

SIEMENS

SINAMICS

SINAMICS S List Manual

Manual

Valid for

Drive

SINAMICS S

Firmware version

2.4

Foreword

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Safety Guidelines

This manual contains notices you have to observe in order to ensure your personal safety, as well as to prevent damage to property. The notices referring to your personal safety are highlighted in the manual by a safety alert symbol, notices referring to property damage only have no safety alert symbol. These notices shown below are graded according to the degree of danger.



Danger

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



Warning

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



Caution

with a safety alert symbol, indicates that minor personal injury can result if proper precautions are not taken.

Caution

without a safety alert symbol, indicates that property damage can result if proper precautions are not taken.

Notice

indicates that an unintended result or situation can occur if the corresponding information is not taken into account.

If more than one degree of danger is present, the warning notice representing the highest degree of danger will be used. A notice warning of injury to persons with a safety alert symbol may also include a warning relating to property damage.

Qualified Personnel

The device/system may only be set up and used in conjunction with this documentation. Commissioning and operation of a device/system may only be performed by **qualified personnel**. Within the context of the safety notes in this documentation qualified persons are defined as persons who are authorized to commission, ground and label devices, systems and circuits in accordance with established safety practices and standards.

Prescribed Usage

Note the following:



Warning

This device may only be used for the applications described in the catalog or the technical description and only in connection with devices or components from other manufacturers which have been approved or recommended by Siemens. Correct, reliable operation of the product requires proper transport, storage, positioning and assembly as well as careful operation and maintenance.

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Disclaimer of Liability

We have reviewed the contents of this publication to ensure consistency with the hardware and software described. Since variance cannot be precluded entirely, we cannot guarantee full consistency. However, the information in this publication is reviewed regularly and any necessary corrections are included in subsequent editions.

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Technical data subject to change

Foreword

SINAMICS documentation

The SINAMICS documentation is sub-divided into 2 areas:

- General documentation/catalogs
- Manufacturer/service documentation

A current overview of the documentation in the available languages is provided in the Internet:

<http://www.siemens.com/motioncontrol>

Follow menu items – "Support" -> "Technical Documentation" -> "Overview of Publications".

The Internet edition of DOConCD, DOConWEB, are available in the Internet:

<http://www.automation.siemens.com/doconweb>

Information on the range of training courses and FAQs (Frequently Asked Questions) are available in the Internet:

<http://www.siemens.com/motioncontrol>

Follow the menu item "Support"

Phases of use and their tools/documents (example)

Table Foreword-1 Phases of use and the available tools/documents

Phases of use	Tools/documents
Orientation	SINAMICS S sales documentation
Planning/engineering	SIZER engineering tool Configuration Manuals, Motors
Select/order	SINAMICS S Catalogs
Configuring/installation	<ul style="list-style-type: none">• SINAMICS S120 Equipment Manual for Control Units and Supplementary System Components• SINAMICS S120 Equipment Manual for Booksize Power Units• SINAMICS S120 Equipment Manual for Chassis Power Units• SINAMICS S150 Operating Instructions

Table Foreword-1 Phases of use and the available tools/documents, continued

Phases of use	Tools/documents
Commissioning	<ul style="list-style-type: none"> • STARTER Parameterizing and Commissioning Tool • SINAMICS S120 Getting Started • SINAMICS S120 Commissioning Manual • SINAMICS S120 Commissioning Manual CANopen • SINAMICS S120 Function Manual • SINAMICS S List Manual • SINAMICS S150 Operating Instructions
Using/operating	<ul style="list-style-type: none"> • SINAMICS S120 Commissioning Manual • SINAMICS S List Manual • SINAMICS S150 Operating Instructions
Service/maintenance	<ul style="list-style-type: none"> • SINAMICS S120 Commissioning Manual • SINAMICS S List Manual • SINAMICS S150 Operating Instructions

Target group

This documentation is aimed at machine manufacturers, commissioning engineers, and service personnel who use SINAMICS.

Benefits

This documentation contains the comprehensive information about parameters, function diagrams and faults and alarms required to commission and service the system.

It must be used as a supplementary document to the other manuals and tools available for the product.

Standard scope

This documentation only describes the functionality of the standard version. Extensions or changes made by the machine tool manufacturer and documented by the machine tool manufacturer.

Other functions not described in this documentation might be able to be executed in the drive system. However, no claim can be made regarding the availability of these functions when the equipment is first supplied or in the event of servicing.

For reasons of clarity, this documentation does not contain all of the detailed information on all of the product types. This documentation cannot take into consideration every conceivable type of installation, operation and service/maintenance.

Finding Your Way Around

The following guides are provided to help you locate information in this manual:

1. Table of Contents
 - General table of contents for complete manual (after the preface).
 - Table of contents for function diagrams (see Section 2.1).
2. List of Abbreviations
3. References
4. Index

Technical Support

If you have any questions, please get in touch with our Hotline:

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Note:

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

<http://www.siemens.com/automation/service&support>

Questions on the manual

Please send any questions regarding the technical documentation (e.g., suggestions for improvement, corrections) to the following fax number or email address:

Fax: +49 (0) 9131 / 98 - 63315
E-Mail: motioncontrol.docu@siemens.com
Fax form: refer to the feedback sheet at the end of the documentation

Internet address for SINAMICS

<http://www.siemens.com/sinamics>

EC Declaration of Conformance

The EC Declaration of Conformance regarding the EMC Directives is available as follows:

- Internet
<http://www.ad.siemens.de/csinfo>
Product/Order No.: 15257461
- Siemens regional office
From the responsible regional offices of the A&D MC business division of Siemens AG.

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Parameters

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1.1 Overview of parameters

1.1.1 Explanation of list of parameters

Basic structure of parameter descriptions

The data in the following example has been chosen at random. The table below shows all the information which can be included in the description of a parameter. Some of the information is optional.

The structure of the parameter list (see Chapter 1.2) is as follows:

----- **Start of example** -----

pxxxx[0...n]	BICO: Full parameter name / Abbreviated name				
Drive object (Function Module)	Changeable in: C1(x), C2(x), U, T				Access level: 2
	Data type: Integer16		Dynamic index: CDS, p0170		Function diagram: 2080
	P group: Cl.-lp. control		Unit group: 7_1		Unit selection: p0505
	Min		Max		Factory setting
	0.00 [Nm]		10.00 [Nm]		2.00 [Nm]
Description:	Text				
Values:	0: Name and meaning of value 0 1: Name and meaning of value 1 2: Name and meaning of value 2 etc.				
Recommendation:	Text				
Index:	[0] = Name and meaning of index 0 [1] = Name and meaning of index 1 [2] = Name and meaning of index 2 etc.				
Bit array:	Bit	Signal name	1-signal	0-signal	FP
	00	Name and meaning of bit 0	Yes	No	8010
	01	Name and meaning of bit 1	Yes	No	-
	02	Name and meaning of bit 2 etc.	Yes	No	8012
Depends on:	Text See also: pxxxx, rxxxx See also: Fxxxx, Axxxx				
Danger!	Corresponds to safety notice "Danger with warning triangle".				
Warning!	Corresponds to safety notice "Warning with warning triangle".				
Caution!	Corresponds to safety notice "Caution with warning triangle".				
Caution:	Corresponds to safety notice "Caution without warning triangle".				
Notice:	Corresponds to safety notice "Notice without warning triangle".				
Note:	Information which might be useful.				

----- **End of example** -----

pxxxx[0...n] Parameter number

The parameter number consists of a "p" or "r", followed by the parameter number and the index (optional).

Examples of number representation in the parameter list:

- p... Adjustable parameter (read and write parameter)
- r... Visualization parameters (read-only)
- p0918 Adjustable parameter 918
- p0099[0...3] Adjustable parameter 99, indices 0 to 3
- p1001[0...n] Adjustable parameter 1001, indices 0 to n (n = configurable)
- r0944 Visualization parameter 944

Other examples of notation in the documentation:

- p1070[1] Adjustable parameter 1070, index 1
- p2098[1].3 Adjustable parameter 2098, index 1 bit 3
- r0945[2](3) Visualization parameter 945, index 2 of drive object 3
- p0795.4 Adjustable parameter 795, bit 4

The following applies to adjustable parameters:

The "shipped" parameter value is specified under "Factory setting" with the relevant unit in square parenthesis. The value can be adjusted within the range defined by "Min" and "Max".

The term "linked parameterization" is used in cases where changes to adjustable parameters affect the settings of other parameters.

Linked parameterization can occur, for example, as a result of the following actions or parameters:

- Execute macros
p0015, p0700, p1000, p1500
- Set PROFIBUS telegram (BICO interconnection)
p0922
- Set component lists
p0230, p0300, p0301, p0400
- Calculate and preset automatically
p0112, p0340, p0578, p3900
- Restore factory settings
p0970

The following applies to visualization parameters:

The fields "Min", "Max" and "Factory setting" are specified with a dash "-" and the relevant unit in square parenthesis.

BICO: Full parameter name/Abbreviated name

Some parameters have the following abbreviations in front of their name:

- **BI:** Binector input
This parameter is used for selecting the source of a digital signal.
- **BO:** Binector output
This parameter is available as a digital signal for interconnection with other parameters.
- **CI:** Connector input
This parameter is used for selecting the source of an analog signal.
- **CO:** Connector output
This parameter is available as an "analog" signal for interconnection with other parameters.
- **CO/BO:** Connector/binector output
This parameter is available as an "analog" and digital signal for interconnection with other parameters.

Drive object (Function Module)

A drive object (DO) is an independent, "self-contained" functional unit which possesses its own parameters and, in some cases, faults and warnings.

When carrying out commissioning using the commissioning software, you can select/deselect additional functions and their parameters by activating/deactivating Function Modules accordingly.

Note:

References: /IH1/ SINAMICS S120 Commissioning Manual

The parameter list specifies the associated drive object and Function Module for each individual parameter.

Examples:

- **p1070 CI: Main setpoint**
SERVO (extended setpoint), VECTOR
The parameter is available only in association with drive object SERVO and the "Extended setpoint channel" Function Module or with drive object VECTOR irrespective of activated Function Modules.
- **p1055 BI: Jog bit 0**
SERVO, VECTOR
The parameter is available in association with drive objects SERVO and VECTOR irrespective of activated Function Modules, i.e. it is available with every activated Function Module belonging to the drive object.

A parameter can belong to either one, several, or all drive objects.

The following information relating to "Drive object" and "Function Module" can be displayed under the parameter number:

Table 1-1 Data in "Drive object (Function Module)" field

Drive object (Function Module)	Meaning
All objects	This parameter belongs to all drive objects.
A_INF	Active Infeed closed-loop control Closed-loop-controlled, self-commutated infeed/regenerative feedback unit for generating a constant DC-link voltage.
A_INF (parallel)	Active Infeed with "Parallel connection" function module (r0108.15).
A_INF (RKA)	Active Infeed with "Cooling system" function module (r0108.28).
A_INF (CBE)	Active Infeed with "CBE COMMUNICATION BOARD" function module (r0108.31).
B_INF	Basic Infeed closed-loop control Unregulated line infeed unit (without feedback) for rectifying the line voltage of the DC Link.
B_INF (parallel)	Basic Infeed with "Parallel connection" function module (r0108.15).
B_INF (RKA)	Basic Infeed with "Cooling system" function module (r0108.28).
B_INF (CBE)	Basic Infeed with "CBE COMMUNICATION BOARD" function module (r0108.31).
S_INF	Smart Infeed closed-loop control Unregulated line infeed/feedback unit for generating the DC link voltage.
S_INF (parallel)	Smart Infeed with "Parallel connection" function module (r0108.15).
S_INF (CBE)	Smart Infeed with "CBE COMMUNICATION BOARD" function module (r0108.31).
CU	Control Unit, all versions.
CU(CAN)	Control Unit with "CAN" function module
CU_S	Control Unit SINAMICS S (SINAMICS S120/S150).
CU_S (CAN)	Control Unit SINAMICS S with "CAN" function module.
CU_CX32	Controller Extension to boost processing performance.
CU_LINK	Object for Controller Extension 32 (CX32).
CU_I	Control Unit SINAMICS Integrated (SIMOTION D4xx only)
SERVO	Servo drive.
SERVO (extended setpoint)	Servo drive with "Extended setpoint channel" function module (r0108.8).
SERVO (Lin)	Servo drive with "Linear motor" function module (r0108.12).
SERVO (Safety rot)	Servo drive with "Safety rotary axis" function module (r0108.13).
SERVO (ext. brake)	Servo drive with "Extended brake control" function module (r0108.14).

Table 1-1 Data in "Drive object (Function Module)" field, continued

Drive object (Function Module)	Meaning
SERVO (Tech_ctrl)	Servo drive with "Technology controller" function module (r0108.16).
SERVO (extended reports)	Servo drive with "Extended reports/monitors" function module (r0108.17).
SERVO (RKA)	Servo drive with "Cooling System" function module (r0108.28).
SERVO(CAN)	Servo drive with "CAN" function module (r0108.29).
SERVO (CBE)	Servo drive with "CBE COMMUNICATION BOARD" function module (r0108.31).
TB30	Terminal Board 30.
TM15	Terminal Module 15 (SIMOTION D4xx only).
TM15DI/DO	Terminal Module 15 (for SINAMICS).
TM17	Terminal Module 17 (SIMOTION D4xx only).
TM31	Terminal Module 31.
TM41	Terminal Module 41.
VECTOR	Vector drive.
VECTOR (n/M)	Vector drive with "Closed-loop speed/torque control" function module (r0108.2).
VECTOR (ext. brake)	Vector drive with "Extended brake control" function module (r0108.14).
VECTOR (parallel)	Vector drive with "Parallel connection" function module (r0108.15).
VECTOR (Tech_ctrl)	Vector drive with "Technology controller" function module (r0108.16).
VECTOR (ext. mess.)	Vector drive with "Extended reports/monitors" function module (r0108.17).
VECTOR (RKA)	Vector drive with "Cooling system" function module (r0108.28).
VECTOR (CBE)	Vector drive with "CBE COMMUNICATION BOARD" Function Module (r0108.31).

Note:

References: //H1/ SINAMICS S120 Installation and Start-Up Manual
 "Drive Objects" section
 "Function Modules" section

Changeable in

The "-" sign indicates that the parameter can be changed in any object state and that the change will be effective immediately.

The letters "C1(x), C2(x), T, U" ((x): mean that the parameter can be changed only in the specified drive object state and that the change will not take effect until the object switches to another state. This can be one or more states.

The following states may be specified:

- C1(x) Device commissioning C1: **Commissioning 1**
 Converter commissioning is in progress (p0009>0).
 Pulses cannot be enabled.
 The parameter can only be changed in the following device commissioning settings (p0009 > 0):
 - C1: Changeable for all settings p0009 > 0.
 - C1(x): Only changeable when p0009 = x.
 A modified parameter value does not take effect until converter commissioning mode is exited with p0009 = 0.

- C2(x) Drive object commissioning C2: **Commissioning 2**
 Drive commissioning is in progress (p0009 = 0 and p0010 > 0).
 Pulses cannot be enabled.
 The parameter can only be changed in the following drive commissioning settings (p0010 > 0):
 - C2: Changeable for all settings p0010 > 0.
 - C2(x): Only changeable when p0010 = x.
 A modified parameter value does not take effect until drive commissioning mode is exited with p0010 = 0.

- U Operation U: **Run**
 Pulses are enabled.

- T Ready T: **Ready to run**
 The pulses are not enabled and status "C1(x)" or "C2(x)" is not active.

Note:

Parameter p0009 is CU-specific (belongs to Control Unit).

Parameter p0010 is drive-specific (belongs to each drive object).

The operating status of individual drive objects is displayed in r0002.

Access level (refers only to access via Basic Operator Panel)

Specifies the access level required to be able to display and change the relevant parameter. The required access level can be set via p0003.

The system uses the following access levels:

1. Standard
2. Extended
3. Expert
4. Service

Please contact your local Siemens office for the password for parameters with access level 4 (service).

5. Macro (the parameter can only be changed via macro)

Note:

Parameter p0003 is CU-specific (belongs to Control Unit).

Data type

The possible data types of parameter values are as follows:

- I8 Integer8 8-bit integer
- I16 Integer16 16-bit integer
- I32 Integer32 32-bit integer
- U8 Unsigned8 8 bits without sign
- U16 Unsigned16 16 bits without sign
- U32 Unsigned32 32 bits without sign
- Float FloatingPoint32 32-bit floating point number

Dynamic index

For parameters with a dynamic index [0...n], the following information is specified here:

- Data set (if available).
- Parameters for the number of indices (n = number - 1).

The following information can be contained in this field:

- "CDS, p0170" (Command Data Set, CDS count)

Example:

p1070[0] → main setpoint [command data set 0]

p1070[1] → main setpoint [command data set 1], etc.

- "DDS, p0180" (Drive Data Set, DDS count)
- "EDS, p0140" (Encoder Data Set, EDS count)
- "MDS, p0130" (Motor Data Set, MDS count)
- "PDS, p0120" (Power unit Data Set, PDS count)
- "p2615" (number of traversing blocks)

Note:

Information on the data sets can be taken from the following references:

References: /IH1/ SINAMICS S120 Installation and Start-Up Manual
"Data sets" section

Function diagram

The parameter is included in this function diagram. The structure of the parameter function and its interrelationship with other parameters is shown in the specified function diagram.

Example:

Function diagram: 3060.3	3060:	Function diagram number
	3:	Signal path (optional)

P group (refers only to access via BOP (Basic Operator Panel))

Specifies the functional group to which the parameter belongs. The required parameter group can be set via p0004.

Note:

Parameter p0004 is CU-specific (belongs to Control Unit).

Unit, unit group and unit choice

The standard units of a parameter is specified in square brackets after the values for "Min", "Max" and "Factory setting".

For parameters where the units can be changed-over, for "Unit group" and "Unit choice" it is specified as to which group this parameter belongs and with which parameter the units can be changed over.

Example:

Unit Group: 7_1, Unit Choice: p0505

The parameter belongs to Unit Group 7_1 and the units can be changed-over using p0505.

Note:

Detailed information on changing-over units can be taken from the following references:

References: /FH1/ SINAMICS S120 Function Manual

References: /BA3/ SINAMICS S150 Operating Instructions

We have listed all possible unit groups together with the unit choice available in the following.

Table 1-2 Unit groups (p0100)

Unit group	Unit choice with p0100 =		Reference with %
	0	1	
7_4	Nm	lbf ft	-
8_4	N	lbf	-
14_2	W	HP	-
14_6	kW	HP	-
25_1	kgm ²	lb ft ²	-
27_1	kg	lb	-
28_1	Nm/A	lbf ft/A	-
29_1	N/Aeff	lbf/Aeff	-
30_1	m	ft	-

Table 1-3 Unit groups (p0349)

Unit group	Unit choice with p0349 =		Reference with %
	1	2	
15_1	mH	%	$\frac{1000 \cdot p0304}{2 \cdot \pi \cdot \sqrt{3} \cdot p0305 \cdot p0310}$
16_1	Ohm	%	$\frac{p0304}{\sqrt{3} \cdot p0305}$

Table 1-4 Unit groups (p0505)

Unit group	Unit choice with p0505 =				Reference with %
	1	2	3	4	
2_1	Hz	%	Hz	%	p2000
2_2	kHz	%	kHz	%	p2000
3_1	1/min	%	1/min	%	p2000
4_1	m/min	%	ft/min	%	p2000
4_2	m/min	m/min	ft/min	ft/min	-
5_1	Veff	%	Veff	%	p2001
5_2	V	%	V	%	p2001
5_3	V	%	V	%	p2001
6_1	mAeff	%	mAeff	%	p2002
6_2	Aeff	%	Aeff	%	p2002
6_3	mA	%	mA	%	p2002
6_4	A	%	A	%	p2002
6_5	A	%	A	%	p2002
7_1	Nm	%	lbf ft	%	p2003
7_2	Nm	Nm	lbf ft	lbf ft	-
7_3	Nm	%	lbf ft	%	1.0
8_1	N	%	lbf	%	p2003
8_2	N	N	lbf	lbf	-
8_3	N	%	lbf	%	1.0
14_1	W	%	HP	%	r2004
14_3	W	%	HP	%	r2004
14_4	W	%	HP	%	r2004
14_5	kW	%	HP	%	r2004
14_7	kW	%	HP	%	r2004
14_8	kW	%	HP	%	r2004

Table 1-4 Unit groups (p0505), continued

Unit group	Unit choice with p0505 =				Reference with %
	1	2	3	4	
14_9	W	W	HP	HP	-
14_10	kW	kW	HP	HP	-
17_1	Nms/rad	%	lbf ft s/rad	%	p2000/p2003
18_1	V/A	%	V/A	%	p2002/p2001
19_1	A/V	%	A/V	%	p2001/p2002
21_1	°C	°C	°F	°F	-
21_2	K	K	°F	°F	-
22_1	m/s ²	m/s ²	ft/s ²	ft/s ²	-
23_1	Veff s/m	Veff s/m	Veff s/ft	Veff s/ft	-
24_1	Ns/m	Ns/m	lbf s/ft	lbf s/ft	-
24_2	Ns/m	%	lbf s/ft	%	p2000/p2003
26_1	m/s ³	m/s ³	ft/s ³	ft/s ³	-

Table 1-5 Unit group (p0595)

Unit group	Unit choice with p0595 =		Reference with %
	Value	Unit	
9_1	The settable values and technological units are displayed p0595 (see Chapter 1.2).		

Parameter values

Min Minimum value of the parameter [unit]

Max Maximum value of the parameter [unit]

Factory setting Shipped value (default) [unit]

A different value may be displayed for certain parameters (e.g. p1800) at the initial commissioning stage.

Reason:

The setting of these parameters is determined by the operating environment of the Control Unit (e.g. depending on converter type, macro, Power Module).

Note:

For SINAMICS G150/G130/S150, the macros and their settings are provided in the following documentation:

References: /BAx/ x = 1, 2, 3
SINAMICS G150/G130/S150 Operating Instructions

Description

Explanation of the function of a parameter.

Values

Lists the possible values of a parameter.

Recommendation

Information about recommended settings.

Index

The name and meaning of each individual index is specified for indexed parameters.

The following applies to the values (min, max, factory setting) of indexed setting parameters:

- Min, Max:
The setting range and unit apply to all indices.
- Factory setting:
When all indices have the same factory setting, index 0 is specified with unit to represent all indices.

When the indices have different factory settings, they are all listed individually with unit.

Bit field

For parameters with bit fields, the following information is provided about each bit:

- Bit number and signal name
- Meaning with signal states 0 and 1
- Function diagram (optional)
The signal is shown on this function diagram.

Dependency

Conditions which need to be fulfilled in connection with this parameter. Also includes special effects which can occur between this parameter and others.




See also: List of other relevant parameters.

Safety-related information

Important information which must be heeded to avoid the risk of physical injury or property damage.

Information which must be observed to avoid problems.

Information which the user or operator may find useful.

Danger!	Corresponds to		Danger
Warning!	Corresponds to		Alarm
Caution!	Corresponds to		Caution
Caution:	Corresponds to		Caution
Notice:	Corresponds to		Notice

Note:

A description of individual safety notices can be found in the appendix to this manual (see **Safety Guidelines**).

1.1.2 Numerical ranges of parameters

Parameters are grouped into the following numerical ranges:

Table 1-6 Numerical Ranges of Parameters

Section		Description
from	to	
0000	0099	Operation and visualization
0100	0199	Commissioning
0200	0299	Power unit
0300	0399	Motor
0400	0499	Encoder
0500	0599	Technology and units
0600	0699	Thermal motor protection and motor model, maximum current
0700	0799	Command sources and terminals on Control Unit, measuring sockets
0800	0839	CDS, DDS data sets (e.g. switch over, copy)
0840	0879	Sequential control (e.g. source for ON/OFF1)
0880	0899	Control and status words
0900	0999	PROFIBUS/PROFIdrive
1000	1199	Setpoint Channel
1200	1299	Functions (e.g. motor holding brake)
1300	1399	V/f control
1400	1799	Closed-loop control
1800	1899	Gating unit
1900	1999	Power Module and motor identification
2000	2099	Communication (PROFIBUS)
2100	2199	Faults and alarms, monitoring functions
2200	2399	Technology controller
2900	2930	Fixed values (e.g. per cent, torque)
3400	3699	Infeed control (Active Line Module)
3900	3999	Management parameters
4000	4199	Terminal Boards, Terminal Modules (e.g. TB30, TM31)
4200	4399	Terminal Modules (e.g. TM15, TM17)
6500	6599	External reports
7000	7499	Parallel connection of Power Modules
7800	7899	EEPROM read/write parameters
8600	8799	CAN bus
8800	8899	Communication Board

Table 1-6 Numerical Ranges of Parameters, continued

Section		Description
from	to	
9400	9499	Parameter consistency and storage
9500	9899	Safety Integrated
9900	9949	Topology
9950	9999	Diagnostics (internal)

1.2 List of parameters

Product: SINAMICS S, Version: 2402300, Label: , Language: eng

r0002	Control Unit operating display / CU op_display		
CU_S	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	99	70
Description:	Operating display for the Control Unit (CU).		
Values:	0: [00] Operation 10: [10] Ready 20: [20] Wait for run-up 31: [31] Commissioning software download active 33: [33] Remove topology error / acknowledge 34: [34] Exit the commissioning mode 35: [35] Carry-out first commissioning 70: [70] Initialization 80: [80] Reset active 99: [99] Internal software error		
r0002	Infeed operating display / INF op_display		
A_INF, S_INF	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	250	44
Description:	Operating display for the infeed. The value provides information about the actual operating state and the conditions necessary to reach the next operating state. The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Run" operating state.		
Values:	0: [00] Operation - everything enabled 21: [21] Ready - set "enable operation" = "1" (p0852) 31: [31] Rdy to power-up - pre-chrg running (p0857) 32: [32] Ready to power-up - set "ON/OFF1" = "0/1" (p0840) 41: [41] Power-on inhibit - set "ON/OFF1" = "0" (p0840) 42: [42] Power-on inhibit - set "OC/OFF2" = "1" (p0844, p0845) 44: [44] Power-on inhibit - connect 24 V to terminal EP (hardware) 45: [45] Power-on inhib - remove fault cause, acknowledge fault 46: [46] Power-on inhibit - exit comm mode (p0009, p0010) 60: [60] Infeed de-activated/not operational 250: [250] Device signals a topology error		
Dependency:	Refer to: r0046		
Note:	OC: Operating condition EP: Enable Pulses (pulse enable) COMM: Commissioning		

r0002 Drive operating display / Drv op_display			
SERVO, VECTOR	Can be changed: -	Access level: 1	
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	250	12
Description:	<p>Operating display for the drive.</p> <p>The value provides information about the actual operating state and the conditions necessary to reach the next operating state.</p> <p>The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Run" operating state.</p>		
Values:	<p>0: [00] Operation - everything enabled</p> <p>10: [10] Operation - set "enable setpoint" = "1" (p1142)</p> <p>11: [11] Operation - set "enable speed controller" = "1" (p0856)</p> <p>12: [12] Operation - RFG frozen, set "RFG start" = "1" (p1141)</p> <p>13: [13] Operation - set "enable RFG" = "1" (p1140)</p> <p>14: [14] Operation - MotID or excitation running and/or brake opens</p> <p>15: [15] Operation - open brake (p1215)</p> <p>16: [16] Oper - withdraw braking w/ OFF1 using "ON/OFF1" = "1"</p> <p>17: [17] Oper - braking w/ OFF3 can only be interrupted w/ OFF2</p> <p>18: [18] Operation - brake on fault, remove fault, acknowledge</p> <p>19: [19] Operation - armature short-circuit active (p1230, p1231)</p> <p>21: [21] Ready - set "enable operation" = "1" (p0852)</p> <p>22: [22] Ready - de-magnetization running (p0347)</p> <p>23: [23] Ready - set "infeed operation" = "1" (p0864)</p> <p>31: [31] Ready to power-up - set "ON/OFF1" = "0/1" (p0840)</p> <p>41: [41] Power-on inhibit - set "ON/OFF1" = "0" (p0840)</p> <p>42: [42] Power-on inhibit - set "OC/OFF2" = "1" (p0844, p0845)</p> <p>43: [43] Power-on inhibit - set "OC/OFF3" = "1" (p0848, p0849)</p> <p>44: [44] Power-on inhibit - connect 24 V to terminal EP (hardware)</p> <p>45: [45] Power-on inhib - remove fault cause, acknowledge fault</p> <p>46: [46] Power-on inhibit - exit comm mode (p0009, p0010)</p> <p>60: [60] Infeed de-activated/not operational</p> <p>250: [250] Device signals a topology error</p>		
Dependency:	Refer to: r0046		
Note:	<p>OC: Operating condition</p> <p>EP: Enable Pulses (pulse enable)</p> <p>RFG: Ramp-function generator</p> <p>COMM: Commissioning</p> <p>MotID: Motor data identification</p>		

r0002 Infeed operating display / INF op_display			
B_INF	Can be changed: -	Access level: 1	
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	250	31
Description:	<p>Operating display for the infeed.</p> <p>The value provides information about the actual operating state and the conditions necessary to reach the next operating state.</p> <p>The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Run" operating state.</p>		

Values:	0: [00] Operation - everything enabled
	31: [31] Rdy to power-up - pre-chrg running (p0857)
	32: [32] Ready to power-up - set "ON/OFF1" = "0/1" (p0840)
	41: [41] Power-on inhibit - set "ON/OFF1" = "0" (p0840)
	42: [42] Power-on inhibit - set "OC/OFF2" = "1" (p0844, p0845)
	44: [44] Power-on inhibit - connect 24 V to terminal EP (hardware)
	45: [45] Power-on inhib - remove fault cause, acknowledge fault
	46: [46] Power-on inhibit - exit comm mode (p0009, p0010)
	60: [60] Infeed de-activated/not operational
	250: [250] Device signals a topology error
Dependency:	Refer to: r0046
Note:	OC: Operating condition COMM: Commissioning

r0002 TB30 operating display / TB30 op_display

TB30	Can be changed: -	Access level: 1
	Data type: Integer16	Dynamic index: -
	P-Group: -	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	0	250
		Factory setting
		70

Description: Operating display for terminal board 30 (TB30).
The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Module in cyclic operation" operating state.

Values:	0: [00] Module in cyclic operation
	40: [40] Module not in cyclic operation
	60: [60] Fault
	70: [70] Initialization
	80: [80] Reset active
	120: [120] Module de-activated
	250: [250] Device signals a topology error

r0002 DMC operating display / DMC op_display

DMC20	Can be changed: -	Access level: 1
	Data type: Integer16	Dynamic index: -
	P-Group: -	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	0	250
		Factory setting
		40

Description: Operating display for the DRIVE-CLiQ Hub Module Cabinet (DMC).
The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Module in cyclic operation" operating state.

Values:	0: [00] Module in cyclic operation
	40: [40] Module not in cyclic operation
	50: [50] Alarm
	60: [60] Fault
	70: [70] Initialization
	120: [120] Module de-activated
	250: [250] Device signals a topology error

r0002	TM31 operating display / TM31 op_display		
TM31	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 250	Factory setting 70
Description:	<p>Operating display for Terminal Module 31 (TM31).</p> <p>The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Module in cyclic operation" operating state.</p>		
Values:	<p>0: [00] Module in cyclic operation</p> <p>40: [40] Module not in cyclic operation</p> <p>50: [50] Alarm</p> <p>60: [60] Fault</p> <p>70: [70] Initialization</p> <p>120: [120] Module de-activated</p> <p>250: [250] Device signals a topology error</p>		
r0002	TM41 operating display / TM41 op_display		
TM41	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 250	Factory setting 31
Description:	<p>Operating display for Terminal Module 41 (TM41).</p> <p>The value provides information about the actual operating state and the conditions necessary to reach the next operating state.</p> <p>The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Run" operating state.</p>		
Values:	<p>0: [00] Operation - everything enabled</p> <p>10: [10] Operation - set "enable setpoint" = "1" (p1142)</p> <p>12: [12] Operation - RFG frozen, set "RFG start" = "1" (p1141)</p> <p>13: [13] Operation - set "enable RFG" = "1" (p1140)</p> <p>18: [18] Operation - brake on fault, remove fault, acknowledge</p> <p>21: [21] Ready - set "enable operation" = "1" (p0852)</p> <p>31: [31] Ready to power-up - set "ON/OFF1" = "0/1" (p0840)</p> <p>41: [41] Power-on inhibit - set "ON/OFF1" = "1/0" (p0840)</p> <p>42: [42] Power-on inhibit - set "OC/OFF2" = "1" (p0844)</p> <p>43: [43] Power-on inhibit - set "OC/OFF3" = "1" (p0848)</p> <p>45: [45] Power-on inhib - remove fault cause, acknowledge fault</p> <p>46: [46] Power-on inhibit - exit comm mode (p0009, p0010)</p> <p>120: [120] Module de-activated</p> <p>250: [250] Device signals a topology error</p>		
Note:	<p>OC: Operating condition</p> <p>RFG: Ramp-function generator</p> <p>COMM: Commissioning</p>		
r0002	TM17 operating display / TM17 op_display		
TM17	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 250	Factory setting 70
Description:	<p>Operating display for Terminal Module 17 (TM17).</p> <p>The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Module in cyclic operation" operating state.</p>		

Values:

0:	[00] Module in cyclic operation
40:	[40] Module not in cyclic operation
50:	[50] Alarm
60:	[60] Fault
70:	[70] Initialization
120:	[120] Module de-activated
250:	[250] Device signals a topology error

r0002 TM15 operating display / TM15 op_display

TM15	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	250	70

Description: Operating display for Terminal Module 15 (TM15).
The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Module in cyclic operation" operating state.

Values:

0:	[00] Module in cyclic operation
40:	[40] Module not in cyclic operation
50:	[50] Alarm
60:	[60] Fault
70:	[70] Initialization
120:	[120] Module de-activated
250:	[250] Device signals a topology error

r0002 TM15DI/DO operating display / TM15D op_display

TM15DI_DO	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	250	70

Description: Operating display for Terminal Module 15 (TM15).
The higher the numerical value, the greater the number of conditions that still have to be fulfilled in order to achieve the "Module in cyclic operation" operating state.

Values:

0:	[00] Module in cyclic operation
40:	[40] Module not in cyclic operation
50:	[50] Alarm
60:	[60] Fault
70:	[70] Initialization
120:	[120] Module de-activated
250:	[250] Device signals a topology error

p0003 BOP access level / BOP access level

CU_S	Can be changed: C1, U, T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	4	1

Description: Sets the access level for reading and writing parameters using the Basic Operator Panel (BOP) and Advanced Operator Panel (AOP).

Values:

0:	User-defined
1:	Standard
2:	Extended
3:	Expert
4:	Service

Note: Access level 0 (user-defined):
Parameters from the user-defined list (p0013).
Access level 1 (standard):
Parameters for the simplest operator control possibility (e.g. p1120 = ramp-function generator, ramp-up time).
Access level 2 (extended):
Parameters to operate the basic functions of the drive unit.
Access level 3 (experts):
Expert know-how is required for these parameters (e.g. BICO parameterization).
Access level 4 (service):
For these parameters, it is necessary that authorized service personnel enter the appropriate password (p3950).

p0004	BOP display filter / BOP display filter		
CU_S	Can be changed: C2(1), U, T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 0
Description:	Sets the display filter for parameters for Basic Operator Panel (BOP) and Advanced Operator Panel (AOP).		
Values:	<ul style="list-style-type: none"> 0: All parameters 1: Displays, signals 2: Power unit 3: Motor 4: Encoder/pos enc 5: Technology/units 7: Digital inputs/outputs, commands, sequence control 8: Analog inputs/outputs 10: Setpoint channel/ramp-fct generator 12: Functions 13: U/f control 14: Control 15: Data sets 17: Basic positioner 18: Gating unit 19: Motor identification 20: Communication 21: Faults, alarms, monitoring functions 25: Cl.-loop pos ctrl 28: Free function blocks 47: Trace and function generator 50: OA parameter 90: Topology 95: Safety Integrated 98: Command Data Sets (CDS) 99: Drive Data Sets (DDS) 		
Dependency:	Refer to: p0003		
Note:	Example: p0004 = 3: Only the parameters for the motor are displayed.		

p0005	BOP operating display selection / BOP op_disp sel		
A_INF, B_INF, CU_S, DMC20, SERVO, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VEC- TOR	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Unsigned16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 2
Description:	Sets the parameter number for display for p0006 = 2, 4 for the Basic Operator Panel (BOP). Examples for the SERVO drive object: p0005 = 21: Speed actual value smoothed (r0021) p0005 = 25: Drive output voltage smoothed (r0025) p0005 = 26: Speed actual value smoothed (r0026) p0005 = 27: Absolute current actual value, smoothed (r0027)		
Dependency:	Refer to: p0006		
Note:	Only the monitoring parameters (only read parameters) can be set, that actually exist for the actual drive object.		
p0006	BOP operating display mode / BOP op_disp mode		
CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 4	Max 4	Factory setting 4
Description:	Sets the mode of the operating display for the Basic Operator Panel (BOP) in the operating states "ready" and "operation".		
Values:	4: p0005		
Dependency:	Refer to: p0005		
Note:	Mode 0 ... 3 can only be selected if also r0020, r0021 are available on the drive object. Mode 4 is available for all drive objects.		
p0006	BOP operating display mode / BOP op_disp mode		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 4	Factory setting 4
Description:	Sets the mode of the operating display for the Basic Operator Panel (BOP) in the operating states "ready" and "operation".		
Values:	0: Operation --> r0021, otherwise r0020 <--> r0021 1: Operation --> r0021, otherwise r0020 2: Operation --> p0005, otherwise p0005 <--> r0020 3: Operation --> r0002, otherwise r0002 <--> r0020 4: p0005		
Dependency:	Refer to: p0005		
Note:	Mode 0 ... 3 can only be selected if also r0020, r0021 are available on the drive object. Mode 4 is available for all drive objects.		

p0007	BOP background lighting / BOP lighting		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0 [s]	Max 2000 [s]	Factory setting 0 [s]
Description:	Sets the delay time until the background lighting of the Basic Operator Panel (BOP) is switched-off. If no keys are actuated, then the background lighting automatically switches itself off after this time has expired.		
Note:	p0007 = 0: Background lighting is always switched on (factory setting).		
p0008	BOP drive object selection / BOP DO select		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 1	Max 65535	Factory setting 1
Description:	Sets the required drive object for reading and writing via the Basic Operator Panel (BOP).		
Note:	The value from p0008 is displayed at the top left on the Basic Operator Panel (BOP). The drive object Control Unit is selected using the value 1.		
p0009	Device commissioning parameter filter / Dev comm par_filt		
CU_S	Can be changed: C1, T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 50	Factory setting 1
Description:	Sets the device and basic drive commissioning. By appropriately setting this parameter, those parameters are filtered that can be written into in the various commissioning steps.		
Values:	0: Ready 1: Device configuration 2: Defining the drive type / drive options 3: Drive basis configuration 4: Data set basis configuration 29: Device download 30: Parameter reset 50: OA application configuration		

Note: The drives can only be powered-up outside the device commissioning (the inverter enabled). In this case, p0009 must be 0 (Ready) and the individual drive objects must have already gone into operation (p0010).
p0009 = 1: Device configuration
At the first commissioning of the devices, after booting, the device is in the "device configuration" state. To start the internal automatic first commissioning of the drive unit, p0009 should be set to 0 (Ready) after the ID for the actual topology (r0098) was transferred into the ID for the target topology (p0099). To do this, it is sufficient to set a single index value of p0099[x] the same as r0098[x]. Before the device has been completely commissioned, no other parameter can be changed. After the first commissioning was carried-out, in this state, when required, other basic device configuration parameters can be adapted (e.g. the basic sampling time in p0110).
p0009 = 2: Defines the drive type / function module
In this state, the drive object types and/or the function modules can be changed or selected for the individual drive objects. To do this, the drive object type can be set using p0107[0...15] and the function can be set using p0108[0...15] (refer to p0101[0...15]).
p0009 = 3: Drive basis configuration
In this state, after the device has been commissioned for the first time, basic changes can be made for the individual drive objects (e.g. sampling times in p0111, p0112, p0115 and the number of data sets in p0120, p0130, p0140, p0170, p0180).
p0009 = 4: Data set basis configuration
In this state, after the device has been commissioned for the first time, for the individual drive objects changes can be made regarding the assignment of the components (p0121, p0131, p0141, p0151, p0161) to the individual data sets and the assignment of the power unit, motor and encoder to the drive data sets (p0185, ...).
p0009 = 29: Device download
If a download is made using the commissioning software, the device is automatically brought into this state. After the download has been completed, p0009 is automatically set to 0 (ready). It is not possible to manually set p0009 to this value.
p0009 = 30: Parameter reset
In order to bring the complete unit into the "first commissioning" state or to load the parameters saved using p0977, to start, p0009 must be set to this value. p0976 can then be changed to the required value.
p0009 = 50: OEM application configuration
In this state, after the device has been commissioned for the first time, changes can be made for the individual drive objects regarding the activity (p4956) of the OEM applications.

p0010		Infeed commissioning parameter filter / INF comm par_filt		
A_INF, B_INF, S_INF	Can be changed: C2(1), T	Data type: Integer16	Dynamic index: -	Access level: 1
	P-Group: -	Units group: -		Function diagram: -
	Min	Max		Unit selection: -
	0	30		Factory setting
				1
Description:	Sets the parameter filter to commission an infeed unit. Setting this parameter filters-out the parameters that can be written into in the various commissioning steps.			
Values:	0: Ready 1: Quick commissioning 2: Power unit commissioning 5: Technological application/units 29: Download 30: Parameter reset			
Note:	The drive can only be powered-up outside the drive commissioning (inverter enable). To realize this, this parameter must be set to 0. For p3900 not equal to 0, at the end of the quick commissioning, this parameter is automatically reset to 0. Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.			

p0010	Drive, commissioning parameter filter / Drv comm. par_filt		
SERVO, VECTOR	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 95	Factory setting 1
Description:	Sets the parameter filter to commission a drive. Setting this parameter filters-out the parameters that can be written into in the various commissioning steps.		
Values:	0: Ready 1: Quick commissioning 2: Power unit commissioning 3: Motor commissioning 4: Encoder commissioning 5: Technological application/units 15: Data sets 17: Basic positioning commissioning 25: Commissioning the position control 29: Download 30: Parameter reset 95: Safety Integrated commissioning		
Note:	The drive can only be powered-up outside the drive commissioning (inverter enable). To realize this, this parameter must be set to 0. For p3900 not equal to 0, at the end of the quick commissioning, this parameter is automatically reset to 0. Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.		
p0010	TB30 commissioning parameter filter / TB30 comm.par_filt		
TB30	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 30	Factory setting 0
Description:	Sets the parameter filter for commissioning a terminal board 30 (TB30). Setting this parameter filters-out the parameters that can be written into in the various commissioning steps. For the BOP, this setting also causes the read access operations to be filtered.		
Values:	0: Ready 29: Download 30: Parameter reset		
Dependency:	Refer to: p0970		
Note:	Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.		
p0010	TM31 commissioning parameter filter / TM31 comm par_filt		
TM31	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 30	Factory setting 0
Description:	Sets the parameter filter for commissioning a Terminal Module 31 (TM31). Setting this parameter filters-out the parameters that can be written into in the various commissioning steps. For the BOP, this setting also causes the read access operations to be filtered.		
Values:	0: Ready 29: Download 30: Parameter reset		
Dependency:	Refer to: p0970		

Note: Only the following values are possible: p0010 = 0, 30
Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.

p0010	TM41 commissioning parameter filter / TM41 comm par_filt		
TM41	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	30	0
Description:	Sets the parameter filter for commissioning a Terminal Module 41 (TM41). Setting this parameter filters-out the parameters that can be written into in the various commissioning steps. For the BOP, this setting also causes the read access operations to be filtered.		
Values:	0: Ready 4: Encoder commissioning 5: Technological application/units 29: Download 30: Parameter reset		
Dependency:	Refer to: p0970		
Note:	Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.		

p0010	TM17 commissioning parameter filter / TM17 comm par_filt		
TM17	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	30	0
Description:	Sets the parameter filter for commissioning a Terminal Module 17 (TM17). Setting this parameter filters-out the parameters that can be written into in the various commissioning steps. For the BOP, this setting also causes the read access operations to be filtered.		
Values:	0: Ready 29: Download 30: Parameter reset		
Dependency:	Refer to: p0970		
Note:	Only the following values are possible: p0010 = 0, 30 Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.		

p0010	TM15 commissioning parameter filter / TM15 comm par_filt		
TM15	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	30	0
Description:	Sets the parameter filter for commissioning a Terminal Module 15 (TM15). Setting this parameter filters-out the parameters that can be written into in the various commissioning steps. For the BOP, this setting also causes the read access operations to be filtered.		
Values:	0: Ready 29: Download 30: Parameter reset		
Dependency:	Refer to: p0970		
Note:	Only the following values are possible: p0010 = 0, 30 Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.		

p0010	TM15DI/DO commissioning the parameterizing filter / TM15D com par_filt		
TM15DI_DO	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 30	Factory setting 0
Description:	Sets the parameter filter for commissioning a Terminal Module 15 (TM15). Setting this parameter filters-out the parameters that can be written into in the various commissioning steps. For the BOP, this setting also causes the read access operations to be filtered.		
Values:	0: Ready 29: Download 30: Parameter reset		
Dependency:	Refer to: p0970		
Note:	Only the following values are possible: p0010 = 0, 30 Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1.		

p0011	BOP password entry (p0013) / BOP passw ent p13		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the password for the Basic Operator Panel (BOP).		
Dependency:	Refer to: p0012, p0013		

p0012	BOP password acknowledgment (p0013) / BOP passw ackn p13		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Acknowledges the password for the Basic Operator Panel (BOP).		
Dependency:	Refer to: p0011, p0013		

p0013[0...49]	BOP user-defined list / BOP list		
A_INF, B_INF, CU_S, DMC20, SERVO, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VEC- TOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the required parameters to read and write via the Basic Operator Panel (BOP). Activation: 1. p0003 = 3 (expert). 2. p0013[0...49] = requested parameter number 3. If required, enter p0011 = password in order to prevent non-authorized de-activation. 4. p0003 = 0 --> activates the selected user-defined list. De-activation/change: 1. p0003 = 3 (expert). 2. If required, p0012 = p0011, in order to be authorized to change or de-activate the list. 3. If required p0013[0...49] = required parameter number. 4. p0003 = 0 --> activates the modified user-defined list. 5. p0003 > 0 --> de-activates the user-defined list.		
Dependency:	Refer to: p0009, p0011, p0012, p0976		
Note:	The following parameters can be read and written on the Control Unit drive object: - p0003 (access stage) - p0009 (device commissioning, parameter filter) - p0012 (BOP password acknowledgment (p0013)) The following applies for the user-defined list: - password protection is only available on the drive object Control Unit and is valid for all of the drive objects. - p0013 cannot be included in the user-defined list for all drive objects. - p0003, p0009, p0011, p0012, p0976 cannot, for the drive object Control Unit, be included in the user-defined list. - the user-defined list can be cleared and de-activated "restore factory setting". A value of 0 means: Entry is empty.		

p0015	Macro drive unit / Macro drv unit		
CU_S	Can be changed: C1	Dynamic index: -	Access level: 1
	Data type: Unsigned32		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 999999	Factory setting 0
Description:	Runs the appropriate ACX file on the CompactFlash card. The selected ACX file must be located in the following directory: ... /PMACROS/DEVICE/P15/PMxxxxx.ACX Example: p0015 = 6 --> the file PM000006.ACX is run.		
Dependency:	The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card. Refer to: p0700, p1000, p1500, r8570		
Note:	The macros in the specified directory are displayed in r8570. Macros available as standard are described in the technical documentation of the particular product.		

p0015	Macro drive object / Macro DO				
A_INF, B_INF, SERVO, S_INF, TM15DI_DO, TM31, VECTOR	Can be changed: C2(1)	Dynamic index: -	Access level: 1		
	Data type: Unsigned32		Function diagram: -		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min 0	Max 999999	Factory setting 0		
Description:	Runs the appropriate ACX file on the CompactFlash card. The selected ACX file must be located in the following directory: ... /PMACROS/<drive object>/P15/PMxxxxx.ACX Example: p0015 = 6 --> the file PM000006.ACX is run.				
Dependency:	The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card. Refer to: p0700, p1000, p1500, r8570				
Notice:	No errors were issued during fast commissioning (p3900 = 1) when writing to parameters of the QUICK_IBN group!				
Note:	The macros in the specified directory are displayed in r8570. Macros available as standard are described in the technical documentation of the particular product.				
r0018	Control Unit firmware version / CU FW_version				
CU_S	Can be changed: -	Dynamic index: -	Access level: 1		
	Data type: Unsigned32		Function diagram: -		
	P-Group: -	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting -		
Description:	Displays the firmware version of the Control Unit.				
Dependency:	Refer to: r0128, r0148, r0158, r0197, r0198				
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.				
r0019	CO/BO: Control word BOP / STW BOP				
CU_S	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned16		Function diagram: -		
	P-Group: Displays, signals	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the control word for the Basic Operator Panel (BOP).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON / OFF (OFF1)	ON	OFF (OFF1)	-
	01	No coast-down / coast-down (OFF2)	No coast down	Coast down (OFF2)	-
	02	No fast stop / fast stop (OFF3)	No fast stop	Fast stop (OFF3)	-
	07	Acknowledge fault (0 -> 1)	Yes	No	-
	13	Motorized potentiometer, raise	Yes	No	-
	14	Motorized potentiometer, lower	Yes	No	-

r0020	Speed setpoint, smoothed / n_set smth		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 5020, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the actual, smoothed speed setpoint at the input of the speed controller or U/f characteristic (after the interpolator).		
Dependency:	Refer to: r0060		
Note:	Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The speed setpoint is available smoothed (r0020) and unsmoothed (r0060).		
r0020	Velocity setpoint, smoothed / v_set smth		
SERVO (Lin)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 5020, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the actual, smoothed velocity setpoint at the input of the velocity controller or U/f characteristic (after the interpolator).		
Dependency:	Refer to: r0060		
Note:	Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The velocity setpoint is available smoothed (r0020) and unsmoothed (r0060).		
r0021	Actual speed, smoothed / n_act smooth		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 1580, 1680, 4710, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the smoothed actual value of the motor speed.		
Dependency:	Refer to: r0063		
Note:	Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The value displayed in r0021 is the smoothed value of r0063.		
r0021	Actual velocity, smoothed / v_act smooth		
SERVO (Lin)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 1580, 1680, 4710, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the smoothed actual value of the motor velocity.		
Dependency:	Refer to: r0063		

Note: Smoothing time constant = 100 ms
The signal is not suitable as process quantity and may only be used as display quantity.
The value displayed in r0021 is the smoothed value of r0063.

r0024 Infeed line frequency smoothed / INF f_line smth

A_INF, S_INF	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Function diagram: 8850, 8950
	Units group: -	Unit selection: -
	Min - [Hz]	Factory setting - [Hz]
	Max - [Hz]	

Description: Displays the smoothed line supply frequency.

Dependency: Refer to: r0066

Note: Smoothing time constant = 300 ms
The signal is not suitable as process quantity and may only be used as display quantity.
The line frequency is available smoothed (r0024) and unsmoothed (r0066).
A positive sign of the frequency is obtained when the line supply phases U, V and W are connected with the correct phase sequence.
A negative sign of the frequency is obtained when the 3 line phases are interchanged therefore designating a negative direction of the rotating field of the 3-phase line supply voltage.

r0024 Drive output frequency smoothed / Drv f_outp smooth

SERVO, VECTOR	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Function diagram: 1690, 5300, 5730, 6799
	Units group: -	Unit selection: -
	Min - [Hz]	Factory setting - [Hz]
	Max - [Hz]	

Description: Displays the smoothed converter frequency.

Dependency: Refer to: r0066

Note: Smoothing time constant = 100 ms
The signal is not suitable as process quantity and may only be used as display quantity.
The output frequency is available smoothed (r0024) and unsmoothed (r0066).

r0025 Infeed input voltage, smoothed / INF U_input smooth

A_INF, S_INF	Can be changed: -	Access level: 2
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Function diagram: 8850, 8950
	Units group: -	Unit selection: -
	Min - [Veff]	Factory setting - [Veff]
	Max - [Veff]	

Description: Displays the smoothed actual value of the input voltage.
This voltage is present at the line supply connection of the infeed.

Dependency: Refer to: r0072

Note: Smoothing time constant = 300 ms
The signal is not suitable as process quantity and may only be used as display quantity.
The input voltage is available smoothed (r0025) and unsmoothed (r0072).

r0025	Drive, output voltage smoothed / Drv U_outp smooth		
SERVO, VECTOR	Can be changed: -	Access level: 2	
	Data type: Floating Point	Dynamic index: -	Function diagram: 1690, 5730, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the smoothed output voltage of the power unit.		
Dependency:	Refer to: r0072		
Note:	Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The output voltage is available smoothed (r0025) and unsmoothed (r0072).		
r0026	CO: DC link voltage, smoothed / Vdc smooth		
A_INF, B_INF, S_INF	Can be changed: -	Access level: 2	
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730, 6799, 8750, 8850, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the smoothed actual value of the DC link voltage.		
Dependency:	Refer to: r0070		
Note:	A_INF, B_INF, S_INF: smoothing time constant = 300 ms SERVO, VECTOR: Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The DC link voltage is available smoothed (r0026) and unsmoothed (r0070).		
r0026	CO: DC link voltage, smoothed / Vdc smooth		
SERVO, VECTOR	Can be changed: -	Access level: 2	
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730, 8750, 8850, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the smoothed actual value of the DC link voltage.		
Dependency:	Refer to: r0070		
Notice:	For SINAMICS S120 AC Drive (AC/AC) the following applies: When measuring a DC link voltage < 200 V, for the Power Module (e.g. PM340) a valid measured value is not supplied. In this case, a value of approx. 300 V is displayed in the display parameter.		
Note:	A_INF, B_INF, S_INF: smoothing time constant = 300 ms SERVO, VECTOR: Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The DC link voltage is available smoothed (r0026) and unsmoothed (r0070).		

r0027	Absolute actual current, smoothed / I_act abs.val.smth		
A_INF, SERVO, S_INF, VECTOR	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 2 Function diagram: 5730, 6799, 8850, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the smoothed absolute actual current value.		
Dependency:	Refer to: r0068		
Note:	A_INF, S_INF, VECTOR: Smoothing time constant = 300 ms SERVO: Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The absolute current actual value is available smoothed (r0027) and unsmoothed (r0068).		
r0028	Modulation depth, smoothed / Modulat depth smth		
A_INF, SERVO, VECTOR	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 5730, 6799, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the smoothed actual value of the modulation depth.		
Dependency:	Refer to: r0074		
Note:	A_INF: Smoothing time constant = 300 ms SERVO, VECTOR: Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The modulation depth is available smoothed (r0028) and unsmoothed (r0074).		
r0029	Infeed, smoothed reactive current actual value / INF I_reactiv smth		
A_INF, S_INF	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 8850, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the smoothed actual value of the reactive current component.		
Note:	Smoothing time constant = 300 ms The signal is not suitable as process quantity and may only be used as display quantity. The reactive current actual value is available smoothed (r0029) and unsmoothed (r0076).		
r0029	Drive, smoothed field-generating current actual value / Drv Id_act smooth		
SERVO, VECTOR	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 5730, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the smoothed field-generating actual current.		
Dependency:	Refer to: r0076		

Note: SERVO: Smoothing time constant = 100 ms
 VECTOR: Smoothing time constant = 300 ms
 The signal is not suitable as process quantity and may only be used as display quantity.
 The field-generating current actual value is available smoothed (r0029) and unsmoothed (r0076).

r0030 Active current actual value, smoothed / I_{active} smooth

A_INF, S_INF	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Function diagram: 8850, 8950
	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]
		Factory setting - [Aeff]

Description: Displays the smoothed actual value of the active current components.

Dependency: Refer to: r0078

Note: Smoothing time constant = 300 ms
 The signal is not suitable as process quantity and may only be used as display quantity.
 The active current actual value is available smoothed (r0030) and unsmoothed (r0078).

r0030 Current actual value, torque-generating, smoothed / I_q_act smooth

SERVO, VECTOR	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Function diagram: 5730, 6799
	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]
		Factory setting - [Aeff]

Description: Displays the smoothed torque-generating actual current.

Dependency: Refer to: r0078

Note: SERVO: Smoothing time constant = 100 ms
 VECTOR: Smoothing time constant = 300 ms
 The signal is not suitable as process quantity and may only be used as display quantity.
 The following applies for SERVO:
 The torque-generating current actual value is available smoothed (r0030 with 100 ms, r0078[1] with p0045) and unsmoothed (r0078[0]).
 For VECTOR, the following applies:
 The torque-generating current actual value is available smoothed (r0030 with 300 ms) and unsmoothed (r0078).

r0031 Actual torque smoothed / M_{act} smooth

SERVO, VECTOR	Can be changed: -	Access level: 2
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Function diagram: 5730, 6799
	Units group: 7_2	Unit selection: p0505
	Min - [Nm]	Max - [Nm]
		Factory setting - [Nm]

Description: Displays the smoothed torque actual value.

Dependency: Refer to: r0080

Note: Smoothing time constant = 100 ms
 The signal is not suitable as process quantity and may only be used as display quantity.
 The active current actual value is available smoothed (r0031) and unsmoothed (r0080).

r0031	Force actual value, smoothed / F_act smooth		
SERVO (Lin)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730, 6799
	P-Group: Displays, signals	Units group: 8_2	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the smoothed force setpoint.		
Dependency:	Refer to: r0080		
Note:	Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The active current actual value is available smoothed (r0031) and unsmoothed (r0080).		
r0032	Active power actual value, smoothed / P_actv_act smth		
A_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730, 6799, 8850, 8950
	P-Group: Displays, signals	Units group: 14_10	Unit selection: p0505
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the smoothed actual value of the active power.		
Dependency:	Refer to: r0082		
Note:	Significance for the drive: Power output at the motor shaft Significance for the infeed: Line power drawn For A_INF and S_INF the following applies: The active power is available smoothed (r0032 with 300 ms) and unsmoothed (r0082). The following applies for SERVO: The active power is available smoothed (r0032 with 100 ms, r0082[1] with p0045) and unsmoothed (r0082[0]). For VECTOR and VECTORMV, the following applies: The active power is available smoothed (r0032 with 100 ms) and unsmoothed (r0082).		
r0033	Torque utilization, smoothed / M_util smooth		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8012
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the smoothed torque/force utilization as a percentage. The torque/force utilization is obtained from the required smoothed torque/force referred to the torque/force limit.		
Note:	Smoothing time constant = 100 ms The signal is not suitable as process quantity and may only be used as display quantity. The torque utilization is available smoothed (r0033) and unsmoothed (r0081). For M_set total (r0079) > M_max offset (p1532), the following applies: - demanded torque = M_set total - M_max offset - actual torque limit = M_max upper effective (r1538) - M_max offset For M_set total (r0079) <= M_max offset (p1532), the following applies: - demanded torque = M_max offset - M_set total - actual torque limit = M_max offset - M_max lower effective (r1539) For the actual torque limit = 0, the following applies: r0033 = 100 % For the actual torque limit < 0, the following applies: r0033 = 0 %		

r0035	CO: Motor temperature / Motor temperature		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8016
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the actual temperature in the motor.		
Note:	<p>For r0035 not equal to -200.0 °C, the following applies:</p> <ul style="list-style-type: none"> - this temperature display is valid. - a KTY sensor is connected. - for induction motors, the thermal motor model is activated (p0600 = 0 or p0601 = 0). <p>For r0035 equal to -200.0 °C, the following applies:</p> <ul style="list-style-type: none"> - this temperature display is not valid (temperature sensor error). - a PTC sensor is connected. - for synchronous motors, the thermal motor model is activated (p0600 = 0 or p0601 = 0). 		
r0036	Power unit overload I2t / LT overload I2t		
A_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8014
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	<p>Displays the power unit overload determined using the I2t calculation.</p> <p>A current reference value is defined for the I2t monitoring of the power unit. It represents the current that can be conducted by the power unit without any influence of the switching losses (e.g. the continuously permissible current of the capacitors, inductances, busbars, etc.).</p> <p>If the I2t reference current of the power unit is not exceeded, then an overload (0 %) is not displayed.</p> <p>In the other case, the degree of thermal overload is calculated whereby 100% corresponds to the maximum permissible value and results in shutdown (trip).</p>		
Dependency:	<p>Refer to: p0290, p0294</p> <p>Refer to: F30005</p>		

r0037[0...19]	CO: Power unit temperatures / LT temperatures		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 8014
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the temperatures in the power unit.		
Index:	[0] = Maximum inverter [1] = Maximum depletion layer [2] = Maximum rectifier [3] = Air intake [4] = Electronics unit in the power unit [5] = Inverter 1 [6] = Inverter 2 [7] = Inverter 3 [8] = Inverter 4 [9] = Inverter 5 [10] = Inverter 6 [11] = Rectifier 1 [12] = Rectifier 2 [13] = Depletion layer 1 [14] = Depletion layer 2 [15] = Depletion layer 3 [16] = Depletion layer 4 [17] = Depletion layer 5 [18] = Depletion layer 6 [19] = Cooling system water intake		
Dependency:	Refer to: p0290		
Note:	A value of -200 indicates that there is no measuring signal.		
r0038	Power factor, smoothed / Cos phi smooth		
A_INF, S_INF, VEC- TOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 6799, 8850, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the smoothed actual power factor.		
Note:	Smoothing time constant = 300 ms The signal is not suitable as process quantity and may only be used as display quantity. Significance for the motor: Motor power factor Significance for the infeed: Power factor at the connection point (p3470, p3471)		
p0045	Smoothing time constant, display values / T_smth display		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 4715, 5610, 5730, 6714, 8012
	P-Group: -	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 200.00 [ms]	Factory setting 1.00 [ms]
Description:	Sets the smoothing time constant for the following display values: SERVO: r0078[1], r0079[1], r0081 (calculated from the quantities smoothed with p0045), r0082[1]. VECTOR: r0063[1], r0068[1], r0080[1], r0082[1].		

r0046 CO/BO: Infeed missing enable signals / INF miss enable

A_INF, S_INF

Can be changed: -**Data type:** Unsigned32**Dynamic index:** -**Access level:** 1**P-Group:** Displays, signals**Units group:** -**Function diagram:** 8934**Unit selection:** -**Min**

-

Max

-

Factory setting

0000 bin

Description:

Displays missing enable signals that are preventing the closed-loop infeed control from being commissioned.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	OFF1 enable missing	Yes	No	-
01	OFF2 enable missing	Yes	No	-
03	Enable operation missing	Yes	No	-
08	EP terminals enable missing	Yes	No	-
16	OFF1 enable internal missing	Yes	No	-
17	OFF2 enable internal missing	Yes	No	-
19	Pulse enable internal missing	Yes	No	-
26	Infeed inactive or not operational	Yes	No	-
29	Cooling system ready signal missing	Yes	No	-

Dependency:

Refer to: r0002

Note:

The value r0046 = 0 indicates that all enable signals for the infeed are present.

Bit 00 = 1 (enable signal missing), if:

- the signal source in p0840 is a 0 signal.

- there is a power-on inhibit.

Bit 01 = 1 (enable signal missing), if:

- the signal source in p0844 or p0845 is a 0 signal.

Bit 03 = 1 (enable signal missing), if:

- the signal source in p0852 is a 0 signal.

Bit 08 = 1 (enable signal missing), if:

- the pulse enable via terminal EP is missing (booksize: X21, chassis: X41).

Bit 16 = 1 (enable signal missing), if:

- there is an OFF1 fault response. The system is only enable if the fault is removed and was acknowledged and the power-on inhibit withdrawn with OFF1 = 0.

Bit 17 = 1 (enable signal missing), if:

- The commissioning mode is selected (p0009 > 0 or p0010 > 0) or there is an OFF2 fault response or the OFF1 signal source (p0840) is changed.

Bit 19 = 1 (internal pulse enable missing), if:

- synchronization is running between the basic clock cycle, DRIVE-CLiQ clock cycle and application clock cycle.

Bit 26 = 1 (enable signal missing), if:

- the infeed is inactive (p0105 = 0) or is not operational (r7850[DO-Index]=0).

Bit 29 = 1 (enable signal missing), if:

- the cooling system ready signal via BI: p0266[1] missing.

r0046		CO/BO: Missing drive enable signals / Drv miss enable		
SERVO, VECTOR	Can be changed: -			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2634
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays missing enable signals that are preventing the closed-loop drive control from being commissioned.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	OFF1 enable missing	Yes	No
	01	OFF2 enable missing	Yes	No
	02	OFF3 enable missing	Yes	No
	03	Enable operation missing	Yes	No
	04	Armature short-circuit, enable missing	Yes	No
	05	STOP2 enable missing	Yes	No
	06	STOP1 enable missing	Yes	No
	08	EP terminals enable missing	Yes	No
	09	Infeed enable missing	Yes	No
	10	Ramp-function generator enable missing	Yes	No
	11	Ramp-function generator start missing	Yes	No
	12	Setpoint enable missing	Yes	No
	16	OFF1 enable internal missing	Yes	No
	17	OFF2 enable internal missing	Yes	No
	18	OFF3 enable internal missing	Yes	No
	19	Pulse enable internal missing	Yes	No
	20	Armature short-circuit, internal enable missing	Yes	No
	21	STOP2 enable internal missing	Yes	No
	22	STOP1 enable internal missing	Yes	No
	25	Function bypass active	Yes	No
	26	Drive inactive or not operational	Yes	No
	27	Demagnetization not completed	Yes	No
	28	Brake open missing	Yes	No
	29	Cooling system ready signal missing	Yes	No
	30	Speed controller inhibited	Yes	No
	31	Jog setpoint active	Yes	No
Dependency:	Refer to: r0002			
Note:	The value r0046 = 0 indicates that all enable signals for this drive are present.			
	Bit 00 = 1 (enable signal missing), if:			
	- the signal source in p0840 is a 0 signal.			
	- there is a power-on inhibit.			
	Bit 01 = 1 (enable signal missing), if:			
	- the signal source in p0844 or p0845 is a 0 signal.			
	Bit 02 = 1 (enable signal missing), if:			
	- the signal source in p0848 or p0849 is a 0 signal.			
	Bit 03 = 1 (enable signal missing), if:			
	- the signal source in p0852 is a 0 signal.			
	Bit 04 = 1 (armature short-circuit active), if:			
	- the signal source in p1230 has a 1 signal			
	Bit 05, Bit 06: Being prepared			
	Bit 08 = 1 (enable signal missing), if:			
	- the pulse enable via terminal EP is missing (booksize: X21, chassis: X41).			
	Bit 09 = 1 (enable signal missing), if:			
	- the signal source in p0864 is a 0 signal.			
	Bit 10 = 1 (enable signal missing), if:			
	- the signal source in p1140 is a 0 signal.			

Bit 11 = 1 (enable signal missing) if the speed setpoint is frozen, because:

- the signal source in p1141 is a 0 signal.

or

- the speed setpoint is entered from jogging and the two signal sources for jogging, bit 0 (p1055) and bit 1 (p1056) have a 1 signal.

Bit 12 = 1 (enable signal missing), if:

- the signal source in p1142 is a 0 signal.

Bit 16 = 1 (enable signal missing), if:

- there is an OFF1 fault response. The system is only enable if the fault is removed and was acknowledged and the power-on inhibit withdrawn with OFF1 = 0.

Bit 17 = 1 (enable signal missing), if:

- the commissioning mode is selected (p0009 > 0 or p0010 > 0) or an OFF2 fault response is present.

Bit 18 = 1 (enable signal missing), if:

- OFF3 has still not be completed or an OFF3 fault response is present.

Bit 19 = 1 (internal pulse enable missing), if:

- synchronization is running between the basic clock cycle, DRIVE-CLiQ clock cycle and application clock cycle.

Bit 20 = 1 (internal armature short-circuit active), if:

- the drive is not in the state "S4: Operation" or in "S5x" (refer to function chart 2610). - the

- the internal pulse enable is missing (r0046.19 = 0).

Bit 21 = 1 (enable signal missing), if:

The pulses have been enabled and the speed setpoint has still not been enabled, because:

- the holding brake opening time (p1216) has still not expired.

- The motor has still not been magnetized (induction motor).

Bit 22: Being prepared

Bit 26 = 1 (enable signal missing), if:

- the drive is inactive (p0105 = 0) or is not operational (r7850[DO-Index]=0).

Bit 27 = 1 (enable signal missing), if:

- de-magnetizing has still not been completed (only for vector).

Bit 28 = 1 (enable signal missing), if:

- the holding brake is closed or has still not been opened.

Bit 29 = 1 (enable signal missing), if:

- the cooling system ready signal via BI: p0266[1] missing.

Bit 30 = 1 (speed controller inhibited), if one of the following reasons is present:

- A 0 signal is available via BI: p0856.

- the function generator with current input is active.

- the measuring function "current controller reference frequency characteristic" is active.

- the pole position identification is active.

- the motor data identification routine is

r0046 CO/BO: Infeed missing enable signals / INF miss enable

B_INF	Can be changed: -	Access level: 1
	Data type: Unsigned32	Dynamic index: -
	P-Group: Displays, signals	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays missing enable signals that are preventing the closed-loop infeed control from being commissioned.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	OFF1 enable missing	Yes	No	-
	01	OFF2 enable missing	Yes	No	-
	08	EP terminals enable missing	Yes	No	-
	16	OFF1 enable internal missing	Yes	No	-
	17	OFF2 enable internal missing	Yes	No	-
	26	Infeed inactive or not operational	Yes	No	-
	29	Cooling system ready signal missing	Yes	No	-

Dependency: Refer to: r0002

Note: The value r0046 = 0 indicates that all enable signals for the infeed are present.

Bit 00 = 1 (enable signal missing), if:

- the signal source in p0840 is a 0 signal.
- there is a power-on inhibit.

Bit 01 = 1 (enable signal missing), if:

- the signal source in p0844 or p0845 is a 0 signal.

Bit 16 = 1 (enable signal missing), if:

- there is an OFF1 fault response. The system is only enable if the fault is removed and was acknowledged and the power-on inhibit withdrawn with OFF1 = 0.

Bit 17 = 1 (enable signal missing), if:

- The commissioning mode is selected (p0009 > 0 or p0010 > 0) or there is an OFF2 fault response or the OFF1 signal source (p0840) is changed.

Bit 26 = 1 (enable signal missing), if:

- the infeed is inactive (p0105 = 0) or is not operational (r7850[DO-Index]=0).

Bit 29 = 1 (enable signal missing), if:

- the cooling system ready signal via BI: p0266[1] missing.

r0047 Status, identification / Status ident

SERVO	Can be changed: -	Access level: 1
	Data type: Integer16	Dynamic index: -
	P-Group: Displays, signals	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	0	104
		Factory setting
		6

Description: Displays the currently executed steps or the first step after the enable for the motor identification and pole position identification routines.

