Is automatically calculated during Autotuning. In increments of 0.1 kg cm ² .	kg cm ² 0.1 0.1 6553.5	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 302F:C _h Modbus 12056 Profibus 12056 CIP 147.1.12
_AT_M_friction	Friction torque of the system (177) Is determined during Autotuning. In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302F:7 _h Modbus 12046 Profibus 12046 CIP 147.1.7

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_AT_M_load	Constant load torque (177) Is determined during Autotuning. In increments of 0.01 A _{rms} .	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 302F:8 _h Modbus 12048 Profibus 12048 CIP 147.1.8
_AT_progress	Progress of Autotuning (176)	% 0 0 100	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302F:B _h Modbus 12054 Profibus 12054 CIP 147.1.11
_AT_state	Autotuning status (176) Bit assignments: Bits 0 ... 10: Last processing step Bit 13: auto_tune_process Bit 14: auto_tune_end Bit 15: auto_tune_err	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302F:2 _h Modbus 12036 Profibus 12036 CIP 147.1.2
_CanDiag	CANopen diagnosis word 0001h: pms read error for TxPdo 0002h: pms write error for RxPdo1 0004h: pms write error for RxPdo2 0008h: pms write error for RxPdo3 0010h: pms write error for RxPdo4 0020h: heartbeat or lifeguard error (timer expired) 0040h: heartbeat msg with wrong state received 0080h: CAN warning level set 0100h: CAN message lost 0200h: CAN busoff 0400h: software queue rx/tx overrun 0800h: error indication from last error	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3041:6 _h Modbus 16652 Profibus 16652 CIP 165.1.6
_Cap1Count	Capture input 1 event counter (341) Counts the capture events. The counter is reset when capture input 1 is activated.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300A:8 _h Modbus 2576 Profibus 2576 CIP 110.1.8
_Cap1Pos	Capture input 1 captured position (341) Captured position at the time of the "capture signal". The captured position is re-calculated after "Position Setting" or "Reference Movement".	usr_p - - -	INT32 INT32 INT32 R/- - -	CANopen 300A:6 _h Modbus 2572 Profibus 2572 CIP 110.1.6
_Cap2Count	Capture input 2 event counter (341) Counts the capture events. The counter is reset when capture input 2 is activated.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300A:9 _h Modbus 2578 Profibus 2578 CIP 110.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_Cap2Pos	Capture input 2 captured position (341) Captured position at the time of the "capture signal". The captured position is re-calculated after "Position Setting" or "Reference Movement".	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 300A:7 _h Modbus 2574 Profibus 2574 CIP 110.1.7
_Cap3Count	Capture input 3 event counter (341) Counts the capture events. The counter is reset when capture input 3 is activated. Available as of hardware version RS03.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300A:14 _h Modbus 2600 Profibus 2600 CIP 110.1.20
_Cap3Pos	Capture input 3 captured position (341) Captured position at the time of the "capture signal". The captured position is re-calculated after "Position Setting" or "Reference Movement". Available as of hardware version RS03.	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 300A:13 _h Modbus 2598 Profibus 2598 CIP 110.1.19
_CapStatus	Status of the capture inputs (340) Read access: Bit 0: Position captured via input CAP1 Bit 1: Position captured via input CAP2 Bit 2: Position captured via input CAP3	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300A:1 _h Modbus 2562 Profibus 2562 CIP 110.1.1
_Cond_State4	Conditions for transition to operating state Ready To Switch On Signal state: 0: Condition not met 1: Condition met Bit 0: DC bus or mains voltage Bit 1: Inputs for safety function Bit 2: No configuration download ongoing Bit 3: Velocity greater than limit value Bit 4: Absolut position has been set Bit 5: Holding brake not manually released	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:26 _h Modbus 7244 Profibus 7244 CIP 128.1.38
_CTRL_ActParSet	Active controller parameter set (151) Value 1: Controller parameter set 1 is active Value 2: Controller parameter set 2 is active A controller parameter set is active after the time for the parameter switching (CTRL_ParChgTime) has elapsed.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3011:17 _h Modbus 4398 Profibus 4398 CIP 117.1.23
_CTRL_KPId	Current controller d component P gain This value is calculated on the basis of the motor parameters. In increments of 0.1 V/A.	V/A 0.5 - 1270.0	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3011:1 _h Modbus 4354 Profibus 4354 CIP 117.1.1

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_CTRL_KPiq	Current controller q component P gain This value is calculated on the basis of the motor parameters. In increments of 0.1 V/A.	V/A 0.5 - 1270.0	UINT16 UINT16 UINT16 R/- per. -	CANopen 3011:3 _h Modbus 4358 Profibus 4358 CIP 117.1.3
_CTRL_TNid	Current controller d component integral action time This value is calculated on the basis of the motor parameters. In increments of 0.01 ms.	ms 0.13 - 327.67	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3011:2 _h Modbus 4356 Profibus 4356 CIP 117.1.2
_CTRL_TNiq	Current controller q component integral action time This value is calculated on the basis of the motor parameters. In increments of 0.01 ms.	ms 0.13 - 327.67	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3011:4 _h Modbus 4360 Profibus 4360 CIP 117.1.4
_DataError	Error code for synchronous errors (DE bit) Drive Profile Lexium: Manufacturer-specific error code that caused the DataError bit to be set. Usually, this is an error that was caused by the changing of an data value within the process data. The DataError bit relates to MT-independent parameters.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:1B _h Modbus 6966 Profibus 6966 CIP 127.1.27
_DataErrorInfo	Additional error information of a DataError (DE bit) Drive Profile Lexium: Indicates the parameter of the mapping that caused the DE bit to be set. The DE bit is set if MT-independent parameters of the current mapping cause an error in connection with a write command. Example: 1 = 1st mapped parameter 2 = 2nd mapped parameter etc.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:1D _h Modbus 6970 Profibus 6970 CIP 127.1.29

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_DCOMopmd_act	Active operating mode -6 / Manual Tuning / Autotuning : Manual Tuning / Autotuning -3 / Motion Sequence : Motion Sequence -2 / Electronic Gear : Electronic Gear -1 / Jog : Jog 0 / Reserved : Reserved 1 / Profile Position : Profile Position 3 / Profile Velocity : Profile Velocity 4 / Profile Torque : Profile Torque 6 / Homing : Homing 7 / Interpolated Position : Interpolated Position 8 / Cyclic Synchronous Position : Cyclic Synchronous Position 9 / Cyclic Synchronous Velocity : Cyclic Synchronous Velocity 10 / Cyclic Synchronous Torque : Cyclic Synchronous Torque	- -6 - 10	INT8 INT16 INT16 INT16 R/- - -	CANopen 6061:0 _h Modbus 6920 Profibus 6920 CIP 127.1.4
_DCOMstatus	DriveCom status word Bits 0 ... 3: Status bits Bit 4: Voltage enabled Bits 5 ... 6: Status bits Bit 7: Warning Bit 8: HALT request active Bit 9: Remote Bit 10: Target reached Bit 11: Internal limit Bit 12: Operating mode-specific Bit 13: x_err Bit 14: x_end Bit 15: ref_ok The meaning of bit 11 can be set via the parameter DS402intLim.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 6041:0 _h Modbus 6916 Profibus 6916 CIP 127.1.2
_DEV_T_current non EdEU	Current device temperature	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:12 _h Modbus 7204 Profibus 7204 CIP 128.1.18
_DPL_BitShiftRefA16	Bit shift for RefA16 for Drive Profile Lexium Velocity scaling may lead to values that cannot be represented as 16 bit values. If RefA16 is used, this parameter indicates the number of bits by which the value is shifted so that transmission is possible. The master must consider this value prior to transmission and shift the bits to the right accordingly. The number of bits is recalculated each time the power stage is enabled. Changed settings become active immediately.	- 0 0 12	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:5 _h Modbus 6922 Profibus 6922 CIP 127.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_DPL_driveInput	Drive Profile Lexium driveInput	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:28 _h Modbus 6992 Profibus 6992 CIP 127.1.40
_DPL_driveStat	Drive Profile Lexium driveStat	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:25 _h Modbus 6986 Profibus 6986 CIP 127.1.37
_DPL_mfStat	Drive Profile Lexium mfStat	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:26 _h Modbus 6988 Profibus 6988 CIP 127.1.38
_DPL_motionStat	Drive Profile Lexium motionStat	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:27 _h Modbus 6990 Profibus 6990 CIP 127.1.39
_ECATaddress [onF → [onF- EcRR	EtherCAT address Currently used EtherCAT slave address set by the master. Changed settings become active immediately.	- - 1 -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3045:7 _h Modbus 17678 Profibus 17678 CIP 169.1.7
_ECATslavestate [onF → [onF- Ec55	EtherCAT slave state 1 / Init / i n t: Init 2 / PreOp / PrOp: Pre-Operational 3 / Boot / boot: Bootstrap 4 / SafeOp / 5FaP: Safe-Operational 8 / Op / aP: Operational	- - 1 -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3045:2 _h Modbus 17668 Profibus 17668 CIP 169.1.2
_ERR_class	Error class (385) Value 0: Warning (no response) Value 1: Error (Quick Stop -> state 7) Value 2: Error (Quick Stop -> state 8, 9) Value 3: Fatal error (state 9, can be acknowledged) Value 4: Fatal error (state 9, cannot be acknowledged)	- 0 - 4	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:2 _h Modbus 15364 Profibus 15364 CIP 160.1.2
_ERR_DCbus	DC bus voltage at error time (386) In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:7 _h Modbus 15374 Profibus 15374 CIP 160.1.7

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_ERR_enable_cycles	Number of cycles of enabling the power stage at error time (387) Number of cycles of enabling the power stage from the time the power supply (control voltage) was switched on to the time the error occurred.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:5 _h Modbus 15370 Profibus 15370 CIP 160.1.5
_ERR_enable_time	Time between enabling of power stage and occurrence of the error (387)	s - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:6 _h Modbus 15372 Profibus 15372 CIP 160.1.6
_ERR_motor_I	Motor current at error time (386) In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:9 _h Modbus 15378 Profibus 15378 CIP 160.1.9
_ERR_motor_v	Motor velocity at error time (387)	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 303C:8 _h Modbus 15376 Profibus 15376 CIP 160.1.8
_ERR_number	Error number (386) Reading this parameter copies the entire error entry (error class, time of occurrence of error, ...) to an intermediate memory from which all elements of the error can then be read. In addition, the read pointer of the error memory is automatically set to the next error entry.	- 0 - 65535	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:1 _h Modbus 15362 Profibus 15362 CIP 160.1.1
_ERR_powerOn non Pulse	Number of power on cycles (386)	- 0 - 4294967295	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 303B:2 _h Modbus 15108 Profibus 15108 CIP 159.1.2
_ERR_qual	Error additional information (386) This entry contains additional information on the error, depending on the error number. Example: a parameter address	- 0 - 65535	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 303C:4 _h Modbus 15368 Profibus 15368 CIP 160.1.4
_ERR_temp_dev	Temperature of device at error time (386)	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 303C:B _h Modbus 15382 Profibus 15382 CIP 160.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_ERR_temp_ps	Temperature of power stage at error time (386)	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 303C:A _h Modbus 15380 Profibus 15380 CIP 160.1.10
_ERR_time	Error time (386) With reference to operating hours counter	s 0 - 536870911	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 303C:3 _h Modbus 15366 Profibus 15366 CIP 160.1.3
_ErrNumFbParSvc	Last error number of fieldbus parameter services Some fieldbus types only provide general error codes if a request for a parameter service is not successful. This parameter returns the vendor-specific error number of the last unsuccessful service. CANopen: SDO service EtherCAT: CoE SDO service EtherNet/IP: CIP explicit message service DeviceNet: CIP explicit message service Modbus TCP: FC3, FC16	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3040:43 _h Modbus 16518 Profibus 16518 CIP 164.1.67
_eSM_funct Non Stop	eSM function Active eSM function Value 0: Safe Torque Off (STO) Value 1: No motion monitoring active Value 2: Safe Operating Stop (SOS) Value 3: Safely Limited Speed (SLS) Value 4: Reserved Value 5: Safe Stop 1 (SS1) Value 6: Safe Stop 2 (SS2) Value 7: Safe Operating Stop (SOS) after error Value 8: Safely Limited Speed (SLS) in machine operating mode Automatic Mode If bit 15 of the value is set: GUARD_ACK was triggered	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304C:17 _h Modbus 19502 Profibus 19502 CIP 176.1.23
_eSM_LI_act	eSM digital inputs channel B Signal state: 0: 0 level 1: 1 level Bit assignments: Bit 0: /ESTOP_B Bit 1: GUARD_B Bit 3: SETUPMODE_B Bit 4: SETUPENABLE_B Bit 6: GUARD_ACK Bit 8: ESMSTART Bit 9: /INTERLOCK_IN	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304C:12 _h Modbus 19492 Profibus 19492 CIP 176.1.18

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_eSM_LI_mask	eSM digital inputs channel B mask Mask of active digital inputs 0: Digital input is not active 1: Digital input is active Bit coding: See digital inputs channel.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304C:13 _h Modbus 19494 Profibus 19494 CIP 176.1.19
_eSM_LO_act	eSM digital outputs channel B Signal state: 0: 0 level 1: 1 level Bit assignments: Bit 0: CCM24V_OUT_B Bit 1: Drive operating state 6 Operation Enabled (B) Bit 2: RELAY_OUT_B Bit 3: AUXOUT2 Bit 4: /INTERLOCK_OUT Bits 5 ... 15: Reserved	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304C:14 _h Modbus 19496 Profibus 19496 CIP 176.1.20
_eSM_state <i>non</i> <i>5n5t</i>	eSM state 0 / eSM module missing / n 55: eSM module missing 1 / Start / 5trt: Start 2 / Not Ready To Switch On / ndrY: Not Ready To Switch On 3 / Switch On Disabled / d 5: Switch On Disabled 4 / Ready To Switch On / rdy: Ready To Switch On 6 / Operation Enabled / run: Operation Enabled 7 / Quick Stop / 95tP: Quick Stop 8 / Fault Reaction Active / FLt: Fault Reaction Active 9 / Fault / FLt: Fault Status word of eSM state machine	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304C:16 _h Modbus 19500 Profibus 19500 CIP 176.1.22
_eSMVer	eSM revision Software Software revision: Bits 0 ... 7: Software evolution (dec) Bits 8 ... 15: Software minor revision (dec) Bits 16 ... 23: Software major revision (dec) Bits 24 ... 31: Reserved	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 304C:F _h Modbus 19486 Profibus 19486 CIP 176.1.15

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_EthFdrError	FDR last error code 0 / No error: No error 2 / Not compatible: Configuration not compatible with drive 3 / Server read error: Error reading file on server 4 / Server connection error: Unable to connect to server 12 / Server file missing: FDR file missing on server 13 / Copy to drive error: Error copying file from server to drive 14 / Invalid configuration: Current drive configuration is invalid	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:46 _h Modbus 17548 Profibus 17548 CIP 168.1.70
_EthFdrStatus	FDR status 0 / Not initialized: Not initialized 1 / Initialization: Initialization 2 / IP assignment: IP assignment 3 / Ready: Ready 4 / Operational: Operational 5 / Unconfigured: Unconfigured 6 / Irrecoverable: Irrecoverable	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:45 _h Modbus 17546 Profibus 17546 CIP 168.1.69
_EthIPFdr1	Current IP address FDR server, byte 1	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:3C _h Modbus 17528 Profibus 17528 CIP 168.1.60
_EthIPFdr2	Current IP address FDR server, byte 2	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:3D _h Modbus 17530 Profibus 17530 CIP 168.1.61
_EthIPFdr3	Current IP address FDR server, byte 3	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:3E _h Modbus 17532 Profibus 17532 CIP 168.1.62
_EthIPFdr4	Current IP address FDR server, byte 4	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:3F _h Modbus 17534 Profibus 17534 CIP 168.1.63
_EthIPgateAct1	Current IP address gateway, byte 1 Byte 1 (x.0.0.0) of the IP address of the gateway.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- -	CANopen 3044:1B _h Modbus 17462 Profibus 17462 CIP 168.1.27

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_EthIPgateAct2	Current IP address gateway, byte 2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:1C _h Modbus 17464 Profibus 17464 CIP 168.1.28
_EthIPgateAct3	Current IP address gateway, byte 3	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:1D _h Modbus 17466 Profibus 17466 CIP 168.1.29
_EthIPgateAct4	Current IP address gateway, byte 4	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:1E _h Modbus 17468 Profibus 17468 CIP 168.1.30
_EthIPmaskAct1	Current IP address subnet mask, byte 1 Byte 1 (x.0.0.0) of the IP address of the subnet mask.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:17 _h Modbus 17454 Profibus 17454 CIP 168.1.23
_EthIPmaskAct2	Current IP address subnet mask, byte 2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:18 _h Modbus 17456 Profibus 17456 CIP 168.1.24
_EthIPmaskAct3	Current IP address subnet mask, byte 3	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:19 _h Modbus 17458 Profibus 17458 CIP 168.1.25
_EthIPmaskAct4	Current IP address subnet mask, byte 4	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:1A _h Modbus 17460 Profibus 17460 CIP 168.1.26
_EthIPmoduleAct1 CONF → Conf- , PR1	Current IP address Ethernet module, byte 1 Byte 1 (x.0.0.0) of the IP address of the Ethernet module.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:13 _h Modbus 17446 Profibus 17446 CIP 168.1.19

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_EthIPmoduleAct 2 $\text{[onF} \rightarrow \text{[on-}$, PR2	Current IP address Ethernet module, byte 2	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:14 _h Modbus 17448 Profibus 17448 CIP 168.1.20
_EthIPmoduleAct 3 $\text{[onF} \rightarrow \text{[on-}$, PR3	Current IP address Ethernet module, byte 3	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:15 _h Modbus 17450 Profibus 17450 CIP 168.1.21
_EthIPmoduleAct 4 $\text{[onF} \rightarrow \text{[on-}$, PR4	Current IP address Ethernet module, byte 4	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:16 _h Modbus 17452 Profibus 17452 CIP 168.1.22
_EthMAC1	MAC address Ethernet module, byte 1	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:1F _h Modbus 17470 Profibus 17470 CIP 168.1.31
_EthMAC2	MAC address Ethernet module, byte 2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:20 _h Modbus 17472 Profibus 17472 CIP 168.1.32
_EthMAC3	MAC address Ethernet module, byte 3	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:21 _h Modbus 17474 Profibus 17474 CIP 168.1.33
_EthMAC4	MAC address Ethernet module, byte 4	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:22 _h Modbus 17476 Profibus 17476 CIP 168.1.34
_EthMAC5	MAC address Ethernet module, byte 5	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:23 _h Modbus 17478 Profibus 17478 CIP 168.1.35

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_EthMAC6	MAC address Ethernet module, byte 6	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3044:24 _h Modbus 17480 Profibus 17480 CIP 168.1.36
_EthStatColl	Collisions	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3044:65 _h Modbus 17610 Profibus 17610 CIP 168.1.101
_fwNoSlot1	Number of firmware slot 1 Example: PR0912.00 The value is provided as a decimal value: 91200. NOTE: If no module is installed, the value 0 is returned.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3002:17 _h Modbus 558 Profibus 558 CIP 102.1.23
_fwNoSlot2	Number of firmware slot 2 Example: PR0912.00 The value is provided as a decimal value: 91200. NOTE: If no module is installed, the value 0 is returned.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3002:1C _h Modbus 568 Profibus 568 CIP 102.1.28
_fwNoSlot3	Number of firmware slot 3 Example: PR0912.00 The value is provided as a decimal value: 91200. NOTE: If no module is installed, the value 0 is returned.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3002:21 _h Modbus 578 Profibus 578 CIP 102.1.33
_fwRevSlot1	Revision of firmware slot 1 The version format is XX.YY.ZZ. Part XX.YY is contained in parameter _prgVerCOM. Part ZZ is used for quality evolution and contained in this parameter. NOTE: If no module is installed, the value 0 is returned. Example: V01.23.45 The value is provided as a decimal value: 45	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3002:19 _h Modbus 562 Profibus 562 CIP 102.1.25
_fwRevSlot2	Revision of firmware slot 2 The version format is XX.YY.ZZ. Part XX.YY is contained in parameter _prgVerCOM. Part ZZ is used for quality evolution and contained in this parameter. NOTE: If no module is installed, the value 0 is returned. Example: V01.23.45 The value is provided as a decimal value: 45	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3002:1E _h Modbus 572 Profibus 572 CIP 102.1.30

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_fwRevSlot3	Revision of firmware slot 3 The version format is XX.YY.ZZ. Part XX.YY is contained in parameter _prgVerCOM. Part ZZ is used for quality evolution and contained in this parameter. NOTE: If no module is installed, the value 0 is returned. Example: V01.23.45 The value is provided as a decimal value: 45	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3002:23 _h Modbus 582 Profibus 582 CIP 102.1.35
_fwVersSlot1	Version of firmware slot 1 The version format is XX.YY.ZZ. Part XX.YY is contained in this parameter. Part ZZ is contained in parameter _prgRevCOM. NOTE: If no module is installed, the value 0 is returned. Example: V01.23.45 The value is provided as a decimal value: 123	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3002:18 _h Modbus 560 Profibus 560 CIP 102.1.24
_fwVersSlot2	Version of firmware slot 2 The version format is XX.YY.ZZ. Part XX.YY is contained in this parameter. Part ZZ is contained in parameter _prgRevCOM. NOTE: If no module is installed, the value 0 is returned. Example: V01.23.45 The value is provided as a decimal value: 123	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3002:1D _h Modbus 570 Profibus 570 CIP 102.1.29
_fwVersSlot3	Version of firmware slot 3 The version format is XX.YY.ZZ. Part XX.YY is contained in this parameter. Part ZZ is contained in parameter _prgRevCOM. NOTE: If no module is installed, the value 0 is returned. Example: V01.23.45 The value is provided as a decimal value: 123	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3002:22 _h Modbus 580 Profibus 580 CIP 102.1.34
HMdisREftoIDX usr	Distance from switching point to index pulse (259) It allows to check the distance between the index pulse and the switching point and serves as a criterion for determining whether the reference movement with index pulse can be reproduced. Available as of firmware version V01.03	usr_p -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/- - -	CANopen 3028:F _h Modbus 10270 Profibus 10270 CIP 140.1.15

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_HMdisREFtoIDX	Distance from switching point to index pulse (259) It allows to check the distance between the index pulse and the switching point and serves as a criterion for determining whether the reference movement with index pulse can be reproduced. The parameter _HMdisREFtoIDX_usr allows you to enter the value in user-defined units. In increments of 0.0001 revolution.	revolution - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 3028:C _h Modbus 10264 Profibus 10264 CIP 140.1.12
_I_act I _{act} I _{act}	Total motor current In increments of 0.01 A _{rms} .	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:3 _h Modbus 7686 Profibus 7686 CIP 130.1.3
_Id_act_rms	Actual motor current (d component, field weakening) In increments of 0.01 A _{rms} .	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:2 _h Modbus 7684 Profibus 7684 CIP 130.1.2
_Id_ref_rms	Reference motor current (d component, field weakening) In increments of 0.01 A _{rms} .	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:11 _h Modbus 7714 Profibus 7714 CIP 130.1.17
_Imax_act	Currently effective current limitation Value of the currently effective current limitation. This is one of the following values (whichever is lowest): This is one of the following values (whichever is lowest): - CTRL_I_max (only during normal operation) - LIM_I_maxQSTP (only during Quick Stop) - LIM_I_maxHalt (only during Halt) - Current limitation via digital input - M_I_max (only if motor is connected) - PA_I_max Limitations caused by I2t monitoring are also taken into account. In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:28 _h Modbus 7248 Profibus 7248 CIP 128.1.40
_Imax_system	Current limitation of the system This parameter specifies the maximum system current. This is the lower value of the maximum motor current and the maximum power stage current. If no motor is connected, only the maximum power stage current is considered in this parameter. In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:27 _h Modbus 7246 Profibus 7246 CIP 128.1.39

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_Inc_ENC2Raw	Actual raw increment value of encoder 2 This parameter is only needed for commissioning of encoder 2 in case of an unknown machine encoder resolution.	Enclnc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:25 _h Modbus 7754 Profibus 7754 CIP 130.1.37
_InvalidParam	Modbus address of parameter with invalid value In case of a configuration error, the Modbus address of the parameter with an invalid value is indicated here.	- - 0 -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:6 _h Modbus 7180 Profibus 7180 CIP 128.1.6
_IO_act	Physical status of the digital inputs and outputs (157) Low byte: Bit 0: DI0 Bit 1: DI1 Bit 2: DI2 Bit 3: DI3 Bit 4: DI4 Bit 5: DI5 High byte: Bit 8: DQ0 Bit 9: DQ1 Bit 10: DQ2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3008:1 _h Modbus 2050 Profibus 2050 CIP 108.1.1
_IO_DI_act fion di fio	Status of digital inputs (157) Bit assignments: Bit 0: DI0 Bit 1: DI1 Bit 2: DI2 Bit 3: DI3 Bit 4: DI4 Bit 5: DI5	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3008:F _h Modbus 2078 Profibus 2078 CIP 108.1.15
_IO_DQ_act fion do fio	Status of digital outputs (157) Bit assignments: Bit 0: DQ0 Bit 1: DQ1 Bit 2: DQ2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3008:10 _h Modbus 2080 Profibus 2080 CIP 108.1.16
_IO_STO_act fion Sto	Status of the inputs for the safety function STO (157) Coding of the individual signals: Bit 0: STO_A Bit 1: STO_B	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3008:26 _h Modbus 2124 Profibus 2124 CIP 108.1.38

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_IOdataMtoS01	I/O parameter data Master to Slave - parameter 01 Actual data of the cyclic communication between the master and slave. This parameter contains the data of the first parameter mapped from the master to the slave. The parameters _IOdataMtoS02 to _IOdataMtoS16 contain the data of the remaining mapped parameters.	- 0 FFFFh -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3040:1 _h Modbus 16386 Profibus 16386 CIP 164.1.1
_IOdataStoM01	I/O parameter data Slave to Master - parameter 01 Actual data of the cyclic communication between the master and slave. This parameter contains the data of the first parameter mapped from the slave to the master. The parameters _IOdataStoM02 to _IOdataStoM16 contain the data of the remaining mapped parameters.	- 0 FFFFh -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3040:21 _h Modbus 16450 Profibus 16450 CIP 164.1.33
_IOM1_AI11_act P00 P011	IOM1 Value of input voltage of AI11 Available as of software version V01.06.00.	mV -10000 - 10000	INT16 INT16 INT16 INT16 R/- - -	CANopen 304F:1 _h Modbus 20226 Profibus 20226 CIP 179.1.1
_IOM1_AI12_act P00 P012	IOM1 Value of input voltage of AI12 Available as of software version V01.06.00.	mV -10000 - 10000	INT16 INT16 INT16 INT16 R/- - -	CANopen 304F:5 _h Modbus 20234 Profibus 20234 CIP 179.1.5
_IOM1_AO11_ref P00 P011	IOM1 Value of AO11 Unit depends on setting in parameter IOM1_AO_mode. If setting is 'Voltage': Unit: mV If setting is 'Current': Unit: µA Available as of software version V01.06.00.	- -10000 - 20000	INT16 INT16 INT16 INT16 R/- - -	CANopen 304F:27 _h Modbus 20302 Profibus 20302 CIP 179.1.39
_IOM1_AO12_ref P00 P012	IOM1 Value of AO12 Unit depends on setting in parameter IOM1_AO_mode. If setting is 'Voltage': Unit: mV If setting is 'Current': Unit: µA Available as of software version V01.06.00.	- -10000 - 20000	INT16 INT16 INT16 INT16 R/- - -	CANopen 304F:31 _h Modbus 20322 Profibus 20322 CIP 179.1.49

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
<code>_IOM1_DI_act</code> <i>flon</i> <i>di IH</i>	IOM1 Status of digital inputs Bit assignments: Bit 0: DI10 Bit 1: DI11 Bit 2: DI12 Bit 3: DI13 Available as of software version V01.06.00.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304F:35 _h Modbus 20330 Profibus 20330 CIP 179.1.53
<code>_IOM1_DQ_act</code> <i>flon</i> <i>do IH</i>	IOM1 Status of digital outputs Bit assignments: Bit 0: DQ10 Bit 1: DQ11 Available as of software version V01.06.00.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 304F:36 _h Modbus 20332 Profibus 20332 CIP 179.1.54
<code>_IOmappingMtoS01</code>	I/O parameter mapping Master to Slave - parameter 01 Actual mapping of the cyclic communication between the master and slave. This parameter contains the mapping of the first parameter mapped from the master to the slave. The parameters <code>_IOmappingMtoS02</code> to <code>_IOmappingMtoS16</code> contain the mapping of the remaining mapped parameters.	- 0 FFFFh -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3040:11 _h Modbus 16418 Profibus 16418 CIP 164.1.17
<code>_IOmappingStoM01</code>	I/O parameter mapping Slave to Master - parameter 01 Actual mapping of the cyclic communication between the master and slave. This parameter contains the mapping of the first parameter mapped from the slave to the master. The parameters <code>_IOmappingStoM02</code> to <code>_IOmappingStoM16</code> contain the mapping of the remaining mapped parameters.	- 0 FFFFh -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3040:31 _h Modbus 16482 Profibus 16482 CIP 164.1.49
<code>_Iq_act_rms</code> <i>flon</i> <i>qRct</i>	Actual motor current (q component, generating torque) In increments of 0.01 A _{rms} .	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:1 _h Modbus 7682 Profibus 7682 CIP 130.1.1
<code>_Iq_ref_rms</code> <i>flon</i> <i>qREF</i>	Reference motor current (q component, generating torque) In increments of 0.01 A _{rms} .	A _{rms} - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:10 _h Modbus 7712 Profibus 7712 CIP 130.1.16
<code>_LastError_Qual</code>	Additional info of last error This parameter contains additional information on the last error, depending on the error number. For example: a parameter address.	- 0 -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:1F _h Modbus 7230 Profibus 7230 CIP 128.1.31

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_LastError Pon LFLt	Error causing a stop (error classes 1 to 4) Number of the current error. Any consecutive errors do not overwrite this error number. Example: If a limit switch error reaction caused an overvoltage error, this parameter would contain the number of the limit switch error. Exception: Errors of error class 4 overwrite existing entries.	- - 0 -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 603F:0 _h Modbus 7178 Profibus 7178 CIP 128.1.5
_LastWarning Pon Lurn	Number of last warning (error class 0) Number of the most recent warning. If the warning becomes inactive again, the number is memorized until the next fault reset. Value 0: No warning occurred	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:9 _h Modbus 7186 Profibus 7186 CIP 128.1.9
_M_BRK_T_apply	Holding brake application time	ms - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:21 _h Modbus 3394 Profibus 3394 CIP 113.1.33
_M_BRK_T_release	Holding brake release time	ms - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:22 _h Modbus 3396 Profibus 3396 CIP 113.1.34
_M_Encoder ConF → rnf- SEnS	Encoder type of motor 1 / SinCos With HiFa / SLuH : SinCos with Hiperface 2 / SinCos Without HiFa / SLuH : SinCos without Hiperface 3 / SinCos With Hall / SLuH : SinCos with Hall 4 / SinCos With EnDat / SLuE : SinCos with EnDat 5 / EnDat Without SinCos / EndR : EnDat without SinCos 6 / Resolver / rE5a : Resolver 7 / Hall / hALL : Hall (not supported yet) 8 / BISS / b, 55 : BISS High byte: Value 0: Rotary encoder Value 1: Linear encoder	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:3 _h Modbus 3334 Profibus 3334 CIP 113.1.3
_M_HoldingBrake	Holding brake identification Value 0: Motor without holding brake Value 1: Motor with holding brake	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:20 _h Modbus 3392 Profibus 3392 CIP 113.1.32