Values:	0:	No measurement
	1:	PollID: Wait for brake closing time
	2:	PollID: Measurement, step 1
	3:	PollID: Measurement, step 2
	4:	PollID: Measurement, step 3
	5:	PollID: Measurement, step 4
	6:	PollID: Measurement, stage 2
	7:	PollID: Measurement evaluation
	8:	PollID: Measurement end

- 11: MotID: Inductance measurement, step 1
- 12: MotID: Inductance measurement, step 2
- 13: MotID: Inductance measurement evaluation
- 14: MotID: Resistance measurement evaluation
- 20: MotID: Rotating inductance measurement, step 1
- 21: MotID: Rotating inductance measurement, step 2
- 22: MotID: Rotating inductance measurement, step 3
- 23: MotID: Rotating inductance measurement, step 4
- 24: MotID: Rotating Inductance measurement evaluation
- 25: MotID: Rotating Inductance measurement end
- 30: MotID: Induction motor measurement, step 1
- 31: MotID: Induction motor measurement, step 2
- 32: MotID: Induction motor measurement, step 3
- 33: MotID: Induction motor measurement, step 4
- 34: MotID: Induction motor measurement, step 5
- 35: MotID: Induction motor measurement, step 6
- 36: MotID: Induction motor measurement, step 7
- 37: MotID: Induction motor measurement, step 8
- 40: MotID: Commutating angle, step 1
- 41: MotID: Commutating angle, step 2
- 42: MotID: Commutating angle, step 3
- 43: MotID: Commutating angle, step 4
- 45: MotID: Commutating angle rotating, step 1
- 46: MotID: Commutating angle rotating, step 2
- 47: MotID: Commutating angle rotating, step 3
- 48: MotID: Commutating angle rotating complete
- 50: MotID: KT determination, step 1
- 51: MotID: KT determination, step 2
- 52: MotID: KT determination, step 3
- 53: MotID: KT determination evaluation
- 54: MotID: KT determination end
- 60: MotID: Reluctance constant measurement, step 1
- 61: MotID: Reluctance motor measurement, step 2
- 62: MotID: Reluctance constant measurement, step 3
- 63: MotID: Reluctance constant measurement end
- 70: MotID: Moment of inertia measurement, step 1
- 71: MotID: Moment of inertia measurement, step 2
- 72: MotID: Moment of inertia measurement, step 3
- 73: MotID: Moment of inertia measurement end
- 80: MotID: Magnetizing inductance measurement, step 1
- 81: MotID: Magnetizing inductance measurement, step 2
- 82: MotID: Magnetizing inductance measurement, step 3
- 83: MotID: Magnetizing inductance measurement evaluation
- 84: MotID: Main inductance measurement end
- 90: MotID: Saturation characteristic. step 1
- 91: MotID: Saturation characteristic. step 2
- 92: MotID: Saturation characteristic. step 3
- 93: MotID: Saturation characteristic evaluation 1
- 94: MotID: Saturation characteristic evaluation 2
- 95: MotID: Saturation characteristic end
- 96: MotID: Converter model, step 1
- 97: MotID: Converter model, step 2
- 98: MotID: Converter model, step 3
- 99: MotID: Converter model, step 4
- 100: PolID: Motion-based, step 1
- 101: PolID: Motion-based, step 2
- 102: PolID: Motion-based, step 3
- 103: PolID: Motion-based, step 4
- 104: PolID: Motion-based, step 5

r0047	Motor data ident. routine and speed controller optimization / MotID and n_opt			
VECTOR	Can be changed: -			Access level: 1
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	0	300		200
Description:	Displays the actual status for the motor data identification (standstill measurement) and the speed/velocity controller optimization (rotating measurement).			
Values:	0: No measurement 120: Speed controller optimization, (vibration test) 140: Calculate speed controller setting 150: Measurement, moment of inertia 170: Measurement, magnetizing current and saturation characteristic 190: Speed encoder test 200: Rotating measurement selected 210: Pole position identification selected 220: identification, leakage inductance 230: Identification, rotor time constant 240: Identification, stator inductance 270: Identification, stator resistance 290: Identification, valve lockout time 300: Standstill measurement selected			
r0049[0...3]	Motor/encoder data set effective / MDS/EDS effective			
SERVO, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned8	Dynamic index: -		Function diagram: 8565
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the effective Motor Data Set (MDS) and the effective Encoder Data Sets (EDS).			
Index:	[0] = Motor Data Set MDS effective [1] = Encoder1 Encoder Data Set EDS effective [2] = Encoder 2 Encoder Data Set EDS effective [3] = Encoder 3 Encoder Data Set EDS effective			
Dependency:	Refer to: p0186, p0187, p0188, p0189, r0838			
Note:	Value 99 means the following: No encoder assigned (not configured).			
r0050	CO/BO: Command Data Set CDS effective / CDS effective			
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned8	Dynamic index: -		Function diagram: 8560
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the effective Command Data Set (CDS).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	CDS eff., bit 0	On	Off
	01	CDS eff., bit 1	On	Off
	02	CDS eff., bit 2	On	Off
	03	CDS eff., bit 3	On	Off
Dependency:	Refer to: p0810, p0811, r0836			
Note:	The command data set selected via binector inputs p0810, p0811, p0812 and p0813 is displayed via r0836.			

r0051 CO/BO: Drive Data Set DDS effective / DDS effective

SERVO, TM41, VEC-TOR **Can be changed:** - **Access level:** 2
Data type: Unsigned8 **Dynamic index:** - **Function diagram:** -
P-Group: Displays, signals **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the effective Drive Data Set (DDS).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DDS eff., bit 0	On	Off	-
	01	DDS eff., bit 1	On	Off	-
	02	DDS eff., bit 2	On	Off	-
	03	DDS eff., bit 3	On	Off	-
	04	DDS eff., bit 4	On	Off	-

Dependency: Refer to: p0820, p0821, p0822, p0823, p0824, r0837

Note: The drive data set changeover is suppressed when selecting the motor identification, during the rotating measurement, the encoder calibration and the friction characteristic plot.

r0056 CO/BO: Status word, closed-loop control / ZSW cl-loop ctrl

SERVO **Can be changed:** - **Access level:** 3
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 2526
P-Group: Displays, signals **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the status word of the closed-loop control.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	De-magnetizing completed	Yes	No	-
	04	Magnetizing completed	Yes	No	2701
	08	Field weakening active	Yes	No	-
	14	Vdc_max controller active	Yes	No	-
	15	Vdc_min controller active	Yes	No	-

Note: Re bit 04:

The bit is immediately set after power-on

Exception:

For an induction motor with brake (except for p1215 = 2), the bit is only set when 60% of the reference flux is reached.

r0056 CO/BO: Status word, closed-loop control / ZSW cl-loop ctrl

VECTOR **Can be changed:** - **Access level:** 3
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 2526
P-Group: Displays, signals **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the status word of the closed-loop control.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Initialization completed	Yes	No	-
	01	De-magnetizing completed	Yes	No	-
	02	Pulse enable present	Yes	No	-
	03	Soft starting present	Yes	No	-
	04	Magnetizing completed	Yes	No	-

06	Accelerating voltage active	Yes	No	-
07	Frequency negative	Yes	No	6719
08	Field weakening active	Yes	No	-
09	Voltage limit active	Yes	No	-
10	Slip limit active	Yes	No	6310
11	Frequency limit active	Yes	No	6719
12	Current limiting controller voltage output active	Yes	No	-
13	Current/torque limiting	active	not active	-
14	Vdc_max controller active	Yes	No	6220, 6320
15	Vdc_min controller active	Yes	No	6220, 6320

r0060**CO: Speed setpoint before the setpoint filter / n_set before filt.**

SERVO, VECTOR

Can be changed: -**Access level:** 3**Data type:** Floating Point**Dynamic index:** -**Function diagram:** 2701,
2704, 5020, 6030, 6799**P-Group:** Displays, signals**Units group:** 3_1**Unit selection:** p0505**Min**

- [1/min]

Max

- [1/min]

Factory setting

- [1/min]

Description:

Displays the actual speed setpoint at the input of the speed controller or U/f characteristic (after the interpolator).

Dependency:

Refer to: r0020

Note:

The speed setpoint is available smoothed (r0020) and unsmoothed (r0060).

r0060**CO: Velocity setpoint before the setpoint filter / v_set before filt.**

SERVO (Lin)

Can be changed: -**Access level:** 3**Data type:** Floating Point**Dynamic index:** -**Function diagram:** 2701,
2704, 5020, 6030, 6799**P-Group:** Displays, signals**Units group:** 4_1**Unit selection:** p0505**Min**

- [m/min]

Max

- [m/min]

Factory setting

- [m/min]

Description:

Displays the actual velocity setpoint at the input of the velocity controller or U/f characteristic (after the interpolator).

Dependency:

Refer to: r0020

Note:

The velocity setpoint is available smoothed (r0020) and unsmoothed (r0060).

r0061[0...1]**CO: Speed actual value motor encoder / n_act mot. encoder**

SERVO, VECTOR

Can be changed: -**Access level:** 2**Data type:** Floating Point**Dynamic index:** -**Function diagram:** 1580,
4710, 4715**P-Group:** Displays, signals**Units group:** 3_1**Unit selection:** p0505**Min**

- [1/min]

Max

- [1/min]

Factory setting

- [1/min]

Description:

Displays the speed sensed by the motor encoder (unsmoothed).

Index:

[0] = Sensor 0 actual value

[1] = Sensor 1 actual value

r0061[0...1]	CO: Velocity actual value, motor encoder / v_act mot encoder		
SERVO (Lin)	Can be changed: -	Access level: 2	Function diagram: 1580, 4710, 4715
	Data type: Floating Point	Dynamic index: -	
	P-Group: Displays, signals	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity sensed by the motor encoder (unsmoothed).		
Index:	[0] = Sensor 0 actual value, [1] = Sensor 1 actual value		
r0062	CO: Speed setpoint after the filter / n_set after filter		
SERVO, VECTOR	Can be changed: -	Access level: 3	Function diagram: 1590, 1750, 5020, 5030, 5210, 6030
	Data type: Floating Point	Dynamic index: -	
	P-Group: Displays, signals	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the actual speed setpoint after the setpoint filters.		
r0062	CO: Velocity setpoint after the filter / v_set after filter		
SERVO (Lin)	Can be changed: -	Access level: 3	Function diagram: 1590, 1750, 5020, 5030, 5210, 6030
	Data type: Floating Point	Dynamic index: -	
	P-Group: Displays, signals	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the actual velocity setpoint after the setpoint filters.		
r0063	CO: Actual speed, smoothed / n_act smooth		
SERVO	Can be changed: -	Access level: 3	Function diagram: 1580, 1590, 4710, 5300
	Data type: Floating Point	Dynamic index: -	
	P-Group: Displays, signals	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the actual, smoothed actual speed for speed control.		
Dependency:	Refer to: r0021		
Note:	The value is calculated in sensorless operation. The speed actual value is available smoothed (r0021) and unsmoothed (r0063).		
r0063	CO: Actual velocity, smoothed / v_act smooth		
SERVO (Lin)	Can be changed: -	Access level: 3	Function diagram: 1580, 1590, 4710, 5300
	Data type: Floating Point	Dynamic index: -	
	P-Group: Displays, signals	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the actual, smoothed velocity actual value for velocity control.		
Dependency:	Refer to: r0021		
Note:	The value is calculated in sensorless operation. The velocity actual value is available smoothed (r0021) and unsmoothed (r0063).		

r0063	CO: Actual speed, smoothed / n_act smooth		
TM41	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the currently smoothed speed actual value.		
Note:	For Terminal Module 41 (TM41), this value is used to interconnect with standard telegram 3 and is always zero.		
r0063[0...1]	CO: Actual speed value / n_act		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1680, 4715
	P-Group: Displays, signals	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the actual speed of the closed-loop speed control and the U/f control.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045		
Dependency:	Refer to: r0021		
Note:	The speed actual value is calculated in sensorless operation and for U/f control. For operation with encoder, r0063 is smoothed with p1441. The speed actual value r0063[0] is additionally displayed - smoothed with p0045 - in r0063[1].		
r0064	CO: Speed controller system deviation / n_ctrl system dev		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5040, 6040
	P-Group: Displays, signals	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the actual system deviation of the speed controller.		
Note:	In the servo control mode with active reference model, the system deviation to the P component of the speed/velocity controller is displayed.		
r0064	CO: Velocity controller system deviation / v_ctrl system dev		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5040, 6040
	P-Group: Displays, signals	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the actual system deviation of the velocity controller.		
Note:	In the servo control mode with active reference model, the system deviation to the P component of the velocity controller is displayed.		

r0065	Slip frequency / f_Slip		
SERVO, VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6310, 6730
	P-Group: Displays, signals	Units group: 2_1	Unit selection: p0505
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the slip frequency for induction motors (ASM).		
r0066	CO: Infeed line frequency / INF f_line		
A_INF, S_INF	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 8850, 8864, 8950, 8964
	P-Group: Displays, signals	Units group: 2_1	Unit selection: p0505
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the line frequency.		
Dependency:	Refer to: r0024		
Note:	The line frequency is available smoothed (r0024) and unsmoothed (r0066). A positive sign of the frequency is obtained when the line supply phases U, V and W are connected with the correct phase sequence. A negative sign of the frequency is obtained when the 3 line phases are interchanged therefore designating a negative direction of the rotating field of the 3-phase line supply voltage.		
r0066	CO: Drive output frequency / Drv f_output		
SERVO, VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 1690, 5300, 5730, 6310, 6730, 6731, 6799
	P-Group: Displays, signals	Units group: 2_1	Unit selection: p0505
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the Motor Module output frequency.		
Dependency:	Refer to: r0024		
Note:	The output frequency is available smoothed (r0024) and unsmoothed (r0066).		
r0067[0...1]	Permissible absolute infeed current magnitude OK / INF I_abs.val.perm		
A_INF, S_INF	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the actual permissible absolute line-side current.		
Index:	[0] = Motor mode [1] = Regenerative mode		
Dependency:	The permissible current is either the maximum converter current or the parameterized current limits, whichever is lower. Refer to: p3530, p3531		

r0067	Maximum drive output current / Drv I_output max		
SERVO, VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 5722, 6300, 6640, 6724
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the maximum output current of the Motor Module.		
Dependency:	The maximum output current is determined by the parameterized current limit and the motor and converter thermal protection. Refer to: p0290, p0640		
r0068	CO: Absolute current actual value / I_act abs.val.		
A_INF, SERVO, S_INF	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730, 8014, 8850, 8950
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays actual absolute current.		
Dependency:	Refer to: r0027		
Notice:	Bei A_INF, S_INF the following applies: The value is updated with the current controller sampling time. The following applies for SERVO: The value is updated with a sampling time of 1 ms.		
Note:	The calculated RMS value is only applicable for alternating currents. For DC current, a value is displayed that is too low by $\sqrt{2}$. Absolute current value = $\sqrt{I_q^2 + I_d^2}$ The absolute current actual value is available smoothed (r0027) and unsmoothed (r0068).		
r0068[0...1]	CO: Absolute current actual value / I_act abs.val.		
VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6714, 6799, 8014
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays actual absolute current.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045		
Dependency:	Refer to: r0027		
Notice:	The value is updated with the current controller sampling time.		
Note:	The calculated RMS value is only applicable for alternating currents. For DC current, a value is displayed that is too low by $\sqrt{2}$. Absolute current value = $\sqrt{I_q^2 + I_d^2}$ The absolute value of the current actual value is available smoothed (r0027 with 300 ms, r0068[1] with p0045) and unsmoothed (r0068[0]).		

r0069[0...6]	Phase current, actual value / I_Phase act value		
A_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1630, 5730, 6714, 6730, 6731, 8850, 8950
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured actual phase currents as peak value.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W [3] = Phase U offset [4] = Phase V offset [5] = Phase W offset [6] = Total U, V, W		
Note:	In indices 3 ... 5, the offset currents of the 3 phases, which are added to correct the phase currents, are displayed. The sum of the 3 corrected phase currents is displayed in index 6.		
r0070	CO: Actual DC link voltage / Vdc_act		
A_INF, B_INF, S_INF	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1774, 8750, 8850, 8864, 8940, 8950, 8964
	P-Group: Displays, signals	Units group: 5_2	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the measured actual value of the DC link voltage.		
Dependency:	Refer to: r0026		
Note:	The DC link voltage is available smoothed (r0026) and unsmoothed (r0070).		
r0070	CO: Actual DC link voltage / Vdc_act		
SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 5730
	P-Group: Displays, signals	Units group: 5_2	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the measured actual value of the DC link voltage.		
Dependency:	Refer to: r0026		
Notice:	For SINAMICS S120 AC Drive (AC/AC) the following applies: When measuring a DC link voltage < 200 V, for the Power Module (e.g. PM340) a valid measured value is not supplied. In this case, a value of approx. 300 V is displayed in the display parameter.		
Note:	The DC link voltage is available smoothed (r0026) and unsmoothed (r0070).		
r0071	Maximum output voltage / U_output max		
VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 6300, 6724
	P-Group: Displays, signals	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the maximum output voltage.		

Dependency: The maximum output voltage depends on the actual DC link voltage (r0070) and the maximum modulation depth (p1803).

Note: As the (driven) motor load increases, the maximum output voltage drops as a result of the reduction in DC-link voltage.

r0072 CO: Infeed, input voltage / INF U_input

A_INF, S_INF	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Units group: 5_1
	Min - [Veff]	Max - [Veff]
		Factory setting - [Veff]

Description: Displays the actual power unit input voltage (Line Module).

Note: The input voltage is available smoothed (r0025) and unsmoothed (r0072).

r0072 CO: Drive, output voltage / Drv U_output

SERVO, VECTOR	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Units group: 5_1
	Min - [Veff]	Max - [Veff]
		Factory setting - [Veff]

Description: Displays the actual power unit output voltage (Motor Module).

Dependency: Refer to: r0025

Note: The output voltage is available smoothed (r0025) and unsmoothed (r0072).

r0073 Maximum modulation depth / Modulat_depth max

VECTOR	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Modulation	Units group: -
	Min - [%]	Max - [%]
		Factory setting - [%]

Description: Displays the maximum modulation depth.

Dependency: Refer to: p1803

r0074 CO: Modulat_depth / Modulat_depth

A_INF, SERVO, VECTOR	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Displays, signals	Units group: -
	Min - [%]	Max - [%]
		Factory setting - [%]

Description: Displays the actual modulation depth.

Dependency: Refer to: r0028

Note: For space vector modulation, 100% corresponds to the maximum output voltage without overcontrol. Values above 100 % indicate an overcontrol condition - values below 100% have no overcontrol. The phase voltage (phase-to-phase, rms) is calculated as follows: $(r0074 * r0070) / (\sqrt{2} * 100 \%)$. The modulation depth is available smoothed (r0028) and unsmoothed (r0074).

r0075	CO: Reactive current setpoint / Id_set		
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the reactive current setpoint.		
Note:	The reactive current requirement of a line filter can be covered by the controlled infeed/regenerative feedback. The magnitude of the reactive current is determined by the capacitance of the line filter (p0221) that is automatically parameterized when a line filter is selected (p0220). For p0221 = 0, the controller does not generate reactive current for a line filter. Setpoint r0075 includes the reactive current for a line filter that depends on the actual operating point.		
r0075	Current setpoint, field-generating / Id_set		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1630, 5714, 5722, 6714
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the field-generating current setpoint (Id_set).		
Note:	This value is irrelevant for the U/f control mode.		
r0076	CO: Reactive current actual value / I_reactive_act		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1774, 1775, 8850, 8946, 8950
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the reactive current actual value.		
Dependency:	Refer to: r0029		
Note:	The reactive current actual value is available smoothed (r0029) and unsmoothed (r0076).		
r0076	Current actual value, field-generating / Id_act		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1630, 1710, 5714, 5730, 6714, 6799
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the field-generating current actual value (Id_act).		
Dependency:	Refer to: r0029		
Note:	This value is irrelevant for the U/f control mode. The field-generating current actual value is available smoothed (r0029) and unsmoothed (r0076).		

r0077	CO: Active current setpoint / Iq_set		
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1774, 8940, 8946
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the active current setpoint (Iq_set).		
r0077	CO: Current setpoint, torque-generating / Iq_set		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1630, 1774, 5714, 6710, 6714, 6719
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the torque/force generating current setpoint.		
Note:	This value is irrelevant for the U/f control mode.		
r0078	CO: Active current actual value / Iq_act		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1774, 1775, 8850, 8946, 8950
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the actual value for the active current.		
Dependency:	Refer to: r0030		
Note:	The active current actual value is available smoothed (r0030) and unsmoothed (r0078).		
r0078	CO: Current actual value, torque-generating / Iq_act		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1710, 6310, 6714, 6799
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the torque-generating current actual value (Iq_act).		
Dependency:	Refer to: r0030		
Note:	This value is irrelevant for the U/f control mode. The torque-generating current actual value is available smoothed (r0030 with 300 ms) and unsmoothed (r0078).		
r0078[0...1]	CO: Current actual value, torque-generating / Iq_act		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1630, 5714, 5730
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the torque-generating current actual value (Iq_act).		

Index: [0] = Unsmoothed
[1] = Smoothed with p0045

Dependency: Refer to: r0030, p0045

Note: These values are irrelevant for the U/f control mode.
The torque-generating current actual value is available smoothed (r0030 with 100 ms, r0078[1] with p0045) and unsmoothed (r0078[0]).

r0078[0...1] CO: Current actual value, torque-generating / Iq_act

SERVO (Lin) **Can be changed:** - **Access level:** 3

Data type: Floating Point **Dynamic index:** - **Function diagram:** 1630, 5714, 5730

P-Group: Displays, signals **Units group:** 6_2 **Unit selection:** p0505

Min **Max** **Factory setting**
- [Aeff] - [Aeff] - [Aeff]

Description: Displays the force-generating current actual value (Iq_act).

Index: [0] = Unsmoothed
[1] = Smoothed with p0045

Dependency: Refer to: r0030, p0045

Note: These values are irrelevant for the U/f control mode.
The force-generating current actual value is available smoothed (r0030 with 100 ms, r0078[1] with p0045) and unsmoothed (r0078[0]).

r0079[0...1] CO: Torque setpoint total / M_set total

SERVO **Can be changed:** - **Access level:** 3

Data type: Floating Point **Dynamic index:** - **Function diagram:** 5610, 8012

P-Group: Displays, signals **Units group:** 7_1 **Unit selection:** p0505

Min **Max** **Factory setting**
- [Nm] - [Nm] - [Nm]

Description: Displays the torque setpoint at the output of the speed controller (before clock cycle interpolation).

Index: [0] = Unsmoothed
[1] = Smoothed with p0045

r0079[0...1] CO: Total force setpoint / F_set total

SERVO (Lin) **Can be changed:** - **Access level:** 3

Data type: Floating Point **Dynamic index:** - **Function diagram:** 5610, 8012

P-Group: Displays, signals **Units group:** 8_1 **Unit selection:** p0505

Min **Max** **Factory setting**
- [N] - [N] - [N]

Description: Displays the force setpoint at the output of the velocity controller (before clock cycle interpolation).

Index: [0] = Unsmoothed
[1] = Smoothed with p0045

r0079 CO: Torque setpoint total / M_set total

VECTOR **Can be changed:** - **Access level:** 3

Data type: Floating Point **Dynamic index:** - **Function diagram:** 1700, 1710, 6030, 6060, 6710, 8012

P-Group: Displays, signals **Units group:** 7_1 **Unit selection:** p0505

Min **Max** **Factory setting**
- [Nm] - [Nm] - [Nm]

Description: Displays the torque setpoint at the output of the speed controller (before clock cycle interpolation).

r0080	CO: Torque actual value / M_act		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730
	P-Group: Displays, signals	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the actual torque value.		
Dependency:	Refer to: r0031		
Note:	The torque actual value is available smoothed (r0031) and unsmoothed (r0080).		
r0080	CO: Force actual value / F_act		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5730
	P-Group: Displays, signals	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the actual force value.		
Dependency:	Refer to: r0031		
Note:	The force actual value is available smoothed (r0031) and unsmoothed (r0080).		
r0080[0...1]	CO: Torque actual value / M_act		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6714, 6799
	P-Group: Displays, signals	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the actual torque value.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045		
Dependency:	Refer to: r0031		
Note:	The torque actual value is available smoothed (r0031 with 100 ms, r0080[1] with p0045) and unsmoothed (r0080[0]).		
r0081	CO: Torque utilization / M_Utilization		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8012
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the torque utilization as a percentage. The torque utilization is obtained from the required smoothed torque referred to the torque limit.		
Dependency:	Refer to: r0033		
Note:	The torque utilization is available smoothed (r0033) and unsmoothed (r0081). For SERVO, the following applies: The calculation of the torque utilization depends on the selected smoothing time constant (p0045).		

r0081	CO: Force utilization / F_utilization		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8012
	P-Group: Displays, signals		Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the force utilization as a percentage. The force utilization is obtained from the required smoothed force referred to the force limit.		
Dependency:	Refer to: r0033		
Note:	The force utilization is available smoothed (r0033) and unsmoothed (r0081). The calculation of the force utilization depends on the selected smoothing time constant (p0045).		
r0082	CO: Active power actual value / P_act		
A_INF, S_INF	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 14_7	Function diagram: 8850, 8950
	P-Group: Displays, signals		Unit selection: p0505
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the instantaneous active power.		
Dependency:	Refer to: r0032		
Note:	The active power is available smoothed (r0032 with 300 ms) and unsmoothed (r0082).		
r0082[0...2]	CO: Active power actual value / P_act		
SERVO	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 14_5	Function diagram: 5730
	P-Group: Displays, signals		Unit selection: p0505
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the instantaneous active power.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045 [2] = Power drawn		
Dependency:	Refer to: r0032		
Note:	The active power is available smoothed (r0032 with 100 ms, r0082[1] with p0045) and unsmoothed (r0082[0]).		
r0082[0...2]	CO: Active power actual value / P_act		
VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 14_5	Function diagram: 6714, 6799
	P-Group: Displays, signals		Unit selection: p0505
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the instantaneous active power.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045 [2] = Power drawn		
Dependency:	Refer to: r0032		
Note:	The active power is available smoothed (r0032 with 100 ms, r0082[1] with p0045) and unsmoothed (r0082[0]). The unsmoothed, electric motor active power is displayed in r0082[2] without taking into account the motor losses.		

r0083	CO: Flux setpoint / Flux setpoint		
SERVO, VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 5722
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the flux setpoint.		
r0084	CO: Actual flux / Actual flux		
SERVO	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 5722
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the actual flux.		
r0084[0...1]	CO: Actual flux / Actual flux		
VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6726, 6730, 6731
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the actual flux.		
Index:	[0] = Unsmoothed [1] = Smoothed		
Note:	The flux actual value Index 1 is only smoothed for separately-excited synchronous motors (p1585).		
r0087	CO: Actual power factor / Cos_phi_act val		
VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6730, 6731, 6799
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the actual active power factor.		
r0088	CO: DC-link voltage setpoint / Vdc setpoint		
A_INF	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940, 8964
	P-Group: Displays, signals	Units group: 5_2	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the setpoint for the DC link voltage.		

r0089[0...2]	Actual phase voltage / U_phase act. val.		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6719
	P-Group: Displays, signals	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual phase voltage.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
p0092	Clock synchronous PROFIBUS operation pre-assignment/check / Clock sync PB oper		
CU_S	Can be changed: C1(1)		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Setting to pre-assign/check the sampling times for the internal controller clock cycles for clock synchronous PROFIBUS operation. p0092 = 1: The controller clock cycles are set so that clock synchronous PROFIBUS operation is possible. If it is not possible to change the controller clock cycles of the clock synchronous PROFIBUS operation, then an appropriate message/signal is output. The pre-setting of the controller clock cycles can result in a de-rating of the Motor Module (e.g. p0115[0] = 400 µs -> 375 µs). p0092 = 0: The controller clock cycles are set without any restrictions by the clock synchronous PROFIBUS operation (as for up to version V2.3).		
Dependency:	Refer to: r0110, p0115 Refer to: A01223, A01224		
r0093	CO: Pole position angle electrically normalized / Pole pos el norm		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the normalized electrical pole position angle.		
Dependency:	Refer to: r0094, p0431, r1778		
Notice:	The following applies for direction of rotation (p1821 = 1): In order to adjust the encoder using the EMF method, the value, determined using the oscilloscope, must be inverted and then entered in p0431.		
Note:	For operation with encoder and pulse cancellation, the following applies: - the value is generated from r0094 + 180 °. - this angle can be used to adjust the encoders of synchronous motors. For pulse enable, the following applies: - the value indicates the transformation angle used by the control + 180 °. - this value is, contrary to r0094, also applicable (provides information) for sensorless operation and after a pole position identification routine.		

r0094	CO: Transformation angle / Transformat_angle		
A_INF, S_INF	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 8850, 8950
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the transformation angle.		
Note:	The transformation angle corresponds to the line supply angle.		
r0094	CO: Transformation angle / Transformat_angle		
SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1580, 4710, 4715, 6714, 6730
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the transformation angle.		
Dependency:	Refer to: r0093, p0431, r1778		
Note:	The transformation angle corresponds to the electrical commutation angle. If no pole position identification is carried-out (p1982), and the encoder is adjusted, the following applies: The encoder supplies the value and indicates the electrical angle of the flux position (d axis).		
p0097	Select drive object type / Select DO type		
CU_S	Can be changed: C1(1)	Dynamic index: -	Access level: 1
	Data type: Integer16		Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 14	Factory setting 0
Description:	Executes an automatic device configuration. In so doing, p0099, p0107 and p0108 are appropriately set.		
Values:	0: No selection 1: Drive object type SERVO 2: Drive object type VECTOR 3: SINAMICS GM (DFEMV & VECTORMV) 4: SINAMICS SM (AFEMV & VECTORMV) 5: SINAMICS GL (VECTORGL) 12: Drive object type VECTOR parallel circuit 13: Drive object type VECTORMV - GM parallel circuit 14: Drive object type VECTORMV - SM parallel circuit		
Dependency:	Refer to: r0098, p0099 Refer to: A01330		
Note:	For p0097 = 0, p0099 is automatically set to the factor setting. The setting p0097 = 1 is not possible for chassis-type power units as well as for SINAMICS G or SINAMICS GM. The setting p0097 = 12 is not possible for booksize power units.		

r0098[0...5]		Actual device topology / Device_act topo	
CU_S	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the automatically detected actual device topology in coded form.		
Index:	[0] = DRIVE-CLiQ socket X100 [1] = DRIVE-CLiQ socket X101 [2] = DRIVE-CLiQ socket X102 [3] = DRIVE-CLiQ socket X103 [4] = DRIVE-CLiQ socket X104 [5] = DRIVE-CLiQ socket X105		
Dependency:	Refer to: p0097, p0099		
Note:	Topology coding: abcd efgh hex a = number of Active Line Modules b = number of Motor Modules c = number of motors d = number of encoders (or the line supply voltage sensing for Active Line Modules) e = number of additional encoders (or the line supply voltage sensing for Active Line Modules) f = number of Terminal Modules g = number of terminal boards h = reserved if the value 0 is displayed in all indices, then components are not detected via DRIVE-CLiQ. If a value F hex occurs at a position of the coding (abcd efgh hex), then an overflow has occurred.		
p0099[0...5]		Device target topology / Device_target topo	
CU_S	Can be changed: C1(1)		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex
Description:	Sets the device target topology in coded form (refer to r0098). The setting is made during commissioning.		
Index:	[0] = DRIVE-CLiQ socket X100 [1] = DRIVE-CLiQ socket X101 [2] = DRIVE-CLiQ socket X102 [3] = DRIVE-CLiQ socket X103 [4] = DRIVE-CLiQ socket X104 [5] = DRIVE-CLiQ socket X105		
Dependency:	The parameter can only be written into for p0097 = 0. To perform an automatic device configuration run, an index of the device target topology must be set to the value of the device actual topology in r0098 for acknowledgement. An index of the device actual topology with a value other than 0 must be selected. Refer to: p0097, r0098 Refer to: A01330		
Note:	The parameter can only be set to the values 0, the value of the actual device topology, the value of the actual device target topology and FFFFFFFF hex. If the value 0 is displayed in all of the indices, then the system has still not be commissioned. The value FFFFFFFF hex indicates that the topology was not generated by the automatic device configuration but was commissioned using the commissioning software (e.g. using parameter download).		

p0100		IEC/NEMA mot stds / IEC/NEMA mot stds		
SERVO, VECTOR	Can be changed: C2(1)			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Converter	Units group: -		Unit selection: -
	Min 0	Max 1		Factory setting 0
Description:	<p>Defines whether the motor and drive converter power settings (e.g. rated motor power - p0307) are expressed in [kW] or [hp].</p> <p>Depending on the selection, the rated motor frequency (p0310) is either set to 50 Hz or 60 Hz.</p> <p>The following applies for IEC drives: The power factor (p0308) should be parameterized.</p> <p>The following applies for NEMA drives: The efficiency (p0309) should be parameterized.</p>			
Values:	<p>0: IEC-Motor (50Hz, SI units)</p> <p>1: NEMA motor (60Hz, US units)</p>			
Dependency:	<p>If p0100 is changed, all of the rated motor parameters are reset.</p> <p>Refer to: r0206, p0210, p0300, p0304, p0305, p0307, p0308, p0309, p0310, p0311, p0312, p0314, p0320, p0322, p0323, p0335, r0336, r0337, p0338, p1800</p>			
Note:	<p>The parameter can only be changed for closed-loop vector control (p0107).</p> <p>The parameter value is not reset when the factory setting is restored (p0010 = 30, p0970).</p>			
p0101[0...15]		Drive object numbers / DO numbers		
CU_S	Can be changed: C1(1)			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Topology	Units group: -		Unit selection: -
	Min 0	Max 62		Factory setting 0
Description:	<p>The parameter contains the object number via which every drive object can be addressed.</p> <p>The number of an existing drive object is entered into each index.</p> <p>The numbers are automatically assigned once and cannot longer be changed as long as the object has not been deleted.</p> <p>In the commissioning software, this object number cannot be entered using the Expert list, but is automatically assigned when inserting an object.</p>			
Index:	<p>[0] = Drive object number, Control Unit</p> <p>[1] = Drive object number, object 1</p> <p>[2] = Drive object number, object 2</p> <p>[3] = Drive object number, object 3</p> <p>[4] = Drive object number, object 4</p> <p>[5] = Drive object number, object 5</p> <p>[6] = Drive object number, object 6</p> <p>[7] = Drive object number, object 7</p> <p>[8] = Drive object number, object 8</p> <p>[9] = Drive object number, object 9</p> <p>[10] = Drive object number, object 10</p> <p>[11] = Drive object number, object 11</p> <p>[12] = Drive object number, object 12</p> <p>[13] = Drive object number, object 13</p> <p>[14] = Drive object number, object 14</p> <p>[15] = Drive object number, object 15</p>			
Note:	<p>Value = 0: No drive object is defined.</p>			

r0102	Number of drive objects / DO count		
CU_S	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the total number of available drive objects.		
Note:	The numbers of the drive objects are in p0101.		
p0103[0...15]	Application-specific view / Appl_spec view		
CU_S	Can be changed: C1(2)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	999	0
Description:	The application-specific view of an existing drive object is entered into each index. The parameter cannot be changed.		
Dependency:	Refer to: p0107, r0107 Refer to: F01051		
Note:	The application-specific views are defined in files on the CompactFlash card with the following structure: PDxxxxyy.ACX xxx: Application-specific view (p0103), yyy: Type of drive object (p0107) Example: PD052011.ACX -> "011" stands for the drive object, type SERVO -> "052" is the number of the view for this drive object		
r0103	Application-specific view / Appl_spec view		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the application-specific view of the individual drive object.		
Dependency:	Refer to: p0107, r0107 Refer to: F01051		
p0105	Activate/de-activate drive object / DO act/de-act		
CU_S	Can be changed: U, T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	1
Description:	Setting to activate/de-activate a drive object.		
Values:	0: De-activate drive object 1: Activate drive object		
Dependency:	Refer to: r0106		
Notice:	The following applies when activating: If components are inserted for the first time and the appropriate drive object is activated, then the drive system is automatically booted. To do this, the pulses of all of the drive objects must be cancelled.		

p0105	Activate/de-activate drive object / DO act/de-act		
A_INF, B_INF, CU_LINK, DMC20, SERVO, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VEC- TOR	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Integer16		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Setting to activate/de-activate a drive object.		
Values:	0: De-activate drive object 1: Activate drive object		
Dependency:	Refer to: r0106		
Notice:	The following applies when activating: If components are inserted for the first time and the appropriate drive object is activated, then the drive system is automatically booted. To do this, the pulses of all of the drive objects must be cancelled.		
Note:	Setting a drive object to de-activated principally corresponds to the "parking axis" function. however, here, all of the DRIVE-CLiQ components, assigned to the drive object, are in involved.		
r0106	Drive object active/inactive / DO act/inact		
All objects	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Integer16		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Displays the "active/inactive" state of a drive object.		
Values:	0: Drive object inactive 1: Drive object active		
Dependency:	Refer to: p0105		
p0107[0...15]	Drive object type / DO type		
CU_S	Can be changed: C1(2)	Dynamic index: -	Access level: 2
	Data type: Integer16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 254	Factory setting 0
Description:	The type of an existing drive object is entered into each index.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV		

100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Index:
 [0] = Drive object time, Control Unit
 [1] = Drive object type, object 1
 [2] = Drive object type, object 2
 [3] = Drive object type, object 3
 [4] = Drive object type, object 4
 [5] = Drive object type, object 5
 [6] = Drive object type, object 6
 [7] = Drive object type, object 7
 [8] = Drive object type, object 8
 [9] = Drive object type, object 9
 [10] = Drive object type, object 10
 [11] = Drive object type, object 11
 [12] = Drive object type, object 12
 [13] = Drive object type, object 13
 [14] = Drive object type, object 14
 [15] = Drive object type, object 15

Dependency:
 Refer to: p0103, r0103
 Refer to: F01051



Caution: If you change this parameter and exit the device commissioning mode, then the complete software will be set up again and all of the previous drive parameter settings are deleted.

Note: The number (p0101) and the associated drive object type are in the same index.
 For SINAMICS S a drive object type can only be changed between SERVO and VECTOR. If you change the parameter and exit drive start-up (p0009 from 2 to 0) the drive parameters are set up again.

r0107 Drive object type / DO type

A_INF	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min	Max	Factory setting
	0	254	10

Description: Displays the type of each drive object.

Values:

- 0: -
- 1: SINAMICS S
- 2: SINAMICS G
- 3: SINAMICS I
- 4: SINAMICS CX32
- 5: SINAMICS GM
- 7: SINAMICS GL
- 10: ACTIVE LINE MODULE
- 11: SERVO
- 12: VECTOR
- 13: VECTORMV
- 14: VECTORGL
- 20: SMART LINE MODULE
- 30: BASIC LINE MODULE
- 40: ACTIVE LINE MODULEMV
- 41: BASIC LINE MODULEMV

100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107 Drive object type / DO type

SERVO	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min	Max	Factory setting
	0	254	11

Description: Displays the type of each drive object.

Values:

0: -
 1: SINAMICS S
 2: SINAMICS G
 3: SINAMICS I
 4: SINAMICS CX32
 5: SINAMICS GM
 7: SINAMICS GL
 10: ACTIVE LINE MODULE
 11: SERVO
 12: VECTOR
 13: VECTORMV
 14: VECTORGL
 20: SMART LINE MODULE
 30: BASIC LINE MODULE
 40: ACTIVE LINE MODULEMV
 41: BASIC LINE MODULEMV
 100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107	Drive object type / DO type		
VECTOR	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	12
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV 100: TB30 (Terminal Board) 150: DMC (DRIVE-CLiQ Hub Module Cabinet) 200: TM31 (Terminal Module) 201: TM41 (Terminal Module) 202: TM17 High Feature (Terminal Module) 203: TM15 (Terminal Module) 204: TM15 (Terminal Module for SINAMICS) 254: CU-LINK		
Dependency:	Refer to: p0103, r0103 Refer to: F01051		

r0107	Drive object type / DO type		
S_INF	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	20
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV		

100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107 Drive object type / DO type

B_INF	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min	Max	Factory setting
	0	254	30

Description: Displays the type of each drive object.

Values:

- 0: -
- 1: SINAMICS S
- 2: SINAMICS G
- 3: SINAMICS I
- 4: SINAMICS CX32
- 5: SINAMICS GM
- 7: SINAMICS GL
- 10: ACTIVE LINE MODULE
- 11: SERVO
- 12: VECTOR
- 13: VECTORMV
- 14: VECTORGL
- 20: SMART LINE MODULE
- 30: BASIC LINE MODULE
- 40: ACTIVE LINE MODULEMV
- 41: BASIC LINE MODULEMV
- 100: TB30 (Terminal Board)
- 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
- 200: TM31 (Terminal Module)
- 201: TM41 (Terminal Module)
- 202: TM17 High Feature (Terminal Module)
- 203: TM15 (Terminal Module)
- 204: TM15 (Terminal Module for SINAMICS)
- 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107	Drive object type / DO type		
TB30	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	100
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV 100: TB30 (Terminal Board) 150: DMC (DRIVE-CLiQ Hub Module Cabinet) 200: TM31 (Terminal Module) 201: TM41 (Terminal Module) 202: TM17 High Feature (Terminal Module) 203: TM15 (Terminal Module) 204: TM15 (Terminal Module for SINAMICS) 254: CU-LINK		
Dependency:	Refer to: p0103, r0103 Refer to: F01051		

r0107	Drive object type / DO type		
DMC20	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	150
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV		

100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107**Drive object type / DO type**

TM31

Can be changed: -**Access level:** 2**Data type:** Integer16**Dynamic index:** -**Function diagram:** -**P-Group:** Closed-loop control**Units group:** -**Unit selection:** -**Min****Max****Factory setting**

0

254

200

Description: Displays the type of each drive object.**Values:**

0: -
 1: SINAMICS S
 2: SINAMICS G
 3: SINAMICS I
 4: SINAMICS CX32
 5: SINAMICS GM
 7: SINAMICS GL
 10: ACTIVE LINE MODULE
 11: SERVO
 12: VECTOR
 13: VECTORMV
 14: VECTORGL
 20: SMART LINE MODULE
 30: BASIC LINE MODULE
 40: ACTIVE LINE MODULEMV
 41: BASIC LINE MODULEMV
 100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107	Drive object type / DO type		
TM41	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	201
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV 100: TB30 (Terminal Board) 150: DMC (DRIVE-CLiQ Hub Module Cabinet) 200: TM31 (Terminal Module) 201: TM41 (Terminal Module) 202: TM17 High Feature (Terminal Module) 203: TM15 (Terminal Module) 204: TM15 (Terminal Module for SINAMICS) 254: CU-LINK		
Dependency:	Refer to: p0103, r0103 Refer to: F01051		

r0107	Drive object type / DO type		
TM17	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	202
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV		

100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107 Drive object type / DO type

TM15	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	203

Description: Displays the type of each drive object.

Values:

- 0: -
- 1: SINAMICS S
- 2: SINAMICS G
- 3: SINAMICS I
- 4: SINAMICS CX32
- 5: SINAMICS GM
- 7: SINAMICS GL
- 10: ACTIVE LINE MODULE
- 11: SERVO
- 12: VECTOR
- 13: VECTORMV
- 14: VECTORGL
- 20: SMART LINE MODULE
- 30: BASIC LINE MODULE
- 40: ACTIVE LINE MODULEMV
- 41: BASIC LINE MODULEMV
- 100: TB30 (Terminal Board)
- 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
- 200: TM31 (Terminal Module)
- 201: TM41 (Terminal Module)
- 202: TM17 High Feature (Terminal Module)
- 203: TM15 (Terminal Module)
- 204: TM15 (Terminal Module for SINAMICS)
- 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

r0107	Drive object type / DO type		
TM15DI_DO	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	204
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV 100: TB30 (Terminal Board) 150: DMC (DRIVE-CLiQ Hub Module Cabinet) 200: TM31 (Terminal Module) 201: TM41 (Terminal Module) 202: TM17 High Feature (Terminal Module) 203: TM15 (Terminal Module) 204: TM15 (Terminal Module for SINAMICS) 254: CU-LINK		
Dependency:	Refer to: p0103, r0103 Refer to: F01051		

r0107	Drive object type / DO type		
CU_LINK	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	254	254
Description:	Displays the type of each drive object.		
Values:	0: - 1: SINAMICS S 2: SINAMICS G 3: SINAMICS I 4: SINAMICS CX32 5: SINAMICS GM 7: SINAMICS GL 10: ACTIVE LINE MODULE 11: SERVO 12: VECTOR 13: VECTORMV 14: VECTORGL 20: SMART LINE MODULE 30: BASIC LINE MODULE 40: ACTIVE LINE MODULEMV 41: BASIC LINE MODULEMV		

100: TB30 (Terminal Board)
 150: DMC (DRIVE-CLiQ Hub Module Cabinet)
 200: TM31 (Terminal Module)
 201: TM41 (Terminal Module)
 202: TM17 High Feature (Terminal Module)
 203: TM15 (Terminal Module)
 204: TM15 (Terminal Module for SINAMICS)
 254: CU-LINK

Dependency: Refer to: p0103, r0103
 Refer to: F01051

p0108[0...15] Drive object, function module / DO function module

CU_S **Can be changed:** C1(2) **Access level:** 2
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: - **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: The function module of an existing drive object is entered into each index.

Index:
 [0] = Function module Control Unit
 [1] = Function module object 1
 [2] = Function module object 2
 [3] = Function module object 3
 [4] = Function module object 4
 [5] = Function module object 5
 [6] = Function module object 6
 [7] = Function module object 7
 [8] = Function module object 8
 [9] = Function module object 9
 [10] = Function module object 10
 [11] = Function module object 11
 [12] = Function module object 12
 [13] = Function module object 13
 [14] = Function module object 14
 [15] = Function module object 15

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	18	Free function blocks	Activated	Not activated	-
	29	CAN	Activated	Not activated	-
	30	COMM BOARD	Activated	Not activated	-
	31	PROFINET	Activated	Not activated	-

Note: A "function module" is a functional expansion of a drive object that can be activated when commissioning.

r0108 Drive object, function module / DO function module

A_INF, B_INF **Can be changed:** - **Access level:** 2
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: Closed-loop control **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the activated function module for the particular drive object.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	15	Parallel cct. config.	Activated	Not activated	-
	18	Free function blocks	Activated	Not activated	-
	26	Braking Module	Activated	Not activated	-
	28	Cooling system	Activated	Not activated	-
	31	PROFINET	Activated	Not activated	-

Note: A "function module" is a functional expansion of a drive object that can be activated when commissioning.

r0108 Drive object, function module / DO function module

SERVO	Can be changed: -	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: -
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays the activated function module for the particular drive object.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Expanded closed-loop torque control	Activated	Not activated	-
	02	Closed-loop speed/torque control	Activated	Not activated	-
	03	Cl.-loop pos ctrl	Activated	Not activated	-
	04	Basic positioner	Activated	Not activated	-
	07	Advanced Positioning Control (APC)	Activated	Not activated	-
	08	Extended setpoint channel	Activated	Not activated	-
	12	Linear motor	Activated	Not activated	-
	13	Safety rotary axis	Activated	Not activated	-
	14	Extended brake control	Activated	Not activated	-
	16	Technology controller	Activated	Not activated	-
	17	Extended messages/monitoring	Activated	Not activated	-
	18	Free function blocks	Activated	Not activated	-
	28	Cooling system	Activated	Not activated	-
	29	CAN	Activated	Not activated	-
	31	PROFINET	Activated	Not activated	-

Note: A "function module" is a functional expansion of a drive object that can be activated when commissioning.

r0108 Drive object, function module / DO function module

VECTOR	Can be changed: -	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: -
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays the activated function module for the particular drive object.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	02	Closed-loop speed/torque control	Activated	Not activated	-
	03	Cl.-loop pos ctrl	Activated	Not activated	-
	04	Basic positioner	Activated	Not activated	-
	08	Extended setpoint channel	Activated	Not activated	-
	14	Extended brake control	Activated	Not activated	-
	15	Parallel cct. config.	Activated	Not activated	-
	16	Technology controller	Activated	Not activated	-
	17	Extended messages/monitoring	Activated	Not activated	-
	18	Free function blocks	Activated	Not activated	-
	28	Cooling system	Activated	Not activated	-
	29	CAN	Activated	Not activated	-
	31	PROFINET	Activated	Not activated	-

Note: A "function module" is a functional expansion of a drive object that can be activated when commissioning.

r0108	Drive object, function module / DO function module				
S_INF	Can be changed: -		Access level: 2		
	Data type: Unsigned32	Dynamic index: -	Function diagram: -		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the activated function module for the particular drive object.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	15	Parallel cct. config.	Activated	Not activated	-
	18	Free function blocks	Activated	Not activated	-
	26	Braking Module	Activated	Not activated	-
	31	PROFINET	Activated	Not activated	-
Note:	A "function module" is a functional expansion of a drive object that can be activated when commissioning.				
r0108	Drive object, function module / DO function module				
TB30, TM15DI_DO, TM31, TM41	Can be changed: -		Access level: 2		
	Data type: Unsigned32	Dynamic index: -	Function diagram: -		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the activated function module for the particular drive object.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	18	Free function blocks	Activated	Not activated	-
	31	PROFINET	Activated	Not activated	-
Note:	A "function module" is a functional expansion of a drive object that can be activated when commissioning.				
r0110[0...2]	DRIVE-CLiQ basis sampling times / DLQ t_basis				
CU_S	Can be changed: -		Access level: 3		
	Data type: Floating Point	Dynamic index: -	Function diagram: -		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	0.00 [µs]	10000.00 [µs]	[0] 125.00 [µs] [1] 250.00 [µs] [2] 250.00 [µs]		
Description:	Displays the basis sampling times. The sampling times are set using p0112 and p0115. The values for the basis sampling times are determined as a result of these settings.				
Index:	[0] = Basis sampling time 0 [1] = Basis sampling time 1 [2] = Basis sampling time 2				
r0111	DRIVE-CLiQ basis sampling time selection / DLQ t_basis sel				
All objects	Can be changed: -		Access level: 3		
	Data type: Integer16	Dynamic index: -	Function diagram: -		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	0	2	0		
Description:	Displays the selected basis sampling time for this drive object.				
Dependency:	Refer to: r0110				

p0112		Sampling times pre-setting p0115 / t_sample for p0115	
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 5	Factory setting 3
Description:	<p>Pre-assignment of the sampling times in p0115.</p> <p>The clock cycles for the current controller/speed controller/flux controller/setpoint channel / - / - / technology controller are pre-assigned as follows:</p> <p>SINAMICS S, servo drive:</p> <p>p0112 = 1: 250 / 250 / 250 / 4000 / 2000 / 8000 / 4000 µs (for chassis drive units)</p> <p>p0112 = 2: 125 / 250 / 250 / 4000 / 2000 / 8000 / 4000 µs</p> <p>p0112 = 3: 125 / 125 / 125 / 4000 / 1000 / 4000 / 4000 µs</p> <p>p0112 = 4: 62.5 / 62.5 / 62.5 / 1000 / 1000 / 2000 / 1000 µs</p> <p>p0112 = 5: Not possible</p> <p>SINAMICS S, Active Infeed (p0112 = 1 not for p0092 = 1):</p> <p>p0112 = 1: 400 / - / - / 1600 µs</p> <p>p0112 = 2: 250 / - / - / 2000 µs</p> <p>p0112 = 3: 125 / - / - / 2000 µs</p> <p>p0112 = 4: 125 / - / - / 1000 µs</p> <p>p0112 = 5: 125 / - / - / 500 µs</p> <p>SINAMICS S, Smart Infeed (p0112 = 1 not for p0092 = 1):</p> <p>p0112 = 1: 400 / - / - / 1600 µs</p> <p>p0112 = 2: 250 / - / - / 2000 µs</p> <p>p0112 = 3: 250 / - / - / 2000 µs</p> <p>p0112 = 4: 250 / - / - / 1000 µs</p> <p>p0112 = 5: Not possible</p> <p>SINAMICS S, basic infeed:</p> <p>p0112 = 1: 2000 / - / - / 2000 µs</p> <p>p0112 = 2: 2000 / - / - / 2000 µs</p> <p>p0112 = 3: 2000 / - / - / 2000 µs</p> <p>p0112 = 4: 1000 / - / - / 1000 µs</p> <p>p0112 = 5: 500 / - / - / 500 µs</p> <p>SINAMICS S/G, vector drive (p0112 = 1 not for p0092 = 1 and not for PM340):</p> <p>p0112 = 1: 400 / 1600 / 1600 / 1600 / 3200 / 3200 / 3200 µs (for a rated pulse frequency of 1.25 / 2.5 kHz)</p> <p>p0112 = 2: 250 / 1000 / 2000 / 1000 / 2000 / 4000 / 4000 µs</p> <p>p0112 = 3: 250 / 1000 / 1000 / 1000 / 2000 / 4000 / 4000 µs (for a rated pulse frequency of 2 / 4 kHz)</p> <p>SINAMICS S, vector drive:</p> <p>p0112 = 4: 250 / 500 / 1000 / 500 / 1000 / 2000 / 2000 µs</p> <p>p0112 = 5: 250 / 250 / 1000 / 250 / 1000 / 2000 / 1000 µs</p>		
Values:	<p>0: Expert</p> <p>1: xLow</p> <p>2: Low</p> <p>3: Standard</p> <p>4: High</p> <p>5: xHigh</p>		
Dependency:	<p>It is prohibited to select a parameter value from p0112 if the associated current controller clock cycle cannot set (e.g. p0112 = 1 is not possible for SINAMICS S and PM349 power unit).</p> <p>Refer to: p0092</p>		
Note:	<p>For p0112 = 0 (expert) the individual sampling times in p0115 can be adjusted.</p> <p>p0112 = 1 cannot be set for a power unit type PM340 (refer to r0203) for vector drives.</p>		

p0113	Pulse frequency, minimum selection / F_puls min sel		
SERVO	Can be changed: C1(3)		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 2.000 [kHz]	Max 4.000 [kHz]	Factory setting 4.000 [kHz]
Description:	The current controller sampling time (p0115[0]) is pre-assigned by selecting the minimum pulse frequency.		
Dependency:	The parameter can only be changed with p0112 = 0 (expert). The required pulse frequency can be set in p1800 after commissioning (p0009 = p0010 = 0). Refer to: p0112, r0114, p0115, p1800		
Note:	The current controller sampling time (p0115[0]) is set to the inverse value of twice the minimum pulse frequency. For p0113 = 2.0 kHz, p0115[0] = 250 µs is set, for p0113 = 4.0 kHz, p0115[0] = 125 µs is set. The current controller sampling time (p0115[0]), calculated from the pulse frequency, is set in a grid of 1.25 µs. For a power unit type PM340 (refer to r0203), only the values 2.0 and 4.0 kHz can be set.		
p0113	Pulse frequency, minimum selection / F_puls min sel		
VECTOR	Can be changed: C1(3)		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1.000 [kHz]	Max 2.000 [kHz]	Factory setting 2.000 [kHz]
Description:	The current controller sampling time (p0115[0]) is pre-assigned by selecting the minimum pulse frequency.		
Dependency:	The parameter can only be changed with p0112 = 0 (expert). The required pulse frequency can be set in p1800 after commissioning (p0009 = p0010 = 0). Refer to: p0112, r0114, p0115, p1800		
Note:	The current controller sampling time (p0115[0]) is set to the inverse value of twice the minimum pulse frequency. For p0113 = 1.0 kHz, p0115[0] = 500 µs is set, for p0113 = 2.0 kHz, p0115[0] = 250 µs is set. The current controller sampling time (p0115[0]), calculated from the pulse frequency, is set in a grid of 1.25 µs. For a power unit type PM340 (refer to r0203), only the values 1.0 and 2.0 kHz can be set. 1.0 kHz can be set in order to achieve a current controller clock cycle of 500µs. However, in this case, the minimum pulse frequency p1800 is limited to 2 kHz.		
r0114[0...9]	Pulse frequency, minimum recommended / F_puls min recom		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [kHz]	Max - [kHz]	Factory setting - [kHz]
Description:	Displays the recommended values for the minimum pulse frequency in indices 0 and 1. These are calculated if the system rejects a change in p0113 that does not lie within the permissible value range.		
Index:	[0] = Only the actual drive is changed [1] = All drives connected to the DRIVE-CLiQ line are changed [2] = 2. possible pulse frequency [3] = 3. possible pulse frequency [4] = 4. possible pulse frequency [5] = 5. possible pulse frequency [6] = 6. possible pulse frequency [7] = 7. possible pulse frequency [8] = 8. possible pulse frequency [9] = 9. possible pulse frequency		
Dependency:	Refer to: p0113		

Note: After existing commissioning (p0009 = p0010 = 0), the pulse frequencies calculated from the sampling time p115[0] are displayed in indices 1 to 8. If additional restrictions do not apply (e.g. due to having selected an output filter), these can be entered into p1800. The maximum pulse frequency of the power units was already taken into account in r0114.
A value of 0 kHz does not define a recommended pulse frequency.

p0115[0...0]	Sampling time for supplementary functions / t_sample suppl fct		
CU_S	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00 [µs]	Max 16000.00 [µs]	Factory setting 4000.00 [µs]
Description:	Sets the basis sampling time for supplementary functions on this object.		
Index:	[0] = Basis sampl. time		
p0115[0...0]	Sampling time for supplementary functions / t_sample suppl fct		
TB30, TM15DI_DO, TM31, TM41	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00 [µs]	Max 16000.00 [µs]	Factory setting 4000.00 [µs]
Description:	Sets the sampling times for supplementary functions on this object.		
Index:	[0] = Basis sampl. time		
p0115[0...6]	Sampling times for internal control loops / t_sample int ctrl		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00 [µs]	Max 16000.00 [µs]	Factory setting [0] 125.00 [µs] [1] 125.00 [µs] [2] 125.00 [µs] [3] 4000.00 [µs] [4] 1000.00 [µs] [5] 4000.00 [µs] [6] 4000.00 [µs]
Description:	Sets the sampling times for the control loops. The default setting is made using p0112 and can only be individually changed for p0112 = 0 (expert).		
Index:	[0] = Current controller [1] = Speed controller [2] = Flux controller [3] = Setpoint channel [4] = Pos controller [5] = Positioning [6] = Technology controller		
Dependency:	The sampling times can only be separately set if p0112 is 0 (expert). If a sampling time is modified in the expert mode, then all of the sampling times with higher indices are automatically changed in the same ratio as the sampling time itself was changed. Slower time slices are only taken if the calculated sampling time is also permitted. Upper limit is 8 ms. Higher-level controls must be calculated in integral ratios to lower-level controls (e.g. p0115[1] = N * p0115[0]; where N is a whole number). Refer to: r0110, r0111, p0112		

Note: For function modules that can be activated (e.g. technology controller), the parameters values are pre-assigned.
 For the Active Line Module (ALM), the currents and DC link voltage controllers operate with the same sampling time.
 For the Basic Line Module (BLM), the DC link voltage measurement operates in the current controller sampling time.
 For a power unit type PM340 (refer to r0203), only current controller sampling times of 62.5 µs, 125 µs, 250µs and 500µs can be set. The minimum current controller clock cycle for vector drives and the maximum current controller clock cycle for servodrives is 250 µs.

r0116[0...1]		Drive object clock cycle recommended / DO_clock recom		
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VEC- TOR	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min - [µs]	Max - [µs]	Factory setting - [µs]	
Description:	Displays the recommended sampling time for the drive objects. r0116[0] = recommended sampling time: Recommended value which would then make the complete system operational. r0116[1] = recommended sampling time: Recommended value, which after changing other clock cycles on the DRIVE-CLiQ line, would result in an operational system.			
Index:	[0] = Change, only for the actual drive object [1] = Changing all objects on the DRIVE-CLiQ line			
Dependency:	Refer to: p0115			
p0117		Current controller computation deadtime mode / I_ctrl t_dead mode		
CU_S	Can be changed: U, T Data type: Integer16	Dynamic index: -	Access level: 4	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min 0	Max 6	Factory setting 6	
Description:	Sets the mode for the computation deadtime of the current controller. 0: Offset (shifted) clocking, minimum computation deadtime of each drive, automatic setting 1: Clocking at the same time, the deadtime aligns itself to the deadtime of the latest drive, automatic setting 2: Manual setting of the computation deadtime, early transfer 3: Manual setting of the computation deadtime, late transfer 4-6: As for 0-2, however, no early transfers are set for vectors			
Dependency:	Refer to: p0118 Refer to: A02100			
Note:	Re p0117 = 0: The times when the setpoints become effective for the individual controls is automatically and individually determined. Another computation deadtime is set for each control (closed-loop) (p0118). Current is impressed for the individual controls without any offset with respect to time (improved EMC compatibility). Re p0117 = 1: The latest closed-loop control determines when the setpoints for each of the individual controls become active. The same computation deadtime is set for each control (p0118). Current is impressed (flows) for the individual controls without any offset with respect to time. Re p0117 = 2: The computation deadtime is manually set. The user must optimize the value in p0118. Re p0117 = 3: Only for internal Siemens use. Re p0117 = 4 - 6: Behavior as for p0117 = 0 - 2, however for vectors, the earliest times are not determined. The modified computation deadtime mode is not effective until the drive unit is powered-up again.			

p0118	Current controller computation deadline / I_ctrl t_dead		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 4
	Data type: Floating Point		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 2000.00 [µs]	Factory setting 0.00 [µs]
Description:	This parameter is preset as a function of the current controller sampling time (p0115[0]) and normally does not have to be changed.		
Dependency:	Refer to: p0117 Refer to: A02100		
Note:	For p0118 <= 0.005 µs, the current controller output is delayed by a complete current controller clock cycle (p0115[0]). After p0118 has been changed, we recommend that the current controller is adapted (p1715).		
p0120	Number of Power unit Data Sets (PDS) / PDS count		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: C1(3)	Dynamic index: -	Access level: 2
	Data type: Unsigned8		Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 1	Max 8	Factory setting 1
Description:	Sets the number of Power unit Data Sets (PDS). The value corresponds to the number of power units connected together for a parallel circuit configuration.		
Dependency:	Refer to: p0107, r0107		
Note:	This parameter is only significant for drive objects A_INF, FEED and VECTOR with a parallel circuit configuration.		
p0121[0...n]	Power unit component number / LT comp_no		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C1(4)	Dynamic index: PDS, p0120	Access level: 4
	Data type: Unsigned8		Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	The power unit data set is assigned to a power unit using this parameter. This unique component number is assigned when parameterizing the topology. Only component numbers can be entered into this parameter that correspond to a power unit.		
Dependency:	Refer to: p0107, r0107		
Note:	For parallel circuit configurations, the parameter index is assigned to a power unit.		
p0124[0...15]	Detection of main components using LED / Detection LED		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Unsigned8		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Detects the main components of the drive object selected via the index.		

p0124[0...n]	Power unit detection via LED / LT detection LED		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: U, T	Dynamic index: PDS, p0120	Access level: 2
	Data type: Unsigned8		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Detects the power unit assigned to this drive and data set.		
Note:	While p0124 = 1, the READY LED flashes green/orange or red/orange with 2 Hz at the appropriate power unit. For parallel circuit configurations, the parameter index is assigned to a power unit.		
p0125[0...n]	Activate/de-activate power unit components / LT_comp act/de-act		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C1(4), T	Dynamic index: PDS, p0120	Access level: 2
	Data type: Integer16		Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Setting to activate/de-activate a power unit component.		
Values:	0: De-activate component 1: Activate component		
Dependency:	Refer to: r0126		
Note:	The activation of a component can be rejected if the component was inserted for the first time. In this case, it is only possible to activate the component when the pulses for all of the drive objects are inhibited.		
r0126[0...n]	Power unit components active/inactive / LT comp act/inact		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: PDS, p0120	Access level: 2
	Data type: Integer16		Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Displays the "active/inactive" state of a power unit component.		
Values:	0: Component inactive 1: Component active		
Dependency:	Refer to: p0105, p0125, p0897		
r0127[0...n]	Power unit version EPROM data / LT EPROM version		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the version of the EPROM data of the power unit.		
Dependency:	Refer to: r0147, r0157		
Note:	For parallel circuit configurations, the parameter index is assigned to a power unit.		

r0128[0...n]	Power unit firmware version / LT FW_version		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the power unit firmware version.		
Dependency:	Refer to: r0018, r0148, r0158, r0197, r0198		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00. For parallel circuit configurations, the parameter index is assigned to a power unit.		
p0130	Number of Motor Data Sets (MDS) / MDS count		
SERVO, VECTOR	Can be changed: C1(3)	Dynamic index: -	Access level: 2
	Data type: Unsigned8		Function diagram: 8575
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 1	Max 16	Factory setting 1
Description:	Sets the number of Motor Data Sets (MDS).		
p0131[0...n]	Motor component number / Mot comp_no		
SERVO, VECTOR	Can be changed: C1(4)	Dynamic index: MDS, p0130	Access level: 4
	Data type: Unsigned8		Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	The motor data set is assigned to a motor using this parameter. This unique component number is assigned when parameterizing the topology. Only component numbers can be entered into this parameter that correspond to a motor.		
p0139[0...2]	Copy Motor Data Set MDS / Copy MDS		
SERVO, VECTOR	Can be changed: C2(15)	Dynamic index: -	Access level: 2
	Data type: Unsigned8		Function diagram: 8575
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 31	Factory setting [0] 0 [1] 0 [2] 0
Description:	Copying a Motor Data Set (MDS) into another.		
Index:	[0] = Source motor data set [1] = Target motor data set [2] = Start copying		
Note:	Procedure: 1. In Index 0, enter which motor data set should be copied. 2. In Index 1, enter the motor data set data that is to be copied into. 3. Start copying: Set index 2 from 0 to 1. p0139[2] is automatically set to 0 when copying is completed. When copying, p0131 is not taken into account.		

p0140	Number of Encoder Data Sets (EDS) / EDS count		
SERVO, VECTOR	Can be changed: C1(3)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 1	Max 16	Factory setting 1
Description:	Sets the number of Encoder Data Sets (EDS).		
Note:	When parameterizing the drive with "no encoder" there must be at least one encoder data set (p0140 >= 1).		
p0141[0...n]	Encoder interface (Sensor Module) component number / Enc_interf comp_no		
SERVO, VECTOR	Can be changed: C1(4)		Access level: 4
	Data type: Unsigned8	Dynamic index: EDS, p0140	Function diagram: 4704, 8570
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	This parameter is used to assign the encoder data set to an encoder evaluation (e.g. SMC). This unique component number is assigned when parameterizing the topology. Only component numbers can be entered into this parameter that correspond to an encoder evaluation.		
Note:	If the encoder evaluation and encoder are integrated (motor with DRIVE-CLiQ), then their component numbers are identical. For an SMC, different component numbers are assigned for the SMC (p0141) and the (actual) encoder (p0142).		
p0142[0...n]	Encoder component number / Encoder comp_no		
SERVO, VECTOR	Can be changed: C1(4)		Access level: 4
	Data type: Unsigned8	Dynamic index: EDS, p0140	Function diagram: 4704
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	This parameter is used to assign the encoder data set to an encoder. This assignment is made using the unique component number that was assigned when parameterizing the topology. Only component numbers can be entered into this parameter that correspond to an encoder.		
Note:	If the encoder evaluation and encoder are integrated (motor with DRIVE-CLiQ), then their component numbers are identical. For an SMC, different component numbers are assigned for the SMC (p0141) and the (actual) encoder (p0142).		
p0144[0...n]	Voltage sensing module detection via LED / VSM detection LED		
A_INF, S_INF	Can be changed: U, T		Access level: 3
	Data type: Unsigned8	Dynamic index: p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Detects the Voltage Sensing Module (VSM) module assigned to this infeed.		

p0144[0...n]	Sensor Module detection via LED / SM detection LED		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Unsigned8	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Detects the Sensor Module assigned to this drive and data set.		
Note:	While p0144 = 1, the READY LED flashes green/orange or red/orange with 2 Hz at the appropriate Sensor Module.		
p0145[0...n]	Voltage Sensing Module, activate/de-activate / VSM act/deact		
A_INF, S_INF	Can be changed: C1(4), T		Access level: 2
	Data type: Integer16	Dynamic index: p0140	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Setting to activate/de-activate a Voltage Sensing Module (VSM).		
Values:	0: De-activate component 1: Activate component		
Dependency:	Refer to: r0146		
Note:	For chassis infeeds, it is not possible to activate/de-activate the Voltage Sensing Module (VSM) via p0145. The VSM can only be activated/de-activated in the group with the appropriate infeed via p0125[0...n]. The activation of a component can be rejected if the component was inserted for the first time. In this case, it is only possible to activate the component when the pulses for all of the drive objects are inhibited.		
p0145[0...n]	Activate/de-activate encoder interface / Enc_intf act/deact		
SERVO, VECTOR	Can be changed: C1(4), U, T		Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Setting to activate/de-activate an encoder interface (Sensor Module).		
Values:	0: De-activate component 1: Activate component		
Dependency:	Refer to: r0146		
Note:	The de-activation of an encoder interface corresponds to the "parking encoder" function and has the same effect. The activation of a component can be rejected if the component was inserted for the first time. In this case, it is only possible to activate the component when the pulses for all of the drive objects are inhibited.		
r0146[0...n]	Voltage Sensing Module, active/inactive / VSM act/inact		
A_INF, S_INF	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: p0140	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Displays the "active" or "inactive" state of a Voltage Sensing Module (VSM).		
Values:	0: Component inactive 1: Component active		
Dependency:	Refer to: p0105, p0145		

r0146[0...n]	Encoder interface active/inactive / Enc_intf act/inact		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Displays the "active" or "inactive" state of an encoder interface (Sensor Module).		
Values:	0: Component inactive 1: Component active		
Dependency:	Refer to: p0105, p0145, p0480, p0897		
r0147[0...n]	Voltage sensing module, EPROM data version / VSM EEPROM version		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the version of the EPROM data of the Voltage Sensing Module (VSM).		
r0147[0...n]	Sensor Module EPROM data version / SM EEPROM version		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the version of the EPROM data of the Sensor Module.		
Dependency:	Refer to: r0127, r0157		
r0148[0...n]	Voltage sensing module, firmware version / VSM FW_version		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the firmware version of the Voltage Sensing Module (VSM).		
Dependency:	Refer to: r0018, r0128, r0158, r0197, r0198		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		
r0148[0...n]	Sensor Module firmware version / SM FW_version		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the Sensor Module firmware version.		
Dependency:	Refer to: r0018, r0128, r0158, r0197, r0198		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		

p0150	Number of VSM data sets / VSM count		
VECTOR	Can be changed: C1(3)		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Sets the number of VSM data sets		
p0151[0...n]	Voltage Sensing Module component number / VSM comp_no		
VECTOR	Can be changed: C1(4)		Access level: 4
	Data type: Unsigned8	Dynamic index: p0150	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	The VSM data set is assigned to a VSM evaluation using this parameter.		
p0151[0...1]	DRIVE-CLiQ Hub component number / Hub comp_no		
DMC20	Can be changed: C1(4)		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	Using this parameter, the data set is assigned to a DRIVE-CLiQ Hub Module Cabinet (DMC). This unique component number is assigned when parameterizing the topology. Only component numbers of components that operate as hub can be entered into this parameter. This parameter has two indices, because there are two DRIVE-CLiQ nodes in the DMC20. [0] = 1. DRIVE-CLiQ node [1] = 2. DRIVE-CLiQ node		
p0151	Terminal Module component number / TM comp_no		
TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: C1(4)		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: 9550, 9552
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	Sets the component number for the Terminal Module. This unique component number is assigned when parameterizing the topology. Only component numbers can be entered into this parameter that correspond to a Terminal Module.		
p0154	DRIVE-CLiQ Hub detection via LED / Hub detection LED		
DMC20	Can be changed: U, T		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Detecting any assigned DRIVE-CLiQ Hub Module Cabinet (DMC).		

p0154	Terminal Module detection via LED / TM detection LED		
TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Detects the Terminal Module assigned to this drive and data set.		
Note:	While p0154 = 1, the READY LED flashes green/orange or red/orange with 2 Hz at the appropriate Terminal Module.		
p0155[0...n]	Voltage Sensing Module, activate/de-activate / VSM act/deact		
VECTOR	Can be changed: C1(4), T	Dynamic index: p0150	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Data sets		Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Setting to activate/de-activate a Voltage Sensing Module (VSM).		
Values:	0: De-activate component 1: Activate component		
Dependency:	Refer to: r0156		
r0156[0...n]	Voltage Sensing Module, active/inactive / VSM act/inact		
VECTOR	Can be changed: -	Dynamic index: p0150	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Data sets		Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Displays the "active" or "inactive" state of a Voltage Sensing Module (VSM).		
Values:	0: Component inactive 1: Component active		
Dependency:	Refer to: p0155		
r0157[0...n]	Voltage sensing module, EPROM data version / VSM EPROM version		
VECTOR	Can be changed: -	Dynamic index: p0150	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the version of the EPROM data of the Voltage Sensing Module (VSM).		
r0157	DRIVE-CLiQ Hub EPROM data version / Hub EPROM version		
DMC20	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the version of the EPROM data of the DRIVE-CLiQ Hub Module Cabinet (DMC).		

r0157	Terminal Module EPROM data version / TM EPROM version		
TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the version of the EPROM data of the Terminal Module.		
Dependency:	Refer to: r0127, r0147		
r0158[0...n]	Voltage sensing module, firmware version / VSM FW_version		
VECTOR	Can be changed: -	Dynamic index: p0150	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the firmware version of the Voltage Sensing Module (VSM).		
Dependency:	Refer to: r0018, r0128, r0197, r0198		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		
r0158	DRIVE-CLiQ Hub, firmware version / Hub FW_version		
DMC20	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the firmware version of the DRIVE-CLiQ Hub Module Cabinet (DMC).		
r0158	Terminal Module firmware version / TM FW_version		
TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the Terminal Module firmware version.		
Dependency:	Refer to: r0018, r0128, r0148, r0197, r0198		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		
p0161	Option board, component number / OptBoard comp_no		
TB30	Can be changed: C1(4)	Dynamic index: -	Access level: 4
	Data type: Unsigned8	Units group: -	Function diagram: 9100
	P-Group: Data sets		Unit selection: -
	Min	Max	Factory setting
	0	199	0
Description:	Sets the component number for the option board (e.g. terminal board 30). This unique component number is assigned when parameterizing the topology. Only component numbers can be entered into this parameter that correspond to an option board.		

p0162	CU link slave component number / CX32 comp_no		
CU_LINK	Can be changed: C1(4)		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
p0170	Number of Command Data Sets (CDS) / CDS count		
A_INF, B_INF, S_INF, TM41	Can be changed: C1(3)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 1	Max 1	Factory setting 1
Description:	Sets the number of Command Data Sets (CDS).		
Note:	It is possible to toggle between command parameters (BICO parameters) using this data set changeover.		
p0170	Number of Command Data Sets (CDS) / CDS count		
SERVO	Can be changed: C1(3)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Sets the number of Command Data Sets (CDS).		
Note:	It is possible to toggle between command parameters (BICO parameters) using this data set changeover.		
p0170	Number of Command Data Sets (CDS) / CDS count		
VECTOR	Can be changed: C1(3)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 2	Max 4	Factory setting 2
Description:	Sets the number of Command Data Sets (CDS).		
Note:	It is possible to toggle between command parameters (BICO parameters) using this data set changeover.		
p0180	Number of Drive Data Sets (DDS) / DDS count		
SERVO, TM41, VEC- TOR	Can be changed: C1(3)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: 8565
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 1	Max 32	Factory setting 1
Description:	Sets the number of Drive Data Sets (DDS).		

p0186[0...n]	Motor Data Sets (MDS) number / MDS number		
SERVO, VECTOR	Can be changed: C1(4)		Access level: 3
	Data type: Unsigned8	Dynamic index: DDS, p0180	Function diagram: 8575
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 15	Factory setting 0
Description:	Using the parameter, each Drive Data Set (= index) is assigned the associated Motor Data Set (MDS). The parameter value therefore corresponds to the number of the assigned motor data set.		

p0187[0...n]	Encoder 1 encoder data set number / Enc 1 EDS number		
SERVO, VECTOR	Can be changed: C1(4)		Access level: 3
	Data type: Unsigned8	Dynamic index: DDS, p0180	Function diagram: 1580, 8570
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 99
Description:	Using the parameter, each Drive Data Set (= index) is assigned the associated Encoder Data Set (EDS) for encoder 1. The parameter value therefore corresponds to the number of the assigned encoder data set. Example: Encoder data set 0 should be assigned to encoder 1 in drive data set 2. -> p0187[2] = 0		
Note:	A value of 99 means that no encoder has been assigned to this drive data set (not configured).		

p0188[0...n]	Encoder 2 encoder data set number / Enc 2 EDS number		
SERVO, VECTOR	Can be changed: C1(4)		Access level: 3
	Data type: Unsigned8	Dynamic index: DDS, p0180	Function diagram: 1580, 8570
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 99
Description:	Using the parameter, each Drive Data Set (= index) is assigned the associated Encoder Data Set (EDS) for encoder 2. The parameter value therefore corresponds to the number of the assigned encoder data set.		
Note:	A value of 99 means that no encoder has been assigned to this drive data set (not configured).		


p0189[0...n]	Encoder 3 encoder data set number / Enc 3 EDS number		
SERVO, VECTOR	Can be changed: C1(4)		Access level: 3
	Data type: Unsigned8	Dynamic index: DDS, p0180	Function diagram: 1580, 8570
	P-Group: Data sets	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 99
Description:	Using the parameter, each Drive Data Set (= index) is assigned the associated Encoder Data Set (EDS) for encoder 3. The parameter value therefore corresponds to the number of the assigned encoder data set.		
Note:	A value of 99 means that no encoder has been assigned to this drive data set (not configured).		

r0192	Power unit firmware properties / LT FW property			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: Converter	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0000 bin	
Description:	Displays the properties supported by the power unit firmware.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Edge modulation possible	Yes	No
	01	Free telegram can be selected	Yes	No
	02	Smart mode possible for Active Line Module	Yes	No
	03	Safety Integrated possible for VECTOR	Yes	No
	06	Water cooling	Yes	No
	07	SERVO pulse frequency changeover, DDS-dependent	Yes	No
	08	Simulation operation possible	Yes	No
	09	Internal armature short-circuit possible	Yes	No
Notice:	This information represents the characteristics/features of the power unit firmware. It does not provide information/data about the characteristics/features of the hardware (e.g. bit 06 = 1 means that although the firmware supports "water cooling", a power unit with water cooling does not have to be used).			
r0194[0...n]	VSM properties / VSM properties			
A_INF, S_INF, VECTOR	Can be changed: -		Access level: 4	
	Data type: Unsigned32	Dynamic index: p0140	Function diagram: -	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0000 bin	
Description:	Displays the properties supported by the Voltage Sensing Module (VSM).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Reserved	Yes	No
				FP
				-
r0197	Loader 1 version / Loader 1 version			
CU_S	Can be changed: -		Access level: 1	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Displays the version of loader 1 (first level loader).			
Dependency:	Refer to: r0018, r0128, r0148, r0158, r0198			
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.			
r0198	Loader 2 version / Loader 2 version			
CU_S	Can be changed: -		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Displays the version of loader 2 (second level loader).			
Dependency:	Refer to: r0018, r0128, r0148, r0158, r0197			
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.			

p0199[0...24]	Drive object name / DO name		
All objects	Can be changed: C1		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Freely assignable name for a drive object. In the commissioning software, this name cannot be entered using the expert list, but is specified in the configuration assistant. The object name can be subsequently modified in the Project Navigator using standard Windows resources.		
r0200[0...n]	Power unit, actual code number / LT code no. actual		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the unique code number of the power unit.		
Note:	r0200 = 0: No power unit found For parallel circuit configurations, the parameter index is assigned to a power unit.		
p0201[0...n]	Power unit code number / LT code number		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C2(2)		Access level: 3
	Data type: Unsigned16	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the actual code number from r0200 to acknowledge the power unit being used. When commissioned for the first time, the code number is automatically transferred from r0200 into p0201.		
Note:	The parameter is used to identify when the drive is being commissioned for the first time. The power unit commissioning can only be exited (p0201 = r0200), if the actual and acknowledged code numbers are identical (p0010 = 2). For parallel circuit configurations, the parameter index is assigned to a power unit.		
r0203[0...15]	Card name / Card name		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	This parameter indicates the card name.		

r0203[0...n]		Actual power unit type / LT actual type			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3		
	Data type: Integer16	Units group: -	Function diagram: -		
	P-Group: Converter	Unit selection: -			
	Min 2	Max 300	Factory setting 100		
Description:	Displays the type of power unit found.				
Values:	2: MICROMASTER 440 3: MICROMASTER 411 4: MICROMASTER 410 5: MICROMASTER 436 6: MICROMASTER 440 PX 7: MICROMASTER 430 100: SINAMICS S 120: PM340 (SINAMICS S120) 150: SINAMICS G 200: SINAMICS GM 250: SINAMICS SM 300: SINAMICS GL				
Note:	For parallel circuit configurations, the parameter index is assigned to a power unit.				
r0204[0...n]		Power unit hardware properties / LT HW property			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3		
	Data type: Unsigned32	Units group: -	Function diagram: -		
	P-Group: Converter	Unit selection: -			
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the properties supported by the power unit hardware.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DC/AC device	DC/AC device	AC/AC device	-
	01	RFI filter available	Yes	No	-
	02	Active Line Module available	Yes	No	-
	03	Smart Line Module available	Yes	No	-
	04	Basic Line Module available with thyristor bridge	Yes	No	-
	05	Basic Line Module available with diode bridge	Yes	No	-
	06	Water cooling	Yes	No	-
	12	Safe Brake Control (SBC) supported	No	Yes	-
Note:	For parallel circuit configurations, the parameter index is assigned to a power unit.				

p0205	Power unit application / LT application		
VECTOR	Can be changed: C2(1)		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 7	Factory setting 6
Description:	Overloading the load duty cycles applies under the prerequisite that before and after the overload, the drive converter is operated with its base load current - in this case, a load duty cycle of 300 s is used as basis. For booksize drive units, the following applies: Only the setting p0205 = 0 can be selected. In this particular case, the base load current has a load duty cycle of 150 % for 60 s and 176 % for 30 s. For chassis drive units, the following applies: The base load current for a slight overload condition is based on a load duty cycle 110 % for 60 s and 150 % for 10 s. The base load current for a high overload condition is based on a load duty cycle 150 % for 60 s and 160 % for 10 s.		
Values:	0: Load duty cycle with high overload for vector drives 1: Load duty cycle with low overload for vector drives 6: S1 duty cycle for servo drives (feed drive) 7: S6 duty cycle for servo drives (spindle drive)		
Note:	When the parameter is changed, all of the motor parameters and the control mode are pre-assigned according to the selected application. The parameter has no influence when calculating the thermal overload. p0205 can only be changed to the settings that are saved in the power unit EEPROM. Its value is not reset when factory values are restored (see p0010 = 30, p0970).		
r0206[0...4]	Rated power unit power / LT P_{rated}		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: 14_6	Unit selection: p0100
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the rated power unit power for various load duty cycles.		
Index:	[0] = Rating plate [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 load duty cycle [4] = S6 load duty cycle		
Dependency:	The value is displayed in [kW] or [hp]. Refer to: p0100, p0205		
r0207[0...4]	Rated power unit current / LT PI_{rated}		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8014
	P-Group: Converter	Units group: -	Unit selection: -
	Min - [A _{eff}]	Max - [A _{eff}]	Factory setting - [A _{eff}]
Description:	Displays the rated power unit power for various load duty cycles.		
Index:	[0] = Rating plate [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 load duty cycle [4] = S6 load duty cycle		
Dependency:	Refer to: p0205		

r0208	Rated power unit line supply voltage / LT U_{rated}		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the rated line supply voltage of the power unit. r0208 = 400: 380 - 480 V +/-10 % r0208 = 500: 500 - 600 V +/-10 % r0208 = 690: 660 - 690 V +/-10 % For the Basic Line Module (BLM) the following applies: r0208 = 690 : 500 - 690 V +/-10 %		
r0209[0...4]	Power unit, maximum current / LT I_{max}		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 8750, 8850, 8950
	P-Group: Converter	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the maximum output current of the power unit.		
Index:	[0] = Catalog [1] = Load duty cycle with high overload [2] = Load duty cycle with low overload [3] = S1 load duty cycle [4] = S6 load duty cycle		
Dependency:	Refer to: p0205		
p0210	Drive unit line supply voltage / Supply voltage		
A_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 1
	Data type: Floating Point		Function diagram: 8960
	P-Group: Converter	Units group: -	Unit selection: -
	Min 100 [Veff]	Max 1000 [Veff]	Factory setting 400 [Veff]
Description:	Sets the drive unit supply voltage. The value corresponds to the rms value of the phase-to-phase rated line supply voltage.		
Dependency:	Refer to: p3400		
Warning:	If the infeed is continually in the controlled mode with high DC link voltages (p3510 > 660 V), depending on the particular application, this can damage the connected motors that have not been specified for these high voltages. Before an active infeed with a line supply voltage p0210 > 415 V goes into pulsed operation it must be ensured that all of the components connected to the DC link can be permanently operated with DC link voltages exceeding 660 V. Controlled operation of booksize power units for p0210 > 415 V is possible if the maximum steady-state DC link voltage (p0280) is increased as follows: p0280 ≥ 1.5 * p0210 and p0280 > 660 V. In this case, the setpoint of the DC link voltage p3510 is not automatically adapted. We recommend p3510 = 1.5 * p0210. Closed-loop voltage controlled operation is active with p3400.0 = 0 and p3400.3 = 1.		
			
Notice:	For p0210 > 415 V for booksize power units with a supply voltage of 3-ph. 380 ... 480 V, the smart mode is automatically activated (p3400.0 = 1). In this case, the smart mode cannot be de-activated. This is because in the voltage controlled mode, the maximum steady-state DC link voltage (p0280) would be exceeded.		

Note: When pre-assigning the setpoint for the DC link voltage (p3510), the following is generally valid:
 $p3510 = 1.5 * p0210$.
 For booksize power units with supply voltage of 3-ph. 380 ... 480 V AC, the following applies:
 380 V \leq p0210 \leq 400 V --> Pre-assignment, setpoint for the DC link voltage: p3510 = 600 V
 401 V \leq p0210 \leq 415 V --> Pre-assignment, setpoint for the DC link voltage: p3510 = 625 V
 416 V \leq p0210 \leq 480 V --> Smart Mode with non-regulated DC link voltage: p3510 = 1.35 * p0210
 The voltage range for the supply voltage depends on the type and the voltage class of the power unit.
 Active Line Module, 400 V unit: 380 V \leq p0210 \leq 480 V
 Active Line Module, 690 V unit: 660 V \leq p0210 \leq 690 V
 Smart Line Module, 400 V unit: 380 V \leq p0210 \leq 480 V
 Smart Line Module, 690 V unit: 500 V \leq p0210 \leq 690 V

p0210 Drive unit line supply voltage / Supply voltage

SERVO, VECTOR	Can be changed: C2(2), T	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Converter		Unit selection: -
	Min 1 [V]	Max 63000 [V]	Factory setting 600 [V]

Description: Sets the drive unit supply voltage.

AC/AC units: The rms value of the phase-to-phase line supply voltage should be entered.
 DC/AC units: The rated DC voltage of the connection busbar should be entered.

Dependency: For VECTOR (p0107) the following applies:

Set p1254 to 0 (automatic detection of the Vdc switch-in levels).

The switch-in thresholds of the Vdc_max controller are then directly determined using p0210.

Caution: If the line supply voltage is higher than the entered value, the Vdc controller may be automatically de-activated in some cases to prevent the motor from accelerating. In this case, an appropriate alarm is output.

Note: For VECTOR (p0107) the following applies:

If the line supply voltage is higher than the parameterized value, then the DC link voltage controller could be automatically de-activated in order to prevent the drive accelerating.

Setting ranges for p0210 as a function of the rated power unit voltage:

U_{rated} = 400 V:

- p0210 = 380 ... 480 V (AC/AC), 510 ... 650 V (DC/AC)

U_{rated} = 500 V:

- p0210 = 500 ... 600 V (AC/AC), 675 ... 810 V (DC/AC)

U_{rated} = 690 V:

- p0210 = 660 ... 690 V (AC/AC), 890 ... 1035 V (DC/AC)

The pre-charging switch-in threshold for the DC link voltage (Vdc) is calculated from p0210:

$V_{dc_pre} = p0210 * 0.82 * 1.35$ (AC/AC)

$V_{dc_pre} = p0210 * 0.82$ (DC/AC)

The undervoltage thresholds for the DC link voltage (Vdc) are calculated from p0210 as a function of the rated power unit voltage:

U_{rated} = 400 V:

- U_{min} = p0210 * 0.78 (AC/AC), p0210 * 0.60 (DC/AC)

U_{rated} = 500 V:

- U_{min} = p0210 * 0.76 (AC/AC)

U_{rated} = 690 V:

- U_{min} = p0210 * 0.74 (AC/AC), p0210 * 0.57 (DC/AC)

p0210	Drive unit line supply voltage / Supply voltage		
B_INF	Can be changed: C2(1)		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 100 [Veff]	Max 1000 [Veff]	Factory setting 400 [Veff]
Description:	Sets the drive unit supply voltage. The value corresponds to the rms value of the phase-to-phase rated line supply voltage.		
Note:	The supply voltage range depends on the voltage class of the power unit. 400 V unit: 380 V <= p0210 <= 480 V 690 V unit: 500 V <= p0210 <= 690 V		
p0211	Rated line freq / Rated line freq		
A_INF, S_INF	Can be changed: C2(1)		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 10 [Hz]	Max 100 [Hz]	Factory setting 50 [Hz]
Description:	Sets the rated line frequency for the infeed.		
p0220	Infeed line filter type / INF line filit type		
A_INF	Can be changed: C2(1)		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 33	Factory setting 0
Description:	Sets the line filter type for the Active Line Module (ALM). Using the line filter type, the filter capacitance (p0221) and filter resistance (p0222) are pre-assigned.		
Values:	<ul style="list-style-type: none"> 0: No line filter 1: Wideband Line Filter Booksize 400 V 16 kW (6SL3000-0BE21-6AA0) 2: Wideband Line Filter Booksize 400 V 36 kW (6SL3000-0BE23-6AA0) 3: Wideband Line Filter Booksize 400 V 55 kW (6SL3000-0BE25-5AA0) 4: Wideband Line Filter Booksize 400 V 80 kW (6SL3000-0BE28-0AA0) 5: Wideband Line Filter Booksize 400 V 120 kW (6SL3000-0BE31-2AA0) 10: Active Interface Module F 400 V 132 kW 160 kW (6SL3300-7TE32-6Ax) 11: Active Interface Module G 400 V 235 kW (6SL3300-7TE33-8Ax0) 12: Active Interface Module G 400 V 300 kW (6SL3300-7TE35-0Ax0) 13: Active Interface Module H 400 V 380 kW 500 kW (6SL3300-7TE38-4Ax) 14: Active Interface Module J 400 V 630 kW 900 kW (6SL3300-7TE41-4Ax) 15: Active Interface Module F 690 V 150 kW (6SL3300-7TH31-4Ax0) 16: Active Interface Module G 690 V 330 kW (6SL3300-7TH33-1Ax0) 17: Active Interface Module H 690 V 560 kW (6SL3300-7TH35-8Ax0) 18: Active Interface Module J 690 V 800 kW (6SL3300-7TH37-4Ax0) 19: Active Interface Module J 690 V 1100 kW 1400 kW (6SL3300-7TH41-3) 31: Basic Line Filter Booksize 400 V 16 kW (6SL3000-0BE21-6DA0) 32: Basic Line Filter Booksize 400 V 36 kW (6SL3000-0BE23-6DA0) 33: Basic Line Filter Booksize 400 V 55 kW (6SL3000-0BE25-5DA0) 		
Notice:	The parameters p0223 and p0224 for the reactor are pre-assigned using the rated drive converter power.		
Note:	The filter capacitance (p0221) and filter resistance (p0222) are required in the closed-loop voltage controlled mode to automatically compensate the filter reactive current.		

p0221	Infeed filter capacitance / INF C_filter		
A_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8950
	P-Group: Converter		Unit selection: -
	Min 0.00 [μ F]	Max 100000.00 [μ F]	Factory setting 0.00 [μ F]
Description:	Sets the filter capacitance of the line filter (connected in a delta configuration).		
Note:	When a Siemens line filter is used (p0220) this parameter is automatically preset with the correct value. For a parallel circuit, the value corresponds to the capacitance of a power unit.		
p0222	Infeed filter resistance / INF R_filter		
A_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8950
	P-Group: Converter		Unit selection: -
	Min 0.00000 [Ohm]	Max 100.00000 [Ohm]	Factory setting 0.00000 [Ohm]
Description:	Sets the filter resistance in series with the filter capacitance.		
Note:	When a Siemens line filter is used (p0220) this parameter is automatically preset with the correct value. For a parallel circuit, the value corresponds to the resistance of a power unit.		
p0223	Infeed inductance between filter and power unit / INF L filter/LT		
A_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8850, 8950
	P-Group: Converter		Unit selection: -
	Min 0.001 [mH]	Max 1000.000 [mH]	Factory setting 2.100 [mH]
Description:	Sets the inductance between the filter and power unit.		
Note:	The parameter is automatically pre-assigned depending on the power unit being used and matches the specified Siemens commutating reactors. For a parallel circuit, the value corresponds to the inductance of a power unit.		
p0224	Infeed resistance between filter and power unit / INF R filter/LT		
A_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8850, 8950
	P-Group: Converter		Unit selection: -
	Min 0.00000 [Ohm]	Max 100.00000 [Ohm]	Factory setting 0.00100 [Ohm]
Description:	Sets the resistance between the filter and power unit		
Note:	The parameter is automatically pre-assigned depending on the power unit being used and matches the specified Siemens commutating reactors. For a parallel circuit, the value corresponds to the resistance of a power unit.		

p0225	Infeed inductance between line supply and filter / INF L line/filter		
A_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 8850, 8950
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0.001 [mH]	Max 1000.000 [mH]	Factory setting 0.001 [mH]
Description:	Sets the inductance between line supply and filter.		
Note:	The value must be, for example, appropriately increased if an additional inductance (reactor or transformer is installed in front of the filter).		
p0226	Infeed resistance between line supply and filter / INF R line/filter		
A_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 8850, 8950
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0.00 [Ohm]	Max 100.00 [Ohm]	Factory setting 0.00 [Ohm]
Description:	Sets the resistance between the line supply and filter.		
Note:	The value must be, for example, appropriately increased if an additional resistor is installed in front of the filter.		
p0227	Infeed, DC-link capacitance, power unit / INF C		
A_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 8850, 8950
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0.001 [mF]	Max 1000.000 [mF]	Factory setting 0.700 [mF]
Description:	Sets the total DC link capacitance.		
Note:	The total DC link capacitance of a DC link group comprises the sum of the sub-capacitances of all motor/infeed modules and the additional DC link capacitors.		
p0230	Drive filter type, motor side / Drv filt type		
VECTOR	Can be changed: C2(1, 2)	Dynamic index: -	Access level: 1
	Data type: Integer16		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 4	Factory setting 0
Description:	Sets the type of the filter at the motor side.		
Values:	<ul style="list-style-type: none"> 0: No filter 1: Motor reactor 2: du/dt filter 3: Sinusoidal filter, Siemens 4: Sinusoidal filter, third-party 		

Dependency: The following parameters are influenced using p0230:
 p0230 = 1:
 -> p0233 (power unit, motor reactor) = filter inductance
 p0230 = 3:
 -> p0233 (power unit, motor reactor) = filter inductance
 -> p0234 (power unit sinusoidal filter capacitance) = filter capacitance
 -> p0290 (power unit overload response) = inhibit pulse frequency reduction
 -> p1082 (maximum speed) = Fmax filter / pole pair number
 -> p1800 (pulse frequency) >= nominal pulse frequency of the filter
 -> p1802 (modulator modes) = space vector modulation without overcontrol
 p0230 = 4:
 -> p0290 (power unit overload response) = inhibit pulse frequency reduction
 -> p1802 (modulator modes) = space vector modulation without overcontrol
 The user must set the following parameters according to the data sheet of the sinusoidal filter and also the user must check whether they are permitted.

-> p0233 (power unit, motor reactor) = filter inductance
 -> p0234 (power unit sinusoidal filter capacitance) = filter capacitance
 -> p1082 (maximum speed) = Fmax filter / pole pair number
 -> p1800 (pulse frequency) >= nominal pulse frequency of the filter
 Refer to: p0233, p0234, p0290, p1082, p1800, p1802
Note: if a filter type cannot be selected, then this filter type is not permitted for the Motor Module.
 p0230 = 2:
 Chassis-type power units with du/dt filter, depending on the rated pulse frequency, may only be operated with a maximum pulse frequency of p1800 = 2.5 kHz or 4 kHz. The output frequency is limited to 150 Hz.
 p0230 = 3:
 Sinusoidal filters with a rated pulse frequency of 1.25 or 2.5 kHz should only be operated with a current controller sampling rate p0115[0] = 400 µs, sinusoidal filters with a rated pulses frequency of 2 or 4 kHz with p0115[0] = 250 µs.
 The sinusoidal filter cannot be selected if the current controller sampling rate hasn't been appropriately set.

p0233	Power unit motor reactor / LT mot reactor		
VECTOR	Can be changed: C2(2), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0.000 [mH]	Max 1000.000 [mH]	Factory setting 0.000 [mH]
Description:	Enter the inductance of a filter connected at the power unit output.		
Dependency:	The parameter is automatically pre-assigned when selecting a filter via p0230. Refer to: p0230		

p0234	Power unit sinusoidal filter capacitance / LT sine filter C		
VECTOR	Can be changed: C2(2), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0.000 [µF]	Max 1000.000 [µF]	Factory setting 0.000 [µF]
Description:	Enters the capacitance of a sinusoidal filter connected at the power unit output.		
Dependency:	The parameter is automatically pre-assigned when selecting a filter via (p0230). Refer to: p0230		
Note:	The parameter value includes the sum of all of the capacitances of a phase connected in series (phase - ground).		

p0235	Number of reactors connected in series / Qty L in series		
VECTOR	Can be changed: C2(1, 2)	Dynamic index: -	Access level: 1
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: Converter		Unit selection: -
	Min 1	Max 3	Factory setting 1
Description:	Number of reactors connected at the power unit output.		
Dependency:	Refer to: p0230		
Caution:	If the number of motor reactors connected in series does not correspond to the parameter value, then this can result in an unfavorable control behavior.		
Note:	The parameter can only be changed for chassis drive units and for p0230 = 1.		
p0251[0...n]	Operating hours counter, power unit fan / LT fan t_oper		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: PDS, p0120	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Modulation		Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Displays the power unit fan operating hours. The number of hours operated can only be reset to 0 in this parameter (e.g. after a fan has been replaced).		
Dependency:	Refer to: p0252		
Note:	The value is in the unit [h] (hours).		
p0252	Maximum operating time, power unit fan / LT fan t_oper max		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: -	Access level: 4
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Modulation		Unit selection: -
	Min 0	Max 50000	Factory setting 40000
Description:	Sets the maximum operating time of the power unit fan. The pre-alarm (warning) is output 500 hours before this set value. The monitoring is de-activated with p0252 = 0.		
Dependency:	Refer to: p0251		
Note:	The value is in the unit [h] (hours). For chassis units, the maximum operating duration in the power unit parameter is set as default to 50000.		
p0260	Cooling system, starting time 1 / RKA start time 1		
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Converter		Unit selection: -
	Min 0.0 [s]	Max 60.0 [s]	Factory setting 5.0 [s]
Description:	Sets starting time 1 to monitor the cooling system after power on command. The following feedback signals are evaluated: - "RKA powered-up" - "RKA water flow OK"		
Dependency:	Refer to: F49152, F49153		
Note:	RKA: Cooling system		

p0261	Cooling system, starting time 2 / RKA start time 2			
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: U, T Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: -	
	P-Group: Converter	Units group: -	Unit selection: -	
	Min 0.0 [s]	Max 1200.0 [s]	Factory setting 180.0 [s]	
Description:	Sets starting time 2 to monitor the cooling system after power on command. The following feedback signals are evaluated: - "RKA conductivity, no fault" - "RKA conductivity, no alarm"			
Dependency:	Refer to: p0266 Refer to: F49151, A49171			
p0262	Cooling system, fault conductivity delay time / RKA cond t_del			
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: U, T Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: -	
	P-Group: Converter	Units group: -	Unit selection: -	
	Min 0.0 [s]	Max 30.0 [s]	Factory setting 0.0 [s]	
Description:	Sets the delay time for the fault "RKA: Conductive limit value exceeded". The fault is only output if the cause is present for a time longer than is set in this parameter.			
Dependency:	Refer to: F49151			
p0263	Cooling system fault water flow, delay time / RKA flow t_del			
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: U, T Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: -	
	P-Group: Converter	Units group: -	Unit selection: -	
	Min 0.0 [s]	Max 20.0 [s]	Factory setting 3.0 [s]	
Description:	Sets the delay time for the fault "RKA: Water flow too low". The fault is only output if the cause is present for a time longer than is set in this parameter.			
Dependency:	Refer to: F49153			
p0264	Cooling system, run-on time / RKA run-on time			
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: U, T Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: -	
	P-Group: Converter	Units group: -	Unit selection: -	
	Min 0.0 [s]	Max 180.0 [s]	Factory setting 30.0 [s]	
Description:	Sets the run-up time of the cooling system after a power-off command.			

r0265	BO: Cooling system, control word / RKA ctrl word				
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned8		Function diagram: -		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the control word for the cooling system.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Power-up cooling system	Power-up	Power-down	-
	01	Message, converter off	Off	On	-
	02	Acknowledge faults	Acknowledgment	No acknowledgment	-
	03	Leakage water detection OK	No leakage water	Leakage water	-

p0266[0...7]	BI: Cooling system, signal source feedback signals / RKA S_src fdbk			
A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)	Can be changed: U, T	Dynamic index: -	Access level: 3	
	Data type: Unsigned32		Function diagram: -	
	P-Group: Communications	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting [0] 1 [1] 1 [2] 1 [3] 1 [4] 1 [5] 1 [6] 1 [7] 1	
Description:	Sets the signal sources for the feedback signals from the cooling system.			
Index:	[0] = Cooling system power-up [1] = Cooling system ready to be powered-up [2] = Cooling system, no alarm present [3] = Cooling system, no fault present [4] = Cooling system, no leakage water [5] = Cooling system water flow OK [6] = Cooling system, conductivity < fault threshold [7] = Cooling system, conductivity < alarm threshold			

r0267 BO: Cooling system status word display / RKA ZSW display

A_INF (RKA), B_INF (RKA), SERVO (RKA), VECTOR (RKA)

Can be changed: -**Data type:** Unsigned16**Dynamic index:** -**Access level:** 3**Function diagram:** -**P-Group:** Commands**Units group:** -**Unit selection:** -**Min**

-

Max

-

Factory setting

0000 bin

Description:

Displays the status word of the cooling system.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	RKA powered-up	Yes	No	-
01	RKA ready to be powered-up	Yes	No	-
02	RKA no alarm present	Yes	No	-
03	RKA no fault present	Yes	No	-
04	RKA no leakage water	Yes	No	-
05	RKA water flow OK	Yes	No	-
06	RKA conductivity, no fault	Yes	No	9974
07	RKA conductivity, no alarm	Yes	No	9974

Dependency:

Refer to: p0266

p0280 DC link voltage maximum steady-state / Vdc_max stat

A_INF

Can be changed: C2(1), T**Data type:** Floating Point**Dynamic index:** -**Access level:** 3**Function diagram:** 8940, 8964**P-Group:** Converter**Units group:** -**Unit selection:** -**Min**

270 [V]

Max

1500 [V]

Factory setting

660 [V]

Description:

Sets the maximum steady-state DC link voltage. When the DC link voltage setpoint reaches the threshold, alarm A06800 is output.

The setpoint for the DC link voltage in p3510 is limited to the value in p0280.

The voltage can be increased (boosted) using the modulation depth reserve controller. The modulation depth reserve (p3480) can be too low if p0210 (drive unit supply voltage) was incorrectly parameterized, a line overvoltage condition is present or a high reactive current is required.

Dependency:

Refer to: p0210

Refer to: A06800

Warning:

Before increasing the voltage limit for pulsed operation of a controlled booksize infeed with line supply voltages p0210 > 415 V it should be checked whether the motors, connected to the DC link, are specified for the higher motor voltages.

The warning information associated with p0210 must be carefully observed.

Caution:

All motors connected to the DC link must be rated for the maximum DC-link voltage set in this parameter.

Notice:

For chassis power modules, for the extended line supply voltage range from 500 V to 690 V, the value in p0280 is automatically adapted if the line supply voltage in p0210 is changed. The individual parameter setting of p0280 is then lost and if necessary must be re-entered.

Note:

A brief, dynamic increase of the DC link voltage does not result in an alarm.

p0281	Line supply overvoltage, warning threshold / U_LineAlrmThrsh up		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8960
	P-Group: Converter	Units group: -	Unit selection: -
	Min 100 [%]	Max 200 [%]	Factory setting 110 [%]
Description:	Sets the alarm threshold for a line supply overvoltage condition. The setting is made as a percentage of the drive unit supply voltage (p0210).		
Dependency:	Refer to: p0211, p0221, p0222, p0223, p0224, p0225, p0226		
Note:	If synchronizing voltages are not detected, the line supply voltage is estimated using a model. It is therefore important to ensure that drive unit data is correctly specified.		
p0282	Line supply undervoltage, alarm threshold / U_LineAlrmThrshLow		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8960
	P-Group: Converter	Units group: -	Unit selection: -
	Min 10 [%]	Max 100 [%]	Factory setting 85 [%]
Description:	Sets the alarm threshold for a line undervoltage condition. The setting is made as a percentage of the drive unit supply voltage (p0210).		
Dependency:	Refer to: p0222, p0224, p0225, p0226, p3421, p3422 Refer to: A06105		
Note:	If synchronizing voltages are not detected, the line supply voltage is estimated using a model. It is therefore important to ensure that drive unit data is correctly specified.		
p0283	Line supply undervoltage, shutdown (trip) threshold / U_line trip_thresh		
A_INF, S_INF	Can be changed: C2(1), T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8960
	P-Group: Converter	Units group: -	Unit selection: -
	Min 10 [%]	Max 100 [%]	Factory setting 75 [%]
Description:	Sets the trip threshold for the line supply undervoltage. The setting is made as a percentage of the drive unit supply voltage (p0210).		
Dependency:	Refer to: p0282 Refer to: F06100		
p0284	Line supply frequency exceeded, alarm threshold / f_LineAlrmThrsh up		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8964
	P-Group: Converter	Units group: -	Unit selection: -
	Min 100.0 [%]	Max 300.0 [%]	Factory setting 110.0 [%]
Description:	Sets the alarm threshold for an excessively high line frequency.		
Dependency:	Set as a percentage of the rated line frequency. Refer to: p0211		

p0285	Line supply frequency fallen below, alarm threshold / f_LineAlrmThrshLow		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8964
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 100.0 [%]	Factory setting 90.0 [%]
Description:	Sets the alarm threshold for an excessively low line frequency.		
Dependency:	Set as a percentage of the rated line frequency. Refer to: p0211		
p0287[0...1]	Ground fault monitoring thresholds / Grnd flt thresh		
A_INF, SERVO, S_INF, VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 100.0 [%]	Factory setting [0] 6.0 [%] [1] 16.0 [%]
Description:	Sets the shutdown thresholds for the ground fault monitoring. The setting is made as a percentage of the maximum power unit current (r0209).		
Index:	[0] = Threshold for pulse inhibit [1] = Threshold for pulse enable		
Dependency:	Refer to: F30021		
Note:	De-activating the ground fault monitoring: - Sequence: --> p0287[1] = 0 --> p0287[0] = 0 - independent of the firmware version of the power unit. Sets the thresholds: - the prerequisite is at least firmware version 2.2 of the power unit.		
r0289	Maximum power unit output current / LT I_output max		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the actual, maximum output current of the power unit taking into account de-rating factors.		
p0290	Power unit overload response / LT overld response		
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 8014
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	Sets the response to a thermal overload condition of the power unit. The following quantities can result in a response to thermal overload: - heatsink temperature (r0037.0) - chip temperature (r0037.1) - power unit overload I2T (r0036) Possible measures to avoid thermal overload: - reduce the output current (closed-loop speed/velocity or torque/force control) or the output frequency (U/f control). - reduce the pulse frequency (only for closed-loop vector control). A reduction, if parameterized, is always realized after an appropriate alarm is output.		

Values:	0: Reduce output current or output frequency 1: No reduction, shutdown when overload threshold is reached 2: Reduce I _{output} or f _{output} and f _{pulse} (not using I _{2t}) 3: Reduce the pulse frequency (not using I _{2t})
Dependency:	If a sinusoidal filter is parameterized as output filter (p0230 = 3, 4), then only responses can be selected without pulse frequency reduction (p0290 = 0, 1). If a fault or alarm is present, then r2135.13 or r2135.15 is set. Refer to: r0036, r0037, p0108, r0108, p0230, r2135 Refer to: A05000, A05001, A07805
Caution:	If the thermal overload of the power unit is not sufficiently reduced by the actions taken, the drive is always shut down. This means that the power unit is always protected independent of the setting of this parameter.
Note:	The setting p0290 = 0, 2 is only practical if the load decreases with decreasing speed (e.g. for applications with variable torque such as for pumps and fans). Under overload conditions, the current and torque limit are reduced, and therefore the motor is braked and forbidden speed ranges (e.g. minimum speed p1080 and suppression [skip] speeds p1091 ... p1094) can be passed through. For p0290 = 2, 3, the I _{2t} overload detection of the power unit does not influence the responses.

p0294	Power unit alarm with I_{2t} overload / LT I_{2t} alarm thresh		
A_INF, SERVO, S_INF, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8014
	P-Group: Converter	Unit selection: -	
	Min 10.0 [%]	Max 100.0 [%]	Factory setting 95.0 [%]
Description:	Sets the alarm threshold for the I _{2t} power unit overload. Drive: If this threshold is exceeded, an overload alarm is generated and the system responds as parameterized in p0290. Infeed: When the threshold value is exceeded, only an overload alarm is output.		
Dependency:	Refer to: r0036, p0290 Refer to: A07805		
Note:	The I _{2t} fault threshold is 100 %. If this value is exceeded, fault F30005 is output.		

p0295	Fan run-on time / Fan run-on time		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Converter	Unit selection: -	
	Min 0 [s]	Max 600 [s]	Factory setting 0 [s]
Description:	Sets the fan run-on time after the power unit has been powered-down. If, after the selected fan run-on time, the heatsink temperature has not fallen below a permanently saved threshold value, then the run-on time is extended until this temperature threshold is actually reached.		

r0296	DC link voltage undervoltage threshold / V_{dc} U_{lower}_thresh		
A_INF, B_INF, S_INF	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Converter	Unit selection: -	
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	If the DC link voltage falls below the threshold specified here, the drive unit is tripped due to a DC link undervoltage condition.		

r0297	DC link voltage overvoltage threshold / Vdc U_upper_thresh		
A_INF, B_INF, S_INF	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Converter		Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	If the DC link voltage exceeds the threshold specified here, the drive unit is tripped due to DC link overvoltage.		
p0300[0...n]	Mot type selection / Mot type selection		
SERVO	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: 6310
	P-Group: Motor		Unit selection: -
	Min 0	Max 10000	Factory setting 0
Description:	<p>Selects the motor type or start to read-in the motor parameters for a motor with DRIVE-CLiQ (p0300 = 10000). The following applies for p0300 < 10000: The first digit of the parameter value always defines the general motor type and corresponds to the unlisted motor belonging to a motor list:</p> <ul style="list-style-type: none"> 1 = Rotating induction motor 2 = Rotating synchronous motor 3 = Linear induction motor (reserved) 4 = Linear synchronous motor 5 = Separately-excited synchronous motor (only VECTOR) 7 = SIEMOSYN motor (only VECTOR) 8 = Reluctance motor (only VECTOR) <p>The type information must be entered to filter motor-specific parameters and to optimize the operating characteristics and behavior. For example, for synchronous motors, power factor (p0308) is neither used nor displayed (in the BOP/AOP).</p>		
Values:	<ul style="list-style-type: none"> 0: No motor selected 1: Induction motor (rotating) 2: Synchronous motor (rotating, permanent-magnet) 4: Synchronous motor (linear, permanent-magnet) 102: 1PH2 induction motor 104: 1PH4 induction motor 107: 1PH7 induction motor 134: 1PM4 induction motor 136: 1PM6 induction motor 206: 1FT6 synchronous motor 236: 1FK6 synchronous motor 237: 1FK7 synchronous motor 261: 1FE1 synchronous motor 276: 1FS6 synchronous motor 283: 1FW3 synchronous motor 286: 1FW6 synchronous motor 291: 2SP1 synchronous motor 401: 1FN1 synchronous motor (linear) 403: 1FN3 synchronous motor (linear) 10000: Motor with DRIVE-CLiQ 		
Dependency:	<p>VECTOR: Motors, selection 206, 236, 237 cannot be operated (also not as motor with DRIVE-CLiQ). p0300 = 5 cannot be selected with SINAMICS G. When the motor type is changed, the code number in p0301 may be reset to 0. p0300 = 12 can only be selected for p0100 = 1 (NEMA). Refer to: p0301</p>		
Notice:	A list of motor/encoder codes can be found in the following literature: SINAMICS S120 Commissioning Manual		

Note: For p0300 = 10000, the motor parameters are automatically downloaded for a motor with DRIVE-CLiQ. If a motor type has not been selected (p0300 = 0), then the drive commissioning routine cannot be exited. A motor type with a value above p0300 >= 100 describes motors for which a motor parameter list exists. Motor types with a value below p0300 < 100 correspond to the selection of an unlisted motor. When appropriately selected, this means that the motor parameters are pre-assigned the settings for an unlisted motor. If a catalog motor is selected (p0300 >= 100) and an associated motor code number (p0301), then the parameters, that are associated if this list, cannot be changed (write protection). The write protection is canceled if the motor type p0300 is set to a non-Siemens motor that matches p0301 (e.g. p0300 = 2 for p0301 = 2xxxx). This also applies for parameters for a motor with DRIVE-CLiQ. In this case p0300 can only be set to p0300 = 10000 (read motor parameters) or to the corresponding non-Siemens motor (first digit of the motor code number) in order to be able to cancel the write protection.

p0300[0...n]	Mot type selection / Mot type selection		
VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: 6310
	P-Group: Motor		Unit selection: -
	Min	Max	Factory setting
	0	10000	0
Description:	<p>Selects the motor type or start to read-in the motor parameters for a motor with DRIVE-CLiQ (p0300 = 10000). The following applies for p0300 < 10000: The first digit of the parameter value always defines the general motor type and corresponds to the unlisted motor belonging to a motor list:</p> <ul style="list-style-type: none"> 1 = Rotating induction motor 2 = Rotating synchronous motor 3 = Linear induction motor (reserved) 4 = Linear synchronous motor 5 = Separately-excited synchronous motor (only VECTOR) 7 = SIEMOSYN motor (only VECTOR) 8 = Reluctance motor (only VECTOR) <p>The type information must be entered to filter motor-specific parameters and to optimize the operating characteristics and behavior. For example, for synchronous motors, power factor (p0308) is neither used nor displayed (in the BOP/AOP).</p>		
Values:	<ul style="list-style-type: none"> 0: No motor selected 1: Induction motor (rotating) 2: Synchronous motor (rotating, permanent-magnet) 5: Synchronous motor (separately excited) 7: SIEMOSYN motor 8: Reluctance motor 11: 1LA1 standard induction motor 12: 1LE2 standard induction motor (NEMA) 15: 1LA5 standard induction motor 16: 1LA6 standard induction motor 17: 1LA7 standard induction motor 18: 1LA8 standard induction motor 102: 1PH2 induction motor 104: 1PH4 induction motor 107: 1PH7 induction motor 134: 1PM4 induction motor 136: 1PM6 induction motor 283: 1FW3 synchronous motor 10000: Motor with DRIVE-CLiQ 		
Dependency:	<p>VECTOR: Motors, selection 206, 236, 237 cannot be operated (also not as motor with DRIVE-CLiQ). p0300 = 5 cannot be selected with SINAMICS G. When the motor type is changed, the code number in p0301 may be reset to 0. p0300 = 12 can only be selected for p0100 = 1 (NEMA). Refer to: p0301</p>		
Notice:	<p>A list of motor/encoder codes can be found in the following literature: SINAMICS S120 Commissioning Manual</p>		

Note: For p0300 = 10000, the motor parameters are automatically downloaded for a motor with DRIVE-CLiQ.
 If a motor type has not been selected (p0300 = 0), then the drive commissioning routine cannot be exited.
 A motor type with a value above p0300 >= 100 describes motors for which a motor parameter list exists.
 Motor types with a value below p0300 < 100 correspond to the selection of an unlisted motor. When appropriately selected, this means that the motor parameters are pre-assigned the settings for an unlisted motor.
 If a catalog motor is selected (p0300 >= 100) and an associated motor code number (p0301), then the parameters, that are associated if this list, cannot be changed (write protection). The write protection is canceled if the motor type p0300 is set to a non-Siemens motor that matches p0301 (e.g. p0300 = 2 for p0301 = 2xxxx).
 This also applies for parameters for a motor with DRIVE-CLiQ. In this case p0300 can only be set to p0300 = 10000 (read motor parameters) or to the corresponding non-Siemens motor (first digit of the motor code number) in order to be able to cancel the write protection.

p0301[0...n] Motor code number selection / Mot code No. sel

SERVO, VECTOR	Can be changed: C2(1, 3), U	Dynamic index: MDS, p0130	Access level: 1
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0	Max 65535	Factory setting 0

Description: The parameter is used to select a motor from a motor parameter list.
 When changing the code number (with the exception to the value 0), all of the motor parameters are pre-assigned from the internally available parameter lists.

Dependency: Only code numbers for motor types can be selected that correspond to the motor type selected in p0300. For 1PH2, 1PH4, 1PH7, 1PM4, 1PM6, 1FT6 motors, code numbers are also possible, whose fourth decimal position is greater by a value of 1 or 2 than the matching motor type in p0300. For 1FE1 motors, the third decimal position can be higher by a value of 1.

Refer to: p0300

Notice: A list of motor/encoder codes can be found in the following literature:
 SINAMICS S120 Commissioning Manual

Note: The motor code number can only be changed if the matching list motor was first selected in p0300.
 For a motor with DRIVE-CLiQ, p0301 cannot be changed. In this case, p0301 is automatically written to the code number of the motor parameter read-in (r0302) if p0300 is set to 10000.
 When selecting a list motor (p0300 >= 100), drive commissioning can only be exited if a code number is selected.

p0301[0...n] Motor code number selection / Mot code No. sel

SERVO (Lin)	Can be changed: C2(1, 3), U	Dynamic index: MDS, p0130	Access level: 1
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0	Max 65535	Factory setting 0


Description: The parameter is used to select a motor from a motor parameter list.
 When changing the code number (with the exception to the value 0), all of the motor parameters are pre-assigned from the internally available parameter lists.

Dependency: Only code numbers for motor types can be selected that correspond to the motor type selected in p0300.
 Refer to: p0300

Notice: A list of motor/encoder codes can be found in the following literature:
 SINAMICS S120 Commissioning Manual

Note: The motor code number can only be changed if the matching list motor was first selected in p0300.
 When selecting a list motor (p0300 >= 100), drive commissioning can only be exited if a code number is selected.

r0302[0...n]	Motor code number of motor with DRIVE-CLiQ / Motor code Mot DLQ		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the motor code number from the saved motor data from a motor with DRIVE-CLiQ.		
Note:	Drive commissioning can only be exited if the code number that was downloaded (r0302) matches the stored code number (p0301). If the numbers differ, then the motor data set should be re-loaded using p0300 = 10000. The motor data are always expected from the first encoder that is assigned to the drive data sets (refer to p0187 = encoder 1) data set number.		
p0304[0...n]	Rated motor voltage / Mot U_{rated}		
SERVO, VECTOR	Can be changed: C2(1, 3)		Access level: 1
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 6300, 6724
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0 [Veff]	Max 20000 [Veff]	Factory setting 0 [Veff]
Description:	Sets the rated motor voltage (rating plate).		
Dependency:	Refer to: p0349		
Note:	The parameter is automatically preset for motors from the motor list (p0301). For synchronous motors (p0300 = 2xx), the parameter can be optionally input. The following applies for SERVO: For synchronous motors, the parameter is of no significance from a control-related perspective. For VECTOR, the following applies: if the rated voltage is entered for synchronous motors during the commissioning phase, then the stator leakage inductance (p0356, p0357) can be more accurately calculated (refer to p0340 and p3900).		
p0305[0...n]	Rated motor current / Mot I_{rated}		
SERVO, VECTOR	Can be changed: C2(1, 3)		Access level: 1
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 6300
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the rated motor current (rating plate).		
Dependency:	Refer to: p0349		
Notice:	For VECTOR, the following applies: If the rated motor current exceeds twice the maximum drive converter current (r0209), then the maximum current is reduced due to the current harmonics that increase overproportionally (r0067).		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0306[0...n]	Number of motors connected in parallel / Motor qty		
SERVO	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 1	Max 100	Factory setting 1
Description:	Number of motors that can be operated in parallel using one motor data set. Internally, an equivalent motor is calculated dependent on the number of motors entered. The following should be carefully observed for motors connected in series: The following rating plate data should only be entered for one motor: - resistances and inductances: p0350, p0352, p0353, p0354, p0356, p0357, p0358, p0360 - currents: p0305, p0318, p0320, p0323, p0325, p0329, p0338, p0391, p0392 - torques/forces: p0312, p0319 - power ratings: p0307 - masses/moments of inertia: p0341, p0344 All other parameters take into account the replacement/equivalent motor (e.g. r0331, r0370, r0373, r0374).		
Dependency:	Refer to: r0331, r0370, r0373, r0374, r0376, r0377, r0382		
Caution:	The motors to be connected-up in parallel, must be of the same type. The mounting regulations when connecting motors in parallel must be carefully maintained! The number of motors set must correspond to the number of motors that are actually connected in parallel. After changing p0306, it is imperative that the control parameters are adapted (e.g. using automatic calculation with p0340 = 1).		
			
Note:	Only possible for SERVO!		
p0307[0...n]	Rated motor power / Mot P_rated		
SERVO	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: 14_6	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.00 [kW]	Max 100000.00 [kW]	Factory setting 0.00 [kW]
Description:	Sets the rated motor power (rating plate).		
Dependency:	IECdrives (p0100 = 0): Units kW NEMA drives (p0100 = 1): Units hp Refer to: p0100		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0307[0...n]	Rated motor power / Mot P_rated		
VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: 14_6	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min -100000.00 [kW]	Max 100000.00 [kW]	Factory setting 0.00 [kW]
Description:	Sets the rated motor power (rating plate).		
Dependency:	IECdrives (p0100 = 0): Units kW NEMA drives (p0100 = 1): Units hp Refer to: p0100		
Note:	The parameter is automatically preset for motors from the motor list (p0301). For generators, a negative rated power should be entered.		

p0308[0...n]	Rated motor power factor / Mot cos_phi_rated		
SERVO, VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.000	Max 1.000	Factory setting 0.000
Description:	Sets the rated motor power factor (cos phi, rating plate). For a parameter value of 0.000, the power factor is internally calculated and displayed in r0332.		
Dependency:	This parameter is only available for IEC motors (p0100 = 0). Refer to: p0100, p0309, r0332		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx). The parameter is automatically preset for motors from the motor list (p0301).		
p0309[0...n]	Rated motor efficiency / Mot eta_rated		
VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [%]	Max 99.9 [%]	Factory setting 0.0 [%]
Description:	Sets the rated motor efficiency (rating plate). For a parameter value of 0.0, the power factor is internally calculated and displayed in r0332.		
Dependency:	This parameter is only available for NEMA motors (p0100 = 1). Refer to: p0100, p0308, r0332		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx). The parameter is automatically preset for motors from the motor list (p0301).		
p0310[0...n]	Rated motor frequency / Mot f_rated		
SERVO, VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 6300
	P-Group: Motor		Unit selection: -
	Min 0.00 [Hz]	Max 3000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Sets the rated motor frequency (rating plate).		
Dependency:	The number of pole pairs (r0313) is automatically re-calculated when the parameter is changed (together with p0311), if p0314 = 0. Only for vector drives (refer to p0107): The rated frequency is restricted to values between 1.00 Hz and 650.00 Hz. Refer to: p0311, r0313, p0314		
Note:	The parameter is automatically pre-assigned for induction motors from the motor list (p0301). For synchronous motors, the parameter is not required and must therefore be pre-assigned zero. For p0310 = 0, it is not possible to calculate the pole pair; instead, it must be entered in p0314.		

p0311[0...n]	Rated motor speed / Mot n_{rated}		
SERVO, VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 0.0 [1/min]
Description:	Sets the rated motor speed (rating plate). For vector drives (refer to p0107): For p0311 = 0, the rated motor slip of induction motors is internally calculated and displayed in r0330. It is especially important to correctly enter the rated motor speed for closed-loop vector control and slip compensation for U/f control.		
Dependency:	If p0311 is changed and for p0314 = 0, the pole pair (r0313) is re-calculated automatically. Refer to: p0310, r0313, p0314		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0311[0...n]	Rated motor velocity / Mot v_{rated}		
SERVO (Lin)	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [m/min]	Max 6000.0 [m/min]	Factory setting 0.0 [m/min]
Description:	Sets the rated motor velocity (rating plate).		
Dependency:	The pole pair width is set in p0315. Refer to: p0310, r0313, p0314		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0312[0...n]	Rated motor torque / Mot M_{rated}		
SERVO	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: 7_4	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the rated motor torque (rating plate).		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0312[0...n]	Rated motor force / Mot F_{rated}		
SERVO (Lin)	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: 8_4	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	Sets the rated motor force (rating plate).		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

r0313[0...n]		Motor pole pair number, actual (or calculated) / Mot PolePairNo act		
SERVO	Can be changed: -			Access level: 2
	Data type: Unsigned8	Dynamic index: MDS, p0130		Function diagram: 5300
	P-Group: Motor	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the number of motor pole pairs. The value is used for internal calculations. Values: r0313 = 1: 2-pole motor r0313 = 2: 4-pole motor etc.			
Dependency:	For p0314 > 0, the entered value is displayed in r0313. For p0314 = 0, the pole pair number (r0313) is automatically calculated from the rated frequency (p0310) and the rated speed (p0311). Refer to: p0310, p0311, p0314			
Note:	For the automatic calculation, the pole pair number is set to the value of 2 if the rated speed or the rated frequency is zero.			
r0313[0...n]		Motor pole pair number, actual (or calculated) / Mot PolePairNo act		
VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned8	Dynamic index: MDS, p0130		Function diagram: 5300
	P-Group: Motor	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the number of motor pole pairs. The value is used for internal calculations. Values: r0313 = 1: 2-pole motor r0313 = 2: 4-pole motor etc.			
Dependency:	For p0314 > 0, the entered value is displayed in r0313. For p0314 = 0, the pole pair number (r0313) is automatically calculated from the rated power (p0307), rated frequency (p0310) and rated speed (p0311). Refer to: p0307, p0310, p0311, p0314			
Note:	For the automatic calculation, the pole pair number is set to the value of 2 if the rated speed or the rated frequency is zero.			
p0314[0...n]		Motor pole pair number / Mot pole pair No.		
SERVO, VECTOR	Can be changed: C2(1, 3)			Access level: 1
	Data type: Unsigned8	Dynamic index: MDS, p0130		Function diagram: -
	P-Group: Motor	Units group: -		Unit selection: -
	Min	Max		Factory setting
	0	127		0
Description:	Sets the motor pole pair number. Values: p0314 = 1: 2-pole motor p0314 = 2: 4-pole motor etc.			
Dependency:	For p0314 = 0, the pole pair number is automatically calculated from the rated frequency (p0310) and the rated speed (p0311) and displayed in r0313.			
Notice:	For induction motors, the value need only be input if the rated data of a generator is entered therefore resulting in a negative rated slip. In this case, the number of pole pairs in r0313 is too low by 1 and must be manually corrected.			

p0315[0...n]	Motor pole pair width / MotPolePair width		
SERVO (Lin)	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 1.00 [mm]	Max 1000.00 [mm]	Factory setting 30.00 [mm]
Description:	Sets the pole pair width of the linear motor.		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0316[0...n]	Motor torque constant / Mot kT		
SERVO	Can be changed: C2(1, 3), U, T	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: 28_1	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.00 [Nm/A]	Max 100.00 [Nm/A]	Factory setting 0.00 [Nm/A]
Description:	Sets the torque constant of the synchronous motor. p0316 = 0: The torque constant is calculated from the motor data. p0316 > 0: The selected value is used as torque constant.		
Dependency:	Refer to: r0334, r1937		
Note:	The parameter is automatically preset for motors from the motor list (p0301). This parameter is not used for induction motors (p0300 = 1xx).		
p0316[0...n]	Motor force constant / Mot kT		
SERVO (Lin)	Can be changed: C2(1, 3), U, T	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: 29_1	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.00 [N/Aeff]	Max 1000.00 [N/Aeff]	Factory setting 0.00 [N/Aeff]
Description:	Sets the force constant of the synchronous motor. p0316 = 0: The force constant is calculated from the motor data. p0316 > 0: The selected value is used as force constant.		
Dependency:	Refer to: r0334, r1937		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0316[0...n]	Motor torque constant / Mot kT		
VECTOR	Can be changed: C2(1, 3), U, T	Dynamic index: MDS, p0130	Access level: 2
	Data type: Floating Point	Units group: 28_1	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.00 [Nm/A]	Max 100.00 [Nm/A]	Factory setting 0.00 [Nm/A]
Description:	Sets the torque constant of the synchronous motor. p0316 = 0: The torque constant is calculated from the motor data. p0316 > 0: The selected value is used as torque constant.		
Dependency:	Refer to: r0334		
Note:	The parameter is automatically preset for motors from the motor list (p0301). This parameter is not used for induction motors (p0300 = 1xx).		

p0317[0...n]	Motor voltage constant / Mot kE		
SERVO	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [Veff]	Max 10000.0 [Veff]	Factory setting 0.0 [Veff]
Description:	Sets the voltage constant for synchronous motors. Units for rotating synchronous motors: Vrms/(1000 RPM), phase-to-phase		
Dependency:	Refer to: r1938		
Note:	The parameter is automatically preset for motors from the motor list (p0301). This parameter is not used for induction motors (p0300 = 1xx).		
p0317[0...n]	Motor voltage constant / Mot kE		
SERVO (Lin)	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [Veff s/m]	Max 1000.0 [Veff s/m]	Factory setting 0.0 [Veff s/m]
Description:	Sets the voltage constant for synchronous motors. Units for linear synchronous motors: Vrms s/m, phase		
Dependency:	Refer to: r1938		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0318[0...n]	Motor stall current / Mot I_standstill		
SERVO	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the stall current for synchronous motors (p0300 = 2xx).		
Note:	The parameter is automatically preset for motors from the motor list (p0301). This parameter is not used for induction motors (p0300 = 1xx). This parameter value is not evaluated from a control-related perspective.		
p0319[0...n]	Motor stall torque / Mot M_standstill		
SERVO	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: 7_4	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.0 [Nm]	Max 100000.0 [Nm]	Factory setting 0.0 [Nm]
Description:	Sets the standstill (stall) torque for rotating synchronous motors (p0300 = 2xx).		
Note:	The parameter is automatically preset for motors from the motor list (p0301). This parameter is not used for induction motors (p0300 = 1xx). This parameter value is not evaluated from a control-related perspective.		

p0319[0...n]	Motor stall force / Mot F_standstill		
SERVO (Lin)	Can be changed: C2(3)	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: 8_4	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.0 [N]	Max 100000.0 [N]	Factory setting 0.0 [N]
Description:	Sets the standstill (stall) force for linear synchronous motors (p0300 = 4xx).		
Note:	The parameter is automatically preset for motors from the motor list (p0301). This parameter value is not evaluated from a control-related perspective.		
p0320[0...n]	Motor rated magnetization current/short-circuit current / Mot I_mag_rated		
SERVO, VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5722
	P-Group: Motor		Unit selection: -
	Min 0.000 [Aeff]	Max 5000.000 [Aeff]	Factory setting 0.000 [Aeff]
Description:	Induction motors: Sets the rated motor magnetizing current. For p0320 = 0.000 the magnetizing current is internally calculated and displayed in r0331. Synchronous motors: Sets the rated motor short-circuit current.		
Note:	The parameter is automatically preset for motors from the motor list (p0301). VECTOR: If, for induction motors, the magnetizing current p0320 is changed outside the commissioning phase (p0010 > 0), then the magnetizing inductance p0360 is changed so that the EMF r0337 remains constant.		
p0322[0...n]	Maximum motor speed / Mot n_max		
SERVO, VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 0.0 [1/min]
Description:	Sets the maximum motor speed.		
Dependency:	Refer to: p1082		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0322[0...n]	Motor maximum velocity / Mot v_max		
SERVO (Lin)	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 0.0 [m/min]
Description:	Sets the maximum motor velocity.		
Dependency:	Refer to: p1082		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0323[0...n]	Maximum motor current / Mot I_max		
SERVO, VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 5722
	P-Group: Motor		Unit selection: -
	Min 0.00 [Aeff]	Max 20000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Set the maximum permissible motor current (e.g. de-magnetizing current for synchronous motors).		
Note:	The parameter is automatically preset for motors from the motor list (p0301). For induction motors, the parameter has not effect if p0323 is set to 0. For synchronous motors, a value must always be entered for the maximum motor current. p0323 is a motor data. The user-selectable current limit is entered into p0640.		
p0325[0...n]	Motor pole position identification current, 1st phase / Mot PoIID 1 1st ph		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.000 [Aeff]	Max 10000.000 [Aeff]	Factory setting 0.000 [Aeff]
Description:	Sets the current for the 1st phase of the two-stage technique for pole position identification routine. The current of the 2nd phase is set in p0329. A two-stage technique is selected with p1980 = 4, 5.		
Dependency:	Refer to: p0329, p1980, p1981, p1982, p1983, r1984, r1985, r1987, p1990, Refer to: F07995		
Notice:	When the motor code (p0301) is changed, it is possible that p0325 is not pre-assigned. p0325 can be pre-assigned using p0340 = 3.		
Note:	The value is automatically pre-assigned for the following events: - For p0325 = 0 and automatic calculation of the closed-loop control parameters (p0340 = 1, 2, 3). - for quick commissioning (p3900 = 1, 2, 3).		
p0326[0...n]	Motor stall torque correction factor / Mot M_stallCorrFac		
SERVO	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 5 [%]	Max 300 [%]	Factory setting 60 [%]
Description:	Sets the correction factor for the stall torque/force at a 600 V DC link voltage.		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0327[0...n]	Optimum motor load angle / Mot phi_load opt		
SERVO, VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5722
	P-Group: Motor		Unit selection: -
	Min 0.0 [°]	Max 135.0 [°]	Factory setting 90.0 [°]
Description:	Sets the optimum load angle for synchronous motors with reluctance torque (e.g. 1FE ... motors). This parameter has no significance for induction motors. SERVO: The load angle is measured at 150% rated motor current. VECTOR: The load angle is measured at the rated motor current.		
Dependency:	Refer to: r1947		
Note:	For synchronous motors without reluctance torque, a angle of 90 degrees must be set. The parameter is automatically preset for motors from the motor list (p0301).		

p0328[0...n]	Motor reluctance torque constant / Mot kT_reluctance		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.00 [mH]	Max 1000.00 [mH]	Factory setting 0.00 [mH]
Description:	Sets the reluctance torque constant for synchronous motors with reluctance torque (e.g. 1FE ... motors). This parameter has no significance for induction motors.		
Dependency:	Refer to: r1939		
Note:	For synchronous motors without reluctance torque, the value 0 must be set. The parameter is automatically preset for motors from the motor list (p0301).		
p0329[0...n]	Motor pole position identification current / Mot PolID current		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the current for the pole position identification routine. For a two-stage technique, the current is set for the second phase.		
Dependency:	Refer to: p0325, p1980, p1981, p1982, p1983, r1984, r1985, r1987, p1990 Refer to: F07995		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
r0330[0...n]	Rated motor slip / Mot slip_rated		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the rated motor slip.		
Dependency:	The rated slip is calculated from the rated frequency, rated speed and number of pole pairs. Refer to: p0310, p0311, r0313		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		
r0331[0...n]	Motor magnetizing current/short-circuit current actual / Mot I_mag_ratedAct		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 5722, 6722, 6724
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Induction motor: Displays the rated magnetizing current from p0320. For p0320 = 0, the internally calculated magnetizing current is displayed. Synchronous motor: Displays the rated short-circuit current from p0320.		
Dependency:	If p0320 was not entered, then the parameter is calculated from the rating plate parameters.		

r0332[0...n]	Rated motor power factor / Mot cos_phi_rated		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the rated power factor for induction motors. For IEC motors, the following applies (p0100 = 0): For p0308 = 0, the internally-calculated power factor is displayed. For p0308 > 0, this value is displayed. For NEMA motors, the following applies (p0100 = 1): For p0309 = 0, the internally-calculated power factor is displayed. For p0309 > 0, this value is converted into the power factor and displayed.		
Dependency:	If p0308 is not entered, the parameter is calculated from the rating plate parameters.		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		
r0333[0...n]	Rated motor torque / Mot M_rated		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 7_4	Unit selection: p0100
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the rated motor torque.		
Note:	For induction and reluctance motors, r0333 is calculated from p0307 and p0311. For synchronous motors, r0333 is calculated from p0305, p0316, p0327 and p0328. The result can deviate from the input in p0312. If p0316 = 0, then r0333 = p0312 is displayed.		
r0333[0...n]	Rated motor force / Mot F_rated		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 8_4	Unit selection: p0100
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the rated motor force.		
Note:	For synchronous motors, r0333 is calculated from p0305, p0316, p0327 and p0328. The result can deviate from the input in p0312. If p0316 = 0, then r0333 = p0312 is displayed.		
r0334[0...n]	Motor-torque constant, actual / Mot kT act		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 28_1	Unit selection: p0100
	Min - [Nm/A]	Max - [Nm/A]	Factory setting - [Nm/A]
Description:	Displays the torque constant of the synchronous motor used.		
Dependency:	Refer to: p0316		
Note:	This parameter is not used for induction motors (p0300 = 1xx). For synchronous motors, parameter r0334 = p0316 is displayed. if p0316 = 0, r0334 is calculated from p0305 and p0312.		

r0334[0...n]	Motor force constant, actual / Mot kT act		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 29_1	Unit selection: p0100
	Min - [N/Aeff]	Max - [N/Aeff]	Factory setting - [N/Aeff]
Description:	Displays the force constant of the synchronous motor used.		
Dependency:	Refer to: p0316		
Note:	For synchronous motors, parameter r0334 = p0316 is displayed. if p0316 = 0, r0334 is calculated from p0305 and p0312.		
p0335[0...n]	Motor cooling type / Motor cooling type		
SERVO, VECTOR	Can be changed: C2(1, 3), T		Access level: 1
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Sets the motor cooling system used.		
Values:	0: Non-ventilated 1: Forced cooling 2: Water cooling 4: Non-ventilated and internal fan 5: Forced cooling and internal fan 6: Water cooling and internal fan		
Note:	The parameter influences the thermal 3-mass motor model. 1LA1 and 1LA8 motors are characterized by the fact that they have an internal rotor fan. This "internal cooling" lies within the motor frame and is not visible. Air is not directly exchanged with the motor ambient air. The parameter is automatically preset for motors from the motor list (p0301).		
r0336[0...n]	Rated motor frequency actual / Mot f_{rated} act		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the rated frequency of the motor. For p0310 > 0, this value is displayed.		
Dependency:	Refer to: p0311, p0314		
Note:	For p0310 = 0 or for synchronous motors, the rated motor frequency r0336 is calculated from the rated speed and the pole pair number. For p0310 > 0, this value is displayed (not for synchronous motors).		
r0337[0...n]	Rated motor EMF / Mot EMF_{rated}		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the rated EMF of the motor.		
Note:	EMF: Electromagnetic force		

r0337[0...n]	Rated motor EMF / Mot EMF_{rated}		
SERVO (Lin)	Can be changed: -	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min - [Veff s/m]	Max - [Veff s/m]	Factory setting - [Veff s/m]
Description:	Displays the rated EMF of the motor.		
Note:	EMF: Electromagnetic force		
p0338[0...n]	Motor limit current / Mot I_{limit}		
SERVO	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the motor limit current for synchronous motors (for a 600 V DC link voltage). Using this current, the maximum torque is achieved at the rated speed (voltage limit characteristic).		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
r0339[0...n]	Rated motor voltage / Mot U_{rated}		
SERVO, VECTOR	Can be changed: -	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the rated motor voltage		
Note:	For induction motors (p0300 = 1xx) the parameter is set to p0304. For synchronous motors, parameter r0339 = p0304 is displayed. If p0304 = 0, then r0339 is calculated from p0305 and p0316.		
p0340	Automatic calculation, control parameters / Calc auto par		
A_INF, S_INF	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Setting to reset and automatically calculate filter and control (closed-loop) parameters.		
Values:	0: No calculation 1: Complete re-calculation. of control parameters with COMM data 2: Reset control parameters		
Notice:	The following parameters are influenced using p0340: p0340 = 1: --> All of the parameters influenced for p0340 = 2 --> p3421 = p0223 + p0225 --> p3422 = p0227 p0340 = 2: --> p3560, p3562, p3564, p3603, p3615 and p3617 are reset to the factory setting. These controller parameters are not available for S_Infeed.		
Note:	When existing the quick commissioning using p3900 > 0, p0340 is automatically set to 1. At the end of the calculations, p0340 is automatically set to 0.		

p0340[0...n]		Automatic calculation of motor/control parameters / Calc auto par	
SERVO, VECTOR	Can be changed: C2(3), T		Access level: 2
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 5	Factory setting 0
Description:	Setting to automatically calculate motor parameters and U/f open-loop and closed-loop control parameters from the rating plate data.		
Values:	0: No calculation 1: Complete calculation 2: Calculation of equivalent circuit diagram parameters 3: Calculation of closed-loop control parameters 4: Calculation of controller parameters 5: Calculation of technological limits and threshold values		
Notice:	The following parameters are influenced using p0340: The parameters designated with (*) are, for list motors (p0300 > 100) not overwritten. SERVO: p0340 = 1: --> All of the parameters influenced for p0340 = 2, 3, 4, 5 --> p0341 (*) --> p0342, p0344, p0600, p0640, p1082, p2000, p2001, p2002, p2003 p0340 = 2: --> p0350 (*), p0354 (*), p0356 (*), p0358 (*), p0360 (*) --> p0625 (matching p0350) p0340 = 3: --> All of the parameters influenced for p0340 = 4, 5 --> p0325 (is only calculated for p0325 = 0) --> p0348 (*) (is only calculated for p0348 = 0) --> p0441, p0442, p0443, p0444, p0445 (only for 1FT6, 1FK6, 1FK7 motors) --> p0492, p1082, p1980, p1319, p1326, p1327, p1612, p1752, p1755 p0340 = 4: --> p1441, p1460, p1462, p1463, p1464, p1465, p1470, p1472, p1590, p1592, p1715, p1717 --> p1461 (for p0348 > p0322, p1461 is set to 100 %) --> p1463 (for p0348 > p0322, p1463 is set to 400 %) p0340 = 5: --> p1037, p1038, p1520, p1521, p1530, p1531, p2140 ... p2142, p2148, p2150, p2155, p2161, p2162, p2163, p2164, p2175, p2177, p2194, p3820 ... p3829		

VECTOR:

p0340 = 1:

-> All of the parameters influenced for p0340 = 2, 3, 4, 5

-> p0341 (*)

-> p0342, p0344, p0600, p0640, p1082, p1349, p1576, p1577, p1609, p1619, p1620, p1621, p1654, p1726, p1825, p1828 ... p1832, p1909, p1959, p2000, p2001, p2002, p2003, p3927, p3928

p0340 = 2:

-> p0350 (*), p0354 ... p0361 (*), p0652 ... p0660

-> p0625 (matching p0350)

p0340 = 3:

-> All of the parameters influenced for p0340 = 4, 5

-> p0346, p0347, p0492, p0622, p1262, p1320 ... p1327, p1582, p1584, p1616, p1744, p1755, p1756, p2178

p0340 = 4:

-> p1290, p1292, p1293, p1299, p1338, p1339, p1340, p1341, p1345, p1346, p1460, p1461, p1462, p1463, p1464, p1465, p1470, p1472, p1590, p1592, p1600, p1628, p1629, p1630, p1643, p1703, p1715, p1717, p1740, p1757, p1760, p1761, p1764, p1767, p1781, p1783, p1785, p1786, p1795, p7036, p7037, p7038

p0340 = 5:

-> p260 ... p264, p1037, p1038, p1520, p1521, p1530, p1531, p1802, p1803, p2140, p2142, p2148, p2150, p2161, p2162, p2163, p2164, p2175, p2177, p2194, p3207, p3208, p3815, p3820 ... p3829

Note:

p0340 = 1 contains the calculations of p0340 = 2, 3, 4, 5 without overwriting the motor parameters from the Siemens motor lists (p0301 > 0).

p0340 = 2 calculates the motor parameters (p0350 ... p0360), but only if it does involve a Siemens catalog motor (p0301 = 0).

p0340 = 3 contains the calculations of p0340 = 4, 5.

p0340 = 4 only calculates the controller parameters.

p0340 = 5 only calculates the controller limits.