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_M_I_0	Continuous stall current of motor In increments of 0.01 A_{rms} .	A_{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:13 _h Modbus 3366 Profibus 3366 CIP 113.1.19
_M_I_max [onF → , nF - n, nR	Maximum current of motor In increments of 0.01 A_{rms} .	A_{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:6 _h Modbus 3340 Profibus 3340 CIP 113.1.6
_M_I_nom [onF → , nF - n, nO	Nominal current of motor In increments of 0.01 A_{rms} .	A_{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:7 _h Modbus 3342 Profibus 3342 CIP 113.1.7
_M_I2t	Maximum permissible time for maximum current of motor	ms - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:11 _h Modbus 3362 Profibus 3362 CIP 113.1.17
_M_Jrot	Moment of inertia of motor Units: Rotary motors: $kgcm^2$ Linear motors: kg In increments of 0.001 motor _f .	motor _f - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 300D:C _h Modbus 3352 Profibus 3352 CIP 113.1.12
_M_kE	Voltage constant kE of motor Voltage constant in V_{rms} at 1000 min^{-1} . Units: Rotary motors: V_{rms}/min^{-1} Linear motors: $V_{rms}/(\text{m/s})$ In increments of 0.1 motor _u .	motor _u - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 300D:B _h Modbus 3350 Profibus 3350 CIP 113.1.11
_M_L_d	Inductance d component of motor In increments of 0.01 mH.	mH - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:F _h Modbus 3358 Profibus 3358 CIP 113.1.15
_M_L_q	Inductance q component of motor In increments of 0.01 mH.	mH - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:E _h Modbus 3356 Profibus 3356 CIP 113.1.14

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_M_load I_{don} I_{dFN}	Current load of motor (373)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:1A _h Modbus 7220 Profibus 7220 CIP 128.1.26
_M_M_0	Continuous stall torque of motor A value of 100 % in operating mode Profile Torque corresponds to this parameter. Units: Rotary motors: Ncm Linear motors: N	motor_m - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:16 _h Modbus 3372 Profibus 3372 CIP 113.1.22
_M_M_max	Maximum torque of motor In increments of 0.1 Nm.	Nm - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:9 _h Modbus 3346 Profibus 3346 CIP 113.1.9
_M_M_nom	Nominal torque/force of motor Units: Rotary motors: Ncm Linear motors: N	motor_m - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:8 _h Modbus 3344 Profibus 3344 CIP 113.1.8
_M_maxoverload	Maximum value of overload of motor (374) Maximum overload of motor during the last 10 seconds.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:1B _h Modbus 7222 Profibus 7222 CIP 128.1.27
_M_n_max $I_{donF} \rightarrow I_{nF}$ I_{nFR}	Maximum permissible speed of rotation/ velocity of motor Units: Rotary motors: min ⁻¹ Linear motors: mm/s	motor_v - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:4 _h Modbus 3336 Profibus 3336 CIP 113.1.4
_M_n_nom	Nominal speed of rotation/velocity of motor Units: Rotary motors: min ⁻¹ Linear motors: mm/s	motor_v - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:5 _h Modbus 3338 Profibus 3338 CIP 113.1.5
_M_overload	Current overload of motor (I _{2t}) (374)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:19 _h Modbus 7218 Profibus 7218 CIP 128.1.25

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_M_Polepair	Number of pole pairs of motor	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:14 _h Modbus 3368 Profibus 3368 CIP 113.1.20
_M_PolePairPitch	Pole pair pitch of motor In increments of 0.01 mm.	mm - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:23 _h Modbus 3398 Profibus 3398 CIP 113.1.35
_M_R_UV	Winding resistance of motor In increments of 0.01 Ω.	Ω - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:D _h Modbus 3354 Profibus 3354 CIP 113.1.13
_M_T_current	Current motor temperature (372) No meaningful indication possible for switching temperature sensors (see parameter M_TempType for temperature sensor type)	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:11 _h Modbus 7202 Profibus 7202 CIP 128.1.17
_M_T_max	Maximum temperature of motor (372)	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 300D:10 _h Modbus 3360 Profibus 3360 CIP 113.1.16
_M_Type [onF → , nF- nE yP	Motor type Value 0: No motor selected Value >0: Connected motor type	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 300D:2 _h Modbus 3332 Profibus 3332 CIP 113.1.2
_M_U_max	Maximum voltage of motor In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:19 _h Modbus 3378 Profibus 3378 CIP 113.1.25
_M_U_nom	Nominal voltage of motor In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300D:A _h Modbus 3348 Profibus 3348 CIP 113.1.10

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_ManuSdoAbort	CANopen Manufacturer-specific SDO Abort Code Provides more detailed information on a general SDO Abort Code (0800 0000).	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3041:A _h Modbus 16660 Profibus 16660 CIP 165.1.10
_ModeError	Error code for synchronous errors (ME bit) Drive Profile Lexium: Manufacturer-specific error code that caused the ModeError bit to be set. Usually, this is an error that was caused by the activation of an operating mode. The ModeError bit relates to MT-dependent parameters.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:19 _h Modbus 6962 Profibus 6962 CIP 127.1.25
_ModeErrorInfo	Additional error information of a ModeError (ME bit) Drive Profile Lexium: Indicates the parameter of the mapping that caused the ME bit to be set. The ME bit is set if MT-dependent parameters of the current mapping cause an error in connection with a write command. Example: 1 = 1st mapped parameter 2 = 2nd mapped parameter etc.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301B:1C _h Modbus 6968 Profibus 6968 CIP 127.1.28
_MSM_avail_ds	Number of available data sets Number of data sets that are available. Changed settings become active immediately.	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 302D:F _h Modbus 11550 Profibus 11550 CIP 145.1.15
_MSMactNum	Current data set number Value -1: Operating mode is inactive or no data set is triggered Values 0 ... 31: Number of the current data set Changed settings become active immediately.	- -1 -1 127	INT16 INT16 INT16 INT16 R/- - -	CANopen 302D:6 _h Modbus 11532 Profibus 11532 CIP 145.1.6
_MSMnextNum	Next data set to be triggered Value -1: Operating mode is inactive or no data set is selected Values 0 ... 31: Number of the next data set Changed settings become active immediately.	- -1 -1 127	INT16 INT16 INT16 INT16 R/- - -	CANopen 302D:7 _h Modbus 11534 Profibus 11534 CIP 145.1.7
_n_act_ENC1	Actual speed of rotation of encoder 1	min ⁻¹ - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:28 _h Modbus 7760 Profibus 7760 CIP 130.1.40

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_n_act_ENC2	Actual speed of rotation of encoder 2 (module)	min ⁻¹ - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:1E _h Modbus 7740 Profibus 7740 CIP 130.1.30
_n_act flon nRct	Actual speed of rotation	min ⁻¹ - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:8 _h Modbus 7696 Profibus 7696 CIP 130.1.8
_n_ref flon nrEF	Reference speed of rotation	min ⁻¹ - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:7 _h Modbus 7694 Profibus 7694 CIP 130.1.7
_OFSp_act	Actual offset position	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 3027:C _h Modbus 10008 Profibus 10008 CIP 139.1.12
_OpHours flon oPh	Operating hours counter	s - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:A _h Modbus 7188 Profibus 7188 CIP 128.1.10
_p_absENC	Absolute position with reference to the encoder range (165) This value corresponds to the modulo position of the absolute encoder range. The value is no longer valid if the gear ratio of machine encoder and motor encoder is changed. A restart is required in such a case.	usr_p - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301E:F _h Modbus 7710 Profibus 7710 CIP 130.1.15
_p_absmodulo	Absolute position with reference to internal resolution in internal units This value is based on encoder raw position with reference to internal resolution (131072 Inc).	Inc - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301E:E _h Modbus 7708 Profibus 7708 CIP 130.1.14
_p_act_ENC1_int	Actual position of encoder 1 in internal units	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:26 _h Modbus 7756 Profibus 7756 CIP 130.1.38

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_p_act_ENC2_int	Actual position of encoder 2 (module) in internal units	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:19 _h Modbus 7730 Profibus 7730 CIP 130.1.25
_p_act_ENC1	Actual position of encoder 1	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:27 _h Modbus 7758 Profibus 7758 CIP 130.1.39
_p_act_ENC2	Actual position of encoder 2 (module)	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:1A _h Modbus 7732 Profibus 7732 CIP 130.1.26
_p_act_int	Actual position in internal units NOTE: The actual position is not valid until the absolute position of the encoder at the specified interface has been determined. In the case of invalid absolute encoder position: _WarnLatched _WarnActive Bit 13: Absolute motor position not yet captured	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 6063:0 _h Modbus 7700 Profibus 7700 CIP 130.1.10
_p_act	Actual position NOTE: The actual position is not valid until the absolute position of the encoder at the specified interface has been determined. In the case of invalid absolute encoder position: _WarnLatched _WarnActive Bit 13: Absolute motor position not yet captured	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 6064:0 _h Modbus 7706 Profibus 7706 CIP 130.1.13
_p_addGEAR	Initial position electronic gear When Electronic Gear is inactive, the reference position for the position controller can be determined here. This position is set when Electronic Gear is activated with the selection of 'Synchronization with compensation movement'.	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:3 _h Modbus 7942 Profibus 7942 CIP 131.1.3
_p_dif_load_peak_usr	Maximum value of the load-dependent position deviation (350) This parameter contains the maximum load-dependent position deviation reached so far. A write access resets this value. Available as of firmware version V01.03 Changed settings become active immediately.	usr_p 0 - 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 301E:15 _h Modbus 7722 Profibus 7722 CIP 130.1.21

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_p_dif_load_peak	<p>Maximum value of the load-dependent position deviation (350)</p> <p>This parameter contains the maximum load-dependent position deviation reached so far. A write access resets this value.</p> <p>The parameter _p_dif_load_peak_usr allows you to enter the value in user-defined units..</p> <p>In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	<p>revolution</p> <p>0.0000</p> <p>-</p> <p>429496.7295</p>	<p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>UINT32</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 301E:1B_h</p> <p>Modbus 7734</p> <p>Profibus 7734</p> <p>CIP 130.1.27</p>
_p_dif_load_usr	<p>Current load-dependent position deviation between reference and actual position (349)</p> <p>The load-dependent position deviation is the difference between the reference position and the actual position caused by the load. This value is used for following error monitoring.</p> <p>Available as of firmware version V01.03</p>	<p>usr_p</p> <p>-2147483648</p> <p>-</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/-</p> <p>-</p> <p>-</p>	<p>CANopen 301E:16_h</p> <p>Modbus 7724</p> <p>Profibus 7724</p> <p>CIP 130.1.22</p>
_p_dif_load	<p>Current load-dependent position deviation between reference and actual position (349)</p> <p>The load-dependent position deviation is the difference between the reference position and the actual position caused by the load. This value is used for following error monitoring.</p> <p>The parameter _p_dif_load_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p>	<p>revolution</p> <p>-214748.3648</p> <p>-</p> <p>214748.3647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/-</p> <p>-</p> <p>-</p>	<p>CANopen 301E:1C_h</p> <p>Modbus 7736</p> <p>Profibus 7736</p> <p>CIP 130.1.28</p>
_p_dif_usr	<p>Current position deviation including dynamic position deviation</p> <p>Position deviation is the difference between reference position and actual position. The current position deviation consists of the load-dependent position deviation and the dynamic position deviation.</p> <p>Available as of firmware version V01.03</p>	<p>usr_p</p> <p>-2147483648</p> <p>-</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/-</p> <p>-</p> <p>-</p>	<p>CANopen 301E:14_h</p> <p>Modbus 7720</p> <p>Profibus 7720</p> <p>CIP 130.1.20</p>
_p_dif	<p>Current position deviation including dynamic position deviation</p> <p>Position deviation is the difference between reference position and actual position. The current position deviation consists of the load-dependent position deviation and the dynamic position deviation.</p> <p>The parameter _p_dif_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p>	<p>revolution</p> <p>-214748.3648</p> <p>-</p> <p>214748.3647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/-</p> <p>-</p> <p>-</p>	<p>CANopen 60F4:0_h</p> <p>Modbus 7716</p> <p>Profibus 7716</p> <p>CIP 130.1.18</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_p_DifENC1toENC2	Current deviation of encoder positions	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:18 _h Modbus 7728 Profibus 7728 CIP 130.1.24
_p_PTI_act	Actual position at PTI interface Counted position increments at position interface PTI.	Inc -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/- - -	CANopen 3008:5 _h Modbus 2058 Profibus 2058 CIP 108.1.5
_p_ref_int	Reference position in internal units Value corresponds to the reference position of the position controller.	Inc - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:9 _h Modbus 7698 Profibus 7698 CIP 130.1.9
_p_ref	Reference position Value corresponds to the reference position of the position controller.	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:C _h Modbus 7704 Profibus 7704 CIP 130.1.12
_PAR_ScalingError	Additional information on error during recalculation Coding: Bits 0 ... 15: Address of the parameter that caused the error Bits 16 ... 31: Number of the data set in the operating mode Motion Sequence that caused the error Changed settings become active immediately.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3004:16 _h Modbus 1068 Profibus 1068 CIP 104.1.22
_PAR_ScalingState	Status of recalculation of the parameters with user-defined units 0 / Recalculation active: Recalculation active 1 / reserved (1): reserved (1) 2 / Recalculation finished - no error: Recalculation finished, no error 3 / Error during recalculation: Error during recalculation 4 / Initialization successful: Initialization successful 5 / reserved (5): reserved (5) 6 / reserved (6): reserved (6) 7 / reserved (7): reserved (7) Status of recalculation of the parameters with user-defined units which are recalculated with a changed scaling factor. Changed settings become active immediately.	- 0 2 7	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3004:15 _h Modbus 1066 Profibus 1066 CIP 104.1.21

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_PBbaud [onF → , nF- Pbbd	Profibus baud rate 0 / None / none : No connection 28 / 9.6 kBaud / 96 : 9.6 kBaud 32 / 19.2 kBaud / 192 : 19.2 kBaud 42 / 93.75 kBaud / 937 : 93.75 kBaud 54 / 187.5 kBaud / 187 : 187.5 kBaud 68 / 500 kBaud / 500 : 500 kBaud 80 / 1500 kBaud / 1500 : 1500 kBaud 82 / 3000 kBaud / 3000 : 3000 kBaud 83 / 6000 kBaud / 6000 : 6000 kBaud 88 / 12000 kBaud / 1200 : 12000 kBaud	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3043:4 _h Modbus 17160 Profibus 17160 CIP 167.1.4
_PBprofile [onF → , nF- PbPr	Profibus drive profile 0 / None / none : No connection 1 / Profidrive Telegram 1 / Pd_1 : Profidrive standard telegram 1 (not yet supported) 2 / Profidrive Telegram 2 / Pd_2 : Profidrive standard telegram 2 (not yet supported) 7 / Profidrive Telegram 7 / Pd_7 : Profidrive standard telegram 7 (not yet supported) 9 / Profidrive Telegram 9 / Pd_9 : Profidrive standard telegram 9 (not yet supported) 103 / Profidrive Manufact / Pd_11 : Profidrive manufacturer-specific (not yet supported) 104 / Drive Profile Lexium 1 / dPL_1 : Drive Profile Lexium telegram 1 (library) 105 / Drive Profile Lexium 2 / dPL_2 : Drive Profile Lexium telegram 2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3043:3 _h Modbus 17158 Profibus 17158 CIP 167.1.3
_PosRegStatus	Status of the position register channels (358) Signal state: 0: Comparison criterion not met 1: Comparison criterion met Bit assignments: Bit 0: State of position register channel 1 Bit 1: State of position register channel 2	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 300B:1 _h Modbus 2818 Profibus 2818 CIP 111.1.1
_Power_act	Current output power	W - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:D _h Modbus 7194 Profibus 7194 CIP 128.1.13
_Power_mean	Mean output power	W - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:E _h Modbus 7196 Profibus 7196 CIP 128.1.14
_pref_acc	Acceleration of reference value for profile generator Sign according to the changed speed value: Increased speed: Positive sign Reduced speed: Negative sign	usr_a - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:9 _h Modbus 7954 Profibus 7954 CIP 131.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_pref_v	Velocity of reference value for profile generator	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:7 _h Modbus 7950 Profibus 7950 CIP 131.1.7
_prgNoDEV [onF →, nF- Prn	Firmware program number Example: PR0912.00 The value is provided as a decimal value: 91200	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 3001:1 _h Modbus 258 Profibus 258 CIP 101.1.1
_prgRevDEV [onF →, nF- Prv	Firmware revision number The version format is XX.YY.ZZ. Part XX.YY is contained in parameter _prgVerDEV. Part ZZ is used for quality evolution and contained in this parameter. Example: V01.23.45 The value is provided as a decimal value: 45	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3001:4 _h Modbus 264 Profibus 264 CIP 101.1.4
_prgVerDEV [onF →, nF- Prv	Firmware version number The version format is XX.YY.ZZ. Part XX.YY is contained in this parameter. Part ZZ is contained in parameter _prgRevDEV. Example: V01.23.45 The value is provided as a decimal value: 123	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3001:2 _h Modbus 260 Profibus 260 CIP 101.1.2
_PS_I_max [onF →, nF- Pi, nR	Maximum current of power stage In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:2 _h Modbus 4100 Profibus 4100 CIP 116.1.2
_PS_I_nom [onF →, nF- Pi, no	Nominal current of power stage In increments of 0.01 A _{rms} .	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:1 _h Modbus 4098 Profibus 4098 CIP 116.1.1
_PS_load nlon LdFP	Current load of power stage (373)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:17 _h Modbus 7214 Profibus 7214 CIP 128.1.23

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_PS_maxoverload	Maximum value of overload of power stage (374) Maximum overload of power stage during the last 10 seconds.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:18 _h Modbus 7216 Profibus 7216 CIP 128.1.24
_PS_overload_cte	Current overload of power stage (chip temperature)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:22 _h Modbus 7236 Profibus 7236 CIP 128.1.34
_PS_overload_I2t	Current overload of power stage (I2t)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:16 _h Modbus 7212 Profibus 7212 CIP 128.1.22
_PS_overload_psq	Current overload of power stage (power squared)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:23 _h Modbus 7238 Profibus 7238 CIP 128.1.35
_PS_overload	Current overload of power stage (374)	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:24 _h Modbus 7240 Profibus 7240 CIP 128.1.36
_PS_T_current flon tPS	Current power stage temperature (372)	°C - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:10 _h Modbus 7200 Profibus 7200 CIP 128.1.16
_PS_T_max	Maximum power stage temperature (372)	°C - - -	INT16 INT16 INT16 INT16 R/- per. -	CANopen 3010:7 _h Modbus 4110 Profibus 4110 CIP 116.1.7
_PS_T_warn	Temperature warning threshold of power stage (372)	°C - - -	INT16 INT16 INT16 INT16 R/- per. -	CANopen 3010:6 _h Modbus 4108 Profibus 4108 CIP 116.1.6

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_PS_U_maxDC	Maximum permissible DC bus voltage In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:3 _h Modbus 4102 Profibus 4102 CIP 116.1.3
_PS_U_minDC	Minimum permissible DC bus voltage In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:4 _h Modbus 4104 Profibus 4104 CIP 116.1.4
_PS_U_minStopDC	DC bus voltage low threshold for Quick Stop If this threshold is reached, the drive performs a Quick Stop. In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:A _h Modbus 4116 Profibus 4116 CIP 116.1.10
_PT_max_val	Maximum possible value for operating mode Profile Torque 100.0 % correspond to the continuous stall torque _M_M_0. In increments of 0.1 %.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:1E _h Modbus 7228 Profibus 7228 CIP 128.1.30
_RAMP_p_act	Actual position of profile generator	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:2 _h Modbus 7940 Profibus 7940 CIP 131.1.2
_RAMP_p_target	Target position of profile generator Absolute position value of the profile generator, calculated on the basis of the relative and absolute position values received.	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:1 _h Modbus 7938 Profibus 7938 CIP 131.1.1
_RAMP_v_act	Actual velocity of profile generator	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 606B:0 _h Modbus 7948 Profibus 7948 CIP 131.1.6
_RAMP_v_target	Target velocity of profile generator	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:5 _h Modbus 7946 Profibus 7946 CIP 131.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_RES_load <i>flon</i> <i>LdFb</i>	Current load of braking resistor (373) Monitoring of internal and external braking resistor depending on parameter RESint_ext.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:14 _h Modbus 7208 Profibus 7208 CIP 128.1.20
_RES_maxoverload	Maximum value of overload of braking resistor (374) Maximum overload of braking resistor during the last 10 seconds.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:15 _h Modbus 7210 Profibus 7210 CIP 128.1.21
_RES_overload	Current overload of braking resistor (I2t) (374) Monitoring of internal and external braking resistor depending on parameter RESint_ext.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301C:13 _h Modbus 7206 Profibus 7206 CIP 128.1.19
_RESint_P	Nominal power of internal braking resistor	W - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:9 _h Modbus 4114 Profibus 4114 CIP 116.1.9
_RESint_R	Resistance value of internal braking resistor In increments of 0.01 Ω.	Ω - - -	UINT16 UINT16 UINT16 UINT16 R/- per. -	CANopen 3010:8 _h Modbus 4112 Profibus 4112 CIP 116.1.8
_ScalePOSmax	Maximum user-defined value for positions This value depends on ScalePOSdenom and ScalePOSnum.	usr_p - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:A _h Modbus 7956 Profibus 7956 CIP 131.1.10
_ScaleRAMPmax	Maximum user-defined value for accelerations and decelerations This value depends on ScaleRAMPdenom and ScaleRAMPnum.	usr_a - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:C _h Modbus 7960 Profibus 7960 CIP 131.1.12
_ScaleVELmax	Maximum user-defined value for velocities This value depends on ScaleVELdenom and ScaleVELnum.	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301F:B _h Modbus 7958 Profibus 7958 CIP 131.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_SigActive	Current status of monitoring signals See _SigLatched for more details on the bit codes.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:7 _h Modbus 7182 Profibus 7182 CIP 128.1.7
_SigLatched non 5, 55	Saved status of monitoring signals (393) Signal state: 0: Not activated 1: Activated Bit assignments: Bit 0: General error Bit 1: Hardware limit switches (LIMP/LIMN/REF) Bit 2: Out of range (software limit switches, tuning) Bit 3: Quick Stop via fieldbus Bit 4: Error in active operating mode Bit 5: Commissioning interface (RS485) Bit 6: Integrated fieldbus Bit 7: Reserved Bit 8: Following error Bit 9: Reserved Bit 10: Inputs STO are 0 Bit 11: Inputs STO different Bit 12: Reserved Bit 13: DC bus voltage low Bit 14: DC bus voltage high Bit 15: Mains phase missing Bit 16: Integrated encoder interface Bit 17: Overtemperature motor Bit 18: Overtemperature power stage Bit 19: Reserved Bit 20: Memory card Bit 21: Optional fieldbus module Bit 22: Optional encoder module Bit 23: Optional safety module or I/O module Bit 24: Reserved Bit 25: Reserved Bit 26: Motor connection Bit 27: Motor overcurrent/short circuit Bit 28: Frequency of reference signal too high Bit 29: EEPROM error Bit 30: System start-up (hardware or parameter) Bit 31: System error (for example, watchdog, internal hardware interface) Monitoring functions are product-dependent.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:8 _h Modbus 7184 Profibus 7184 CIP 128.1.8

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_SuppDriveModes	Supported operating modes as per DSP402 Bit 0: Profile Position Bit 2: Profile Velocity Bit 3: Profile Torque Bit 5: Homing Bit 16: Jog Bit 17: Electronic Gear Bit 21: Manual Tuning Bit 23: Motion Sequence The availability of the individual bits is product-dependent.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 6502:0 _h Modbus 6952 Profibus 6952 CIP 127.1.20
_tq_act	Actual torque value 100.0 % correspond to the continuous stall torque _M_M_0. In increments of 0.1 %.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 6077:0 _h Modbus 7752 Profibus 7752 CIP 130.1.36
_Ud_ref	Reference motor voltage d component In increments of 0.1 V.	V - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:5 _h Modbus 7690 Profibus 7690 CIP 130.1.5
_UDC_act <i>U_{DC}</i> <i>U_{DC}A</i>	Voltage at DC bus In increments of 0.1 V.	V - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 301C:F _h Modbus 7198 Profibus 7198 CIP 128.1.15
_Udq_ref	Total motor voltage (vector sum d components and q components) Square root of (_Uq_ref ² + _Ud_ref ²) In increments of 0.1 V.	V - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:6 _h Modbus 7692 Profibus 7692 CIP 130.1.6
_Uq_ref	Reference motor voltage q component In increments of 0.1 V.	V - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:4 _h Modbus 7688 Profibus 7688 CIP 130.1.4
_v_act_ENC1	Actual velocity of encoder 1	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:29 _h Modbus 7762 Profibus 7762 CIP 130.1.41

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_v_act_ENC2	Actual velocity of encoder 2 (module)	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:23 _h Modbus 7750 Profibus 7750 CIP 130.1.35
_v_act Don URct	Actual velocity	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 606C:0 _h Modbus 7744 Profibus 7744 CIP 130.1.32
_v_PTI_act	Actual velocity at PTI interface Determined pulse frequency at position interface PTI.	Inc/s -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/- - -	CANopen 3008:6 _h Modbus 2060 Profibus 2060 CIP 108.1.6
_v_ref Don UrEF	Reference velocity	usr_v - - -	INT32 INT32 INT32 INT32 R/- - -	CANopen 301E:1F _h Modbus 7742 Profibus 7742 CIP 130.1.31
_Vmax_act	Currently effective velocity limitation Value of the currently effective velocity limitation. This is one of the following values (whichever is lowest): - CTRL_v_max - M_n_max (only if motor is connected) - Velocity limitation via digital input	usr_v - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:29 _h Modbus 7250 Profibus 7250 CIP 128.1.41
_VoltUtil Don udcr	Degree of utilization of DC bus voltage With a value of 100%, the drive operates at the voltage limit.	% - - -	INT16 INT16 INT16 INT16 R/- - -	CANopen 301E:13 _h Modbus 7718 Profibus 7718 CIP 130.1.19
_WarnActive	Active warnings, bit-coded See _WarnLatched for more details on the bit codes.	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:B _h Modbus 7190 Profibus 7190 CIP 128.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
_WarnLatched Warn Warn5	<p>Saved warnings, bit-coded (392)</p> <p>Saved warning bits are deleted in the case of a Fault Reset. Bits 10, 13 are deleted automatically.</p> <p>Signal state: 0: Not activated 1: Activated</p> <p>Bit assignments: Bit 0: General warning Bit 1: Reserved Bit 2: Out of range (SW limit switches, tuning) Bit 3: Reserved Bit 4: Active operating mode Bit 5: Commissioning interface (RS485) Bit 6: Integrated fieldbus Bit 7: Reserved Bit 8: Following warning limit reached Bit 9: Reserved Bit 10: Inputs STO_A and/or STO_B Bit 11: Reserved Bit 12: Reserved Bit 13: Low voltage DC bus or mains phase missing Bit 14: Reserved Bit 15: Reserved Bit 16: Integrated encoder interface Bit 17: Temperature of motor high Bit 18: Temperature of power stage high Bit 19: Reserved Bit 20: Memory card Bit 21: Optional fieldbus module Bit 22: Optional encoder module Bit 23: Optional safety module or I/O module Bit 24: Reserved Bit 25: Reserved Bit 26: Reserved Bit 27: Reserved Bit 28: Reserved Bit 29: Braking resistor overload (I^2t) Bit 30: Power stage overload (I^2t) Bit 31: Motor overload (I^2t)</p> <p>Monitoring functions are product-dependent.</p>	- - - -	UINT32 UINT32 UINT32 UINT32 R/- - -	CANopen 301C:C _h Modbus 7192 Profibus 7192 CIP 128.1.12
AbsHomeRequest	<p>Absolute positioning only after homing</p> <p>0 / No: No 1 / Yes: Yes</p> <p>This parameter has no function if the parameter 'PP_ModeRangeLim' is set to '1' which allows overtraveling of the movement range (ref_ok is set to 0 when the range is overtraveled).</p> <p>Changed settings become active immediately.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:16 _h Modbus 1580 Profibus 1580 CIP 106.1.22

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
AccessLock	<p>Locking other access channels (199)</p> <p>Value 0: Allow control via other access channels Value 1: Lock control via other access channels</p> <p>Example: The access channel is used by the fieldbus. In this case, control via the commissioning software or the HMI is not possible.</p> <p>The access channel can only be locked after the current operating mode has terminated.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3001:E _h Modbus 284 Profibus 284 CIP 101.1.14
AT_dir oP → t un- 5t, n	<p>Direction of movement for Autotuning (174)</p> <p>1 / Positive Negative Home / Pnh: Positive direction first, then negative direction with return to initial position 2 / Negative Positive Home / nPh: Negative direction first, then positive direction with return to initial position 3 / Positive Home / P-h: Positive direction only with return to initial position 4 / Positive / P--: Positive direction only without return to initial position 5 / Negative Home / n-h: Negative direction only with return to initial position 6 / Negative / n--: Negative direction only without return to initial position</p> <p>Changed settings become active the next time the motor moves.</p>	- 1 1 6	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302F:4 _h Modbus 12040 Profibus 12040 CIP 147.1.4
AT_dis_usr	<p>Movement range for Autotuning (174)</p> <p>Range within which the control parameters are automatically optimized. The range is entered with reference to the current position.</p> <p>NOTE: In the case of "Movement in one direction only" (Parameter AT_dir), the specified range is used for each optimization step. The actual movement typically corresponds to 20 times the value, but it is not limited.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active the next time the motor moves.</p>	usr_p 1 32768 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 302F:12 _h Modbus 12068 Profibus 12068 CIP 147.1.18

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
AT_dis	<p>Movement range for Autotuning (175)</p> <p>Range within which the control parameters are automatically optimized. The range is entered with reference to the current position.</p> <p>NOTE: In the case of "Movement in one direction only" (Parameter AT_dir), the specified range is used for each optimization step. The actual movement typically corresponds to 20 times the value, but it is not limited.</p> <p>The parameter AT_dis_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.1 revolution.</p> <p>Changed settings become active the next time the motor moves.</p>	revolution 1.0 2.0 999.9	UINT32 UINT32 UINT32 UINT32 R/W - -	CANopen 302F:3 _h Modbus 12038 Profibus 12038 CIP 147.1.3
AT_mechanical	<p>Type of coupling of the system (175)</p> <p>1 / Direct Coupling: Direct coupling 2 / Belt Axis: Belt axis 3 / Spindle Axis: Spindle axis</p> <p>Changed settings become active the next time the motor moves.</p>	- 1 2 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302F:E _h Modbus 12060 Profibus 12060 CIP 147.1.14
AT_n_ref	<p>Jump of speed of rotation for Autotuning</p> <p>The parameter AT_v_ref allows you to enter the value in user-defined units.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active the next time the motor moves.</p>	min ⁻¹ 10 100 1000	UINT32 UINT32 UINT32 UINT32 R/W - -	CANopen 302F:6 _h Modbus 12044 Profibus 12044 CIP 147.1.6
AT_start	<p>Autotuning start (175)</p> <p>Value 0: Terminate Value 1: Activate EasyTuning Value 2: Activate ComfortTuning</p> <p>Changed settings become active immediately.</p>	- 0 - 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302F:1 _h Modbus 12034 Profibus 12034 CIP 147.1.1
AT_v_ref	<p>Jump of velocity for Autotuning</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_v 1 100 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 302F:13 _h Modbus 12070 Profibus 12070 CIP 147.1.19
AT_wait	<p>Waiting time between Autotuning steps (178)</p> <p>Changed settings become active the next time the motor moves.</p>	ms 300 500 10000	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302F:9 _h Modbus 12050 Profibus 12050 CIP 147.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
BRK_AddT_apply	Additional time delay for applying the holding brake (161) The overall time delay for applying the holding brake is the time delay from the electronic nameplate of the motor and the additional time delay in this parameter. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	ms 0 0 1000	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3005:8 _h Modbus 1296 Profibus 1296 CIP 105.1.8
BRK_AddT_release	Additional time delay for releasing the holding brake (160) The overall time delay for releasing the holding brake is the time delay from the electronic nameplate of the motor and the additional time delay in this parameter. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	ms 0 0 400	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3005:7 _h Modbus 1294 Profibus 1294 CIP 105.1.7
CANaddress [onF → [onF- [onF → FSu- [oRd	CANopen address (node number) Changed settings become active the next time the product is switched on.	- 1 - 127	R/W per. -	
CANbaud [onF → [onF- [onF → FSu- [obd	CANopen baud rate 50 kBaud / 50: 50 kBaud 125 kBaud / 125: 125 kBaud 250 kBaud / 250: 250 kBaud 500 kBaud / 500: 500 kBaud 1 MBaud / 1000: 1 MBaud Changed settings become active the next time the product is switched on.	- 50 250 1000	R/W per. -	
CANpdo1Event	PDO 1 event mask Changes of values in the object trigger an event: Bit 0: First PDO object Bit 1: Second PDO object Bit 2: Third PDO object Bit 3: Fourth PDO object Changed settings become active immediately.	- 0 1 15	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3041:B _h Modbus 16662 Profibus 16662 CIP 165.1.11
CANpdo2Event	PDO 2 event mask Changes of values in the object trigger an event: Bit 0: First PDO object Bit 1: Second PDO object Bit 2: Third PDO object Bit 3: Fourth PDO object Changed settings become active immediately.	- 0 1 15	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3041:C _h Modbus 16664 Profibus 16664 CIP 165.1.12

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CANpdo3Event	PDO 3 event mask Changes of values in the object trigger an event: Bit 0: First PDO object Bit 1: Second PDO object Bit 2: Third PDO object Bit 3: Fourth PDO object Changed settings become active immediately.	- 0 1 15	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3041:D _h Modbus 16666 Profibus 16666 CIP 165.1.13
CANpdo4Event	PDO 4 event mask Changes of values in the object trigger an event: Bit 0: First PDO object Bit 1: Second PDO object Bit 2: Third PDO object Bit 3: Fourth PDO object Changed settings become active immediately.	- 0 15 15	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3041:E _h Modbus 16668 Profibus 16668 CIP 165.1.14
Cap1Activate	Capture input 1 start/stop (342) 0 / Capture Stop: Cancel capture function 1 / Capture Once: Start one-time capture 2 / Capture Continuous: Start continuous capture In the case of one-time capture, the function is terminated when the first value is captured. In the case of continuous capture, the function continues to run. Changed settings become active immediately.	- 0 - 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:4 _h Modbus 2568 Profibus 2568 CIP 110.1.4
Cap1Config	Capture input 1 configuration (344) 0 / Falling Edge: Position capture at falling edge 1 / Rising Edge: Position capture at rising edge Changed settings become active immediately.	- 0 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:2 _h Modbus 2564 Profibus 2564 CIP 110.1.2
Cap1Source	Capture input 1 encoder source (343) 0 / Pact Encoder 1: Source for capture input 1 is Pact of encoder 1 1 / Pact Encoder 2: Source for capture input 1 is Pact of encoder 2 (module) Changed settings become active immediately.	- 0 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:A _h Modbus 2580 Profibus 2580 CIP 110.1.10

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
Cap2Activate	<p>Capture input 2 start/stop (342)</p> <p>0 / Capture Stop: Cancel capture function 1 / Capture Once: Start one-time capture 2 / Capture Continuous: Start continuous capture</p> <p>In the case of one-time capture, the function is terminated when the first value is captured. In the case of continuous capture, the function continues to run.</p> <p>Changed settings become active immediately.</p>	- 0 - 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:5 _h Modbus 2570 Profibus 2570 CIP 110.1.5
Cap2Config	<p>Capture input 2 configuration (344)</p> <p>0 / Falling Edge: Position capture at falling edge 1 / Rising Edge: Position capture at rising edge</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:3 _h Modbus 2566 Profibus 2566 CIP 110.1.3
Cap2Source	<p>Capture input 2 encoder source (343)</p> <p>0 / Pact Encoder 1: Source for capture input 2 is Pact of encoder 1 1 / Pact Encoder 2: Source for capture input 2 is Pact of encoder 2 (module)</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:B _h Modbus 2582 Profibus 2582 CIP 110.1.11
Cap3Activate	<p>Capture input 3 start/stop (342)</p> <p>0 / Capture Stop: Cancel capture function 1 / Capture Once: Start one-time capture 2 / Capture Continuous: Start continuous capture</p> <p>In the case of one-time capture, the function is terminated when the first value is captured. In the case of continuous capture, the function continues to run.</p> <p>Available as of hardware version RS03.</p> <p>Changed settings become active immediately.</p>	- 0 - 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:12 _h Modbus 2596 Profibus 2596 CIP 110.1.18
Cap3Config	<p>Capture input 3 configuration (344)</p> <p>0 / Falling Edge: Position capture at falling edge 1 / Rising Edge: Position capture at rising edge</p> <p>Available as of hardware version RS03.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:11 _h Modbus 2594 Profibus 2594 CIP 110.1.17

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
Cap3Source	<p>Capture input 3 encoder source (343)</p> <p>0 / Pact Encoder 1: Source for capture input 3 is Pact of encoder 1</p> <p>1 / Pact Encoder 2: Source for capture input 3 is Pact of encoder 2 (module)</p> <p>Available as of hardware version RS03.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300A:15 _h Modbus 2602 Profibus 2602 CIP 110.1.21
CLSET_p_DiffWin_usr	<p>Position deviation for parameter set switching (318)</p> <p>If the position deviation of the position controller is less than the value of this parameter, the controller parameter set 2 is used. Otherwise, controller parameter set 1 is used.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor</p> <p>Changed settings become active immediately.</p>	usr_p 0 164 2147483647	INT32 INT32 INT32 R/W per. -	CANopen 3011:25 _h Modbus 4426 Profibus 4426 CIP 117.1.37
CLSET_p_DiffWin	<p>Position deviation for parameter set switching (319)</p> <p>If the position deviation of the position controller is less than the value of this parameter, the controller parameter set 2 is used. Otherwise, controller parameter set 1 is used.</p> <p>The parameter CLSET_p_DiffWin_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	revolution 0.0000 0.0100 2.0000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:1C _h Modbus 4408 Profibus 4408 CIP 117.1.28

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CLSET_ParSwiCond	<p>Condition for parameter set switching (318)</p> <p>0 / None Or Digital Input: None or digital input function selected</p> <p>1 / Inside Position Deviation: Inside position deviation (value definition in parameter CLSET_p_DiffWin)</p> <p>2 / Below Reference Velocity: Below reference velocity (value definition in parameter CLSET_v_Threshold)</p> <p>3 / Below Actual Velocity: Below actual velocity (value definition in parameter CLSET_v_Threshold)</p> <p>In the case of parameter set switching, the values of the following parameters are changed gradually:</p> <ul style="list-style-type: none"> - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAUref - CTRL_TAUiref - CTRL_KFPp <p>The following parameters are changed immediately after the time for parameter set switching (CTRL_ParChgTime):</p> <ul style="list-style-type: none"> - CTRL_Nf1damp - CTRL_Nf1freq - CTRL_Nf1bandw - CTRL_Nf2damp - CTRL_Nf2freq - CTRL_Nf2bandw - CTRL_Osupdamp - CTRL_Osupdelay - CTRL_Kfric <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:1A _h Modbus 4404 Profibus 4404 CIP 117.1.26
CLSET_v_Threshold	<p>Velocity threshold for parameter set switching (319)</p> <p>If the reference velocity or the actual velocity are less than the value of this parameter, the controller parameter set 2 is used. Otherwise, controller parameter set 1 is used.</p> <p>Changed settings become active immediately.</p>	usr_v 0 50 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3011:1D _h Modbus 4410 Profibus 4410 CIP 117.1.29
CLSET_winTime	<p>Time window for parameter set switching (319)</p> <p>Value 0: Window monitoring deactivated. Value >0: Window time for the parameters CLSET_v_Threshold and CLSET_p_DiffWin.</p> <p>Changed settings become active immediately.</p>	ms 0 0 1000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:1B _h Modbus 4406 Profibus 4406 CIP 117.1.27

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_GlobGain OP → Tun- GR, n	<p>Global gain factor (affects parameter set 1)</p> <p>The global gain factor affects the following parameters of controller parameter set 1:</p> <ul style="list-style-type: none"> - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAUref <p>The global gain factor is set to 100%</p> <ul style="list-style-type: none"> - if the controller parameters are set to default - at the end of the Autotuning process - if the controller parameter set 2 is copied to set 1 via the parameter CTRL_ParSetCopy <p>NOTE: If a full configuration is transmitted via the fieldbus, the value for CTRL_GlobGain must be transmitted prior to the values of the controller parameters CTRL_KPn, CTRL_TNn, CTRL_KPp and CTRL_TAUref. If CTRL_GlobGain is changed during a configuration transmission, CTRL_KPn, CTRL_TNn, CTRL_KPp and CTRL_TAUref must also be part of the configuration.</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p>	% 5.0 100.0 1000.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:15 _h Modbus 4394 Profibus 4394 CIP 117.1.21
CTRL_I_max_fw	<p>Maximum current for field weakening (d component)</p> <p>This value is only limited by the minimum/maximum parameter range (no limitation of this value by motor/power stage).</p> <p>The actual field weakening current is the minimum of CTRL_I_max_fw and one half of the lower value of the nominal current of the power stage and the motor.</p> <p>In increments of 0.01 A_{rms}.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	A _{rms} 0.00 0.00 300.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3011:F _h Modbus 4382 Profibus 4382 CIP 117.1.15

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_I_max [OnF → dr[- , PRH	<p>Current limitation (152)</p> <p>During operation, the actual current limit is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - CTRL_I_max - M_I_max - PA_I_max - Current limitation via digital input <p>Limitations caused by I2t monitoring are also taken into account.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	<p>A_{rms}</p> <p>0.00</p> <p>-</p> <p>300.00</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3011:C_h</p> <p>Modbus 4376</p> <p>Profibus 4376</p> <p>CIP 117.1.12</p>
CTRL_KFAcc	<p>Gain acceleration feed forward</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p>	<p>%</p> <p>0.0</p> <p>0.0</p> <p>350.0</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>expert</p>	<p>CANopen 3011:A_h</p> <p>Modbus 4372</p> <p>Profibus 4372</p> <p>CIP 117.1.10</p>
CTRL_ParChgTime	<p>Period of time for parameter switching (151)</p> <p>In the case of parameter set switching, the values of the following parameters are changed gradually:</p> <ul style="list-style-type: none"> - CTRL_KPn - CTRL_TNn - CTRL_KPp - CTRL_TAU_{nref} - CTRL_TAU_iref - CTRL_KFPp <p>Such a parameter switching can be caused by</p> <ul style="list-style-type: none"> - change of the active controller parameter set - change of the global gain - change of any of the parameters listed above - switching off the integral term of the velocity controller <p>Changed settings become active immediately.</p>	<p>ms</p> <p>0</p> <p>0</p> <p>2000</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3011:14_h</p> <p>Modbus 4392</p> <p>Profibus 4392</p> <p>CIP 117.1.20</p>
CTRL_ParSetCopy	<p>Controller parameter set copying (320)</p> <p>Value 1: Copy controller parameter set 1 to set 2</p> <p>Value 2: Copy controller parameter set 2 to set 1</p> <p>If parameter set 2 copied to parameter set 1, the parameter CTRL_GlobGain is set to 100%.</p> <p>Changed settings become active immediately.</p>	<p>-</p> <p>0.0</p> <p>-</p> <p>0.2</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>-</p> <p>-</p>	<p>CANopen 3011:16_h</p> <p>Modbus 4396</p> <p>Profibus 4396</p> <p>CIP 117.1.22</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_PwrUpParSet	Selection of controller parameter set at power up (315) 0 / Switching Condition: The switching condition is used for parameter set switching 1 / Parameter Set 1: Parameter set 1 is used 2 / Parameter Set 2: Parameter set 2 is used The selected value is also written to CTRL_ParSetSel (non-persistent). Changed settings become active immediately.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:18 _h Modbus 4400 Profibus 4400 CIP 117.1.24
CTRL_SelParSet	Selection of controller parameter set (non-persistent) (151) Coding see parameter: CTRL_PwrUpParSet Changed settings become active immediately.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3011:19 _h Modbus 4402 Profibus 4402 CIP 117.1.25
CTRL_SpdFric	Speed of rotation up to which the friction compensation is linear Changed settings become active immediately.	min ⁻¹ 0 5 20	UINT32 UINT32 UINT32 UINT32 R/W per. expert	CANopen 3011:9 _h Modbus 4370 Profibus 4370 CIP 117.1.9
CTRL_TAUnact	Filter time constant to smooth velocity of motor The default value is calculated on the basis of the motor data. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 - 30.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3011:8 _h Modbus 4368 Profibus 4368 CIP 117.1.8
CTRL_v_max [onF → dr] - nPRH	Velocity limitation (154) During operation, the actual velocity limit is one of the following values (whichever is lowest): - CTRL_v_max - M_n_max - Velocity limitation via digital input Changed settings become active immediately.	usr_v 1 13200 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3011:10 _h Modbus 4384 Profibus 4384 CIP 117.1.16

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL_VelObsActi v	<p>Activation of velocity observer</p> <p>0 / Velocity Observer Off: Velocity observer is off</p> <p>1 / Velocity Observer Passive: Velocity observer is on, but not used for motor control</p> <p>2 / Velocity Observer Active: Velocity observer is on and used for motor control</p> <p>Velocity observer control reduces velocity ripple and enhances controller bandwidth.</p> <p>NOTE: It is important to set the correct dynamics and inertia values before activation.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3011:22 _h Modbus 4420 Profibus 4420 CIP 117.1.34
CTRL_VelObsDyn	<p>Dynamics of velocity observer</p> <p>Dynamics of the velocity observer. This time constant should be much smaller than that of the velocity controller.</p> <p>In increments of 0.01 ms.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	ms 0.03 0.25 200.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3011:23 _h Modbus 4422 Profibus 4422 CIP 117.1.35
CTRL_VelObsInert t	<p>Inertia value for velocity observer</p> <p>System inertia that is used for velocity observer calculations.</p> <p>In the case of autotuning, the value of CTRL_SpdObsInert can be set equal to that of _AT_J.</p> <p>The default value of CTRL_SpdObsInert is the inertia of the mounted motor.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	g cm ² 1 - 2147483648	UINT32 UINT32 UINT32 UINT32 R/W per. expert	CANopen 3011:24 _h Modbus 4424 Profibus 4424 CIP 117.1.36
CTRL_vPIDDPart	<p>PID velocity controller: D gain</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p>	% 0.0 0.0 400.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3011:6 _h Modbus 4364 Profibus 4364 CIP 117.1.6
CTRL_vPIDDTime	<p>PID velocity controller: Time constant of D term smoothing filter</p> <p>In increments of 0.01 ms.</p> <p>Changed settings become active immediately.</p>	ms 0.01 0.25 10.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3011:5 _h Modbus 4362 Profibus 4362 CIP 117.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_KFPp [onF → dr[- FPP]	Velocity feed-forward (321) This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 200.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:6 _h Modbus 4620 Profibus 4620 CIP 118.1.6
CTRL1_Kfric	Friction compensation: Gain (323) In increments of 0.01 A _{rms} . Changed settings become active immediately.	A _{rms} 0.00 0.00 10.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:10 _h Modbus 4640 Profibus 4640 CIP 118.1.16
CTRL1_KPn [onF → dr[- Pn]	Velocity controller P gain (182) The default value is calculated on the basis of the motor parameters. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.0001 A/min ⁻¹ . Changed settings become active immediately.	A/min ⁻¹ 0.0001 - 1.2700	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:1 _h Modbus 4610 Profibus 4610 CIP 118.1.1
CTRL1_KPp [onF → dr[- PP]	Position controller P gain (188) The default value is calculated. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 1/s. Changed settings become active immediately.	1/s 2.0 - 900.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:3 _h Modbus 4614 Profibus 4614 CIP 118.1.3
CTRL1_Nf1bandw	Notch filter 1: Bandwidth (322) Definition of bandwidth: 1 - Fb/F0 In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:A _h Modbus 4628 Profibus 4628 CIP 118.1.10
CTRL1_Nf1damp	Notch filter 1: Damping (322) In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:8 _h Modbus 4624 Profibus 4624 CIP 118.1.8
CTRL1_Nf1freq	Notch filter 1: Frequency (322) The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:9 _h Modbus 4626 Profibus 4626 CIP 118.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_Nf2bandw	Notch filter 2: Bandwidth (322) Definition of bandwidth: $1 - F_b/F_0$ In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:D _h Modbus 4634 Profibus 4634 CIP 118.1.13
CTRL1_Nf2damp	Notch filter 2: Damping (322) In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:B _h Modbus 4630 Profibus 4630 CIP 118.1.11
CTRL1_Nf2freq	Notch filter 2: Frequency (322) The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:C _h Modbus 4632 Profibus 4632 CIP 118.1.12
CTRL1_Osupdamp	Overshoot suppression filter: Damping (322) The filter is switched off at a value of 0. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 50.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:E _h Modbus 4636 Profibus 4636 CIP 118.1.14
CTRL1_Osupdelay	Overshoot suppression filter: Time delay (322) The filter is switched off at a value of 0. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.00 75.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3012:F _h Modbus 4638 Profibus 4638 CIP 118.1.15
CTRL1_TAUiref	Filter time constant of the reference current value filter (186) This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.50 4.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:5 _h Modbus 4618 Profibus 4618 CIP 118.1.5
CTRL1_TAUiref [onF → dr[- tRu i	Filter time constant of the reference velocity value filter (184) This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 9.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:4 _h Modbus 4616 Profibus 4616 CIP 118.1.4

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL1_TNn [onF → drL - t, n l	Velocity controller integral action time (182) The default value is calculated on the basis of CTRL_TAUiref. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 - 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3012:2 _h Modbus 4612 Profibus 4612 CIP 118.1.2
CTRL2_KFPp [onF → drL - FPP2	Velocity feed-forward (324) This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 200.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:6 _h Modbus 4876 Profibus 4876 CIP 119.1.6
CTRL2_Kfric	Friction compensation: Gain (324) In increments of 0.01 A _{rms} . Changed settings become active immediately.	A _{rms} 0.00 0.00 10.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:10 _h Modbus 4896 Profibus 4896 CIP 119.1.16
CTRL2_KPn [onF → drL - Pn2	Velocity controller P gain (182) The default value is calculated on the basis of the motor parameters. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.0001 A/min ⁻¹ . Changed settings become active immediately.	A/min ⁻¹ 0.0001 - 1.2700	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:1 _h Modbus 4866 Profibus 4866 CIP 119.1.1
CTRL2_KPp [onF → drL - PP2	Position controller P gain (188) The default value is calculated. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.1 1/s. Changed settings become active immediately.	1/s 2.0 - 900.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:3 _h Modbus 4870 Profibus 4870 CIP 119.1.3
CTRL2_Nf1bandw	Notch filter 1: Bandwidth (324) Definition of bandwidth: 1 - Fb/F0 In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:A _h Modbus 4884 Profibus 4884 CIP 119.1.10
CTRL2_Nf1damp	Notch filter 1: Damping (324) In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:8 _h Modbus 4880 Profibus 4880 CIP 119.1.8

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL2_Nf1freq	Notch filter 1: Frequency (324) The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:9 _h Modbus 4882 Profibus 4882 CIP 119.1.9
CTRL2_Nf2bandw	Notch filter 2: Bandwidth (325) Definition of bandwidth: 1 - Fb/F0 In increments of 0.1 %. Changed settings become active immediately.	% 1.0 70.0 90.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:D _h Modbus 4890 Profibus 4890 CIP 119.1.13
CTRL2_Nf2damp	Notch filter 2: Damping (325) In increments of 0.1 %. Changed settings become active immediately.	% 55.0 90.0 99.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:B _h Modbus 4886 Profibus 4886 CIP 119.1.11
CTRL2_Nf2freq	Notch filter 2: Frequency (325) The filter is switched off at a value of 15000. In increments of 0.1 Hz. Changed settings become active immediately.	Hz 50.0 1500.0 1500.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:C _h Modbus 4888 Profibus 4888 CIP 119.1.12
CTRL2_Osupdamp	Overshoot suppression filter: Damping (325) The filter is switched off at a value of 0. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 0.0 50.0	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:E _h Modbus 4892 Profibus 4892 CIP 119.1.14
CTRL2_Osupdelay	Overshoot suppression filter: Time delay (325) The filter is switched off at a value of 0. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.00 75.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3013:F _h Modbus 4894 Profibus 4894 CIP 119.1.15
CTRL2_TAUiref	Filter time constant of the reference current value filter (186) This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 0.50 4.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:5 _h Modbus 4874 Profibus 4874 CIP 119.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
CTRL2_TAUref [onF → dr[- tRu2	Filter time constant of the reference velocity value filter (184) This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 9.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:4 _h Modbus 4872 Profibus 4872 CIP 119.1.4
CTRL2_TNn [onF → dr[- t, n2	Velocity controller integral action time (182) The default value is calculated on the basis of CTRL_TAUref. This parameter is switched gradually over the time defined in CTRL_ParChgTime. In increments of 0.01 ms. Changed settings become active immediately.	ms 0.00 - 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3013:2 _h Modbus 4868 Profibus 4868 CIP 119.1.2
DCbus_compat	DC bus compatibility LXM32 and ATV32 0 / No DC bus or LXM32 only: DC bus not used or only LXM32 connected via the DC bus 1 / DC bus with LXM32 and ATV32: LXM32 and ATV32 connected via the DC bus NOTE: Connecting LXM32 drives and ATV32 drives via the DC bus may change the technical data. Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:26 _h Modbus 1356 Profibus 1356 CIP 105.1.38
DCOMcontrol	DriveCom control word Refer to chapter Operation, Operating States, for bit coding information. Bit 0: Switch on Bit 1: Enable Voltage Bit 2: Quick Stop Bit 3: Enable Operation Bits 4 ... 6: Operating mode specific Bit 7: Fault Reset Bit 8: Halt Bit 9: Change on setpoint Bits 10 ... 15: Reserved (must be 0) Changed settings become active immediately.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 6040:0 _h Modbus 6914 Profibus 6914 CIP 127.1.1

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DCOMopmode	<p>Operating mode</p> <p>-6 / Manual Tuning / Autotuning: Manual Tuning or Autotuning</p> <p>-3 / Motion Sequence: Motion Sequence</p> <p>-2 / Electronic Gear: Electronic Gear</p> <p>-1 / Jog: Jog</p> <p>0 / Reserved: Reserved</p> <p>1 / Profile Position: Profile Position</p> <p>3 / Profile Velocity: Profile Velocity</p> <p>4 / Profile Torque: Profile Torque</p> <p>6 / Homing: Homing</p> <p>7 / Interpolated Position: Interpolated Position</p> <p>8 / Cyclic Synchronous Position: Cyclic Synchronous Position</p> <p>9 / Cyclic Synchronous Velocity: Cyclic Synchronous Velocity</p> <p>10 / Cyclic Synchronous Torque: Cyclic Synchronous Torque</p> <p>Changed settings become active immediately.</p>	- -6 - 10	INT8 INT16 INT16 INT16 R/W - -	CANopen 6060:0 _h Modbus 6918 Profibus 6918 CIP 127.1.3
DEVcmdinterf CONF → REG- nonE dEUE	<p>Specification of the control mode (200)</p> <p>1 / Local Control Mode / α: Local control mode</p> <p>2 / Fieldbus Control Mode / Fb5: Fieldbus control mode</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:1 _h Modbus 1282 Profibus 1282 CIP 105.1.1
DI_0_Debounce	<p>Debounce time of DI0</p> <p>0 / No: No software debouncing</p> <p>1 / 0.25 ms: 0.25 ms</p> <p>2 / 0.50 ms: 0.50 ms</p> <p>3 / 0.75 ms: 0.75 ms</p> <p>4 / 1.00 ms: 1.00 ms</p> <p>5 / 1.25 ms: 1.25 ms</p> <p>6 / 1.50 ms: 1.50 ms</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:20 _h Modbus 2112 Profibus 2112 CIP 108.1.32
DI_1_Debounce	<p>Debounce time of DI1</p> <p>0 / No: No software debouncing</p> <p>1 / 0.25 ms: 0.25 ms</p> <p>2 / 0.50 ms: 0.50 ms</p> <p>3 / 0.75 ms: 0.75 ms</p> <p>4 / 1.00 ms: 1.00 ms</p> <p>5 / 1.25 ms: 1.25 ms</p> <p>6 / 1.50 ms: 1.50 ms</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:21 _h Modbus 2114 Profibus 2114 CIP 108.1.33

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DI_2_Debounce	Debounce time of DI2 0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:22 _h Modbus 2116 Profibus 2116 CIP 108.1.34
DI_3_Debounce	Debounce time of DI3 0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:23 _h Modbus 2118 Profibus 2118 CIP 108.1.35
DI_4_Debounce	Debounce time of DI4 0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:24 _h Modbus 2120 Profibus 2120 CIP 108.1.36
DI_5_Debounce	Debounce time of DI5 0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:25 _h Modbus 2122 Profibus 2122 CIP 108.1.37

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DPL_Activate	<p>Activation of Drive Profile Lexium</p> <p>Value 0: Deactivate Drive Profile Lexium Value 1: Activate Drive Profile Lexium</p> <p>The access channel via which the drive profile has been activated is the only access channel that can use the drive profile.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 301B:8 _h Modbus 6928 Profibus 6928 CIP 127.1.8
DPL_dmControl	Drive Profile Lexium dmControl	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 301B:1F _h Modbus 6974 Profibus 6974 CIP 127.1.31
DPL_intLim	<p>Setting for bit 9 of _DPL_motionStat and _actionStatus</p> <p>0 / None: Not used (reserved) 1 / Current Below Threshold: Current threshold value 2 / Velocity Below Threshold: Velocity threshold value 3 / In Position Deviation Window: Position Deviation Window 4 / In Velocity Deviation Window: Velocity Deviation Window 5 / Position Register Channel 1: Position register channel 1 6 / Position Register Channel 2: Position register channel 2 7 / Position Register Channel 3: Position register channel 3 8 / Position Register Channel 4: Position register channel 4 9 / Hardware Limit Switch: Hardware limit switch 10 / RMAC active or finished: Relative movement after capture is active or finished 11 / Standstill Window: Standstill window</p> <p>Setting for bit 9 of the parameters _DPL_motionStat and _actionStatus</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.08.xx.</p>	- 0 11 11	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 301B:35 _h Modbus 7018 Profibus 7018 CIP 127.1.53
DPL_RefA16	Drive Profile Lexium RefA16	- - - -	INT16 INT16 INT16 INT16 R/W - -	CANopen 301B:22 _h Modbus 6980 Profibus 6980 CIP 127.1.34

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DPL_RefA32	Drive Profile Lexium RefA32	- - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 301B:20 _h Modbus 6976 Profibus 6976 CIP 127.1.32
DPL_RefB32	Drive Profile Lexium RefB32	- - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 301B:21 _h Modbus 6978 Profibus 6978 CIP 127.1.33
DS402compatib	<p>DS402 state machine: State transition from 3 to 4</p> <p>0 / Automatic: Automatic (state transition is performed automatically)</p> <p>1 / DS402-compliant: DS402-compliant (state transition must be controlled via the fieldbus)</p> <p>Determines the state transition between the states SwitchOnDisabled (3) and Ready-ToSwitchOn (4).</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 301B:13 _h Modbus 6950 Profibus 6950 CIP 127.1.19

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DS402intLim	<p>DS402 status word: Setting for bit 11 (internal limit)</p> <p>0 / None: Not used (reserved)</p> <p>1 / Current Below Threshold: Current threshold value</p> <p>2 / Velocity Below Threshold: Velocity threshold value</p> <p>3 / In Position Deviation Window: Position deviation window</p> <p>4 / In Velocity Deviation Window: Velocity deviation window</p> <p>5 / Position Register Channel 1: Position register channel 1</p> <p>6 / Position Register Channel 2: Position register channel 2</p> <p>7 / Position Register Channel 3: Position register channel 3</p> <p>8 / Position Register Channel 4: Position register channel 4</p> <p>9 / Hardware Limit Switch: Hardware limit switch</p> <p>10 / RMAC active or finished: Relative movement after capture is active or finished</p> <p>11 / Standstill Window: Standstill window</p> <p>Setting for:</p> <ul style="list-style-type: none"> - bit 11 of the parameter <code>_DCOMstatus</code> and - bit 10 of the parameters <code>_motionStat</code> and <code>_actionStatus</code> <p>Changed settings become active immediately.</p>	- 0 0 11	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 301B:1E _h Modbus 6972 Profibus 6972 CIP 127.1.30
DVNaddress <i>Conf → Conf- Conf → FSu- dnRd</i>	<p>DeviceNet node address (MAC ID)</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 63 63	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3042:1 _h Modbus 16898 Profibus 16898 CIP 166.1.1
DVNbaud <i>Conf → Conf- Conf → FSu- dnbd</i>	<p>DeviceNet baud rate</p> <p>0 / 125 kBaud / 125: 125 kBaud</p> <p>1 / 250 kBaud / 250: 250 kBaud</p> <p>2 / 500 kBaud / 500: 500 kBaud</p> <p>3 / Autobaud / Auto: Autobaud</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 3 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3042:2 _h Modbus 16900 Profibus 16900 CIP 166.1.2
DVNbuspower	<p>Monitoring of DeviceNet bus power supply</p> <p>0: Monitoring off</p> <p>1: Monitoring on</p> <p>Changed settings become active immediately.</p>	- 0 1 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 3042:3 _h Modbus 16902 Profibus 16902 CIP 166.1.3