When existing the quick commissioning using p3900 > 0, p0340 is automatically set to 1.

At the end of the calculations, p0340 is automatically set to 0.

If the STARTER commissioning software (start-up tool) writes a 3 into p0340 when "downloading into the target device", then this corresponds to a "complete calculation of the motor/control parameters without equivalent circuit diagram data". The same calculations are carried-out as for p0340 = 1, however, without the equivalent circuit diagram parameters of the motor (refer to p0340 = 2), the motor moment of inertia (p0341) and the motor weight (p0344).

For third-party linear synchronous motors (p300 = 4) equivalent circuit diagram data are not calculated (refer to p340 = 2).

p0341[0...n]	Motor moment of inertia / Mot M_mom of inert		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 5210
	P-Group: Motor	Units group: 25_1	Unit selection: p0100
	Min 0.00000 [kgm ²]	Max 100000.00000 [kgm ²]	Factory setting 0.00000 [kgm ²]
Description:	Sets the motor moment of inertia (without load).		
Dependency:	This means that together with p0342, the rated starting time of the motor is calculated. Refer to: p0342, r0345		
Note:	The parameter is automatically preset for motors from the motor list (p0301). SERVO: p0341 * p0342 + p1498 influence the speed/torque precontrol in sensorless operation. VECTOR: The product p0341 * p0342 is taken into account when automatically calculating the speed controller (p0340 = 4).		

p0341[0...n]	Motor weight / Mot weight		
SERVO (Lin)	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: 27_1	Function diagram: 5210
	P-Group: Motor		Unit selection: p0100
	Min 0.00000 [kg]	Max 10000.00000 [kg]	Factory setting 0.00000 [kg]
Description:	Sets the high moments of inertia (without load).		
Dependency:	This means that together with p0342, the rated starting time of the motor is calculated. Refer to: p0342, r0345		
Note:	The parameter is automatically preset for motors from the motor list (p0301). SERVO: p0341 * p0342 + p1498 influence the speed/torque precontrol in sensorless operation.		
p0342[0...n]	Ratio between the total and motor moment of inertia / Mot Momlnert Ratio		
SERVO, VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5210
	P-Group: Motor		Unit selection: -
	Min 1.000	Max 10000.000	Factory setting 1.000
Description:	Sets the ratio between the total moment of inertia/mass (load + motor) and the intrinsic motor moment of inertia/mass (no load).		
Dependency:	This means that together with p0341, the rated starting (accelerating time) of the motor is calculated for a vector drive. Refer to: p0341, r0345, p1498		
Note:	SERVO: p0341 * p0342 + p1498 influence the speed/torque precontrol in sensorless operation. VECTOR: The product p0341 * p0342 is taken into account when automatically calculating the speed controller (p0340 = 4).		
p0344[0...n]	Motor weight / Motor weight		
SERVO, VECTOR	Can be changed: C2(3), T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: 27_1	Function diagram: -
	P-Group: Motor		Unit selection: p0100
	Min 0.0 [kg]	Max 50000.0 [kg]	Factory setting 0.0 [kg]
Description:	Sets the motor weight. The following applies for vector drives (refer to p0107): The parameter influences the thermal 3 mass model of the induction motor.		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx). The parameter is automatically preset for motors from the motor list (p0301).		
r0345[0...n]	Nominal motor starting time / Mot t_start Rated		
VECTOR	Can be changed: -	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min - [s]	Max - [s]	Factory setting - [s]
Description:	Displays the rated motor starting time. This time corresponds to the time from standstill up to reaching the motor rated speed and the acceleration with motor rated torque (r0333).		
Dependency:	Refer to: r0313, r0333, r0336, p0341, p0342		

p0346[0...n]	Motor excitation build-up time / Mot t_excitation		
VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 20.000 [s]	Factory setting 0.000 [s]
Description:	Sets the excitation build-up time of the motor. This involves the delay time between enabling the pulses and enabling the ramp-function generator. The induction motor is magnetized during this time.		
Notice:	If the parameter is set to 0 s for separately-excited synchronous motors (p0300 = 5), then an excitation current setpoint is generated even if the drive is powered-down. In the base speed range, this is the no-load excitation current (p0389). In the field-weakening range, the value is reduced with the inverse value of the actual speed. An excitation current setpoint is not generated during de-magnetization (p0347) and if an encoder fault is detected.		
Note:	The parameter is calculated using p0340 = 1, 3. For induction motors, the result depends on the rotor time constant (r0384). If this time is excessively reduced, this can result in an inadequate magnetization of the induction motor. This means that the parameter cannot be set less than 25% of the rotor time constant. For permanent-magnet synchronous motors and vector control, the value depends on the stator time constant (r0386). Here, it defines the time to establish the current for sensorless operation immediately after the pulses have been enabled.		
p0347[0...n]	Motor de-excitation time / Mot t_de-excitat.		
VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 20.000 [s]	Factory setting 0.000 [s]
Description:	Sets the de-magnetizing time (for induction motors) after the inverter pulses have been cancelled. The inverter pulses cannot be switched-in (enabled) within this delay time.		
Note:	The parameter is calculated using p0340 = 1, 3. For induction motors, the result depends on the rotor time constant (r0384). if this time is shortened too much, then this can result in an inadequate de-magnetization of the induction motor and in an overcurrent condition when the pulses are subsequently enabled (only when the flying restart function is activated and the motor is rotating).		
p0348[0...n]	Speed at the start of field weakening Vdc = 600 V / Mot n_field weaken		
SERVO	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 5722
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 0.0 [1/min]
Description:	Sets the speed at the start of field weakening for a DC link voltage of 600 V.		
Dependency:	Refer to: p0320, r0331		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0348[0...n]	Velocity at the start of field weakening Vdc = 600 V / Mot v_field weaken		
SERVO (Lin)	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 5722
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 0.0 [m/min]
Description:	Sets the velocity at the start of field weakening for a DC link voltage of 600 V.		
Dependency:	Refer to: p0320, r0331		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0349	Selects system of units, motor equivalent circuit diagram data / Sel UnitSys MotESB		
SERVO, VECTOR	Can be changed: C2(3)		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Setting parameter of the actual system of units for motor equivalent circuit diagram data		
Values:	1: System of units, physical 2: System of units, referred		
Dependency:	Refer to: p0304, p0305, p0310		
Note:	The reference parameter for resistances of the rated motor impedance $Z = p0304 / (1.732 * p0305)$ is in the % units system. Inductances are converted into a resistance using the factor $2 * \text{Pi} * p0310$. If a reference parameter (p0304, p305, p0310) is zero, then it is not possible to make a changeover to per unit (referred) values.		
p0350[0...n]	Motor stator resistance, cold / Mot R_stator cold		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min 0.00000 [Ohm]	Max 2000.00000 [Ohm]	Factory setting 0.00000 [Ohm]
Description:	Sets the stator resistance of the motor at ambient temperature p0625.		
Dependency:	Refer to: p0625, r1912		
Note:	The parameter is automatically preset for motors from the motor list (p0301). The motor identification routine determines the stator resistance from the total stator resistance minus the cable resistance (p0352).		
p0352[0...n]	Cable resistance / Mot R_cable cold		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min 0.00000 [Ohm]	Max 120.00000 [Ohm]	Factory setting 0.00000 [Ohm]
Description:	Resistance of the power cable between the Motor Module and motor.		
Note:	The parameter influences the temperature adaptation of the stator resistance. The motor identification routine does not change the cable resistance. This is subtracted from the total measured stator resistance in order to calculate the stator resistance (p0350, p0352).		

p0353[0...n]	Motor series inductance / Mot L_series		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.000 [mH]	Max 1000000.000 [mH]	Factory setting 0.000 [mH]
Description:	Sets the series inductance.		
Note:	For the automatic calculation with p0340 = 1 or 3, the calculation of p0348 is influenced by p0353 if p0348 was 0. For the automatic calculation with p0340 = 1, 3 or 4, the calculation of p1715 is influenced by p0353.		
p0354[0...n]	Motor rotor resistance cold / damping resistance d axis / Mot R_r cold / RDd		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min 0.00000 [Ohm]	Max 300.00000 [Ohm]	Factory setting 0.00000 [Ohm]
Description:	Sets the rotor/secondary section resistance of the motor at the ambient temperature p0625. For separately-excited synchronous motors: Sets the damping resistance in the rotor direction (d-axis). This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910) (not for separately-excited synchronous motors).		
Dependency:	Refer to: p0625		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx). The parameter is automatically preset for motors from the motor list (p0301).		
p0355[0...n]	Motor damping resistance, q axis / Mot R_damping_q		
VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min 0.00000 [Ohm]	Max 300.00000 [Ohm]	Factory setting 0.00000 [Ohm]
Description:	Sets the damping resistance of the separately-excited synchronous motor quadrature to the rotor direction (q axis). This parameter value is automatically calculated using the motor model (p0340 = 1, 2).		
p0356[0...n]	Motor stator leakage inductance / Mot L_stator leak.		
SERVO	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 1000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Induction motor, separately-excited synchronous motor: Sets the rotor leakage inductance of the motor. Synchronous motor: Sets the stator quadrature axis inductance of the motor. This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910).		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0356[0...n]	Motor stator leakage inductance / Mot L_stator leak.		
VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 1000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Induction motor, separately-excited synchronous motor: Sets the rotor leakage inductance of the motor. Synchronous motor: Sets the stator quadrature axis inductance of the motor. This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910).		
Note:	The parameter is automatically preset for motors from the motor list (p0301). If the stator leakage inductance p0356 for induction motors is changed outside the commissioning phase (p0010 > 0), then the magnetizing inductance p0360 is automatically adapted to the new EMF r0337. After this, we recommend that the saturation characteristic measurement (refer to rotating measurement p1960) should be repeated. For permanent-magnet synchronous motors (p300=2), this is the non-saturated value and is therefore ideally applicable for a low current.		
p0357[0...n]	Motor stator inductance, d axis / Mot L_stator_d		
VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 1000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Sets the stator direct-axis inductance of the synchronous motor. This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910).		
Note:	The parameter is not used for separately-excited synchronous motors (p0300 = 5). For permanent-magnet synchronous motors (p300 = 2), this is the non-saturated value and is therefore ideally applicable for a low current.		
p0358[0...n]	Motor rotor leakage inductance / damping inductance, d axis / Mot L_r leak / LDd		
SERVO, VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 1000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Sets the rotor/secondary section leakage inductance of the motor. For separately-excited synchronous motors: Sets the damping inductance in the rotor direction (d-axis). This value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910) (not for separately-excited synchronous motors).		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx). The parameter is automatically preset for motors from the motor list (p0301). VECTOR: If the rotor leakage inductance p0358 for induction motors is changed outside the commissioning phase (p0010 > 0), then the magnetizing inductance p0360 is automatically adapted to the new EMF r0337. After this, we recommend that the saturation characteristic measurement (refer to rotating measurement p1960) should be repeated.		

p0359[0...n]	Motor damping inductance, q axis / Mot L_damping_q		
VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 1000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Sets the damping inductance of the separately-excited synchronous motor quadrature to the rotor direction (q axis). This parameter value is automatically calculated using the motor model (p0340 = 1, 2).		
p0360[0...n]	Motor magnetizing inductance/magn. inductance, d axis saturated / Mot Lh/Lh d sat		
SERVO, VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 10000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Sets the magnetizing inductance of the motor. For separately-excited synchronous motors: Sets the saturated magnetizing inductance in the rotor direction (d-axis). This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910) (not for separately-excited synchronous motors).		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx). The parameter is automatically preset for motors from the motor list (p0301).		
p0361[0...n]	Motor magnetizing inductance, q axis, saturated / Mot Lh q_sat		
VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min 0.00000 [mH]	Max 10000.00000 [mH]	Factory setting 0.00000 [mH]
Description:	Sets the saturated magnetizing inductance of the separately-excited synchronous motor quadrature to the rotor direction (q axis). This parameter value is automatically calculated using the motor model (p0340 = 1, 2).		
p0362[0...n]	Saturation characteristic flux 1 / Mot saturat.flux 1		
VECTOR	Can be changed: C2(3), U, T	Access level: 3	
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 60.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the y coordinate (flux) for the 1st value pair of the characteristic. Sets the first flux value of the saturation characteristic as a [%] referred to the rated motor flux (100%).		
Dependency:	The following applies for the flux values: p0362 < p0363 < p0364 < p0365 Refer to: p0366		
Note:	For induction motors, p0362 = 100 % corresponds to the rated motor flux. For separately-excited synchronous motors p0362 = 100% corresponds to an induced terminal voltage with the magnitude of the rated motor voltage (under no-load conditions at the synchronous speed).		

p0363[0...n]	Saturation characteristic flux 2 / Mot saturat.flux 2		
VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 85.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the y coordinate (flux) for the 2nd value pair of the characteristic. Sets the second flux value of the saturation characteristic as a [%] referred to the rated motor flux (100%).		
Dependency:	The following applies for the flux values: p0362 < p0363 < p0364 < p0365 Refer to: p0367		
Note:	For induction motors, p0363 = 100 % corresponds to the rated motor flux. For separately-excited synchronous motors p0363 = 100% corresponds to an induced terminal voltage with the magnitude of the rated motor voltage (under no-load conditions at the synchronous speed).		
p0364[0...n]	Saturation characteristic flux 3 / Mot saturat.flux 3		
VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 115.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the y coordinate (flux) for the 3rd value pair of the characteristic. Sets the third flux value of the saturation characteristic as a [%] referred to the rated motor flux (100%).		
Dependency:	The following applies for the flux values: p0362 < p0363 < p0364 < p0365 Refer to: p0368		
Note:	For induction motors, p0364 = 100 % corresponds to the rated motor flux. For separately-excited synchronous motors p0364 = 100% corresponds to an induced terminal voltage with the magnitude of the rated motor voltage (under no-load conditions at the synchronous speed).		
p0365[0...n]	Saturation characteristic flux 4 / Mot saturat.flux 4		
VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 125.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the y coordinate (flux) for the 4th value pair of the characteristic. Sets the fourth flux value of the saturation characteristic as a [%] referred to the rated motor flux (100%).		
Dependency:	The following applies for the flux values: p0362 < p0363 < p0364 < p0365 Refer to: p0369		
Note:	For induction motors, p0365 = 100 % corresponds to the rated motor flux. For separately-excited synchronous motors p0365 = 100% corresponds to an induced terminal voltage with the magnitude of the rated motor voltage (under no-load conditions at the synchronous speed).		

p0366[0...n]	Saturation characteristic I_mag 1 / Mot sat. I_mag 1		
VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 5.0 [%]	Max 800.0 [%]	Factory setting 50.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the x coordinate (magnetizing current) for the 1st value pair of the characteristic. Sets the first magnetizing current of the saturation characteristic as a [%] referred to the rated magnetizing current (r0331), for separately-excited synchronous motors referred to the no-load excitation current.		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0362		
p0367[0...n]	Saturation characteristic I_mag 2 / Mot sat. I_mag 2		
VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 5.0 [%]	Max 800.0 [%]	Factory setting 75.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the x coordinate (magnetizing current) for the 2nd value pair of the characteristic. Sets the second magnetizing current of the saturation characteristic as a [%] referred to the rated magnetizing current (r0331), for separately-excited synchronous motors referred to the no-load excitation current.		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0363		
p0368[0...n]	Saturation characteristic I_mag 3 / Mot sat. I_mag 3		
VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 5.0 [%]	Max 800.0 [%]	Factory setting 150.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the x coordinate (magnetizing current) for the 3rd value pair of the characteristic. Sets the third magnetizing current of the saturation characteristic as a [%] referred to the rated magnetizing current (r0331), for separately-excited synchronous motors referred to the no-load excitation current.		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0364		

p0369[0...n]	Saturation characteristic I_mag 4 / Mot sat. I_mag 4		
VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor		Unit selection: -
	Min 5.0 [%]	Max 800.0 [%]	Factory setting 210.0 [%]
Description:	The saturation characteristics (flux as a function of the magnetizing current) is defined using 4 points. This parameter specifies the x coordinate (magnetizing current) for the 4th value pair of the characteristic. Sets the fourth magnetizing current of the saturation characteristic as a [%] referred to the rated magnetizing current (r0331), for separately-excited synchronous motors referred to the no-load excitation current.		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0365		
r0370[0...n]	Motor stator resistance, cold / Mot R_stator cold		
SERVO, VECTOR	Can be changed: -	Dynamic index: MDS, p0130	Access level: 4
	Data type: Floating Point	Units group: 16_1	Function diagram: -
	P-Group: Motor		Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the motor stator resistance at an ambient temperature p0625. The value does not include the cable resistance.		
Dependency:	Refer to: p0625		
r0372[0...n]	Cable resistance / Mot R_cable		
VECTOR	Can be changed: -	Dynamic index: MDS, p0130	Access level: 4
	Data type: Floating Point	Units group: 16_1	Function diagram: -
	P-Group: Motor		Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the cable resistance between the Motor Module and motor.		
Dependency:	Refer to: p0352		
r0373[0...n]	Motor rated stator resistance / Mot R_stator rated		
SERVO, VECTOR	Can be changed: -	Dynamic index: MDS, p0130	Access level: 4
	Data type: Floating Point	Units group: 16_1	Function diagram: -
	P-Group: Motor		Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the rated motor stator resistance at rated temperature (sum from p0625 and p0627).		
Dependency:	Refer to: p0627		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		

r0374[0...n]	Motor rotor resistance cold / damping resistance d axis / Mot R_r cold / RDd		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the rotor/secondary section resistance of the motor for the ambient temperature p0625. For separately-excited synchronous motors: Displays the damping resistance in the rotor direction (d-axis).		
Dependency:	Refer to: p0625		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		
r0375[0...n]	Motor damping resistance, q axis / Mot R_damping_q		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the damping resistance of the separately-excited synchronous motor quadrature to the rotor direction (q axis).		
r0376[0...n]	Rated motor rotor resistance / Mot R_rotor rated		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the rated (nominal) rotor/secondary section resistance of the motor at the rated temperature (sum of p0625 and p0628).		
Dependency:	Refer to: p0628		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		
r0377[0...n]	Motor leakage inductance, total / Mot L_leak total		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 6640
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Induction motor, separately-excited synchronous motor: Displays the stator leakage inductance of the motor including the series inductance (p0353) for servo drives and the motor reactor (p0233) for vector drives. Synchronous motor: Displays the stator quadrature axis inductance including the series inductance (p0353) for servo drives and the motor reactor (p0233) for vector drives.		

r0378[0...n]	Motor stator inductance, d axis / Mot L_stator_d		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the stator longitudinal inductance of the synchronous motor including the series inductance (p0353) and the motor reactor (p0233).		
Note:	The parameter is not used for separately-excited synchronous motors (p0300 = 5).		
r0380[0...n]	Motor damping inductance, d axis / Mot L_damping_d		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the damping inductance of the separately-excited synchronous motor in the rotor direction (d-axis).		
r0381[0...n]	Motor damping inductance, q axis / Mot L_damping_q		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the damping inductance of a separately-excited synchronous motor quadrature to the rotor direction (q axis).		
r0382[0...n]	Motor magnetizing inductance transformed / Lh d axis saturated / Mot Lh t. / Lh d_s		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the magnetizing inductance of the motor. For separately-excited synchronous motors: Displays the saturated magnetizing inductance in the rotor direction (d-axis).		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		
r0383[0...n]	Motor magnetizing inductance q axis, saturated / Mot Lh q_sat		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: 15_1	Unit selection: p0349
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the saturated magnetizing inductance of a separately-excited synchronous motor quadrature to the rotor direction (q axis).		

r0384[0...n]	Motor rotor time constant / damping time constant d axis / Mot T_rot / T_Dd		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 6722
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the rotor time constant. For separately-excited synchronous motors: Displays the damping time constant in the rotor direction (d-axis).		
Note:	The parameter is not used for synchronous motors. The value is calculated from the sum of the inductances on the rotor side (p0358, p0360) divided by the rotor/damping resistance (p0354). The temperature adaptation of the rotor resistance for induction motors is not taken into account.		
r0385[0...n]	Motor damping time constant, q axis / Mot T_Dq		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the damping time constant of a separately-excited synchronous motor quadrature to the rotor direction (q axis).		
Note:	The value is calculated from the sum of the inductances on the damping side (p0359, p0361) divided by the damping resistance (p0355).		
r0386[0...n]	Motor stator leakage time constant / Mot T_stator leak		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the stator leakage time constant.		
Note:	The value is calculated from the sum of all leakage inductances (p0233*, p0353**, p0356, p0358) divided by the sum of all motor resistances (p0350, p0352*, p0354). The temperature adaptation of the resistances is not taken into account. * only applies for VECTOR (r0107). ** only applies for SERVO (r0107).		
r0387[0...n]	Motor stator leakage time constant, q axis / Mot T_Sleak / T_Sq		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the stator leakage time constant quadrature to the rotor direction (q axis).		
Note:	The value is calculated from the sum of all leakage inductances (p0233, p0356, p0359) divided by the sum of all motor resistances (p0350, p0352, p0355). The temperature adaptation of the resistances is not taken into account.		

p0389[0...n]	Motor no-load excitation current / Mot I_exc_no-load		
VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 6727
	P-Group: Motor		Unit selection: -
	Min 0.00 [A]	Max 10000.00 [A]	Factory setting 0.00 [A]
Description:	Sets the excitation no-load current I_F0		
p0390[0...n]	Motor rated excitation current / Mot I_exc_rated		
VECTOR	Can be changed: C2(1, 3)	Dynamic index: MDS, p0130	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 6727
	P-Group: Motor		Unit selection: -
	Min 0.00 [A]	Max 10000.00 [A]	Factory setting 0.00 [A]
Description:	Sets the excitation rated current I_F.		
p0391[0...n]	Current controller adaptation, lower starting point / I_adapt pt. lower		
SERVO	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5714
	P-Group: Motor		Unit selection: -
	Min 0.00 [Aeff]	Max 6000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the lower starting point of the current-dependent current controller adaptation.		
Dependency:	Refer to: p0392, p0393, p1715		
Note:	For p0393 = 100 %, the current controller adaptation is disabled and p1715 is effective over the entire range. The parameter is automatically preset for motors from the motor list (p0301).		
p0392[0...n]	Current controller adaptation, upper starting point / I_adapt pt. upper		
SERVO	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5714
	P-Group: Motor		Unit selection: -
	Min 0.00 [Aeff]	Max 6000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the upper starting point of the current-dependent current controller adaptation.		
Dependency:	Refer to: p0391, p0393, p1715		
Note:	For p0393 = 100 %, the current controller adaptation is disabled and p1715 is effective over the entire range. The parameter is automatically preset for motors from the motor list (p0301).		
p0393[0...n]	Current controller adaptation, P gain, scaling upper / I_adapt Kp upper		
SERVO	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5714
	P-Group: Motor		Unit selection: -
	Min 0.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the factor for the current controller P gain after the adaptation range (currents greater than p0392). The value is referred to p1715.		
Dependency:	Refer to: p0391, p0392, p1715		
Note:	For p0393 = 100 %, the current controller adaptation is disabled and p1715 is effective over the entire range. The parameter is automatically preset for motors from the motor list (p0301).		

r0395[0...n]	Stator resistance, actual / R_stator active		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 6300, 6730, 6731
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the actual stator resistance (phase value). The parameter is influenced by the temperature model and includes the temperature-independent cable resistance.		
r0396[0...n]	Rotor resistance, actual / R_rotor active		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 6730
	P-Group: Motor	Units group: 16_1	Unit selection: p0349
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the actual rotor/secondary section resistance (phase value). The parameter is influenced by the temperature model.		
Note:	This parameter is not used for synchronous motors (p0300 = 2xx).		

p0400[0...n]	Enc type selection / Enc type selection		Access level: 1
SERVO, VECTOR	Can be changed: C2(1, 4)	Dynamic index: EDS, p0140	Function diagram: 1580, 4704
	Data type: Integer16		Unit selection: -
	P-Group: Encoder	Units group: -	Factory setting 0
	Min 0	Max 10000	
Description:	Selects the encoder from the list of encoder types supported.		
Values:	0: No encoder 1001: Resolver 1 speed 1002: Resolver 2 speed 1003: Resolver 3 speed 1004: Resolver 4 speed 2001: 2048, 1 Vpp, A/B C/D R 2002: 2048, 1 Vpp, A/B R 2003: 256, 1 Vpp, A/B R 2004: 400, 1 Vpp, A/B R 2005: 512, 1 Vpp, A/B R 2010: 18000, 1 Vpp, A/B R distance-coded 2050: Encoder with EnDat interface identified 2051: 2048, 1 Vpp, A/B, EnDat, Multiturn 4096 2052: 32, 1 Vpp, A/B, EnDat, Multiturn 4096 2053: 512, 1 Vpp, A/B, EnDat, Multiturn 4096 2054: 16, 1 Vpp, A/B, EnDat, Multiturn 4096 2055: 2048, 1 Vpp, A/B, EnDat, Singleturn 2081: 2048, 1 Vpp, A/B, SSI, Singleturn 2082: 2048, 1 Vpp, A/B, SSI, Multiturn 4096 2110: 4000 nm, 1 Vpp, A/B R distance-coded 2111: 20000 nm, 1 Vpp, A/B R distance-coded 2112: 40000 nm, 1 Vpp, A/B R distance-coded 2151: 16000 nm, 1 Vpp, A/B, EnDat, resolution 100 nm 3001: 1024 HTL A/B R 3002: 1024 TTL A/B R 3003: 2048 HTL A/B R 3005: 1024 HTL A/B 3006: 1024 TTL A/B 3007: 2048 HTL A/B 3008: 2048 TTL A/B 3009: 1024 HTL A/B unipolar 3011: 2048 HTL A/B unipolar 3020: 2048 TTL A/B R, with sense 3081: SSI, Singleturn, 24 V 3082: SSI, Multiturn 4096, 24 V 3090: 4096, HTL, A/B, SSI, Singleturn 9999: User-defined 10000: Identify encoder		
Notice:	A list of motor/encoder codes can be found in the following literature: SINAMICS S120 Commissioning Manual		
Note:	The connected encoder can be identified by p0400 = 10000. This means that the encoder must support this and is possible in the following cases: Motor with DRIVE-CLiQ, encoder with EnDat interface. If an identification is not possible, then p0400 is set to 0. The encoder data (e.g. pulse number p0408) can only be changed when p0400 = 9999. Using p0400 = 20000, the encoder type can be selected from the list of OEM encoders using p0401.		

p0401[0...n]	Encoder type, OEM selection / Enc type OEM sel			
SERVO, VECTOR	Can be changed: C2(1, 4)			Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140		Function diagram: 1580, 4704
	P-Group: Encoder	Units group: -		Unit selection: -
	Min 0	Max 32767		Factory setting 0
Description:	Selects the encoder from the list of encoder types that the OEM supports.			
Note:	The connected encoder can be identified by p0400 = 10000. This means that the encoder must support this and is possible in the following cases: Motor with DRIVE-CLiQ, encoder with EnDat interface. If an identification is not possible, then p0400 is set to 0. The encoder data (e.g. pulse number p0408) can only be changed when p0400 = 9999. Using p0400 = 20000, the encoder type can be selected from the list of OEM encoders using p0401.			
p0402[0...n]	Gearbox type selection / Gearbox type			
SERVO, VECTOR	Can be changed: C2(1, 4)			Access level: 1
	Data type: Integer16	Dynamic index: EDS, p0140		Function diagram: -
	P-Group: Encoder	Units group: -		Unit selection: -
	Min 1	Max 10000		Factory setting 1
Description:	Selects the gearbox from the list of gearbox types that are actually supported.			
Values:	1: 1:1 not inverted 2: 3.5:1 inverted 3: 4.25:1 inverted 9999: User-defined 10000: Identify gearbox			
Note:	The gearbox used can be identified by p0402 = 10000. This means that the encoder must support this and is possible in the following cases: Motor with DRIVE-CLiQ. If an identification is not possible, then p0402 is set to 1.			
p0404[0...n]	Encoder configuration effective / Enc_config eff			
SERVO, VECTOR	Can be changed: C2(4)			Access level: 3
	Data type: Unsigned32	Dynamic index: EDS, p0140		Function diagram: 4704
	P-Group: Encoder	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Settings for the basic encoder properties.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Linear encoder	Yes	No
	01	Abs value encoder	Yes	No
	02	Multiturn encoder	Yes	No
	03	Track A/B sq-wave	Yes	No
	04	Track A/B sinus	Yes	No
	05	Track C/D	Yes	No
	06	Hall sensor	Yes	No
	08	EnDat encoder	Yes	No
				FP
				-
				-
				-
				-
				-
				-
				-

09	SSI encoder	Yes	No	-
12	Equidistant zero mark	Yes	No	-
13	Irregular zero mark	Yes	No	-
14	Distance-coded zero mark	Yes	No	-
15	Commutation with zero mark	Yes	No	-
16	Acceleration	Yes	No	-
20	Voltage level 5 V	Yes	No	-
21	Voltage level 24 V	Yes	No	-
22	Remote sense (only SMC30)	Yes	No	-
23	Resolver excit.	Yes	No	-

Note:

ZM: Zero mark

SMC: Sensor Module Cabinet

If a technique to determine the commutation information/data has not been selected (e.g. track C/D, Hall sensor), and the encoder pulse number is an integer multiple of the pole number, then the following applies:

The track A/B is adjusted to match the magnetic position of the motor.

Re bit 1, 2 (absolute encoder, multi-turn encoder):

These bits can only be selected for EnDat or SSI encoders.

Re bit 12 (equidistant zero mark):

The zero marks occur at regular intervals (e.g. rotary encoder with 1 zero mark per revolution). The bit activates the monitoring of the zero mark clearance (p0425).

Re bit 13 (irregular zero mark):

The zero marks occur at irregular intervals (e.g. a linear scale with only 1 zero mark in the traversing range). The zero mark clearance is not monitored.

Re bit 14 (clearance-coded zero mark):

The distance (clearance) between two or several consecutive zero marks allows the absolute position to be calculated.

Re bit 15 (commutation with zero mark):

For clearance-coded zero marks, the following applies:

The phase sequence of the Hall signal (if available) must be the same as the phase sequence of the encoder.

The fine synchronization is only started after two zero marks have been passed.

p0405[0...n] Square-wave encoder track A/B / Sq-wave enc A/B

SERVO, VECTOR

Can be changed: C2(4)**Access level:** 3**Data type:** Unsigned32**Dynamic index:** EDS, p0140**Function diagram:** 4704**P-Group:** Encoder**Units group:** -**Unit selection:** -**Min****Max****Factory setting**

-

-

1111 bin

Description:

Settings for the track A/B of a square-wave encoder. For square-wave encoders, p0404.3 must also be 1.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Signal	Bipolar	Unipolar	-
01	Level	TTL	HTL	-
02	Track monitoring	A/B <> -A/B	None	-
03	Zero pulse	Same as A/B track	24 V unipolar	-

p0407[0...n] Linear encoder grid division / Enc grid div

SERVO, VECTOR

Can be changed: C2(4)**Access level:** 3**Data type:** Unsigned32**Dynamic index:** EDS, p0140**Function diagram:** 4010, 4704**P-Group:** Encoder**Units group:** -**Unit selection:** -**Min****Max****Factory setting**

0 [nm]

250000000 [nm]

16000 [nm]


Description:

Sets the grid division for a linear encoder.

Note:

The lowest permissible value is 250 nm.

p0408[0...n]	Rotary encoder pulse No. / Rot enc pulse No.			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: 4010, 4704	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 0	Max 16777215	Factory setting 2048	
Description:	Sets the number of pulses for a rotary encoder.			
Note:	The number of pole pairs for a resolver is entered here. The smallest permissible value is 1 pulse.			
p0408	Rotary encoder pulse No. / Rot enc pulse No.			
TM41	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9674, 9676	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 1000	Max 8192	Factory setting 2048	
Description:	Sets the number of pulses for a rotary encoder.			
p0410[0...n]	Encoder inversion actual value / Enc inv act value			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Setting to invert actual values.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Invert speed actual value	Yes	No
	01	Invert position actual value	Yes	No
				FP 4710, 4715 4704
Note:	The inversion influences the following parameters: Bit 00: r0061, r0063 (exception: sensorless control), r0094 Bit 01: r0482, r0483			
p0411[0...n]	Measuring gearbox, configuration / Config			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 1	
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Sets the configuration for position tracking of a measuring gearbox.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Measuring gearbox, activate position tracking	Yes	No
	02	Measuring gearbox, reset position	Yes	No
				FP -
Note:	For the following events, the non-volatile, saved position values are automatically reset: - when an encoder replacement has been identified. - when changing the configuration of the Encoder Data Set (EDS).			

p0413[0...n]		Measuring gearbox, position tracking tolerance window / Pos track window		
SERVO, VECTOR	Can be changed: C2(4)			Access level: 3
	Data type: Unsigned32	Dynamic index: EDS, p0140		Function diagram: -
	P-Group: Encoder	Units group: -		Unit selection: -
	Min 0	Max 4294967295		Factory setting 0
Description:	Sets a tolerance window for position tracking. After the system is powered-up, the difference between the saved position and the actual position is determined, and depending on this, the following is initiated: Difference within the tolerance window --> The position is reproduced as a result of the encoder actual value. Difference outside the tolerance window --> An appropriate message is output.			
Dependency:	Refer to: F31501, F32501, F33501			
Caution:	Rotation, e.g. through a complete encoder range is not detected.			
				
Note:	For p0411.0 = 1, the value is automatically pre-assigned half the encoder range. Example: Half the encoder range = (p0408 * p0421) / 2			

p0418[0...n]		Fine resolution Gx_XIST1 (in bits) / Enc fine Gx_XIST1		
SERVO, VECTOR	Can be changed: C2(4)			Access level: 3
	Data type: Unsigned8	Dynamic index: EDS, p0140		Function diagram: 4010, 4704
	P-Group: Encoder	Units group: -		Unit selection: -
	Min 2	Max 18		Factory setting 11
Description:	Sets the fine resolution in bits of the incremental position actual values.			
Note:	The parameter applies for the following process data: - Gx_XIST1 - Gx_XIST2 for reference mark or flying measurement			

p0418		Fine resolution Gx_XIST1 (in bits) / Enc fine Gx_XIST1		
TM41	Can be changed: C2(4)			Access level: 3
	Data type: Unsigned8	Dynamic index: -		Function diagram: 9674, 9676
	P-Group: Encoder	Units group: -		Unit selection: -
	Min 2	Max 18		Factory setting 11
Description:	Sets the fine resolution in bits of the incremental position actual values.			

p0419[0...n]		Fine resolution absolute value Gx_XIST2 (in bits) / Enc fine Gx_XIST2		
SERVO, VECTOR	Can be changed: C2(4)			Access level: 3
	Data type: Unsigned8	Dynamic index: EDS, p0140		Function diagram: 4704
	P-Group: Encoder	Units group: -		Unit selection: -
	Min 2	Max 18		Factory setting 9
Description:	Sets the fine resolution in bits of the absolute position actual values.			
Note:	This parameter applies to process data Gx_XIST2 when reading the absolute value.			

p0420[0...n]	Encoder connection / Encoder connection			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Selecting the encoder connection.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	SUB-D	Yes	No
	01	Terminal	Yes	No
				FP
				-
				-
p0421[0...n]	Absolute encoder rotary multi-turn resolution / Enc abs multiturn			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: 4704	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 0	Max 65535	Factory setting 4096	
Description:	Sets the number of rotations that can be resolved for a rotary absolute encoder.			
p0422[0...n]	Absolute encoder linear measuring step resolution / Enc abs meas step			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: 4704	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 0 [nm]	Max 4294967295 [nm]	Factory setting 100 [nm]	
Description:	Sets the resolution of the absolute position for a linear absolute encoder.			
Note:	The serial protocol of an absolute encoder provides the position with a certain resolution , e.g. 100 nm. This value must be entered here.			
p0423[0...n]	Absolute encoder rotary single-turn resolution / Enc abs singleturn			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: 4704	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 0	Max 1073741823	Factory setting 8192	
Description:	Sets the number of measuring steps per revolution for a rotary absolute encoder. The resolution refers to the absolute position.			
p0424[0...n]	Encoder, linear zero mark distance / Enc lin ZM_dist			
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3	
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 0 [mm]	Max 65535 [mm]	Factory setting 20 [mm]	
Description:	Sets the distance between two zero marks for a linear encoder. This information is used for zero mark monitoring.			
Note:	For distance-coded zero marks, this means the basic distance.			

p0425[0...n]	Encoder, rotary zero mark distance / Enc rot dist ZM		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: 4704, 8570
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 16777215	Factory setting 2048
Description:	Sets the distance in pulses between two zero marks for a rotary encoder. This information is used for zero mark monitoring.		
Note:	For distance-coded zero marks, this means the basic distance.		

p0427[0...n]	Encoder SSI baud rate / Enc SSI baud rate		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Floating Point	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0 [kHz]	Max 65535 [kHz]	Factory setting 100 [kHz]
Description:	Sets the baud rate for an SSI encoder.		
Note:	SSI: Synchronous Serial Interface		

p0428[0...n]	Encoder SSI monoflop time / Enc SSI t_monoflop		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0 [μ s]	Max 65535 [μ s]	Factory setting 30 [μ s]
Description:	Sets the minimum delay time between two data transfers of the absolute value for an SSI encoder.		

p0429[0...n]	Encoder SSI configuration / Enc SSI config				
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3		
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -		
	P-Group: Encoder	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Sets the configuration for an SSI encoder.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Transfer code	Binary code	Gray code	-
	02	Transfer absolute value twice	Yes	No	-
	06	Data line during the monoflop time	High level	Low level	-
Note:	Re bit 06: The quiescent signal level of the data line corresponds to the inverted, set level.				

p0430[0...n] Sensor Module configuration / SM config

SERVO, VECTOR	Can be changed: C2(4)	Dynamic index: EDS, p0140	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min -	Max -	Factory setting 1110 0000 0000 1000 0000 0000 0000 0000 bin

Description: Sets the configuration of the Sensor Module.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	17	Burst oversampling	Yes	No	-
	19	Safety position actual value sensing	Yes	No	-
	20	Speed calculation mode (only SMC30)	Incremental diff	Flank time meas	-
	21	Zero mark tolerance	Yes	No	-
	29	Phase correction	Yes	No	-
	30	Amplitude correction	Yes	No	-
	31	Offset correction	Yes	No	-

p0431[0...n] Angular commutation offset / Ang_com offset

SERVO, VECTOR	Can be changed: C2(4)	Dynamic index: EDS, p0140	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min -180.00 [°]	Max 180.00 [°]	Factory setting 0.00 [°]

Description: Sets the angular commutation offset.

Dependency: The value is taken into account in r0094.
Refer to: r0094, r1778

Notice: The angular commutation offset cannot be generally taken from other drive systems. As a minimum - the sign of the offset determined for SIMODRIVE 611 digital and SIMODRIVE 611 universal must be reversed for SINAMICS (p0431 (SINAMICS) = -p1016 (SIMODRIVE)).

Note: For p0404.5 = 1 (track C/D) the following applies:
The angular offset in p0431 acts on track A/B, the zero mark on track C/D.
For p0404.6 = 1 (Hall sensor) the following applies:
The angular offset in p0431 acts on track A/B and the zero mark.

p0432[0...n] Gearbox factor, encoder revolutions / Grbx_fact enc_rev

SERVO, VECTOR	Can be changed: C2(4)	Dynamic index: EDS, p0140	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min 1	Max 10000	Factory setting 1

Description: Sets the encoder revolutions for the gearbox factor of the encoder evaluation.
The gearbox factor specifies the ratio between the encoder shaft and motor shaft (for motor encoders) or between the encoder shaft and the load.

Dependency: Refer to: p0402, p0410, p0433

Note: Negative gearbox factors should be implemented with p0410.

p0433[0...n]	Gearbox factor, motor/load revolutions / Grbx_fact mot_rev		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Integer16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 1	Max 10000	Factory setting 1
Description:	Sets the motor and load revolutions for the gearbox factor of the encoder evaluation. The gearbox factor specifies the ratio between the encoder shaft and motor shaft (for motor encoders) or between the encoder shaft and the load.		
Dependency:	Refer to: p0402, p0410, p0432		
Note:	Negative gearbox factors should be implemented with p0410.		
p0434[0...n]	Encoder SSI error bit / Enc SSI error bit		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the position and level of the error bit in the SSI protocol.		
Notice:	The bit may only be positioned before (p0446) or after (p0448) the absolute value in the SSI protocol.		
Note:	Value = dcba ba: Position of the error bit in the protocol (0 ... 63). c: Level (0: Low level, 1: High level). d: State of the evaluation (0: Off, 1: On). Example: p0434 = 1013 --> The evaluation is switched-in and the error bit is at position 13 with a low level. p0434 = 1113 --> The evaluation is switched-in and the error bit is at position 13 with a high level.		
p0435[0...n]	Encoder SSI alarm bit / Enc SSI alarm bit		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the position and level of the alarm bit in the SSI protocol.		
Notice:	The bit may only be positioned before (p0446) or after (p0448) the absolute value in the SSI protocol.		
Note:	Value = dcba ba: Position of the alarm bit in protocol (0 ... 63). c: Level (0: Low level, 1: High level). d: State of the evaluation (0: Off, 1: On). Example: p0435 = 1014 --> The evaluation is switched-in and the alarm bit is at position 14 with a low level. p0435 = 1114 --> The evaluation is switched-in and the alarm bit is at position 14 with a high level.		

p0436[0...n]	Encoder SSI parity bit / Enc SSI parity bit		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the position and parity of the parity bit in the SSI protocol.		
Notice:	The bit may only be positioned before (p0446) or after (p0448) the absolute value in the SSI protocol.		
Note:	Value = dcba ba: Position of the parity bit in the protocol (0 ... 63). c: Parity (0: even, 1: uneven). d: State of the evaluation (0: Off, 1: On). Example: p0436 = 1015 --> The evaluation is switched-in and the parity bit is at position 15 with even parity. p0436 = 1115 --> The evaluation is switched-in and the parity bit is at position 15 with uneven parity.		
p0440[0...n]	Copy encoder serial number / Copy enc ser_no		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Integer16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0000 hex	Max 0001 hex	Factory setting 0000 hex
Description:	Copies the actual serial number of the encoder belong to this encoder data set to p0441 ... p0445. Example: For p0440[0] = 1, the serial number of the encoder belonging EDS0 is copied to p0441[0] ... p0445[0].		
Values:	0: No action 1: Transfer serial number		
Dependency:	Refer to: p0441, p0442, p0443, p0444, p0445, r0460, r0461, r0462, r0463, r0464, p1990		
Note:	For encoders with serial number, encoder replacement is monitored in order to request angular commutation calibration (adjustment) for motor encoders and absolute calibration for direct measuring systems with absolute value data. The serial number, which from then onwards is used for monitoring purposes, can be transferred using p0440. In the following cases, copying is automatically started in the following cases: 1.) When commissioning 1FT6, 1FK6, 1FK7 motors. 2.) When writing into p0431. 3.) For p1990 = 1. p0440 is automatically set to 0 when the copying has been completed. In order to permanently accept the copied values, it is necessary to save in a non-volatile fashion (p0977).		
p0441[0...n]	Encoder commissioning serial number part 1 / Enc comm ser_no 1		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 4
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Serial number part 1 of the encoder for the commissioning.		
Dependency:	Refer to: p0440, p0442, p0443, p0444, p0445, r0460, r0461, r0462, r0463, r0464 Refer to: F07414		
Note:	A value of zero is displayed if an encoder is not present.		

p0442[0...n]	Encoder commissioning serial number part 2 / Enc comm ser_no 2		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 4
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Serial number part 2 of the encoder for the commissioning.		
Dependency:	Refer to: p0440, p0441, p0443, p0444, p0445, r0460, r0461, r0462, r0463, r0464 Refer to: F07414		
Note:	A value of zero is displayed if an encoder is not present.		
p0443[0...n]	Encoder commissioning serial number part 3 / Enc comm ser_no 3		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 4
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Serial number part 3 of the encoder for the commissioning.		
Dependency:	Refer to: p0440, p0441, p0442, p0444, p0445, r0460, r0461, r0462, r0463, r0464 Refer to: F07414		
Note:	A value of zero is displayed if an encoder is not present.		
p0444[0...n]	Encoder commissioning serial number part 4 / Enc comm ser_no 4		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 4
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Serial number part 4 of the encoder for the commissioning.		
Dependency:	Refer to: p0440, p0441, p0442, p0443, p0445, r0460, r0461, r0462, r0463, r0464 Refer to: F07414		
Note:	A value of zero is displayed if an encoder is not present.		
p0445[0...n]	Encoder commissioning serial number part 5 / Enc comm ser_no 5		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 4
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Serial number part 5 of the encoder for the commissioning.		
Dependency:	Refer to: p0440, p0441, p0442, p0443, p0444, r0460, r0461, r0462, r0463, r0464 Refer to: F07414		
Note:	A value of zero is displayed if an encoder is not present.		

p0446[0...n]	Encoder SSI number of bits before the absolute value / Enc SSI bit before		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the number of bits before the absolute value in the SSI protocol.		
Note:	For example, error bit, alarm bit or parity bit can be positioned at these bits.		
p0447[0...n]	Encoder SSI number of bits absolute value / Enc SSI bit val		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 25
Description:	Sets the number of bits for the absolute value in the SSI protocol.		
p0448[0...n]	Encoder SSI number of bits after the absolute value / Enc SSI bit after		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the number of bits after the absolute value in the SSI protocol.		
Note:	For example, error bit, alarm bit or parity bit can be positioned at these bits.		
p0449[0...n]	Encoder SSI number of bits, filler bits / Enc SSI fill bits		
SERVO, VECTOR	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: EDS, p0140	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 1
Description:	Sets the number of filler bits for double absolute value transfer in the SSI protocol.		
Dependency:	Refer to: p0429		
Note:	This parameter is only of significance for p0429.2 = 1.		
r0451[0...2]	Commutation angle factor / Enc commut_factor		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 4710
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the relationship between the electrical and mechanical pole positions.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
Note:	A value of zero is displayed if an encoder is not present.		

r0455[0...2] Encoder configuration recognized / Enc config act

SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Displays the detected encoder configuration.
In this case, the encoder must automatically support the function (e.g. encoder with EnDat interface).

Index:
[0] = Encoder 1
[1] = Encoder 2
[2] = Encoder 3

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Linear encoder	Yes	No	-
	01	Abs value encoder	Yes	No	-
	02	Multiturn encoder	Yes	No	-
	03	Track A/B sq-wave	Yes	No	-
	04	Track A/B sinus	Yes	No	-
	05	Track C/D	Yes	No	-
	06	Hall sensor	Yes	No	-
	08	EnDat encoder	Yes	No	-
	09	SSI encoder	Yes	No	-
	12	Equidistant zero mark	Yes	No	-
	13	Irregular zero mark	Yes	No	-
	14	Distance-coded zero mark	Yes	No	-
	15	Commutation with zero mark	Yes	No	-
	16	Acceleration	Yes	No	-
	20	Voltage level 5 V	Yes	No	-
	21	Voltage level 24 V	Yes	No	-
	22	Remote sense (only SMC30)	Yes	No	-
	23	Resolver excit.	Yes	No	-

Dependency: Refer to: p0404

Note: ZM: Zero mark
This parameter is only used for diagnostics.
A value of zero is displayed if an encoder is not present.

r0456[0...2] Encoder configuration supported / Enc config supp

SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Contains the encoder configuration supported by the Sensor Module.

Index:
[0] = Encoder 1
[1] = Encoder 2
[2] = Encoder 3

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Linear encoder	Yes	No	-
	01	Abs value encoder	Yes	No	-
	02	Multiturn encoder	Yes	No	-
	03	Track A/B sq-wave	Yes	No	-
	04	Track A/B sinus	Yes	No	-
	05	Track C/D	Yes	No	-
	06	Hall sensor	Yes	No	-
	08	EnDat encoder	Yes	No	-

09	SSI encoder	Yes	No	-
12	Equidistant zero mark	Yes	No	-
13	Irregular zero mark	Yes	No	-
14	Distance-coded zero mark	Yes	No	-
15	Commutation with zero mark	Yes	No	-
16	Acceleration	Yes	No	-
20	Voltage level 5 V	Yes	No	-
21	Voltage level 24 V	Yes	No	-
22	Remote sense (only SMC30)	Yes	No	-
23	Resolver excit.	Yes	No	-

Dependency: Refer to: p0404
Note: ZM: Zero mark
 This parameter is only used for diagnostics.
 A value of zero is displayed if an encoder is not present.

r0458[0...2] Sensor Module properties / SM properties

SERVO, VECTOR **Can be changed:** - **Access level:** 3
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 4704
P-Group: Encoder **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Sets the Sensor Module configuration.

Index: [0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Encoder data available	Yes	No	-
	01	Motor data available	Yes	No	-
	02	KTY84 connection available	Yes	No	-
	03	PTC connection available	Yes	No	-
	04	Module temperature available	Yes	No	-
	05	Absolute encoder p0408/p0421, no power of 2	Yes	No	-
	06	Encoder module permits parking/unparking	Yes	No	-
	07	Hall sensor can be combined with actual value inversion	Yes	No	-
	08	External temperature evaluation being used	Yes	No	-
	09	Encoder fault and its associated information available	Yes	No	-
	10	Speed diagnostics in the sensor module	Yes	No	-
	16	Pole position identification	Yes	No	-
	17	Burst oversampling	Yes	No	-
	19	Safety position actual value sensing	Yes	No	-
	20	Extended speed calculation being used (only SMC30)	Yes	No	-
	21	Zero mark tolerance	Yes	No	-
	29	Phase correction	Yes	No	-
	30	Amplitude correction	Yes	No	-
	31	Offset correction	Yes	No	-

Dependency: Refer to: p0600, p0601
Note: A value of zero is displayed if an encoder is not present.

r0460[0...2] Encoder serial number part 1 / Enc ser_no 1

SERVO, VECTOR **Can be changed:** - **Access level:** 3
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: Encoder **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - -

Description: Displays the actual serial number part 1 of the appropriate encoder.
Index: [0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3
Dependency: Refer to: p0441, p0442, p0443, p0444, p0445, r0461, r0462, r0463, r0464

r0461[0...2] Encoder serial number part 2 / Enc ser_no 2

SERVO, VECTOR **Can be changed:** - **Access level:** 3
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: Encoder **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - -

Description: Displays the actual serial number part 2 of the appropriate encoder.
Index: [0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3
Dependency: Refer to: p0441, p0442, p0443, p0444, p0445, r0460, r0462, r0463, r0464

r0462[0...2] Encoder serial number part 3 / Enc ser_no 3

SERVO, VECTOR **Can be changed:** - **Access level:** 3
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: Encoder **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - -

Description: Displays the actual serial number part 3 of the appropriate encoder.
Index: [0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3
Dependency: Refer to: p0441, p0442, p0443, p0444, p0445, r0460, r0461, r0463, r0464

r0463[0...2] Encoder serial number part 4 / Enc ser_no 4

SERVO, VECTOR **Can be changed:** - **Access level:** 3
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: Encoder **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - -

Description: Displays the actual serial number part 4 of the appropriate encoder.
Index: [0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3
Dependency: Refer to: p0441, p0442, p0443, p0444, p0445, r0460, r0461, r0462, r0464

r0464[0...2]	Encoder serial number part 5 / Enc ser_no 5		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual serial number part 5 of the appropriate encoder.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
Dependency:	Refer to: p0441, p0442, p0443, p0444, p0445, r0460, r0461, r0462, r0463		
r0479[0...2]	CO: Diagnostics encoder position actual value Gn_XIST1 / Diag Gn_XIST1		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the encoder actual position value Gn_XIST1 according to PROFIdrive for diagnostics. In contrast to p0482, the value is updated in each DRIVE-CLiQ basic clock cycle and displayed with sign.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
r0479	CO: Diagnostics encoder position actual value Gn_XIST1 / Diag Gn_XIST1		
TM41	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: 9674
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the encoder actual position value Gn_XIST1 according to PROFIdrive for diagnostics. In contrast to p0482, the value is updated in each DRIVE-CLiQ basic clock cycle and displayed with sign.		
p0480[0...2]	CI: Signal source for encoder control word Gn_STW / Enc S_src Gn_STW		
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1580, 4720
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the encoder control word Gn_STW according to PROFIdrive.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		

r0481[0...2]	CO: Encoder status word Gn_ZSW / Enc Gn_ZSW		
SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: 4010, 4704, 4730
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Displays the encoder status word Gn_ZSW according to PROFIdrive.

Index:
 [0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Function 1 active	Yes	No	-
	01	Function 2 active	Yes	No	-
	02	Function 3 active	Yes	No	-
	03	Function 4 active	Yes	No	-
	04	Value 1	Displayed in r0483	Does not exist	-
	05	Value 2	Displayed in r0483	Does not exist	-
	06	Value 3	Displayed in r0483	Does not exist	-
	07	Value 4	Displayed in r0483	Does not exist	-
	08	Measuring probe 1 deflected	Yes	No	-
	09	Measuring probe 2 deflected	Yes	No	-
	11	Encoder fault acknowledge active	Yes	No	-
	13	Absolute value cyclically	Displayed in r0483	No	-
	14	Parking encoder active	Yes	No	-
	15	Encoder fault	Displayed in r0483	None	-

r0481	CO: Encoder status word Gn_ZSW / Enc Gn_ZSW		
TM41	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Displays the encoder status word Gn_ZSW according to PROFIdrive.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Function 1 active	Yes	No	-
	01	Function 2 active	Yes	No	-
	02	Function 3 active	Yes	No	-
	03	Function 4 active	Yes	No	-
	04	Value 1	Displayed in r0483	Does not exist	-
	05	Value 2	Displayed in r0483	Does not exist	-
	06	Value 3	Displayed in r0483	Does not exist	-
	07	Value 4	Displayed in r0483	Does not exist	-
	08	Measuring probe 1 deflected	Yes	No	-
	09	Measuring probe 2 deflected	Yes	No	-
	11	Encoder fault acknowledge active	Yes	No	-
	13	Absolute value cyclically	Displayed in r0483	No	-
	14	Parking encoder active	Yes	No	-
	15	Encoder fault	Displayed in r0483	None	-

Note: For p4401 = 0, the following applies:
 For Terminal Module 41 (TM41), this value is used to interconnect with standard telegram 3 and is always zero.
 For p4401 = 1, the following applies:
 r0481.0 indicates as to whether the zero mark synchronization is active.
 r0481.4 indicates whether the zero mark of the incremental encoder was found.
 r0481.14 indicates whether the output of track A/B is activated.

r0482[0...2]	CO: Encoder actual position value Gn_XACT1 / Enc Gn_XIST1		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1580, 2450, 3090, 4010, 4704, 4740
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the encoder actual position value Gn_XIST1 according to PROFIdrive.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
Note:	This value is reset when de-selecting the function "parking axis".		
r0482	CO: Encoder actual position value Gn_XACT1 / Enc Gn_XIST1		
TM41	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9674
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the encoder actual position value Gn_XIST1 according to PROFIdrive.		
r0483[0...2]	CO: Encoder actual position value Gn_XACT2 / Enc Gn_XIST2		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1580, 2450, 4704
	P-Group: Encoder	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the encoder actual position value Gn_XIST2 according to PROFIdrive.		
Recommendation:	Possible causes of the error codes: Error code 4097 and 4098: Defective Control Unit hardware. Error codes 4099 and 4100: Too many measuring pulses have occurred.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
Note:	If Gx_ZSW.14 = 0 and GxZSW.15 = 1 (r0481), then an error code with the following significance is located in Gx_XIST2 (r0483): 1: Encoder fault 2: Reserved 3: Reserved 4: Abort, reference mark search 5: Abort, retrieve reference value 6: Abort, flying measurement 7: Abort, retrieve measured value 8: Abort, absolute value transfer 3841: Function not supported 4097: Abort, reference mark search due to an initialization error 4098: Abort, flying measurement due to an initialization error 4099: Abort, reference mark search due to a measuring error 4100: Abort, flying measurement due to a measuring error		

r0483	CO: Encoder actual position value Gn_XACT2 / Enc Gn_XIST2		
TM41	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the encoder actual position value Gn_XIST2 according to PROFIdrive.		
Note:	For Terminal Module 41 (TM41), this value is used to interconnect with standard telegram 3 and is always zero.		
r0484[0...2]	CO: Redundant coarse encoder position + CRC Gn_XIST1 / Enc red pos+CRC		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the redundant coarse encoder position including CRC (Cyclic Redundancy Check). Upper 16 bits: CRC over the redundant coarse encoder position. Lower 16 bits: Redundant coarse encoder position. The count direction is opposite to r0482 (encoder position actual value Gn_XIST1). The value contains 2 bit fine resolution.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
Dependency:	The values are valid when the safety position actual value sensing is activated (p0430.19 = 1). Refer to: p0430		
Note:	This absolute value does not change, contrary to r0482, when de-selecting the function "parking axis".		
r0485[0...2]	CO: Measuring gearbox, encoder raw value incremental / Enc raw val incr		
SERVO, VECTOR	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the raw value of the incremental encoder actual value before the measuring gearbox.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
r0486[0...2]	CO: Measuring gearbox, encoder raw value absolute / Enc raw val abs		
SERVO, VECTOR	Can be changed: -		Access level: 1
	Data type: Signed32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the raw value of the absolute encoder actual value before the measuring gearbox.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		

r0487[0...2]		Diagnostic encoder control word Gn_STW / Enc Gn_STW			
SERVO, VECTOR	Can be changed: -		Access level: 3		
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1580, 4704, 4720, 4740		
	P-Group: Encoder	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the encoder control word Gn_STW according to PROFIdrive for diagnostics.				
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Request function 1	Yes	No	-
	01	Request function 2	Yes	No	-
	02	Request function 3	Yes	No	-
	03	Request function 4	Yes	No	-
	04	Request command bit 0	Yes	No	-
	05	Request command bit 1	Yes	No	-
	06	Request command bit 2	Yes	No	-
	07	Mode flying measurement / search for reference	Flying measurement	Reference marks	-
	13	Request absolute value cyclic	Yes	No	-
	14	Request parking encoder	Yes	No	-
	15	Request acknowledge encoder fault	Yes	No	-
Note:	The signal source for the encoder control word is set with p0480.				

p0488[0...2]		Measuring probe 1 input terminal / Meas probe 1 input		
SERVO, VECTOR	Can be changed: U, T		Access level: 3	
	Data type: Integer16	Dynamic index: -	Function diagram: 4740	
	P-Group: Encoder	Units group: -	Unit selection: -	
	Min 0	Max 6	Factory setting 0	
Description:	Sets the input terminal to connect probe 1.			
Values:	0: No meas probe 1: DI/DO 9 (X122.8/X121.8) 2: DI/DO 10 (X122.10/X121.10) 3: DI/DO 11 (X122.11/X121.11) 4: DI/DO 13 (X132.8) 5: DI/DO 14 (X132.10) 6: DI/DO 15 (X132.11)			
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3			
Dependency:	Refer to: p0489, p0490, p0728			
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.			
Note:	DI/DO: Bidirectional Digital Input/Output The terminal must be set as input (p0728). Refer to the encoder interface for PROFIdrive.			

p0489[0...2]		Measuring probe 2 input terminal / Meas probe 2 input			
SERVO, VECTOR	Can be changed: U, T			Access level: 3	
	Data type: Integer16	Dynamic index: -		Function diagram: 4740	
	P-Group: Encoder	Units group: -		Unit selection: -	
	Min 0	Max 6		Factory setting 0	
Description:	Sets the input terminal to connect probe 2.				
Values:	0: No meas probe 1: DI/DO 9 (X122.8/X121.8) 2: DI/DO 10 (X122.10/X121.10) 3: DI/DO 11 (X122.11/X121.11) 4: DI/DO 13 (X132.8) 5: DI/DO 14 (X132.10) 6: DI/DO 15 (X132.11)				
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3				
Dependency:	Refer to: p0488, p0490, p0728				
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.				
Note:	DI/DO: Bidirectional Digital Input/Output The terminal must be set as input (p0728). Refer to the encoder interface for PROFIdrive.				
p0490		Invert measuring probe or equivalent zero mark / Meas. probe invert			
CU_S	Can be changed: U, T			Access level: 3	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 4740	
	P-Group: Encoder	Units group: -		Unit selection: -	
	Min -	Max -		Factory setting 0000 bin	
Description:	Setting to invert the digital input signals to connect a measuring probe or an equivalent zero mark.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	09	DI/DO 9 (X122.8/X121.8)	Inverted	Not inverted	-
	10	DI/DO 10 (X122.10/X121.10)	Inverted	Not inverted	-
	11	DI/DO 11 (X122.11/X121.11)	Inverted	Not inverted	-
	13	DI/DO 13 (X132.8)	Inverted	Not inverted	-
	14	DI/DO 14 (X132.10)	Inverted	Not inverted	-
	15	DI/DO 15 (X132.11)	Inverted	Not inverted	-
Dependency:	Refer to: p0488, p0489, p0495, p0728				
Notice:	To the terminal designation: The second designation is only applicable for CU310.				
Note:	The terminal must be set as input. When the measuring probe or the equivalent zero mark is inverted, this has no effect on the status displays of the digital inputs (r0721, r0722, r0723). DI: Digital input, DO: Digital output				

p0491 Motor encoder fault response ENCODER / Fault resp ENCODER

SERVO	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0

Description: Sets the behavior for the ENCODER fault response (motor encoder).
This means, for example, if an encoder fault occurs, sensorless operation can be automatically selected with a shutdown behavior that can be selected.

Values:

0:	Encoder fault results in OFF2
1:	Enc fault results in sensorless oper. and oper. continues
2:	Encoder fault results in sensorless operation and OFF1
3:	Encoder fault results in sensorless operation and OFF3

Dependency: The following parameters are relevant for sensorless operation.
Refer to: p0341, p0342, p1470, p1472, p1517, p1612, p1755
Refer to: F07575

Note: For a value 1, 2, 3, the following applies:
Encoderless operation must have been commissioned.
Refer to the status display "sensorless operation due to a fault" (BO: r1407.13).
For sensorless operation (p1404 = 0 or p1300 = 20), the following applies:
- The condition must be fulfilled: $p1800 \geq n / (2 * p0115[0])$, $n = 1, 2, \dots$
- For motors with a small power rating (< 300 W) we recommend to set $n \geq 2$.

p0491 Motor encoder fault response ENCODER / Fault resp ENCODER

VECTOR	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0

Description: Sets the behavior for the ENCODER fault response (motor encoder).
This means, for example, if an encoder fault occurs, sensorless operation can be automatically selected with a shutdown behavior that can be selected.

Values:

0:	Encoder fault results in OFF2
1:	Enc fault results in sensorless oper. and oper. continues
2:	Encoder fault results in sensorless operation and OFF1
3:	Encoder fault results in sensorless operation and OFF3

Dependency: The following parameters are relevant for sensorless operation.
Refer to: p0341, p0342, p1470, p1472, p1517, p1612, p1755
Refer to: F07575

Note: For a value 1, 2, 3, the following applies:
Encoderless operation must have been commissioned.
Refer to the status display "sensorless operation due to a fault" (BO: r1407.13).
Not possible for separately excited synchronous motors (p0300 = 5).

p0492	Square-wave encoder, maximum speed difference per sampling cycle / n_dif max/samp_cyc		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 0.0 [1/min]
Description:	Maximum permissible speed difference between two computation cycles when evaluating square-wave encoders. When the value is exceeded, depending on p0491, either sensorless closed-loop speed/torque control is selected or the drive is powered-down.		
Note:	For a value of 0.0, the speed change monitoring is disabled. When half of the parameter value is exceeded, an alarm is already generated and the speed limiting is limited to this. The parameter is only pre-assigned for vector drives when selecting p0340 = 1, 3.		
p0492	Square-wave encoder, max. velocity difference per sampling cycle / v_dif max/samp_cyc		
SERVO (Lin)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Encoder		Unit selection: -
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 0.0 [m/min]
Description:	Maximum permissible velocity difference between two computation cycles when evaluating square-wave encoders. When the value is exceeded, depending on p0491, either a sensorless closed-loop velocity/force control is selected or the drive is powered-down.		
Note:	For a value of 0.0, the velocity change monitoring is disabled. When half of the parameter value is exceeded, an alarm is already generated and the velocity change is limited to this.		
p0495[0...2]	Equivalent zero mark, input terminal / Zero mark input		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: 4735
	P-Group: Encoder		Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Selects the input terminal for connecting an equivalent zero mark (external encoder zero mark).		
Values:	0: No equivalent zero mark (evaluation of the encoder zero mark) 1: DI/DO 9 (X122.8/X121.8) 2: DI/DO 10 (X122.10/X121.10) 3: DI/DO 11 (X122.11/X121.11) 4: DI/DO 13 (X132.8) 5: DI/DO 14 (X132.10) 6: DI/DO 15 (X132.11)		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
Dependency:	Refer to: p0490		
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.		
Note:	Refer to the encoder interface for PROFIdrive. The terminal must be set as input. For p0495 = 0 (factory setting), the encoder zero mark is evaluated as zero mark. For p0495 > 0, the following applies:		

Depending on the direction of motion, the positive or negative edge at the appropriate input is evaluated.

- increasing position actual values (r0482) --> the 0/1 edge is evaluated.

- decreasing position actual values (r0482) --> the 1/0 edge is evaluated.

Only one zero mark is supported. If function 2, 3 or 4 is selected, this results in an error message in Gn_ZSW.

The inversion of the inputs via p0490 affects the function "referencing with equivalent zero mark". This is the reason that the edge evaluation is interchanged as a function of the direction of motion.

An input can only be assigned to one encoder as measuring probe 1, 2 or equivalent zero mark. Exception: The same encoder can be simultaneously used as measuring probe and equivalent zero mark as both functions cannot be simultaneously requested.

p0496[0...2] Encoder diagnostic signal selection / Enc diag selection

SERVO, VECTOR

Can be changed: U, T

Access level: 4

Data type: Integer16

Dynamic index: -

Function diagram: -

P-Group: Encoder

Units group: -

Unit selection: -

Min

Max

Factory setting

0

42

0

Description:

Selects the trace signal to be output in r0497, r0498 and r0499 for encoder diagnostics.

Values:

0: not active
 1: r0497: Mechanical revolution
 10: r0498: Raw value, track A, r0499: Raw value, track B
 11: r0498: Fine position X (-A/2), r0499: Fine position Y (-B/2)
 12: r0498: Fine position Phi, r0499: -
 13: r0498: Offset correction X, r0499: Offset correction Y
 14: r0498: Phase correction X, r0499: Amplitude correction Y
 20: r0498: Raw value, track C, r0499: Raw value, track D
 21: r0498: CD position X (-D/2), r0499: CD position Y (C/2)
 22: r0498: CD position Phi, r0499: CD pos. Phi - mech. revolution
 23: r0497: Zero mark status
 30: r0497: Absolute position serial
 31: r0497: Absolute position, incremental
 32: r0497: Zero mark position
 40: r0498: Raw temperature, r0499: Temperature in 0.1 °C
 41: r0498: Resistance in 0.1 Ohm, r0499: Temperature in 0.1 °C
 42: r0497: Resistance 2500 Ohm

Index:

[0] = Encoder 1
 [1] = Encoder 2
 [2] = Encoder 3

Note:

Re p0496 = 1: 360 ° <--> 2³²
 Re p0496 = 10, 20 (resolver): 2900 mV <--> 26214 dec
 Re p0496 = 10, 20 (sin/cos 1 Vpp, EnDat): 500 mV <--> 21299 dec
 Re p0496 = 11, 21 (resolver): 2900 mV <--> 13107 dec, internal processor offset is corrected
 Re p0496 = 13 (resolver): 2900 mV <--> 13107 dec
 Re p0496 = 11, 21 (sin/cos 1 Vpp, EnDat): 500 mV <--> 10650 dec, internal processor offset is corrected
 Re p0496 = 13 (sin/cos 1 Vpp, EnDat): 500 mV <--> 10650 dec
 Re p0496 = 12: 180 ° fine position <--> 32768 dec
 Re p0496 = 14: 100 % <--> 16384 dec
 Re p0496 = 22: 180 ° <--> 32768 dec
 Re p0496 = 23: Encoder zero mark <--> MSB set (detected during the zero mark or at least 1 current controller clock cycle)
 Re p0496 = 30: Rotary: 1 single-turn measuring step <--> 1 dec, linear: 1 measuring step <--> 1 dec
 Re p0496 = 31: Absolute position, incremental in 1/4 encoder pulses
 Re p0496 = 32: Zero mark position in 1/4 encoder pulses
 Re p0496 = 40: r0498 <--> (R_KTY/1 kOhm - 0.9) * 32768
 Re p0496 = 42: 2500 Ohm <--> 2³²

r0497[0...2] Encoder diagnostic signal double word / Enc diag DW			
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Trace signal for encoder diagnostics (double word representation). The output signal is selected in p0496.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
r0498[0...2] Encoder diagnostic signal word low / Enc diag word low			
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Trace signal for encoder diagnostics (low component). The output signal is selected in p0496.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
r0499[0...2] Encoder diagnostic signal word high / Enc diag word high			
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Trace signal for encoder diagnostics (high component). The output signal is selected in p0496.		
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3		
p0500 Technology application / Techn application			
SERVO	Can be changed: C2(1, 5), T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Applications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	100	102	100
Description:	Sets the technology application. The parameter influences the calculation of open-loop and closed-loop control parameters that is e.g. initiated using p0578. The calculation of the following parameters depends on p0500 (only for servo drives): p1520, p1521, p1530, p1531		
Values:	100: Standard drive (SERVO) 101: Feed drive (limit current limitation) 102: Spindle drive (rated current limitation)		
Note:	The calculation of parameters, dependent on the technological application can be called-up as follows: - when exiting the quick commissioning using p3900 > 0 - when writing p0340 = 1, 3, 5 - when writing p0578 = 1		

p0500	Technology application / Techn application		
VECTOR	Can be changed: C2(1, 5), T	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Applications		Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Sets the technology application. The parameter influences the calculation of open-loop and closed-loop control parameters that is e.g. initiated using p0578. The calculation of the following parameters depends on p0500 (only for servo drives): p1520, p1521, p1530, p1531		
Values:	0: Standard drive (VECTOR) 1: Pumps and fans		
Note:	The calculation of parameters, dependent on the technological application can be called-up as follows: - when exiting the quick commissioning using p3900 > 0 - when writing p0340 = 1, 3, 5 - when writing p0578 = 1		
p0505	Selecting the system of units / Select unit sys		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: C2(5)	Dynamic index: -	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Applications		Unit selection: -
	Min 1	Max 4	Factory setting 1
Description:	Setting parameter of the actual system of units.		
Values:	1: System of units SI 2: System of units, referred/SI 3: US system of units 4: System of units, referred/US		
Note:	Reference parameter for the unit system % are, for example, p2000 ... p2004. Depending on what has been selected, these are displayed using either SI or US units.		
p0528	Units system for controller gains / Units for Kp		
SERVO, TM41	Can be changed: C2(5)	Dynamic index: -	Access level: 4
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Applications		Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	For controller gains, changes-over the units system between physical and referred (without dimensions) representation types.		
Values:	0: Physical representation 1: No dimensions (referred) representation type		
Note:	Controller gain factors are always saved as physical units. For VECTOR (r0107) the following applies: The parameter is pre-assigned a value of 1. The parameter cannot be changed.		

p0528	Units system for controller gains / Units for Kp		
VECTOR	Can be changed: C2(5)		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Applications	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	For controller gains, changes-over the units system between physical and referred (without dimensions) representation types.		
Values:	0: Physical representation 1: No dimensions (referred) representation type		
Note:	Controller gain factors are always saved as physical units. For VECTOR (r0107) the following applies: The parameter is pre-assigned a value of 1. The parameter cannot be changed.		
p0578[0...n]	Calculate parameters that are dependent on the technology/units / Calc techn par		
SERVO, VECTOR	Can be changed: C2(5), T		Access level: 2
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Applications	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	This parameter is used to calculate all parameters that depend on the technology of the application (p0500). All of the parameters are calculated that can also be determined using p0340 = 5.		
Values:	0: No calculation 1: Complete parameterization		
Note:	At the end of the calculations, p0578 is automatically set to 0.		
p0580	Measuring probe, input terminal / Meas probe term		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Sets the input terminal for the measuring probe for speed actual value measurement.		
Values:	0: No meas probe 1: DI/DO 9 (X122.8/X121.8) 2: DI/DO 10 (X122.10/X121.10) 3: DI/DO 11 (X122.11/X121.11) 4: DI/DO 13 (X132.8) 5: DI/DO 14 (X132.10) 6: DI/DO 15 (X132.11)		
Dependency:	Refer to: p0581, p0728 Refer to: A07350		
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.		
Note:	DI/DO: Bidirectional Digital Input/Output The terminal must be set as input (p0728).		

p0581	Meas probe, edge / Meas probe, edge		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the edge to evaluate the measuring probe signal for speed actual value measurement. 0: 0/1 edge 1: 1/0 edge		
Dependency:	Refer to: p0580		
p0582	Measuring probe, pulses per revolution / Meas probe pulses		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 1	Max 12	Factory setting 1
Description:	Sets the number of pulses per revolution (e.g. for disks with holes).		
p0583	Measuring probe, maximum measuring time / Meas probe t_max		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0 [s]	Max 10 [s]	Factory setting 10 [s]
Description:	Sets the maximum measuring time for the measuring probe. If a new pulse is not received before the maximum measuring time has expired, then the speed actual value in r0586 is set to zero. This timer stage is re-started with the next pulse.		
Dependency:	Refer to: r0586		
r0586	CO: Measuring probe, speed actual value / Meas probe n_act		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed actual value measured using the BERO.		
Dependency:	Refer to: p0580, p0583		
Note:	If a measuring probe is not selected (p0580 = 0), then a value of zero is displayed.		
r0586	CO: Measuring probe, velocity actual value / Meas probe v_act		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity actual value measured using the BERO.		
Dependency:	Refer to: p0580, p0583		
Note:	If a measuring probe is not selected (p0580 = 0), then a value of zero is displayed.		

r0587	CO: Measuring probe, measuring time measured / Meas probe t_meas		
SERVO	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time between the last two BERO pulses. The measuring time is specified as 32-bit value with a resolution of 1/48 µs. If a new pulse is not received before the maximum measured time in p0583 expires, then r0587 is set to the maximum measuring time.		
Dependency:	Refer to: p0580		
Note:	If a measuring probe is not selected (p0580 = 0), then a value of zero is displayed.		
r0588	CO: Measuring probe, pulse counter / Meas probe P_count		
SERVO	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of measuring pulses that have occurred (been received) up until now.		
Dependency:	Refer to: p0580		
Note:	After reaching 4294967295 ($2^{32} - 1$), the counter starts again at 0.		
r0589	Measuring probe, delay time / Meas probe t_delay		
SERVO	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time since the last measuring pulse was detected. The delay time is specified as 32-bit value with a resolution of 1/48 µs. When a measuring pulse occurs (is received) the delay time is reset and is limited to the maximum measuring time in p0583.		
Dependency:	Refer to: p0580		
Note:	If a measuring probe is not selected (p0580 = 0), then a value of zero is displayed.		
r0590[0...69]	Units descriptor display / Unit descriptor		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Indicates the unit descriptors including the currently set units.		
Dependency:	Refer to: p0100, p0349, p0505, r0591, r0592, r0593, p0596		
Note:	All indices of r590, r592 and r593 designate the same conversion rule. The unit descriptor is in r590[x], the actual factor for this in r592[x] and the actual offset for this in r593[x].		

r0591	Number of unit descriptors / Qty unitDescriptor		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Unsigned16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Number of unit descriptors.		
Dependency:	Refer to: r0590, r0592, r0593		
r0592[0...69]	Unit descriptors factor / Unit descrip fac		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Factor for the unit descriptor. The factor is part of a calculation rule that allows conversion into the currently set units of the unit descriptor. The value -1.0 means that this calculation rule is not valid.		
Dependency:	Refer to: r0590, r0591, r0593		
Note:	All indices of r590, r592 and r593 designate the same conversion rule. The unit descriptor is in r590[x], the actual factor for this in r592[x] and the actual offset for this in r593[x].		
r0593[0...69]	Unit descriptor offset / UnitDescriptor off		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Offset to the the unit descriptor. The offset is part of a calculation rule that allows conversion into the currently set units of the unit descriptor.		
Dependency:	Refer to: r0590, r0591, r0592		
Note:	All indices of r590, r592 and r593 designate the same conversion rule. The unit descriptor is in r590[x], the actual factor for this in r592[x] and the actual offset for this in r593[x].		

p0595 Selecting technological units / Select tech units

SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: C2(5) Data type: Integer16 P-Group: Applications	Dynamic index: - Units group: -	Access level: 1 Function diagram: - Unit selection: - Factory setting: 1
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Description: Selects the units for the parameters of the technology controller.

- Values:**
- 1: %
 - 2: 1 referred, no dimensions
 - 3: Bar
 - 4: °C
 - 5: Pa
 - 6: ltr/s
 - 7: m³/s
 - 8: ltr/min
 - 9: m³/min
 - 10: ltr/h
 - 11: m³/h
 - 12: kg/s
 - 13: kg/min
 - 14: kg/h
 - 15: t/min
 - 16: t/h
 - 17: N
 - 18: kN
 - 19: Nm
 - 20: psi
 - 21: °F
 - 22: gallon/s
 - 23: inch³/s
 - 24: gallon/min
 - 25: inch³/min
 - 26: gallon/h
 - 27: inch³/h
 - 28: lb/s
 - 29: lb/min
 - 30: lb/h
 - 31: lbf
 - 32: lbf ft

Dependency: Refer to: p0596

p0596 Reference quantity, technological units / Ref tech units

SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T Data type: Floating Point P-Group: -	Dynamic index: - Units group: -	Access level: 1 Function diagram: - Unit selection: - Factory setting: 1.00
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Description: Sets the reference quantity for the technological units. When changing-over using changeover parameter 595 to absolute units, all of the parameters involved refer to the reference quantity.

Dependency: Refer to: p0595

p0600[0...n]	Motor temperature sensor for monitoring / Mot temp_sensor		
SERVO	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: 8016
	P-Group: Motor		Unit selection: -
	Min 0	Max 11	Factory setting 1
Description:	Sets the sensor to monitor the motor temperature.		
Values:	0: No sensor 1: Temperature sensor via encoder 1 2: Temperature sensor via encoder 2 3: Temperature sensor via encoder 3 10: Temperature sensor via a BICO interconnection 11: Temperature sensor via Motor Module		
Dependency:	Refer to: r0458, p0601, p0603		
Note:	p0600 = 0: The temperature monitoring function is disabled for permanent magnet and separately excited synchronous motors. p0600 = 10, the BICO interconnection should be executed via p0603.		
p0600[0...n]	Motor temperature sensor for monitoring / Mot temp_sensor		
VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: 8016
	P-Group: Motor		Unit selection: -
	Min 0	Max 11	Factory setting 0
Description:	Sets the sensor to monitor the motor temperature.		
Values:	0: No sensor 1: Temperature sensor via encoder 1 2: Temperature sensor via encoder 2 3: Temperature sensor via encoder 3 10: Temperature sensor via a BICO interconnection 11: Temperature sensor via Motor Module		
Dependency:	Refer to: r0458, p0601, p0603		
Note:	p0600 = 0: The temperature monitoring function is disabled for permanent magnet and separately excited synchronous motors. p0600 = 10, the BICO interconnection should be executed via p0603.		
p0601[0...n]	Motor temperature sensor type / Mot temp_sensortyp		
SERVO, VECTOR	Can be changed: C2(3), U, T	Dynamic index: MDS, p0130	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: 8016
	P-Group: Motor		Unit selection: -
	Min 0	Max 10	Factory setting 2
Description:	Sets the sensor type for the motor temperature monitoring. When evaluating using SME120 or SME125 (p0601 = 10), 4 temperature channels are available, which are parameterized using p4600, p4601, p4602, p4603. The selection is only possible if an SME120 or an SME125 is being used and bit 8 is set in r0458.		
Values:	0: No sensor available 1: PTC thermistor 2: KTY84 3: KTY84 and PTC (only for temperature sensor via encoder) 10: SME120 or SME125		
Dependency:	Refer to: r0458, p0600		
Note:	PTC thermistor (p0601 = 1): Tripping resistance = 1650 Ohm. The temperature sensor for the temperature evaluation is set in p0600. For p0600 = 10 (temperature sensor via a BICO interconnection), the setting in p0601 has no significance.		

p0602	Par_circuit power unit number, temperature sensor / LT_no. temp_sensor		
VECTOR (Parallel)	Can be changed: C2(3), U, T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 10	Factory setting 0
Description:	Sets the power unit number to which the temperature sensor is connected. The value corresponds to the Power unit Data Set number (PDS) of the power unit. The number of power unit data sets is defined in p0120.		

p0603	CI: Motor temperature / Mot temperature		
SERVO, VECTOR	Can be changed: C2(3), T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8016
	P-Group: Motor	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to evaluate the motor temperature via a BICO interconnection.		
Dependency:	Refer to: p0600		
Note:	Temperature sensor KTY: Valid temperature range -48 °C ... 248 °C. PTC temperature sensor: For the -50 °C, the following applies: Motor temperature < nominal response temperature of the PTC. For the 250 °C, the following applies: Motor temperature >= nominal response temperature of the PTC. Note: When using a Terminal Module 31 (TM31), the following applies: - the sensor type used is set using p4100. - the temperature signal is interconnected using CO: r4105.		

p0604[0...n]	Motor overtemperature alarm threshold / Mot TempAlrmThresh		
SERVO	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min 0.0 [°C]	Max 200.0 [°C]	Factory setting 120.0 [°C]
Description:	Sets the alarm threshold for monitoring the motor temperature.		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0604[0...n]	Motor overtemperature alarm threshold / Mot TempAlrmThresh		
VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min 0.0 [°C]	Max 200.0 [°C]	Factory setting 130.0 [°C]
Description:	Sets the alarm threshold for monitoring the motor temperature.		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		

p0605[0...n]	Motor overtemperature fault threshold / MotTempFaultThresh		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min 0.0 [°C]	Max 200.0 [°C]	Factory setting 145.0 [°C]
Description:	Sets the fault threshold to monitor the motor temperature.		
Note:	The parameter is automatically preset for motors from the motor list (p0301).		
p0606[0...n]	Motor overtemperature timer / Mot TempTimeStage		
SERVO	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 600.000 [s]	Factory setting 240.000 [s]
Description:	Sets the timer stage for the alarm threshold for the motor temperature monitoring function. This timer stage is started when the temperature alarm threshold (p0604) is exceeded. If the timer stage expires before the temperature in the meantime falls below the alarm threshold, the fault F07011 is output. If the temperature fault threshold (p0605) is prematurely exceeded before the timer stage has expired, then fault F07011 is immediately output. As long as the motor temperature has still not exceeded the fault threshold, the fault can be acknowledged.		
Dependency:	Refer to: p0604, p0605 Refer to: F07011, A07910		
Note:	With p0606 = 0 s, the timer stage is de-activated and only the fault threshold is effective. KTY sensor: When setting the minimum value, the timer is disabled and a fault is not output until p0605 is exceeded. PTC sensor: The timer minimum value has no particular significance.		
p0606[0...n]	Motor overtemperature timer / Mot TempTimeStage		
VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 600.000 [s]	Factory setting 0.000 [s]
Description:	Sets the timer stage for the alarm threshold for the motor temperature monitoring function. This timer stage is started when the temperature alarm threshold (p0604) is exceeded. If the timer stage expires before the temperature in the meantime falls below the alarm threshold, the fault F07011 is output. If the temperature fault threshold (p0605) is prematurely exceeded before the timer stage has expired, then fault F07011 is immediately output. As long as the motor temperature has still not exceeded the fault threshold, the fault can be acknowledged.		
Dependency:	Refer to: p0604, p0605 Refer to: F07011, A07910		
Note:	With p0606 = 0 s, the timer stage is de-activated and only the fault threshold is effective. KTY sensor: When setting the minimum value, the timer is disabled and a fault is not output until p0605 is exceeded. PTC sensor: The timer minimum value has no particular significance.		

p0607[0...n]	Temperature sensor fault timer / Sensor fault time		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 600.000 [s]	Factory setting 0.100 [s]
Description:	Sets the timer stage between the output of alarm and fault for a temperature sensor fault. If there is a sensor fault, this timer stage is started. If the sensor fault is still present after the timer stage has expired, a corresponding fault message is output.		
Note:	If the motor is an induction motor, the timer is switched off when setting the minimum value and no alarm is output. Temperature monitoring is then based on the thermal model.		
p0610[0...n]	Response to motor overtemperature condition / Mot temp response		
VECTOR	Can be changed: C2(3), T		Access level: 2
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 1
Description:	Sets the system response when the motor temperature reaches the alarm threshold.		
Values:	0: No response, only alarm, no reduction of I _{max} 1: Alarm and reduction of I _{max} and fault (F07011) 2: Alarm and fault (F07011), no reduction of I _{max}		
Dependency:	Refer to: p0601, p0604, p0605		
Note:	the I _{max} reduction is not executed for PTC (p0601 = 1). The I _{max} reduction results in a lower output frequency.		
p0620[0...n]	Thermal adaptation, stator and rotor resistance / Mot therm_adapt R		
SERVO	Can be changed: C2(3), U, T		Access level: 2
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 2
Description:	Sets the thermal adaptation of the stator/primary section resistance and rotor/secondary section resistance according to r0395 and r0396.		
Values:	0: No thermal adaptation of stator and rotor resistances 1: Resistances adapted to the temperatures of the thermal model 2: Resistances adapted to the measured stator winding temperature		
Note:	For p0620 = 1, the following applies: The stator resistance is adapted using the temperature in r0035 and the rotor resistance together with the model temperature in r0633. For p0620 = 2, the following applies: The stator resistance is adapted using the temperature in r0035. The rotor temperature to adapt the rotor resistance is calculated as follows from the stator temperature (r0035). $\theta_{R} = (r0628 + r0625) / (r0627 + r0625) * r0035$		

p0620[0...n]	Thermal adaptation, stator and rotor resistance / Mot therm_adapt R		
VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 1
Description:	Sets the thermal adaptation of the stator/primary section resistance and rotor/secondary section resistance according to r0395 and r0396.		
Values:	0: No thermal adaptation of stator and rotor resistances 1: Resistances adapted to the temperatures of the thermal model 2: Resistances adapted to the measured stator winding temperature		
Note:	For p0620 = 1, the following applies: The stator resistance is adapted using the temperature in r0035 and the rotor resistance together with the model temperature in r0633. For p0620 = 2, the following applies: The stator resistance is adapted using the temperature in r0035. The rotor temperature to adapt the rotor resistance is calculated as follows from the stator temperature (r0035). $\text{theta_R} = (\text{r0628} + \text{r0625}) / (\text{r0627} + \text{r0625}) * \text{r0035}$		
p0621[0...n]	Temperature identification after restart / Temp_ident restart		
VECTOR (n/M)	Can be changed: C2(3), T		Access level: 2
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Configuration of the temperature identification after powering-up again. If the identification is selected, when powering-up for the first time after the system run-up, the stator resistance is measured and from this the temperature determined. The thermal model is then suitably initialized.		
Values:	0: No temperature identification 1: Temperature identification after restart 2: Temperature identification after each power-up		
p0622[0...n]	Motor excitation time for temp_ident after powering-up again / t_excit temp_id		
VECTOR (n/M)	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 20.000 [s]	Factory setting 0.000 [s]
Description:	Sets the excitation time of the motor during the temperature identification after powering-up again (restart).		
r0623	Stator resistance after temperature identification / TempId R_stator		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the identified stator resistance after the temperature identification run.		

p0625[0...n]	Motor ambient temperature / Mot T_ambient		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min -40 [°C]	Max 80 [°C]	Factory setting 20 [°C]
Description:	Defines the ambient temperature of the motor to calculate the temperature model.		
Note:	The parameters for stator and rotor resistance (p0350, p0354) refer to this temperature.		
p0626[0...n]	Motor overtemperature, stator core / Mot T_over core		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_2	Unit selection: p0505
	Min 20 [K]	Max 200 [K]	Factory setting 50 [K]
Description:	Defines the rated overtemperature of the stator core referred to the ambient temperature.		
Dependency:	Refer to: p0625		
p0627[0...n]	Motor overtemperature, stator winding / Mot T_over stator		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_2	Unit selection: p0505
	Min 20 [K]	Max 200 [K]	Factory setting 80 [K]
Description:	Defines the rated overtemperature of the stator winding referred to the ambient temperature.		
Dependency:	Refer to: p0625		
p0628[0...n]	Rotor winding overtemperature / Mot T_over rotor		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_2	Unit selection: p0505
	Min 20 [K]	Max 200 [K]	Factory setting 100 [K]
Description:	Defines the rated overtemperature of the squirrel cage rotor referred to ambient temperature.		
Dependency:	Refer to: p0625		
r0630[0...n]	Motor temperature model ambient temperature / MotTMod T_amb.		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the ambient temperature of the motor temperature model.		

r0631[0...n]	Motor temperature model, stator core temperature / MotTMod T_iron		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the stator core temperature of the motor temperature model.		
r0632[0...n]	Motor temperature model, stator winding temperature / MotTMod T_copper		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the stator winding temperature of the motor temperature model.		
r0633[0...n]	Motor temperature model, rotor temperature / MotTMod T_rotor		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: 8016
	P-Group: Motor	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the rotor temperature of the motor temperature model.		
p0640[0...n]	Current limit / Current limit		
SERVO, VECTOR	Can be changed: C2(1, 3), U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5722, 6640
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the current limit.		
Dependency:	Refer to: r0209, p0323		
Note:	<p>The parameter is part of the fast commissioning (p0010 = 1); this means that it is appropriately pre-assigned when changing p0304 and p0323.</p> <p>The current limit p0640 is limited to r0209 and p0323. The limit to p0323 is not realized if a value of zero is entered there.</p> <p>The following additionally applies for vector drives (refer to p0107): p0640 is limited to 4.0 * p0305.</p> <p>The resulting current limit is displayed in r0067 and if required, r0067 is reduced by the thermal model of the Motor Module.</p> <p>The torque and power limits (p1520, p1521, p1530, p1531) matching the current limit are automatically calculated when exiting the quick commissioning using p3900 > 0 or using the automatic parameterization with p0340 = 3, 5. For servo drives, the following applies (refer to p0107):</p> <p>p0640 is pre-assigned as follows using the automatic parameterization (p0340 = 1, p3900 > 0) taking into account the limits r0209 and r0323:</p> <ul style="list-style-type: none"> - for induction motors: p0640 = 1.5 * p0305 - for synchronous motors: p0640 = p0338 <p>For vector drives (refer to p0107), the following applies:</p> <p>p0640 is pre-assigned for the automatic self commissioning routine (e.g. to 1.5 * p0305, with p0305 = r0207[1]). p0640 must be entered when commissioning the system. This is the reason that p0640 is not calculated by the automatic parameterization when exiting the fast commissioning (p3900 > 0).</p>		

p0643[0...n]		Overvoltage protection for synchronous motors / Overvolt_protect		
SERVO	Can be changed: T			Access level: 3
	Data type: Integer16		Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor		Units group: -	Unit selection: -
	Min 0		Max 1	Factory setting 0
Description:	Sets the overvoltage protection for synchronous motors in the field-weakening range.			
Values:	0: No measure 1: Voltage Protection Module (VPM)			
Dependency:	Refer to: p0316, p1082, p1231, p9601, p9801 Refer to: F07432, F07906, F07907			
Note:	In the field-weakening range, synchronous motors can, when a fault condition exists, generate high DC link voltages. The following possibilities exist to protect the drive system from being destroyed due to overvoltage: - limit the maximum speed (p1082) without any additional protection. The maximum speed without protection is calculated from p1082 = 9590/p0316. - use a voltage protection module (VPM) in conjunction with the function "safe standstill" (p9601, p9801). When a fault condition exists, the VPM short-circuits the motors. During the short-circuit, the pulses must be cancelled - this means that the terminals for the safe standstill must be connected to the VPM. - activating the internal voltage protection (IVP) with p1231 = 3.			
p0650[0...n]		Actual motor operating hours / Mot t_oper act		
SERVO, VECTOR	Can be changed: T			Access level: 3
	Data type: Unsigned32		Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor		Units group: -	Unit selection: -
	Min 0 [h]		Max 4294967295 [h]	Factory setting 0 [h]
Description:	Displays the operating hours for the corresponding motor. The motor operating time counter continues to run when the pulses are enabled. When the pulse enable is withdrawn, the counter is held and the value saved.			
Dependency:	The following prerequisites must be fulfilled in order to be able to save the operating hours counter in a non-volatile fashion: - firmware with V2.2 or higher. - Control Unit 320 (CU320) with hardware version C or higher (module with NVRAM). Refer to: p0651, Refer to: A01590			
Note:	The value is in the unit [h] (hours). The operating hours counter in p0650 can only be reset to 0. In this case, p0651 is automatically set to 0. For p0651 = 0, the operating hours counter is disabled. The operating hours counter only runs for MDS0 and MDS1 (Motor Data Set).			
p0651[0...n]		Motor operating hours maintenance interval / Mot t_op maint		
SERVO, VECTOR	Can be changed: T			Access level: 3
	Data type: Unsigned32		Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor		Units group: -	Unit selection: -
	Min 0 [h]		Max 99999 [h]	Factory setting 0 [h]
Description:	Sets the service/maintenance intervals in hours for the appropriate motor. An appropriate fault is output when the operating hours set here are reached.			
Dependency:	Refer to: p0650 Refer to: A01590			
Note:	The value is in the unit [h] (hours). For p0651 = 0, the operating hours counter is disabled. The operating hours counter only runs for MDS0 and MDS1 (Motor Data Set).			

p0652[0...n]	Motor stator resistance, scaling / Mot R_stator scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the stator resistance.		
Dependency:	Refer to: p0350, r0370		
p0653[0...n]	Motor stator leakage inductance, scaling / Mot L_S_leak scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the stator leakage inductance.		
Dependency:	Refer to: p0356, r0377		
p0655[0...n]	Motor magnetizing inductance, d axis, saturated scaling / Mot Lhd_sat scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the magnetizing inductance in the direction of the rotor axis (d axis).		
Dependency:	Refer to: p0360, r0382		
p0656[0...n]	Motor magnetizing inductance, q axis, saturated scaling / Mot Lhq_sat scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the magnetizing inductance quadrature to the rotor axis (q axis).		
Dependency:	Refer to: p0361, r0383		
p0657[0...n]	Motor damping inductance, d axis scaling / Mot L_damp_d scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the damping inductance in the direction of the rotor axis (d axis).		
Dependency:	Refer to: p0358, r0380		

p0658[0...n]	Motor damping inductance, q axis scaling / Mot L_damp_q scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the damping inductance quadrature to the rotor axis (q axis).		
Dependency:	Refer to: p0359, r0381		

p0659[0...n]	Motor damping resistance, d axis scaling / Mot R_damp_d scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the damping resistance in the direction of the rotor axis (d axis).		
Dependency:	Refer to: p0354, r0374		

p0660[0...n]	Motor damping resistance, q axis scaling / Mot R_damp_q scal		
VECTOR	Can be changed: C2(3), U, T		Access level: 4
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Factor to evaluate the damping resistance quadrature to the rotor axis (q axis).		
Dependency:	Refer to: p0355, r0375		

p0680[0...5]	Central measuring probe, input terminal / Cen meas inpt		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Sets the digital input used for the function "central measuring probe evaluation". p0680[0]: Digital input, measuring probe 1 p0680[1]: Digital input, measuring probe 2 p0680[2]: Digital input, measuring probe 3 p0680[3]: Digital input, measuring probe 4 p0680[4]: Digital input, measuring probe 5 p0680[5]: Digital input, measuring probe 6		
Values:	0: No meas probe 1: DI/DO 9 (X122.8/X121.8) 2: DI/DO 10 (X122.10/X121.10) 3: DI/DO 11 (X122.11/X121.11) 4: DI/DO 13 (X132.8) 5: DI/DO 14 (X132.10) 6: DI/DO 15 (X132.11)		
Dependency:	Refer to: p0728		
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.		

Note: Prerequisite: The DI/DO must be set as input (p0728.x = 0).
DI/DO: Bidirectional Digital Input/Output

p0681	BI: Central measuring probe, synchronizing signal, signal source / Cen meas sync_sig		
CU_S	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the synchronizing signal (SYN) of the function "central measuring probe evaluation". The signal is used to synchronize the common system time between the master and slave.		

p0682	CI: Central measuring probe, control word signal source / Cen meas STW S_src		
CU_S	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the control word of the function "central measuring probe evaluation".		

p0684	Central measuring probe evaluation technique / Cen meas eval		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	0	0
Description:	Sets the evaluation technique for the function "central measuring probe evaluation".		
Values:	0: Measurement with handshake		

r0685	Central measuring probe, control word display / Cen meas STW disp		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description:	Displays the control word for the function "central measuring probe evaluation".				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Falling edge, measuring probe 1	Yes	No	-
	01	Falling edge, measuring probe 2	Yes	No	-
	02	Falling edge, measuring probe 3	Yes	No	-
	03	Falling edge, measuring probe 4	Yes	No	-
	04	Falling edge, measuring probe 5	Yes	No	-
	05	Falling edge, measuring probe 6	Yes	No	-
	08	Rising edge, measuring probe 1	Yes	No	-
	09	Rising edge, measuring probe 2	Yes	No	-
	10	Rising edge, measuring probe 3	Yes	No	-
	11	Rising edge, measuring probe 4	Yes	No	-
	12	Rising edge, measuring probe 5	Yes	No	-
	13	Rising edge, measuring probe 6	Yes	No	-

r0686[0...5]	CO: Central measuring probe, measuring time rising edge / CenMeas t_meas 0/1				
CU_S	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: -	
	P-Group: Displays, signals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		-	
Description:	Displays the measuring time for a rising edge at the digital input for the "central measuring probe evaluation" function. The measuring time is specified as 16-bit value with a resolution of 0.25 µs. r0686[0]: Measuring time, rising edge measuring probe 1 r0686[1]: Measuring time, rising edge measuring probe 2 r0686[2]: Measuring time, rising edge measuring probe 3 r0686[3]: Measuring time, rising edge measuring probe 4 r0686[4]: Measuring time, rising edge measuring probe 5 r0686[5]: Measuring time, rising edge measuring probe 6				
r0687[0...5]	CO: Central measuring probe, measuring time falling edge / CenMeas t_meas 1/0				
CU_S	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: -	
	P-Group: Displays, signals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		-	
Description:	Displays the measuring time for a falling edge at the digital input for the "central measuring probe evaluation" function. The measuring time is specified as 16-bit value with a resolution of 0.25 µs. r0687[0]: Measuring time, falling edge measuring probe 1 r0687[1]: Measuring time, falling edge measuring probe 2 r0687[2]: Measuring time, falling edge measuring probe 3 r0687[3]: Measuring time, falling edge measuring probe 4 r0687[4]: Measuring time, falling edge measuring probe 5 r0687[5]: Measuring time, falling edge measuring probe 6				
r0688	CO: Central measuring probe, status word display / Cen meas ZSW disp				
CU_S	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: -	
	P-Group: Displays, signals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the status word for the function "central measuring probe evaluation".				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Digital input, measuring probe 1	High	Low	-
	01	Digital input, measuring probe 2	High	Low	-
	02	Digital input, measuring probe 3	High	Low	-
	03	Digital input, measuring probe 4	High	Low	-
	04	Digital input, measuring probe 5	High	Low	-
	05	Digital input, measuring probe 6	High	Low	-
	08	Sub-sampling, measuring probe 1	High	Low	-
	09	Sub-sampling, measuring probe 2	High	Low	-
	10	Sub-sampling, measuring probe 3	High	Low	-
	11	Sub-sampling, measuring probe 4	High	Low	-
	12	Sub-sampling, measuring probe 5	High	Low	-
	13	Sub-sampling, measuring probe 6	High	Low	-

p0700[0...n]		Macro Binector Input (BI) / Macro BI			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C2(1), T	Data type: Unsigned32	Dynamic index: CDS, p0170	Access level: 1	
	P-Group: Commands	Units group: -		Function diagram: -	
	Min 0	Max 999999		Unit selection: -	
				Factory setting 0	
Description:	Runs the appropriate ACX file on the CompactFlash card. The binector inputs (BI) of the appropriate Command Data Set (CDS) are appropriately interconnected. The selected ACX file must be located in the following directory: ... /PMACROS/<drive object>/P700/PMxxxxxx.ACX Example: p0700 = 6 --> the file PM000006.ACX is run.				
Dependency:	The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card. Refer to: p0015, p1000, p1500, r8571				
Notice:	No errors were issued during fast commissioning (p3900 = 1) when writing to parameters of the QUICK_IBN group!				
Note:	The macros in the specified directory are displayed in r8571. Macros available as standard are described in the technical documentation of the particular product. BI: Binector input				
r0721		CU digital inputs, terminal actual value / CU DI actual value			
CU_S	Can be changed: -	Data type: Unsigned32	Dynamic index: -	Access level: 2	
	P-Group: Commands	Units group: -		Function diagram: 1510, 2020, 2030, 2031, 2100, 2120, 2130, 2131, 2132, 2133	
	Min -	Max -		Unit selection: -	
				Factory setting 0000 bin	
Description:	Displays the actual value at the digital inputs. This means that the actual input signal can be checked at terminal DI x or DI/DO x prior to switching from the simulation mode (p0795.x = 1) to terminal mode (p0795.x = 0). The input signal at terminal DI x is displayed in bit x of r0721.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X122.1/X121.1)	High	Low	-
	01	DI 1 (X122.2/X121.2)	High	Low	-
	02	DI 2 (X122.3/X121.3)	High	Low	-
	03	DI 3 (X122.4/X121.4)	High	Low	-
	04	DI 4 (X132.1)	High	Low	-
	05	DI 5 (X132.2)	High	Low	-
	06	DI 6 (X132.3)	High	Low	-
	07	DI 7 (X132.4)	High	Low	-
	08	DI/DO 8 (X122.7/X121.7)	High	Low	-
	09	DI/DO 9 (X122.8/X121.8)	High	Low	-
	10	DI/DO 10 (X122.10/X121.10)	High	Low	-
	11	DI/DO 11 (X122.11/X121.11)	High	Low	-
	12	DI/DO 12 (X132.7)	High	Low	-
	13	DI/DO 13 (X132.8)	High	Low	-
	14	DI/DO 14 (X132.10)	High	Low	-
	15	DI/DO 15 (X132.11)	High	Low	-
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.				
Note:	If a DI/DO is parameterized as output (p0728.x = 1), then r0721.x = 0 is displayed. DI: Digital input DI/DO: Bidirectional Digital Input/Output				

r0722		CO/BO: CU digital inputs, status / CU DI status			
CU_S	Can be changed: -	Dynamic index: -	Access level: 1		
	Data type: Unsigned32		Function diagram: 1510, 2020, 2030, 2031, 2100, 2120, 2130, 2131, 2132, 2133		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the status of the digital inputs.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X122.1/X121.1)	High	Low	-
	01	DI 1 (X122.2/X121.2)	High	Low	-
	02	DI 2 (X122.3/X121.3)	High	Low	-
	03	DI 3 (X122.4/X121.4)	High	Low	-
	04	DI 4 (X132.1)	High	Low	-
	05	DI 5 (X132.2)	High	Low	-
	06	DI 6 (X132.3)	High	Low	-
	07	DI 7 (X132.4)	High	Low	-
	08	DI/DO 8 (X122.7/X121.7)	High	Low	-
	09	DI/DO 9 (X122.8/X121.8)	High	Low	-
	10	DI/DO 10 (X122.10/X121.10)	High	Low	-
	11	DI/DO 11 (X122.11/X121.11)	High	Low	-
	12	DI/DO 12 (X132.7)	High	Low	-
	13	DI/DO 13 (X132.8)	High	Low	-
	14	DI/DO 14 (X132.10)	High	Low	-
	15	DI/DO 15 (X132.11)	High	Low	-
Dependency:	Refer to: r0723				
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.				
Note:	DI: Digital input DI/DO: Bidirectional Digital Input/Output				

r0723		BO: CU digital inputs, status inverted / CU DI status inv			
CU_S	Can be changed: -	Dynamic index: -	Access level: 1		
	Data type: Unsigned32		Function diagram: 1510, 2020, 2030, 2031, 2100, 2120, 2130, 2131 2132, 2133		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the inverted status of the digital inputs.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X122.1/X121.1)	High	Low	-
	01	DI 1 (X122.2/X121.2)	High	Low	-
	02	DI 2 (X122.3/X121.3)	High	Low	-
	03	DI 3 (X122.4/X121.4)	High	Low	-
	04	DI 4 (X132.1)	High	Low	-
	05	DI 5 (X132.2)	High	Low	-

06	DI 6 (X132.3)	High	Low	-
07	DI 7 (X132.4)	High	Low	-
08	DI/DO 8 (X122.7/X121.7)	High	Low	-
09	DI/DO 9 (X122.8/X121.8)	High	Low	-
10	DI/DO 10 (X122.10/X121.10)	High	Low	-
11	DI/DO 11 (X122.11/X121.11)	High	Low	-
12	DI/DO 12 (X132.7)	High	Low	-
13	DI/DO 13 (X132.8)	High	Low	-
14	DI/DO 14 (X132.10)	High	Low	-
15	DI/DO 15 (X132.11)	High	Low	-

Dependency: Refer to: r0722

Notice: To the terminal designation:

The first designation is valid for CU320, the second for CU310.

Note: DI: Digital input

DI/DO: Bidirectional Digital Input/Output

p0728 CU, set input or output / CU DI or DO

CU_S

Can be changed: T

Data type: Unsigned32

Dynamic index: -

Access level: 1

Function diagram: 1510,
2030, 2031, 2130, 2131, 2132,
2133

P-Group: Commands

Units group: -

Unit selection: -

Min

Max

Factory setting

-

-

0000 bin

Description: Sets the bidirectional digital inputs/outputs as an input or output.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
08	DI/DO 8 (X122.7/X121.7)	Output	Input	-
09	DI/DO 9 (X122.8/X121.8)	Output	Input	-
10	DI/DO 10 (X122.10/X121.10)	Output	Input	-
11	DI/DO 11 (X122.11/X121.11)	Output	Input	-
12	DI/DO 12 (X132.7)	Output	Input	-
13	DI/DO 13 (X132.8)	Output	Input	-
14	DI/DO 14 (X132.10)	Output	Input	-
15	DI/DO 15 (X132.11)	Output	Input	-

Notice: To the terminal designation:

The first designation is valid for CU320, the second for CU310.

Note: DI/DO: Bidirectional Digital Input/Output

p0738 BI: CU, signal source for terminal DI/DO 8 / CU S_src DI/DO 8

CU_S

Can be changed: U, T

Data type: Unsigned32

Dynamic index: -

Access level: 1

Function diagram: 1510,
2030, 2130

P-Group: Commands

Units group: -

Unit selection: -

Min

Max

Factory setting

-

-

0

Description: Sets the signal source for terminal DI/DO 8 (X122.7).

Notice: To the terminal designation:

The first designation is valid for CU320, the second for CU310.

Note: Prerequisite: The DI/DO must be set as an output (p0728.8 = 1).

DI/DO: Bidirectional Digital Input/Output

p0739	BI: CU, signal source for terminal DI/DO 9 / CU S_src DI/DO 9		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2030, 2130
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for terminal DI/DO 9 (X122.8).		
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.9 = 1). DI/DO: Bidirectional Digital Input/Output		
p0740	BI: CU, signal source for terminal DI/DO 10 / CU S_src DI/DO 10		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2031, 2131
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for terminal DI/DO 10 (X122.10).		
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.10 = 1). DI/DO: Bidirectional Digital Input/Output		
p0741	BI: CU, signal source for terminal DI/DO 11 / CU S_src DI/DO 11		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1510, 2031, 2131
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for terminal DI/DO 11 (X122.11).		
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.11 = 1). DI/DO: Bidirectional Digital Input/Output		
p0742	BI: CU, signal source for terminal DI/DO 12 / CU S_src DI/DO 12		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1510, 2132
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for terminal DI/DO 12 (X132.7).		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.12 = 1). DI/DO: Bidirectional Digital Input/Output		

p0743	BI: CU, signal source for terminal DI/DO 13 / CU S_src DI/DO 13		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2132
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 13 (X132.8).		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.13 = 1). DI/DO: Bidirectional Digital Input/Output		

p0744	BI: CU, signal source for terminal DI/DO 14 / CU S_src DI/DO 14		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2133
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 14 (X132.10).		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.14 = 1). DI/DO: Bidirectional Digital Input/Output		

p0745	BI: CU, signal source for terminal DI/DO 15 / CU S_src DI/DO 15		
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1510, 2133
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 15 (X132.11).		
Note:	Prerequisite: The DI/DO must be set as an output (p0728.15 = 1). DI/DO: Bidirectional Digital Input/Output		

r0747	CU, digital outputs status / CU DO status				
CU_S	Can be changed: -		Access level: 1		
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2130, 2131, 2132, 2133		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the status of digital outputs.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	08	DI/DO 8 (X122.7/X121.7)	High	Low	-
	09	DI/DO 9 (X122.8/X121.8)	High	Low	-
	10	DI/DO 10 (X122.10/X121.10)	High	Low	-
	11	DI/DO 11 (X122.11/X121.11)	High	Low	-
	12	DI/DO 12 (X132.7)	High	Low	-
	13	DI/DO 13 (X132.8)	High	Low	-
	14	DI/DO 14 (X132.10)	High	Low	-
	15	DI/DO 15 (X132.11)	High	Low	-
Notice:	To the terminal designation: The first designation is valid for CU320, the second for CU310.				
Note:	Inversion using p0748 has been taken into account. The setting of the DI/DO as either input or output is of no significance (p0728). DI/DO: Bidirectional Digital Input/Output				

r0774[0...2]	Test sockets output voltage / TestSks U_output		
CU_S	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 8134
	P-Group: Terminals		Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual output voltage for the test sockets.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Refer to: p0771, r0772, p0776, p0777, p0778, p0779, p0780, p0783, p0784, r0786		
p0776[0...2]	Test socket mode / Test skt mode		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 4
	Data type: Integer16	Units group: -	Function diagram: 8134
	P-Group: Terminals		Unit selection: -
	Min 96	Max 99	Factory setting 99
Description:	Sets the mode for the test sockets.		
Values:	96: Physical address (32-bit integer signal, unsigned) 97: Physical address (32-bit integer signal) 98: Physical address (32-bit floating-point signal) 99: BICO signal		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Refer to: p0771, r0772, r0774, p0777, p0778, p0779, p0780, p0783, p0784, r0786, p0788, p0789, r0790		
p0777[0...2]	Test socket characteristic value x1 / Test skt char x1		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 8134
	P-Group: Terminals		Unit selection: -
	Min -100000.00 [%]	Max 100000.00 [%]	Factory setting 0.00 [%]
Description:	The normalization characteristic for the test sockets is defined using two points. This parameter specifies the x coordinate (percentage) of the first point on the characteristic.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Can only be set when p0776 = 99. Refer to: p0778, p0779, p0780, r0786		
Note:	The value 0.00 % corresponds to 2.49 V.		

p0778[0...2]	Test socket characteristic value y1 / Test skt char y1		
CU_S	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8134
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.00 [V]	Max 4.98 [V]	Factory setting 2.49 [V]
Description:	The normalization characteristic for the test sockets is defined using two points. This parameter specifies the y coordinate (output voltage) of the first point on the characteristic.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Can only be set when p0776 = 99. Refer to: p0777, p0779, p0780, r0786		
p0779[0...2]	Test socket characteristic value x2 / Test skt char x2		
CU_S	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8134
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -100000.00 [%]	Max 427.9E9 [%]	Factory setting 100.00 [%]
Description:	The normalization characteristic for the test sockets is defined using two points. This parameter specifies the x coordinate (percentage) of the second point on the characteristic.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Can only be set when p0776 = 99. Refer to: p0777, p0778, p0780, r0786		
Note:	The value 100.00 % corresponds to 4.98 V.		
p0780[0...2]	Test socket characteristic value y2 / Test skt char y2		
CU_S	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8134
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.00 [V]	Max 4.98 [V]	Factory setting 4.98 [V]
Description:	The normalization characteristic for the test sockets is defined using two points. This parameter specifies the y coordinate (output voltage) of the second point on the characteristic.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Can only be set when p0776 = 99. Refer to: p0777, p0778, p0779, r0786		

p0783[0...2]	Test sockets offset / Test skt offset		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 8134
	P-Group: Terminals		Unit selection: -
	Min -4.98 [V]	Max 4.98 [V]	Factory setting 0.00 [V]
Description:	Sets an additional offset for the test sockets.		
Index:	[0] = T0 [1] = T1 [2] = T2		
p0784[0...2]	Test socket limit on/off / TestSktLim on/off		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: 8134
	P-Group: Terminals		Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the limit for a signal to be output via test sockets.		
Values:	0: Limiting off 1: Limiting on		
Index:	[0] = T0 [1] = T1 [2] = T2		
Note:	Limiting on: If signals are output outside the permissible measuring range, the signal is limited to 4.98 V or to 0 V. Limiting off: If signals are output outside the permissible measuring range, this causes signal overflow. In the case of signal overflow, the signal jumps from 0 V to 4.98 V or from 4.98 V to 0 V.		
r0786[0...2]	Test socket normalization per volt / TestSktNorm/Volt		
CU_S	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 8134
	P-Group: Terminals		Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the normalization of the signal to be output. A change in the output voltage by 1 volt corresponds to the value in this parameter. The units are determined by the interconnected test signal.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Refer to: p0771, r0772, r0774, p0777, p0778, p0779, p0780, p0783, p0784		
Note:	Example: r0786[0] = 1500.0 and the measuring signal is r0063 (CO: Speed actual value smoothed [RPM]). A change of 1 V at the output of test socket T0 corresponds to 1500.0 [RPM].		

p0788[0...2]	Test sockets physical address / Test skt PhyAddr		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the physical address to output signals via the test sockets.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Changes only become effective if p0776 does not equal 99. Refer to: p0789, r0790		

p0789[0...2]	Test sockets physical address gain / TestSktPhyAddrGain		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -340.28235E36	Max 340.28235E36	Factory setting 1.00000
Description:	Sets the gain of a signal output of a physical address via test sockets.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Changes only become effective if p0776 does not equal 99. Refer to: p0788		

r0790[0...2]	Test sockets physical address signal value / TestSksPhyAddrVal		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the actual value of a signal determined via a physical address.		
Index:	[0] = T0 [1] = T1 [2] = T2		
Dependency:	Only effective when p0776 = 97 or p0776 = 96. Refer to: p0788		

p0795		CU digital inputs simulation mode / CU DI simulation		
CU_S	Can be changed: U, T	Data type: Unsigned32	Dynamic index: -	Access level: 2
	P-Group: Commands		Units group: -	Function diagram: 1510, 2020, 2030, 2031, 2100, 2120, 2130, 2131, 2132, 2133
	Min		Max	Unit selection: -
	-		-	Factory setting 0000 bin
Description:	Sets the simulation mode for digital inputs.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X122.1/X121.1)	Simulation	Terminal eval.
	01	DI 1 (X122.2/X121.2)	Simulation	Terminal eval.
	02	DI 2 (X122.3/X121.3)	Simulation	Terminal eval.
	03	DI 3 (X122.4/X121.4)	Simulation	Terminal eval.
	04	DI 4 (X132.1)	Simulation	Terminal eval.
	05	DI 5 (X132.2)	Simulation	Terminal eval.
	06	DI 6 (X132.3)	Simulation	Terminal eval.
	07	DI 7 (X132.4)	Simulation	Terminal eval.
	08	DI/DO 8 (X122.7/X121.7)	Simulation	Terminal eval.
	09	DI/DO 9 (X122.8/X121.8)	Simulation	Terminal eval.
	10	DI/DO 10 (X122.10/X121.10)	Simulation	Terminal eval.
	11	DI/DO 11 (X122.11/X121.11)	Simulation	Terminal eval.
	12	DI/DO 12 (X132.7)	Simulation	Terminal eval.
	13	DI/DO 13 (X132.8)	Simulation	Terminal eval.
	14	DI/DO 14 (X132.10)	Simulation	Terminal eval.
	15	DI/DO 15 (X132.11)	Simulation	Terminal eval.
Dependency:	The setpoint for the input signals is specified using p0796. Refer to: p0796, p9620			
Notice:	It is not permissible to select the simulation of a digital input using the Safety SH (p9620) and this is rejected. To the terminal designation: The first designation is valid for CU320, the second for CU310.			
Note:	DI: Digital input DI/DO: Bidirectional Digital Input/Output This parameter is not saved when data is backed-up (p0971, p0977).			

p0796		CU digital inputs simulation mode setpoint / CU DI simul setpt		
CU_S	Can be changed: U, T	Data type: Unsigned32	Dynamic index: -	Access level: 2
	P-Group: Commands		Units group: -	Function diagram: 1510, 2020, 2030, 2031, 2100, 2120, 2130, 2131, 2132, 2133
	Min		Max	Unit selection: -
	-		-	Factory setting 0000 bin
Description:	Sets the setpoint for the input signals in the digital input simulation mode.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X122.1/X121.1)	High	Low
	01	DI 1 (X122.2/X121.2)	High	Low
	02	DI 2 (X122.3/X121.3)	High	Low
	03	DI 3 (X122.4/X121.4)	High	Low
	04	DI 4 (X132.1)	High	Low
	05	DI 5 (X132.2)	High	Low

06	DI 6 (X132.3)	High	Low	-
07	DI 7 (X132.4)	High	Low	-
08	DI/DO 8 (X122.7/X121.7)	High	Low	-
09	DI/DO 9 (X122.8/X121.8)	High	Low	-
10	DI/DO 10 (X122.10/X121.10)	High	Low	-
11	DI/DO 11 (X122.11/X121.11)	High	Low	-
12	DI/DO 12 (X132.7)	High	Low	-
13	DI/DO 13 (X132.8)	High	Low	-
14	DI/DO 14 (X132.10)	High	Low	-
15	DI/DO 15 (X132.11)	High	Low	-

Dependency: The simulation of a digital input is selected using p0795.
Refer to: p0795

Notice: To the terminal designation:
The first designation is valid for CU320, the second for CU310.

Note: DI: Digital input
DI/DO: Bidirectional Digital Input/Output
This parameter is not saved when data is backed-up (p0971, p0977).

p0799 CU inputs/outputs, sampling time / CU I/O t_sampl

CU_S **Can be changed:** C1(3) **Access level:** 3
Data type: Floating Point **Dynamic index:** - **Function diagram:** 2020, 2030, 2031, 2120, 2121, 2130, 2131, 2132, 2133
P-Group: Commands **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
0.00 [µs] 5000.00 [µs] 4000.00 [µs]

Description: Sets the sampling time for the inputs and outputs.

Dependency: The parameter can only be modified for p0009 = 3, 29.
The sampling times can only be set as an integer multiple of the basic sampling time (p0110, p0111).
Refer to: p0009, r0110, r0111

Note: The modified sampling time is not effective until the drive unit is powered-up again.

p0806 BI: Inhibit master control / PcCtrl inhibit

A_INF, B_INF, SERVO, S_INF, VECTOR **Can be changed:** T **Access level:** 3
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** -
P-Group: Commands **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
- - 0

Description: Sets the signal source to block the master control.

Dependency: Refer to: r0807

Note: The master control is used from the commissioning software (drive control panel) and from the Advanced Operator Panel (AOP, LOCAL mode).

r0807	BO: Master control active / PcCtrl active			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: -	Access level: 2	
	Data type: Unsigned8		Function diagram: -	
	P-Group: Displays, signals	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays what has the master control. The drive can be controlled via the BICO interconnection or from external (e.g. the commissioning software).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Master control active	Yes	No
				FP 5030
Dependency:	Refer to: p0806			
Notice:	The master control only influences control word 1 and speed setpoint 1. Other control words/setpoints can be transferred from another automation device.			
Note:	Bit 0 = 0: BICO interconnection active Bit 0 = 1: Master control for PC/AOP The master control is used from the commissioning software (drive control panel) and from the Advanced Operator Panel (AOP, LOCAL mode).			
p0809[0...2]	Copy Command Data Set CDS / Copy CDS			
SERVO, VECTOR	Can be changed: T	Dynamic index: -	Access level: 2	
	Data type: Unsigned8		Function diagram: 8560	
	P-Group: Commands	Units group: -	Unit selection: -	
	Min 0	Max 15	Factory setting 0	
Description:	Copies one Command Data Set (CDS) into another.			
Index:	[0] = Source Command Data Set [1] = Target command data set [2] = Start copying			
Note:	Procedure: 1. In Index 0, enter which command data set should be copied. 2. In Index 1, enter the command data set that is to be copied into. 3. Start copying: Set index 2 from 0 to 1. p0809[2] is automatically set to 0 when copying is completed.			
p0810	BI: Command Data Set selection CDS bit 0 / CDS select., bit 0			
SERVO, VECTOR	Can be changed: T	Dynamic index: -	Access level: 3	
	Data type: Unsigned32		Function diagram: 8560	
	P-Group: Commands	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the signal source to select the Command Data Set bit 0 (CDS bit 0).			
Dependency:	Refer to: r0050, p0811, r0836			
Note:	Command data sets are selected using the binector inputs p0810, p0811, p0812 and p0813. For a command data set, selected using the binector inputs, is displayed in r0836. The currently effective command data set is displayed in r0050. A command data set can be copied using p0809.			

p0811	BI: Command data set selection CDS bit 1 / CDS select., bit 1		
VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8560
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the Command Data Set bit 1 (CDS bit 1).		
Dependency:	Refer to: r0050, p0810, r0836		
Note:	Command data sets are selected using the binector inputs p0810, p0811, p0812 and p0813. For a command data set, selected using the binector inputs, is displayed in r0836. The currently effective command data set is displayed in r0050. A command data set can be copied using p0809.		
p0819[0...2]	Copy Drive Data Set DDS / Copy DDS		
SERVO, TM41, VEC-TOR	Can be changed: C2(15)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: 8565
	P-Group: Data sets	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	31	[0] 0 [1] 0 [2] 0
Description:	Copies a Drive Data Set (DDS) into another.		
Index:	[0] = Source drive data set [1] = Target drive data set [2] = Start copying		
Note:	Procedure: 1. In Index 0, enter which drive data set is to be copied. 2. In Index 1, enter the drive data set data that is to be copied into. 3. Start copying: Set index 2 from 0 to 1. p0819[2] is automatically set to 0 when copying is completed.		
p0820[0...n]	BI: Drive data set selection DDS bit 0 / DDS select., bit 0		
SERVO, TM41, VEC-TOR	Can be changed: C2(15), T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 8565
	P-Group: Data sets	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the Drive Data Set, bit 0 (DDS, bit 0).		
Dependency:	Refer to: r0051, r0837		
p0821[0...n]	BI: Drive data set selection DDS bit 1 / DDS select., bit 1		
SERVO, TM41, VEC-TOR	Can be changed: C2(15), T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 8565
	P-Group: Data sets	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the Drive Data Set, bit 1 (DDS, bit 1).		
Dependency:	Refer to: r0051, r0837		

p0822[0...n]	BI: Drive data set selection DDS bit 2 / DDS select., bit 2		
SERVO, TM41, VEC-TOR	Can be changed: C2(15), T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 8565
	P-Group: Data sets		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the Drive Data Set, bit 2 (DDS, bit 2).		
Dependency:	Refer to: r0051, r0837		
p0823[0...n]	BI: Drive data set selection DDS bit 3 / DDS select., bit 3		
SERVO, TM41, VEC-TOR	Can be changed: C2(15), T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 8565
	P-Group: Data sets		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the Drive Data Set, bit 3 (DDS, bit 3).		
Dependency:	Refer to: r0051, r0837		
p0824[0...n]	BI: Drive data set selection DDS bit 4 / DDS select., bit 4		
SERVO, TM41, VEC-TOR	Can be changed: C2(15), T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 8565
	P-Group: Data sets		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the Drive Data Set, bit 4 (DDS, bit 4).		
Dependency:	Refer to: r0051, r0837		
p0826[0...n]	Motor changeover, motor number / Mot_chng mot No.		
SERVO, VECTOR	Can be changed: C2(3), U	Dynamic index: MDS, p0130	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: 8575
	P-Group: Motor		Unit selection: -
	Min	Max	Factory setting
	0	15	0
Description:	Sets the freely-assignable motor number for the motor changeover.		
Dependency:	Refer to: p0827		
Caution:	When changing over motor data sets with the same motor number (e.g. star/delta changeover) and for a motor with brake, the motor brake remains open during the changeover.		
Note:	When the motor data sets are changed-over, the following applies: The same motor number signifies the same thermal model.		
p0827[0...n]	Motor changeover status word bit number / Mot_chg ZSW bitNo.		
SERVO, VECTOR	Can be changed: C2(3), U	Dynamic index: MDS, p0130	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: 8575
	P-Group: Motor		Unit selection: -
	Min	Max	Factory setting
	0	15	0
Description:	Sets the bit number for every motor data set. Example: p0827[0] = 0: For MDS0, r0830.0 is switched. p0827[1] = 5: For MDS1, r0830.5 is switched.		

Dependency: Refer to: p0826, r0830
Note: A motor is only changed over (a new motor selected) after the pulses have been cancelled.
 When the motor data sets are changed-over, the following applies:
 Bit numbers that are not identical, signify that the motor must be changed over.

p0828[0...n] **BI: Motor changeover, feedback signal / Mot_chng fdbk sig**
 SERVO, VECTOR **Can be changed:** C2(3), T **Access level:** 3
Data type: Unsigned32 **Dynamic index:** CDS, p0170 **Function diagram:** 8575
P-Group: Motor **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0

Description: Sets the signal source for the feedback signal when changing over the motor.
 For p0833.0 = 1 the following applies:
 This feedback signal (0/1 edge) is required after a motor changeover to enable the pulses.

Dependency: Refer to: p0833

r0830 **CO/BO: Motor changeover, status word / Mot_chngov ZSW**
 SERVO, VECTOR **Can be changed:** - **Access level:** 2
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 8575
P-Group: Displays, signals **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the status word of the motor changeover.
 These signals can be connected to digital outputs to change over the motor.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Motor selection, bit 0	High	Low	-
	01	Motor selection, bit 1	High	Low	-
	02	Motor selection, bit 2	High	Low	-
	03	Motor selection, bit 3	High	Low	-
	04	Motor selection, bit 4	High	Low	-
	05	Motor selection, bit 5	High	Low	-
	06	Motor selection, bit 6	High	Low	-
	07	Motor selection, bit 7	High	Low	-
	08	Motor selection, bit 8	High	Low	-
	09	Motor selection, bit 9	High	Low	-
	10	Motor selection, bit 10	High	Low	-
	11	Motor selection, bit 11	High	Low	-
	12	Motor selection, bit 12	High	Low	-
	13	Motor selection, bit 13	High	Low	-
	14	Motor selection, bit 14	High	Low	-
	15	Motor selection, bit 15	High	Low	-

Dependency: Refer to: p0827

p0831[0...15]	BI: Motor changeover, contactor feedback / Mot_chg cont fdbk		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8575
	P-Group: Motor	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	<p>Sets the signal source for the feedback signal of the contactors when changing over motors. There is a fixed inter-relationship between energizing the contactor and the feedback signal.</p> <p>Example:</p> <p>A changeover is to be made between MDS0 (motor 0) and MDS1 (motor 1). The contactors should be switched using bit 4 (contactor 0) and 5 (contactor 1). The changeover should be made with an interconnection of the feedback signal.</p> <p>Implementation:</p> <p>MDS0: p0827[0] = 4, interconnect output to switch contactor 0 to r0830.4, p0831[4] = "input, feedback signal, contactor 0"</p> <p>MDS1: p0827[1] = 5, interconnect output to switch contactor 1 to r0830.5, p0831[5] = "input, feedback signal, contactor 1"</p> <p>The following sequence applies when changing over from MDS0 to MDS1:</p> <ol style="list-style-type: none"> 1. The status bit p0830.4 is deleted. When the feedback signal (p0831[4]) is connected, the system waits until the feedback signal "contactor open" is displayed. If the feedback signal is not connected, then the system waits for the switch-off interlocking time of 320 ms. 2. The status bit p0830.5 is set. If the feedback signal (p0831[5]) is connected, the system waits until the feedback signal "contactor closed" is displayed. If the feedback signal is not connected, then the system waits for the switch-on interlocking time of 160 ms. 		
Index:	<p>[0] = Feedback signal, contactor 0 [1] = Feedback signal, contactor 1 [2] = Feedback signal, contactor 2 [3] = Feedback signal, contactor 3 [4] = Feedback signal, contactor 4 [5] = Feedback signal, contactor 5 [6] = Feedback signal, contactor 6 [7] = Feedback signal, contactor 7 [8] = Feedback signal, contactor 8 [9] = Feedback signal, contactor 9 [10] = Feedback signal, contactor 10 [11] = Feedback signal, contactor 11 [12] = Feedback signal, contactor 12 [13] = Feedback signal, contactor 13 [14] = Feedback signal, contactor 14 [15] = Feedback signal, contactor 15</p>		

r0832 CO/BO: Mot. changeover, contactor feedback sig. status word / Mot_chng fdbk ZSW

SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8575
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Displays the status word of the contactor feedback signals when changing over a motor.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Feedback signal, contactor 0	Closed	Opened	-
	01	Feedback signal, contactor 1	Closed	Opened	-
	02	Feedback signal, contactor 2	Closed	Opened	-
	03	Feedback signal, contactor 3	Closed	Opened	-
	04	Feedback signal, contactor 4	Closed	Opened	-
	05	Feedback signal, contactor 5	Closed	Opened	-
	06	Feedback signal, contactor 6	Closed	Opened	-
	07	Feedback signal, contactor 7	Closed	Opened	-
	08	Feedback signal, contactor 8	Closed	Opened	-
	09	Feedback signal, contactor 9	Closed	Opened	-
	10	Feedback signal, contactor 10	Closed	Opened	-
	11	Feedback signal, contactor 11	Closed	Opened	-
	12	Feedback signal, contactor 12	Closed	Opened	-
	13	Feedback signal, contactor 13	Closed	Opened	-
	14	Feedback signal, contactor 14	Closed	Opened	-
	15	Feedback signal, contactor 15	Closed	Opened	-

Dependency: Refer to: p0831

p0833 Data set changeover configuration / DS_chng config

SERVO	Can be changed: C2(15), U		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8575
	P-Group: Data sets	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Sets the configuration for the motor and encoder changeover.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Contactor changeover from the applica- tion/drive	application	Drive	-
	01	Pulse cancellation by application/drive	application	Drive	-
	02	Suppress drive parking for EDS changeover	Yes	No	-

Note: For VECTOR, the following applies:

The "flying restart" function should be activated (p1200) when changing-over to a motor that is already running.

Re bit 00:

When the bit is set and the motor has to be changed over, then p0827 must be set differently in the appropriate motor data sets.

Re bit 02:

The bit defines whether, for an EDS changeover, the status signal Gn_ZSW.14 is suppressed (parking encoder active).

p0833	Data set changeover configuration / DS_chng config			
VECTOR	Can be changed: C2(15), U		Access level: 2	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8575	
	P-Group: Data sets	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0010 bin	
Description:	Sets the configuration for the motor and encoder changeover.			
Bit field:	Bit	Signal name	1 signal	0 signal FP
	00	Contactor changeover from the application/drive	application	Drive -
	01	Pulse cancellation by application/drive	application	Drive -
	02	Suppress drive parking for EDS changeover	Yes	No -
Note:	For VECTOR, the following applies: The "flying restart" function should be activated (p1200) when changing-over to a motor that is already running. Re bit 00: When the bit is set and the motor has to be changed over, then p0827 must be set differently in the appropriate motor data sets. Re bit 02: The bit defines whether, for an EDS changeover, the status signal Gn_ZSW.14 is suppressed (parking encoder active).			
r0835	CO/BO: Motor data set changeover status word / MDS_chngov ZSW			
SERVO, VECTOR	Can be changed: -		Access level: 2	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8575	
	P-Group: Displays, signals	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0000 bin	
Description:	Displays the status word for the motor data set changeover.			
Bit field:	Bit	Signal name	1 signal	0 signal FP
	00	Motor data set changeover active	active	Not active 8575
r0836	CO/BO: Command Data Set CDS selected / CDS selected			
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -		Access level: 2	
	Data type: Unsigned8	Dynamic index: -	Function diagram: 1530, 8560	
	P-Group: Displays, signals	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0000 bin	
Description:	Displays the Command Data Set (CDS) selected using p0810 ... p0813.			
Bit field:	Bit	Signal name	1 signal	0 signal FP
	00	CDS select. bit 0	On	Off -
	01	CDS select. bit 1	On	Off -
	02	CDS select. bit 2	On	Off -
	03	CDS select. bit 3	On	Off -
Dependency:	Refer to: r0050, p0810, p0811			
Note:	The currently effective command data set is displayed in r0050.			

r0837	CO/BO: Drive Data Set DDS selected / DDS selected				
SERVO, TM41, VEC-TOR	Can be changed: -	Dynamic index: -	Access level: 2		
	Data type: Unsigned8	Units group: -	Function diagram: 8565		
	P-Group: Displays, signals		Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the Drive Data Set (DDS) selected using p0820 ... p0824.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DDS select. bit 0	On	Off	-
	01	DDS select. bit 1	On	Off	-
	02	DDS select. bit 2	On	Off	-
	03	DDS select. bit 3	On	Off	-
	04	DDS select. bit 4	On	Off	-
Dependency:	Refer to: r0051, p0820, p0821, p0822, p0823, p0824				
Note:	If there is only one data set, then a value of 0 is displayed in this parameter and not the selection via binector inputs.				
r0838[0...3]	Motor/encoder data set selected / MDS/EDS selected				
SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 2		
	Data type: Unsigned8	Units group: -	Function diagram: 8565		
	P-Group: Displays, signals		Unit selection: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the selected Motor Data Set (MDS) and the selected Encoder Data Sets (EDS).				
Index:	[0] = Motor Data Set MDS selected [1] = Encoder 1 Encoder Data Set EDS selected [2] = Encoder 2 Encoder Data Set EDS selected [3] = Encoder 3 Encoder Data Set EDS selected				
Dependency:	Refer to: r0049, p0186, p0187, p0188, p0189				
Note:	Value 99 means the following: No encoder assigned (not configured).				
p0840[0...n]	BI: ON/OFF1 / ON/OFF1				
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3		
	Data type: Unsigned32	Units group: -	Function diagram: 2501, 2610, 8720, 8920		
	P-Group: Commands		Unit selection: -		
	Min	Max	Factory setting		
	-	-	0		
Description:	Sets the signal source for control word 1 bit 0 (ON/OFF1).				
Recommendation:	When the signal source is set, this does not trigger a response - but only a signal change of the source.				
Dependency:	Refer to: p1055, p1056				
Notice:	For BI: p0840 = 0 signal, the motor can be moved, jogging using BI: p1055 or BI: p1056. The command "ON/OFF1" can be issued using BI: p0840 or using BI: p1055/p1056. Only the signal source that was used to power-up can also be used to power-down again.				

Note: For drives with closed-loop speed control (p1300 = 20, 21), the following applies:
 Bit 0 = 0: OFF1 (braking with the ramp-function generator, then pulse cancellation and power-on inhibit)
 For drives with closed-loop torque control (p1300 = 22, 23), the following applies:
 Bit 0 = 0: Immediate pulse cancellation
 For drives with closed-loop torque control (activated using p1501), the following applies:
 Bit 0 = 0: No dedicated braking response, but pulse cancellation when standstill is detected (p1226, p1227)
 For drives with closed-loop speed/torque control, the following applies:
 Bit 0 = 0/1: ON (pulses can be enabled)
 For active infeeds (Active Line Module and Smart Line Module) the following applies:
 Bit 0 = 0: OFF1 (reduce Vdc along the ramp, then pulse cancellation and pre-charging contactor/line contactor open)
 Bit 0 = 0/1: ON (pre-charging contactor/line contactor closed, pulses can be enabled)
 For passive infeeds (Basic Line Module) the following applies:
 Bit 0 = 0: OFF1 (pre-charging contactor/line contactor open)
 Bit 0 = 0/1: ON (pre-charging contactor/line contactor closed)
 r0863.1 of a drive can also be selected as signal source.

p0840	BI: ON/OFF1 / ON/OFF1		
TM41	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for control word 1 bit 0 (ON/OFF1).		
Dependency:	Refer to: p1055, p1056		
Notice:	For BI: p0840 = 0 signal, the motor can be moved, jogging using BI: p1055 or BI: p1056. The command "ON/OFF1" can be issued using BI: p0840 or using BI: p1055/p1056. Only the signal source that was used to power-up can also be used to power-down again.		
Note:	Bit 0 = 0: OFF1 (pulse cancellation and power-on inhibit) Bit 0 = 0/1: ON (pulses can be enabled)		


p0844[0...n]	BI: 1. OFF2 / 1. OFF2		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2501, 8720, 8920
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1


Description: Sets the signal source for the 1st OC/OFF2.
 The AND logic operation of the 1st OC/OFF2 and 2nd OC/OFF2 results in control word 1, bit 1 (OC/OFF2).
 When "master control from PC" is activated, this binector input is ineffective.