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
DVNioDataIn	<p>DeviceNet I/O data input</p> <p>110 / Position Controller Profile: Position Controller Profile 111 / Standard Assembly: Standard assembly 112 / Extended Assembly: Extended assembly</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 110 110 112	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3042:4 _h Modbus 16904 Profibus 16904 CIP 166.1.4
DVNioDataOut	<p>DeviceNet I/O data output</p> <p>100 / Position Controller Profile: Position Controller Profile 101 / Standard Assembly: Standard assembly 102 / Extended Assembly: Extended assembly</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 100 100 102	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3042:5 _h Modbus 16906 Profibus 16906 CIP 166.1.5
ECAT2ndaddress [onF → [on]- Ec5R	<p>EtherCAT second address</p> <p>Second address for EtherCAT slave used for 'Hot Connect'. Value 0: 'Hot Connect' not used</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3045:6 _h Modbus 17676 Profibus 17676 CIP 169.1.6
ENC_abs_source	<p>Source for setting absolute encoder position</p> <p>0 / Encoder 1: Absolute position determined from encoder 1 1 / Encoder 2 (module): Absolute position determined from encoder 2 (module)</p> <p>This parameter defines the encoder source which is used to determine the base absolute position after power cycling. If this is set to Encoder 1, the absolute position from encoder 1 is read and copied to the system values of encoder 2.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:25 _h Modbus 1354 Profibus 1354 CIP 105.1.37

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENC_ModeOfMaEnc	<p>Selection of mode of machine encoder</p> <p>0 / None: Machine encoder is not used for motor control</p> <p>1 / Position Control: Machine encoder is used for position control</p> <p>2 / Velocity And Position Control: Machine encoder is used for velocity and position control</p> <p>NOTE: It is not possible to use the machine encoder for speed control and the motor encoder for position control.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3050:2 _h Modbus 20484 Profibus 20484 CIP 180.1.2
ENC1_adjustment	<p>Adjustment of absolute position of encoder 1 (166)</p> <p>The value range depends on the encoder type.</p> <p>Singleturn encoder: 0 ... max_pos_usr/rev. - 1</p> <p>Singleturn encoder (shifted with parameter ShiftEncWorkRang): -(max_pos_usr/rev)/2 ... (max_pos_usr/rev)/2 - 1</p> <p>Multiturn encoder: 0 ... (4096 * max_pos_usr/rev.) - 1</p> <p>Multiturn encoder (shifted with parameter ShiftEncWorkRang): -2048 * max_pos_usr/rev ... (2048 * max_pos_usr/rev.) - 1</p> <p>max_pos_usr/rev.: Maximum user-defined position for one encoder turn. This value is 16384 with the default scaling.</p> <p>NOTE: * If processing is to be performed with inversion of the direction of movement, this must be set before the encoder position is adjusted. * After the write access, a wait time of at least 1 second is required before the drive is switched off. * Changing this value also changes the position of the virtual index pulse and the index pulse for the encoder simulation.</p> <p>Changed settings become active the next time the product is switched on.</p>	usr_p - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 3005:16 _h Modbus 1324 Profibus 1324 CIP 105.1.22

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENC2_adjustment	<p>Adjustment of absolute position of encoder 2 (167)</p> <p>The value range depends on the encoder type at the physical port ENC2.</p> <p>ENC2_adjustment can only be changed if ENC_abs_source = Encoder 2.</p> <p>Singleturn encoder: 0 ... max_pos_usr/rev. - 1</p> <p>Singleturn encoder (shifted with parameter ShiftEncWorkRang): -(max_pos_usr/rev)/2 ... (max_pos_usr/rev.) / 2 - 1</p> <p>Multiturn encoder: 0 ... (revolutions * max_pos_usr/rev.) - 1</p> <p>Multiturn encoder (shifted with parameter ShiftEncWorkRang): -(revolutions * max_pos_usr/rev)/2 ... (revolutions * max_pos_usr/rev.) / 2 - 1</p> <p>max_pos_usr/rev.: Maximum user-defined position for one encoder turn. This value is 16384 with the default scaling.</p> <p>NOTE: * If processing is to be performed with inversion of the direction of movement, this must be set before the encoder position is adjusted. * After the write access, the parameter values has to be saved to the EEPROM and the drive has to be switched off, before the change becomes active. * Changing this value also changes the position of the virtual index pulse and the index pulse for the encoder simulation.</p> <p>Changed settings become active the next time the product is switched on.</p>	usr_p - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 3005:24 _h Modbus 1352 Profibus 1352 CIP 105.1.36

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENC2_type	<p>Type of encoder at encoder 2 (module)</p> <p>0 / none: Undefined</p> <p>1 / SinCos Hiperface (rotary): SinCos Hiperface (rotary)</p> <p>2 / SinCos 1Vpp (wake & shake - rotary): SinCos 1Vpp (wake & shake, rotary)</p> <p>3 / Sincos 1Vpp Hall (no wake & shake - rotary): SinCos 1Vpp Hall (no wake & shake, rotary)</p> <p>5 / EnDat 2.2 (rotary): EnDat 2.2 (rotary)</p> <p>6 / Resolver: Resolver</p> <p>8 / BISS: BISS</p> <p>9 / A/B/I (rot): A/B/I (rotary)</p> <p>10 / SSI (rot): SSI (rotary)</p> <p>257 / SinCos Hiperface (linear): SinCos Hiperface (linear)</p> <p>258 / SinCos 1Vpp (wake & shake - linear): SinCos 1Vpp (wake & shake, linear)</p> <p>259 / SinCos 1Vpp Hall (no wake & shake - linear): SinCos 1Vpp Hall (no wake & shake, linear)</p> <p>261 / EnDat 2.2 (linear): EnDat 2.2 (linear)</p> <p>265 / A/B/I (linear): A/B/I (linear)</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 265	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3050:3 _h Modbus 20486 Profibus 20486 CIP 180.1.3
ENC2_usage	<p>Type of usage of encoder 2 (module)</p> <p>0 / None: Undefined</p> <p>1 / Motor: Configured as motor encoder</p> <p>2 / Machine: Configured as machine encoder</p> <p>NOTE: If the parameter is set to "Motor", encoder 1 has no functionality.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3050:1 _h Modbus 20482 Profibus 20482 CIP 180.1.1
ENCAnaPowSupply	<p>Power supply encoder module ANA (analog interface)</p> <p>5 / 5V: 5 V supply voltage</p> <p>12 / 12V: 12 V supply voltage</p> <p>Power supply of the analog encoder only if the encoder is used as a machine encoder supplying 1Vpp encoder signals. This parameter is not used for Hiperface encoders. Hiperface encoders are supplied with 12 V.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 5 5 12	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3051:2 _h Modbus 20740 Profibus 20740 CIP 181.1.2

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENCDigABI- MaxFreq	<p>ABI maximum frequency</p> <p>The maximum possible ABI frequency is encoder-specific (specified by the encoder manufacturer). The encoder module DIG supports a maximum ABI frequency of 1 MHz (this is the default and maximum value of ENCDigABIMaxFreq). An ABI frequency of 1 MHz means that there are 4000000 encoder increments in 1 second.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	<p>kHz</p> <p>1</p> <p>1000</p> <p>1000</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3052:6_h</p> <p>Modbus 21004</p> <p>Profibus 21004</p> <p>CIP 182.1.6</p>
ENCDigABImaxIx	<p>ABI maximum distance for index pulse search</p> <p>In the case of a reference movement to the index pulse, ENCDigABImaxIx contains the maximum distance within which the index pulse must be found. If no physical index pulse is found over this range, an error message is generated.</p> <p>Example: A rotary ABI encoder with one index pulse per revolution is connected. The resolution of the encoder is 8000 encoder increments per revolution (this value can be determined using parameter _Inc_Enc2Raw. _Inc_Enc2Raw and ENCDigABImaxIx have the same scaling). The maximum distance necessary for a reference movement to the index pulse is one revolution. This means that ENCDigABImaxIx should be set to 8000. Internally, a tolerance of 10% is added. This means that during a reference movement to the index pulse, an index pulse must be found within 8800 encoder increments.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	<p>Enclnc</p> <p>1</p> <p>10000</p> <p>-</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3052:7_h</p> <p>Modbus 21006</p> <p>Profibus 21006</p> <p>CIP 182.1.7</p>
ENCDigBISSCoding	<p>Position coding of BISS encoder</p> <p>0 / binary: Binary coding 1 / gray: Gray coding</p> <p>This parameter defines the type of position coding of the BISS encoder.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	<p>-</p> <p>0</p> <p>0</p> <p>1</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3052:A_h</p> <p>Modbus 21012</p> <p>Profibus 21012</p> <p>CIP 182.1.10</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENCDigBISSRes-Mul	<p>BISS multiturn resolution</p> <p>This parameter is only relevant for BISS encoders (singleturn and multiturn). If a singleturn BISS encoder is used, ENCDigBISSResMult must be set to 0.</p> <p>Example: If ENCDigBISSResMult is set to 12, the number of turns of the encoder used must be $2^{12} = 4096$.</p> <p>The sum of ENCDigBISSResMult + ENCDigBISSResSgl must be less than or equal to 46 bits.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	bit 0 0 24	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:9 _h Modbus 21010 Profibus 21010 CIP 182.1.9
ENCDigBISSRes-Sgl	<p>BISS singleturn resolution</p> <p>This parameter is only relevant for BISS encoders (singleturn and multiturn).</p> <p>Example: If ENCDigBISSResSgl is set to 13, an BISS encoder with a singleturn resolution of $2^{13} = 8192$ increments must be used.</p> <p>If a multiturn encoder is used, the sum of ENCDigBISSResMult + ENCDigBISSResSgl must be less than or equal to 46 bits.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	bit 8 13 25	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:8 _h Modbus 21008 Profibus 21008 CIP 182.1.8
ENCDigPowSupply	<p>Power supply encoder module DIG (digital interface)</p> <p>5 / 5V: 5 V supply voltage 12 / 12V: 12 V supply voltage</p> <p>Power supply of the digital encoder.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 5 5 12	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:4 _h Modbus 21000 Profibus 21000 CIP 182.1.4
ENCDigResMulUsed	<p>Number of bits of the multiturn resolution used of the encoder</p> <p>Specifies the number of bits of the multiturn resolution used for position evaluation.</p> <p>If ENCDigResMulUsed = 0, all bits of the multiturn resolution of the encoder are used.</p> <p>Example: If ENCDigResMulUsed = 11, only 11 bits of the multiturn resolution of the encoder are used.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	bit 0 0 24	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:B _h Modbus 21014 Profibus 21014 CIP 182.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENCDigSSICoding	<p>Position coding of SSI encoder</p> <p>0 / binary: Binary coding 1 / gray: Gray coding</p> <p>This parameter defines the type of position coding of the SSI encoder.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:3 _h Modbus 20998 Profibus 20998 CIP 182.1.3
ENCDigSSI- MaxFreq	<p>SSI maximum transfer frequency</p> <p>This parameter is only relevant for SSI encoders (singleturn and multiturn). The maximum possible SSI transfer frequency is encoder-specific (specified by encoder manufacturer). The value of ENCDigSSIMaxFreq and the possible SSI transfer frequencies of the encoder module are used to configure an optimum SSI transfer frequency (the encoder module supports 0.2 MHz and 1 MHz transfer frequencies). Example: The encoder has a maximum transfer frequency of 400 kHz. ENCDigSSI-MaxFreq is set to 400. Internally, the transfer frequency is set to 200 kHz.</p> <p>If the encoder cable is very long, ENCDigSSIMaxFreq may have to be reduced. In this case, the response time of the drive is slightly reduced. The higher the transfer frequency, the lower the lag time in the control loop.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	kHz 200 200 1000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:5 _h Modbus 21002 Profibus 21002 CIP 182.1.5
ENCDigSSIRes- Mult	<p>SSI multiturn resolution</p> <p>This parameter is only relevant for SSI encoders (singleturn and multiturn). If a singleturn SSI encoder is used, ENCDigSSIResMult must be set to 0.</p> <p>Example: If ENCDigSSIResMult is set to 12, the number of turns of the encoder used must be $2^{12} = 4096$.</p> <p>The sum of ENCDigSSIResMult + ENCDigSSIResSgl must be less than or equal to 32 bits.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	bit 0 0 24	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:2 _h Modbus 20996 Profibus 20996 CIP 182.1.2

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ENCDigSSIResSgl	SSI singleturn resolution This parameter is only relevant for SSI encoders (singleturn and multiturn). Example: If ENCDigSSIResSgl is set to 13, an SSI encoder with a singleturn resolution of $2^{13} = 8192$ increments must be used. If a multiturn encoder is used, the sum of ENCDigSSIResMult + ENCDigSSIResSgl must be less than or equal to 32 bits. Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	bit 8 13 25	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3052:1 _h Modbus 20994 Profibus 20994 CIP 182.1.1
ENCSinCosMaxIx	Maximum distance for search for index pulse for SinCos encoder The parameter specifies the maximum number of periods during which the index pulse must be found (search range). A tolerance of 10 % is added to this value. If no index pulse is found within this range (including the 10% tolerance), an error message is generated. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 1 1024 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3051:4 _h Modbus 20744 Profibus 20744 CIP 181.1.4
ERR_clear	Clear error memory (385) Value 1: Delete all entries in the error memory The clearing process is completed if a 0 is returned after a read access. Changed settings become active immediately.	- 0 - 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 303B:4 _h Modbus 15112 Profibus 15112 CIP 159.1.4
ERR_reset	Reset error memory read pointer (385) Value 1: Set error memory read pointer to oldest error entry. Changed settings become active immediately.	- 0 - 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 303B:5 _h Modbus 15114 Profibus 15114 CIP 159.1.5
ErrorResp_bit_DE	Error response to data error (DE bit) -1 / No Error Response: No error response 0 / Warning: Warning 1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3 For the Drive Profile Lexium, the error response to data error (DE bit) can be parameterized. For EtherCAT RxPDO data error handling, this parameter is also used to classify the error response.	- -1 -1 3	INT16 INT16 INT16 INT16 R/W per. -	CANopen 301B:6 _h Modbus 6924 Profibus 6924 CIP 127.1.6

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ErrorResp_bit_ME	<p>Error response to mode error (ME bit)</p> <p>-1 / No Error Response: No error response 0 / Warning: Warning 1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3</p> <p>For Drive Profile Lexium, the error response for an mode error (ME bit) can be parameterized.</p>	- -1 -1 3	INT16 INT16 INT16 INT16 R/W per. -	CANopen 301B:7 _h Modbus 6926 Profibus 6926 CIP 127.1.7
ErrorResp_Flt_AC	<p>Error response to missing mains phase (376)</p> <p>1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 1 2 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:A _h Modbus 1300 Profibus 1300 CIP 105.1.10
ErrorResp_I2tRES	<p>Error response to 100% I2t braking resistor</p> <p>0 / Warning: Warning (error class 0) 1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:22 _h Modbus 1348 Profibus 1348 CIP 105.1.34
ErrorResp_p_diff	<p>Error response to following error (351)</p> <p>1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 1 3 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:B _h Modbus 1302 Profibus 1302 CIP 105.1.11
ESIM_scale [onF →, -o- E55C	<p>Resolution of encoder simulation (291)</p> <p>Resolution defines the number of increments per revolution (AB signal with quadruple evaluation).</p> <p>The index pulse is created once per revolution at an interval where signal A and signal B are high.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	Enclnc 8 4096 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:15 _h Modbus 1322 Profibus 1322 CIP 105.1.21

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
eSM_BaseSetting	eSM basic settings None: No function Auto Start: Automatic start (ESMSTART) Ignore GUARD_ACK: GUARD_ACK inactive Ignore INTERLOCK_IN: INTERLOCK chain inactive Setting can only be changed if power stage is disabled.	- - - -	R/W per. -	
eSM_dec_NC	eSM deceleration ramp Deceleration ramp for monitored deceleration Value 0: Disabled, no monitoring of deceleration ramp Value >0: Deceleration ramp in min ⁻¹ /s Setting can only be changed if power stage is disabled.	min ⁻¹ /s 0 0 32786009	R/W per. -	
eSM_dec_Qstop	eSM deceleration ramp for Quick Stop Deceleration ramp for monitored Quick Stop. This value must be greater than 0. Value 0: eSM module is not configured Value >0: Deceleration ramp in min ⁻¹ /s Setting can only be changed if power stage is disabled.	min ⁻¹ /s 0 0 32786009	R/W per. -	
eSM_disable	eSM disable Value 0: No action Value 1: Force a change of eSM state 6 to eSM state 3 Setting can only be changed if power stage is disabled.	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 304C:1A _h Modbus 19508 Profibus 19508 CIP 176.1.26

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
eSM_FuncAUXOUT1	<p>eSM function of status output AUXOUT1</p> <p>None: No function</p> <p>/ESTOP: Signal state /ESTOP</p> <p>GUARD: Signal state GUARD</p> <p>SETUPMODE: Signal state SETUPMODE</p> <p>SETUPENABLE: Signal state SETUPENABLE</p> <p>GUARD_ACK: Signal state GUARD_ACK</p> <p>/INTERLOCK_IN: Signal state /INTERLOCK_IN</p> <p>STO by eSM: Signal state of internal STO</p> <p>RELAY: Signal state RELAY</p> <p>/INTERLOCK_OUT: Signal state /INTERLOCK_OUT</p> <p>Standstill: Standstill (v = 0)</p> <p>SLS: SLS</p> <p>Error class 4: Error of error class 4 occurred</p> <p>Error class 1 ... 4: Error of error classes 1 ... 4 occurred</p> <p>/ESTOP inv.: Signal state /ESTOP, inverted</p> <p>GUARD inv.: Signal state GUARD, inverted</p> <p>SETUPMODE inv.: Signal state SETUPMODE, inverted</p> <p>SETUPENABLE inv.: Signal state SETUPENABLE, inverted</p> <p>GUARD_ACK inv.: Signal state GUARD_ACK, inverted</p> <p>/INTERLOCK_IN inv.: Signal state /INTERLOCK_IN, inverted</p> <p>STO by eSM inv.: Signal state of internal STO, inverted</p> <p>RELAY inv.: Signal state RELAY, inverted</p> <p>/INTERLOCK_OUT inv.: Signal state /INTERLOCK_OUT, inverted</p> <p>Standstill inv.: Standstill, inverted</p> <p>SLS inv.: SLS, inverted</p> <p>Error class 4 inv.: Error of error class 4 occurred, inverted</p> <p>Error class 1 ... 4 inv.: Error of error classes 1 ... 4 occurred, inverted</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	R/W per. -	

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
eSM_FuncAUXOUT2	<p>eSM function of status output AUXOUT2</p> <p>None: No function /ESTOP: Signal state /ESTOP GUARD: Signal state GUARD SETUPMODE: Signal state SETUPMODE SETUPENABLE: Signal state SETUPENABLE GUARD_ACK: Signal state GUARD_ACK /INTERLOCK_IN: Signal state /INTERLOCK_IN STO by eSM: Signal state of internal STO RELAY: Signal state RELAY /INTERLOCK_OUT: Signal state /INTERLOCK_OUT Standstill: Standstill (v = 0) SLS: SLS Error class 4: Error of error class 4 occurred Error class 1 ... 4: Error of error classes 1 ... 4 occurred /ESTOP inv.: Signal state /ESTOP, inverted GUARD inv.: Signal state GUARD, inverted SETUPMODE inv.: Signal state SETUPMODE, inverted SETUPENABLE inv.: Signal state SETUPENABLE, inverted GUARD_ACK inv.: Signal state GUARD_ACK, inverted /INTERLOCK_IN inv.: Signal state /INTERLOCK_IN, inverted STO by eSM inv.: Signal state of internal STO, inverted RELAY inv.: Signal state RELAY, inverted /INTERLOCK_OUT inv.: Signal state /INTERLOCK_OUT, inverted Standstill inv.: Standstill, inverted SLS inv.: SLS, inverted Error class 4 inv.: Error of error class 4 occurred, inverted Error class 1 ... 4 inv.: Error of error classes 1 ... 4 occurred, inverted</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	R/W per. -	
eSM_LO_mask	<p>eSM digital outputs channel B mask</p> <p>Mask of active digital outputs</p> <p>0: Digital output is not active 1: Digital output is active</p> <p>Bit coding: See digital outputs channel.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 304C:15 _h Modbus 19498 Profibus 19498 CIP 176.1.21
eSM_t_NCDe1	<p>eSM delay time until start of monitored deceleration</p> <p>Delay time until monitoring of the deceleration ramp starts. This time can be adjusted to meet the requirements of a PLC.</p> <p>Setting can only be changed if power stage is disabled.</p>	ms 0 0 10000	R/W per. -	

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
eSM_t_Relay	eSM deactivation of output RELAY Deactivation of the digital output RELAY: Value 0: Immediate, no delay time Value 1: At motor standstill ($v = 0$) Value 2: At motor standstill ($v = 0$) and INTERLOCK_OUT = 1 Value >2: Delay time in ms, deactivation of output after this time has passed Setting can only be changed if power stage is disabled.	ms 0 0 10000	R/W per. -	
eSM_v_maxAuto	eSM maximum velocity for machine operating mode Automatic Mode This value defines the maximum velocity for machine operating mode Automatic Mode. Value 0: Maximum velocity inactive Value >0: Maximum velocity Setting can only be changed if power stage is disabled.	min^{-1} 0 0 8000	R/W per. -	
eSM_v_maxSetup	eSM maximum velocity for machine operating mode Setup Mode This value defines the maximum velocity for machine operating mode Setup Mode. Setting can only be changed if power stage is disabled.	min^{-1} 0 0 8000	R/W per. -	
EthErrorMgt	FDR error management 0 / Off: FDR problem does not trigger an error 1 / On: FDR problem triggers an error Specifies the response to a missing or invalid FDR file. Changed settings become active immediately.	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:42 _h Modbus 17540 Profibus 17540 CIP 168.1.66
EthFdrAction	FDR action 0 / IDLE: No action 1 / SAVE: Save current configuration to server 2 / RESTORE: Restore configuration from server 3 / DELETE: Delete configuration on server Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3044:43 _h Modbus 17542 Profibus 17542 CIP 168.1.67
EthFdrEnable [onF → Conf- [onF → F5u- EFdr	FDR service 0 / Off / OFF: FDR service disabled 1 / On / on: FDR service enabled Enable Ethernet service "Fast Device Replacement" (FDR). If FDR is enabled, the DHCP server must support FDR, otherwise no IP address can be obtained via DHCP.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:40 _h Modbus 17536 Profibus 17536 CIP 168.1.64

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
EthFdrLocalCfg	FDR local configuration 0 / Server: Server configuration 1 / Local: Local configuration Specifies whether the drive configuration is downloaded from an FDR server or whether the local drive configuration is used. Changed settings become active immediately.	- 0 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:41 _h Modbus 17538 Profibus 17538 CIP 168.1.65
EthFdrTime	FDR autosave time Interval for periodic saving of the configuration to the FDR server. Value 0: No autosave Changed settings become active immediately.	minutes 0 10 9999	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:44 _h Modbus 17544 Profibus 17544 CIP 168.1.68
EthIPgate1 [onF] → [onF-], PG1	IP address gateway, byte 1 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:F _h Modbus 17438 Profibus 17438 CIP 168.1.15
EthIPgate2 [onF] → [onF-], PG2	IP address gateway, byte 2 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:10 _h Modbus 17440 Profibus 17440 CIP 168.1.16
EthIPgate3 [onF] → [onF-], PG3	IP address gateway, byte 3 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:11 _h Modbus 17442 Profibus 17442 CIP 168.1.17
EthIPgate4 [onF] → [onF-], PG4	IP address gateway, byte 4 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:12 _h Modbus 17444 Profibus 17444 CIP 168.1.18
EthIPmask1 [onF] → [onF- [onF] → FSu-], PN1	IP address subnet mask, byte 1 Changed settings become active the next time the product is switched on.	- 0 255 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:B _h Modbus 17430 Profibus 17430 CIP 168.1.11
EthIPmask2 [onF] → [onF- [onF] → FSu-], PN2	IP address subnet mask, byte 2 Changed settings become active the next time the product is switched on.	- 0 255 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:C _h Modbus 17432 Profibus 17432 CIP 168.1.12

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
EthIPmask3 [onF → [onF- [onF → F5u- , Pn3	IP address subnet mask, byte 3 Changed settings become active the next time the product is switched on.	- 0 255 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:D _h Modbus 17434 Profibus 17434 CIP 168.1.13
EthIPmask4 [onF → [onF- [onF → F5u- , Pn4	IP address subnet mask, byte 4 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:E _h Modbus 17436 Profibus 17436 CIP 168.1.14
EthIPmaster1	IP address master, byte 1 IP address of the master that is permitted to perform Modbus TCP I/O scanning. If set to 0.0.0.0 (default), any master can perform I/O scanning. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:29 _h Modbus 17490 Profibus 17490 CIP 168.1.41
EthIPmaster2	IP address master, byte 2 Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2A _h Modbus 17492 Profibus 17492 CIP 168.1.42
EthIPmaster3	IP address master, byte 3 Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2B _h Modbus 17494 Profibus 17494 CIP 168.1.43
EthIPmaster4	IP address master, byte 4 Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2C _h Modbus 17496 Profibus 17496 CIP 168.1.44
EthIpMode [onF → [onF- [onF → F5u- , Pnd	Type of obtaining IP address 0 / Manual / Pn_{nu} : Manual 1 / BOOTP / boot : BOOTP 2 / DHCP / dhcP : DHCP When selecting DHCP, also set the parameter EthFdrEnable to ON or OFF, depending on whether or not your DHCP server supports FDR. Changed settings become active immediately.	- 0 0 2 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:5 _h Modbus 17418 Profibus 17418 CIP 168.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
EthIPmodule1 [onF] → [on]- [onF] → FSU- Pc1	IP address Ethernet module, byte 1 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:7 _h Modbus 17422 Profibus 17422 CIP 168.1.7
EthIPmodule2 [onF] → [on]- [onF] → FSU- Pc2	IP address Ethernet module, byte 2 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:8 _h Modbus 17424 Profibus 17424 CIP 168.1.8
EthIPmodule3 [onF] → [on]- [onF] → FSU- Pc3	IP address Ethernet module, byte 3 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:9 _h Modbus 17426 Profibus 17426 CIP 168.1.9
EthIPmodule4 [onF] → [on]- [onF] → FSU- Pc4	IP address Ethernet module, byte 4 Changed settings become active the next time the product is switched on.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:A _h Modbus 17428 Profibus 17428 CIP 168.1.10
EthMbIPswap1	IP address of master for Modbus word swap, byte 1 IP address of a Modbus master device. For this master, the word order is swapped to "Low word first", instead of the default "High word first". High word first -> Modicon Quantum Low word first -> Premium, HMI (Schneider Electric) Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:50 _h Modbus 17568 Profibus 17568 CIP 168.1.80
EthMbIPswap2	IP address of master for Modbus word swap, byte 2 Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:51 _h Modbus 17570 Profibus 17570 CIP 168.1.81
EthMbIPswap3	IP address of master for Modbus word swap, byte 3 Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:52 _h Modbus 17572 Profibus 17572 CIP 168.1.82

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
EthMbIPswap4	IP address of master for Modbus word swap, byte 4 Changed settings become active immediately.	- 0 0 255	UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:53 _h Modbus 17574 Profibus 17574 CIP 168.1.83
EthMbScanner	Modbus TCP I/O scanning 0 / Off: Modbus TCP I/O scanning off 1 / On: Modbus TCP I/O scanning on I/O scanning only works if the parameter EthMode is set to Modbus TCP. Changed settings become active immediately.	- 0 1 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:28 _h Modbus 17488 Profibus 17488 CIP 168.1.40
EthMbScanTime-out	Modbus TCP I/O scanning timeout Communication monitoring timeout for Modbus TCP. Value 0: Timeout monitoring disabled In increments of 0.1 s. Changed settings become active immediately.	s 0.0 2.0 60.0	UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2D _h Modbus 17498 Profibus 17498 CIP 168.1.45
EthMode [onF] → [on]- Etd	Protocol 0 / Modbus TCP / RCP: Modbus TCP I/O scanning is enabled 1 / EtherNet/IP / EtP: EtherNet/IP communication is enabled NOTE: Modbus TCP parameter access is possible irrespective of the selected setting. Changed settings become active the next time the product is switched on.	- 0 1 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:1 _h Modbus 17410 Profibus 17410 CIP 168.1.1
EthOptMapInp1	Optionally mapped input parameter 1 (drive to PLC) Modbus address of parameter which is optionally mapped to Ethernet/IP assembly or Modbus TCP I/O scanner data (drive to PLC). Changed settings become active immediately.	- - 0 -	UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:34 _h Modbus 17512 Profibus 17512 CIP 168.1.52
EthOptMapInp2	Optionally mapped input parameter 2 (drive to PLC) Modbus address of parameter which is optionally mapped to Ethernet/IP assembly or Modbus TCP I/O scanner data (drive to PLC). Changed settings become active immediately.	- - 0 -	UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:35 _h Modbus 17514 Profibus 17514 CIP 168.1.53

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
EthOptMapInp3	Optionally mapped input parameter 3 (drive to PLC) Modbus address of parameter which is optionally mapped to Ethernet/IP assembly or Modbus TCP I/O scanner data (drive to PLC). Changed settings become active immediately.	- - 0 -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:36 _h Modbus 17516 Profibus 17516 CIP 168.1.54
EthOptMapOut1	Optionally mapped output parameter 1 (PLC to drive) Modbus address of parameter which is optionally mapped to Ethernet/IP assembly or Modbus TCP I/O scanner data (PLC to drive). Changed settings become active immediately.	- - 0 -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2E _h Modbus 17500 Profibus 17500 CIP 168.1.46
EthOptMapOut2	Optionally mapped output parameter 2 (PLC to drive) Modbus address of parameter which is optionally mapped to Ethernet/IP assembly or Modbus TCP I/O scanner data (PLC to drive). Changed settings become active immediately.	- - 0 -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2F _h Modbus 17502 Profibus 17502 CIP 168.1.47
EthOptMapOut3	Optionally mapped output parameter 3 (PLC to drive) Modbus address of parameter which is optionally mapped to Ethernet/IP assembly or Modbus TCP I/O scanner data (PLC to drive). Changed settings become active immediately.	- - 0 -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:30 _h Modbus 17504 Profibus 17504 CIP 168.1.48
EthRateSet	Transmission rate setting 0 / Autodetect: Autodetect 1 / 10 Mbps Full: 10 Mbps full duplex 2 / 10 Mbps Half: 10 Mbps half duplex 3 / 100 Mbps Full: 100 Mbps full duplex 4 / 100 Mbps Half: 100 Mbps half duplex Changed settings become active immediately.	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:2 _h Modbus 17412 Profibus 17412 CIP 168.1.2
EthWebserver	Ethernet webserver 0 / Off: Ethernet webserver off 1 / On: Ethernet webserver on Changed settings become active the next time the product is switched on.	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3044:6 _h Modbus 17420 Profibus 17420 CIP 168.1.6
GEARdenom	Denominator of gear ratio (225) See description GEARnum	- 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:3 _h Modbus 9734 Profibus 9734 CIP 138.1.3