Caution:



Note: For drives, the following applies:
 Bit 1 = 0: OFF2 (immediate pulse cancellation and power-on inhibit)
 Bit 1 = 1: No OFF2 (enable is possible)
 For infeed units, the following applies:
 Bit 1 = 0: OFF2 (immediate pulse cancellation for active infeed modules and Smart Line Modules, pre-charging contactor/line contactor open and power-on inhibit)
 Bit 1 = 1: No OFF2 (enable is possible)
 OC: Operating condition

p0844	BI: OFF2 / OFF2		
TM41	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for control word 1, bit 1 (OC/OFF2).		
Note:	Bit 1 = 0: OFF2 (immediate pulse cancellation and power-on inhibit) Bit 1 = 1: No OFF2 (enable is possible) OC: Operating condition		
p0845[0...n]	BI: 2. OFF2 / 2. OFF2		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2501, 8720, 8920
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the 2nd OC/OFF2. The AND logic operation of the 1st OC/OFF2 and 2nd OC/OFF2 results in control word 1, bit 1 (OC/OFF2).		
Note:	For drives, the following applies: Bit 1 = 0: OFF2 (immediate pulse cancellation and power-on inhibit) Bit 1 = 1: No OFF2 (enable is possible) For infeed units, the following applies: Bit 1 = 0: OFF2 (immediate pulse cancellation for active infeed modules and Smart Line Modules, pre-charging con- tactor/line contactor open and power-on inhibit) Bit 1 = 1: No OFF2 (enable is possible) OC: Operating condition		
p0848[0...n]	BI: 1. OFF3 / 1. OFF3		
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2501
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the 1st OC/OFF3. The AND logic operation of the 1st OC/OFF3 and 2nd OC/OFF3 results in control word 1, bit 2 (OC/OFF3).		
Caution:	When "master control from PC" is activated, this binector input is ineffective.		
			
Note:	Bit 2 = 0: OFF3 (braking along the OFF3 ramp (p1135), then pulse cancellation and power-on inhibit) Bit 2 = 1: No OFF3 (enable is possible) OC: Operating condition		

p0848	BI: OFF3 / OFF3			
TM41	Can be changed: T			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		1
Description:	Sets the signal source for control word 1, bit 2 (OC/OFF3).			
Note:	Bit 2 = 0: OFF3 (pulse cancellation and power-on inhibit) Bit 2 = 1: No OFF3 (enable is possible) OC: Operating condition			
p0849[0...n]	BI: 2. OFF3 / 2. OFF3			
SERVO, VECTOR	Can be changed: T			Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170		Function diagram: 2501
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		1
Description:	Sets the signal source for the 2nd OC/OFF3. The AND logic operation of the 1st OC/OFF3 and 2nd OC/OFF3 results in control word 1, bit 2 (OC/OFF3).			
Note:	Bit 2 = 0: OFF3 (braking along the OFF3 ramp (p1135), then pulse cancellation and power-on inhibit) Bit 2 = 1: No OFF3 (enable is possible) OC: Operating condition			
p0852[0...n]	BI: Enable operation / Enable operation			
A_INF, SERVO, S_INF, VECTOR	Can be changed: T			Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170		Function diagram: 2442, 2443, 2501, 8920
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		1
Description:	Sets the signal source for control word 1 bit 3 (enable operation)			
Caution:	When "master control from PC" is activated, this binector input is ineffective.			
				
Note:	Bit 3 = 0: Inhibit operation (cancel pulses) Bit 3 = 1: Enable operation (pulses can be enabled)			
p0852	BI: Enable operation / Enable operation			
TM41	Can be changed: T			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		1
Description:	Sets the signal source for control word 1 bit 3 (enable operation)			
Note:	Bit 3 = 0: Inhibit operation (cancel pulses) Bit 3 = 1: Enable operation (pulses can be enabled)			

p0854[0...n]	BI: Master ctrl by PLC / Master ctrl by PLC		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2501, 2442, 2443, 8720, 8920
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 10 (PLC control).		
Note:	Bit 10 = 0: No control from PLC Bit 10 = 1: Control from PLC This bit is used to initiate a response for the drives when the control fails (F07220). If there is not control available, then BI: p0854 should be set to a 1 signal.		
p0855[0...n]	BI: Unconditionally release holding brake / Uncond open brake		
SERVO, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2501, 2701, 2707
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the command "unconditionally open holding brake".		
Dependency:	Refer to: p0858		
Note:	The signal via BI: p0858 (unconditionally close holding brake) has a higher priority than via BI: p0855 (unconditionally open holding brake).		
p0856[0...n]	BI: Enable speed controller / Enable n_ctrl		
SERVO, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2501, 2701
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the command "enable speed controller" (r0898.12). 0 signal: Set the I component and speed controller output to zero. 1 signal: Enable speed controller.		
Dependency:	Refer to: r0898		
Note:	If "enable speed controller" is withdrawn, then if a brake being used, then it is closed. If "speed controller enable" is withdrawn, the pulses are not cancelled.		

p0857	Power unit monitoring time / LT t_monit		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 2610, 8932, 8964
	P-Group: Commands	Units group: -	Unit selection: -
	Min 100.0 [ms]	Max 60000.0 [ms]	Factory setting 6000.0 [ms]
Description:	Sets the monitoring time for the power unit. The following applies for infeeds and drives: The monitoring time is started after an 0/1 edge of the ON/OFF1 command. If the power unit does not return a READY signal within the monitoring time, then fault F06000 (infeeds) or F07802 (drives) is output. For drives, the following also applies: After the pulse enable (operation enabled, p0852), the monitoring time is re-started. If the infeed does not signal ready to the drive within the monitoring time (using BI: p0864 of the drive), fault F07840 is initiated.		
Dependency:	Refer to: F06000, F07802, F07840, F30027		
Notice:	The time to pre-charge the DC link is monitored in the power unit and cannot be changed. The maximum duration of the pre-charging depends on the power class and the power unit design. The monitoring time for the pre-charging is started after the 0/1 edge of the ON/OFF1 command. Fault F30027 is output when the maximum pre-charging duration is exceeded.		
Note:	The pre-assignment (default) value for p0857 depends on the power class and the design of the power unit. The monitoring time for the ready signal of the power unit includes the time to pre-charge the DC link and, if relevant, the de-bounce time of the contactors. If an excessively low value is entered into p0857, then after enable, this results in a fault.		
p0858[0...n]	BI: Unconditionally close holding brake / Uncond close brake		
SERVO	Can be changed: T	Dynamic index: CDS, p0170	Access level: 2
	Data type: Unsigned32		Function diagram: 2501, 2701, 2707
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 9719.13
Description:	Sets the signal source for the command "unconditionally close holding brake".		
Dependency:	Refer to: p0855		
Note:	The signal via BI: p0858 (unconditionally close holding brake) has a higher priority than via BI: p0855 (unconditionally open holding brake). For a 1 signal via BI: p0858, the command "unconditionally close the holding brake" is executed and internally a zero setpoint is entered.		
p0858[0...n]	BI: Unconditionally close holding brake / Uncond close brake		
VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 2
	Data type: Unsigned32		Function diagram: 2501, 2701, 2707
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the command "unconditionally close holding brake".		
Dependency:	Refer to: p0855		
Note:	The signal via BI: p0858 (unconditionally close holding brake) has a higher priority than via BI: p0855 (unconditionally open holding brake). For a 1 signal via BI: p0858, the command "unconditionally close the holding brake" is executed and internally a zero setpoint is entered.		

p0860	BI: Line cont. fdbk sig / Line contact feedb		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 8734, 8934
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 863.1
Description:	Sets the signal source for the feedback signal from the line contactor.		
Recommendation:	When the monitoring is activated (BI: p0860 not equal to r0863.1), then to control the line contactor, signal BO: r0863.1 of its own drive object should be used.		
Dependency:	Refer to: p0861, r0863 Refer to: F07300		
Notice:	The line contactor monitoring is de-activated if the control signal of the particular drive object is set as the signal source for the feedback signal of the line contactor (BI: p0860 = r0863.1).		
Note:	The state of the line contactor is monitored depending on signal BO: r0863.1. When the monitoring is activated (BI: p0860 not equal to r0863.1), fault F07300 is then also output if the contactor is closed before it is controlled using r0863.1.		
p0861	Line contactor monitoring time / LineContact. t_mon		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 8734, 8934
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0 [ms]	Max 5000 [ms]	Factory setting 100 [ms]
Description:	Sets the monitoring time of the line contactor. This time starts each time that the line contactor switches (r0863.1). If a feedback signal is not received from the line contactor within the time, a message is output.		
Dependency:	Refer to: p0860, r0863 Refer to: F07300		
Note:	The monitoring function is disabled for the factory setting of p0860.		
p0862	Power unit ON delay / LT t_on		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 2610, 8932
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0 [ms]	Max 65000 [ms]	Factory setting 0 [ms]
Description:	Sets the delay time for the control command of the power unit and a line contactor, if used.		
Note:	This means that it is possible to realize a shifted (delayed) pre-charging or power-on using a single ON command. When the infeed units are active, before the line contactor is closed, an offset adjustment of the current measurement is carried-out for a duration of 120 ms (p3491).		

r0863	CO/BO: Drive coupling status word/control word / CoupleZSW/STW			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -	Dynamic index: -	Access level: 2	
	Data type: Unsigned16		Function diagram: 1773, 1774	
	P-Group: Commands	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the status and control words of the drive coupling.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Closed-loop control operation	Yes	No
	01	Energize contactor	Yes	No
	02	Infeed line supply failure	Yes	No
				FP 8732, 8932 2610, 8734, 8934 -
Dependency:	Refer to: p0864			
Note:	Bit 0 signals that the infeed is ready. Bit 1 is used to control an external line contactor. When the operating signal is transferred via BO: r0863.0 this allows several drives to start (run-up) staggered over time when they are simultaneously powered-up. To realize this, the following connections/interconnections are required: Drive 1: Internconnect BI: p0864 with BO: r0863.0 of the infeed Drive 2: Internconnect BI: p0864 with BO: r0863.0 of drive 1 Drive 3: Internconnect BI: p0864 with BO: r0863.0 of drive 2, etc. The first drive only transfers the operating signal to the next drive after it has reached its ready condition.			
p0864	BI: Infeed operation / INF operation			
SERVO, VECTOR	Can be changed: T	Dynamic index: -	Access level: 2	
	Data type: Unsigned32		Function diagram: 1773, 1774, 2610	
	P-Group: Commands	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the signal source for the operating signal of the infeed (e.g. BO: r0863.0).			
Dependency:	Refer to: r0863			
Note:	The sequence control of a servo/vector drive requires this signal. The following applies for an infeed without DRIVE-CLiQ: For these infeeds, the "ready" signal is available via an output terminal. This signal must be connected to a digital input. The drives supplied from this infeed must use this signal as ready signal (BI: p0864 = digital input).			
r0873	CO/BO: Infeed, total operation / INF total oper			
B_INF, S_INF	Can be changed: -	Dynamic index: -	Access level: 2	
	Data type: Unsigned16		Function diagram: -	
	P-Group: Commands	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting -	
Description:	Displays the operational readiness of the infeeds when using Smart Line Module (SLM) and Basic Line Module (BLM) together (mixed operation). In order that signal BO: r0873 is available at one of the infeeds, then BI: p0874 of the one infeed must be interconnected to BO: r0863.0 of the other infeed.			
Dependency:	Refer to: r0863, p0874			
Note:	Mixed operation is not possible with the Active Line Module (ALM)!			

p0874	BI: Smart/ Basic Line Module operation / SLM/BLM operation			
B_INF, S_INF	Can be changed: T			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0
Description:	Setting to interconnect the ready signal for mixed operation of Smart Line Module (SLM) and Basic Line Module (BLM). In order that signal BO: r0873 is available at one of the infeeds, then BI: p0874 of the one infeed must be interconnected to BO: r0863.0 of the other infeed.			
Dependency:	Refer to: r0863, r0873			
Note:	Mixed operation is not possible with the Active Line Module (ALM)!			
p0895[0...n]	BI: Activate/de-activate power unit components / LT_comp act/de-act			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: T			Access level: 1
	Data type: Unsigned32	Dynamic index: PDS, p0120		Function diagram: -
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		1
Description:	Sets the signal source to activate/de-activate a power unit component.			
Dependency:	Refer to: p0125, r0126 Refer to: A05054			
Note:	The power unit is only de-activated when the pulses are cancelled.			
r0896	BO: Parking axis, status word / Parking axis, ZSW			
SERVO, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned8	Dynamic index: -		Function diagram: -
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the status word for the "parking axis" function.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Parking axis active	Yes	No
Dependency:	Refer to: p0897			
p0897	BI: Parking axis selection / Parking axis sel			
SERVO, VECTOR	Can be changed: T			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0
Description:	Sets the signal source to select the "parking axis" function.			
Dependency:	Refer to: r0896			
Note:	After it has been selected the "parking axis" function only becomes active when the pulses are cancelled.			

r0898		CO/BO: Control word drive object 1 / STW DO1		
CU_S	Can be changed: -			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the control word of drive object 1 (Control Unit).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Synchronization signal SYN	Yes	No
	01	Real time synchronization PING	Yes	No
	07	Acknowledge fault	Yes	No
	12	Master sign-of-life bit 0	Yes	No
	13	Master sign-of-life bit 1	Yes	No
	14	Master sign-of-life bit 2	Yes	No
	15	Master sign-of-life bit 3	Yes	No

r0898		CO/BO: Control word sequence control infeed / STW seq_ctrl INF		
A_INF, S_INF	Can be changed: -			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: 1530, 8920
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays control word 1 of the infeed.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	ON/OFF1	Yes	No
	01	OC / OFF2	Yes	No
	03	Enable operation	Yes	No
	05	Inhibit motoring operation	Yes	No
	06	Inhibit regenerating	Yes	No
	10	Master ctrl by PLC	Yes	No
Note:	OC: Operating condition			

r0898		CO/BO: Control word sequence control / STW seq_ctrl		
SERVO, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: 1530, 2501
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the control word for the sequence control.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	ON/OFF1	Yes	No
	01	OC / OFF2	Yes	No
	02	OC / OFF3	Yes	No
	03	Enable operation	Yes	No
	04	Enables the ramp-function generator	Yes	No
	05	Freeze ramp-function generator	No	Yes
	06	Enable speed setpoint	Yes	No
	07	Command, open brake	Yes	No
	08	Jog 1	Yes	No
	09	Jog 2	Yes	No
	10	Master ctrl by PLC	Yes	No
	12	Speed controller enable	Yes	No
	14	Command, close brake	Yes	No

r0898	CO/BO: Control word sequence control infeed / STW seq_ctrl INF		
B_INF	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays control word 1 of the infeed.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	ON/OFF1	Yes No -
	01	OC / OFF2	Yes No -
	10	Master ctrl by PLC	Yes No -
Note:	OC: Operating condition		

r0898	CO/BO: Control word sequence control / STW seq_ctrl		
TM41	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1530
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays the control word for the sequence control.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	ON/OFF1	Yes No -
	01	OC / OFF2	Yes No -
	02	OC / OFF3	Yes No -
	03	Enable operation	Yes No -
	04	Enables the ramp-function generator	Yes No -
	05	Start ramp-function generator	Yes No -
	06	Enable speed setpoint	Yes No -
	07	Acknowledge fault	Yes No -
	13	Enable zero mark	Yes No -
Note:	OC: Operating condition		

r0899	CO/BO: Status word drive object 1 / ZSW DO1		
CU_S	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays the status word from drive object 1 (Control Unit).		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	03	Fault present	Yes No -
	07	Alarm present	Yes No -
	08	System time synchronized	Yes No -
	12	Slave sign-of-life bit 0	Yes No -
	13	Slave sign-of-life bit 1	Yes No -
	14	Slave sign-of-life bit 2	Yes No -
	15	Slave sign-of-life bit 3	Yes No -

r0899 CO/BO: Status word sequence control infeed / ZSW seq_ctrl INF

A_INF, S_INF

Can be changed: -**Access level:** 2**Data type:** Unsigned16**Dynamic index:** -**Function diagram:** 1530,
8926**P-Group:** Displays, signals**Units group:** -**Unit selection:** -**Min****Max****Factory setting**
0000 bin**Description:** Displays the status word of the infeed sequence control.**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
00	Ready to power up	Yes	No	-
01	Ready	Yes	No	-
02	Operation enabled	Yes	No	-
04	No OFF2 active	OFF2 inactive	OFF2 active	-
06	Power-on inhibit	Yes	No	-
09	Control requested	Yes	No	-
11	Pre-charging compl	Yes	No	-
12	Line contactor closed	Yes	No	8934

Note:

Re bit 12:

The feedback signal of a line contactor (auxiliary contact) can be interconnected via BI: p0860.

r0899 CO/BO: Status word sequence control / ZSW seq_ctrl

SERVO, VECTOR

Can be changed: -**Access level:** 2**Data type:** Unsigned16**Dynamic index:** -**Function diagram:** 1530,
2503**P-Group:** Displays, signals**Units group:** -**Unit selection:** -**Min****Max****Factory setting**
0000 bin**Description:** Displays the status word of the sequence control.**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
00	Ready to power up	Yes	No	-
01	Ready	Yes	No	-
02	Operation enabled	Yes	No	-
03	Jog active	Yes	No	-
04	No coasting active	OFF2 inactive	OFF2 active	-
05	No fast stop active	OFF3 inactive	OFF3 active	-
06	Power-on inhibit active	Yes	No	-
07	Drive ready	Yes	No	-
08	Controller enable	Yes	No	-
09	Control requested	Yes	No	-
11	Pulses enabled	Yes	No	-
12	Holding brake open	Yes	No	-
13	Command, close holding brake	Yes	No	-
14	Pulse enable from the brake control	Yes	No	-
15	Setpoint enable from the brake control	Yes	No	-

Note:

Re bit 0, 1, 2, 4, 5, 6, 9:

For PROFIdrive, these signals are used for status word 1.

Re bit 13:

When the "Safe Brake Control" (SBC) is activated and selected, the brake is no longer controlled using this signal.

Re bit 14, 15:

These signals are only of significance when the "extended brake control" function module is activated (r0108.14 = 1).

r0899		CO/BO: Status word sequence control infeed / ZSW seq_ctrl INF			
B_INF	Can be changed: -			Access level: 2	
	Data type: Unsigned16	Dynamic index: -		Function diagram: -	
	P-Group: Displays, signals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the status word of the infeed sequence control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Ready to power up	Yes	No	-
	01	Ready	Yes	No	-
	02	Operation enabled	Yes	No	-
	04	No OFF2 active	OFF2 inactive	OFF2 active	-
	06	Power-on inhibit	Yes	No	-
	09	Control requested	Yes	No	-
	11	Pre-charging compl	Yes	No	-
	12	Line contactor closed	Yes	No	-
Note:	Re bit 0, 1, 2, 4, 5, 6, 9: For PROFIdrive, these signals are used for status word 1.				

r0899		CO/BO: Status word sequence control / ZSW seq_ctrl			
TM41	Can be changed: -			Access level: 2	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 1530	
	P-Group: Displays, signals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the status word of the sequence control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Ready to power up	Yes	No	-
	01	Ready	Yes	No	-
	02	Operation enabled	Yes	No	-
	04	Coast down active	No	Yes	-
	05	Fast stop active	No	Yes	-
	06	Power-on inhibit	Yes	No	-
	08	Actual value in tolerance	Yes	No	-
	09	Control requested	Yes	No	-
	12	Holding brake closed	Yes	No	-
	13	Zero mark enabled	Yes	No	-
	14	Tracks A/B enabled	Yes	No	-
	15	Interface encoder emulation enabled	Yes	No	-
Note:	Re bit 0, 1, 2, 6: For PROFIdrive, these signals are used for status word 1.				

p0915[0...35]	TM17 PROFIBUS PZD setpoint assignment / TM17 PB PZD setpt		
TM17	Can be changed: T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0	Max 4265	Factory setting [0] 4201 [1] 4204 [2] 4211 [3] 4212 [4] 0 [5] 0 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0 [20] 0 [21] 0 [22] 0 [23] 0 [24] 0 [25] 0 [26] 0 [27] 0 [28] 0 [29] 0 [30] 0 [31] 0 [32] 0 [33] 0 [34] 0 [35] 0

Description: Is used to assign the process data received the PROFIBUS master (PZD, setpoints).

Values:

- 0: ZERO
- 4201: r4201 (system time for synchronization)
- 4204: r4204 (control digital output 0 ... 15)
- 4211: r4211 (edge mode digital input 0 ... 7)
- 4212: r4212 (edge mode digital input 8 ... 15)
- 4250: r4250 (set/resetting time, digital output 0)
- 4251: r4251 (set/resetting time, digital output 1)
- 4252: r4252 (set/resetting time, digital output 2)
- 4253: r4253 (set/resetting time, digital output 3)
- 4254: r4254 (set/resetting time, digital output 4)
- 4255: r4255 (set/resetting time, digital output 5)
- 4256: r4256 (set/resetting time, digital output 6)
- 4257: r4257 (set/resetting time, digital output 7)
- 4258: r4258 (set/resetting time, digital output 8)
- 4259: r4259 (set/resetting time, digital output 9)
- 4260: r4260 (set/resetting time, digital output 10)
- 4261: r4261 (set/resetting time, digital output 11)

4262: r4262 (set/resetting time, digital output 12)
4263: r4263 (set/resetting time, digital output 13)
4264: r4264 (set/resetting time, digital output 14)
4265: r4265 (set/resetting time, digital output 15)

Index:

[0] = PZD 1
[1] = PZD 2
[2] = PZD 3
[3] = PZD 4
[4] = PZD 5
[5] = PZD 6
[6] = PZD 7
[7] = PZD 8
[8] = PZD 9
[9] = PZD 10
[10] = PZD 11
[11] = PZD 12
[12] = PZD 13
[13] = PZD 14
[14] = PZD 15
[15] = PZD 16
[16] = PZD 17
[17] = PZD 18
[18] = PZD 19
[19] = PZD 20
[20] = PZD 21
[21] = PZD 22
[22] = PZD 23
[23] = PZD 24
[24] = PZD 25
[25] = PZD 26
[26] = PZD 27
[27] = PZD 28
[28] = PZD 29
[29] = PZD 30
[30] = PZD 31
[31] = PZD 32
[32] = PZD 33
[33] = PZD 34
[34] = PZD 35
[35] = PZD 36

Note:

Example:

The telegram for the setpoints should have the following process data (PZD) and assignments:

PZD 1 (r4201), PZD 2 (r4204), PZD 3 (r4250), PZD 4 (r4250)

The setpoint assignment must be realized as follows:

p0915[0] = 4201 - 16 bit

p0915[1] = 4204 - 16 bit

p0915[2] = 4250 - 32 bit - specified twice one after the other

p0915[3] = 4250 - 32 bit

p0915[4] = 0

...

p0915[35] = 0

p0915[0...29]	TM15 PROFIBUS PZD setpoint assignment / TM15 PB PZD setpt		
TM15	Can be changed: T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0	Max 4273	Factory setting [0] 4201 [1] 4204 [2] 4205 [3] 4211 [4] 4212 [5] 4213 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0 [20] 0 [21] 0 [22] 0 [23] 0 [24] 0 [25] 0 [26] 0 [27] 0 [28] 0 [29] 0
Description:	Is used to assign the process data received the PROFIBUS master (PZD, setpoints).		
Values:	0: ZERO 4201: r4201 (system time for synchronization) 4204: r4204 (control digital output 0 ... 15) 4205: r4205 (control digital output 16 ... 23) 4211: r4211 (edge mode digital input 0 ... 7) 4212: r4212 (edge mode digital input 8 ... 15) 4213: r4213 (edge mode digital input 16 ... 23) 4250: r4250 (set/resetting time, digital output 0) 4251: r4251 (set/resetting time, digital output 1) 4252: r4252 (set/resetting time, digital output 2) 4253: r4253 (set/resetting time, digital output 3) 4254: r4254 (set/resetting time, digital output 4) 4255: r4255 (set/resetting time, digital output 5) 4256: r4256 (set/resetting time, digital output 6) 4257: r4257 (set/resetting time, digital output 7) 4258: r4258 (set/resetting time, digital output 8) 4259: r4259 (set/resetting time, digital output 9) 4260: r4260 (set/resetting time, digital output 10) 4261: r4261 (set/resetting time, digital output 11) 4262: r4262 (set/resetting time, digital output 12) 4263: r4263 (set/resetting time, digital output 13) 4264: r4264 (set/resetting time, digital output 14) 4265: r4265 (set/resetting time, digital output 15) 4266: r4266 (set/resetting time, digital output 16)		

4267: r4267 (set/resetting time, digital output 17)
4268: r4268 (set/resetting time, digital output 18)
4269: r4269 (set/resetting time, digital output 19)
4270: r4270 (set/resetting time, digital output 20)
4271: r4271 (set/resetting time, digital output 21)
4272: r4272 (set/resetting time, digital output 22)
4273: r4273 (set/resetting time, digital output 23)

Index:

[0] = PZD 1
[1] = PZD 2
[2] = PZD 3
[3] = PZD 4
[4] = PZD 5
[5] = PZD 6
[6] = PZD 7
[7] = PZD 8
[8] = PZD 9
[9] = PZD 10
[10] = PZD 11
[11] = PZD 12
[12] = PZD 13
[13] = PZD 14
[14] = PZD 15
[15] = PZD 16
[16] = PZD 17
[17] = PZD 18
[18] = PZD 19
[19] = PZD 20
[20] = PZD 21
[21] = PZD 22
[22] = PZD 23
[23] = PZD 24
[24] = PZD 25
[25] = PZD 26
[26] = PZD 27
[27] = PZD 28
[28] = PZD 29
[29] = PZD 30

Note:

Example:

The telegram for the setpoints should have the following process data (PZD) and assignments:

PZD 1 (r4201), PZD 2 (r4204), PZD 3 (r4250)

The setpoint assignment must be realized as follows:

p0915[0] = 4201 - 16 bit

p0915[1] = 4204 - 16 bit

p0915[2] = 4250 - 16 bit

p0915[3] = 0

...

p0915[29] = 0

p0916[0...35]	TM17 PROFIBUS PZD actual value assignment / TM17 PB PZD actVal		
TM17	Can be changed: T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0	Max 4365	Factory setting [0] 4301 [1] 4304 [2] 4311 [3] 4312 [4] 0 [5] 0 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0 [20] 0 [21] 0 [22] 0 [23] 0 [24] 0 [25] 0 [26] 0 [27] 0 [28] 0 [29] 0 [30] 0 [31] 0 [32] 0 [33] 0 [34] 0 [35] 0

Description: Is used to assign the process data to be set to the PROFIBUS master (PZD, actual values).

Values:

- 0: ZERO
- 4301: r4301 (module synchronization)
- 4304: r4304 (status digital input 0 ... 15)
- 4311: r4311 (edge status digital input 0 ... 7)
- 4312: r4312 (edge status digital input 8 ... 15)
- 4350: r4350 (edge times digital input 0)
- 4351: r4351 (edge times digital input 1)
- 4352: r4352 (edge times digital input 2)
- 4353: r4353 (edge times digital input 3)
- 4354: r4354 (edge times digital input 4)
- 4355: r4355 (edge times digital input 5)
- 4356: r4356 (edge times digital input 6)
- 4357: r4357 (edge times digital input 7)
- 4358: r4358 (edge times digital input 8)
- 4359: r4359 (edge times digital input 9)
- 4360: r4360 (edge times digital input 10)
- 4361: r4361 (edge times digital input 11)

4362: r4362 (edge times digital input 12)
4363: r4363 (edge times digital input 13)
4364: r4364 (edge times digital input 14)
4365: r4365 (edge times digital input 15)

Index:

[0] = PZD 1
[1] = PZD 2
[2] = PZD 3
[3] = PZD 4
[4] = PZD 5
[5] = PZD 6
[6] = PZD 7
[7] = PZD 8
[8] = PZD 9
[9] = PZD 10
[10] = PZD 11
[11] = PZD 12
[12] = PZD 13
[13] = PZD 14
[14] = PZD 15
[15] = PZD 16
[16] = PZD 17
[17] = PZD 18
[18] = PZD 19
[19] = PZD 20
[20] = PZD 21
[21] = PZD 22
[22] = PZD 23
[23] = PZD 24
[24] = PZD 25
[25] = PZD 26
[26] = PZD 27
[27] = PZD 28
[28] = PZD 29
[29] = PZD 30
[30] = PZD 31
[31] = PZD 32
[32] = PZD 33
[33] = PZD 34
[34] = PZD 35
[35] = PZD 36

Note:

Example:

The telegram for the actual values should have the following process data (PZD) and assignments:

PZD 1 (r4301), PZD 2 (r4304), PZD 3 (r4350), PZD 4 (r4350)

The setpoint assignment must be realized as follows:

p0916[0] = 4301 - 16 bit

p0916[1] = 4304 - 16 bit

p0916[2] = 4350 - 32 bit - specified twice one after the other

p0916[3] = 4350 - 32 bit

p0916[4] = 0

...

p0916[35] = 0

p0916[0...29]	TM15 PROFIBUS PZD actual value assignment / TM15 PB PZD actVal		
TM15	Can be changed: T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0	Max 4373	Factory setting [0] 4301 [1] 4304 [2] 4305 [3] 4311 [4] 4312 [5] 4313 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0 [20] 0 [21] 0 [22] 0 [23] 0 [24] 0 [25] 0 [26] 0 [27] 0 [28] 0 [29] 0
Description:	Is used to assign the process data to be set to the PROFIBUS master (PZD, actual values).		
Values:	0: ZERO 4301: r4301 (module synchronization) 4304: r4304 (status digital input 0 ... 15) 4305: r4305 (status digital input 16 ... 23) 4311: r4311 (edge status digital input 0 ... 7) 4312: r4312 (edge status digital input 8 ... 15) 4313: r4313 (edge status digital input 16 ... 23) 4350: r4350 (edge times digital input 0) 4351: r4351 (edge times digital input 1) 4352: r4352 (edge times digital input 2) 4353: r4353 (edge times digital input 3) 4354: r4354 (edge times digital input 4) 4355: r4355 (edge times digital input 5) 4356: r4356 (edge times digital input 6) 4357: r4357 (edge times digital input 7) 4358: r4358 (edge times digital input 8) 4359: r4359 (edge times digital input 9) 4360: r4360 (edge times digital input 10) 4361: r4361 (edge times digital input 11) 4362: r4362 (edge times digital input 12) 4363: r4363 (edge times digital input 13) 4364: r4364 (edge times digital input 14) 4365: r4365 (edge times digital input 15)		

4366: r4366 (edge times digital input 16)
4367: r4367 (edge times digital input 17)
4368: r4368 (edge times digital input 18)
4369: r4369 (edge times digital input 19)
4370: r4370 (edge times digital input 20)
4371: r4371 (edge times digital input 21)
4372: r4372 (edge times digital input 22)
4373: r4373 (edge times digital input 23)

Index:

[0] = PZD 1
[1] = PZD 2
[2] = PZD 3
[3] = PZD 4
[4] = PZD 5
[5] = PZD 6
[6] = PZD 7
[7] = PZD 8
[8] = PZD 9
[9] = PZD 10
[10] = PZD 11
[11] = PZD 12
[12] = PZD 13
[13] = PZD 14
[14] = PZD 15
[15] = PZD 16
[16] = PZD 17
[17] = PZD 18
[18] = PZD 19
[19] = PZD 20
[20] = PZD 21
[21] = PZD 22
[22] = PZD 23
[23] = PZD 24
[24] = PZD 25
[25] = PZD 26
[26] = PZD 27
[27] = PZD 28
[28] = PZD 29
[29] = PZD 30

Note:

Example:

The telegram for the actual values should have the following process data (PZD) and assignments:

PZD 1 (r4301), PZD 2 (r4304), PZD 3 (r4350)

The actual value assignment must be implemented as follows:

p0916[0] = 4301 - 16 bit

p0916[1] = 4304 - 16 bit

p0916[2] = 4350 - 16 bit

p0916[3] = 0

...

p0916[29] = 0

p0918	PROFIBUS address / PROFIBUS address		
CU_S	Can be changed: T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min 1	Max 126	Factory setting 126
Description:	Displays or sets the PROFIBUS address for PROFIBUS interface (X126) on the Control Unit. The address can be set as follows: 1) Using the DIP switch power-up the Control Unit. --> p0918 can then only be read and displays the selected address. --> A change only becomes effective after a POWER ON. 2) Using p0918 --> only if all of the DIP switches - from S1 to S7 - are either set to ON or OFF. --> The address is saved in a non-volatile fashion using the function "copy from RAM to ROM". --> A change only becomes effective after a POWER ON.		
Note:	Permissible PROFIBUS addresses: 1 ... 126 Address 126 is intended for commissioning. Every PROFIBUS address change only becomes effective after a POWER ON.		
p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
CU_S	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 390	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either standard telegrams according to PROFIdrive can be selected or a telegram can be freely configured.		
Values:	390: SIEMENS telegram 390, PZD-1/1 391: SIEMENS telegram 391, PZD-3/7 392: SIEMENS telegram 392, PZD-3/15 999: Free telegram configuration with BICO		
p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
A_INF, B_INF, S_INF	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min 370	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either a manufacturer-specific telegram 370 can be selected or a telegram can be freely configured.		
Values:	370: SIEMENS telegram 370, PZD-1/1 999: Free telegram configuration with BICO		
Dependency:	Refer to: F01505, F01506		
Note:	If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.		

p0922		PROFIBUS PZD telegram selection / PB PZD telegr_eval		
SERVO	Can be changed: C2(1), T	Dynamic index: -	Access level: 1	
	Data type: Unsigned16		Function diagram: 1520, 2420, 2460, 2470	
	P-Group: Communications	Units group: -	Unit selection: -	
	Min 2	Max 999	Factory setting 999	
Description:	Sets the send and receive telegram for PROFIBUS. Either standard telegrams according to PROFIdrive, manufacturer-specified telegrams or telegrams that can be freely configured can be selected.			
Values:	2: Standard telegram 2, PZD-4/4 3: Standard telegram 3, PZD-5/9 4: Standard telegram 4, PZD-6/14 5: Standard telegram 5, PZD-9/9 6: Standard telegram 6, PZD-10/14 102: SIEMENS telegram 102, PZD-6/10 103: SIEMENS telegram 103, PZD-7/15 105: SIEMENS telegram 105, PZD-10/10 106: SIEMENS telegram 106, PZD-11/15 116: SIEMENS telegram 116, PZD-11/19 999: Free telegram configuration with BICO			
Dependency:	Refer to: p2038 Refer to: F01505, F01506			
Note:	For p0922 = 100 ... 199, p2038 is automatically set to 1 and p2038 can no longer be changed. This means that for these telegrams, the "SIMODRIVE 611 universal" interface mode is set and cannot be changed. If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.			
p0922		PROFIBUS PZD telegram selection / PB PZD telegr_eval		
SERVO (Pos ctrl)	Can be changed: C2(1), T	Dynamic index: -	Access level: 1	
	Data type: Unsigned16		Function diagram: 1520, 2420, 2460, 2470	
	P-Group: Communications	Units group: -	Unit selection: -	
	Min 999	Max 999	Factory setting 999	
Description:	Sets the send and receive telegram for PROFIBUS. Either standard telegrams according to PROFIdrive, manufacturer-specified telegrams or telegrams that can be freely configured can be selected.			
Values:	999: Free telegram configuration with BICO			
Dependency:	Refer to: p2038 Refer to: F01505, F01506			
Note:	For p0922 = 100 ... 199, p2038 is automatically set to 1 and p2038 can no longer be changed. This means that for these telegrams, the "SIMODRIVE 611 universal" interface mode is set and cannot be changed. If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.			

p0922		PROFIBUS PZD telegram selection / PB PZD telegr_eval		
SERVO (EPOS)	Can be changed: C2(1), T			Access level: 1
	Data type: Unsigned16		Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications		Units group: -	Unit selection: -
	Min 7		Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either standard telegrams according to PROFIdrive, manufacturer-specified telegrams or telegrams that can be freely configured can be selected.			
Values:	7: Standard telegram 7, PZD-2/2 110: SIEMENS telegram 110, PZD-12/7 999: Free telegram configuration with BICO			
Dependency:	Refer to: p2038 Refer to: F01505, F01506			
Note:	For p0922 = 100 ... 199, p2038 is automatically set to 1 and p2038 can no longer be changed. This means that for these telegrams, the "SIMODRIVE 611 universal" interface mode is set and cannot be changed. If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.			
p0922		PROFIBUS PZD telegram selection / PB PZD telegr_eval		
SERVO (Extended setp.)	Can be changed: C2(1), T			Access level: 1
	Data type: Unsigned16		Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications		Units group: -	Unit selection: -
	Min 1		Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either standard telegrams according to PROFIdrive, manufacturer-specified telegrams or telegrams that can be freely configured can be selected.			
Values:	1: Standard telegram 1, PZD-2/2 2: Standard telegram 2, PZD-4/4 3: Standard telegram 3, PZD-5/9 4: Standard telegram 4, PZD-6/14 5: Standard telegram 5, PZD-9/9 6: Standard telegram 6, PZD-10/14 102: SIEMENS telegram 102, PZD-6/10 103: SIEMENS telegram 103, PZD-7/15 105: SIEMENS telegram 105, PZD-10/10 106: SIEMENS telegram 106, PZD-11/15 116: SIEMENS telegram 116, PZD-11/19 999: Free telegram configuration with BICO			
Dependency:	Refer to: p2038 Refer to: F01505, F01506			
Note:	For p0922 = 100 ... 199, p2038 is automatically set to 1 and p2038 can no longer be changed. This means that for these telegrams, the "SIMODRIVE 611 universal" interface mode is set and cannot be changed. If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.			

p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
VECTOR	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min 1	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either a standard telegram 1 according to PROFIdrive can be selected or a telegram can be freely configured.		
Values:	1: Standard telegram 1, PZD-2/2 2: Standard telegram 2, PZD-4/4 20: Standard telegram 20, PZD-2/6 352: SIEMENS telegram 352, PZD-6/6 999: Free telegram configuration with BICO		
Dependency:	Refer to: F01505, F01506		
Caution:	Telegrams 2, 3 and 4 are not suitable for sensorless closed-loop vector control (p1300 = 20). For sensorless closed-loop vector control, it is necessary that the setpoint speed is entered at the ramp-function generator input (e.g. p1070) and not after the ramp-function generator (p1155).		
Note:	If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.		

p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
VECTOR (n/M)	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min 1	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either a standard telegram 1 according to PROFIdrive can be selected or a telegram can be freely configured.		
Values:	1: Standard telegram 1, PZD-2/2 2: Standard telegram 2, PZD-4/4 3: Standard telegram 3, PZD-5/9 4: Standard telegram 4, PZD-6/14 20: Standard telegram 20, PZD-2/6 352: SIEMENS telegram 352, PZD-6/6 999: Free telegram configuration with BICO		
Dependency:	Refer to: F01505, F01506		
Caution:	Telegrams 2, 3 and 4 are not suitable for sensorless closed-loop vector control (p1300 = 20). For sensorless closed-loop vector control, it is necessary that the setpoint speed is entered at the ramp-function generator input (e.g. p1070) and not after the ramp-function generator (p1155).		
Note:	If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.		

p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
VECTOR (Pos ctrl)	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min 2	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either a standard telegram 1 according to PROFIdrive can be selected or a telegram can be freely configured.		
Values:	2: Standard telegram 2, PZD-4/4 999: Free telegram configuration with BICO		
Dependency:	Refer to: F01505, F01506		
Caution:	Telegrams 2, 3 and 4 are not suitable for sensorless closed-loop vector control (p1300 = 20). For sensorless closed-loop vector control, it is necessary that the setpoint speed is entered at the ramp-function generator input (e.g. p1070) and not after the ramp-function generator (p1155).		
Note:	If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.		
p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
VECTOR (EPOS)	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min 7	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either a standard telegram 1 according to PROFIdrive can be selected or a telegram can be freely configured.		
Values:	7: Standard telegram 7, PZD-2/2 110: SIEMENS telegram 110, PZD-12/7 999: Free telegram configuration with BICO		
Dependency:	Refer to: F01505, F01506		
Caution:	Telegrams 2, 3 and 4 are not suitable for sensorless closed-loop vector control (p1300 = 20). For sensorless closed-loop vector control, it is necessary that the setpoint speed is entered at the ramp-function generator input (e.g. p1070) and not after the ramp-function generator (p1155).		
Note:	If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.		
p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
TM41	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1520, 2420, 2460, 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min 3	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Either a standard telegram 3 according to PROFIdrive can be selected or a telegram can be freely configured.		
Values:	3: Standard telegram 3, PZD-5/9 999: Free telegram configuration with BICO		
Dependency:	Refer to: F01505, F01506		
Note:	If a value is not equal to 999, a telegram is set and the automatically set interconnections in the telegram are inhibited. The inhibited interconnections can only be changed again if a value of 999 was set.		

p0922	PROFIBUS PZD telegram selection / PB PZD telegr_eval		
TM15, TM17	Can be changed: C2(1), T	Dynamic index: -	Access level: 1
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Communications		Unit selection: -
	Min 0	Max 0	Factory setting 0
Description:	Sets the send and receive telegram for PROFIBUS. Free telegram configuring is permanently set and cannot be changed.		
Values:	0: Free telegram configuring with P915/P916		
p0925	PROFIBUS clock synchronous sign-of-life tolerance / Master SoL_tol		
CU_S, SERVO, TM41, VECTOR (n/M)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: 2410
	P-Group: Communications		Unit selection: -
	Min 0	Max 65535	Factory setting 1
Description:	Number of tolerated consecutive sign-of-life errors of the clock synchronous PROFIBUS master. The sign-of-life signal is normally received in PZD4 (control word 2) from the master.		
Dependency:	Refer to: p2045, r2065 Refer to: F01912		
Note:	The sign-of-life monitoring is disabled for p0925 = 65535.		
r0930	PROFIBUS operating mode / PB operating mode		
SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the operating mode. 1: Closed-loop speed controlled operation with ramp-function generator 2: Closed-loop position controlled operation 3: Closed-loop speed controlled operation without ramp-function generator		
r0944	Counter for fault buffer changes / Fault buff change		
All objects	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: 8060
	P-Group: Messages		Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays fault buffer changes. This counter is incremented every time the fault buffer changes.		
Recommendation:	Used to check whether the fault buffer has been read out consistently.		
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109		

r0945[0...63] Fault code / Fault code

All objects	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16		Function diagram: 1750, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Displays the numbers of faults that have occurred.

Dependency: Refer to: r0947, r0948, r0949, r2109, r2130, r2133, r2136

Note: The buffer parameters are cyclically updated in the background (refer to status signal in r2139).

Fault buffer structure (general principle):

r0945[0], r0949[0], r0948[0], r2109[0] --> actual fault case, fault 1

.

.

.r0945[7], r0949[7], r0948[7], r2109[7] --> actual fault case, fault 8

r0945[8], r0949[8], r0948[8], r2109[8] --> 1st acknowledged fault case, fault 1

.

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r0945[15], r0949[15], r0948[15], r2109[15] --> 1st acknowledged fault case, fault 8

.

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r0945[56], r0949[56], r0948[56], r2109[56] --> 7th acknowledged fault case, fault 1

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r0945[63], r0949[63], r0948[63], r2109[63] --> 7th acknowledged fault case, fault 8

r0946[0...65534] Fault code list / Fault code list

All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Lists the fault codes stored in the drive unit.

The indices can only be accessed with a valid fault code.

Dependency: The parameter assigned to the fault code is entered in r0951 under the same index.

Refer to: r0951

r0947[0...63] Fault number / Fault number

All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: 1750, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: This parameter is identical to r0945.

r0948[0...63]	Fault time received in milliseconds / t_fault rcv ms		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1750, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the system runtime in milliseconds when the fault occurred.		
Dependency:	Refer to: r0945, r0947, r0949, r2109, r2114, r2130, r2133, r2136		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r0949[0...63]	Fault value / Fault value		
All objects	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: 1750, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays additional information about the fault that occurred (as integer number).		
Dependency:	Refer to: r0945, r0947, r0948, r2109, r2130, r2133, r2136		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r0951[0...65534]	Fault number list / Fault number list		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Lists parameters assigned to a fault.		
Dependency:	Refer to: r0946		

p0952	Fault cases, counter / Fault cases qty		
All objects	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1710, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Number of fault situations that have occurred since the last reset.		
Dependency:	The fault buffer is deleted (cleared) by setting p0952 to 0. Refer to: r0945, r0947, r0948, r0949, r2109, r2130, r2133, r2136		

r0963		PROFIBUS baud rate / PROFIBUS baud rate	
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	255	3
Values:	0: 9.6 kbit/s		
	1: 19.2 kbit/s		
	2: 93.75 kbit/s		
	3: 187.5 kbit/s		
	4: 500 kbit/s		
	6: 1.5 Mbit/s		
	7: 3 Mbit/s		
	8: 6 Mbit/s		
	9: 12 Mbit/s		
	10: 31.25 kbit/s		
	11: 45.45 kbit/s		
	255: Unknown		

r0964[0...6]		Device identification / Device ident.	
CU_S	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the device identification.		
Index:	[0] = Company (Siemens = 42) [1] = Device type [2] = Firmware version [3] = Firmware date (year) [4] = Firmware date (day/month) [5] = Number of drive objects [6] = Firmware patch/hot fix		
Note:	Example: r0964[0] = 42 --> SIEMENS r0964[1] = 5000 --> SINAMICS S CU320 r0964[1] = 5200 --> SINAMICS G CU320 r0964[2] = 102 --> first part of the firmware version V01.02 (second part, refer under index 6) r0964[3] = 2003 --> year 2003 r0964[4] = 1401 --> 14th of January r0964[5] = 4 --> 4 drive objects r0964[6] = 600 --> second part, firmware version (complete version: V01.02.06.00)		

r0965		PROFIBUS profile number / PB profile number	
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the PROFIBUS profile number and profile version. Constant value = 0303 hex. Byte 1: Profile number = 03 hex = PROFIdrive profile Byte 2: Profile version = 03 hex = Version 3		

p0969	System runtime relative / t_System relative		
CU_S	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1750, 8060
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min 0 [ms]	Max 4294967295 [ms]	Factory setting 0 [ms]
Description:	Displays the system runtime in ms since the last POWER ON.		
Note:	The value in p0969 can only be reset to 0. The value overflows after approx. 49 days.		
p0970	Reset infeed parameter / INF par reset		
A_INF, B_INF, S_INF	Can be changed: C2(30)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min 0	Max 100	Factory setting 0
Description:	The parameter is used to initiate that the parameters of an individual infeed unit are reset. The parameters of the basic commissioning (refer to p0009) are in this case not reset (p0107, p0108, p0121, p0170). These can only be reset using the factory setting of the complete drive unit (p0976). The sampling times (p0111, p0112, p0115) are only not reset if this results in a conflict with the basic clock cycle (p0110).		
Values:	0: not active 1: Starts a parameter reset 100: Starts a BICO interconnection reset		
Note:	A factory setting run can only be started if p0010 was first set to 30 (parameter reset). At the end of the calculations, p0970 is automatically set to 0.		
p0970	Reset drive parameters / Drive par reset		
SERVO, VECTOR	Can be changed: C2(30)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min 0	Max 100	Factory setting 0
Description:	The parameter is used to initiate that the parameters of an individual drive unit are reset. Parameters p0100, p0205 (only for VECTOR) and the parameters of the basic drive commissioning (p0009) are not reset (p0107, p0108, p0111, p0112, p0115, p0121, p0130, p0131, p0140, p0141, p0142, p0170, p0186 ... p0189). These can only be reset using the factory setting of the complete drive unit (p0976).		
Values:	0: not active 1: Starts a parameter reset 100: Starts a BICO interconnection reset		
Note:	A factory setting run can only be started if p0010 was first set to 30 (parameter reset). At the end of the calculations, p0970 is automatically set to 0.		

p0970 TB30 reset parameters / TB30 par reset

TB30	Can be changed: C2(30)	Access level: 2
	Data type: Unsigned16	Dynamic index: -
	P-Group: Factory settings	Function diagram: -
		Unit selection: -
	Min	Max
	0	100
		Factory setting
		0

Description: The parameter is used to initiate that the parameters are reset on Terminal Board 30 (TB30).
The sampling time p4099 is not reset if in so doing a conflict occurs with the basic clock cycle.
Parameter p0161 is not reset. It is only reset if the entire drive unit is reset to the factory settings (p0976).

Values:
0: not active
1: Starts a parameter reset
100: Starts a BICO interconnection reset

Note: A factory setting run can only be started if p0010 was first set to 30 (parameter reset).
At the end of the calculations, p0970 is automatically set to 0.

p0970 TM31 reset parameters / TM31 par reset

TM31	Can be changed: C2(30)	Access level: 2
	Data type: Unsigned16	Dynamic index: -
	P-Group: Factory settings	Function diagram: -
		Unit selection: -
	Min	Max
	0	100
		Factory setting
		0

Description: The parameter is used to initiate that the parameters are reset on Terminal Module 31 (TM31).
The sampling time p4099 is not reset if in so doing a conflict occurs with the basic clock cycle.
Parameter p0151 is not reset. It is only reset if the entire drive unit is reset to the factory settings (p0976).

Values:
0: not active
1: Starts a parameter reset
100: Starts a BICO interconnection reset

Dependency: Refer to: p0010

Note: A factory setting run can only be started if p0010 was first set to 30 (parameter reset).
At the end of the calculations, p0970 is automatically set to 0.

p0970 TM41 reset parameters / TM41 par reset

TM41	Can be changed: C2(30)	Access level: 2
	Data type: Unsigned16	Dynamic index: -
	P-Group: Factory settings	Function diagram: -
		Unit selection: -
	Min	Max
	0	100
		Factory setting
		0

Description: The parameter is used to initiate that the parameters are reset on Terminal Module 41 (TM41).
Parameter p0151 is not reset. It is only reset if the entire drive unit is reset to the factory settings (p0976).

Values:
0: not active
1: Starts a parameter reset
100: Starts a BICO interconnection reset

Dependency: Refer to: p0010

Note: A factory setting run can only be started if p0010 was first set to 30 (parameter reset).
At the end of the calculations, p0970 is automatically set to 0.

p0970	TM17 reset parameter / TM17 par reset		
TM17	Can be changed: C2(30)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min 0	Max 100	Factory setting 0
Description:	The parameter is used to initiate that the parameters are reset on Terminal Module 17 (TM17). Parameter p0151 is not reset. It is only reset if the entire drive unit is reset to the factory settings (p0976).		
Values:	0: not active 1: Starts a parameter reset 100: Starts a BICO interconnection reset		
Dependency:	Refer to: p0010		
Note:	A factory setting run can only be started if p0010 was first set to 30 (parameter reset). At the end of the calculations, p0970 is automatically set to 0.		

p0970	TM15 reset parameter / TM15 par reset		
TM15	Can be changed: C2(30)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min 0	Max 100	Factory setting 0
Description:	The parameter is used to initiate that the parameters are reset on Terminal Module 15 (TM15). Parameter p0151 is not reset. It is only reset if the entire drive unit is reset to the factory settings (p0976).		
Values:	0: not active 1: Starts a parameter reset 100: Starts a BICO interconnection reset		
Dependency:	Refer to: p0010		
Note:	A factory setting run can only be started if p0010 was first set to 30 (parameter reset). At the end of the calculations, p0970 is automatically set to 0.		

p0970	TM15DI/DO reset parameter / TM15D par reset		
TM15DI_DO	Can be changed: C2(30)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min 0	Max 100	Factory setting 100
Description:	The parameter is used to initiate that the parameters are reset on Terminal Module 15 (TM15). The sampling time p4099 is not reset if in so doing a conflict occurs with the basic clock cycle. Parameter p0151 is not reset. It is only reset if the entire drive unit is reset to the factory settings (p0976).		
Values:	0: not active 1: Starts a parameter reset 100: Starts a BICO interconnection reset		
Dependency:	Refer to: p0010		
Note:	A factory setting run can only be started if p0010 was first set to 30 (parameter reset). At the end of the calculations, p0970 is automatically set to 0.		

p0971	Save drive object parameters / Save drv_obj		
All objects	Can be changed: U, T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Saves the parameters of the particular drive object in the non-volatile memory (CompactFlash card).		
Values:	0: not active 1: Save drive object		
Dependency:	Refer to: p0977, p1960, p3845		
Caution:	The Control Unit power supply may only be powered-down after data has been saved (i.e. after data save has been started, wait until the parameter again has the value 0).		
Note:	Starting from the particular drive object, the following parameters are saved: CU3xx: Device-specific parameters and PROFIBUS device parameters. Other objects: Parameters of the actual object and PROFIBUS device parameters. Prerequisite: In order that the parameter of a drive object, saved with p0971 = 1, is read the next time that the Control Unit is booted, then all parameters must, as a minimum, have first been saved once with p0977 = 1.		

r0975[0...10]	Drive object identification / DO identification		
All objects	Can be changed: -		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the identification of the drive object.		
Index:	[0] = Company (Siemens = 42) [1] = Drive object type [2] = Firmware version [3] = Firmware date (year) [4] = Firmware date (day/month) [5] = PROFIdrive drive object, type class [6] = PROFIdrive drive object, sub-type Class 1 [7] = Reserved [8] = Reserved [9] = Reserved [10] = Firmware patch/hot fix		
Note:	Example: r0975[0] = 42 --> SIEMENS r0975[1] = 11 --> SERVO drive object type r0975[2] = 102 --> first part, firmware version V01.02 (second part, refer to index 10) r0975[3] = 2003 --> year 2003 r0975[4] = 1401 --> 14th of January r0975[5] = 1 --> PROFIdrive drive object, type class r0975[6] = 9 --> PROFIdrive drive object sub-type class 1 r0975[7] = 0 (reserved) r0975[8] = 0 (reserved) r0975[9] = 0 (reserved) r0975[10] = 600 --> second part, firmware version (complete version: V01.02.06.00)		

p0976			
Reset and load all parameters / Reset load all par			
CU_S	Can be changed: C1(30)		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1013	0
Description:	Resets or downloads all parameters of the drive system.		
Values:	<ul style="list-style-type: none"> 0: not active 1: Starts to reset all parameters to factory setting 2: Starts to download param. saved in non-volatile way w/ p0977 = 1 3: Start to download the volatile parameters from RAM 10: Starts to download param. saved in non-volatile way w/ p0977=10 11: Starts to download param. saved in non-volatile way w/ p0977=11 12: Starts to download param. saved in non-volatile way w/ p0977=12 20: Starts to download Siemens internal setting 20 21: Starts to download Siemens internal setting 21 22: Starts to download Siemens internal setting 22 23: Starts to download Siemens internal setting 23 24: Starts to download Siemens internal setting 24 25: Starts to download Siemens internal setting 25 26: Starts to download Siemens internal setting 26 100: Starts to reset all BICO interconnections 1011: Starts to download param. saved in volatile way w/ p0977 = 1011 1012: Starts to download param. saved in volatile way w/ p0977 = 1012 1013: Starts to download param. saved in volatile way w/ p0977 = 1013 		
Note:	<p>After all of the parameters have been reset to their factory setting, the system must commissioned for the first time again.</p> <p>Resetting or loading is realized in the non-volatile memory.</p> <p>Procedure:</p> <ol style="list-style-type: none"> 1. Set p0009 = 30 (parameter reset). 2. Set p0976 to "required value". The system is rebooted. <p>p0976 is automatically set to 0 and p0009 is automatically set to 1 after this has been carried-out.</p>		
p0977			
Save all parameters / Save all par			
CU_S	Can be changed: U, T		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Factory settings	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1013	0
Description:	Saves all parameters of the drive system to the non-volatile memory (CompactFlash card).		
Values:	<ul style="list-style-type: none"> 0: not active 1: Save in non-volatile fashion - downloaded at POWER ON 10: Save as opt. in non-vol. fashion - downloaded w/ p0976=10 11: Save as opt. in non-vol. fashion - downloaded w/ p0976=11 12: Save as opt. in non-vol. fashion - downloaded w/ p0976=12 20: Save in a non-volatile fashion as setting 20 (reserved) 21: Save in a non-volatile fashion as setting 21 (reserved) 22: Save in a non-volatile fashion as setting 22 (reserved) 23: Save in a non-volatile fashion as setting 23 (reserved) 24: Save in a non-volatile fashion as setting 24 (reserved) 25: Save in a non-volatile fashion as setting 25 (reserved) 26: Save in a non-volatile fashion as setting 26 (reserved) 1011: Save in volatile fashion, loaded with p0976=1011 1012: Save in volatile fashion, loaded with p0976=1012 1013: Save in volatile fashion, loaded with p0976=1013 		
Dependency:	Refer to: p0976, p1960, p3845		

Caution: The Control Unit power supply may only be powered-down after data has been saved (i.e. after data save has been started, wait until the parameter again has the value 0).

Note: Parameters saved with p0977 = 10, 11 or 12 can be downloaded again with p0976 = 10, 11 or 12.

p0978[0...16]	List of drive objects / List of the DO		
CU_S	Can be changed: C1(1)		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	255	[0] 1
			[1] 0
			[2] 0
			[3] 0
			[4] 0
			[5] 0
			[6] 0
			[7] 0
			[8] 0
			[9] 0
			[10] 0
			[11] 0
			[12] 0
			[13] 0
			[14] 0
			[15] 0
			[16] 0

Description: This parameter is an image of p0101 in conformance with PROFIdrive. Parameters p0101 and p0978 contain the following information:

- 1) The same number of drive objects
- 2) The same drive objects

In this sense, they are consistent.

Difference between p0101 and p0978:

p0978 can be re-sorted and a zero inserted in order to identify those drive objects that participate in the process data exchange and to define their sequence in the process data exchange. Drive objects that are listed after the first zero, are excluded from the process data exchange.

For p0978, in addition, the value 255 can be inserted a multiple number of times.

p0978[n] = 255 means: The drive object is visible for the PROFIBUS master and is empty (without any actual process data exchange). This allows cyclic communications of a PROFIBUS master with unchanged configuring to the drive units with a lower number of drive objects.

Dependency: Refer to: p0101, p0971, p0977

Note: p0978 cannot be changed when the drive system is first commissioned. The reason for this is that at this time the actual topology has still not been acknowledged (p0099 is still not equal to r0098 and p0009 is set to 0).

r0979[0...30] Encoder format PROFdrive / Encoder format			
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4010, 4704
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual position encoder used according to PROFdrive.		
Index:	<ul style="list-style-type: none"> [0] = Header [1] = Type, encoder 1 [2] = Resolution encod 1 [3] = Shift factor G1_XACT1 [4] = Shift factor G1_XACT2 [5] = Distinguishable revolutions encoder 1 [6] = Reserved [7] = Reserved [8] = Reserved [9] = Reserved [10] = Reserved [11] = Type, encoder 2 [12] = Resolution encod 2 [13] = Shift factor G2_XACT1 [14] = Shift factor G2_XACT2 [15] = Distinguishable revolutions encoder 2 [16] = Reserved [17] = Reserved [18] = Reserved [19] = Reserved [20] = Reserved [21] = Type, encoder 3 [22] = Resolution encod 3 [23] = Shift factor G3_XACT1 [24] = Shift factor G3_XACT2 [25] = Distinguishable revolutions encoder 3 [26] = Reserved [27] = Reserved [28] = Reserved [29] = Reserved [30] = Reserved 		
Note:	Information on the individual indices should be taken from the PROFdrive Profile Drive Technology.		

r0979[0...10]	Encoder format PROFIdrive / Encoder format		
TM41	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4010, 4704
	P-Group: Encoder	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual position encoder used according to PROFIdrive.		
Index:	[0] = Header [1] = Type, encoder 1 [2] = Resolution encod 1 [3] = Shift factor G1_XACT1 [4] = Shift factor G1_XACT2 [5] = Distinguishable revolutions encoder 1 [6] = Reserved [7] = Reserved [8] = Reserved [9] = Reserved [10] = Reserved		
Note:	Information on the individual indices should be taken from the PROFIdrive Profile Drive Technology.		
r0980[0...99]	List of existing parameters 1 / List avail par 1		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the parameters that exist for this drive.		
Dependency:	Refer to: r0981, r0989		
Note:	The existing parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here. In a long list, index 99 contains the parameter number at which position the list continues. This list completely comprises the following parameters: r0980[0...99], r0981[0...99] ... r0989[0...99] The parameters in this list are not displayed in the expert list of the commissioning software. However, they can be read from a higher-level control system (e.g. PROFIBUS master).		
r0981[0...99]	List of existing parameters 2 / List avail par 2		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the parameters that exist for this drive.		
Dependency:	Refer to: r0980, r0989		
Note:	The existing parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here. In a long list, index 99 contains the parameter number at which position the list continues. This list completely comprises the following parameters: r0980[0...99], r0981[0...99] ... r0989[0...99] The parameters in this list are not displayed in the expert list of the commissioning software. However, they can be read from a higher-level control system (e.g. PROFIBUS master).		

r0989[0...99]	List of existing parameters 10 / List avail par 10		
All objects	Can be changed: -	Dynamic index: -	Access level: 4
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	-	Factory setting
	-	-	-
Description:	Displays the parameters that exist for this drive.		
Dependency:	Refer to: r0980, r0981		
Note:	The existing parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here. This list completely comprises the following parameters: r0980[0...99], r0981[0...99] ... r0989[0...99] The parameters in this list are not displayed in the expert list of the commissioning software. However, they can be read from a higher-level control system (e.g. PROFIBUS master).		
r0990[0...99]	List of modified parameters 1 / List chang. par 1		
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	-	Factory setting
	-	-	-
Description:	Displays those parameters with a value other than the factory setting for this drive.		
Dependency:	Refer to: r0991, r0999		
Note:	Modified parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here. In a long list, index 99 contains the parameter number at which position the list continues. This list completely comprises the following parameters: r0990[0...99], r0991[0...99] ... r0999[0...99] The parameters in this list are not displayed in the expert list of the commissioning software. However, they can be read from a higher-level control system (e.g. PROFIBUS master).		
r0991[0...99]	List of modified parameters 2 / List chang. par 2		
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	-	Factory setting
	-	-	-
Description:	Displays those parameters with a value other than the factory setting for this drive.		
Dependency:	Refer to: r0990, r0999		
Note:	Modified parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here. In a long list, index 99 contains the parameter number at which position the list continues. This list completely comprises the following parameters: r0990[0...99], r0991[0...99] ... r0999[0...99] The parameters in this list are not displayed in the expert list of the commissioning software. However, they can be read from a higher-level control system (e.g. PROFIBUS master).		

r0999[0...99]	List of modified parameters 10 / List chang. par 10		
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	-	Factory setting
	-	-	-
Description:	Displays those parameters with a value other than the factory setting for this drive.		
Dependency:	Refer to: r0990, r0991		
Note:	Modified parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here. This list completely comprises the following parameters: r0990[0...99], r0991[0...99] ... r0999[0...99] The parameters in this list are not displayed in the expert list of the commissioning software. However, they can be read from a higher-level control system (e.g. PROFIBUS master).		
p1000[0...n]	Macro Connector Inputs (CI) for speed setpoints / Macro CI n_set		
SERVO, VECTOR	Can be changed: C2(1), T	Dynamic index: CDS, p0170	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Commands	Max	Unit selection: -
	Min	999999	Factory setting
	0	0	0
Description:	Runs the appropriate ACX file on the CompactFlash card. The Connector Inputs (CI) for the speed setpoints of the appropriate Command Data Set (CDS) are appropriately interconnected. The selected ACX file must be located in the following directory: ... /PMACROS/<drive object>/P1000/PMxxxxxx.ACX Example: p1000 = 6 --> the file PM000006.ACX is run.		
Dependency:	The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card. Refer to: p0015, p0700, p1500, r8572		
Notice:	No errors were issued during fast commissioning (p3900 = 1) when writing to parameters of the QUICK_IBN group!		
Note:	The macros in the specified directory are displayed in r8572. Macros available as standard are described in the technical documentation of the particular product. CI: Connector Input		
p1000[0...n]	Macro Connector Inputs (CI) for velocity setpoints / Macro CI v_set		
SERVO (Lin)	Can be changed: C2(1), T	Dynamic index: CDS, p0170	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Commands	Max	Unit selection: -
	Min	999999	Factory setting
	0	0	0
Description:	Runs the appropriate ACX file on the CompactFlash card. The Connector Inputs (CI) for the velocity setpoints of the appropriate Command Data Set (CDS) are appropriately interconnected. The selected ACX file must be located in the following directory: ... /PMACROS/<drive object>/P1000/PMxxxxxx.ACX Example: p1000 = 6 --> the file PM000006.ACX is run.		

Dependency: The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card.
Refer to: p0015, p0700, p1500, r8572

Notice: No errors were issued during fast commissioning (p3900 = 1) when writing to parameters of the QUICK_IBN group!

Note: The macros in the specified directory are displayed in r8572.
Macros available as standard are described in the technical documentation of the particular product.
CI: Connector Input

p1001[0...n] CO: Fixed speed setpoint 1 / n_set_fixed 1

SERVO (Extended setp.), VECTOR	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]

Description: Sets a value for the fixed speed / velocity setpoint 1.

Dependency: Refer to: p1020, p1021, p1022, p1023, r1024, r1197

Notice: A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.

p1001[0...n] CO: Fixed velocity setpoint 1 / n_set_fixed 1

SERVO (Extended setp., Lin)	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]

Description: Sets a value for the fixed speed / velocity setpoint 1.

Dependency: Refer to: p1020, p1021, p1022, p1023, r1024, r1197

Notice: A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.

p1002[0...n] CO: Fixed speed setpoint 2 / n_set_fixed 2

SERVO (Extended setp.), VECTOR	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]

Description: Sets a value for the fixed speed / velocity setpoint 2.

Dependency: Refer to: p1020, p1021, p1022, p1023, r1024, r1197

Notice: A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.

p1002[0...n] CO: Fixed velocity setpoint 2 / n_set_fixed 2

SERVO (Extended setp., Lin)	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]

Description: Sets a value for the fixed speed / velocity setpoint 2.

Dependency: Refer to: p1020, p1021, p1022, p1023, r1024, r1197

Notice: A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.

p1003[0...n]	CO: Fixed speed setpoint 3 / n_set_fixed 3		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 3.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1003[0...n]	CO: Fixed velocity setpoint 3 / n_set_fixed 3		
SERVO (Extended setp., Lin)	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 3.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1004[0...n]	CO: Fixed speed setpoint 4 / n_set_fixed 4		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 4.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1004[0...n]	CO: Fixed velocity setpoint 4 / n_set_fixed 4		
SERVO (Extended setp., Lin)	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 4.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1005[0...n]	CO: Fixed speed setpoint 5 / n_set_fixed 5		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 5.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p1005[0...n]	CO: Fixed velocity setpoint 5 / n_set_fixed 5		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 5.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1006[0...n]	CO: Fixed speed setpoint 6 / n_set_fixed 6		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 6.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1006[0...n]	CO: Fixed velocity setpoint 6 / n_set_fixed 6		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 6.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1007[0...n]	CO: Fixed speed setpoint 7 / n_set_fixed 7		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 7.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1007[0...n]	CO: Fixed velocity setpoint 7 / n_set_fixed 7		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 7.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p1008[0...n]	CO: Fixed speed setpoint 8 / n_set_fixed 8		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 8.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1008[0...n]	CO: Fixed velocity setpoint 8 / n_set_fixed 8		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 8.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1009[0...n]	CO: Fixed speed setpoint 9 / n_set_fixed 9		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 9.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1009[0...n]	CO: Fixed velocity setpoint 9 / n_set_fixed 9		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 9.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1010[0...n]	CO: Fixed speed setpoint 10 / n_set_fixed 10		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 10.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p1010[0...n]	CO: Fixed velocity setpoint 10 / n_set_fixed 10		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 10.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1011[0...n]	CO: Fixed speed setpoint 11 / n_set_fixed 11		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 11.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1011[0...n]	CO: Fixed velocity setpoint 11 / n_set_fixed 11		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 11.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1012[0...n]	CO: Fixed speed setpoint 12 / n_set_fixed 12		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 12.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1012[0...n]	CO: Fixed velocity setpoint 12 / n_set_fixed 12		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 12.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p1013[0...n]	CO: Fixed speed setpoint 13 / n_set_fixed 13		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 13.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1013[0...n]	CO: Fixed velocity setpoint 13 / n_set_fixed 13		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 13.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1014[0...n]	CO: Fixed speed setpoint 14 / n_set_fixed 14		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 14.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1014[0...n]	CO: Fixed velocity setpoint 14 / n_set_fixed 14		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 14.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1015[0...n]	CO: Fixed speed setpoint 15 / n_set_fixed 15		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets a value for the fixed speed / velocity setpoint 15.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p1015[0...n]	CO: Fixed velocity setpoint 15 / n_set_fixed 15		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3010
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets a value for the fixed speed / velocity setpoint 15.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024, r1197		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1020[0...n]	BI: Fixed speed setpoint selection Bit 0 / n_set_fixed Bit 0		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Displays the number of the actual fixed speed setpoint in r1197. Sets a value for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1021, p1022, p1023, r1197		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
p1020[0...n]	BI: Fixed velocity setpoint selection Bit 0 / v_set_fixed Bit 0		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed velocity setpoint.		
Dependency:	Selects the required fixed velocity setpoint using p1020 ... p1023. Displays the number of the actual fixed velocity setpoint in r1197. Sets a value for the fixed velocity setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1021, p1022, p1023, r1197		
Note:	If a fixed velocity setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
p1021[0...n]	BI: Fixed speed setpoint selection Bit 1 / n_set_fixed Bit 1		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Displays the number of the actual fixed speed setpoint in r1197. Sets a value for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1022, p1023, r1197		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		

p1021[0...n]	BI: Fixed velocity setpoint selection Bit 1 / v_set_fixed Bit 1		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the fixed velocity setpoint.		
Dependency:	Selects the required fixed velocity setpoint using p1020 ... p1023. Displays the number of the actual fixed velocity setpoint in r1197. Sets a value for the fixed velocity setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1022, p1023, r1197		
Note:	If a fixed velocity setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
p1022[0...n]	BI: Fixed speed setpoint selection Bit 2 / n_set_fixed Bit 2		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Displays the number of the actual fixed speed setpoint in r1197. Sets a value for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1021, p1023, r1197		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
p1022[0...n]	BI: Fixed velocity setpoint selection Bit 2 / v_set_fixed Bit 2		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the fixed velocity setpoint.		
Dependency:	Selects the required fixed velocity setpoint using p1020 ... p1023. Displays the number of the actual fixed velocity setpoint in r1197. Sets a value for the fixed velocity setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1021, p1023, r1197		
Note:	If a fixed velocity setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
p1023[0...n]	BI: Fixed speed setpoint selection Bit 3 / n_set_fixed Bit 3		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Displays the number of the actual fixed speed setpoint in r1197. Sets a value for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1021, p1022, r1197		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		

p1023[0...n]	BI: Fixed velocity setpoint selection Bit 3 / v_set_fixed Bit 3		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed velocity setpoint.		
Dependency:	Selects the required fixed velocity setpoint using p1020 ... p1023. Displays the number of the actual fixed velocity setpoint in r1197. Sets a value for the fixed velocity setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1021, p1022, r1197		
Note:	If a fixed velocity setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
r1024	CO: Fixed speed setpoint effective / n_set_fixed eff		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 3_1	Function diagram: 1550, 3010
	P-Group: Setpoints		Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the selected and effective fixed speed setpoint. This setpoint is the output value for the fixed speed setpoints and must be appropriately interconnected (e.g. with the main setpoint).		
Recommendation:	Interconnect the signal with main setpoint (p1070).		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Displays the number of the actual fixed speed setpoint in r1197. Sets a value for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1070, r1197		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		
r1024	CO: Fixed velocity setpoint effective / v_set_fixed eff		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 1550, 3010
	P-Group: Setpoints		Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the selected and effective fixed velocity setpoint. This setpoint is the output value for the fixed velocity setpoints and must be appropriately interconnected (e.g. with the main setpoint).		
Recommendation:	Interconnect the signal with main setpoint (p1070).		
Dependency:	Selects the required fixed velocity setpoint using p1020 ... p1023. Displays the number of the actual fixed velocity setpoint in r1197. Sets a value for the fixed velocity setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1070, r1197		
Note:	If a fixed velocity setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).		

p1030[0...n]		Motorized potentiometer, configuration / Mop configuration		
SERVO (Extended setp.), VECTOR	Can be changed: U, T			Access level: 3
	Data type: Unsigned16		Dynamic index: DDS, p0180	Function diagram: 3020
	P-Group: Closed-loop control		Units group: -	Unit selection: -
	Min -		Max -	Factory setting 0110 bin
Description:	Sets the configuration for the motorized potentiometer.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Data save active	Yes	No
	01	Automatic mode, ramp-function generator active	Yes	No
	02	Initial rounding-off active	Yes	No
Note:	03	Save in NVRAM active	Yes	No
	Re bit 00:			
	0: The setpoint for the motorized potentiometer is not saved and after ON is entered using p1040.			
	1: The setpoint for the motorized potentiometer is saved after OFF and after ON set to the saved value. In order to save in a non-volatile fashion, bit 03 should be set to 1.			
	Re bit 01:			
	0: Without ramp-function generator in the automatic mode (ramp-up/ramp-down time = 0).			
	1: With ramp-function generator in the automatic mode.			
	For manual operation (0 signal via BI: p1041), the ramp-function generator is always active.			
	Re bit 02:			
	0: Without initial rounding-off			
1: With initial rounding-off. The selected ramp-up/down time is correspondingly exceeded. The initial rounding-off is a sensitive way of specifying small changes (progressive reaction when keys are pressed). The jerk for the initial rounding-off is independent of the ramp-up time and only depends on the selected maximum speed (p1082). It is calculated as follows: $r = 0.01 \% * p1082 [1/s] / 0.13^2 [s^2]$ The jerk acts up until the maximum acceleration is reached ($a_{max} = p1082 [1/s] / p1047 [s]$), and then the drive continues to run linearly with a constant rate of acceleration. The higher the maximum acceleration (the lower that p1047 is), the longer the ramp-up time increases with respect to the set ramp-up time.				
Re bit 03:				
0: Non-volatile data save de-activated.				
1: The setpoint for the motorized potentiometer is saved in a non-volatile fashion (for bit 00 = 1). The following prerequisites must be fulfilled in order to be able to save the setpoint in a non-volatile fashion: - Firmware with V2.3 or higher. - Control Unit 320 (CU320) with hardware version C or higher (module with NVRAM).				

p1035[0...n]		BI: Motorized potentiometer, setpoint, raise / Mop raise		
SERVO (Extended setp.), VECTOR	Can be changed: T			Access level: 3
	Data type: Unsigned32		Dynamic index: CDS, p0170	Function diagram: 2442, 2505
	P-Group: Setpoints		Units group: -	Unit selection: -
	Min -		Max -	Factory setting 0
Description:	Sets the signal source to increase the setpoint for the motorized potentiometer			
Dependency:	Refer to: p1036			

p1035	BI: Enable zero marks / Enable ZM			
TM41	Can be changed: T		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: Setpoints	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0	
Description:	Sets the signal source to enable the zero marks.			
p1036[0...n]	BI: Motorized potentiometer, lower setpoint / Mop lower			
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3	
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2442, 2505	
	P-Group: Setpoints	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0	
Description:	Sets the signal source to reduce the setpoint for the motorized potentiometer.			
Dependency:	Refer to: p1035			
p1037[0...n]	Motorized potentiometer, maximum speed / Mop n_max			
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3020	
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505	
	Min	Max	Factory setting	
	-210000.000 [1/min]	210000.000 [1/min]	0.000 [1/min]	
Description:	Sets the maximum speed/velocity for the motorized potentiometer.			
Note:	This parameter is automatically pre-assigned in the commissioning phase. The setpoint output from the motorized potentiometer is limited to this value.			
p1037[0...n]	Motorized potentiometer, maximum velocity / Mop n_max			
SERVO (Extended setp., Lin)	Can be changed: U, T		Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3020	
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505	
	Min	Max	Factory setting	
	-1000.000 [m/min]	1000.000 [m/min]	0.000 [m/min]	
Description:	Sets the maximum speed/velocity for the motorized potentiometer.			
Note:	This parameter is automatically pre-assigned in the commissioning phase. The setpoint output from the motorized potentiometer is limited to this value.			
p1038[0...n]	Motorized potentiometer, minimum speed / Mop n_min			
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 2	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3020	
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505	
	Min	Max	Factory setting	
	-210000.000 [1/min]	210000.000 [1/min]	0.000 [1/min]	
Description:	Sets the minimum speed/velocity for the motorized potentiometer.			
Note:	This parameter is automatically pre-assigned in the commissioning phase. The setpoint output from the motorized potentiometer is limited to this value.			

p1038[0...n]	Motorized potentiometer, minimum velocity / Mop n_min		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3020
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the minimum speed/velocity for the motorized potentiometer.		
Note:	This parameter is automatically pre-assigned in the commissioning phase. The setpoint output from the motorized potentiometer is limited to this value.		
p1039[0...n]	BI: Motorized potentiometer, inversion / Mop inversion		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 3020
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to invert the maximum or minimum speed/velocity for the motorized potentiometer.		
Dependency:	Refer to: p1037, p1038		
Note:	The inversion is only active during "motorized potentiometer raise" or "motorized potentiometer lower".		
p1040[0...n]	Motorized potentiometer, starting value / Mop start value		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3020
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the starting value for the motorized potentiometer. This starting value becomes effective after the drive has been powered-up.		
Dependency:	Only effective if p1030.0 = 0. Refer to: p1030		
p1040[0...n]	Motorized potentiometer, starting value / Mop start value		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3020
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the starting value for the motorized potentiometer. This starting value becomes effective after the drive has been powered-up.		
Dependency:	Only effective if p1030.0 = 0. Refer to: p1030		

p1041[0...n]	BI: Motorized potentiometer, manual/automatic / Mop manual/auto		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3020
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to change over from manual to automatic when using a motorized potentiometer. In the manual mode, the setpoint is changed using two signals - raise and lower. In the automatic mode, the setpoint must be interconnected via a connector input.		
Dependency:	Refer to: p1030, p1035, p1036, p1042		
Note:	The effectiveness of the internal ramp-function generator can be set in automatic mode.		
p1042[0...n]	CI: Motorized potentiometer, automatic setpoint / Mop auto setpoint		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3020
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setpoint of the motorized potentiometer in the automatic mode.		
Dependency:	Refer to: p1041		
p1043[0...n]	BI: Motorized potentiometer, accept setpoint / Mop accept set val		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3020
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setting command to accept the setting value for the motorized potentiometer.		
Dependency:	Refer to: p1044		
p1044[0...n]	CI: Motorized potentiometer, setting value / Mop setting value		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3020
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setting value for the motorized potentiometer.		
Dependency:	Refer to: p1043		
Note:	The value becomes effective for a 0/1 edge of the setting command.		
r1045	CO: Mot. potentiometer, speed setp. in front of ramp-fct. gen. / Mop n_set bef. RFG		
SERVO (Extended setp.), VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3020
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Sets the effective setpoint in front of the internal motorized potentiometer ramp-function generator.		

r1045	CO: Mot. potentiom.,velocity setp. in front of ramp-fct. gen. / Mop n_set bef. RFG		
SERVO (Extended setp., Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3020
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Sets the effective setpoint in front of the internal motorized potentiometer ramp-function generator.		
p1047[0...n]	Motorized potentiometer, ramp-up time / Mop ramp-up time		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3020
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 1000.000 [s]	Factory setting 10.000 [s]
Description:	Sets the ramp-up time for the internal ramp-function generator for the motorized potentiometer. The setpoint is changed from the zero up to the speed/velocity limit (p1082) within this time (if no initial rounding-off has been activated).		
Dependency:	Refer to: p1030, p1048, p1082		
Note:	When the initial rounding-off is activated (p1030.2) the ramp-up time is correspondingly extended.		
p1048[0...n]	Motorized potentiometer, ramp-down time / Mop ramp-down time		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3020
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 1000.000 [s]	Factory setting 10.000 [s]
Description:	Sets the ramp-down time for the internal ramp-function generator for the motorized potentiometer. The setpoint is changed from the speed/velocity limit (p1082) to zero within this time (if no initial rounding-off has been activated).		
Dependency:	Refer to: p1030, p1047, p1082		
Note:	The deceleration time is extended corresponding to the activated initial rounding-off (p1030.2).		
r1050	CO: Motor. potentiometer, setpoint after the ramp-function generator / Mop setp after RFG		
SERVO (Extended setp.), VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1550, 3020
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Sets the effective setpoint after the internal motorized potentiometer ramp-function generator. This setpoint is the output value of the motorized potentiometer and must be appropriately interconnected onwards (e.g. with the main setpoint).		
Recommendation:	Interconnect the signal with main setpoint (p1070).		
Dependency:	Refer to: p1070		
Note:	For "With ramp-function generator", after an OFF1, OFF2, OFF3 or for a 0 signal via BI: p0852 (inhibit operation, cancel pulses) the ramp-function generator output (r1050) is set to the starting value (configuration via p1030.0).		

r1050	CO: Motor. potentiometer, setpoint after the ramp-function generator / Mop setp after RFG		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 3020
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Sets the effective setpoint after the internal motorized potentiometer ramp-function generator. This setpoint is the output value of the motorized potentiometer and must be appropriately interconnected onwards (e.g. with the main setpoint).		
Recommendation:	Interconnect the signal with main setpoint (p1070).		
Dependency:	Refer to: p1070		
Note:	For "With ramp-function generator", after an OFF1, OFF2, OFF3 or for a 0 signal via BI: p0852 (inhibit operation, cancel pulses) the ramp-function generator output (r1050) is set to the starting value (configuration via p1030.0).		
p1055[0...n]	BI: Jog bit 0 / Jog bit 0		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2501, 2610, 3030
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for jog 1.		
Recommendation:	When the signal source is set, this does not trigger a response - but only a signal change of the source.		
Dependency:	Refer to: p0840, p1058		
Notice:	The drive is enabled for jogging using BI: p1055 or BI: p1056. The command "ON/OFF1" can be issued using BI: p0840 or using BI: p1055/p1056. Only the signal source that was used to power-up can also be used to power-down again.		
p1056[0...n]	BI: Jog bit 1 / Jog bit 1		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2501, 2610, 3030
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for jog 2.		
Recommendation:	When the signal source is set, this does not trigger a response - but only a signal change of the source.		
Dependency:	Refer to: p0840, p1059		
Notice:	The drive is enabled for jogging using BI: p1055 or BI: p1056. The command "ON/OFF1" can be issued using BI: p0840 or using BI: p1055/p1056. Only the signal source that was used to power-up can also be used to power-down again.		

p1058[0...n]	Jog 1 speed setpoint / Jog 1 n_set		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the speed/velocity for jog 1. Jogging is level-triggered and allows the motor to be incrementally moved.		
Dependency:	Refer to: p1055, p1056		
p1058[0...n]	Jog 1 velocity setpoint / Jog 1 n_set		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the speed/velocity for jog 1. Jogging is level-triggered and allows the motor to be incrementally moved.		
Dependency:	Refer to: p1055, p1056		
p1059[0...n]	Jog 2 speed setpoint / Jog 2 n_set		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min -210000.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the speed/velocity for jog 2. Jogging is level-triggered and allows the motor to be incrementally moved.		
Dependency:	Refer to: p1055, p1056		
p1059[0...n]	Jog 2 velocity setpoint / Jog 2 n_set		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min -1000.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the speed/velocity for jog 2. Jogging is level-triggered and allows the motor to be incrementally moved.		
Dependency:	Refer to: p1055, p1056		
p1063[0...n]	Speed limit, setpoint channel / n_limit setp.		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point	Units group: 3_1	Function diagram: -
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 210000.000 [1/min]
Description:	Sets the speed limit/velocity limit effective in the setpoint channel.		
Dependency:	Refer to: p1082, p1083, p1085, p1086, p1088		

p1063[0...n]	Velocity limit, setpoint channel / v_limit setp.		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point	Units group: 4_1	Function diagram: -
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 1000.000 [m/min]
Description:	Sets the speed limit/velocity limit effective in the setpoint channel.		
Dependency:	Refer to: p1082, p1083, p1085, p1086, p1088		
p1070[0...n]	CI: Main setpoint / Main setpoint		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 1550, 3030
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 1024[0]
Description:	Sets the signal source for the main setpoint. Examples: r1024: Fixed speed setpoint effective r1050: Motor. potentiometer, setpoint after the ramp-function generator		
Dependency:	Refer to: p1071, r1073, r1078		
p1071[0...n]	CI: Main setpoint scaling / Main setpt scal		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 3030
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for scaling the main setpoint.		
r1073	CO: Main setpoint effective / Main setpoint eff		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 3_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the effective main setpoint. The value shown is the main setpoint after scaling.		
r1073	CO: Main setpoint effective / Main setpoint eff		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the effective main setpoint. The value shown is the main setpoint after scaling.		

p1075[0...n]	CI: Suppl setpoint / Suppl setpoint		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1550, 3030
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the supplementary setpoint.		
Dependency:	Refer to: p1076, r1077, r1078		
p1076[0...n]	CI: Supplementary setpoint scaling / Suppl setpt scal		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 3030
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for scaling the supplementary setpoint.		
r1077	CO: Supplementary setpoint effective / Suppl setpoint eff		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 3030
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the effective supplementary setpoint. The value shown is the additional setpoint after scaling.		
r1077	CO: Supplementary setpoint effective / Suppl setpoint eff		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 3030
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the effective supplementary setpoint. The value shown is the additional setpoint after scaling.		
r1078	CO: Total setpoint effective / Total setpoint eff		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 3030
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the total effective setpoint. The value indicates the sum of the effective main setpoint and supplementary setpoint.		

r1078	CO: Total setpoint effective / Total setpoint eff		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 3030
	P-Group: Setpoints		Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the total effective setpoint. The value indicates the sum of the effective main setpoint and supplementary setpoint.		
p1080[0...n]	Minimum speed / Minimum speed		
SERVO (Extended setp.), VECTOR	Can be changed: C2(1), T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point	Units group: 3_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [1/min]	Max 19500.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the lowest possible speed/velocity. This value is not fallen below in operation.		
Note:	The parameter value applies for both motor directions of rotation. In exception cases, the motor can operate below this value (e.g. when reversing).		
p1080[0...n]	Minimum velocity / Minimum speed		
SERVO (Extended setp., Lin)	Can be changed: C2(1), T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point	Units group: 4_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the lowest possible speed/velocity. This value is not fallen below in operation.		
Note:	The parameter value applies for both motor directions of rotation. In exception cases, the motor can operate below this value (e.g. when reversing).		

p1082[0...n]		Maximum speed / Maximum speed	
SERVO	Can be changed: C2(1), T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point		Function diagram: 3020, 3050, 3060, 3070, 3095, 5300
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 1500.000 [1/min]
Description:	Sets the highest possible speed.		
Dependency:	Refer to: p0115, p0322		
Note:	<p>The parameter applies for both motor directions. The parameter has a limiting effect and is the reference quantity for all ramp-up and ramp-down times (e.g. down ramps, ramp-function generator, motor potentiometer).</p> <p>The parameter is part of the fast commissioning (p0010 = 1); this means that it is appropriately pre-assigned when changing p0311 and p0322.</p> <p>The following limits are always effective for p1082: $p1082 \leq p0322$, if $p0322 > 0$ $p1082 \leq 1 / (10.5 * p0115[0] * r0313)$ $p1082 \leq \text{maximum power unit pulse frequency} / (5.3 * r0313)$</p> <p>For the automatic calculation (p0340 = 1) the value of the parameter is pre-assigned the maximum motor speed (p0322). If p0322 = 0, the rated motor speed (p0311) is used as default (pre-assignment) value. For induction motors that are not catalog motors (p0301 = 0), the synchronous no-load speed is used as default (pre-assignment) value ($p0310 * 60 / r0313$).</p> <p>For synchronous motors, the following additionally applies: In the automatic calculation (p0340 = 1), p1082 is limited to speeds for which the steady-state maximum current of the power unit is not sufficient as field current: $p1082 < p0348 / (1 - r0207 / r0331)$. On the other hand, an additional limit is effective, which prevents the EMF from exceeding the maximum DC link voltage.</p> <p>The effective assignment of the motor data set parameter (e.g. p0311) to the drive data set parameter p1082 when pre-assigning should be taken from p186.</p> <p>Parameter p1082 is also available in the fast commissioning (p0010=1); this means that when exiting via p3900 > 0, the value is not changed.</p>		
p1082[0...n]		Maximum velocity / Maximum speed	
SERVO (Lin)	Can be changed: C2(1), T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point		Function diagram: 3020, 3050, 3060, 3070, 3095, 5300
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 1000.000 [m/min]
Description:	Sets the highest possible velocity.		
Dependency:	Refer to: p0115, p0322		
Note:	<p>The parameter applies for both motor directions. The parameter has a limiting effect and is the reference quantity for all ramp-up and ramp-down times (e.g. down ramps, ramp-function generator, motor potentiometer).</p> <p>The parameter is part of the fast commissioning (p0010 = 1); this means that it is appropriately pre-assigned when changing p0311 and p0322.</p> <p>The following limits are always effective for p1082: $p1082 \leq p0322$, if $p0322 > 0$ $p1082 \leq 1 / (10.5 * p0115[0] * r0313)$ $p1082 \leq \text{maximum power unit pulse frequency} / (5.3 * r0313)$</p> <p>For the automatic calculation (p0340 = 1) the value of the parameter is pre-assigned the maximum motor speed (p0322). If p0322 = 0, the rated motor speed (p0311) is used as default (pre-assignment) value. For induction motors that are not catalog motors (p0301 = 0), the synchronous no-load speed is used as default (pre-assignment) value ($p0310 * 60 / r0313$).</p>		

For synchronous motors, the following additionally applies:

In the automatic calculation (p0340 = 1), p1082 is limited to speeds for which the steady-state maximum current of the power unit is not sufficient as field current: $p1082 < p0348 / (1 - r0207 / r0331)$. On the other hand, an additional limit is effective, which prevents the EMF from exceeding the maximum DC link voltage.

The effective assignment of the motor data set parameter (e.g. p0311) to the drive data set parameter p1082 when pre-assigning should be taken from p186.

Parameter p1082 is also available in the fast commissioning (p0010=1); this means that when exiting via p3900 > 0, the value is not changed.

p1082[0...n]	Maximum speed / Maximum speed		
VECTOR	Can be changed: C2(1), T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3020, 3050, 3060, 3070, 3095, 5300
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 1500.000 [1/min]
Description:	Sets the highest possible speed.		
Dependency:	Refer to: p0115, p0230, r0313, p0322, r0336		
Note:	<p>The parameter applies for both motor directions. The parameter has a limiting effect and is the reference quantity for all ramp-up and ramp-down times (e.g. down ramps, ramp-function generator, motor potentiometer).</p> <p>The parameter is part of the fast commissioning (p0010 = 1); this means that it is appropriately pre-assigned when changing p0311 and p0322.</p> <p>The following limits are always effective for p1082:</p> $p1082 \leq p0322, \text{ if } p0322 > 0$ $p01082 \leq \text{Maximum}(15 * r0336, 650 \text{ Hz}) / r0313$ $p01082 \leq \text{maximum power unit pulse frequency} / (k * r0313)$ $k = 12 \text{ for closed-loop vector control (r0108 bit2 = 1), } k = 6.5 \text{ for U/f control (r0108 bit2 = 0)}$ <p>If a sinusoidal filter (p0230 = 3) is parameterized as output filter, then the maximum speed is limited corresponding to the maximum permissible filter output frequency (refer to the filter data sheet). For reactors and du/dt filters, it is limited to 150 Hz / r0313 (for chassis power units) or 120Hz / r0313 (for booksize power units).</p> <p>For the automatic calculation (p0340 = 1) the value of the parameter is pre-assigned the maximum motor speed (p0322). If p0322 = 0, the rated motor speed (p0311) is used as default (pre-assignment) value. For induction motors that are not catalog motors (p0301 = 0), the synchronous no-load speed is used as default (pre-assignment) value ($p0310 * 60 / r0313$).</p> <p>For synchronous motors, the following additionally applies:</p> <p>In the automatic calculation (p0340), p1082 is limited to speeds where the EMF does not exceed the DC link voltage.</p> <p>The effective assignment of the motor data set parameter (e.g. p0311) to the drive data set parameter p1082 when pre-assigning should be taken from p186.</p> <p>Parameter p1082 is also available in the fast commissioning (p0010=1); this means that when exiting via p3900 > 0, the value is not changed.</p>		

p1083[0...n]	CO: Speed limit in positive direction of rotation / n_limit pos		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3050
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 210000.000 [1/min]
Description:	Sets the maximum speed for the positive direction.		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p1083[0...n]	CO: Velocity limit, positive direction / v_limit pos		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3050
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 1000.000 [m/min]
Description:	Sets the maximum velocity for the positive direction.		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
r1084	Speed limit positive effective / n_limit pos eff		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3050, 5030, 5210, 6640, 7020, 8010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the effective positive speed limit.		
r1084	Velocity limit positive effective / v_limit pos eff		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3050, 5030, 5210, 6640, 7020, 8010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the effective positive velocity limit.		
p1085[0...n]	CI: Speed limit in positive direction of rotation / n_limit pos		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3050
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1083[0]
Description:	Sets the signal source for the speed limit of the positive direction.		
p1085[0...n]	CI: Velocity limit, positive direction / v_limit pos		
SERVO (Extended setp., Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3050
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1083[0]
Description:	Sets the signal source for the velocity limit of the positive direction.		

p1086[0...n]	CO: Speed limit negative direction of rotation / n_limit neg		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3050
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min -210000.000 [1/min]	Max 0.000 [1/min]	Factory setting -210000.000 [1/min]
Description:	Sets the speed limit for the negative direction.		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1086[0...n]	CO: Velocity limit, negative direction / v_limit neg		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3050
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min -1000.000 [m/min]	Max 0.000 [m/min]	Factory setting -1000.000 [m/min]
Description:	Sets the velocity limit for the negative direction.		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
r1087	Speed limit negative effective / n_limit neg eff		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3050, 5030, 5210, 6640, 7020, 8010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the effective negative speed limit.		
r1087	Velocity limit negative effective / v_limit neg eff		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3050, 5030, 5210, 6640, 7020, 8010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the effective negative velocity limit.		
p1088[0...n]	CI: Speed limit negative direction of rotation / n_limit neg		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3050
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1086[0]
Description:	Sets the signal source for the speed/velocity limit of the negative direction.		

p1088[0...n]	Cl: Velocity limit, negative direction / n_limit neg		
SERVO (Extended setp., Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 3050
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 1086[0]
Description:	Sets the signal source for the speed/velocity limit of the negative direction.		
p1091[0...n]	Skip speed 1 / Skip speed 1		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 3_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the skip speed/velocity 1.		
Dependency:	Refer to: p1092, p1093, p1094, p1101		
Note:	The skip (suppression) speeds can be used to prevent the effects of mechanical resonance.		
p1091[0...n]	Skip velocity 1 / Skip speed 1		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the skip speed/velocity 1.		
Dependency:	Refer to: p1092, p1093, p1094, p1101		
Note:	The skip (suppression) speeds can be used to prevent the effects of mechanical resonance.		
p1092[0...n]	Skip speed 2 / Skip speed 2		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 3_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the skip speed/velocity 2.		
Dependency:	Refer to: p1091, p1093, p1094, p1101		
p1092[0...n]	Skip velocity 2 / Skip speed 2		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the skip speed/velocity 2.		
Dependency:	Refer to: p1091, p1093, p1094, p1101		

p1093[0...n]	Skip speed 3 / Skip speed 3		
SERVO (Extended setp.), VECTOR	Can be changed: U, T Data type: Floating Point P-Group: Setpoints	Dynamic index: DDS, p0180 Units group: 3_1	Access level: 3 Function diagram: 3050 Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the skip speed/velocity 3.		
Dependency:	Refer to: p1091, p1092, p1094, p1101		
p1093[0...n]	Skip velocity 3 / Skip speed 3		
SERVO (Extended setp., Lin)	Can be changed: U, T Data type: Floating Point P-Group: Setpoints	Dynamic index: DDS, p0180 Units group: 4_1	Access level: 3 Function diagram: 3050 Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the skip speed/velocity 3.		
Dependency:	Refer to: p1091, p1092, p1094, p1101		
p1094[0...n]	Skip speed 4 / Skip speed 4		
SERVO (Extended setp.), VECTOR	Can be changed: U, T Data type: Floating Point P-Group: Setpoints	Dynamic index: DDS, p0180 Units group: 3_1	Access level: 3 Function diagram: 3050 Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the skip speed/velocity 4.		
Dependency:	Refer to: p1091, p1092, p1093, p1101		
p1094[0...n]	Skip velocity 4 / Skip speed 4		
SERVO (Extended setp., Lin)	Can be changed: U, T Data type: Floating Point P-Group: Setpoints	Dynamic index: DDS, p0180 Units group: 4_1	Access level: 3 Function diagram: 3050 Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the skip speed/velocity 4.		
Dependency:	Refer to: p1091, p1092, p1093, p1101		
p1101[0...n]	Skip speed bandwidth / Skip_n bandwidth		
SERVO (Extended setp.), VECTOR	Can be changed: U, T Data type: Floating Point P-Group: Setpoints	Dynamic index: DDS, p0180 Units group: 3_1	Access level: 3 Function diagram: 3050 Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 0.000 [1/min]
Description:	Sets the bandwidth for the skip speeds/velocities 1 to 4.		
Dependency:	Refer to: p1091, p1092, p1093, p1094		
Note:	The setpoint (reference) speeds are skipped (suppressed) in the range of the skip speed +/-p1101. Steady-state operation is not possible in the skipped (suppressed) speed range. The skip (suppression) range is skipped. Example: p1091 = 600 and p1101 = 20 --> setpoint speeds of between 580 and 620 [RPM] are skipped.		

p1101[0...n]	Skip velocity bandwidth / Skip_n bandwidth		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 0.000 [m/min]
Description:	Sets the bandwidth for the skip speeds/velocities 1 to 4.		
Dependency:	Refer to: p1091, p1092, p1093, p1094		
Note:	The setpoint (reference) speeds are skipped (suppressed) in the range of the skip speed +/-p1101. Steady-state operation is not possible in the skipped (suppressed) speed range. The skip (suppression) range is skipped. Example: p1091 = 600 and p1101 = 20 --> setpoint speeds of between 580 and 620 [RPM] are skipped.		
p1110[0...n]	BI: Inhibit negative direction / Inhib neg dir rot		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to disable the negative direction.		
Dependency:	Refer to: p1111		
p1111[0...n]	BI: Inhibit positive direction / Inhib pos dir rot		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2505
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to disable the positive direction.		
Dependency:	Refer to: p1110		
r1112	CO: Speed setpoint after minimum limiting / n_set n. min_lim		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 3_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed / velocity setpoint after the minimum limiting.		
Dependency:	Refer to: p1091, p1092, p1093, p1094, p1101		
r1112	CO: Velocity setpoint after minimum limiting / n_set n. min_lim		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 3050
	P-Group: Setpoints		Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the speed / velocity setpoint after the minimum limiting.		
Dependency:	Refer to: p1091, p1092, p1093, p1094, p1101		

p1113[0...n]	BI: Direction reversal / Direction reversal		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2442, 2505
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to reverse the motor direction (of rotation).		
Dependency:	Refer to: r1198		
r1114	CO: Setpoint after the direction of rotation limit / Setpt after limit		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 3040, 3050
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed/velocity setpoint after the changeover and limiting the direction.		
r1114	CO: Setpoint after the direction limiting / Setpt after limit		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 3040, 3050
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the speed/velocity setpoint after the changeover and limiting the direction.		
p1115	Ramp-function generator selection / RFG selection		
SERVO (Extended setp.), VECTOR	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: 1550, 3080
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the ramp-function generator type.		
Values:	0: Basic ramp-function generator 1: Extended ramp-function generator		
Note:	Another ramp-function generator type can only be selected when the motor is at a standstill.		
r1119	CO: Ramp-function generator setpoint at the input / RFG setpt at input		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 1750, 3050, 3060, 3070, 8010
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the setpoint at the input of the ramp-function generator.		
Note:	The setpoint is influenced by other functions, e.g. skip (suppressed) speeds, minimum and maximum limits.		

r1119	CO: Ramp-function generator setpoint at the input / RFG setpt at input		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 1750, 3050, 3060, 3070, 8010
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the setpoint at the input of the ramp-function generator.		
Note:	The setpoint is influenced by other functions, e.g. skip (suppressed) speeds, minimum and maximum limits.		
p1120[0...n]	Ramp-function generator ramp-up time / RFG ramp-up time		
SERVO (Extended setp.), VECTOR	Can be changed: C2(1), U, T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point		Function diagram: 3060, 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 999999.000 [s]	Factory setting 10.000 [s]
Description:	The drive is accelerated from standstill (setpoint = 0) up to the maximum speed (p1082) in this time.		
Dependency:	Refer to: p1082		
Note:	The parameter is adapted during the rotating measurement (p1960 > 0). This is the reason that during the rotating measurement, the motor can accelerate faster than was originally parameterized.		
p1120[0...n]	Ramp-function generator ramp-up time / RFG ramp-up time		
SERVO (Extended setp., Lin)	Can be changed: C2(1), U, T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point		Function diagram: 3060, 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 999999.000 [s]	Factory setting 10.000 [s]
Description:	The drive is accelerated from standstill (setpoint = 0) up to the maximum velocity (p1082) in this time.		
Dependency:	Refer to: p1082		
Note:	The parameter is adapted during the rotating measurement (p1960 > 0). This is the reason that during the rotating measurement, the motor can accelerate faster than was originally parameterized.		
p1121[0...n]	Ramp-function generator ramp-down time / RFG ramp-down time		
SERVO, VECTOR	Can be changed: C2(1), U, T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Floating Point		Function diagram: 3060, 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 999999.000 [s]	Factory setting 10.000 [s]
Description:	The drive is decelerated from the maximum speed (p1082) down to standstill (setpoint = 0) in this time.		
Dependency:	Refer to: p1082		

p1121[0...n]	Ramp-function generator ramp-down time / RFG ramp-down time		
SERVO (Lin)	Can be changed: C2(1), U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3060, 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 999999.000 [s]	Factory setting 0.000 [s]
Description:	The drive is decelerated from the maximum velocity (p1082) down to standstill (setpoint = 0) in this time.		
Dependency:	Refer to: p1082		
p1122[0...n]	BI: Bypass ramp-function generator / Bypass RFG		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2505
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for bypassing the ramp generator (ramp-up and ramp-down times = 0).		
Note:	For VECTOR in sensorless operation, it is not permissible that the ramp-function generator is bypassed.		
p1130[0...n]	Ramp-function generator initial rounding-off time / RFG t_start_round		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 30.000 [s]	Factory setting 0.000 [s]
Description:	Sets the initial rounding-off time for the extended ramp generator. The value applies to ramp-up and ramp-down.		
Note:	Rounding-off times avoid an abrupt response and prevent damage to the mechanical system.		
p1131[0...n]	Ramp-function generator final rounding-off time / RFG t_end_delay		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 30.000 [s]	Factory setting 0.000 [s]
Description:	Sets the final rounding-off time for the extended ramp generator. The value applies to ramp-up and ramp-down.		
Note:	Rounding-off times avoid an abrupt response and prevent damage to the mechanical system.		

p1134[0...n]	Ramp-function generator rounding-off type / RFG round-off type		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: 3070
	P-Group: Setpoints		Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the smoothed response to the OFF1 command or the reduced setpoint for the extended ramp-function generator.		
Values:	0: Cont. smoothing 1: Discont smoothing		
Dependency:	No effect up to initial rounding-off time (p1130) > 0 s.		
Note:	p1134 = 0 (continuous smoothing) If the setpoint is reduced while ramping-up, initially a final rounding-off is carried-out and then the ramp-up completed. During the final rounding-off, the output of the ramp-function generator continues to go in the direction of the previous setpoint (overshoot). After the final rounding-off has been completed, the output goes toward the new setpoint. p1134 = 1 (discontinuous smoothing) If the setpoint is reduced while ramping-up, then the output goes immediately in the direction of the new setpoint. For the setpoint change there is no rounding-off.		
p1135[0...n]	OFF3 ramp-down time / RFG OFF3 t_ramp-dn		
SERVO, VECTOR	Can be changed: C2(1), U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 3060, 3070
	P-Group: Setpoints		Unit selection: -
	Min 0.000 [s]	Max 600.000 [s]	Factory setting 0.000 [s]
Description:	Sets the ramp-down time from the maximum speed down to zero speed for the OFF3 command.		
Note:	This time can be exceeded if the DC-link voltage reaches its maximum value.		
p1135[0...n]	OFF3 ramp-down time / RFG OFF3 t_ramp-dn		
SERVO (Lin)	Can be changed: C2(1), U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 3060, 3070
	P-Group: Setpoints		Unit selection: -
	Min 0.000 [s]	Max 600.000 [s]	Factory setting 0.000 [s]
Description:	Sets the ramp-down time from the maximum velocity down to zero speed for the OFF3 command.		
Note:	This time can be exceeded if the DC-link voltage reaches its maximum value.		
p1136[0...n]	OFF3 initial rounding-off time / RFG OFF3 t_strt_rnd		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 3070, 3080
	P-Group: Setpoints		Unit selection: -
	Min 0.000 [s]	Max 30.000 [s]	Factory setting 0.000 [s]
Description:	Sets the initial rounding-off time for OFF3 for the extended ramp generator.		

p1137[0...n]	OFF3 final rounding-off time / RFG OFF3 t_end_del		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 3070
	P-Group: Setpoints		Unit selection: -
	Min 0.000 [s]	Max 30.000 [s]	Factory setting 0.000 [s]
Description:	Sets the final rounding-off time for OFF3 for the extended ramp generator.		
p1140[0...n]	BI: Enables the ramp-function generator / Enable RFG		
SERVO, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2442, 2443, 2501
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 4 (operating condition/disable ramp-function generator).		
Dependency:	Refer to: p1141, p1142		
Note:	Bit 4 = 0: Inhibits the ramp-function generator (the ramp-function generator output is set to zero) Bit 4 = 1: Operating condition (the ramp-function generator can be enabled)		
p1140	BI: Enables the ramp-function generator / Enable RFG		
TM41	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 4 (operating condition/disable ramp-function generator).		
Dependency:	Refer to: p1141, p1142		
Note:	Bit 4 = 0: Inhibits the ramp-function generator (the ramp-function generator output is set to zero) Bit 4 = 1: Operating condition (the ramp-function generator can be enabled)		
p1141[0...n]	BI: Start ramp-function generator / Start RFG		
SERVO, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 2442, 2443, 2501
	P-Group: Setpoints		Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 5 (enables ramp-function generator/ stops ramp-function generator)		
Dependency:	Refer to: p1140, p1142		
Notice:	The ramp-function generator is, independent of the status of the signal source, active in the following cases: - OFF1/OFF3. - ramp-function generator output within the suppression bandwidth. - ramp-function generator output below the minimum speed.		
Note:	Bit 5 = 0: Stop the ramp-function generator (the ramp-function generator output is frozen) Bit 5 = 1: Enable ramp-function generator		

p1141	BI: Start ramp-function generator / Start RFG		
TM41	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 5 (enables ramp-function generator/ stops ramp-function generator)		
Dependency:	Refer to: p1140, p1142		
Note:	Bit 5 = 0: Stop the ramp-function generator (the ramp-function generator output is frozen) Bit 5 = 1: Enable ramp-function generator		
p1142[0...n]	BI: Enable speed setpoint / Enable n_set		
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2442, 2443, 2501
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 6 (enables setpoint/disable setpoint).		
Dependency:	Refer to: p1140, p1141		
Note:	Bit 6 = 0: Inhibits the setpoint (the ramp-function generator input is set to zero) Bit 6 = 1: Enable setpoint		
p1142[0...n]	BI: Enable velocity setpoint / Enable v_set		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2442, 2443, 2501
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 6 (enables setpoint/disable setpoint).		
Dependency:	Refer to: p1140, p1141		
Note:	Bit 6 = 0: Inhibits the setpoint (the ramp-function generator input is set to zero) Bit 6 = 1: Enable setpoint		
p1142	BI: Enable speed setpoint / Enable n_set		
TM41	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for control word 1 bit 6 (enables setpoint/disable setpoint).		
Dependency:	Refer to: p1140, p1141		
Note:	Bit 6 = 0: Inhibits the setpoint (the ramp-function generator input is set to zero) Bit 6 = 1: Enable setpoint		

p1143[0...n]	BI: Ramp-function generator, accept setting value / Accept RFG set val		
SERVO (Extended setp.), VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for accepting the setting value of the ramp-function generator.		
Dependency:	The signal source for the ramp-function generator setting value is set using parameters. Refer to: p1144		
Note:	0/1 signal: The ramp-function generator output is immediately (without delay) set to the setting value of the ramp-function generator. 1 signal: The setting value of the ramp-function generator is effective. 1/0 signal: The input value of the ramp-function generator is effective. The ramp-function generator output is adapted to the input value using the ramp-up time or the ramp-down time. 0 signal: The input value of the ramp-function generator is effective.		
p1144[0...n]	CI: Ramp-function generator setting value / RFG setting value		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 3070
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the ramp-function generator setting value.		
Dependency:	The signal source for accepting the setting value is set using parameters. Refer to: p1143		
p1145[0...n]	Ramp-function generator tracking intensity. / RFG track intens		
SERVO (Extended setp.), VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3080
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.0	Max 50.0	Factory setting 1.3
Description:	Sets the ramp-function generator tracking. The output value of the ramp-function generator is tracked (corrected) corresponding to the maximum possible drive acceleration. The reference value is the deviation at the speed/velocity controller input that is necessary to ensure that the motor accelerates at the torque/force limit.		
Recommendation:	p1145 = 0.0: This value de-activates the ramp-function generator tracking. p1145 = 0.0 ... 1.0: Generally, these values are not practical. They cause the motor to accelerate below its torque limit. The lower the selected value, the greater the margin between the controller and torque limit when accelerating. p1145 > 1.0: The greater the value, the higher the permissible deviation between the speed setpoint and speed actual value.		
Note:	In the U/f mode, the ramp-function generator tracking is not active. For SERVO with U/f operation, the following applies: The complete ramp-function generator is not active, i.e. ramp-up and ramp-down time = 0.		

p1148[0...n]	Ramp-function gen., tolerance for ramp-up and ramp-down active / RFG tol HL/RL act		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 3060, 3070
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 1000.00 [1/min]	Factory setting 19.80 [1/min]
Description:	Sets the tolerance value for the status of the ramp-function generator (ramp-up active, ramp-down active). If the input of the ramp-function generator does not change in comparison to the output by more than the entered tolerance time, then the status bits "ramp-up active" and "ramp-down active" are not influenced.		
Dependency:	Refer to: r1199		
p1148[0...n]	Ramp-function gen., tolerance for ramp-up and ramp-down active / RFG tol HL/RL act		
SERVO (Extended setp., Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 3060, 3070
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 10.00 [m/min]	Factory setting 0.20 [m/min]
Description:	Sets the tolerance value for the status of the ramp-function generator (ramp-up active, ramp-down active). If the input of the ramp-function generator does not change in comparison to the output by more than the entered tolerance time, then the status bits "ramp-up active" and "ramp-down active" are not influenced.		
Dependency:	Refer to: r1199		
r1150	CO: Ramp-function generator speed setpoint at the output / RFG n_set at outp		
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 3060, 3070, 3080
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the setpoint at the output of the ramp-function generator.		
r1150	CO: Ramp-function generator velocity setpoint at the output / RFG n_set at outp		
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 3060, 3070, 3080
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the setpoint at the output of the ramp-function generator.		

p1151[0...n]	Ramp-function generator configuration / RFG config		
SERVO (Extended setp.), VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: 3070
	P-Group: Setpoints		Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Sets the configuration for the expanded ramp-function generator.		
Bit field:	Bit	Signal name	1 signal
	00	Disable rounding-off at the zero cross-over	Yes
			0 signal
			No
			FP
			3070
Notice:	Re bit 00: If the ramp-up time is longer than the ramp-down time (p1120 > p1121), then there is an acceleration step after the zero crossover.		
Note:	Re bit 00: When the bit is set, at the direction change there is no rounding-off before and after the zero crossover.		
p1152	BI: Setpoint 2 enable / Setpt 2 enable		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 2711
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	899.15
Description:	Sets the signal source for "setpoint 2 enable".		
p1155[0...n]	CI: Speed controller speed setpoint 1 / n_ctrl n_set 1		
SERVO, VECTOR	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1550, 3080
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for speed setpoint 1 of the speed controller.		
Dependency:	The effectiveness of this setpoint depends on, e.g. STW1.4 and STW1.6. Refer to: r0898, p1140, p1142, p1160, r1170		
p1155[0...n]	CI: Velocity controller, velocity setpoint 1 / v_ctrl n_set 1		
SERVO (Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1550, 3080
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the velocity setpoint 1 of the speed controller.		
Dependency:	The effectiveness of this setpoint depends on, e.g. STW1.4 and STW1.6. Refer to: r0898, p1140, p1142, p1160, r1170		

p1155	CI: Incremental encoder emulation speed setpoint 1 / Enc_emulat n_set 1		
TM41	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9674
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for speed setpoint 1 of the incremental encoder emulation.		
Dependency:	The effectiveness of this setpoint depends on control word 1 (STW1). Refer to: r0898		
p1160[0...n]	CI: Speed controller speed setpoint 2 / n_ctrl n_set 2		
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 1550, 3080
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for speed setpoint 2 of the speed controller.		
Dependency:	Refer to: p1155, r1170		
Note:	For OFF1/OFF3, the ramp-function generator ramp is effective. The ramp-function generator is set (SERVO: to the actual value, VECTOR: To the setpoint (r1170)) and stops the drive corresponding to the ramp-downtime (p1121 or p1135). While stopping via the ramp-function generator, STW1.4 is effective (enable ramp-function generator).		
p1160[0...n]	CI: Velocity controller, velocity setpoint 2 / v_ctrl n_set 2		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 1550, 3080
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for velocity setpoint 2 of the velocity controller.		
Dependency:	Refer to: p1155, r1170		
Note:	For OFF1/OFF3, the ramp-function generator ramp is effective. The ramp-function generator is set to the actual value and stops the drive corresponding to the ramp-downtime (p1121 or p1135). While stopping via the ramp-function generator, STW1.4 is effective (enable ramp-function generator).		
r1169	CO: Speed controller, speed setpoints 1 and 2 / n_ctrl n_set 1/2		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3080
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed setpoint after the addition of the speed setpoint 1 (p1155) and speed setpoint 2 (p1160).		
Dependency:	Refer to: p1155, p1160		
Note:	The value is only correctly displayed when the drive has been enabled.		

r1169	CO: Velocity controller, velocity setpoints 1 and 2 / v_ctrl n_set 1/2			
SERVO (Lin)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: 3080
	P-Group: Setpoints	Units group: 4_1		Unit selection: p0505
	Min - [m/min]	Max - [m/min]		Factory setting - [m/min]
Description:	Displays the velocity setpoint after the addition of the velocity setpoint 1 (p1155) and velocity setpoint 2 (p1160).			
Dependency:	Refer to: p1155, p1160			
Note:	The value is only correctly displayed when the drive has been enabled.			
r1170	CO: Speed controller, setpoint sum / n_ctr setp sum			
SERVO, VECTOR	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: 1550, 1590, 3080, 5020
	P-Group: Setpoints	Units group: 3_1		Unit selection: p0505
	Min - [1/min]	Max - [1/min]		Factory setting - [1/min]
Description:	Displays the speed setpoint after selecting the ramp-function generator and adding the speed setpoint 1 (p1155) and speed setpoint 2 (p1160).			
Dependency:	Refer to: r1150, p1155, p1160			
r1170	CO: Velocity controller, setpoint sum / v_ctrl setp sum			
SERVO (Lin)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: 1550, 1590, 3080, 5020
	P-Group: Setpoints	Units group: 4_1		Unit selection: p0505
	Min - [m/min]	Max - [m/min]		Factory setting - [m/min]
Description:	Displays the velocity setpoint after selecting the ramp-function generator and adding the velocity setpoint 1 (p1155) and velocity setpoint 2 (p1160).			
Dependency:	Refer to: r1150, p1155, p1160			
p1189[0...n]	Speed setpoint configuration / n_ctrl config			
SERVO, VECTOR	Can be changed: U, T			Access level: 2
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 3080
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0011 bin
Description:	Sets the configuration for the speed setpoint.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Interpolation ramp-fct gen/speed controller active	Yes	No
	01	Interpol. op-loop ctrl /speed controller active	Yes	No
Note:	Re bit 01: The interpolator is only effective for clock-cycle synchronous PROFIBUS operation and when the master receives a sign of life (STW 2.12 ... STW 2.15).			


p1189[0...n]	Velocity setpoint configuration / v_ctrl config		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 3080
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0011 bin
Description:	Sets the configuration for the velocity setpoint.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Interpolation ramp-fct gen/speed controller active	Yes No 3080
	01	Interpol. op-loop ctrl /speed controller active	Yes No 3080
Note:	Re bit 01: The interpolator is only effective for clock-cycle synchronous PROFIBUS operation and when the master receives a sign of life (STW 2.12 ... STW 2.15).		
p1189	Incremental encoder emulation configuration / Enc_emulat config		
TM41	Can be changed: U, T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9674
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0010 bin
Description:	Sets the configuration for the incremental encoder emulation.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	01	Interpol. op-loop ctrl /speed controller active	Yes No 9674
Note:	Re bit 01: The interpolator is only effective for clock-cycle synchronous PROFIBUS operation and when the master receives a sign of life (STW 2.12 ... STW 2.15).		
p1190	CI: DSC position deviation XERR / DSC XERR		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1550, 3090
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the position deviation XERR for DSC (position controller output of the higher-level control).		
Dependency:	Clock synchronous PROFIBUS must be active. The position controller gain factor (KPC), the position deviation (XERR) and the speed setpoint (N_SOLL_B) must be included in the setpoint telegram. At least the encoder interface (Gx_XIST1) must be included in the actual value telegram. The position actual value used for the internal position controller can be selected using p1192. Refer to: p1191, p1192		
Note:	DSC: Dynamic Servo Control		


p1191	CI: DSC position controller gain KPC / DSC KPC		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1550, 3090
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the position controller gain KPC for DSC.		
Dependency:	Refer to: p1190		
Note:	DSC: Dynamic Servo Control		
p1192[0...n]	DSC enc selection / DSC enc selection		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 3090
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 1	Max 3	Factory setting 1
Description:	Sets the number of the encoder used for DSC.		
Values:	1: Encoder 1 (motor encoder) 2: Encoder 2 3: Encoder 3		
Note:	DSC: Dynamic Servo Control Value 1 corresponds to encoder 1 (motor encoder); the encoder data set is assigned via p0187. Value 2 corresponds to encoder 2; the encoder data set is assigned via p0188. Value 3 corresponds to encoder 3; the encoder data set is assigned via p0189.		
p1193[0...n]	DSC encoder adaptation factor / DSC encodAdaptFact		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 3090
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min 0.000	Max 1000000.000	Factory setting 1.000
Description:	Sets the factor to adapt the encoder when using either encoder 2 or 3 for DSC. The factor sets the ratio of the pulse difference between the motor encoder and the selected encoder for the same distance moved through. This factor takes into account gear ratios, differences in the number of encoder pulses, etc.		
Dependency:	Refer to: p1192		
Note:	Example: Encoder 1: Motor encoder with 2048 pulses/revolution, ballscrew with 10 mm/revolution pitch Encoder 2: Linear scale with 20 µm grid division as direct measuring system $p1193 = \text{number of pulses, encoder 1 per motor revolution} / \text{number of pulses, encoder 2 per motor revolution}$ $p1193 = 2048 / (10 \text{ mm} / 20 \text{ µm}) = 4.096$		

r1197	Fixed speed setpoint, actual number / n_set_fixed No act				
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned32	Units group: -	Function diagram: 3010		
	P-Group: Setpoints		Unit selection: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the number of the selected fixed speed/velocity setpoint.				
Dependency:	Refer to: p1020, p1021, p1022, p1023				
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).				
r1197	Fixed velocity setpoint, actual number / n_set_fixed No act				
SERVO (Extended setp., Lin)	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned32	Units group: -	Function diagram: 3010		
	P-Group: Setpoints		Unit selection: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the number of the selected fixed speed/velocity setpoint.				
Dependency:	Refer to: p1020, p1021, p1022, p1023				
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0, r1197 = 0), then r1024 = 0 (setpoint = 0).				
r1198	CO/BO: Control word setpoint channel / STW setpoint chan				
SERVO (Extended setp.), VECTOR	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned16	Units group: -	Function diagram: 1530, 2505		
	P-Group: Setpoints		Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the control word for the setpoint channel.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed setp. bit 0	Yes	No	-
	01	Fixed setp. bit 1	Yes	No	-
	02	Fixed setp. bit 2	Yes	No	-
	03	Fixed setp. bit 3	Yes	No	-
	05	Inhibit negative direction	Yes	No	-
	06	Inhibit positive direction	Yes	No	-
	11	Direction reversal	Yes	No	-
	13	Motorized potentiometer, raise	Yes	No	-
	14	Motorized potentiometer, lower	Yes	No	-
	15	Bypass ramp-function generator	Yes	No	-

r1199 CO/BO: Ramp-function generator status word / RFG ZSW					
SERVO (Extended setp.), VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16		Dynamic index: -	Function diagram: 1550, 3080, 8010	
	P-Group: Setpoints		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Displays the status word for the ramp-function generator (RFG).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Ramp-up active	Yes	No	-
	01	Ramp-down active	Yes	No	-
	02	Ramp-function generator active	Yes	No	-
	03	Ramp-function generator set	Yes	No	-
	04	Ramp-function generator held	Yes	No	-
	05	Ramp-function generator tracking active	Yes	No	-
	06	Maximum limit active	Yes	No	-
Note:	Re bit 02: The bit is an OR logic operation - bit 00 and bit 01.				

p1200[0...n]	FlyRest oper mode / FlyRest oper mode		
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Integer16	Function diagram: 1690	Function diagram: 1690
	P-Group: Functions	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	6	0
Description:	Sets the operating mode for flying restart. The flying restart allows the drive converter to be powered-up while the motor is still rotating. In so doing, the drive converter output frequency is changed until the actual motor speed/velocity is found.. The motor then accelerates up to the setpoint at the ramp generator setting.		
Values:	0: Flying restart inactive 1: Flying restart always active (start in setpoint direction) 2: FlyRestart active after on, fault, OFF2 (start in setp. dir.) 3: FlyRestart active after fault, OFF2 (start in setp. direction) 4: Flying restart always active (start only in setpoint direction) 5: FlyRestart active after on, fault, OFF2 (start only in setp_dir) 6: FlyRestart active after fault, OFF2 (start only in setp. dir.)		
Dependency:	A differentiation is made between flying restart for U/f control and for vector control (p1300). Flying restart, U/f control: p1202, p1203, r1204 Flying restart for vector control: p1202, p1203, r1205		
Notice:	The "flying restart" function must be used in cases where the motor is possibly still running (e.g. after a brief line supply interruption) or is being driven by the load. The system might otherwise shut down as a result of overcurrent. It does not make sense to use "flying restart" together with the "motor holding brake function" (p1215 > 0) because then the flying restart will always be realized with the motor stationary.		
Note:	For p1202 = 100 % and p1203 = 100 %, the following applies: The flying restart takes, as a maximum, twice as long as the motor excitation time (p0346). For p1200 = 1, 4, the following applies: Flying restart is active after faults, OFF1, OFF2, OFF3. For p1200 = 2, 5, the following applies: The "power-on" is the first power-on operation after the drive system has been booted. This is practical for motors with a high-inertia load. For p1200 = 1, 2, 3, the following applies: The search is made in both directions. For p1200 = 4, 5, 6, the following applies: The search is only made in the setpoint direction. For operation with encoder, the following applies: p1200 = 1, 4 as well as p1200 = 2, 5 and p1200 = 3, 6 have the same meaning. For U/f control (p1300 > 20), the following applies: The speed can only be sensed for values above approx. 5% of the rated motor speed. At lower speeds, it is assumed that the motor is at a standstill (zero speed). If p1200 is changed while commissioning (p0009, p0010 > 0), then it is possible that the old value will no longer be able to be set. The reason for this is that the dynamic limits of p1200 have been changed by a parameter that was set when the drive was commissioned (e.g. p0300).		

p1202[0...n]	FlyRest srch curr / FlyRest srch curr		
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 4
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Functions		Unit selection: -
	Min 10 [%]	Max 400 [%]	Factory setting 100 [%]
Description:	Sets the search current for the "flying restart" function. The value is referred to the motor magnetizing current.		
Dependency:	Refer to: r0331		
Caution:	An unfavorable parameter value can result in the motor behaving in an uncontrollable fashion.		
			
Note:	Reducing the search current can improve the flying restart performance (if the system moment of inertia is not very high).		

p1203[0...n]	Flying restart search rate factor / FlyRst v_Srch Fact		
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 4
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Functions		Unit selection: -
	Min 10 [%]	Max 400 [%]	Factory setting 100 [%]
Description:	The value influences the rate at which the output frequency is changed during a flying restart . A higher value results in a longer search time.		
Caution:	An unfavorable parameter value can result in the motor behaving in an uncontrollable fashion.		
			
Notice:	For vector control, a value that is too low or too high can cause flying restart to become unstable.		

r1204	CO/BO: Flying restart, U/F control status / FlyRestrt Uf stat				
VECTOR	Can be changed: -	Dynamic index: -	Access level: 4		
	Data type: Unsigned16	Units group: -	Function diagram: -		
	P-Group: Functions		Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the status for checking and monitoring flying restart states in the U/f control mode.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Current impressed	Yes	No	-
	01	No current flow	Yes	No	-
	02	Voltage input	Yes	No	-
	03	Voltage reduced	Yes	No	-
	04	Start ramp-function generator	Yes	No	-
	05	Wait for execution	Yes	No	-
	06	Slope filter act	Yes	No	-
	07	Positive gradient	Yes	No	-
	08	Current < thresh	Yes	No	-
	09	Current minimum	Yes	No	-
	10	Search in the positive direction	Yes	No	-
	11	Stop after positive direction	Yes	No	-
	12	Stop after negative direction	Yes	No	-
	13	No result	Yes	No	-

r1205		CO/BO: Flying restart, vector control status / FlyRestrtVectStat			
VECTOR	Can be changed: -			Access level: 4	
	Data type: Unsigned16	Dynamic index: -		Function diagram: -	
	P-Group: Functions	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the status for checking and monitoring flying restart states in the vector control mode.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Save the angle of the speed adaptation circuit	Yes	No	-
	01	Set speed adaptation circuit gain to 0	Yes	No	-
	02	Enable Isd channel	Yes	No	-
	03	Speed control switched-in	Yes	No	-
	04	Quadrature arm switched-in	Yes	No	-
	05	Special transformation active	Yes	No	-
	06	Set I comp of the speed adaptation circuit to 0	Yes	No	-
	07	Current control on	Yes	No	-
	08	Isd_set = 0 A	Yes	No	-
	09	Reserved	Yes	No	-
	10	Search in the positive direction	Yes	No	-
	11	Search Started	Yes	No	-
	12	Current impressed	Yes	No	-
	13	Search interrupted	Yes	No	-
	14	Deviation of the speed adaptation circuit = 0	Yes	No	-
	15	Speed control activated	Yes	No	-
Note:	Bits 0..9: Used by the control in internal sequences during the flying restart. Depending on the machine type (p0300), the number of active bits differs. Bits 10..15: Are used to monitor the flying restart sequence. For PEM, only bits 10, 11 and 15 are supported.				
p1207		BI: AR connection following drive object / AR connection DO			
A_INF, B_INF, S_INF	Can be changed: U, T			Access level: 3	
	Data type: Unsigned32	Dynamic index: -		Function diagram: -	
	P-Group: -	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0	
Description:	Modifies the pre-charging monitoring of the infeed. The active automatic restart (AR) of the following drive object can be interconnected using this binector input (BI: p1207 = r1214.2). This means that when the automatic restart is operational, the pre-charging monitoring of the infeed is de-activated and is only re-activated under the following conditions: - the absolute current in the DC link is greater than 2 % of the maximum current (r0209) of the infeed to provide protection against short-circuit in the DC link. - if a Voltage Sensing Module (VSM) is being used, the line supply voltage amplitude is greater than 3 % of the parameterized unit supply voltage (p0210) to protect the pre-charging resistors against continuous filter current when the line supply partially returns.				
Dependency:	Refer to: r0209, p0210, r1214				

p1208[0...1]	BI: AR infeed fault / AR infeed fault		
VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	Factory setting	
	-	-	0
Description:	<p>Modifying the automatic restart.</p> <p>By interconnecting the binector output of the infeed "Infeed fault" to this binector input Index 0 (p1208[0] = r2139.3), the automatic restart function of the subsequent DOs - in mode p1210 = 6 - can respond to infeed faults.</p> <p>By interconnecting the binector output of the infeed "Infeed line supply failure" to this binector input Index 1 (p1208[1] = r0863.2), the automatic restart function of the subsequent DOs, in the mode p1210 = 4, can respond to the line supply failure of the infeed.</p>		
Index:	<p>[0] = Infeed fault [1] = Fault</p>		
Dependency:	Refer to: r0863, r2139		
p1210	Automatic restart, mode / AR mode		
A_INF, B_INF, S_INF	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Functions	Max	Unit selection: -
	Min	Factory setting	
	0	6	0
Description:	Sets the automatic restart mode (AR).		
Values:	<p>0: Disables automatic restart 1: Acknowledges all faults without restarting 4: Restart after power failure without additional start attempts 6: Restart after fault with additional start attempts</p>		
Dependency:	<p>The automatic restart requires an active ON command, e.g. that is available at a digital input.</p> <p>If, for p1210 = 4, 6 there is no active ON command, then the automatic restart is interrupted.</p> <p>When using an Advanced Operator Panel (AOP) in the LOCAL Mode, then there is no automatic restart.</p> <p>Refer to: p0840, p0857, p1267</p> <p>Refer to: F30003</p>		
Caution:	<p>A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).</p> <p>For p1210 > 1, the infeed is automatically started.</p>		
Note:	<p>p1210 = 4: An automatic restart is only executed if fault F06200 has occurred. If additional faults are present, then these faults are also acknowledged and when successful, starting continues. If the 24 V CU power supply fails, then this is interpreted as a line supply failure.</p> <p>p1210 = 6: An automatic restart is carried-out if any fault has occurred.</p> <p>p1210 = 1: Faults that are present are automatically acknowledged. If new faults occur after a successful fault acknowledgement, then these are also automatically acknowledged again. A minimum time of p1212 + 1s must expire between a successful fault acknowledgement and a fault re-occurring if the signal ON/OFF1 (control word 1, bit 0) is at a HIGH signal level. If the signal ON/OFF1 is at a LOW signal level, then the time between a successful fault acknowledgement and a new fault must be at least 1s.</p> <p>For p1210 = 1, fault F07320 is not generated if the acknowledgement attempt was not successful, for example, due to frequently occurring faults.</p>		

p1210	Automatic restart, mode / AR mode		
VECTOR	Can be changed: U, T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Sets the automatic restart mode (AR).		
Values:	0: Disables automatic restart 1: Acknowledges all faults without restarting 4: Restart after power failure without additional start attempts 6: Restart after fault with additional start attempts		
Dependency:	The automatic restart requires an active ON command, e.g. that is available at a digital input. If, for p1210 = 4, 6 there is no active ON command, then the automatic restart is interrupted. When using an Advanced Operator Panel (AOP) in the LOCAL Mode, then there is no automatic restart. Refer to: p0840, p0857, p1267 Refer to: F30003		
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1). For p1210 > 1, the motor is automatically started.		
Note:	For brief line supply failures, the motor shaft can still be rotating when restarting. In order to restart while the motor shaft is still rotating, the "flying restart" function should be activated using p1200. p1210 = 4: An automatic restart is only carried-out if Fault F30003 occurred at the Motor Module or a high signal is present at the binector input p1208[1]. If additional faults are present, then these faults are also acknowledged and when successful, starting continues. If the 24 V CU power supply fails, then this is interpreted as a line supply failure. p1210 = 6: An automatic restart is carried-out if any fault has occurred and there is a high signal at binector input p1208[0]. p1210 = 1: Faults that are present are automatically acknowledged. If new faults occur after a successful fault acknowledgement, then these are also automatically acknowledged again. A minimum time of p1212 + 1s must expire between a successful fault acknowledgement and a fault re-occurring if the signal ON/OFF1 (control word 1, bit 0) is at a HIGH signal level. If the signal ON/OFF1 is at a LOW signal level, then the time between a successful fault acknowledgement and a new fault must be at least 1s. For p1210 = 1, fault F07320 is not generated if the acknowledgement attempt was not successful, for example, due to frequently occurring faults.		

p1211 Automatic restart, start attempts / AR start attempts		
A_INF	Can be changed: U, T	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Functions	Units group: -
	Min 0	Max 10
		Factory setting 3
Description:	Sets the absolute number of start attempts for the automatic restart function when any faults are automatically acknowledged (p1210 = 6).	
Dependency:	The setting of this parameter is always effective for p1210 = 6. For p1210 = 4, the parameter only has an influence if an additional line phase failure (F6200) occurs at the start attempt. Refer to: p1210, r1214 Refer to: F07320	
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).	
Notice:	After fault F07320 occurs, the power-on command must be withdrawn and all of the faults acknowledged so that the automatic restart function is re-activated.	
Note:	<p>A starting attempt starts immediately when a fault occurs. The restart attempt is considered to have been completed if the infeed was powered-up and an additional delay time of 1 s has expired.</p> <p>As long as a fault is present, an acknowledge command is generated in the time intervals of p1212 / 2. When successfully acknowledged, the start counter is decremented. If, after this, a fault re-occurs before a restart has been completed, then acknowledgement starts again from the beginning.</p> <p>Fault F07320 is output if, after several faults occur, the number of parameterized start attempts has been reached. After a successful start attempt - i.e. a fault/error no longer occurred up to the end of the power-up operation - after 1s the start counter is again reset to the parameter value. If a fault re-occurs - the parameterized number of start attempts is again available.</p> <p>At least one start attempt is always carried-out.</p> <p>After a line supply failure, acknowledgement is immediate and when the line supply returns, the system is powered-up. If, between successfully acknowledging the line fault and the line supply returning, another fault occurs, then its acknowledgement also causes the start counter to be decremented.</p>	

p1211		Automatic restart, start attempts / AR start attempts		
VECTOR	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Functions	Units group: -		Unit selection: -
	Min 0	Max 10		Factory setting 3
Description:	Sets the absolute number of start attempts for the automatic restart function when any faults are automatically acknowledged (p1210 = 6).			
Dependency:	The setting of this parameter is always effective for p1210 = 6. For p1210 = 4, the parameter only has an influence if an additional undervoltage fault occurs at the start attempt. Refer to: p1210, r1214 Refer to: F07320			
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).			
Notice:	After fault F07320 occurs, the power-on command must be withdrawn and all of the faults acknowledged so that the automatic restart function is re-activated.			
Note:	<p>A starting attempt starts immediately when a fault occurs. The start attempt is considered to be completed if the motor was magnetized (r0056.4 = 1) and an additional delay time of 1 s has expired.</p> <p>As long as a fault is present, an acknowledge command is generated in the time intervals of p1212 / 2. When successfully acknowledged, the start counter is decremented. If, after this, a fault re-occurs before a restart has been completed, then acknowledgement starts again from the beginning.</p> <p>Fault F07320 is output if, after several faults occur, the number of parameterized start attempts has been reached. After a successful start attempt, i.e. a fault/error has no longer occurred up to the end of the magnetizing phase, the start counter is again reset to the parameter value after 1 s. If a fault re-occurs - the parameterized number of start attempts is again available.</p> <p>At least one start attempt is always carried-out.</p> <p>After a line supply failure, acknowledgement is immediate and when the line supply returns, the system is powered-up. If, between successfully acknowledging the line fault and the line supply returning, another fault occurs, then its acknowledgement also causes the start counter to be decremented.</p>			
p1211		Automatic restart, start attempts / AR start attempts		
B_INF, S_INF	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Functions	Units group: -		Unit selection: -
	Min 0	Max 10		Factory setting 3
Description:	Sets the absolute number of start attempts for the automatic restart function when any faults are automatically acknowledged (p1210 = 6).			
Dependency:	The setting of this parameter is always effective for p1210 = 6. For p1210 = 4, the parameter only has an influence if an additional line phase failure (F6200) occurs at the start attempt. Refer to: p1210, r1214 Refer to: F07320			
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).			
Notice:	After fault F07320 occurs, the power-on command must be withdrawn and all of the faults acknowledged so that the automatic restart function is re-activated.			

Note: A starting attempt starts immediately when a fault occurs. The restart attempt is considered to have been completed if the infeed was powered-up and an additional delay time of 1 s has expired.

As long as a fault is present, an acknowledge command is generated in the time intervals of $p1212 / 2$. When successfully acknowledged, the start counter is decremented. If, after this, a fault re-occurs before a restart has been completed, then acknowledgement starts again from the beginning.

Fault F07320 is output if, after several faults occur, the number of parameterized start attempts has been reached. After a successful start attempt, i.e. a fault/error has no longer occurred up to the end of the power-up operation, the start counter is again reset to the parameter value after 1 s. If a fault re-occurs - the parameterized number of start attempts is again available.

At least one start attempt is always carried-out.

After a line supply failure, acknowledgement is immediate and when the line supply returns, the system is powered-up. If, between successfully acknowledging the line fault and the line supply returning, another fault occurs, then its acknowledgement also causes the start counter to be decremented.

p1212	Automatic restart, delay time start attempts / AR t_wait start		
A_INF, B_INF, S_INF, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Functions		Unit selection: -
	Min 0.1 [s]	Max 600.0 [s]	Factory setting 1.0 [s]
Description:	Sets the delay time up to restart.		
Dependency:	This parameter setting is active for $p1210 = 1, 4, 6$. Refer to: p1210, r1214		
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).		
Note:	The faults are automatically acknowledged after half of the waiting time has expired and the full waiting time. If the cause of a fault is not removed in the first halves of the delay time, then it is no longer possible to acknowledge in this time slice.		

p1213	Automatic restart, monitoring time line supply return / AR t_mon line sup		
A_INF, B_INF, S_INF	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Functions		Unit selection: -
	Min 0.0 [s]	Max 1999.0 [s]	Factory setting 0.0 [s]
Description:	Sets the monitoring time of the automatic restart (AR).		
Dependency:	Refer to: p1210, r1214		
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).		
Notice:	After fault F07320 occurs, the power-on command must be withdrawn and all of the faults acknowledged so that the automatic restart function is re-activated.		
Note:	The monitoring time starts when the faults are detected. If the automatic acknowledgements are not successful, the monitoring time runs again. After fault F07320 occurs, the power-on command must be withdrawn and all of the faults acknowledged so that the automatic restart can be re-activated.		
	The monitoring is de-activated with $p1213 = 0$. If the time in p1213 is set lower than in p1212, then fault F07320 is also generated at each restart.		
	The monitoring time must be extended, if the faults that occur cannot be immediately and successfully acknowledged (e.g. for faults that are permanently present).		

p1213	Automatic restart, monitoring time line supply return / AR t_mon line sup		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.0 [s]	Max 1999.0 [s]	Factory setting 0.0 [s]
Description:	Sets the monitoring time of the automatic restart (AR).		
Dependency:	Refer to: p1210, r1214		
Caution:	A change is only accepted and made if the state "initialization" (r1214.0) and "wait for alarm" (r1214.1).		
Notice:	After fault F07320 occurs, the power-on command must be withdrawn and all of the faults acknowledged so that the automatic restart function is re-activated.		
Note:	The monitoring time starts when the faults are detected. If the automatic acknowledgements are not successful, the monitoring time runs again. If, after the monitoring time has expired, the drive has still not successfully started again (flying restart and magnetization of the motor must have been completed: r0056.4 = 1), then fault F07320 is output. The monitoring is de-activated with p1213 = 0. If p1213 is set lower than the sum of p1212, the magnetizing time p0346 and the additional delay time due to the flying restart, then fault F07320 is generated at each restart. If, for p1210 = 1, the time in p1213 is set lower than in p1212, then fault F07320 is also generated at each restart. The monitoring time must extended, if the faults that occur cannot be immediately and successfully acknowledged (e.g. for faults that are permanently present).		

r1214	CO/BO: Automatic restart, status / AR status			
A_INF, B_INF, S_INF	Can be changed: -			Access level: 4
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Functions	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Automatic restart (AR) status word.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Initialization	Yes	No
	01	Wait for alarm	Yes	No
	02	Auto restart act.	Yes	No
	03	Setting the acknowledgement command	Yes	No
	04	Acknowledge alarms	Yes	No
	05	Restart	Yes	No
	06	Delay time running after automatic power-up	Yes	No
	07	Fault	Yes	No
	12	Start count. bit 0	On	Off
	13	Start count. bit 1	On	Off
	14	Start count. bit 2	On	Off
	15	Start count. bit 3	On	Off
Note:	Re bit 00: Status to display the single initialization after power on.			
	Re bit 01: State in which the automatic restart function waits for faults (initial state).			
	Re bit 02: General display that a fault has been identified and that the restart or acknowledgement has been initiated.			
	Re bit 03: Displays the acknowledge command within the 'acknowledge alarms' status (bit 04 = 1). For bit 05 = bit 06 = 1, the acknowledge command is continually displayed.			

Re bit 04:

State in which the faults that are present are acknowledged. The status is exited again after successful acknowledgement. A change is only made into the next state if it is signaled that a fault is no longer present after an acknowledgement command (bit 3 = 1).

Re bit 05:

State in which the drive is automatically powered-up (only for p1210 = 4, 6).