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
GEARdenom2	Denominator of gear ratio number 2 (225) See description GEARnum	- 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:C _h Modbus 9752 Profibus 9752 CIP 138.1.12
GEARdir_enabl	Enabled movement direction of gear processing (229) 1 / Positive: Positive direction 2 / Negative: Negative direction 3 / Both: Both directions This allows you to activate a return movement lock function. Changed settings become active immediately.	- 1 3 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:5 _h Modbus 9738 Profibus 9738 CIP 138.1.5
GEARjerklim [onF →, -o- GF, L	Activation of jerk filter processing (338) 0 / Off / oFF: Jerk filter deactivated. 1 / PosSyncOn / P_on: Jerk filter active in processing modes with position synchronization. The jerk filter processing time must be activated via parameter RAMP_v_jerk. Setting can only be changed if power stage is disabled. Changed settings become active immediately. Available as of software version V01.02.05.	- 0 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:7 _h Modbus 9742 Profibus 9742 CIP 138.1.7
GEARnum	Numerator of gear ratio (225) GEARnum ----- = Gear ratio GEARdenom The new gear ratio is applied when the numerator value is supplied. Changed settings become active immediately.	- -2147483648 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:4 _h Modbus 9736 Profibus 9736 CIP 138.1.4
GEARnum2	Numerator of gear ratio number 2 (225) GEARnum2 ----- = Gear ratio GEARdenom2 The new gear ratio is applied when the numerator value is supplied. Changed settings become active immediately.	- -2147483648 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3026:D _h Modbus 9754 Profibus 9754 CIP 138.1.13

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
GEARposChgMode	<p>Consideration of position changes with inactive power stage (227)</p> <p>0 / Off: Position changes in states with inactive power stage are discarded.</p> <p>1 / On: Position changes in states with inactive power stage are considered.</p> <p>This setting has an effect only if gear processing is started in the mode 'Synchronization with compensation movement'.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:B _h Modbus 9750 Profibus 9750 CIP 138.1.11
GEARratio CONF → 1 - 11 GFRC	<p>Selection of special gear ratios (224)</p> <p>0 / Gear Factor / FRct: Usage of gear ratio adjusted with GEARnum/GEARdenom</p> <p>1 / 200 / 200: 200</p> <p>2 / 400 / 400: 400</p> <p>3 / 500 / 500: 500</p> <p>4 / 1000 / 1000: 1000</p> <p>5 / 2000 / 2000: 2000</p> <p>6 / 4000 / 4000: 4000</p> <p>7 / 5000 / 5000: 5000</p> <p>8 / 10000 / 1000: 10000</p> <p>9 / 4096 / 4096: 4096</p> <p>10 / 8192 / 8192: 8192</p> <p>11 / 16384 / 1638: 16384</p> <p>A change of the reference value by the specified value causes one motor revolution.</p> <p>Changed settings become active immediately.</p>	- 0 0 11	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3026:6 _h Modbus 9740 Profibus 9740 CIP 138.1.6
GEARreference	<p>Processing mode for operating mode Electronic Gear (226)</p> <p>0 / Deactivated: Deactivated</p> <p>1 / Position Synchronization Immediate: Position synchronization without compensation movement</p> <p>2 / Position Synchronization Compensated: Position synchronization with compensation movement</p> <p>3 / Velocity Synchronization: Velocity synchronization</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 301B:12 _h Modbus 6948 Profibus 6948 CIP 127.1.18
GEARselect	<p>Gear ratio selection (224)</p> <p>Switches between two gear ratios:</p> <p>Value 0: Use gear ratio defined by parameter GEARratio</p> <p>Value 1: Use gear ratio from parameters GEARnum2/GEARdenom2</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3026:E _h Modbus 9756 Profibus 9756 CIP 138.1.14

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMdis	Distance from switching point (257) The distance from the switching point is defined as the reference point. The parameter is only effective during a reference movement without index pulse. Changed settings become active the next time the motor moves.	usr_p 1 200 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:7 _h Modbus 10254 Profibus 10254 CIP 140.1.7
HMIDispPara <i>flon</i> <i>SuPU</i>	HMI display when motor moves 0 / OperatingState / StAct : Operating state 1 / v_act / UAct : Actual motor velocity 2 / I_act / IAct : Actual motor current Changed settings become active immediately.	- 0 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303A:2 _h Modbus 14852 Profibus 14852 CIP 158.1.2
HMIlocked	Lock HMI (199) 0 / Not Locked / nLac : HMI not locked 1 / Locked / Lac : HMI locked The following functions can no longer be started when the HMI is locked: - Parameter change - Jog - Autotuning - Fault Reset Changed settings become active immediately.	- 0 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303A:1 _h Modbus 14850 Profibus 14850 CIP 158.1.1

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMmethod	<p>Homing method (256)</p> <p>1: LIMN with index pulse 2: LIMP with index pulse 7: REF+ with index pulse, inv., outside 8: REF+ with index pulse, inv., inside 9: REF+ with index pulse, not inv., inside 10: REF+ with index pulse, not inv., outside 11: REF- with index pulse, inv., outside 12: REF- with index pulse, inv., inside 13: REF- with index pulse, not inv., inside 14: REF- with index pulse, not inv., outside 17: LIMN 18: LIMP 23: REF+, inv., outside 24: REF+, inv., inside 25: REF+, not inv., inside 26: REF+, not inv., outside 27: REF-, inv., outside 28: REF-, inv., inside 29: REF-, not inv., inside 30: REF-, not inv., outside 33: Index pulse neg. direction 34: Index pulse pos. direction 35: Position setting</p> <p>Abbreviations: REF+: Search movement in pos. direction REF-: Search movement in neg. direction inv.: Invert direction in switch not inv.: Direction not inverted in switch outside: Index pulse / distance outside switch inside: Index pulse / distance inside switch</p> <p>Changed settings become active immediately.</p>	- 1 18 35	INT8 INT16 INT16 INT16 R/W - -	CANopen 6098:0 _h Modbus 6936 Profibus 6936 CIP 127.1.12
HMoutdis	<p>Maximum distance for search for switching point (258)</p> <p>0: Monitoring of distance inactive >0: Maximum distance</p> <p>After detection of the switch, the drive starts to search for the defined switching point. If the defined switching point is not found within the distance defined here, the reference movement is canceled with an error.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_p 0 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:6 _h Modbus 10252 Profibus 10252 CIP 140.1.6
HMp_home	<p>Position at reference point (257)</p> <p>After a successful reference movement, this position is automatically set at the reference point.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_p -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:B _h Modbus 10262 Profibus 10262 CIP 140.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
HMp_setP	Position for Position Setting (264) Position for operating mode Homing, method 35. Changed settings become active immediately.	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W - -	CANopen 301B:16 _h Modbus 6956 Profibus 6956 CIP 127.1.22
HMprefmethod oP → hoñ- ñEŁh	Preferred homing method (256) Changed settings become active immediately.	- 1 18 35	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3028:A _h Modbus 10260 Profibus 10260 CIP 140.1.10
HMsrchdis	Maximum search distance after overtravel of switch (258) 0: Search distance monitoring disabled >0: Search distance The switch must be activated again within this search distance, otherwise the reference movement is canceled. Changed settings become active the next time the motor moves.	usr_p 0 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:D _h Modbus 10266 Profibus 10266 CIP 140.1.13
HMv_out	Target velocity for moving away from switch (259) The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active the next time the motor moves.	usr_v 1 6 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6099:2 _h Modbus 10250 Profibus 10250 CIP 140.1.5
HMv oP → hoñ- hññ	Target velocity for searching the switch (259) The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active the next time the motor moves.	usr_v 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6099:1 _h Modbus 10248 Profibus 10248 CIP 140.1.4
InvertDirOf- Count	Inversion of direction of counting at PTI interface (223) 0 / Inversion Off: Inversion of direction of counting is off 1 / Inversion On: Inversion of direction of counting is on Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3008:7 _h Modbus 2062 Profibus 2062 CIP 108.1.7
InvertDirOfMa- Enc	Inversion of direction of machine encoder 0 / Inversion Off: Inversion of direction is off 1 / Inversion On: Inversion of direction is on Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3050:8 _h Modbus 20496 Profibus 20496 CIP 180.1.8

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
InvertDirOfMove [onF] → REG- inDir	<p>Inversion of direction of movement (164)</p> <p>0 / Inversion Off / off: Inversion of direction of movement is off</p> <p>1 / Inversion On / on: Inversion of direction of movement is on</p> <p>The limit switch which is reached with a movement in positive direction must be connected to the positive limit switch input and vice versa.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:C _h Modbus 1560 Profibus 1560 CIP 106.1.12
IO_AutoEnable [onF] → REG- oRE	<p>Enabling the power stage at PowerOn</p> <p>0 / Off / off: After start-up, a rising edge with the signal input function Enable enables the power stage</p> <p>1 / On / on: After start-up, an active signal input with signal input function Enable enables the power stage</p> <p>2 / AutoOn / Auto: After start-up, the power stage is automatically enabled</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:6 _h Modbus 1292 Profibus 1292 CIP 105.1.6
IO_DQ_set	<p>Setting the digital outputs directly</p> <p>Write access to output bits is only active if the signal pin is available as an output and if the function of the output was set to 'Available as required'.</p> <p>Coding of the individual signals: Bit 0: DQ0 Bit 1: DQ1 Bit 2: DQ2</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3008:11 _h Modbus 2082 Profibus 2082 CIP 108.1.17
IO_GEARmethod [onF] → REG- oGN	<p>Processing mode for operating mode Electronic Gear</p> <p>1 / Position Synchronization Immediate / PosI: Position synchronization without compensation movement</p> <p>2 / Position Synchronization Compensated / PosCo: Position synchronization with compensation movement</p> <p>3 / Velocity Synchronization / VELo: Velocity synchronization</p> <p>Changed settings become active the next time the motor moves.</p>	- 1 1 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:17 _h Modbus 1326 Profibus 1326 CIP 105.1.23
IO_I_limit [onF] → I - o- L, I	<p>Current limitation via input (336)</p> <p>A current limit can be activated via a digital input.</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	A _{rms} 0.00 0.20 300.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:27 _h Modbus 1614 Profibus 1614 CIP 106.1.39

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IO_JOGmethod [onF → RLL- , oJG	Selection of jog method 0 / Continuous Movement / coFlo: Jog with continuous movement 1 / Step Movement / StFlo: Jog with step movement Changed settings become active the next time the motor moves.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:18 _h Modbus 1328 Profibus 1328 CIP 105.1.24
IO_ModeSwitch [onF → RLL- , oP5	Operating mode for signal input function Operating Mode Switch 0 / None / nonE: None 1 / Profile Torque / torP: Profile Torque 2 / Profile Velocity / VELP: Profile Velocity 3 / Electronic Gear / GERr: Electronic Gear Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2F _h Modbus 1630 Profibus 1630 CIP 106.1.47
IO_v_limit	Velocity limitation via input (334) A velocity limitation can be activated via a digital input. NOTE: In operating mode Profile Torque, the minimum velocity is internally limited to 100 min ⁻¹ . Changed settings become active immediately.	usr_v 1 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:1E _h Modbus 1596 Profibus 1596 CIP 106.1.30
IOdefaultMode [onF → RLL- , o-P	Operating mode 0 / None / nonE: None 1 / Profile Torque / torP: Profile Torque 2 / Profile Velocity / VELP: Profile Velocity 3 / Electronic Gear / GERr: Electronic Gear 5 / Jog / JoG: Jog 6 / Motion Sequence / MotS: Motion Sequence Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on.	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:3 _h Modbus 1286 Profibus 1286 CIP 105.1.3

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI0 CONF → I - DI di 0	<p>Function Input DI0 (297)</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / Fault Reset / FrES: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / i L n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrAR: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / dStR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / dSEL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / dSb0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / dSb1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / dSb2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / dSb3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GOF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GOF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / LPRr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / nSLt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / EnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / dSb4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / dSb5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / dSb6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / R i1: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / R i2: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:1 _h Modbus 1794 Profibus 1794 CIP 107.1.1
512	Changed settings become active the next time the product is switched on.			AC servo drive

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI1 [onF →, -o- di, i	<p>Function Input DI1 (298)</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / Fault Reset / FrE5: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrRt: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / d5tR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / d5EL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / d5b0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / d5b1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / d5b2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / d5b3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / CPPr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / n5Lt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / tnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / 5tN5: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / d5b4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / d5b5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / d5b6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / R i 1: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / R i 2: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:2 _h Modbus 1796 Profibus 1796 CIP 107.1.2
AC servo drive	Changed settings become active the next time the product is switched on.			513

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI2 CONF → I - DI di 2	<p>Function Input DI2 (299)</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / Fault Reset / FrES: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / i L n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrAR: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / dStR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / dSEL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / dSb0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / dSb1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / dSb2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / dSb3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GOF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GOF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / LPRr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / nSLt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / EnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / dSb4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / dSb5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / dSb6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / A I1 i: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / A I2 i: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:3 _h Modbus 1798 Profibus 1798 CIP 107.1.3
514	Changed settings become active the next time the product is switched on.			AC servo drive

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI3 [onF →, -o- di 3	<p>Function Input DI3 (300)</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / Fault Reset / FrE5: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrRt: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / d5tR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / d5EL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / d5b0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / d5b1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / d5b2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / d5b3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / CPPr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / n5Lt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / tnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / 5tN5: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / d5b4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / d5b5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / d5b6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / R11: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / R12: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:4 _h Modbus 1800 Profibus 1800 CIP 107.1.4
AC servo drive	Changed settings become active the next time the product is switched on.			515

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI4 CONF → I - DI di 4	<p>Function Input DI4 (301)</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / Fault Reset / FrE5: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / i L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrAR: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / d5tR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / d5EL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / d5b0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / d5b1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / d5b2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / d5b3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GOF 1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GOF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / LPRr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / nSLt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / EnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / d5b4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / d5b5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / d5b6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / A I 1 : Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / A I 2 : Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:5 _h Modbus 1802 Profibus 1802 CIP 107.1.5
516	Changed settings become active the next time the product is switched on.			AC servo drive

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DI5 [onF →, -o- di 5	<p>Function Input DI5 (302)</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / Fault Reset / FrE5: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrRt: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / d5tR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / d5EL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / d5b0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / d5b1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / d5b2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / d5b3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / CPPr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / n5Lt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / tnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / 5tN5: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / d5b4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / d5b5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / d5b6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / R11: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / R12: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:6 _h Modbus 1804 Profibus 1804 CIP 107.1.6
AC servo drive	Changed settings become active the next time the product is switched on.			517

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DQ0 [onF →, -o- do0	<p>Function Output DQ0 (305)</p> <p>1 / Freely Available / onF: Available as required</p> <p>2 / No Fault / nFLt: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / i n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / i n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Ut hr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / i t hr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALt: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nSt d: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFo: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nSEd: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrL1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrL2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrL3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrL4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:9 _h Modbus 1810 Profibus 1810 CIP 107.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DQ1 [onF →, -o- do i	<p>Function Output DQ1 (306)</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / No Fault / nFLt: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / thr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALt: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nStd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFo: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nScd: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrC1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrC2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrC3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrC4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:Ah Modbus 1812 Profibus 1812 CIP 107.1.10

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOfunct_DQ2 CONF →, -o- do2	<p>Function Output DQ2 (307)</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / No Fault / nFLT: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / Ithr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALT: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nSLd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFa: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nSLa: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrL1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrL2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrL3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrL4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3007:B _h Modbus 1814 Profibus 1814 CIP 107.1.11
IOM1_AI11_I_max CONF →, -o- L I I	<p>IOM1 Limitation of current at 10 V of AI11</p> <p>In increments of 0.01 A_{rms}.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	A _{rms} 0.00 3.00 300.00	UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:F _h Modbus 20254 Profibus 20254 CIP 179.1.15

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI11_M_scale [onF →, -o- t i l t	<p>IOM1 Target torque at 10 V in operating mode Profile Torque of AI11</p> <p>100.0 % correspond to the continuous stall torque _M_M_0.</p> <p>By using a negative sign, you can invert the evaluation of the analog signal.</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	% -3000.0 100.0 3000.0	INT16 INT16 INT16 INT16 R/W per. -	CANopen 304F:12 _h Modbus 20260 Profibus 20260 CIP 179.1.18
IOM1_AI11_mode [onF →, -o- R i l u	<p>IOM1 Type of usage of AI11</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / Lr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 1 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:E _h Modbus 20252 Profibus 20252 CIP 179.1.14
IOM1_AI11_offset [onF →, -o- R i l o	<p>IOM1 Offset voltage of AI11</p> <p>The analog input AI11 is corrected/offset by the offset value. If you have defined a zero voltage window, this window is effective in the zero pass range of the corrected analog input AI11.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	mV -5000 0 5000	INT16 INT16 INT16 INT16 R/W per. -	CANopen 304F:B _h Modbus 20246 Profibus 20246 CIP 179.1.11
IOM1_AI11_Tau [onF →, -o- R i l F	<p>IOM1 Filter time constant of AI11</p> <p>First-order low pass (PT1) filter time constant for analog input AI11.</p> <p>In increments of 0.01 ms.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	ms 0.00 0.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:2 _h Modbus 20228 Profibus 20228 CIP 179.1.2
IOM1_AI11_v_max	<p>IOM1 Limitation of velocity at 10 V of AI11</p> <p>The maximum velocity is limited to the setting in CTRL_v_max.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	usr_v 1 3000 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 304F:10 _h Modbus 20256 Profibus 20256 CIP 179.1.16

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI11_v_scale	<p>IOM1 Target velocity at 10 V in operating mode Profile Velocity of AI11</p> <p>The maximum velocity is limited to the setting in CTRL_v_max.</p> <p>By using a negative sign, you can invert the evaluation of the analog signal.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	<p>usr_v</p> <p>-2147483648</p> <p>6000</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:11_h</p> <p>Modbus 20258</p> <p>Profibus 20258</p> <p>CIP 179.1.17</p>
IOM1_AI11_win CONF →, -o- Rili	<p>IOM1 Zero voltage window of AI11</p> <p>Threshold value up to which an input voltage value is treated as 0 V. Example: Value 20, this means a range from -20 ... +20 mV is treated as 0 mV.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	<p>mV</p> <p>0</p> <p>0</p> <p>1000</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:9_h</p> <p>Modbus 20242</p> <p>Profibus 20242</p> <p>CIP 179.1.9</p>
IOM1_AI12_I_max CONF →, -o- Li2,	<p>IOM1 Limitation of current at 10 V of AI12</p> <p>In increments of 0.01 A_{rms}.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	<p>A_{rms}</p> <p>0.00</p> <p>3.00</p> <p>300.00</p>	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:14_h</p> <p>Modbus 20264</p> <p>Profibus 20264</p> <p>CIP 179.1.20</p>
IOM1_AI12_M_scale CONF →, -o- Li2,	<p>IOM1 Target torque at 10 V in operating mode Profile Torque of AI12</p> <p>100.0 % correspond to the continuous stall torque _M_M_0.</p> <p>By using a negative sign, you can invert the evaluation of the analog signal.</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	<p>%</p> <p>-3000.0</p> <p>100.0</p> <p>3000.0</p>	<p>INT16</p> <p>INT16</p> <p>INT16</p> <p>INT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:17_h</p> <p>Modbus 20270</p> <p>Profibus 20270</p> <p>CIP 179.1.23</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI12_mode [onF →, -o- R i2u	<p>IOM1 Type of usage of AI12</p> <p>0 / None / none: No function</p> <p>1 / Target Velocity / SPd5: Target velocity for the velocity controller</p> <p>2 / Target Torque / Lr95: Target torque for the current controller</p> <p>3 / Velocity Limitation / LSPd: Limitation of the velocity for the velocity controller</p> <p>4 / Torque Limitation / LTr9: Limitation of the torque for the current controller</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:13 _h Modbus 20262 Profibus 20262 CIP 179.1.19
IOM1_AI12_offset [onF →, -o- R i2o	<p>IOM1 Offset voltage of AI12</p> <p>The analog input AI12 is corrected/offset by the offset value. If you have defined a zero voltage window, this window is effective in the zero pass range of the corrected analog input AI12.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	mV -5000 0 5000	INT16 INT16 INT16 INT16 R/W per. -	CANopen 304F:C _h Modbus 20248 Profibus 20248 CIP 179.1.12
IOM1_AI12_Tau [onF →, -o- R i2F	<p>IOM1 Filter time constant of AI12</p> <p>First-order low pass (PT1) filter time constant for analog input AI12.</p> <p>In increments of 0.01 ms.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	ms 0.00 0.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:18 _h Modbus 20272 Profibus 20272 CIP 179.1.24
IOM1_AI12_v_max	<p>IOM1 Limitation of velocity at 10 V of AI12</p> <p>The maximum velocity is limited to the setting in CTRL_v_max.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p> <p>Available as of software version V01.06.00.</p>	usr_v 1 3000 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 304F:15 _h Modbus 20266 Profibus 20266 CIP 179.1.21
IOM1_AI12_v_scale	<p>IOM1 Target velocity at 10 V in operating mode Profile Velocity of AI12</p> <p>The maximum velocity is limited to the setting in CTRL_v_max.</p> <p>By using a negative sign, you can invert the evaluation of the analog signal.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	usr_v -2147483648 6000 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 304F:16 _h Modbus 20268 Profibus 20268 CIP 179.1.22

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AI12_win [onF →, -o- R i2L	IOM1 Zero voltage window of AI12 Threshold value up to which an input voltage value is treated as 0 V. Example: Value 20, this means a range from -20 ... +20 mV is treated as 0 mV. Changed settings become active immediately. Available as of software version V01.06.00.	mV 0 0 1000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:A _h Modbus 20244 Profibus 20244 CIP 179.1.10
IOM1_AO_ErrResp	IOM1 Error response to overload of analog outputs 0 / Error Class 0: Error class 0 1 / Error Class 1: Error class 1 2 / Error Class 2: Error class 2 3 / Error Class 3: Error class 3 Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 1 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:1F _h Modbus 20286 Profibus 20286 CIP 179.1.31
IOM1_AO_mode [onF →, -o- R oLl	IOM1 Type of usage of analog outputs 0 / none / nonE: Analog outputs are deactivated 1 / Voltage / UoLl: Both analog outputs are voltage outputs 2 / Current / Curr: Both analog outputs are current outputs Setting can only be changed if power stage is disabled. Changed settings become active the next time the product is switched on. Available as of software version V01.06.00.	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:20 _h Modbus 20288 Profibus 20288 CIP 179.1.32
IOM1_AO11_FixVal l	IOM1 Fixed value for AO11 Only available if parameter IOM1_AO11_func is set to 'Fixed Value'. Unit and range depend on setting in parameter IOM1_AO_mode. If setting is 'Voltage': Unit: mV Range: -10000 ... 10000 If setting is 'Current': Unit: µA Range: 0 ... 20000 Changed settings become active immediately. Available as of software version V01.06.00.	- -10000 0 20000	INT16 INT16 INT16 INT16 R/W - -	CANopen 304F:24 _h Modbus 20296 Profibus 20296 CIP 179.1.36

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AO11_func [onF] →, -o- R111	<p>IOM1 Function of AO11</p> <p>0 / None / none: No function</p> <p>1 / Actual Velocity / URCL: Actual velocity (10 V / 20 mA correspond to value in CTRL_v_max)</p> <p>2 / Actual Torque / tRCL: Actual torque (10 V / 20 mA correspond to value in CTRL_I_max)</p> <p>3 / Reference Velocity / UrEF: Reference velocity (10 V / 20 mA correspond to value in CTRL_v_max)</p> <p>4 / Reference Torque / trEF: Reference torque (10 V / 20 mA correspond to value in CTRL_I_max)</p> <p>5 / Position Deviation / Pd F: Position deviation (10 V / 20 mA correspond to value in MON_p_dif_load_usr)</p> <p>6 / Fixed Value / F, UR: Fixed value (setting in parameter IOM1_AO11_FixVal)</p> <p>7 / Actual Position / PRCL: Actual position in the modulo range (10 V / 20 mA correspond to value in MOD_Max)</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 7	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:21 _h Modbus 20290 Profibus 20290 CIP 179.1.33
IOM1_AO11_I_range [onF] →, -o- R112	<p>IOM1 Range of current of AO11</p> <p>0 / 0-20mA / 0-2: 0 mA ... 20 mA (0 mA correspond to 0 user-defined units)</p> <p>1 / 4-20mA unsigned / 4-2u: 4 mA ... 20 mA (4 mA correspond to 0 user-defined units)</p> <p>2 / 4-20mA signed / 4-2S: 4 mA ... 20 mA (12 mA correspond to 0 user-defined units)</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:22 _h Modbus 20292 Profibus 20292 CIP 179.1.34
IOM1_AO11_invert t	<p>IOM1 Inversion of AO11</p> <p>Only available if output is set to a voltage output.</p> <p>Value 0: No inversion Value 1: Inversion active</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:23 _h Modbus 20294 Profibus 20294 CIP 179.1.35

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AO12_FixVal 1	<p>IOM1 Fixed value for AO12</p> <p>Only available if parameter IOM1_AO12_func is set to 'Fixed Value'.</p> <p>Unit and range depend on setting in parameter IOM1_AO_mode.</p> <p>If setting is 'Voltage': Unit: mV Range: -10000 ... 10000</p> <p>If setting is 'Current': Unit: μA Range: 0 ... 20000</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- -10000 0 20000	INT16 INT16 INT16 INT16 R/W - -	CANopen 304F:2E _h Modbus 20316 Profibus 20316 CIP 179.1.46
IOM1_AO12_func Function →, -0- R 127	<p>IOM1 Function of AO12</p> <p>0 / None / none: No function</p> <p>1 / Actual Velocity / VRL: Actual velocity (10 V / 20 mA correspond to value in CTRL_v_max)</p> <p>2 / Actual Torque / LRL: Actual torque (10 V / 20 mA correspond to value in CTRL_I_max)</p> <p>3 / Reference Velocity / VREF: Reference velocity (10 V / 20 mA correspond to value in CTRL_v_max)</p> <p>4 / Reference Torque / LREF: Reference torque (10 V / 20 mA correspond to value in CTRL_I_max)</p> <p>5 / Position Deviation / Pdif: Position deviation (10 V / 20 mA correspond to value in MON_p_dif_load_usr)</p> <p>6 / Fixed Value / F, UR: Fixed value (setting in parameter IOM1_AO12_FixVal)</p> <p>7 / Actual Position / PRL: Actual position in the modulo range (10 V / 20 mA correspond to value in MOD_Max)</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 0 7	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:2B _h Modbus 20310 Profibus 20310 CIP 179.1.43
IOM1_AO12_I_range Function →, -0- R 128	<p>IOM1 Range of current of AO12</p> <p>0 / 0-20mA / 0-2: 0 mA ... 20 mA (0 mA correspond to 0 user-defined units)</p> <p>1 / 4-20mA unsigned / 4-2u: 4 mA ... 20 mA (4 mA correspond to 0 user-defined units)</p> <p>2 / 4-20mA signed / 4-2s: 4 mA ... 20 mA (12 mA correspond to 0 user-defined units)</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:2C _h Modbus 20312 Profibus 20312 CIP 179.1.44

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_AO12_invert	<p>IOM1 Inversion of AO12</p> <p>Only available if output is set to a voltage output.</p> <p>Value 0: No inversion Value 1: Inversion active</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:2D _h Modbus 20314 Profibus 20314 CIP 179.1.45
IOM1_DI_10_Deb	<p>IOM1 Debounce time of DI10</p> <p>0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:40 _h Modbus 20352 Profibus 20352 CIP 179.1.64
IOM1_DI_11_Deb	<p>IOM1 Debounce time of DI11</p> <p>0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:41 _h Modbus 20354 Profibus 20354 CIP 179.1.65
IOM1_DI_12_Deb	<p>IOM1 Debounce time of DI12</p> <p>0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:42 _h Modbus 20356 Profibus 20356 CIP 179.1.66

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_DI_13_Deb	<p>IOM1 Debounce time of DI13</p> <p>0 / No: No software debouncing 1 / 0.25 ms: 0.25 ms 2 / 0.50 ms: 0.50 ms 3 / 0.75 ms: 0.75 ms 4 / 1.00 ms: 1.00 ms 5 / 1.25 ms: 1.25 ms 6 / 1.50 ms: 1.50 ms</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.06.00.</p>	- 0 6 6	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:43 _h Modbus 20358 Profibus 20358 CIP 179.1.67
IOM1_DQ_set	<p>IOM1 Setting the digital outputs directly</p> <p>Write access to output bits is only active if the signal pin is available as an output and if the function of the output was set to 'Available as required'.</p> <p>Coding of the individual signals: Bit 0: DQ10 Bit 1: DQ11</p> <p>Available as of software version V01.06.00.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 304F:37 _h Modbus 20334 Profibus 20334 CIP 179.1.55

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_IOfunct_DI 10 CONF → , -0- di IQ	<p>IOM1 Function Input DI10</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / Fault Reset / FrE5: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrRt: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / d5tR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / d5EL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / d5b0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / d5b1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / d5b2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / d5b3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / CPPr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / n5Lt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / tnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / d5b4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / d5b5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / d5b6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / R11: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / R12: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:50_n</p> <p>Modbus 20384</p> <p>Profibus 20384</p> <p>CIP 179.1.80</p>
AC servo drive	<p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>			529

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_IOfunct_DI11 CONF → I -> -> di 11	<p>IOM1 Function Input DI11</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / Fault Reset / FrES: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / i L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLtP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrAR: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / dStA: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / dSEL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / dSb0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / dSb1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / dSb2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / dSb3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / LPRr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / nSLt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / tnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / dSb4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / dSb5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / dSb6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / A11i: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / A12i: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:51_h</p> <p>Modbus 20386</p> <p>Profibus 20386</p> <p>CIP 179.1.81</p>
530	<p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>			AC servo drive

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_IOfunct_DI 12 [onF →, -o- di 12	<p>IOM1 Function Input DI12</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / Fault Reset / FrE5: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / L, n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL, n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrAt: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / d5tR: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / d5EL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / d5b0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / d5b1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / d5b2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / d5b3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L, nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L, nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / CPAr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / n5L: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / tnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / d5b4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / d5b5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / d5b6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / R11: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / R12: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:52_h</p> <p>Modbus 20388</p> <p>Profibus 20388</p> <p>CIP 179.1.82</p>
AC servo drive	<p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>			531

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_IOfunct_DI13 CONF → IOM1 di 13	<p>IOM1 Function Input DI13</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / Fault Reset / FrES: Fault reset after error</p> <p>3 / Enable / EnAb: Enables the power stage</p> <p>4 / Halt / hALt: Halt</p> <p>5 / Start Profile Positioning / SPtP: Start request for movement</p> <p>6 / Current Limitation / i L n: Limits the current to parameter value</p> <p>7 / Zero Clamp / CLnP: Zero clamping</p> <p>8 / Velocity Limitation / UL n: Limits the velocity to parameter value</p> <p>9 / Jog Positive / JoGP: Jog: Moves in positive direction</p> <p>10 / Jog Negative / JoGn: Jog: Moves in negative direction</p> <p>11 / Jog Fast/Slow / JoGF: Jog: Switches between slow and fast movement</p> <p>12 / Gear Ratio Switch / GrAR: Electronic Gear: Switches between two gear ratios</p> <p>13 / Start Single Data Set / dStA: Motion Sequence: Starts a single data set</p> <p>14 / Data Set Select / dSEL: Motion Sequence: Data set selection</p> <p>15 / Data Set Bit 0 / dSb0: Motion Sequence: Data set bit 0</p> <p>16 / Data Set Bit 1 / dSb1: Motion Sequence: Data set bit 1</p> <p>17 / Data Set Bit 2 / dSb2: Motion Sequence: Data set bit 2</p> <p>18 / Data Set Bit 3 / dSb3: Motion Sequence: Data set bit 3</p> <p>19 / Gear Offset 1 / GoF1: Electronic Gear: Adds first gear offset</p> <p>20 / Gear Offset 2 / GoF2: Electronic Gear: Adds second gear offset</p> <p>21 / Reference Switch (REF) / rEF: Reference switch</p> <p>22 / Positive Limit Switch (LIMP) / L nP: Positive limit switch</p> <p>23 / Negative Limit Switch (LIMN) / L nN: Negative limit switch</p> <p>24 / Switch Controller Parameter Set / CPPr: Switches controller parameter set</p> <p>27 / Operating Mode Switch / nSLt: Switches operating mode</p> <p>28 / Velocity Controller Integral Off / EnoF: Switches off velocity controller integral term</p> <p>29 / Start Motion Sequence / StnS: Motion Sequence: Starts a motion sequence</p> <p>35 / Data Set Bit 4 / dSb4: Motion Sequence: Data set bit 4</p> <p>36 / Data Set Bit 5 / dSb5: Motion Sequence: Data set bit 5</p> <p>37 / Data Set Bit 6 / dSb6: Motion Sequence: Data set bit 6</p> <p>38 / Inversion AI11 (IO Module) / A i1: Inverts analog input AI11 (I/O module)</p> <p>39 / Inversion AI12 (IO Module) / A i2: Inverts analog input AI12 (I/O module)</p> <p>Setting can only be changed if power stage is disabled.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 304F:53 _h Modbus 20390 Profibus 20390 CIP 179.1.83
532	<p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>			AC servo drive

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_IOfunct_DQ10 [onF →, -o- do IQ	<p>IOM1 Function Output DQ10</p> <p>1 / Freely Available / nonE: Available as required</p> <p>2 / No Fault / nFLt: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / thr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALt: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nStd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFo: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nScd: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrC1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrC2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrC3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrC4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>	- - - -	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:5A_h</p> <p>Modbus 20404</p> <p>Profibus 20404</p> <p>CIP 179.1.90</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOM1_IOfunct_DQ11 CONF → , - - do !!	<p>IOM1 Function Output DQ11</p> <p>1 / Freely Available / none: Available as required</p> <p>2 / No Fault / nFLT: Signals operating states Ready To Switch On, Switched On and Operation Enable</p> <p>3 / Active / Rct: Signals operating state Operation Enable</p> <p>5 / In Position Deviation Window / , n-P: Position deviation is within window</p> <p>6 / In Velocity Deviation Window / , n-U: Velocity deviation is within window</p> <p>7 / Velocity Below Threshold / Uthr: Motor velocity below threshold</p> <p>8 / Current Below Threshold / , thr: Motor current below threshold</p> <p>9 / Halt Acknowledge / hALT: Halt acknowledgement</p> <p>11 / Motion Sequence: Start Acknowledge / dSRc: Motion Sequence: Acknowledgement of start request</p> <p>13 / Motor Standstill / nStd: Motor at a standstill</p> <p>14 / Selected Error / SErr: One of the selected errors is active</p> <p>15 / Valid Reference (ref_ok) / rEFa: Drive has a valid reference (ref_ok)</p> <p>16 / Selected Warning / SWrn: One of the selected warnings is active</p> <p>17 / Motion Sequence: Done / nSLd: Motion Sequence: Sequence done</p> <p>18 / Position Register Channel 1 / PrL1: Position register channel 1</p> <p>19 / Position Register Channel 2 / PrL2: Position register channel 2</p> <p>20 / Position Register Channel 3 / PrL3: Position register channel 3</p> <p>21 / Position Register Channel 4 / PrL4: Position register channel 4</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p> <p>Available as of software version V01.06.00.</p>	- - - -	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 304F:5B_h</p> <p>Modbus 20406</p> <p>Profibus 20406</p> <p>CIP 179.1.91</p>
IOsigLIMN	<p>Signal evaluation for negative limit switch (346)</p> <p>0 / Inactive: Inactive</p> <p>1 / Normally closed: Normally closed NC</p> <p>2 / Normally open: Normally open NO</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 1 2	<p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>UINT16</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3006:F_h</p> <p>Modbus 1566</p> <p>Profibus 1566</p> <p>CIP 106.1.15</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
IOsigLIMP	Signal evaluation for positive limit switch (346) 0 / Inactive: Inactive 1 / Normally closed: Normally closed NC 2 / Normally open: Normally open NO Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:10 _h Modbus 1568 Profibus 1568 CIP 106.1.16
IOsigREF	Signal evaluation for reference switch (347) 1 / Normally Closed: Normally closed NC 2 / Normally Open: Normally open NO The reference switch is only active while a reference movement to the reference switch is processed. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 1 1 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:E _h Modbus 1564 Profibus 1564 CIP 106.1.14
IOsigRespOfPS	Response to active limit switch during enabling of power stage 0 / Error: Active limit switch triggers an error. 1 / No Error: Active limit switch does not trigger an error. Defines the response when the power stage is enabled while a hardware limit switch is active. Changed settings become active immediately.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:6 _h Modbus 1548 Profibus 1548 CIP 106.1.6
IP_IntTimInd	Interpolation time index Available as of software version V01.08.	- -128 -3 63	INT8 INT16 INT16 INT16 R/W - -	CANopen 60C2:2 _h Modbus 7002 Profibus 7002 CIP 127.1.45
IP_IntTimPerVal	Interpolation time period value Available as of software version V01.08.	s 0 1 255	UINT8 UINT16 UINT16 UINT16 R/W - -	CANopen 60C2:1 _h Modbus 7000 Profibus 7000 CIP 127.1.44
IPp_target	Position reference value for operating mode Interpolated Position Available as of software version V01.08.	- -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 60C1:1 _h Modbus 7004 Profibus 7004 CIP 127.1.46

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
JOGactivate	Activation of operating mode Jog Bit 0: Positive direction of movement Bit 1: Negative direction of movement Bit 2: 0=slow 1=fast Changed settings become active immediately.	- 0 0 7	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 301B:9 _h Modbus 6930 Profibus 6930 CIP 127.1.9
JOGmethod	Selection of jog method (216) 0 / Continuous Movement / <i>cañlo</i> : Jog with continuous movement 1 / Step Movement / <i>Stñlo</i> : Jog with step movement Changed settings become active immediately.	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3029:3 _h Modbus 10502 Profibus 10502 CIP 141.1.3
JOGstep	Distance for step movement (217) Changed settings become active the next time the motor moves.	usr_p 1 20 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3029:7 _h Modbus 10510 Profibus 10510 CIP 141.1.7
JOGtime	Wait time for step movement (217) Changed settings become active the next time the motor moves.	ms 1 500 32767	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3029:8 _h Modbus 10512 Profibus 10512 CIP 141.1.8
JOGv_fast <i>oP → Joñ-Jñh,</i>	Velocity for fast movement (216) The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active immediately.	usr_v 1 180 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3029:5 _h Modbus 10506 Profibus 10506 CIP 141.1.5
JOGv_slow <i>oP → Joñ-JñLo</i>	Velocity for slow movement (216) The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active immediately.	usr_v 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3029:4 _h Modbus 10504 Profibus 10504 CIP 141.1.4

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_HaltReaction [onF → RLG- hLpP	<p>Halt option code (328)</p> <p>1 / Deceleration Ramp / dEcE: Deceleration ramp 3 / Torque Ramp / tOrP: Torque ramp</p> <p>Type of deceleration for Halt.</p> <p>Setting of deceleration ramp with parameter RAMP_v_dec. Setting of torque ramp with parameter LIM_I_maxHalt.</p> <p>If a deceleration ramp is already active, the parameter cannot be written.</p> <p>Changed settings become active immediately.</p>	- 1 1 3	INT16 INT16 INT16 INT16 R/W per. -	CANopen 605D:0 _h Modbus 1582 Profibus 1582 CIP 106.1.23
LIM_I_maxHalt [onF → RLG- hcur	<p>Current value for Halt (153)</p> <p>This value is only limited by the minimum/maximum value range (no limitation of this value by motor/power stage).</p> <p>In the case of a Halt, the actual current limit (<u>I</u>max_{actual}) is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - LIM_I_maxHalt - M_I_max - PA_I_max <p>Further current reductions caused by I_{2t} monitoring are also taken into account during a Halt.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:E _h Modbus 4380 Profibus 4380 CIP 117.1.14
LIM_I_maxQSTP [onF → FLt- qcur	<p>Current value for Quick Stop (153)</p> <p>This value is only limited by the minimum/maximum value range (no limitation of this value by motor/power stage).</p> <p>In the case of a Quick Stop, the actual current limit (<u>I</u>max_{actual}) is one of the following values (whichever is lowest):</p> <ul style="list-style-type: none"> - LIM_I_maxQSTP - M_I_max - PA_I_max <p>Further current reductions caused by I_{2t} monitoring are also taken into account during a Quick Stop.</p> <p>Default: PA_I_max at 8 kHz PWM frequency and 230/480 V mains voltage</p> <p>In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	A _{rms} - - -	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3011:D _h Modbus 4378 Profibus 4378 CIP 117.1.13

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
LIM_QStopReact	<p>Quick Stop option code (331)</p> <p>-2 / Torque ramp (Fault): Use torque ramp and transit to operating state 9 Fault</p> <p>-1 / Deceleration Ramp (Fault): Use deceleration ramp and transit to operating state 9 Fault</p> <p>6 / Deceleration ramp (Quick Stop): Use deceleration ramp and remain in operating state 7 Quick Stop</p> <p>7 / Torque ramp (Quick Stop): Use torque ramp and remain in operating state 7 Quick Stop</p> <p>Type of deceleration for Quick Stop.</p> <p>Setting of deceleration ramp with parameter RAMPquickstop.</p> <p>Setting of torque ramp with parameter LIM_I_maxQSTP.</p> <p>If a deceleration ramp is already active, the parameter cannot be written.</p> <p>Changed settings become active immediately.</p>	- -2 6 7	INT16 INT16 INT16 INT16 R/W per. -	CANopen 3006:18 _h Modbus 1584 Profibus 1584 CIP 106.1.24
Mains_reactor	<p>Mains reactor</p> <p>0 / No: No</p> <p>1 / Yes: Yes</p> <p>Value 0: No mains reactor connected. The nominal power of the power stage is reduced.</p> <p>Value 1: A mains reactor is connected.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:20 _h Modbus 1344 Profibus 1344 CIP 105.1.32
MBaddress └┐onF → └┐on┐- ┐bRd	<p>Modbus address</p> <p>Valid addresses: 1 to 247</p> <p>Changed settings become active the next time the product is switched on.</p>	- 1 1 247	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3016:4 _h Modbus 5640 Profibus 5640 CIP 122.1.4
MBbaud └┐onF → └┐on┐- ┐bbd	<p>Modbus baud rate</p> <p>9600 / 9600 Baud / 95: 9600 Baud</p> <p>19200 / 19200 Baud / 192: 19200 Baud</p> <p>38400 / 38400 Baud / 384: 38400 Baud</p> <p>Changed settings become active the next time the product is switched on.</p>	- 9600 19200 38400	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3016:3 _h Modbus 5638 Profibus 5638 CIP 122.1.3
Mfb_ResRatio	<p>Transformation ratio</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0.3 - 1.0	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 305C:17 _h Modbus 23598 Profibus 23598 CIP 192.1.23

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MOD_AbsDirection	<p>Direction of absolute movement with Modulo (285)</p> <p>0 / Shortest Distance: Movement with shortest distance 1 / Positive Direction: Movement only in positive direction 2 / Negative Direction: Movement only in negative direction</p> <p>If the parameter is set to 0, the drive calculates the shortest way to the new target position and starts the movement in the corresponding direction. If the distance to the target position is identical in positive and negative directions, the movement takes place in positive direction.</p> <p>Changed settings become active immediately.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:3B _h Modbus 1654 Profibus 1654 CIP 106.1.59
MOD_AbsMultiRng	<p>Multiple ranges for absolut movement with Modulo (286)</p> <p>0 / Multiple Ranges Off: Absolute movement in one modulo range 1 / Multiple Ranges On: Absolute movement in multiple modulo ranges</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:3C _h Modbus 1656 Profibus 1656 CIP 106.1.60
MOD_Enable [onF → RCL- RtYP	<p>Activation of Modulo (284)</p> <p>0 / Modulo Off / oFF: Modulo is off 1 / Modulo On / on: Modulo is on</p> <p>Activating Modulo does not automatically change the value of other parameters. Before changing this value, verify that the parameter settings for the intended application are correct. NOTE: Modulo must be deactivated for Auto-tuning.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:38 _h Modbus 1648 Profibus 1648 CIP 106.1.56
MOD_Max	<p>Maximum position of modulo range (285)</p> <p>The maximum position value of the modulo range must be greater than the minimum position value of the modulo range. The value must not exceed the maximum possible value of position scaling _ScalePOSmax.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	usr_p - 3600 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:3A _h Modbus 1652 Profibus 1652 CIP 106.1.58

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MOD_Min	<p>Minimum position of modulo range (285)</p> <p>The minimum position value of the modulo range must be less than the maximum position value of the modulo range. The value must not exceed the maximum possible value of position scaling _ScalePOSmax.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:39 _h Modbus 1650 Profibus 1650 CIP 106.1.57
MON_ChkTime [onF →, -o- t t h r	<p>Monitoring of time window (365)</p> <p>Adjustment of a time for monitoring of position deviation, speed deviation, speed value and current value. If the monitored value is in the permissible range during the adjusted time, the monitoring function delivers a positive result. The status can be output via a parameterizable output.</p> <p>Changed settings become active immediately.</p>	ms 0 0 9999	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1D _h Modbus 1594 Profibus 1594 CIP 106.1.29
MON_commutat	<p>Commutation monitoring (375)</p> <p>0 / Off: Commutation monitoring off 1 / On: Commutation monitoring on</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:5 _h Modbus 1290 Profibus 1290 CIP 105.1.5
MON_GroundFault	<p>Ground fault monitoring (378)</p> <p>0 / Off: Ground fault monitoring off 1 / On: Ground fault monitoring on</p> <p>In exceptional cases, deactivation may be necessary, for example: - Long motor cables Deactivate ground fault monitoring if it responds in an unwanted way.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3005:10 _h Modbus 1312 Profibus 1312 CIP 105.1.16

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_HW_Limits	<p>Temporary deactivation of hardware limit switches</p> <p>0: No limit switch deactivated 1: Deactivate positive limit switch 2: Deactivate negative limit switch 3: Deactivate both limit switches</p> <p>With this parameter, a PLC can temporarily deactivate hardware limit switches. This is useful if a homing procedure controlled by a PLC is to use a limit switch as a reference switch without an error response of the drive. The parameter is only available with the EtherCAT module.</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3006:11 _h Modbus 1570 Profibus 1570 CIP 106.1.17
MON_I_Threshold [onF →, -a- , t hr	<p>Monitoring of current threshold (371)</p> <p>The system checks whether the drive is below the defined value during the period set with MON_ChkTime. The status can be output via a parameterizable output. The parameter <code>_Iq_act_rms</code> is used as comparison value. In increments of 0.01 A_{rms}.</p> <p>Changed settings become active immediately.</p>	A _{rms} 0.00 0.20 300.00	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:1C _h Modbus 1592 Profibus 1592 CIP 106.1.28
MON_IO_SelErr1	<p>First number for the signal output function Selected Error</p> <p>Changed settings become active immediately.</p>	- 0 0 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303B:6 _h Modbus 15116 Profibus 15116 CIP 159.1.6
MON_IO_SelErr2	<p>Second number for the signal output function Selected Error</p> <p>Changed settings become active immediately.</p>	- 0 0 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303B:7 _h Modbus 15118 Profibus 15118 CIP 159.1.7
MON_IO_SelWar1	<p>First number for the signal output function Selected Warning</p> <p>Changed settings become active immediately.</p>	- 0 0 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303B:8 _h Modbus 15120 Profibus 15120 CIP 159.1.8
MON_IO_SelWar2	<p>Second number for the signal output function Selected Warning</p> <p>Changed settings become active immediately.</p>	- 0 0 65535	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 303B:9 _h Modbus 15122 Profibus 15122 CIP 159.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_MainsVolt	<p>Detection and monitoring of mains phases (377)</p> <p>0 / Automatic Mains Detection: Automatic detection and monitoring of mains voltage</p> <p>1 / DC-Bus Only (Mains 1~230 V / 3~480 V): DC bus supply only, corresponding to mains voltage 230 V (single-phase) or 480 V (three phases)</p> <p>2 / DC-Bus Only (Mains 1~115 V / 3~208 V): DC bus supply only, corresponding to mains voltage 115 V (single-phase) or 208 V (three phases)</p> <p>3 / Mains 1~230 V / 3~480 V: Mains voltage 230 V (single-phase) or 480 V (three phases)</p> <p>4 / Mains 1~115 V / 3~208 V: Mains voltage 115 V (single-phase) or 208 V (three phases)</p> <p>Value 0: As soon as a mains voltage detected, the device automatically checks whether the mains voltage is 115 V or 230 V in the case of single-phase devices or 208 V or 400/480 V in the case of three-phase devices.</p> <p>Values 1 ... 2: If the device is supplied only via the DC bus, the parameter has to be set to the voltage value corresponding to the mains voltage of the supplying device. There is no mains voltage monitoring.</p> <p>Values 3 ... 4: If the mains voltage is not detected properly during start-up, the mains voltage to be used can be selected manually.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3005:F _h Modbus 1310 Profibus 1310 CIP 105.1.15
MON_p_dif_load_usr	<p>Maximum load-dependent position deviation (following error) (351)</p> <p>The load-dependent position deviation is the difference between the reference position and the actual position caused by the load.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active immediately.</p>	usr_p 1 16384 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:3E _h Modbus 1660 Profibus 1660 CIP 106.1.62

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_p_dif_load	<p>Maximum load-dependent position deviation (following error) (351)</p> <p>The load-dependent position deviation is the difference between the reference position and the actual position caused by the load.</p> <p>The parameter MON_p_dif_load_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	<p>revolution</p> <p>0.0001 1.0000 200.0000</p>	<p>UINT32 UINT32 UINT32 UINT32 R/W per. -</p>	<p>CANopen 6065:0_h Modbus 1606 Profibus 1606 CIP 106.1.35</p>
MON_p_dif_warn	<p>Maximum load-dependent position deviation (warning) (350)</p> <p>100.0 % correspond to the maximum position deviation (following error) as specified by means of parameter MON_p_dif_load.</p> <p>Changed settings become active immediately.</p>	<p>%</p> <p>0 75 100</p>	<p>UINT16 UINT16 UINT16 UINT16 R/W per. -</p>	<p>CANopen 3006:29_h Modbus 1618 Profibus 1618 CIP 106.1.41</p>
MON_p_DiffWin_usr	<p>Monitoring of position deviation (365)</p> <p>The system checks whether the drive is within the defined deviation during the period set with MON_ChkTime.</p> <p>The status can be output via a parameterizable output.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active immediately.</p>	<p>usr_p</p> <p>0 16 2147483647</p>	<p>INT32 INT32 INT32 INT32 R/W per. -</p>	<p>CANopen 3006:3F_h Modbus 1662 Profibus 1662 CIP 106.1.63</p>
MON_p_DiffWin	<p>Monitoring of position deviation (365)</p> <p>The system checks whether the drive is within the defined deviation during the period set with MON_ChkTime.</p> <p>The status can be output via a parameterizable output.</p> <p>The parameter MON_p_DiffWin_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.0001 revolution.</p> <p>Changed settings become active immediately.</p>	<p>revolution</p> <p>0.0000 0.0010 0.9999</p>	<p>UINT16 UINT16 UINT16 UINT16 R/W per. -</p>	<p>CANopen 3006:19_h Modbus 1586 Profibus 1586 CIP 106.1.25</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_p_win_usr	Standstill window, permissible control deviation (356) The control deviation for the standstill window time must be within this range for a standstill of the drive to be detected. Processing of the standstill window must be activated via the parameter MON_p_winTime. The minimum value, the factory setting and the maximum value depend on the scaling factor. Changed settings become active immediately.	usr_p 0 16 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:40 _h Modbus 1664 Profibus 1664 CIP 106.1.64
MON_p_win	Standstill window, permissible control deviation (356) The control deviation for the standstill window time must be within this range for a standstill of the drive to be detected. Processing of the standstill window must be activated via the parameter MON_p_winTime. The parameter MON_p_win_usr allows you to enter the value in user-defined units. In increments of 0.0001 revolution. Changed settings become active immediately.	revolution 0.0000 0.0010 3.2767	UINT32 UINT16 UINT16 UINT16 R/W per. -	CANopen 6067:0 _h Modbus 1608 Profibus 1608 CIP 106.1.36
MON_p_winTime	Standstill window, time (356) Value 0: Monitoring of standstill window deactivated Value >0: Time in ms during which the control deviation must be in the standstill window Changed settings become active immediately.	ms 0 0 32767	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 6068:0 _h Modbus 1610 Profibus 1610 CIP 106.1.37
MON_p_winTout	Timeout time for standstill window monitoring (356) Value 0: Timeout monitoring deactivated Value >0: Timeout time in ms Standstill window processing values are set via MON_p_win and MON_p_winTime. Time monitoring starts when the target position (reference position of position controller) is reached or when the profile generator has finished processing. Changed settings become active immediately.	ms 0 0 16000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:26 _h Modbus 1612 Profibus 1612 CIP 106.1.38

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_SW_Limits	Monitoring of software limit switches (348) 0 / None: Deactivated 1 / SWLIMP: Activation of software limit switches positive direction 2 / SWLIMN: Activation of software limit switches negative direction 3 / SWLIMP+SWLIMN: Activation of software limit switches both directions Monitoring of software limit switches only works in case of successful homing (ref_ok = 1). Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:3 _h Modbus 1542 Profibus 1542 CIP 106.1.3
MON_swLimN	Negative position limit for software limit switch (348) Refer to description 'MON_swLimP' Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	usr_p - -2147483648 -	INT32 - INT32 INT32 R/W per. -	CANopen 607D:1 _h Modbus 1546 Profibus 1546 CIP 106.1.5
MON_swLimP	Positive position limit for software limit switch (348) If a user-defined value entered is outside of the permissible range, the limit switch limits are automatically set to the maximum user-defined value. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	usr_p - 2147483647 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 607D:2 _h Modbus 1544 Profibus 1544 CIP 106.1.4
MON_tq_win	Torque window, permissible deviation (353) The torque window can only be activated in operating mode Profile Torque. In increments of 0.1 %. Changed settings become active immediately.	% 0.0 3.0 3000.0	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2D _h Modbus 1626 Profibus 1626 CIP 106.1.45
MON_tq_winTime	Torque window, time (353) Value 0: Torque window monitoring deactivated Changing the value causes a restart of torque monitoring. NOTE: Torque window is only used in operating mode Profile Torque. Changed settings become active immediately.	ms 0 0 16383	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2E _h Modbus 1628 Profibus 1628 CIP 106.1.46

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MON_v_DiffWin	Monitoring of velocity deviation (367) The system checks whether the drive is within the defined deviation during the period set with MON_ChkTime. The status can be output via a parameterizable output. Changed settings become active immediately.	usr_v 1 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:1A _h Modbus 1588 Profibus 1588 CIP 106.1.26
MON_v_Threshold	Monitoring of velocity threshold (368) The system checks whether the drive is below the defined value during the period set with MON_ChkTime. The status can be output via a parameterizable output. Changed settings become active immediately.	usr_v 1 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:1B _h Modbus 1590 Profibus 1590 CIP 106.1.27
MON_v_win	Velocity window, permissible deviation (354) Changed settings become active immediately.	usr_v 1 10 2147483647	UINT16 UINT32 UINT32 UINT32 R/W per. -	CANopen 606D:0 _h Modbus 1576 Profibus 1576 CIP 106.1.20
MON_v_winTime	Velocity window, time (354) Value 0: Velocity window monitoring deactivated Changing the value causes a restart of velocity monitoring. Changed settings become active immediately.	ms 0 0 16383	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 606E:0 _h Modbus 1578 Profibus 1578 CIP 106.1.21
MON_v_zeroclamp	Velocity limit for Zero Clamp (338) A Zero Clamp operation is only possible if the reference velocity is below the Zero Clamp velocity limit. Changed settings become active immediately.	usr_v 0 10 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:28 _h Modbus 1616 Profibus 1616 CIP 106.1.40
MSM_CondSequ	Start condition for the start of a sequence via a signal input (269) 0 / Rising Edge: Rising edge 1 / Falling Edge: Falling edge 2 / 1-level: 1 level 3 / 0-level: 0 level The start condition defines the way the start request is to be processed. This setting is used for the first start after activation of the operating mode. Changed settings become active the next time the motor moves.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:8 _h Modbus 11536 Profibus 11536 CIP 145.1.8

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MSM_datasetnum	Selection of data set number in data set table Before an entry in the data set table can be read or written, the corresponding data set number must be selected. Changed settings become active immediately.	- 0 0 127	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302D:10 _h Modbus 11552 Profibus 11552 CIP 145.1.16
MSM_ds_logopera	Logical operator 0 / None: None 1 / Logical AND: Logical AND 2 / Logical OR: Logical OR Transition condition 1 and transition condition 2 can be logically combined. Changed settings become active immediately.	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:1A _h Modbus 11572 Profibus 11572 CIP 145.1.26
MSM_ds_setA	Setting A The value depends on the type of data set as selected with parameter MSM_ds_type: - Move Absolute: Acceleration - Move Relative: Acceleration - Reference Movement: Homing method (except method 35) - Position Setting: Position for Position Setting - Repeat: Loop counter - Move Additive: Acceleration - Move Velocity: Acceleration Changed settings become active immediately.	- -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 302D:12 _h Modbus 11556 Profibus 11556 CIP 145.1.18
MSM_ds_setB	Setting B The value depends on the type of data set as selected with parameter MSM_ds_type: - Move Absolute: Velocity - Move Relative: Velocity - Reference Movement: Position at reference point after a successful reference movement - Position Setting: - - Repeat: Number of data set to be executed - Move Additive: Velocity - Move Velocity: Velocity Changed settings become active immediately.	- -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 302D:13 _h Modbus 11558 Profibus 11558 CIP 145.1.19

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MSM_ds_setC	<p>Setting C</p> <p>The value depends on the type of data set as selected with parameter MSM_ds_type:</p> <ul style="list-style-type: none"> - Move Absolute: Absolute position - Move Relative: Relative position - Reference Movement: - - Position Setting: - - Repeat: - - Move Additive: Relative position - Move Velocity: Selection of direction <p>Value 0: Positive Value 1: Negative Value 2: Current direction</p> <p>Changed settings become active immediately.</p>	- -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 302D:14 _h Modbus 11560 Profibus 11560 CIP 145.1.20
MSM_ds_setD	<p>Setting D</p> <p>The value depends on the type of data set as selected with parameter MSM_ds_type:</p> <ul style="list-style-type: none"> - Move Absolute: Deceleration - Move Relative: Deceleration - Reference Movement: - - Position Setting: - - Repeat: - - Move Additive: Deceleration - Move Velocity: Deceleration <p>Changed settings become active immediately.</p>	- -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 302D:15 _h Modbus 11562 Profibus 11562 CIP 145.1.21
MSM_ds_sub_ds	<p>Subsequent data set</p> <p>Number of the next data set to be started.</p> <p>Changed settings become active immediately.</p>	- 0 0 127	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:17 _h Modbus 11566 Profibus 11566 CIP 145.1.23
MSM_ds_trancon1	<p>Transition condition 1</p> <p>0 / Continue Without Condition: Continue without condition 1 / Wait Time: Wait time 2 / Start Request Edge: Start request edge 3 / Start Request Level: Start request level</p> <p>Changed settings become active immediately.</p>	- 0 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:18 _h Modbus 11568 Profibus 11568 CIP 145.1.24
MSM_ds_trancon2	<p>Transition condition 2</p> <p>0 / Continue Without Condition: Continue without condition 2 / Start Request Edge: Start request edge 3 / Start Request Level: Start request level</p> <p>Changed settings become active immediately.</p>	- 0 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:1C _h Modbus 11576 Profibus 11576 CIP 145.1.28

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MSM_ds_transiti	<p>Transition type</p> <p>0 / No Transition: No transition 1 / Abort And Go Next: Abort and go next 2 / Buffer And Start Next: Buffer and start next 3 / Blending Previous: Blending previous 4 / Blending Next: Blending next</p> <p>Changed settings become active immediately.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:16 _h Modbus 11564 Profibus 11564 CIP 145.1.22
MSM_ds_tranval1	<p>Value for transition condition 1</p> <p>The value depends on the type of data set as selected with parameter MSM_ds_trancon1:</p> <ul style="list-style-type: none"> - Continue Without Condition: No transition condition value - Waiting Time: Value 0 ... 30000: Wait time from 0 ... 30000 in ms - Start Request Edge: Value 0: Rising edge Value 1: Falling edge Value 4: Rising or falling edge - Start Request Level: Value 2: 1 level Value 3: 0 level <p>Changed settings become active immediately.</p>	- 0 0 30000	INT32 INT32 INT32 INT32 R/W per. -	CANopen 302D:19 _h Modbus 11570 Profibus 11570 CIP 145.1.25
MSM_ds_tranval2	<p>Value for transition condition 2</p> <p>The value depends on the type of data set as selected with parameter MSM_ds_trancon2:</p> <ul style="list-style-type: none"> - Continue Without Condition: No transition condition value - Start Request Edge: Value 0: Rising edge Value 1: Falling edge Value 4: Rising or falling edge - Start Request Level: Value 2: 1 level Value 3: 0 level <p>Changed settings become active immediately.</p>	- 0 0 4	INT32 INT32 INT32 INT32 R/W per. -	CANopen 302D:1D _h Modbus 11578 Profibus 11578 CIP 145.1.29

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
MSM_ds_type	<p>Data set type (244)</p> <p>0 / None: None 1 / Move Absolute: Absolute movement 2 / Move Additive: Additive movement 3 / Reference Movement: Reference Movement 4 / Position Setting: Position setting 5 / Repeat: Repeat 6 / Move Relative: Relative movement 7 / Move Velocity: Movement with a defined velocity</p> <p>The values for the selected data set type are specified by means of the parameters MSM_ds_set1 to MSM_ds_set4.</p> <p>Changed settings become active immediately.</p>	- 0 0 7	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 302D:11 _h Modbus 11554 Profibus 11554 CIP 145.1.17
MSM_start_ds	<p>Selection of a data set to be started for operating mode Motion Sequence</p> <p>Changed settings become active immediately.</p>	- 0 0 31	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 301B:A _h Modbus 6932 Profibus 6932 CIP 127.1.10
MT_dismax_usr	<p>Maximum permissible distance</p> <p>If the reference value is active and the maximum permissible distance is exceeded, an error of error class 1 is generated.</p> <p>The value 0 switches off monitoring.</p> <p>The minimum value, the factory setting and the maximum value depend on the scaling factor.</p> <p>Available as of firmware version V01.03</p> <p>Changed settings become active the next time the motor moves.</p>	usr_p 0 16384 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 302E:A _h Modbus 11796 Profibus 11796 CIP 146.1.10
MT_dismax	<p>Maximum permissible distance</p> <p>If the reference value is active and the maximum permissible distance is exceeded, an error of error class 1 is generated.</p> <p>The value 0 switches off monitoring.</p> <p>The parameter MT_dismax_usr allows you to enter the value in user-defined units.</p> <p>In increments of 0.1 revolution.</p> <p>Changed settings become active the next time the motor moves.</p>	revolution 0.0 1.0 999.9	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 302E:3 _h Modbus 11782 Profibus 11782 CIP 146.1.3

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
OFS_PosActivate	Offset movement with relative offset position (228) This parameter starts an offset movement with one the relative offset positions specified by means of the parameters OFSp_RelPos1 and OFSp_RelPos2. Value 0: No offset movement Value 1: Start offset movement with relative offset position 1 (OFSp_RelPos1) Value 2: Start offset movement with relative offset position 2 (OFSp_RelPos2) Changed settings become active immediately.	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3027:B _h Modbus 10006 Profibus 10006 CIP 139.1.11
OFS_Ramp	Acceleration and deceleration for offset movement (228) Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3027:6 _h Modbus 9996 Profibus 9996 CIP 139.1.6
OFSp_abs	Start absolute offset movement Changed settings become active immediately.	Inc -2147483648 - 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 3027:1 _h Modbus 9986 Profibus 9986 CIP 139.1.1
OFSp_rel	Start relative offset movement Changed settings become active immediately.	Inc -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 3027:3 _h Modbus 9990 Profibus 9990 CIP 139.1.3
OFSp_RelPos1	Relative offset position 1 for offset movement (228) Changed settings become active immediately.	Inc -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3027:8 _h Modbus 10000 Profibus 10000 CIP 139.1.8
OFSp_RelPos2	Relative offset position 2 for offset movement (228) Changed settings become active immediately.	Inc -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3027:A _h Modbus 10004 Profibus 10004 CIP 139.1.10
OFSp_SetPos	Set offset position Changed settings become active immediately.	Inc -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W - -	CANopen 3027:5 _h Modbus 9994 Profibus 9994 CIP 139.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
OFsv_target	<p>Target velocity for offset movement (228)</p> <p>The maximum possible value is 5000 if the user-defined scaling factor of the velocity scaling is 1.</p> <p>This applies to all user-defined scaling factors. Example: If the user-defined scaling factor of the velocity scaling is 2 (ScaleVELnum = 2, ScaleVELdenom = 1), the maximum possible value is 2500.</p> <p>Changed settings become active immediately.</p>	usr_v 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3027:4 _h Modbus 9992 Profibus 9992 CIP 139.1.4
p_MaxDifToENC2	<p>Max. permissible deviation of encoder positions</p> <p>The maximum permissible position deviation between the encoder positions is cyclically monitored. If the limit is exceeded, an error is generated.</p> <p>The current position deviation is available via the parameter '_p_DifEnc1ToEnc2'.</p> <p>The default value corresponds to 1/2 motor revolution.</p> <p>The maximum value corresponds to 10 motor revolutions.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	Inc 1 65536 1310720	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3050:7 _h Modbus 20494 Profibus 20494 CIP 180.1.7
PAR_CTRLreset CONF → FCS- rESC	<p>Reset controller parameters</p> <p>0 / No / na: No 1 / Yes / YES: Yes</p> <p>Reset of all controller parameters. The current controller parameters are recalculated on the basis of the motor data of the connected motor.</p> <p>NOTE: Current and velocity limitations are not reset. Therefore, a user parameter reset is required.</p> <p>NOTE: The new settings are not saved to the EEPROM.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3004:7 _h Modbus 1038 Profibus 1038 CIP 104.1.7

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PAR_ScalingStart	<p>Recalculation of parameters with user-defined units</p> <p>The parameters with user-defined units can be recalculated with a changed scaling factor.</p> <p>Value 0: Inactive Value 1: Initialize recalculation Value 2: Start recalculation</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3004:14 _h Modbus 1064 Profibus 1064 CIP 104.1.20
PAReepSave	<p>Save parameter values to EEPROM</p> <p>Value 1: Save all persistent parameters Value 2: Save motion sequence data Value 3: Save all persistent parameters and save motion sequence data</p> <p>The currently set parameters are saved to the non-volatile memory (EEPROM). The saving process is complete when the parameter is read and 0 is returned.</p> <p>Changed settings become active immediately.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3004:1 _h Modbus 1026 Profibus 1026 CIP 104.1.1
PARfactorySet Conf → FLS- rStF	<p>Restore factory settings (default values)</p> <p>No / na: No Yes / YES: Yes</p> <p>All parameters are set to their default values, these are saved to the EEPROM. Restoring the factory settings is possible via the HMI or the commissioning software. The saving process is complete when the parameter is read and 0 is returned.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 - 1	R/W - -	

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PARuserReset CONF → FCS- rESu	<p>Reset user parameters</p> <p>0 / No / na: No 65535 / Yes / YE5: Yes</p> <p>Bit 0: Set persistent user and controller parameters to default values Bit 1: Set Motion Sequence parameters to default values Bits 2 ... 15: Reserved</p> <p>All parameters are reset with the exception of: - Communication parameters - Inversion of direction of movement - Selection of signal type for position interface PTI - Settings of encoder simulation - Functions of digital inputs and outputs</p> <p>NOTE: The new settings are not saved to the EEPROM.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 - 65535	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3004:8 _h Modbus 1040 Profibus 1040 CIP 104.1.8
PBaddress CONF → Conf- CONF → FSu- PbRd	<p>Profibus address</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 1 126 126	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3043:2 _h Modbus 17156 Profibus 17156 CIP 167.1.2
PDOMask	<p>Deactivate receive PDO</p> <p>Value 0: Activate receive PDO Value 1: Deactivate receive PDO</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3040:42 _h Modbus 16516 Profibus 16516 CIP 164.1.66

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg1Mode	<p>Selection of comparison criterion for position register channel 1 (360)</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 1</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 1</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:4 _h Modbus 2824 Profibus 2824 CIP 111.1.4
PosReg1Source	<p>Selection of source for position register channel 1 (359)</p> <p>0 / Pact Encoder 1: Source for position register channel 1 is Pact of encoder 1</p> <p>1 / Pact Encoder 2: Source for position register channel 1 is Pact of encoder 2 (module)</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:6 _h Modbus 2828 Profibus 2828 CIP 111.1.6
PosReg1Start	<p>Start/stop of position register channel 1 (358)</p> <p>0 / Off (keep last state): Position Register channel 1 is off and status bit keeps last state</p> <p>1 / On: Position Register channel 1 is on</p> <p>2 / Off (set state 0): Position Register channel 1 is off and status bit is set to 0</p> <p>3 / Off (set state 1): Position Register channel 1 is off and status bit is set to 1</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300B:2 _h Modbus 2820 Profibus 2820 CIP 111.1.2
PosReg1ValueA	Comparison value A for position register channel 1 (362)	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 300B:8 _h Modbus 2832 Profibus 2832 CIP 111.1.8
PosReg1ValueB	Comparison value B for position register channel 1 (362)	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 300B:9 _h Modbus 2834 Profibus 2834 CIP 111.1.9

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg2Mode	<p>Selection of comparison criterion for position register channel 2 (361)</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 2</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 2</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:5 _h Modbus 2826 Profibus 2826 CIP 111.1.5
PosReg2Source	<p>Selection of source for position register channel 2 (359)</p> <p>0 / Pact Encoder 1: Source for position register channel 2 is Pact of encoder 1</p> <p>1 / Pact Encoder 2: Source for position register channel 2 is Pact of encoder 2 (module)</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:7 _h Modbus 2830 Profibus 2830 CIP 111.1.7
PosReg2Start	<p>Start/stop of position register channel 2 (358)</p> <p>0 / Off (keep last state): Position Register channel 2 is off and status bit keeps last state</p> <p>1 / On: Position Register channel 2 is on</p> <p>2 / Off (set state 0): Position Register channel 2 is off and status bit is set to 0</p> <p>3 / Off (set state 1): Position Register channel 2 is off and status bit is set to 1</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 R/W - -	CANopen 300B:3 _h Modbus 2822 Profibus 2822 CIP 111.1.3
PosReg2ValueA	Comparison value A for position register channel 2 (362)	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:A _h Modbus 2836 Profibus 2836 CIP 111.1.10
PosReg2ValueB	Comparison value B for position register channel 2 (362)	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:B _h Modbus 2838 Profibus 2838 CIP 111.1.11

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg3Mode	<p>Selection of comparison criterion for position register channel 3 (361)</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 3</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 3</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:E _h Modbus 2844 Profibus 2844 CIP 111.1.14
PosReg3Source	<p>Selection of source for position register channel 3 (359)</p> <p>0 / Pact Encoder 1: Source for position register channel 3 is Pact of encoder 1</p> <p>1 / Pact Encoder 2: Source for position register channel 3 is Pact of encoder 2 (module)</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:10 _h Modbus 2848 Profibus 2848 CIP 111.1.16
PosReg3Start	<p>Start/stop of position register channel 3 (359)</p> <p>0 / Off (keep last state): Position Register channel 3 is off and status bit keep last state</p> <p>1 / On: Position Register channel 3 is on</p> <p>2 / Off (set state 0): Position Register channel 3 is off and status bit is set to 0</p> <p>3 / Off (set state 1): Position Register channel 3 is off and status bit is set to 1</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 300B:C _h Modbus 2840 Profibus 2840 CIP 111.1.12
PosReg3ValueA	Comparison value A for position register channel 3 (363)	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:12 _h Modbus 2852 Profibus 2852 CIP 111.1.18
PosReg3ValueB	Comparison value B for position register channel 3 (363)	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:13 _h Modbus 2854 Profibus 2854 CIP 111.1.19

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PosReg4Mode	<p>Selection of comparison criterion for position register channel 4 (362)</p> <p>0 / Pact greater equal A: Current position is greater than or equal to comparison value A for position register channel 4</p> <p>1 / Pact less equal A: Current position is less than or equal to comparison value A for position register channel 4</p> <p>2 / Pact in [A-B] (basic): Current position is in the range A-B including limits (basic)</p> <p>3 / Pact out [A-B] (basic): Current position is out of the range A-B excluding limits (basic)</p> <p>4 / Pact in [A-B] (extended): Current position is in the range A-B including limits (extended)</p> <p>5 / Pact out [A-B] (extended): Current position is out of the range A-B excluding limits (extended)</p> <p>Changed settings become active immediately.</p>	- 0 0 5	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:F _h Modbus 2846 Profibus 2846 CIP 111.1.15
PosReg4Source	<p>Selection of source for position register channel 4 (360)</p> <p>0 / Pact Encoder 1: Source for position register channel 4 is Pact of encoder 1</p> <p>1 / Pact Encoder 2: Source for position register channel 4 is Pact of encoder 2 (module)</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 R/W per. -	CANopen 300B:11 _h Modbus 2850 Profibus 2850 CIP 111.1.17
PosReg4Start	<p>Start/stop of position register channel 4 (359)</p> <p>0 / Off (keep last state): Position Register channel 4 is off and status bit keeps last state</p> <p>1 / On: Position Register channel 4 is on</p> <p>2 / Off (set state 0): Position Register channel 4 is off and status bit is set to 0</p> <p>3 / Off (set state 1): Position Register channel 4 is off and status bit is set to 1</p> <p>Changed settings become active immediately.</p>	- 0 0 3	UINT16 UINT16 UINT16 R/W - -	CANopen 300B:D _h Modbus 2842 Profibus 2842 CIP 111.1.13
PosReg4ValueA	Comparison value A for position register channel 4 (363)	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:14 _h Modbus 2856 Profibus 2856 CIP 111.1.20
PosReg4ValueB	Comparison value B for position register channel 4 (363)	usr_p - 0 -	INT32 INT32 INT32 R/W per. -	CANopen 300B:15 _h Modbus 2858 Profibus 2858 CIP 111.1.21

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PP_ModeRangeLim	<p>Absolute movement beyond movement range (280)</p> <p>0 / NoAbsMoveAllowed: Absolute movement beyond movement range is not possible 1 / AbsMoveAllowed: Absolute movement beyond movement range is possible</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3023:7 _h Modbus 8974 Profibus 8974 CIP 135.1.7
PP_OpmChgType	<p>Change to operating mode Profile Position during movements (209)</p> <p>0 / WithStandStill: Change with standstill 1 / OnTheFly: Change without standstill</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3023:9 _h Modbus 8978 Profibus 8978 CIP 135.1.9
PPoption	<p>Options for operating mode Profile Position (246)</p> <p>Determines the reference position for relative positioning: 0: Relative with reference to the previous target position of the profile generator 1: Not supported 2: Relative with reference to the actual position of the motor</p> <p>Changed settings become active the next time the motor moves.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 60F2:0 _h Modbus 6960 Profibus 6960 CIP 127.1.24
PPp_target	<p>Target position for operating mode Profile Position (245)</p> <p>Minimum/maximum values depend on: - Scaling factor - Software limit switches (if they are activated)</p> <p>Changed settings become active immediately.</p>	usr_p - - - -	INT32 INT32 INT32 INT32 R/W - -	CANopen 607A:0 _h Modbus 6940 Profibus 6940 CIP 127.1.14
PPv_target	<p>Target velocity for operating mode Profile Position (245)</p> <p>The target velocity is limited to the setting in CTRL_v_max and RAMP_v_max.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_v 1 60 -	UINT32 UINT32 UINT32 UINT32 R/W - -	CANopen 6081:0 _h Modbus 6942 Profibus 6942 CIP 127.1.15

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PTI_pulse_filter	<p>Filter time for input signals at the PTI interface</p> <p>A signal at the PTI interface is only evaluated if it is available for a time that is longer than the set filter time. For example, if an interference pulse is available for a period shorter than the set filter time, the interference pulse is not evaluated.</p> <p>The interval between 2 signals must also be greater than the set filter time.</p> <p>In increments of 0.01 µs.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	µs 0.00 0.25 13.00	UINT16 UINT16 UINT16 UINT16 R/W per. expert	CANopen 3005:2F _h Modbus 1374 Profibus 1374 CIP 105.1.47
PTI_signal_type CONF → , -o- , oP, , oP,	<p>Selection of signal type for PTI interface (223)</p> <p>0 / A/B Signals / Ab: Signals ENC_A and ENC_B (quadruple evaluation) 1 / P/D Signals / Pd: Signals PULSE and DIR 2 / CW/CCW Signals / cLcc: Signals CW and CCW</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:2 _h Modbus 1284 Profibus 1284 CIP 105.1.2
PTO_mode CONF → REG- PtoN	<p>Type of usage of PTO interface (291)</p> <p>0 / Off / oFF: PTO interface disabled 1 / Esim pAct Enc 1 / PEn1: Encoder simulation based on actual position of encoder 1 2 / Esim pRef / PrEF: Encoder simulation based on reference position values (_p_ref) 3 / PTI Signal / Pti: Directly the signal from PTI interface 4 / Esim pAct Enc 2 / PEn2: Encoder simulation based on actual position of encoder 2 (module)</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	- 0 0 4	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:1F _h Modbus 1342 Profibus 1342 CIP 105.1.31
PTtq_target	<p>Target torque for operating mode Profile Torque (235)</p> <p>100.0 % correspond to the continuous stall torque _M_M_0.</p> <p>In increments of 0.1 %.</p> <p>Changed settings become active immediately.</p>	% -3000.0 0.0 3000.0	INT16 INT16 INT16 INT16 R/W - -	CANopen 6071:0 _h Modbus 6944 Profibus 6944 CIP 127.1.16

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
PVv_target	Target velocity for operating mode Profile Velocity (242) The target velocity is limited to the setting in CTRL_v_max and RAMP_v_max. Changed settings become active immediately.	usr_v - 0 -	INT32 INT32 INT32 INT32 R/W - -	CANopen 60FF:0 _h Modbus 6938 Profibus 6938 CIP 127.1.13
RAMP_tq_enable	Activation of the motion profile for torque (236) 0 / Profile Off: Profile off 1 / Profile On: Profile on The motion profile for torque can be activated or deactivated for the operating mode Profile Torque. In all other operating modes, the motion profile for torque is inactive. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2C _h Modbus 1624 Profibus 1624 CIP 106.1.44
RAMP_tq_slope	Slope setting of the motion profile for torque (236) 100.0 % correspond to the continuous stall torque _M_M_0. In increments of 0.1 %/s. Changed settings become active immediately.	%/s 0.1 10000.0 3000000.0	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6087:0 _h Modbus 1620 Profibus 1620 CIP 106.1.42
RAMP_v_acc	Acceleration of the motion profile for velocity (309) Writing the value 0 has no effect on the parameter. Changed settings become active the next time the motor moves.	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6083:0 _h Modbus 1556 Profibus 1556 CIP 106.1.10

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RAMP_v_dec	<p>Deceleration of the motion profile for velocity (309)</p> <p>The minimum value depends on the operating mode:</p> <p>Operating modes with minimum value 1: Electronic Gear (velocity synchronisation) Profile Velocity Motion Sequence (Move Velocity)</p> <p>Operating modes with minimum value 120: Jog Profile Position Homing Motion Sequence (Move Absolute, Move Relative, Reference Movement and Move Additive)</p> <p>Writing the value 0 has no effect on the parameter.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_a 1 600 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6084:0 _h Modbus 1558 Profibus 1558 CIP 106.1.11
RAMP_v_enable	<p>Activation of the motion profile for velocity (309)</p> <p>0 / Profile Off: Profile off 1 / Profile On: Profile on</p> <p>The motion profile for velocity can be activated or deactivated for the operating modes Profile Velocity and Electronic Gear (velocity synchronization).</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active immediately.</p>	- 0 1 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:2B _h Modbus 1622 Profibus 1622 CIP 106.1.43
RAMP_v_jerk [onF → dr[- JEr	<p>Jerk limitation of the motion profile for velocity (337)</p> <p>0 / Off / oFF: Off 1 / 1 / 1: 1 ms 2 / 2 / 2: 2 ms 4 / 4 / 4: 4 ms 8 / 8 / 8: 8 ms 16 / 16 / 16: 16 ms 32 / 32 / 32: 32 ms 64 / 64 / 64: 64 ms 128 / 128 / 128: 128 ms</p> <p>Adjustments can only be made if the operating mode is inactive (x_end=1).</p> <p>Changed settings become active the next time the motor moves.</p>	ms 0 0 128	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3006:D _h Modbus 1562 Profibus 1562 CIP 106.1.13

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RAMP_v_max [onF → RLL- onNP	<p>Maximum velocity of the motion profile for velocity (309)</p> <p>If a greater reference speed is set in one of these operating modes, it is automatically limited to RAMP_v_max. This way, commissioning at limited speed is easier to perform.</p> <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_v 1 13200 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 607F:0 _h Modbus 1554 Profibus 1554 CIP 106.1.9
RAMP_v_sym	<p>Acceleration and deceleration of the motion profile for velocity</p> <p>The values are internally multiplied by 10 (example: 1 = 10 min⁻¹/s).</p> <p>Write access changes the values under RAMP_v_acc and RAMP_v_dec. The limit values are checked on the basis of the values indicated for these parameters. Read access returns the greater value from RAMP_v_acc/RAMP_v_dec. If the value cannot be represented as a 16 bit value, the value is set to 65535 (maximum UINT16 value)</p> <p>Changed settings become active the next time the motor moves.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3006:1 _h Modbus 1538 Profibus 1538 CIP 106.1.1
RAMPaccdec	<p>Acceleration and deceleration for the Drive Profile Lexium</p> <p>High word: Acceleration Low word: Deceleration</p> <p>The values are internally multiplied by 10 (example: 1 = 10 min⁻¹/s).</p> <p>Write access changes the values in RAMP_v_acc and RAMP_v_dec. The limit values are checked on the basis of the values indicated for these parameters. If the value cannot be represented as a 16 bit value, the value is set to 65535 (maximum UINT16 value).</p> <p>Changed settings become active the next time the motor moves.</p>	- - - -	UINT32 UINT32 UINT32 UINT32 R/W - -	CANopen 3006:2 _h Modbus 1540 Profibus 1540 CIP 106.1.2
RAMPquickstop	<p>Deceleration ramp for Quick Stop (331)</p> <p>Deceleration ramp for a software stop or an error with error class 1 or 2.</p> <p>Changed settings become active the next time the motor moves.</p>	usr_a 1 6000 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3006:12 _h Modbus 1572 Profibus 1572 CIP 106.1.18

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RESext_P CONF → REG- Pabr	Nominal power of external braking resistor (171) Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	W 1 10 32767	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:12 _h Modbus 1316 Profibus 1316 CIP 105.1.18
RESext_R CONF → REG- rbr	Resistance value of external braking resistor (171) The minimum value depends on the power stage. In increments of 0.01 Ω. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	Ω - 100.00 327.67	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:13 _h Modbus 1318 Profibus 1318 CIP 105.1.19
RESext_ton CONF → REG- tbr	Maximum permissible switch-on time of external braking resistor (172) Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	ms 1 1 30000	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:11 _h Modbus 1314 Profibus 1314 CIP 105.1.17
RESint_ext CONF → REG- E, br	Selection of internal or external braking resistor (171) 0 / Internal Braking Resistor / r_{nt} : Internal braking resistor 1 / External Braking Resistor / r_{ht} : External braking resistor Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:9 _h Modbus 1298 Profibus 1298 CIP 105.1.9
ResolENC2Denom	Resolution of encoder 2, denominator Refer to ResolEnc2Num. Denominator as positive 32 bit number, maximum value 1 million. Setting can only be changed if power stage is disabled. Changed settings become active the next time the power stage is enabled.	revolution 1 1 16383	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3050:5 _h Modbus 20490 Profibus 20490 CIP 180.1.5

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ResolENC2Num	<p>Resolution of encoder 2, numerator</p> <p>Digital encoders: Specification of the encoder increments the external encoder returns for one or several revolutions of the motor shaft. The value is indicated with a numerator and a denominator so that it is possible, for example, to consider the gear ratio of a mechanical gearing. NOTE: The value may not be set to 0.</p> <p>The resolution factor is not applied until this numerator value is specified.</p> <p>Example: One motor revolution causes 1/3 encoder revolution at an encoder resolution of 16384 EncInc/revolution.</p> $\frac{\text{ResolENC2Num}}{\text{ResolENC2Denom}} = \frac{16384 \text{ EncInc}}{3 \text{ revolutions}}$ <p>Analog encoders: Num/Denom must be set equivalent to the number of analog periods per 1 motor revolution.</p> <p>Example: One motor revolution causes 1/3 encoder revolution at an encoder resolution of 16 analog periods per revolution.</p> $\frac{\text{ResolENC2Num}}{\text{ResolENC2Denom}} = \frac{16 \text{ periods}}{3 \text{ revolutions}}$ <p>Setting can only be changed if power stage is disabled.</p> <p>Changed settings become active the next time the power stage is enabled.</p>	<p>EncInc</p> <p>1</p> <p>10000</p> <p>-</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3050:6_h</p> <p>Modbus 20492</p> <p>Profibus 20492</p> <p>CIP 180.1.6</p>
ScalePOSdenom	<p>Position scaling: Denominator (277)</p> <p>Refer to numerator (ScalePOSnum) for a description.</p> <p>A new scaling is activated when the numerator value is supplied.</p> <p>Setting can only be changed if power stage is disabled.</p>	<p>usr_p</p> <p>1</p> <p>16384</p> <p>2147483647</p>	<p>INT32</p> <p>INT32</p> <p>INT32</p> <p>INT32</p> <p>R/W</p> <p>per.</p> <p>-</p>	<p>CANopen 3006:7_h</p> <p>Modbus 1550</p> <p>Profibus 1550</p> <p>CIP 106.1.7</p>

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ScalePOSnum	Position scaling: Numerator (277) Specification of the scaling factor: Motor revolutions ----- User-defined units [usr_p] A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	revolution 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:8 _h Modbus 1552 Profibus 1552 CIP 106.1.8
ScaleRAMPdenom	Ramp scaling: Denominator (279) Refer to numerator (ScaleRAMPnum) for a description. A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled.	usr_a 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:30 _h Modbus 1632 Profibus 1632 CIP 106.1.48
ScaleRAMPnum	Ramp scaling: Numerator (279) Setting can only be changed if power stage is disabled. Changed settings become active immediately.	min ⁻¹ /s 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:31 _h Modbus 1634 Profibus 1634 CIP 106.1.49
ScaleVELdenom	Velocity scaling: Denominator (278) Refer to numerator (ScaleVELnum) for a description. A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled.	usr_v 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:21 _h Modbus 1602 Profibus 1602 CIP 106.1.33
ScaleVELnum	Velocity scaling: Numerator (278) Specification of the scaling factor: Speed of rotation of motor [min ⁻¹] ----- User-defined units [usr_v] A new scaling is activated when the numerator value is supplied. Setting can only be changed if power stage is disabled. Changed settings become active immediately.	min ⁻¹ 1 1 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3006:22 _h Modbus 1604 Profibus 1604 CIP 106.1.34

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
ShiftEncWorkRang	<p>Shifting of the encoder working range (169)</p> <p>0 / Off: Shifting off 1 / On: Shifting on</p> <p>Value 0: Position values are between 0 ... 4096 revolutions.</p> <p>Value 1: Position values are between -2048 ... 2048 revolutions.</p> <p>After activating the shifting function, the position range of a multiturn encoder is shifted for half of the range. Example for the position range of a multiturn encoder with 4096 revolutions.</p> <p>Changed settings become active the next time the product is switched on.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:21 _h Modbus 1346 Profibus 1346 CIP 105.1.33
SimAbsolutePos [onF → RLG- 9Rb5	<p>Simulation of absolute position at power cycling</p> <p>0 / Simulation Off / off: Do not use the last mechanical position after power cycling 1 / Simulation On / on: Use last mechanical position after power cycling</p> <p>This parameter defines the way position values are handled over a power cycle and allows for the simulation of an absolute position encoder using singleturn encoders.</p> <p>If this function is activated, the device saves the relevant position data before a shutdown to restore the mechanical position the next time it is switched on.</p> <p>In the case of singleturn encoders, the position can be restored if the motor shaft is not moved by more than 0.25 revolutions while the drive is off.</p> <p>In the case of multiturn encoders, the permissible shaft movement while the drive is off can be much greater, depending on the type of multiturn encoder.</p> <p>For this function to work, the drive may only be shut down while the motor is at a standstill and the motor shaft must not be moved outside of the permissible range (for example, use a brake).</p> <p>Changed settings become active immediately.</p>	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3005:23 _h Modbus 1350 Profibus 1350 CIP 105.1.35

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
SyncMechStart	<p>Activation of synchronization mechanism</p> <p>Value 0: Deactivate synchronization mechanism</p> <p>Value 1: Activate synchronization mechanism (CANmotion).</p> <p>Value 2: Activate synchronization mechanism, standard CANopen mechanism.</p> <p>The cycle time of the synchronization signal is derived from the parameters intTimPerVal and intTimInd.</p> <p>Changed settings become active immediately.</p>	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3022:5 _h Modbus 8714 Profibus 8714 CIP 134.1.5
SyncMechStatus	<p>Status of synchronization mechanism</p> <p>Status of synchronization mechanism:</p> <p>Value 1: Synchronization mechanism of drive is inactive.</p> <p>Value 32: Drive is synchronizing with external sync signal.</p> <p>Value 64: Drive is synchronized with external sync signal.</p>	- - - -	UINT16 UINT16 UINT16 UINT16 R/- - -	CANopen 3022:6 _h Modbus 8716 Profibus 8716 CIP 134.1.6
SyncMechTol	<p>Synchronization tolerance</p> <p>This parameter is used to increase the synchronization tolerance in the operating mode Interpolated Position. The value is applied when the synchronization mechanism is activated via the parameter SyncMechStart.</p> <p>Changed settings become active immediately.</p> <p>Available as of software version V01.08.</p>	- 1 1 20	UINT16 UINT16 UINT16 UINT16 R/W - -	CANopen 3022:4 _h Modbus 8712 Profibus 8712 CIP 134.1.4

12 Accessories and spare parts

12

12.1 Commissioning tools

Description	Order no.
Commissioning software Lexium CT can be downloaded at: www.schneider-electric.com	-
PC connection kit, serial connection between drive and PC, USB-A to RJ45	TCSMCNAM3M002P
Multiloader, device for copying the parameter settings to a PC or to another drive	VW3A8121
Modbus cable, 1 m, 2 x RJ45	VW3A8306R10
External graphic display terminal	VW3A1101

12.2 Memory cards

Description	Order no.
Memory card for copying parameter settings	VW3M8705
25 memory cards for copying parameter settings	VW3M8704

12.3 Additional modules

Description	Order no.
I/O module IOM1, additional analog and digital inputs and outputs with spring terminals	VW3M3302
Fieldbus module CANopen (module identification CAN) with 2 x RJ45 connection	VW3A3608
Fieldbus module CANopen (module identification CAN) with DE9 D-SUB connection (male)	VW3A3618
Fieldbus module Profibus DP (module identification PDP) with DE9 D-SUB connection (female)	VW3A3607
Fieldbus module DeviceNet (module identification DNT) with Open Style Connection (female)	VW3M3301
Fieldbus module EtherNet/IP (module identification ETH) with 2 x RJ45 connection. For EtherNet/IP and Modbus TCP.	VW3A3616
Fieldbus module EtherCAT (module identification ECT) with 2 x RJ45 connection	VW3A3601
Encoder module RSR (resolver interface) with DE9 D-SUB connection (female)	VW3M3401
Encoder module DIG (digital interface) with HD15 D-SUB connection (female)	VW3M3402
Encoder module ANA (analog interface) with HD15 D-SUB connection (female)	VW3M3403

12.4 Safety module eSM

Description	Order no.
Safety module eSM with safety functions SOS, SLS, SS1, SS2 as per IEC/EN 61800-5-2	VW3M3501
Cable for safety module eSM, 3 m; 24-pin connector, other cable end open	VW3M8801R30
Cable for safety module eSM, 1.5 m; 2 x 24-pin connector	VW3M8802R15
Cable for safety module eSM, 3 m; 2 x 24-pin connector	VW3M8802R30
Connection terminal adapter for eSM safety module, for easy wiring of several safety modules in the control cabinet	VW3M8810
Connector with wire jumper (for INTERLOCK signal) for eSM terminal adapter; 4 pieces	VW3M8820

12.5 Application nameplate

Description	Order no.
Application name plate to be clipped onto the top of the drive, size 38.5 mm x 13 mm for label size 1.5 inches x 0.5 inches, 50 pieces	VW3M2501

12.6 CANopen cable with connectors

Description	Order no.
CANopen cable, 0.3 m, 2 x RJ45	VW3CANCARR03
CANopen cable, 1 m, 2 x RJ45	VW3CANCARR1
2 m, 2 x RJ45, shielded twisted pair cable	490NTW00002
5 m, 2 x RJ45, shielded twisted pair cable	490NTW00005
12 m, 2 x RJ45, shielded twisted pair cable	490NTW00012
2 m, 2 x RJ45, shielded twisted pair cable with UL and CSA 22.1 certification	490NTW00002U
5 m, 2 x RJ45, shielded twisted pair cable with UL and CSA 22.1 certification	490NTW00005U
12 m, 2 x RJ45, shielded twisted pair cable with UL and CSA 22.1 certification	490NTW00012U
CANopen cable, 1 m, D9-SUB (female) to RJ45	TCSCCN4F3M1T
CANopen cable, 1 m, D9-SUB (female) with integrated terminating resistor to RJ45	VW3M3805R010
CANopen cable, 3 m, D9-SUB (female) with integrated terminating resistor to RJ45	VW3M3805R030
CANopen cable, 0.3 m, 2 x D9-SUB (female), LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1)	TSXCANCADD03
CANopen cable, 1 m, 2 x D9-SUB (female), LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1)	TSXCANCADD1
CANopen cable, 3 m, 2 x D9-SUB (female), LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1)	TSXCANCADD3
CANopen cable, 5 m, 2 x D9-SUB (female), LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1)	TSXCANCADD5
CANopen cable, 0.3 m, 2 x D9-SUB (female), flame-retardant, tested as per IEC 60332-2, UL certification	TSXCANCBDD03
CANopen cable, 1 m, 2 x D9-SUB (female), flame-retardant, tested as per IEC 60332-2, UL certification	TSXCANCBDD1
CANopen cable, 3 m, 2 x D9-SUB (female), flame-retardant, tested as per IEC 60332-2, UL certification	TSXCANCBDD3
CANopen cable, 5 m, 2 x D9-SUB (female), flame-retardant, tested as per IEC 60332-2, UL certification	TSXCANCBDD5

12.7 CANopen connectors, distributors, terminating resistors

Description	Order no.
CANopen terminating resistor, 120 Ohm, integrated in RJ45 connector	TCSCAR013M120
CANopen connector with PC interface, D9-SUB (female), with switchable terminating resistor and additional D9-SUB (male) to connect a PC to the bus, PC interface straight, bus cable angled 90°	TSXCANKCDF90TP
CANopen connector, D9-SUB (female), with switchable terminating resistor, angled 90°	TSXCANKCDF90T
CANopen connector, D9-SUB (female), with switchable terminating resistor, straight	TSXCANKCDF180T
Four-port tap, for connection of 4 drop lines to trunk line, 4 x D9-SUB (male) with switchable terminating resistor	TSXCANTDM4
Two-port tap for connection of 2 drop lines to trunk line, with additional commissioning interface, 3 x RJ45 (female), with switchable terminating resistor	VW3CANTAP2

12.8 CANopen cables

Cables with open cable ends are suitable for connection of D-SUB connectors. Observe the cable cross section and the connection cross section of the required connector.

Description	Order no.
CANopen cable, 50 m, [(2 x AWG 22) + (2 x AWG 24)], LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1), both cable ends open	TSXCANCA50
CANopen cable, 100 m, [(2 x AWG 22) + (2 x AWG 24)], LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1), both cable ends open	TSXCANCA100
CANopen cable, 300 m, [(2 x AWG 22) + (2 x AWG 24)], LSZH standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1), both cable ends open	TSXCANCA300
CANopen cable, 50 m, [(2 x AWG 22) + (2 x AWG 24)], flame-retardant, tested as per IEC 60332-2, UL certification, both cable ends open	TSXCANCB50
CANopen cable, 100 m, [(2 x AWG 22) + (2 x AWG 24)], flame-retardant, tested as per IEC 60332-2, UL certification, both cable ends open	TSXCANCB100
CANopen cable, 300 m, [(2 x AWG 22) + (2 x AWG 24)], flame-retardant, tested as per IEC 60332-2, UL certification, both cable ends open	TSXCANCB300
CANopen cable, 50 m, [(2 x AWG 22) + (2 x AWG 24)], flexible LSZH HD standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1), for heavy-duty or flexible installation, oil-resistant, both cable ends open	TSXCANCD50
CANopen cable, 100 m, [(2 x AWG 22) + (2 x AWG 24)], flexible LSZH HD standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1), for heavy-duty or flexible installation, oil-resistant, both cable ends open	TSXCANCD100
CANopen cable, 300 m, [(2 x AWG 22) + (2 x AWG 24)], flexible LSZH HD standard cable (low-smoke, zero halogen, flame-retardant, tested as per IEC 60332-1), for heavy-duty or flexible installation, oil-resistant, both cable ends open	TSXCANCD300

12.9 Adapter cable for encoder signals LXM05/LXM15 to LXM32

Description	Order no.
Encoder adapter cable Molex 10-pin (LXM05) to RJ45 10-pin (LXM32), 1 m	VW3M8111R10
Encoder adapter cable D15-SUB (LXM15) to RJ45 10-pin (LXM32), 1 m	VW3M8112R10

12.10 Cables for PTO and PTI

Description	Order no.
Signal cable 2 x RJ45, PTO to PTI, 0.3 m	VW3M8502R03
Signal cable 2 x RJ45, PTO to PTI, 1.5 m	VW3M8502R15
Signal cable 1 x RJ45, other cable end open, for connecting PTI in the control cabinet, 3 m	VW3M8223R30

12.11 Motor cables

12.11.1 Motor cables 1.5 mm²

For BMH070, BMH100 (flange 70 mm and 100 mm).

Description	Order no.
Motor cable 1.5 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R15
Motor cable 3 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R30
Motor cable 5 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R50
Motor cable 10 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R100
Motor cable 15 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R150
Motor cable 20 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R200
Motor cable 25 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R250
Motor cable 50 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R500
Motor cable 75 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5101R750
Motor cable 25 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5301R250
Motor cable 50 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5301R500
Motor cable 100 m, [(4 x 1.5 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5301R1000

12.11.2 Motor cables 2.5 mm²

For BMH140, (flange 140 mm).

Description	Order no.
Motor cable 1.5 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R15
Motor cable 3 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R30
Motor cable 5 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R50
Motor cable 10 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R100
Motor cable 15 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R150
Motor cable 20 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R200
Motor cable 25 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R250
Motor cable 50 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R500
Motor cable 75 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M23, other cable end open	VW3M5102R750
Motor cable 25 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5302R250
Motor cable 50 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5302R500
Motor cable 100 m, [(4 x 2.5 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5302R1000

12.11.3 Motor cables 4 mm²

For BMH205, (flange 205 mm).

Description	Order no.
Motor cable 3 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R30
Motor cable 5 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R50
Motor cable 10 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R100
Motor cable 15 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R150
Motor cable 20 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R200
Motor cable 25 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R250
Motor cable 50 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R500
Motor cable 75 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; motor end 8-pin circular connector M40, other cable end open	VW3M5103R750
Motor cable 25 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5303R250
Motor cable 50 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5303R500
Motor cable 100 m, [(4 x 4 mm ²) + (2 x 1 mm ²)] shielded; both cable ends open	VW3M5303R1000

12.12 Encoder cables

Suitable for BMH motors:

Description	Order no.
Encoder cable 1.5 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R15
Encoder cable 3 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R30
Encoder cable 5 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R50
Encoder cable 10 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R100
Encoder cable 15 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R150
Encoder cable 20 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R200
Encoder cable 25 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R250
Encoder cable 50 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R500
Encoder cable 75 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; motor end 12-pin circular connector M23, device end 10-pin connector RJ45	VW3M8102R750
Encoder cable 25 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; both cable ends open	VW3M8222R25
Encoder cable 50 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; both cable ends open	VW3M8222R500
Encoder cable 100 m, [3 x (2 x 0.14 mm ²) + (2 x 0.34 mm ²)] shielded; both cable ends open	VW3M8222R1000
D9-SUB (male) connector, for encoder module resolver	AEOCON011
Encoder cable 100 m, [5*(2*0.25 mm ²)] and [1*(2*0.5 mm ²)] shielded; both cable ends open	VW3M8221R1000
Encoder cable 1 m, shielded; HD15 D-SUB (male); other cable end open	VW3M4701
Encoder cable 5 m, shielded; HD15 D-SUB (male); other cable end open	VW3M4705

12.13 Connector

Description	Order no.
Encoder connector (cable end) for motor M23, 5 pcs	VW3M8214
Encoder connector (cable end) for drive RJ45 (10 pins), 5 pcs	VW3M2208
Motor connector (cable end) M23, 1.5 ... 2.5 mm ² , 5 pcs	VW3M8215
Motor connector (cable end) M40, 4 mm ² , 5 pcs	VW3M8217

Tools The tools required for cable assembly can be ordered directly from the manufacturer.

- Crimping tool for encoder connector M23:
Coninvers SF-Z0007 www.coninvers.com
- Crimping tools for encoder connector RJ45 10 pins:
Yamaichi Y-ConTool-11, Y-ConTool-20, Y-ConTool-30
www.yamaichi.com
- Crimping tool for power connector M23/M40:
Coninvers SF-Z0008 www.coninvers.com

12.14 External braking resistors

Description	Order no.
Braking resistor IP65; 10 Ω ; maximum continuous power 400 W; 0.75 m connection cable, UL	VW3A7601R07
Braking resistor IP65; 10 Ω ; maximum continuous power 400 W; 2 m connection cable, UL	VW3A7601R20
Braking resistor IP65; 10 Ω ; maximum continuous power 400 W; 3 m connection cable, UL	VW3A7601R30
Braking resistor IP65; 27 Ω ; maximum continuous power 100 W; 0.75 m connection cable, UL	VW3A7602R07
Braking resistor IP65; 27 Ω ; maximum continuous power 100 W; 2 m connection cable, UL	VW3A7602R20
Braking resistor IP65; 27 Ω ; maximum continuous power 100 W; 3 m connection cable, UL	VW3A7602R30
Braking resistor IP65; 27 Ω ; maximum continuous power 200 W; 0.75 m connection cable, UL	VW3A7603R07
Braking resistor IP65; 27 Ω ; maximum continuous power 200 W; 2 m connection cable, UL	VW3A7603R20
Braking resistor IP65; 27 Ω ; maximum continuous power 200 W; 3 m connection cable, UL	VW3A7603R30
Braking resistor IP65; 27 Ω ; maximum continuous power 400 W; 0.75 m connection cable, UL	VW3A7604R07
Braking resistor IP65; 27 Ω ; maximum continuous power 400 W; 2 m connection cable, UL	VW3A7604R20
Braking resistor IP65; 27 Ω ; maximum continuous power 400 W; 3 m connection cable, UL	VW3A7604R30
Braking resistor IP65; 72 Ω ; maximum continuous power 100 W; 0.75 m connection cable, UL	VW3A7605R07
Braking resistor IP65; 72 Ω ; maximum continuous power 100 W; 2 m connection cable, UL	VW3A7605R20
Braking resistor IP65; 72 Ω ; maximum continuous power 100 W; 3 m connection cable, UL	VW3A7605R30
Braking resistor IP65; 72 Ω ; maximum continuous power 200 W; 0.75 m connection cable, UL	VW3A7606R07
Braking resistor IP65; 72 Ω ; maximum continuous power 200 W; 2 m connection cable, UL	VW3A7606R20
Braking resistor IP65; 72 Ω ; maximum continuous power 200 W; 3 m connection cable, UL	VW3A7606R30
Braking resistor IP65; 72 Ω ; maximum continuous power 400 W; 0.75 m connection cable	VW3A7607R07
Braking resistor IP65; 72 Ω ; maximum continuous power 400 W; 2 m connection cable	VW3A7607R20
Braking resistor IP65; 72 Ω ; maximum continuous power 400 W; 3 m connection cable	VW3A7607R30
Braking resistor IP65; 100 Ω ; maximum continuous power 100 W; 0.75 m connection cable	VW3A7608R07
Braking resistor IP65; 100 Ω ; maximum continuous power 100 W; 2 m connection cable	VW3A7608R20
Braking resistor IP65; 100 Ω ; maximum continuous power 100 W; 3 m connection cable	VW3A7608R30
Braking resistor IP20; 15 Ω ; maximum continuous power 2500 W; connection terminals, UL	VW3A7704
Braking resistor IP20; 10 Ω ; maximum continuous power 2500 W; connection terminals, UL	VW3A7705

12.15 DC bus accessories

Description	Order no.
LXM ATV DC bus connection cable, pre-assembled, 0.1 m, 5 pieces	VW3M7101R01
DC bus connector kit, connector housing and contacts, 10 pieces	VW3M2207

12.16 Mains reactors

Description	Order no.
Mains reactor 1~; 50-60Hz; 7A; 5mH; IP00	VZ1L007UM50
Mains reactor 1~; 50-60Hz; 18A; 2mH; IP00	VZ1L018UM20
Mains reactor 3~; 50-60Hz; 16A; 2mH; IP00	VW3A4553
Mains reactor 3~; 50-60Hz; 30A; 1mH; IP00	VW3A4554

12.17 External mains filters

Description	Order no.
Mains filter 1~; 9 A; 115/230 VAC for LXM32	VW3A4420
Mains filter 1~; 16 A; 115/230 VAC for LXM32	VW3A4421
Mains filter 3~; 15A; 208/400/480VAC for LXM32	VW3A4422
Mains filter 3~; 25A; 208/400/480VAC for LXM32	VW3A4423

12.18 Spare parts connectors, fans, cover plates

Description	Order no.
Connector kit LXM32M: 3 x AC power stage supply (230/400 V _{ac}), 1 x control supply, 3 x digital inputs/outputs (4-pin), 2 x motor (10 A / 24 A), 1 x holding brake	VW3M2203
Cover plate for module slot, spare part to replace broken/lost cover plates, 10 pieces	VW3M2405
Cooling fan kit 40 mm x 40 mm, plastic housing, with connection cable	VW3M2401
Cooling fan kit 60 mm x 60 mm, plastic housing, with connection cable	VW3M2402
Cooling fan kit 80 mm x 80 mm, plastic housing, with connection cable	VW3M2403

13 Service, maintenance and disposal

13



The product may only be repaired by a Schneider Electric customer service center. No warranty or liability is accepted for repairs made by unauthorized persons.

13.1 Service address

If you cannot resolve an error yourself please contact your sales office. Have the following details available:

- Nameplate (type, identification number, serial number, DOM, ...)
- Type of error (with LED flash code or error number)
- Previous and concomitant circumstances
- Your own assumptions concerning the cause of the error

Also include this information if you return the product for inspection or repair.



If you have any questions please contact your sales office. Your sales office staff will be happy to give you the name of a customer service office in your area.

<http://www.schneider-electric.com>

13.2 Maintenance

Check the product for pollution or damage at regular intervals.

13.2.1 Lifetime STO safety function

The STO safety function is designed for a lifetime of 20 years. After this period, the data of the safety function are no longer valid. The expiry date is determined by adding 20 years to the DOM shown on the nameplate of the product.

- This date must be included in the maintenance plan of the system.

Do not use the safety function after this date.

Example

The DOM on the nameplate of the product is shown in the format DD.MM.YY, for example 31.12.08. (31 December 2008). This means: Do not use the safety function after December 31, 2028.

13.3 Replacing devices

⚠ WARNING

UNINTENDED BEHAVIOR

The behavior of the drive system is governed by numerous stored data or settings. Unsuitable settings or data may trigger unexpected movements or responses to signals and disable monitoring functions.

- Do NOT operate the drive system with unknown settings or data.
- Verify that the stored data and settings are correct.
- When commissioning, carefully run tests for all operating states and potential error situations.
- Verify the functions after replacing the product and also after making changes to the settings or data.
- Only start the system if there are no persons or obstructions in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.



Prepare a list with the parameters required for the functions used.

Observe the following procedure when replacing devices.

- ▶ Save all parameter settings. To do so, use a memory card, see chapter 7.8 "Memory Card", page 191, or save the data to a PC using the commissioning software, see chapter 7.5 "Commissioning software", page 147.
- ▶ Switch off all supply voltages. Verify that no voltages are present (safety instructions).
- ▶ Label all connections and remove all connection cables (unlock connector locks).
- ▶ Uninstall the product.
- ▶ Note the identification number and the serial number shown on the product nameplate for later identification.
- ▶ Install the new product as per chapter 6 "Installation".
- ▶ If the product to be installed has previously been used in a different system or application, you must restore the factory settings before commissioning the product.
- ▶ Commission the product as per chapter 7 "Commissioning".

13.4 Replacing modules

⚠ WARNING

UNINTENDED BEHAVIOR

The behavior of the drive system is governed by numerous stored data or settings. Unsuitable settings or data may trigger unexpected movements or responses to signals and disable monitoring functions.

- Do NOT operate the drive system with unknown settings or data.
- Verify that the stored data and settings are correct.
- When commissioning, carefully run tests for all operating states and potential error situations.
- Verify the functions after replacing the product and also after making changes to the settings or data.
- Only start the system if there are no persons or obstructions in the hazardous area.

Failure to follow these instructions can result in death, serious injury or equipment damage.



Prepare a list with the parameters required for the functions used.

See chapter 6.1.1 "Installing and removing modules", page 87 for information on installing and removing modules.

13.5 Changing the motor

⚠ WARNING

UNEXPECTED MOVEMENT

Drive systems may perform unexpected movements because of incorrect connection or other errors.

- Operate the device with approved motors only. Even if motors are similar, different adjustment of the encoder system may be a source of hazards.
- Even if the connectors for power connection and encoder match mechanically, this does NOT imply that they may be used.

Failure to follow these instructions can result in death, serious injury or equipment damage.

- ▶ Switch off all supply voltages. Verify that no voltages are present (safety instructions).
- ▶ Label all connections and uninstall the product.
- ▶ Note the identification number and the serial number shown on the product nameplate for later identification.
- ▶ Install the new product as per chapter 6 "Installation".

If the connected motor is replaced by another motor, the motor data set is read again. If the device detects a different motor type, the controller parameters are recalculated and the HMI displays *fault*. See chapter 10.3.4 "Acknowledging a motor change", page 391 for additional information.

If the motor is replaced, the encoder parameters must also be re-adjusted, see chapter 7.6.9 "Setting parameters for encoder", page 165.

If a motor encoder is connected via encoder 2 (module), a motor replacement is not detected. Observe the information provided in the encoder manual.

Changing the motor type temporarily

- ▶ If you want to operate the new motor type only temporarily via the device, press ESC at the HMI.
- ◁ The newly calculated controller parameters are not saved to the EEPROM. This way, you can resume operation with the original motor using the saved controller parameters.

Changing the motor type permanently

- ▶ If you want to operate the new motor type permanently via this device, press the navigation button at the HMI.
- ◁ The newly calculated controller parameters are saved to the EEPROM.

See also chapter 10.3.4 "Acknowledging a motor change", page 391.

13.6 Shipping, storage, disposal

Note the ambient conditions on page 21.

- | | |
|-----------------|---|
| <i>Shipping</i> | The product must be protected against shocks during transportation. If possible, use the original packaging for shipping. |
| <i>Storage</i> | The product may only be stored in spaces where the specified permissible ambient conditions are met.
Protect the product from dust and dirt. |
| <i>Disposal</i> | The product consists of various materials that can be recycled. Dispose of the product in accordance with local regulations. |

14 Glossary

14

14.1 Units and conversion tables

The value in the specified unit (left column) is calculated for the desired unit (top row) with the formula (in the field).

Example: conversion of 5 meters [m] to yards [yd]
 $5 \text{ m} / 0.9144 = 5.468 \text{ yd}$

14.1.1 Length

	in	ft	yd	m	cm	mm
in	-	/ 12	/ 36	* 0.0254	* 2.54	* 25.4
ft	* 12	-	/ 3	* 0.30479	* 30.479	* 304.79
yd	* 36	* 3	-	* 0.9144	* 91.44	* 914.4
m	/ 0.0254	/ 0.30479	/ 0.9144	-	* 100	* 1000
cm	/ 2.54	/ 30.479	/ 91.44	/ 100	-	* 10
mm	/ 25.4	/ 304.79	/ 914.4	/ 1000	/ 10	-

14.1.2 Mass

	lb	oz	slug	kg	g
lb	-	* 16	* 0.03108095	* 0.4535924	* 453.5924
oz	/ 16	-	* $1.942559 \cdot 10^{-3}$	* 0.02834952	* 28.34952
slug	/ 0.03108095	/ $1.942559 \cdot 10^{-3}$	-	* 14.5939	* 14593.9
kg	/ 0.45359237	/ 0.02834952	/ 14.5939	-	* 1000
g	/ 453.59237	/ 28.34952	/ 14593.9	/ 1000	-

14.1.3 Force

	lb	oz	p	dyne	N
lb	-	* 16	* 453.55358	* 444822.2	* 4.448222
oz	/ 16	-	* 28.349524	* 27801	* 0.27801
p	/ 453.55358	/ 28.349524	-	* 980.7	* $9.807 \cdot 10^{-3}$
dyne	/ 444822.2	/ 27801	/ 980.7	-	/ $100 \cdot 10^3$
N	/ 4.448222	/ 0.27801	/ $9.807 \cdot 10^{-3}$	* $100 \cdot 10^3$	-

14.1.4 Power

	HP	W
HP	-	* 746
W	/ 746	-

14.1.5 Rotation

	min ⁻¹ (RPM)	rad/s	deg./s
min ⁻¹ (RPM)	-	* π / 30	* 6
rad/s	* 30 / π	-	* 57.295
deg./s	/ 6	/ 57.295	-

14.1.6 Torque

	lb-in	lb-ft	oz-in	Nm	kp-m	kp-cm	dyne-cm
lb-in	-	/ 12	* 16	* 0.112985	* 0.011521	* 1.1521	* 1.129*10 ⁶
lb-ft	* 12	-	* 192	* 1.355822	* 0.138255	* 13.8255	* 13.558*10 ⁶
oz-in	/ 16	/ 192	-	* 7.0616*10 ⁻³	* 720.07*10 ⁻⁶	* 72.007*10 ⁻³	* 70615.5
Nm	/ 0.112985	/ 1.355822	/ 7.0616*10 ⁻³	-	* 0.101972	* 10.1972	* 10*10 ⁶
kp-m	/ 0.011521	/ 0.138255	/ 720.07*10 ⁻⁶	/ 0.101972	-	* 100	* 98.066*10 ⁶
kp-cm	/ 1.1521	/ 13.8255	/ 72.007*10 ⁻³	/ 10.1972	/ 100	-	* 0.9806*10 ⁶
dyne-cm	/ 1.129*10 ⁶	/ 13.558*10 ⁶	/ 70615.5	/ 10*10 ⁶	/ 98.066*10 ⁶	/ 0.9806*10 ⁶	-

14.1.7 Moment of inertia

	lb-in ²	lb-ft ²	kg-m ²	kg-cm ²	kp-cm-s ²	oz-in ²
lb-in ²	-	/ 144	/ 3417.16	/ 0.341716	/ 335.109	* 16
lb-ft ²	* 144	-	* 0.04214	* 421.4	* 0.429711	* 2304
kg-m ²	* 3417.16	/ 0.04214	-	* 10*10 ³	* 10.1972	* 54674
kg-cm ²	* 0.341716	/ 421.4	/ 10*10 ³	-	/ 980.665	* 5.46
kp-cm-s ²	* 335.109	/ 0.429711	/ 10.1972	* 980.665	-	* 5361.74
oz-in ²	/ 16	/ 2304	/ 54674	/ 5.46	/ 5361.74	-

14.1.8 Temperature

	°F	°C	K
°F	-	(°F - 32) * 5/9	(°F - 32) * 5/9 + 273.15
°C	°C * 9/5 + 32	-	°C + 273.15
K	(K - 273.15) * 9/5 + 32	K - 273.15	-

14.1.9 Conductor cross section

AWG	1	2	3	4	5	6	7	8	9	10	11	12	13
mm ²	42.4	33.6	26.7	21.2	16.8	13.3	10.5	8.4	6.6	5.3	4.2	3.3	2.6

AWG	14	15	16	17	18	19	20	21	22	23	24	25	26
mm ²	2.1	1.7	1.3	1.0	0.82	0.65	0.52	0.41	0.33	0.26	0.20	0.16	0.13

14.2 Terms and Abbreviations

See chapter 2.7 "Standards and terminology" for information on the pertinent standards on which many terms are based. Some terms and abbreviations may have specific meanings with regard to the standards.

<i>AC</i>	Alternating current
<i>Actual position</i>	Current position of moving components in the drive system.
<i>CAN</i>	(Controller A rea N etwork), standardized open fieldbus as per ISO 11898, allows drives and other devices from different manufacturers to communicate.
<i>CCW</i>	C ounter C lockwise.
<i>CW</i>	C lockwise.
<i>DC</i>	Direct current
<i>DC bus</i>	Circuit that supplies the power stage with energy (direct voltage).
<i>DOM</i>	D ate o f m anufacturing: The nameplate of the product shows the date of manufacture in the format DD.MM.YY or in the format DD.MM.YYYY. Example: 31.12.09 corresponds to December 31, 2009 31.12.2009 corresponds to December 31, 2009
<i>Degree of protection</i>	The degree of protection is a standardized specification for electrical equipment that describes the protection against the ingress of foreign objects and water (for example: IP 20).
<i>Direction of rotation</i>	Rotation of the motor shaft in a positive or negative direction of rotation. Positive direction of rotation is when the motor shaft rotates clockwise as you look at the end of the protruding motor shaft.
<i>Drive system</i>	System consisting of controller, power stage and motor.
<i>EMC</i>	Electromagnetic compatibility
<i>Electronic gear</i>	Calculation of a new output velocity for the motor movement based on the input velocity and the values of an adjustable gear ratio; calculated by the drive system.
<i>Encoder</i>	Sensor for detection of the angular position of a rotating component. Installed in a motor, the encoder shows the angular position of the rotor.
<i>Error</i>	Discrepancy between a computed, observed or measured value or condition and the specified or theoretically correct value or condition.
<i>Error class</i>	Classification of errors into groups. The different error classes allow for specific responses to errors, for example by severity.
<i>Factory setting</i>	Factory settings when the product is shipped
<i>Fatal error</i>	In the case of fatal error, the product is no longer able to control the motor so that the power stage must be immediately disabled.
<i>Fault</i>	Fault is a state that can be caused by an error. Further information can be found in the pertinent standards such as IEC 61800-7, ODVA Common Industrial Protocol (CIP).
<i>Fault reset</i>	A function used to restore the drive to an operational state after a detected error is cleared by removing the cause of the error so that the error is no longer active.

<i>Holding brake</i>	The holding brake in the motor has the task of holding the current motor position when the power stage is disabled, even if external forces act (for example, in the case of a vertical axis). The holding brake is not a safety function. The signals of the holding brake meet the PELV requirements.
<i>I/O</i>	Inputs/outputs
<i>I²t monitoring</i>	Anticipatory temperature monitoring. The expected temperature rise of components is calculated in advance on the basis of the motor current. If a limit value is exceeded, the drive reduces the motor current.
<i>IT mains</i>	Mains in which all active components are isolated from ground or are grounded by a high impedance. IT: isol�� terre (French), isolated ground. Opposite: Grounded mains, see TT/TN mains
<i>Inc</i>	Increments
<i>Index pulse</i>	Signal of an encoder to reference the rotor position in the motor. The encoder returns one index pulse per revolution.
<i>Internal units</i>	Resolution of the power stage at which the motor can be positioned. Internal units are specified in increments.
<i>Limit switch</i>	Switches that signal overtravel of the permissible range of travel.
<i>NMT</i>	Network Management (NMT), part of the CANopen communication profile; tasks include initialization of the network and devices, starting, stopping and monitoring of devices
<i>Node guarding</i>	Monitoring of the connection to the slave at an interface for cyclic data traffic.
<i>PC</i>	Personal Computer
<i>PELV</i>	Protective Extra Low Voltage, low voltage with isolation. For more information: IEC 60364-4-41
<i>PLC</i>	Programmable logic controller
<i>Parameter</i>	Device data and values that can be read and set (to a certain extent) by the user.
<i>Persistent</i>	Indicates whether the value of the parameter remains in the memory after the device is switched off.
<i>Power stage</i>	The power stage controls the motor. The power stage generates current for controlling the motor on the basis of the positioning signals from the controller.
<i>Profibus</i>	Standardized open fieldbus as per EN 50254-2 which allows drives and other devices from different manufacturers to communicate.
<i>Pulse/direction signals</i>	Digital signals with variable pulse frequencies which signal changes in position and direction of movement via separate signal wires.
<i>Quick Stop</i>	Function which can be used for fast deceleration of the motor via a command or in the event of an error.
<i>RCD</i>	RCD residual current device.
<i>rms</i>	"Root Mean Square" value of a voltage (V_{rms}) or a current (A_{rms})
<i>RS485</i>	Fieldbus interface as per EIA-485 which enables serial data transmission with multiple devices.
<i>Scaling factor</i>	This factor is the ratio between an internal unit and a user-defined unit.

<i>TT mains, TN mains</i>	Grounded mains, differ in terms of the ground connection (PE conductor connection). Opposite: Ungrounded mains, see IT mains.
<i>User-defined unit</i>	Unit whose reference to motor movement can be determined by the user via parameters.
<i>Warning</i>	If the term is used outside the context of safety instructions, a warning alerts to a potential problem that was detected by a monitoring function. A warning does not cause a transition of the operating state.

15 Index

15

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