Re bit 06:

State in which the system waits after having been powered-up, to the end of the start attempt.
For p1210 = 1, this signal is directly set after the faults have been successfully acknowledged.

Re bit 07:

State, which is assumed after a fault occurs within the automatic restart function.

Re bits 12 ... 15:

Actual state of the start counter (binary coded).

r1214

CO/BO: Automatic restart, status / AR status

VECTOR

Can be changed: -

Access level: 4

Data type: Unsigned16

Dynamic index: -

Function diagram: -

P-Group: Functions

Units group: -

Unit selection: -

Min

Max

Factory setting
0000 bin

-

-

Description:

Automatic restart (AR) status word.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Initialization	Yes	No	-
01	Wait for alarm	Yes	No	-
02	Auto restart act.	Yes	No	-
03	Setting the acknowledgement command	Yes	No	-
04	Acknowledge alarms	Yes	No	-
05	Restart	Yes	No	-
06	Delay time running after automatic power-up	Yes	No	-
07	Fault	Yes	No	-
12	Start count. bit 0	On	Off	-
13	Start count. bit 1	On	Off	-
14	Start count. bit 2	On	Off	-
15	Start count. bit 3	On	Off	-

Note:

Re bit 00:

Status to display the single initialization after power on.

Re bit 01:

State in which the automatic restart function waits for faults (initial state).

Re bit 02:

General display that a fault has been identified and that the restart or acknowledgement has been initiated.

Re bit 03:

Displays the acknowledge command within the 'acknowledge alarms' status (bit 04 = 1). For bit 05 = bit 06 = 1, the acknowledge command is continually displayed.

Re bit 04:

State in which the faults that are present are acknowledged. The status is exited again after successful acknowledgement. A change is only made into the next state if it is signaled that a fault is no longer present after an acknowledgement command (bit 3 = 1).

Re bit 05:

State in which the drive is automatically powered-up (only for p1210 = 4, 6).

Re bit 06:

State in which the system waits after having been powered-up, to the end of the start attempt (to the end of the magnetization process).

For p1210 = 1, this signal is directly set after the faults have been successfully acknowledged.

Re bit 07:

State, which is assumed after a fault occurs within the automatic restart function.

Re bits 12 ... 15:

Actual state of the start counter (binary coded).

p1215		Motor holding brake configuration / Brake config		
SERVO, VECTOR	Can be changed: U, T			Access level: 2
	Data type: Integer16		Dynamic index: -	Function diagram: 2701, 2707, 2711
	P-Group: Functions		Units group: -	Unit selection: -
	Min 0		Max 3	Factory setting 0
Description:	Sets the holding brake configuration.			
Values:	0: No motor holding brake being used 1: Motor holding brake acc. to sequence control 2: Motor holding brake always open 3: Motor holding brake like sequence control, connection via BICO			
Dependency:	Refer to: p1216, p1217, p1226, p1227, p1228			
Caution:	For the setting p1215 = 0, if a brake is used, it remains closed. If the motor moves, this will destroy the brake.			
Notice:	If p1215 was set to 1 or if p1215 was set to 3, then when the pulses are cancelled, the brake is closed even if the motor is still rotating. Pulse cancellation can either be caused by a 0 signal at p0844, p0845 or p0852 or as a result of a fault with OFF2 response. If this is not desirable (e.g. for a flying restart), then the brake can be kept open using a 1 signal at p0855.			
Note:	If the configuration is set to "no holding brake present" when booting, then the motor holding brake will be automatically identified. If a motor holding brake is detected, the configuration is set to "motor holding brake as for sequence control". if an external motor holding brake is being used, then p1215 should be set to 3 and r0899.12 should be interconnected as control signal. When the function module "extended brake control" is activated (r0108.14 = 1), r1229.1 should be interconnected as control signal. The parameter can only be set to zero when the pulses are inhibited. The parameterization "no motor holding brake available" and "Safe Brake Control" enabled (p1215 = 0, p9602 = 1, p9802 = 1) is not practical if there is no motor holding brake. The parameterization "motor holding brake the same as sequence control, connection via BICO" and "Safe Brake Control" enabled (p1215 = 3, p9602 = 1, p9802 = 1) is not practical.			

p1216		Motor holding brake, opening time / Brake t_{open}		
SERVO, VECTOR	Can be changed: U, T			Access level: 2
	Data type: Floating Point		Dynamic index: -	Function diagram: 2701, 2711
	P-Group: Functions		Units group: -	Unit selection: -
	Min 0 [ms]		Max 10000 [ms]	Factory setting 100 [ms]
Description:	Sets the time to open the motor holding brake. After controlling the holding brake (opens), the speed/velocity setpoint remains at zero for this time. After this, the speed/velocity setpoint is enabled.			
Recommendation:	This time should be set longer than the actual opening time of the brake. This ensures that the drive cannot accelerate when the brake is applied.			
Dependency:	Refer to: p1215, p1217			

p1217	Motor holding brake closing time / Brake t_close		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 2701, 2711
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0 [ms]	Max 10000 [ms]	Factory setting 100 [ms]
Description:	Sets the time to apply the motor holding brake. After OFF1 or OFF3 and the holding brake is controlled (the brake closes), then the drive remains closed-loop controlled for this time stationary with a speed setpoint/velocity setpoint of zero. The pulses are cancelled when the time expires.		
Recommendation:	This time should be set longer than the actual closing time of the brake. This ensures that the pulses are only canceled after the brake has closed.		
Dependency:	Refer to: p1215, p1216		
Notice:	If the selected closing time is too short with respect to the actual closing time of the brake, then the load can sag. If the closing time is selected to be too long with respect to the actual closing time of the brake, the control works against the brake and therefore reduces its lifetime.		
p1218[0...1]	BI: Open motor holding brake / Open brake		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2707
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for a conditional opening of the motor holding brake.		
Dependency:	Refer to: p1215		
Note:	[0]: Signal, open brake, AND logic operation, input 1 [1]: Signal, open brake, AND logic operation, input 2		
p1219[0...3]	BI: Immediately close motor holding brake / Close brake		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2707
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting [0] 0 [1] 0 [2] 0 [3] 1229.9
Description:	Sets the signal source for an unconditional (immediate) closing of the motor holding brake.		
Dependency:	Refer to: p1215, p1275		
Note:	[0]: Signal, immediately close brake, inversion via p1275.0 [1]: Signal, immediately close brake, inversion via p1275.1 [2]: Signal, immediately close brake [3]: Signal, immediately close brake - refer to the factory setting These four signals form an OR logic operation.		

p1220	CI: Open motor holding brake, signal source, threshold / Open brake thresh		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2707
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the command "open brake".		
Dependency:	Refer to: p1215, p1221, r1229, p1277		
p1221	Open motor holding brake, threshold / Open brake thresh		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 2707
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Sets the threshold value for the command "open brake".		
Dependency:	Refer to: p1220, r1229, p1277		
p1222	BI: Motor holding brake, feedback signal, brake closed / Brake feedb closed		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2711
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the feedback signal "brake closed". For motor holding brakes with feedback signal, the signal "brake closed" can be activated using p1275.5 = 1.		
Dependency:	Refer to: p1223, p1275		
Note:	1 signal: Brake closed. When braking with 1 feedback signal, the inverted feedback signal is connected to the BICO input for the second feedback signal (p1223).		
p1223	BI: Motor holding brake, feedback signal, brake open / Brake feedb open		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2711
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the feedback signal "brake open". For motor holding brakes with feedback signal, the signal "brake open" can be activated using p1275.5 = 1.		
Dependency:	Refer to: p1222, p1275		
Note:	1 signal: Brake open. When braking with 1 feedback signal, the inverted feedback signal is connected to the BICO input for the second feedback signal (p1222).		

p1224[0...3]	BI: Close motor holding brake at standstill / Brk close standst		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2704
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for close brake at standstill.		
Dependency:	Refer to: p1275		
Note:	[0]: Signal, close brake at standstill, inversion via p1275.2 [1]: Signal, close brake at standstill, inversion via p1275.3 [2]: Signal, close brake at standstill [3]: Signal, close brake at standstill These four signals form an OR logic operation.		
p1225	CI: Standstill detection, threshold value / Standstill thresh		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2704
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 63[0]
Description:	Sets the signal source "threshold value" for the standstill identification.		
Dependency:	Refer to: p1226, p1228, r1229		
p1226	Threshold for zero speed detection / n_standst n_thresh		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 2701, 2704
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 20.0 [1/min]
Description:	Sets the speed threshold for the standstill identification. Acts on the actual value and setpoint monitoring. When braking with OFF1 or OFF3, when the threshold is fallen below, standstill is identified. The following applies when the braking signal is activated: When the threshold is fallen below, the braking signal is started and the system waits for the brake closing time in p1217. The pulses are then canceled. if the braking signal is not activated, the following applies: When the threshold is fallen below, the pulses are cancelled and the drive coasts down.		
Dependency:	Refer to: p1215, p1216, p1217, p1227		
Note:	Standstill is detected if the actual speed drops below the speed threshold in p1226 or if the monitoring time (p1227) - started when speed setpoint <= speed threshold (p1226) - has expired. The actual value sensing is subject to measuring noise. For this reason, standstill cannot be detected if the speed threshold is too low.		

p1226	Standstill detection, velocity threshold / v_standst v_thresh		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 2701, 2704
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 0.2 [m/min]
Description:	Sets the velocity threshold for the standstill identification. Acts on the actual value and setpoint monitoring. When braking with OFF1 or OFF3, when the threshold is fallen below, standstill is identified. The following applies when the braking signal is activated: When the threshold is fallen below, the braking signal is started and the system waits for the brake closing time in p1217. The pulses are then canceled. If the braking signal is not activated, the following applies: When the threshold is fallen below, the pulses are cancelled and the drive coasts down.		
Dependency:	Refer to: p1215, p1216, p1217, p1227		
Note:	Standstill is detected if the actual velocity drops below the velocity threshold in p1226 or if the monitoring time (p1227) - started when the velocity setpoint <= velocity threshold (p1226) - has expired. The actual value sensing is subject to measuring noise. For this reason, standstill cannot be detected if the velocity threshold is too low.		
p1227	Zero speed detection monitoring time / n_standst t_monit		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 2701, 2704
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 300.000 [s]	Factory setting 4.000 [s]
Description:	Sets the monitoring time for the standstill identification. When braking with OFF1 or OFF3, standstill is identified after this time has expired, after the setpoint speed has fallen below p1226 (also refer to p1145). After this, the braking signal is started, the system waits for the closing time in p1217 and then the pulses are cancelled.		
Dependency:	Refer to: p1215, p1216, p1217, p1226		
Note:	Standstill (zero speed) is detected if, during the complete monitoring time (p1227), the speed setpoint falls below the speed threshold (p1226). For p1227 = 300.000 s, the following applies: The monitoring is deactivated. For p1227 = 0.000 s, the following applies: With OFF1 or OFF3 and a ramp-down time = 0, the pulses are immediately cancelled and the motor "coasts" down.		
p1228	Pulse cancellation delay time / Pulse canc t_del		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 2701, 2704
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 10.000 [s]	Factory setting 0.000 [s]
Description:	Sets the delay time for pulse cancellation. After OFF1 or OFF3 and zero speed detection, the system waits for this time to expire and the pulses are then canceled.		
Dependency:	Refer to: p1226, p1227		
Note:	Standstill (zero speed) is detected if, during the complete delay time (p1228), the speed actual value falls below the speed threshold (p1226).		

r1229 CO/BO: Motor holding brake status word / Brake ZSW

SERVO (Extended brk), VECTOR (Extended brk)

Can be changed: -**Data type:** Unsigned32**Dynamic index:** -**Access level:** 2**Function diagram:** -**P-Group:** Functions**Units group:** -**Unit selection:** -**Min**

-

Max

-

Factory setting

0000 bin

Description: Displays the status word for the motor holding brake.**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
01	Command, open brake (continuous signal)	Yes	No	2711
03	Pulse enable, expanded brake control	Yes	No	2711
04	Brake does not open	Yes	No	2711
05	Brake does not close	Yes	No	2711
06	Brake threshold exceeded	Yes	No	2707
07	Brake threshold fallen below	Yes	No	2704
08	Brake monitoring time expired	Yes	No	2704
09	Pulse enable request missing/n_ctrl inhibited	Yes	No	2707
10	Brake OR logic operation result	Yes	No	2707
11	Brake AND logic operation result	Yes	No	2707

p1230[0...n] BI: Activating armature short-circuit / ASC act

SERVO, VECTOR

Can be changed: T**Data type:** Unsigned32**Dynamic index:** CDS, p0170**Access level:** 1**Function diagram:** -**P-Group:** Functions**Units group:** -**Unit selection:** -**Min**

-

Max

-

Factory setting

0

Description: Sets the signal source to activate the armature short-circuit.**Dependency:** Refer to: p1231, p1235, p1236, p1237, r1239**Note:** 0 signal: Armature short-circuit is de-activated.
1 signal: Armature short-circuit is activated.**p1231[0...n] Configuration, armature short-circuit / ASC config**

SERVO, VECTOR

Can be changed: U, T**Data type:** Integer16**Dynamic index:** MDS, p0130**Access level:** 1**Function diagram:** -**P-Group:** Functions**Units group:** -**Unit selection:** -**Min**

0

Max

3

Factory setting

0

Description: Setting to activate various types of armature short-circuit configurations.**Values:** 0: No function
1: External armature short-circuit with contactor feedback signal
2: Ext. armature short-circuit without contactor feedback signal
3: Internal voltage protection**Dependency:** Refer to: p0300, p1230, p1235, p1236, p1237, r1239

Danger:

Re p1231 = 1, 2:

- only short-circuit proof motors may be used and suitable resistors must be used to short-circuit the motor.

Re p1231 = 3:

- when the internal voltage protection is active, after pulse cancellation, all of the motor terminals are at half of the DC link voltage (without an internal voltage protection, the motor terminals are at zero potential)!

- it is only permissible to use motors that are short-circuit proof (p0320<p0323).

- the Motor Module must be able to continually conduct 180% short-circuit current (r0331) of the motor (r0289).

- the internal voltage protection cannot be interrupted due to a fault response. If an overcurrent condition occurs during the active, internal voltage protection, then this can destroy the Motor Module and/or the motor.

- in order to ensure safe function of IVP when the power fails, an external 24 V power supply (UPS) must be used for all of the components.

Note:

Re p1231 = 1, 2:

The external armature short-circuit can only be selected for synchronous motors (p0300). In this case, control bit BO: r1239.0 must be interconnected to control the external contactor (e.g. to a digital input).

Re p1231 = 3:

The internal voltage protection (using an internal armature short-circuit) can only be selected for synchronous motors (p0300) and Booksize Motor Modules. Further, it is not permissible that Safety is active (i.e. p9501 = 0 and p9601 = 0). The internal voltage protection prevents the DC link capacitance from being charged if there is no possibility of regenerating the EMF of a motor operated in the field-weakening mode.

Note:

ASC: Armature Short-Circuit

IVP: Internal Voltage Protection

UPS: Uninterruptible Power Supply

p1235[0...n]	BI: External armature short-circuit, contactor feedback signal / ASC ext feedback		
SERVO, VECTOR	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the contactor feedback signal for external armature short-circuit.		
Dependency:	Refer to: p1230, p1231, p1236, p1237, r1239		
Notice:	In order that the pulses are not enabled when the contactor is closed, the contactor feedback signal must lag by a sufficiently long time when opening the contactor.		
Note:	1 signal: The contactor is closed. 0 signal: The contactor is open.		

p1236[0...n]	Ext. armature short-cct., contactor feedback signal monit. time / ASC ext t_monit		
SERVO, VECTOR	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0 [ms]	1000 [ms]	200 [ms]
Description:	Sets the monitoring time of the contactor feedback signal for the external armature short-circuit configuration. If the contactor feedback signal (p1235) is parameterized, then the appropriate feedback signal (r1239.1) is expected within this monitoring time after either opening or closing the contactor.		
Dependency:	Refer to: p1230, p1231, p1235, p1237, r1239 Refer to: A07904, F07905		

p1237[0...n]	External armature short-circuit, waiting time when opening / ASC ext t_wait		
SERVO, VECTOR	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 200 [ms]
Description:	Sets the delay time when opening the contactor of the external armature short-circuit. If no contactor feedback signal has been selected (p1235), then the system waits for this time before the pulses are switched-in.		
Dependency:	Refer to: p1230, p1231, p1235, p1236, r1239		
Notice:	This delay time must be at least long enough so that the contactor contacts reliably open before the pulses are switched-in. The delay time must be greater than the contactor response time. The Motor Module can be damaged if the delay time is too short.		
r1238	CO: Armature short-circuit, external state / EASC state		
SERVO, VECTOR	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: 2610
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Displays the state for the external armature short-circuit.		
Values:	<ul style="list-style-type: none"> 0: Powered-down 1: Ready 2: active 3: Active - feedback signal "closed" OK 4: Active - feedback signal "closed" missing 5: Prompt to remove the armature short-circuit 6: Active - feedback signal "open" missing 		
Dependency:	Refer to: p1230, p1231, p1235, p1236, p1237, r1239 Refer to: A07904, F07905		
Note:	<p>Activation criteria (one of the following criteria is fulfilled):</p> <ul style="list-style-type: none"> - the signal at BI: p1230 (armature short-circuit activation) is 0. - the drive is not in the state "S4: Operation" or in S5x (refer to function chart 2610). - the internal pulse enable is missing (r0046.19 = 0). <p>Re state "switched-out" (r1238 = 0):</p> <ul style="list-style-type: none"> - the external armature short-circuit can be selected with p1231 = 1. <p>Re state "ready" (r1238 = 1):</p> <ul style="list-style-type: none"> - as soon as the activation criteria is fulfilled, then a transition is made into the state "active" (r1238 = 2). <p>Regarding the state "active" (r1238 = 2), "active - feedback signal "closed" OK" (r1238 = 3), "active - feedback signal "closed" missing" (r1238 = 4)":</p> <ul style="list-style-type: none"> - the control signal to close contactor r1239.0 is set to "1" (closed) and the pulses are cancelled. - if a contactor feedback signal is not connected (BI: p1235 = 0), then a transition is immediately made into state 3. - if a contactor feedback signal is connected, then a transition is made into state 3 if the feedback signal at BI: p1235 goes to "1" (closed) within the monitoring time (p1236). - otherwise, a transition is made into state 4. 		

Re state "prompt to remove the armature short-circuit" (r1238 = 5):

- the activation criteria is no longer fulfilled. An attempt is made to again remove the armature short circuit.
- the control signal to close the contactor r1239.0 is set to "0" (open) and the pulses remain cancelled.
- if a contactor feedback signal is not connected (BI: p1235 = 0), the system waits for the delay time (p1237) to expire until a transition is made into state 1.
- if a contactor feedback signal is connected, the system waits until the feedback signal at BI:p1235 goes to "0" (open) until a transition is made into state 1. If this does not occur within the monitoring time (p1236), then a transition is made into state 6.

Re state "active - feedback signal "open" missing" (r1238 = 6):

- this error state can be exited by de-selecting the external armature short-circuit (p1231 = 0).

r1239**CO/BO: Armature short-circuit status word / ASC ZSW**

SERVO, VECTOR

Can be changed: -**Access level:** 1**Data type:** Unsigned32**Dynamic index:** -**Function diagram:** -**P-Group:** Functions**Units group:** -**Unit selection:** -**Min****Max****Factory setting**

-

-

0000 bin

Description:

Displays the status word for armature short-circuit.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	External armature short-circuit	active	not active	-
01	External armature short-circuit, contactor feedback signal	Closed	Open	-
02	External armature short-circuit ready	Yes	No	-
03	External armature short-circuit with contactor feedback signal	Yes	No	-
04	Internal armature short-circuit	active	not active	-
05	Int. armature short-circuit, feedback signal from power unit	active	not active	-
06	Internal armature short-circuit ready	Yes	No	-

Dependency:

Refer to: p1230, p1231, p1235, p1236, p1237

Note:

External armature short-circuit, bits 0 ... 3:

Re bit 00:

Using this signal, the motor is short-circuited through an external contactor circuit. This means that this BO: p1239.0 must be interconnected e.g. to a digital output.

Re bit 01:

This signal indicates the state of the contactor to establish the armature short-circuit. To do this, BI: p1235 must be interconnected to a digital input.

Re bit 02:

The external armature short-circuit configuration is ready and is activated as soon as the activation criteria is fulfilled.

Re bit 03:

1: A feedback signal from an external contactor was parameterized in BI: p1235.

Internal voltage protection, bits 4 ... 6:

Re bit 04:

The Control Unit issues the command to the Motor Module to short-circuit the motor through the power semiconductors.

Re bit 05:

The Motor Module signals that the motor is short-circuited in the Motor Module through the power semiconductors.

Re bit 06:


The internal voltage protection short-circuit is ready and is activated as soon as the activation criteria is fulfilled.

Activation criteria (one of the following criteria is fulfilled):

- the signal at BI: p1230 (armature short-circuit activation) is 0.
- the drive is not in the state "S4: Operation" or in S5x (refer to function chart 2610).
- the internal pulse enable is missing (r0046.19 = 0).

p1240		Vdc controller or Vdc monitoring configuration / Vdc_ctrl config		
SERVO	Can be changed: U, T			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: 6220
	P-Group: Functions	Units group: -		Unit selection: -
	Min	Max		Factory setting
	0	6		0
Description:	Sets the configuration of the controller or monitoring for the DC link voltage (Vdc).			
Values:	0: Inhib Vdc ctrl 1: Enables Vdc_max controller 2: Enables Vdc_min controller (kinetic buffering) 3: Enables Vdc_min controller and Vdc_max controller 4: Activates Vdc_max monitoring 5: Activates Vdc_min monitoring 6: Activates Vdc_min monitoring and Vdc_max monitoring			
Dependency:	Refer to: p1244, p1248, p1250			
Note:	p1240 = 1, 3: When the upper DC link voltage threshold is reached (p1244), then the following applies: - the Vdc_max controller limits the regenerative energy in order that the DC link voltage is kept below the maximum DC link voltage when braking. - when other drives regenerate into the DC link, then the Vdc_max controller causes the motor to accelerate. p1240 = 2, 3: When the lower DC link voltage threshold is reached (p1248), the following applies: - the Vdc_min controller limits the energy taken from the DC link in order to keep the DC link voltage above the minimum DC link voltage when accelerating. - the motor is braked in order to use its kinetic energy to buffer the DC link. p1240 = 4, 5, 6: When the threshold in p1244 or p1248 is reached, the DC link voltage monitoring initiates a fault with a response and therefore reduces additional negative effects on the DC link voltage.			
p1240[0...n]		Vdc controller configuration / Vdc_ctrl config		
VECTOR (n/M)	Can be changed: U, T			Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180		Function diagram: -
	P-Group: Functions	Units group: -		Unit selection: -
	Min	Max		Factory setting
	0	3		1
Description:	Sets the controller configuration of the DC link voltage (Vdc controller) in the closed-loop control mode.			
Values:	0: Inhib Vdc ctrl 1: Enables Vdc_max controller 2: Enables Vdc_min controller (kinetic buffering) 3: Enables Vdc_min controller and Vdc_max controller			
Recommendation:	If fault F07403 is output, then proceed as follows: - increase the dynamic factor (p1247). - if this fault is still output: Increase the switch-in level (p1245).			
Dependency:	Refer to: p1245 Refer to: F07403			
Notice:	An excessively high value in p1245 can possibly negatively influence the normal operation of the drive.			
Note:	p1240 = 1, 3: When the DC link voltage limit, specified for the Motor Module is reached, the following applies: - the Vdc_max controller limits the regenerative energy in order that the DC link voltage is kept below the maximum DC link voltage when braking. - the ramp-down times are automatically increased. p1240 = 2, 3: When the switch-in threshold of the Vdc_min controller is reached (p1245), the following applies: - the Vdc_min controller limits the energy taken from the DC link in order to keep the DC link voltage above the minimum DC link voltage when accelerating. - the motor is braked in order to use its kinetic energy to buffer the DC link.			

r1242	Vdc_min controller switch-in level / Vdc_max on_level		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 6220
	P-Group: Functions		Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	<p>Displays the switch-in level for the Vdc_max controller.</p> <p>If p1254 = 0 (automatic sensing of the switch-in level = off), then the following applies: AC/AC devices: $r1242 = 1.15 * \sqrt{2} * V_{line\ supply} = 1.15 * \sqrt{2} * p0210$ (supply voltage) DC/AC devices: $r1242 = 1.15 * V_{dc} = 1.15 * p0210$ (supply voltage)</p> <p>If p1254 = 1 (automatic sensing of the switch-in level = on), then the following applies: $r1242 = V_{dc_max} - 50.0\ V$ (Vdc_max: Overvoltage threshold of the power unit)</p>		
p1243[0...n]	Vdc_max controller dynamic factor / Vdc_max dyn_factor		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 6220
	P-Group: Functions		Unit selection: -
	Min 1 [%]	Max 10000 [%]	Factory setting 100 [%]
Description:	<p>Sets the dynamic factor for the DC link voltage controller (Vdc_max controller).</p> <p>100 % means that p1250, p1251 and p1252 (gain, integral time and rate time) are used corresponding to their basic settings and based on a theoretical controller optimization.</p> <p>If subsequent optimization is required, then this can be realized using the dynamic factor. In this case p1250, p1251, p1252 are weighted with the dynamic factor p1243.</p> <p>If several modules are connected to the DC link, then the dynamic factor must be increased corresponding to the ratio of the additional capacitances to the capacitance of the module involved.</p>		
Note:	<p>The pre-setting of the dynamic factor is based on the power units connected at DRIVE-CLiQ. It is assumed that the power unit, connected via DRIVE-CLiQ is also electrically connected to the DC link. If this is not the case, then the dynamic factor must be optimized manually.</p>		
p1244	DC link voltage threshold, upper / Vdc upper thresh		
SERVO	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Functions		Unit selection: -
	Min 400 [V]	Max 800 [V]	Factory setting 750 [V]
Description:	<p>Sets the upper threshold for the DC link voltage.</p> <p>For p1240 = 1, 3, this threshold is used as limit setpoint for the Vdc_max controller.</p> <p>For p1240 = 4, 6, for DC link voltages above this threshold, an appropriate fault is output.</p>		
Dependency:	Refer to: p1240, p1248, p1250		

p1245[0...n]	Vdc_min controller switch-in level (kinetic buffering) / Vdc_min on_level		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 65 [%]	Max 115 [%]	Factory setting 76 [%]
Description:	Sets the switch-in level for the Vdc-min controller (kinetic buffering). The value is obtained as follows: AC/AC devices: $p1245[V] = p1245[\%] * \sqrt{2} * p0210$ DC/AC devices: $p1245[V] = p1245[\%] * p0210$ Notice: For SINAMICS GM/SM, the following applies: Minimum value = 0.75 Maximum value = 0.90		
Dependency:	Refer to: p0210		
Warning:	An excessively large value may adversely influence normal drive operation.		
			
r1246	Vdc_min controller switch-in level (kinetic buffering) / Vdc_min on_level		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6220
	P-Group: Functions	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the switch-in level for the Vdc_min controller (kinetic buffering).		
p1247[0...n]	Vdc_min controller dynamic factor (kinetic buffering) / Vdc_min dyn_factor		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6220
	P-Group: Functions	Units group: -	Unit selection: -
	Min 1 [%]	Max 10000 [%]	Factory setting 100 [%]
Description:	Sets the dynamic factor for the Vdc-min controller (kinetic buffering). 100 % means that p1250, p1251 and p1252 (gain, integral time and rate time) are used corresponding to their basic settings and based on a theoretical controller optimization. If subsequent optimization is required, then this can be realized using the dynamic factor. In this case p1250, p1251, p1252 are weighted with the dynamic factor p1247. If several modules are connected to the DC link, then the dynamic factor must be increased corresponding to the ratio of the additional capacitances to the capacitance of the module involved.		
Note:	The pre-setting of the dynamic factor is based on the power units connected at DRIVE-CLiQ. It is assumed that the power unit, connected via DRIVE-CLiQ is also electrically connected to the DC link. If this is not the case, then the dynamic factor must be optimized manually.		

p1248	DC link voltage threshold, lower / Vdc lower thresh		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 100 [V]	Max 700 [V]	Factory setting 450 [V]
Description:	Sets the lower threshold for the DC link voltage. For p1240 = 2, 3, this threshold is used as limit setpoint for the Vdc_min controller. For p1240 = 5, 6, for DC link voltages below this threshold, an appropriate fault is output.		
Dependency:	Refer to: p1240, p1244, p1250		
p1250	Vdc controller proportional gain / Vdc_ctrl Kp		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6220
	P-Group: Functions	Units group: 19_1	Unit selection: p0505
	Min 0.00 [A/V]	Max 10.00 [A/V]	Factory setting 1.00 [A/V]
Description:	Sets the proportional gain for the Vdc controller (DC link voltage controller).		
Dependency:	Refer to: p1240, p1244, p1248		
p1250[0...n]	Vdc controller proportional gain / Vdc_ctrl Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.00	Max 100.00	Factory setting 1.00
Description:	Sets the proportional gain for the Vdc controller (DC link voltage controller).		
Dependency:	The effective proportional gain is obtained taking into account p1243 (Vdc_max controller dynamic factor).		
Note:	The gain factor is proportional to the capacitance of the DC link. The parameter is preset to a value that is optimally adapted to the capacitance of the individual Motor Module. The capacitances of the other power units, which are connected to the DC link, can be taken into account using the dynamic factor (p1247 or p1243).		
p1251[0...n]	Vdc controller integral time / Vdc_ctrl Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6220
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0 [ms]	Max 10000 [ms]	Factory setting 0 [ms]
Description:	Sets the integral time for the Vdc controller (DC link voltage controller).		
Dependency:	The effective integral time is obtained taking into account p1243 (Vdc_max controller dynamic factor).		
Note:	An integral time is normally not required for single axis drives. For multi-axis drives on the other hand, it may be possible to compensate for interference from other axes using the integral time (integral component) . An integral time of 0 (default) de-activates the controller.		

p1252[0...n]	Vdc controller rate time / Vdc_ctrl t_rate		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6220
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 0 [ms]
Description:	Sets the rate time constant for the Vdc controller (DC link voltage controller).		
Dependency:	The effective rate time is obtained taking into account p1243 (Vdc_max controller dynamic factor).		
Note:	During controlled operation this parameter has no effect.		
p1254	Vdc_max controller automatic ON level detection / Vdc_max SenseOnLev		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Activates/de-activates the automatic sensing of the switch-in level for the Vdc_max controller.		
Values:	0: Automatic detection disabled 1: Automatic detection enabled		
p1255[0...n]	Vdc_min controller time threshold / Vdc_min t_thresh		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 10000.000 [s]	Factory setting 0.000 [s]
Description:	Sets the time threshold for the Vdc_min controller (kinetic buffering). If this value is exceeded a fault is output; the required response can be parameterized . Prerequisite: p1256 = 1.		
Dependency:	Refer to: F07406		
p1256[0...n]	Vdc_min controller response (kinetic buffering) / Vdc_min response		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the response for the Vdc_min controller (kinetic buffering).		
Values:	0: Buffer Vdc until undervoltage, n<p1257 -> F07405 1: Buff. Vdc until undervolt., n<p1257 -> F07405, t>p1255 -> F07406		
Dependency:	Refer to: F07405, F07406		
p1257[0...n]	Vdc_min controller speed threshold / Vdc_min n_thresh		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 50.0 [1/min]
Description:	Sets the speed threshold for the Vdc-min controller (kinetic buffering). If this value is exceeded a fault is output; the required response can be parameterized .		

r1258	CO: Vdc controller output / Vdc_ctrl output			
VECTOR (n/M)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: 6220
	P-Group: Functions	Units group: 6_2		Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]		Factory setting - [Aeff]
Description:	Displays the actual output of the Vdc controller (DC link voltage controller)			
Note:	The regenerative power limit p1531 is used for closed-loop vector control to pre-control the Vdc_max controller. The lower the power limit is set, the lower the correction signals of the controller when the voltage limit is reached.			
p1260	Bypass configuration / Bypass config			
VECTOR (Tech_ctrl)	Can be changed: U, T			Access level: 2
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min 0	Max 3		Factory setting 0
Description:	Selecting the bypass functionality.			
Values:	0: Bypass function de-activated 1: Bypass with synchronization and overlap 2: Bypass with synchronization without overlap 3: Bypass without synchronization			
Dependency:	The bypass functionality is enabled together with the technology controller function module (refer to p0108 bit 16). When selecting p1260 = 2 (bypass with synchronization without overlap) and p1260 = 3 (bypass without synchronization), then the flying restart function must be activated (refer to p1200).			
Note:	If the bypass function is selected ((p1260 > 0), then when the power unit restarts after POWER OFF, the state of the bypass switch is evaluated. This means that after the ramp-up, it is possible to directly change into the standby mode. This is only possible for p1267 = 0 (bypass using the control signal) and if the control command after the system has been motor is still available (refer to p1266). This function has a high priority than the automatic restart function (refer to p1210). The bypass function can only be switched-out again (p1260 = 0) if the bypass is not active or the bypass function has a fault.			
r1261	CO/BO: Bypass control/status word / Bypass STW / ZSW			
VECTOR (Tech_ctrl)	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Control and feedback signals of the bypass switch.			
Bit field:	Bit	Signal name	1 signal	0 signal FP
	00	Command switch motor - drive	Close	Open -
	01	Command switch motor - line supply	Close	Open -
	02	Synchronization requested	Yes	No -
	03	Staging status	active	Not active -
	05	Feedback signal, switch motor - drive	Closed	Opened -
	06	Feedback signal, switch motor - line supply	Closed	Opened -
	07	Bypass command (from p1266)	Yes	No -
	08	Feedback signal synchronization completed (from p1268)	Yes	No -
	09	Staging requested (from p2369)	Yes	No -
Dependency:	Refer to: p2369			
Note:	Control bits 0 and 1 should be interconnected to the signal outputs via which the switches in the motor feeder cables should be controlled. These should be selected/dimensioned for switching under load.			

p1262[0...n]	Bypass deadtime / Bypass t_{dead}		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 20.000 [s]	Factory setting 1.000 [s]
Description:	Sets the deadtime for non-synchronized bypass.		
Note:	This parameter is used to define the changeover time of the contactors. It should not be shorter than the de-magnetization time of the motor (p0347).		
p1263	Debypass delay time / Debypass t_{del}		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 300.000 [s]	Factory setting 1.000 [s]
Description:	Delay time when changing back to drive converter operation with a non-synchronized bypass.		
p1264	Bypass delay time / Bypass t_{del}		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 300.000 [s]	Factory setting 1.000 [s]
Description:	Delay time when changing over to drive converter operation with a non-synchronized bypass.		
p1265	Bypass speed threshold / Bypass n_{thresh}		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: 3_1	Unit selection: p0505
	Min 0 [1/min]	Max 210000 [1/min]	Factory setting 1480 [1/min]
Description:	Sets the bypass speed threshold.		
Note:	When selecting p1260 = 3 and p1267.1, the bypass is automatically activated when this motor speed is reached.		
p1266	BI: Bypass, control command / Bypass BI command		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Input for the command to the bypass.		

p1267	Bypass changeover source configuration / Chngov_src config		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Sets the cause that should initiate the bypass.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Bypass using control signal (from 1266)	Yes No -
	01	Bypass when reaching the speed threshold	Yes No -
Note:	The parameter only has an effect for a non-synchronized bypass.		
	p1267 = 0: The bypass is initiated by setting a binary signal. When the command is reset, after the debypass delay time has expired, operation at the Motor Module is re-selected.		
	p1267 = 1: When the speed threshold entered in p1265 is reached, the bypass is switched-in. The system only switches back when the speed setpoint again falls below the threshold value.		
p1268	BI: Bypass, feedback synchronization completed / FdbkSig sync compl		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	3819.2
Description:	Input for the feedback signal that synchronization was successfully completed.		
Dependency:	Refer to: r3819		
p1269[0...1]	BI: Bypass switch feedback signal / Bypass FS		
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the feedback signal of the bypass switch.		
Index:	[0] = Switch motor - drive [1] = Switch motor - line supply		
p1272	Simulation mode / Simulation mode		
VECTOR	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	In the simulation mode, the closed-loop control or U/f control can be operated without motor. The simulation mode is used to test the power unit. Even though the DC link voltage is missing, the pulses are enabled when powering-up. The DC link pre-charging is bypassed and the undervoltage detection is disabled. Closed-loop speed control with an encoder is possible if the torque setpoint (r0079) is used in order to operate a second drive in the closed-loop torque controlled mode.		
Values:	0: Off 1: On		

- Dependency:** The following functions are de-activated in the simulation mode:
- motor data identification routine
 - motor data identification routine, rotating without encoder
 - pole position identification routine
- For U/f control and sensorless vector control, flying restart is not carried-out (refer to p1200).
Refer to: r0192, p1900, p1910, p1960, p1990
Refer to: A07825, F07826
- Note:** Simulation operation is only possible for DC link voltages below 40 V. In order that the closed-loop control can be calculated, the displayed DC link voltage (r0026, r0070) is set to the rated DC link voltage (refer to p0210). Closed-loop current control and motor model are switched-out (disabled) - the same is true for the speed controller for sensorless closed-loop speed control.
When fault messages occur, the parameter is not automatically reset. This function is not implemented for SINAMICS GM.

p1274[0...1] Bypass switch monitoring time / Switch t_monit

- VECTOR (Tech_ctrl) **Can be changed:** U, T **Access level:** 2
- Data type:** Floating Point **Dynamic index:** - **Function diagram:** -
- P-Group:** - **Units group:** - **Unit selection:** -
- Min** **Max** **Factory setting**
- 0 [ms] 5000 [ms] 1000 [ms]
- Description:** Sets the bypass switch monitoring time.
- Index:** [0] = Switch motor - drive
[1] = Switch motor - line supply
- Note:** The monitoring is de-activated with p1274 = 0 ms.

p1275 Motor holding brake control word / Brake STW

- SERVO (Extended brk), VECTOR (Extended brk) **Can be changed:** U, T **Access level:** 2
- Data type:** Unsigned32 **Dynamic index:** - **Function diagram:** -
- P-Group:** Functions **Units group:** - **Unit selection:** -
- Min** **Max** **Factory setting**
- - 0000 bin
- Description:** Sets the control word for the motor holding brake.
- Bit field:**
- | Bit | Signal name | 1 signal | 0 signal | FP |
|-----|-----------------------|----------|----------|------|
| 00 | Inverting BI: 1219[0] | Yes | No | 2707 |
| 01 | Inverting BI: 1219[1] | Yes | No | 2707 |
| 02 | Inverting BI: 1224[0] | Yes | No | 2704 |
| 03 | Inverting BI: 1224[1] | Yes | No | 2704 |
| 05 | Brake with feedback | Yes | No | 2711 |

p1276 Motor holding brake, standstill detection, bypass / Brk standst bypass

- SERVO (Extended brk), VECTOR (Extended brk) **Can be changed:** U, T **Access level:** 2
- Data type:** Floating Point **Dynamic index:** - **Function diagram:** 2704
- P-Group:** Functions **Units group:** - **Unit selection:** -
- Min** **Max** **Factory setting**
- 0.000 [s] 300.000 [s] 300.000 [s]
- Description:** Sets the delay time for closing the brake at standstill.
After this time has expired, if the "close brake at standstill" or OFF1/OFF3 is present, the brake is closed and the pulses are cancelled.
For p1276 = 300.000 s, the timer is de-activated - this means that the timer output is always zero.

p1277	Motor holding brake, braking threshold delay exceeded / Del thresh exceed.		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 2707
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 300.000 [s]	Factory setting 0.000 [s]
Description:	Sets the delay time for the signal "braking threshold exceeded" (BO: r1229.6).		
Dependency:	Refer to: p1220, p1221, r1229		
p1278	Motor holding brake type / Brake type		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Integer16		Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the motor holding brake type.		
Values:	0: Motor holding brake with feedback signals 1: Motor holding brake without feedback signals		
Note:	If the configuration of the motor holding brake (p1215) is set to "no holding brake present" when booting, then an automatic identification of the motor holding brake will be carried-out. If a motor holding brake is identified without feedback signals (e.g. Relay Brake Module), then the parameter is set to "motor holding braking without feedback signals". It is not permissible to parameterize "motor holding brake without feedback signals" and also enable "safe brake control" (p1278 = 1, p9602 = 1, p9802 = 1).		
p1279[0...3]	BI: Motor holding brake, OR/AND logic operation / Brake OR AND		
SERVO (Extended brk), VECTOR (Extended brk)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned32		Function diagram: 2707
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the OR/AND logic operation.		
Dependency:	Refer to: r1229		
Note:	[0]: OR logic operation, input 1 --> the result is displayed in r1229.10. [1]: OR logic operation, input 2 --> the result is displayed in r1229.10. [2]: AND logic operation, input 1 --> the result is displayed in r1229.11. [3]: AND logic operation, input 2 --> the result is displayed in r1229.11.		
p1280[0...n]	Vdc controller configuration (U/f) / Vdc_ctrl config		
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16		Function diagram: 1690, 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 1
Description:	Sets the configuration of the controller for the DC link voltage (Vdc controller) in the U/f operating mode.		
Values:	0: Inhib Vdc ctrl 1: Enables Vdc_max controller 2: Enables Vdc_min controller (kinetic buffering) 3: Enables Vdc_min controller and Vdc_max controller		

r1282	Vdc_max controller switch-in level (U/f) / Vdc_max on_level		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	<p>Displays the switch-in level for the Vdc_max controller.</p> <p>If p1294 = 0 (automatic sensing of the switch-in level = off), then the following applies: AC/AC devices: $r1282 = 1.15 * \sqrt{2} * V_{mains} = 1.15 * \sqrt{2} * p0210$ (supply voltage) DC/AC devices: $r1282 = 1.15 * V_{dc} = 1.15 * p0210$ (supply voltage)</p> <p>If p1294 = 1 (automatic sensing of the switch-in level = on), then the following applies: $r1282 = V_{dc_max} - 50.0 \text{ V}$ (V_{dc_max}: Overvoltage threshold of the power unit)</p>		
p1283[0...n]	Vdc_max controller dynamic factor (U/f) / Vdc_max dyn_factor		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 1 [%]	Max 10000 [%]	Factory setting 100 [%]
Description:	<p>Sets the dynamic factor for the DC link voltage controller (Vdc_max controller).</p> <p>100 % means that p1290, p1291 and p1292 (gain, integral time and rate time) are used corresponding to their basic settings and based on a theoretical controller optimization.</p> <p>If subsequent optimization is required, then this can be realized using the dynamic factor. In this case p1290, p1291, p1292 are weighted with the dynamic factor p1283.</p> <p>If several modules are connected to the DC link, then the dynamic factor must be increased corresponding to the ratio of the additional capacitances to the capacitance of the module involved.</p>		
Note:	<p>The pre-setting of the dynamic factor is based on the power units connected at DRIVE-CLiQ. It is assumed that the power unit, connected via DRIVE-CLiQ is also electrically connected to the DC link. If this is not the case, then the dynamic factor must be optimized manually.</p>		
p1285[0...n]	Vdc_min controller switch-in level (kinetic buffering) (U/f) / Vdc_min on_level		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 65 [%]	Max 115 [%]	Factory setting 76 [%]
Description:	<p>Sets the switch-in level for the Vdc-min controller (kinetic buffering).</p> <p>The value is obtained as follows: AC/AC devices: $p1285[V] = p1245[\%] * \sqrt{2} * p0210$ DC/AC devices: $p1285[V] = p1245[\%] * p0210$</p>		
r1286	Vdc_min controller switch-in level (kinetic buffering) (U/f) / Vdc_min on_level		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	<p>Displays the switch-in level for the Vdc_min controller (kinetic buffering).</p>		

p1287[0...n]	Vdc_min controller dynamic factor (kinetic buffering) (U/f) / Vdc_min dyn_factor		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 1 [%]	Max 10000 [%]	Factory setting 100 [%]
Description:	Sets the dynamic factor for the Vdc-min controller (kinetic buffering). 100 % means that p1290, p1291 and p1292 (gain, integral time and rate time) are used corresponding to their basic settings and based on a theoretical controller optimization. If subsequent optimization is required, then this can be realized using the dynamic factor. In this case p1290, p1291, p1292 are weighted with the dynamic factor p1287. If several modules are connected to the DC link, then the dynamic factor must be increased corresponding to the ratio of the additional capacitances to the capacitance of the module involved.		
Note:	The pre-setting of the dynamic factor is based on the power units connected at DRIVE-CLiQ. It is assumed that the power unit, connected via DRIVE-CLiQ is also electrically connected to the DC link. If this is not the case, then the dynamic factor must be optimized manually.		
p1290[0...n]	Vdc controller proportional gain (U/f) / Vdc_ctrl Kp		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.00	Max 100.00	Factory setting 1.00
Description:	Sets the proportional gain for the Vdc controller (DC link voltage controller).		
Note:	The gain factor is proportional to the capacitance of the DC link. The parameter is preset to a value that is optimally adapted to the capacitance of the individual Motor Module. The capacitances of the other power units, which are connected to the DC link, can be taken into account using the dynamic factor (p1287 or p1283).		
p1291[0...n]	Vdc controller integral time (U/f) / Vdc_ctrl Tn		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0 [ms]	Max 10000 [ms]	Factory setting 40 [ms]
Description:	Sets the integral time for the Vdc controller (DC link voltage controller).		
p1292[0...n]	Vdc controller rate time (U/f) / Vdc_ctrl t_rate		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 10 [ms]
Description:	Sets the rate time constant for the Vdc controller (DC link voltage controller).		
p1293[0...n]	Vdc controller output limit (U/f) / Vdc_ctrl outp_lim		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6320
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.0 [Hz]	Max 600.0 [Hz]	Factory setting 10.0 [Hz]
Description:	Sets the output limit for the Vdc controller (DC link voltage controller).		

p1294	Vdc_max controller automatic detection ON signal level (U/f) / Vdc_max SenseOnLev		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Activates/de-activates the automatic sensing of the switch-in level for the Vdc_max controller.		
Values:	0: Automatic detection disabled 1: Automatic detection enabled		
p1295[0...n]	Vdc_min controller time threshold (U/f) / Vdc_min t_thresh		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 10000.000 [s]	Factory setting 0.000 [s]
Description:	Sets the time threshold for the Vdc_min controller (kinetic buffering). If this value is exceeded a fault is output; the required response can be parameterized . Prerequisite: p1296 = 1.		
p1296[0...n]	Vdc_min controller response (kinetic buffering) (U/f / Vdc_min response		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the response for the Vdc_min controller (kinetic buffering).		
Values:	0: Buffer Vdc until undervoltage, n<p1257 -> F07405 1: Buff. Vdc until undervolt., n<p1257 -> F07405, t>p1255 -> F07406		
p1297[0...n]	Vdc_min controller speed threshold (U/f) / Vdc_min n_thresh		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 50.0 [1/min]
Description:	Sets the speed threshold for the Vdc-min controller (kinetic buffering). If this value is exceeded a fault is output; the required response can be parameterized .		
r1298	CO: Vdc controller output (U/f) / Vdc_ctrl output		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6320
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the actual output of the Vdc controller (DC link voltage controller)		

p1300[0...n]		Open-loop/closed-loop control operating mode / Control mode		
SERVO	Can be changed: C2(1), T			Access level: 2
	Data type: Integer16	Dynamic index: DDS, p0180		Function diagram: 1590, 1690, 5060, 6300
	P-Group: V/f open-loop control	Units group: -		Unit selection: -
	Min 20	Max 23		Factory setting 21
Description:	Sets the open and closed loop control mode of a drive.			
Values:	20: Speed control (sensorless) 21: Speed control (with encoder) 23: Torque control (with encoder)			
Dependency:	Closed-loop speed or torque control (with encoder) cannot be selected if the encoder type is not entered (p0400). Refer to: p0108, r0108, p0300, p0311, p0400, p1501			
Note:	The closed-loop torque control can only be changed over in operation (p1300 = 20 or 21) by selecting the closed-loop speed control (p1501). At the changeover, the setting of p1300 does not change. In this case, the actual state is displayed in r1407, bit 2 and bit 3. For sensorless operation (p1404 = 0 or p1300 = 20), the following applies: - The condition must be fulfilled: $p1800 \geq n / (2 * p0115[0])$, $n = 1, 2, \dots$ - For motors with a small power rating (< 300 W) we recommend to set $n \geq 2$.			
p1300[0...n]		Open-loop/closed-loop control operating mode / Control mode		
VECTOR	Can be changed: C2(1), T			Access level: 2
	Data type: Integer16	Dynamic index: DDS, p0180		Function diagram: 1590, 1690, 5060, 6300
	P-Group: V/f open-loop control	Units group: -		Unit selection: -
	Min 0	Max 23		Factory setting 20
Description:	Sets the open and closed loop control mode of a drive.			
Values:	0: U/f control with linear characteristic 1: U/f control with linear characteristic and FCC 2: U/f control with parabolic characteristic 3: U/f control with parameterizable characteristic 5: U/f control for drives requiring a precise freq. (e.g. textiles) 6: U/f control for drives requiring a precise frequency with FCC 18: I/f control with fixed current 19: U/f control with independent voltage setpoint 20: Speed control (sensorless) 21: Speed control (with encoder) 22: Torque control (sensorless) 23: Torque control (with encoder)			
Dependency:	Closed-loop speed or torque control (with encoder) cannot be selected if the encoder type is not entered (p0400). Closed-loop speed or torque control can be selected if the closed-loop speed/torque control was selected as operating mode (p0108 bit 2). Only operation with U/f characteristic is possible if the rated motor speed is not entered (p0311). A reluctance motor can only be operated in a U/f control mode (p1300 < 20). Refer to: p0108, r0108, p0300, p0311, p0400, p1501			
Note:	The closed-loop torque control can only be changed over in operation (p1300 = 20 or 21) by selecting the closed-loop speed control (p1501). At the changeover, the setting of p1300 does not change. In this case, the actual state is displayed in r1407, bit 2 and bit 3. For the open-loop control modes p1300 = 5 and 6 (textile sector), the slip compensation p1335 and the resonance damping p1338 are internally switched-out (disabled) in order to be able to precisely set the output frequency. Separately-excited synchronous motors can only be operated in the modes p1300 = 21 and 23 - or for diagnostic purposes in the modes p1300 = 0, 3 and 18. For I/f control (p1300 = 18), the current amplitude can be set using p1609. Both for U/f as well as for I/f control only a small load may be applied to the separately-excited synchronous motor because the excitation current is not calculated as a function of the load. During operation (the pulses enabled) the open-loop/closed-loop control mode cannot be changed by changing-over drive data sets.			

p1310[0...n]		Voltage boost permanent / U_boost perm	
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point		Function diagram: 1690, 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 250.0 [%]	Factory setting 50.0 [%]
Description:	<p>Defines the voltage boost as a [%] referred to the rated motor current (p0305). The magnitude of the permanent voltage boost is reduced with increasing frequency so that at the rated motor frequency, the rated motor voltage is present. The magnitude of the boost in Volt at a frequency of zero is defined as follows: Voltage boost [V] = p0305 (rated motor current [A]) x p0350 (stator/primary section resistance [ohm]) x p1310 (permanent voltage boost [%]) / 100 % At low output frequencies, there is only a low output voltage in order to maintain the motor flux. However, the output voltage can be too low in order to achieve the following:</p> <ul style="list-style-type: none"> - magnetize the induction motor. - hold the load. - compensate for losses in the system. <p>This is the reason that the output voltage can be increased using p1310. The voltage boost can be used for both linear as well as square-law U/f characteristics and is calculated as follows: Voltage boost = p0305 (rated motor current x p0350 (stator/primary section resistance) x p1310 (permanent voltage boost)</p>		
Dependency:	<p>Setting in p0640 (motor overload factor [%]) limits the boost. For closed-loop vector control, the permanent voltage boost (p1310) has no effect as the drive converter automatically sets the optimum operating conditions. Refer to: p1300, p1311, r1315</p>		
Notice:	The voltage boost increases the motor temperature (particularly at zero speed).		
Note:	<p>The voltage boost is only effective for U/f control (p1300). The boost values are combined with one another if the permanent voltage boost (p1310) is used in conjunction with other boost parameters (acceleration boost (p1311)). However, these parameters are assigned the following priorities: p1310 > p1311</p>		
p1311[0...n]		Voltage boost at acceleration / U_boost accelerate	
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point		Function diagram: 1690, 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 250.0 [%]	Factory setting 0.0 [%]
Description:	<p>p1311 only results in a voltage boost when accelerating and generates a supplementary torque/force to accelerate the load. The voltage boost becomes effective for a positive setpoint increase and disappears as soon as the setpoint has been reached. The magnitude of the boost in Volt at a frequency of zero is defined as follows: Voltage boost [V] = p0305 (rated motor current [A]) x p0350 (stator/primary section resistance [ohm]) x p1310 (permanent voltage boost [%]) / 100 %</p>		
Dependency:	<p>Setting in p0640 (motor overload factor [%]) limits the boost. Refer to: p1300, p1310, r1315</p>		
Notice:	The voltage boost results in a higher motor temperature increase.		
Note:	<p>The voltage boost when accelerating can improve the response to small, positive setpoint changes. Assigning priorities for the voltage boosts: refer to p1310</p>		

r1315	Voltage boost total / U_boost total		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the total resulting voltage boost in volt (p1310 + p1311).		
p1317[0...n]	U/f control diagnostics activation / Uf diagn act		
SERVO	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 5718
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Activates the U/f control with linear characteristic for diagnostic purposes. 0: Operation as set in p1300. 1: Activates the U/f control.		
Values:	0: Off (p1300 eff) 1: On		
Dependency:	Refer to: p1318, p1319, p1326, p1327		
p1318[0...n]	U/f control ramp-up/ramp-down time / Uf t_rmp-up_rmp-dn		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 999999.000 [s]	Factory setting 10.000 [s]
Description:	Sets the ramp-up and ramp-down time for the U/f control. The ramp-function generator requires this time to reach the maximum speed (p1082) from zero.		
Dependency:	Refer to: p1317, p1319, p1326, p1327		
Note:	This ramp is used for stall protection and operates independently of any ramp-function generator that might have been configured.		
p1319[0...n]	U/f control voltage at zero frequency / Uf U at f=0 Hz		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [Veff]	Max 25.0 [Veff]	Factory setting 0.0 [Veff]
Description:	The linear characteristic for the U/f control is defined by 0 Hz / p1319 and p1326 / p1327. This parameter specifies the voltage for a frequency of 0 Hz.		
Dependency:	Activates the U/f control using p1317. Refer to: p1317, p1326, p1327		
Note:	Linear interpolation is carried-out between the points 0 Hz / p1319 and p1326 / p1327.		

p1320[0...n]	U/f control programmable characteristic frequency 1 / Uf char f1		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 3000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the first point along the characteristic.		
Dependency:	Selects the freely programmable characteristic using p1300 = 3. The following applies to the frequency values: p1320 <= p1322 <= p1324 <= p1326. Otherwise, a standard characteristic is used that contains the rated motor operating point. Refer to: p1300, p1310, p1311, p1321, p1322, p1323, p1324, p1325, p1326, p1327		
Note:	Linear interpolation is carried-out between the points 0 Hz / p1310, p1320 / p1321 ... p1326 / p1327. The voltage boost when accelerating (p1311) is also applied to the freely programmable V/Hz characteristic.		
p1321[0...n]	U/f control programmable characteristic voltage 1 / Uf char U1		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [Veff]	Max 10000.0 [Veff]	Factory setting 0.0 [Veff]
Description:	The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the first point along the characteristic.		
Dependency:	Selects the freely programmable characteristic using p1300 = 3. Refer to: p1310, p1311, p1320, p1322, p1323, p1324, p1325, p1326, p1327		
Note:	Linear interpolation is carried-out between the points 0 Hz / p1310, p1320 / p1321 ... p1326 / p1327. The voltage boost when accelerating (p1311) is also applied to the freely programmable V/Hz characteristic.		
p1322[0...n]	U/f control programmable characteristic frequency 2 / Uf char f2		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 3000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the second point along the characteristic.		
Dependency:	The following applies to the frequency values: p1320 <= p1322 <= p1324 <= p1326. Otherwise, a standard characteristic is used that contains the rated motor operating point. Refer to: p1310, p1311, p1320, p1321, p1323, p1324, p1325, p1326, p1327		
p1323[0...n]	U/f control programmable characteristic voltage 2 / Uf char U2		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [Veff]	Max 10000.0 [Veff]	Factory setting 0.0 [Veff]
Description:	The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the second point along the characteristic.		
Dependency:	Refer to: p1310, p1311, p1320, p1321, p1322, p1324, p1325, p1326, p1327		

p1324[0...n]	U/f control programmable characteristic frequency 3 / Uf char f3		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 3000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the third point along the characteristic.		
Dependency:	The following applies to the frequency values: p1320 <= p1322 <= p1324 <= p1326. Otherwise, a standard characteristic is used that contains the rated motor operating point. Refer to: p1310, p1311, p1320, p1321, p1322, p1323, p1325, p1326, p1327		
p1325[0...n]	U/f control programmable characteristic voltage 3 / Uf char U3		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [Veff]	Max 10000.0 [Veff]	Factory setting 0.0 [Veff]
Description:	The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the third point along the characteristic.		
Dependency:	Refer to: p1310, p1311, p1320, p1321, p1322, p1323, p1324, p1326, p1327		
p1326[0...n]	U/f control programmable characteristic frequency 4 / Uf char f4		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5300, 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 10000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	In the servo control mode the following applies: The linear characteristic for the U/f control is defined by 0 Hz / p1319 and p1326 / p1327. For closed-loop vector control, the following applies: The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the fourth point along the characteristic.		
Dependency:	In the servo control mode the following applies: Activates the U/f control using p1317. For closed-loop vector control, the following applies: Selects the freely programmable characteristic using p1300 = 3. The following applies to the frequency values: p1320 <= p1322 <= p1324 <= p1326. Otherwise, a standard characteristic is used that contains the rated motor operating point. Refer to: p1310, p1311, p1317, p1319, p1320, p1321, p1322, p1323, p1324, p1325, p1327		
Note:	In the servo control mode the following applies: Linear interpolation is carried-out between the points 0 Hz / p1319 and p1326 / p1327. For closed-loop vector control, the following applies: Linear interpolation is carried-out between the points 0 Hz / p1310, p1320 / p1321 ... p1326 / p1327. The voltage boost when accelerating (p1311) is also applied to the freely programmable V/Hz characteristic.		

p1327[0...n]	U/f control programmable characteristic voltage 4 / Uf char U4		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5300, 6300
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [Veff]	Max 10000.0 [Veff]	Factory setting 0.0 [Veff]
Description:	<p>In the servo control mode the following applies: The linear characteristic for the U/f control is defined by 0 Hz / p1319 and p1326 / p1327. For closed-loop vector control, the following applies: The programmable characteristic for the U/f control is defined using 4 points and 0 Hz/p1310. This parameter specifies the voltage of the fourth point along the characteristic.</p>		
Dependency:	<p>In the servo control mode the following applies: Activates the U/f control using p1317. For closed-loop vector control, the following applies: Selects the freely programmable characteristic using p1300 = 3. Refer to: p1310, p1311, p1317, p1319, p1320, p1321, p1322, p1323, p1324, p1325, p1326</p>		
Note:	<p>In the servo control mode the following applies: Linear interpolation is carried-out between the points 0 Hz / p1319 and p1326 / p1327. For closed-loop vector control, the following applies: Linear interpolation is carried-out between the points 0 Hz / p1310, p1320 / p1321 ... p1326 / p1327. The voltage boost when accelerating (p1311) is also applied to the freely programmable V/Hz characteristic.</p>		
p1330[0...n]	CI: V/Hz control independent voltage setpoint / Uf U_set independ.		
VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the voltage setpoint for U/f control with an independent voltage setpoint (p1300 = 19).		
Dependency:	<p>Selects the U/f control with independent voltage setpoint via p1300 = 19. Refer to: p1300</p>		
p1335[0...n]	Slip compensation, scaling / Slip comp scal		
VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1690, 6310
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 600.0 [%]	Factory setting 0.0 [%]
Description:	<p>Sets the setpoint for slip compensation in [%] referred to r0330 (motor rated slip). p1335 = 0.0 %: Slip compensation de-activated. p1335 = 100.0 %: The slip is completely compensated.</p>		
Dependency:	<p>Prerequisite for a precise slip compensation for p1335 = 100 % are the precise motor parameters (p0350 ... p0360). If the parameters are not precisely known, a precise compensation can be achieved by varying p1335.</p>		

Note: The purpose of slip compensation is to maintain a constant motor speed regardless of the applied load. The fact that the motor speed decreases with increasing load is a typical characteristic of induction motors. For synchronous motors, this effect does not occur and the parameter has no effect in this case. For the open-loop control modes p1300 = 5 and 6 (textile sector), the slip compensation is internally disabled in order to be able to precisely set the output frequency. If p1335 is changed while commissioning (p0009, p0010 > 0), then it is possible that the old value will no longer be able to be set. The reason for this is that the dynamic limits of p1335 have been changed by a parameter that was set when the drive was commissioned (e.g. p0300).

p1336[0...n] **Slip compensation limit value / Slip comp lim val**
 VECTOR **Can be changed:** U, T **Access level:** 2
Data type: Floating Point **Dynamic index:** DDS, p0180 **Function diagram:** 6310
P-Group: V/f open-loop control **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0.00 [%] 600.00 [%] 250.00 [%]

Description: Sets the limit value for slip compensation in [%] referred to r0330 (motor rated slip).

r1337 **Actual slip compensation / Slip comp act.val.**
 VECTOR **Can be changed:** - **Access level:** 3
Data type: Floating Point **Dynamic index:** - **Function diagram:** 6310
P-Group: V/f open-loop control **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - [%] - [%] - [%]

Description: Displays the actual compensated slip [%] referred to r0330 (rated motor slip).
Dependency: p1335 > 0 %: Slip compensation active.
 Refer to: p1335

p1338[0...n] **U/f mode resonance damping gain / Uf Res_damp gain**
 VECTOR **Can be changed:** U, T **Access level:** 3
Data type: Floating Point **Dynamic index:** DDS, p0180 **Function diagram:** 1690, 6310
P-Group: V/f open-loop control **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0.00 100.00 0.00

Description: Sets the controller gain for resonance damping for U/f control.
Dependency: Refer to: p1300, p1339, p1349
Note: The resonance damping function dampens active current oscillations that frequency occur under no-load conditions. The resonance damping is active in a range of approximately 5 ... 90 % of the rated motor frequency (p0310), but up to a maximum of 45 Hz. For the open-loop control modes p1300 = 5 and 6 (textile sectors), the resonance damping is internally disabled in order that the output frequency can be precisely set.

p1339[0...n] **U/f mode resonance damping filter time constant / Uf Res_damp T**
 VECTOR **Can be changed:** U, T **Access level:** 3
Data type: Floating Point **Dynamic index:** DDS, p0180 **Function diagram:** 6310
P-Group: V/f open-loop control **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 1.00 [ms] 1000.00 [ms] 20.00 [ms]

Description: Sets the filter time constant of the controller for resonance damping with U/f control.
Dependency: Refer to: p1300, p1338, p1349

p1340[0...n]	I_max frequency controller proportional gain / I_max_ctrl Kp		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 0.500	Factory setting 0.000
Description:	Proportional gain of the I_max voltage controller. The I_max controller reduces the drive converter/inverter output current if the maximum current (r0067) is exceeded. In the U/f operating modes (refer to p1300) for the I_max control, one controller is used that acts on the output frequency and one controller that acts on the output voltage. The frequency controller reduces the current by decreasing the converter output frequency. The frequency is reduced down to a minimum value (equaling twice rated slip). If the overcurrent condition cannot be successfully resolved using this measure, then the drive converter output voltage is reduced using the I_max voltage controller. Once the overcurrent condition has been resolved, the drive is accelerated along the ramp set in p1120 (ramp-up time).		
Dependency:	In the U/f modes (p1300) for textile applications and for external voltage setpoints, only the I_max voltage controller is used.		
Notice:	When de-activating the I_max controller, the following must be carefully observed: When the maximum current (r0067) is exceeded, the output current is no longer reduced, however, overcurrent alarm messages are generated. The drive is shut down if the overcurrent limit (r0209) is exceeded.		
Note:	The I_max limiting controller becomes ineffective if the ramp-function generator is de-activated with p1122 = 1. p1341 = 0: I_max frequency controller de-activated and I_max voltage controller activated over the complete speed range.		
p1341[0...n]	I_max frequency controller integral time / I_max_ctrl Tn		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 50.000 [s]	Factory setting 0.300 [s]
Description:	Sets the integral time for the I_max frequency controller.		
Dependency:	Refer to: p1340		
r1343	I_max controller frequency output / I_max_ctrl f_outp		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the effective frequency limit.		
Dependency:	Refer to: p1340		
r1344	I_max controller voltage output / I_max_ctrl U_outp		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the amount by which the converter output voltage is reduced.		
Dependency:	Refer to: p1340		

p1345[0...n]	I_max voltage controller proportional gain / I_max_U_ctrl Kp		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 100000.000	Factory setting 0.000
Description:	Sets the proportional gain for the I_max voltage controller.		
Dependency:	Refer to: p1340		
p1346[0...n]	I_max voltage controller integral time / I_max_U_ctrl Tn		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 50.000 [s]	Factory setting 0.030 [s]
Description:	Sets the integral time for the I_max voltage controller.		
Dependency:	Refer to: p1340		
Note:	p1346 = 0: I_max voltage controller de-activated.		
p1349[0...n]	U/f mode resonance damping maximum frequency / Uf res_damp F_max		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6310
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 3000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Sets the maximum output frequency above which the resonance damping for U/f control is de-activated.		
Dependency:	Refer to: p1338, p1339		
p1350[0...n]	Soft starting / Soft starting		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 1690
	P-Group: V/f open-loop control	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets whether the voltage is continuously increased during the magnetizing phase (p1350 = 1, On) or whether it jumps directly to the voltage boost (p1350 = 0, Off).		
Values:	0: Off 1: On		
Note:	The settings for this parameter have the following advantages and disadvantages: 0 = off (jump directly to voltage boost) Advantage: Flux is established quickly -> torque is quickly available Disadvantage: The motor can move while it is being magnetized 1 = on (voltage is continually established) Advantage: The motor is unlikely to rotate Disadvantage: The flux is established slower -> torque is available later		

p1356[0...n]	CI: U/f control, angular setpoint / Uf ang setpoint				
VECTOR	Can be changed: U, T		Access level: 3		
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -		
	P-Group: V/f open-loop control	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0		
Description:	Sets the signal source for the differential angular generation for U/f control.				
p1358[0...n]	Angular difference, symmetrizing, actual angle / Sym act angle				
VECTOR	Can be changed: U, T		Access level: 3		
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -		
	P-Group: V/f open-loop control	Units group: -	Unit selection: -		
	Min 0	Max 1	Factory setting 0		
Description:	Sets the deadtime for the symmetrizing of the actual angle value for the differential angular generation. The selected multiplier refers to the current controller clock cycle (deadtime= p1358 * p0115[0]).				
r1359	CO: Angular difference / Angular difference				
VECTOR	Can be changed: -		Access level: 3		
	Data type: Floating Point	Dynamic index: -	Function diagram: -		
	P-Group: V/f open-loop control	Units group: -	Unit selection: -		
	Min - [°]	Max - [°]	Factory setting - [°]		
Description:	Displays the output of the differential angular generation.				
Note:	The difference between the setpoint angle, read-in in p1356 and the actual value of the U/f control delayed with p1358 is displayed.				
p1400[0...n]	Speed control configuration / n_ctrl config				
SERVO	Can be changed: U, T		Access level: 2		
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 1590, 5490		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 0011 1010 1000 bin		
Description:	Sets the configuration for the closed-loop speed control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	03	Reference model speed setpoint, I component	On	Off	5030
	04	Torque limiting motoring/regenerating active	Yes	No	-
	05	Kp/Tn adaptation active	Yes	No	-
	07	Interpolation speed precontrol active	Yes	No	-
	08	Interpolation torque setpoint active	Yes	No	-
	09	Damping for sensorless open-loop controlled oper.	Yes	No	-
	10	Speed precontrol	For balancing	For setp_filter 2	-
	11	Sensorless oper. speed actual value starting value	Setpoint	0.0	-
	12	Sensorless operation changeover	Steady-state	When accelerating	-
	13	Motor/generator dependent on	Speed setpoint	Actual speed value	-
Note:	Re bit 07: The interpolator is only effective for clock-cycle synchronous PROFIBUS operation and when the master receives a sign of life (STW 2.12 ... STW 2.15). Further, for active Dynamic Servo Control (DSC) an additional deadtime of one speed controller clock cycle is obtained.				

p1400[0...n]		Velocity control, configuration / v_ctrl config			
SERVO (Lin)	Can be changed: U, T			Access level: 2	
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 1590, 5490	
	P-Group: Closed-loop control	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 0011 1010 1000 bin	
Description:	Sets the configuration for the closed-loop velocity control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	03	Reference model speed setpoint, I component	On	Off	5030
	04	Torque limiting motoring/regenerating active	Yes	No	-
	05	Kp/Tn adaptation active	Yes	No	-
	07	Interpolation speed precontrol active	Yes	No	-
	08	Interpolation torque setpoint active	Yes	No	-
	09	Damping for sensorless open-loop controlled oper.	Yes	No	-
	10	Speed precontrol	For balancing	For setp_filter 2	-
	11	Sensorless oper. speed actual value starting value	Setpoint	0.0	-
	12	Sensorless operation changeover	Steady-state	When accelerating	-
	13	Motor/generator dependent on	Speed setpoint	Actual speed value	-
Note:	Re bit 07: The interpolator is only effective for clock-cycle synchronous PROFIBUS operation and when the master receives a sign of life (STW 2.12 ... STW 2.15). Further, for active Dynamic Servo Control (DSC) an additional deadtime of one speed controller clock cycle is obtained.				

p1400[0...n]		Speed control configuration / n_ctrl config			
VECTOR (n/M)	Can be changed: U, T			Access level: 2	
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 6490	
	P-Group: Closed-loop control	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		1000 0000 0010 0001 bin	
Description:	Sets the configuration for the closed-loop speed control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Automatic Kp/Tn adaptation active	Yes	No	-
	01	Sensorless closed-loop vector ctrl freeze I comp	Yes	No	-
	02	Acceleration pre-control source	External (p1495)	Internal (n_set)	6031
	03	Reference model speed setpoint, I component	On	Off	6031
	05	Kp/Tn adaptation active	Yes	No	-
	06	Free Tn adaptation active	Yes	No	-
	14	Torque precontrol	Always active	For n_ctrl enab	-
	15	Sensorless vector control, speed precontrol	Yes	No	-
Note:	Re bit 01: When the bit is set, the I component of the speed controller is kept when changing into the open-loop controlled mode.				

p1401[0...n]	Flux control configuration / F_ctrl config			
VECTOR (n/M)	Can be changed: U, T		Access level: 3	
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 6491, 6722	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	1110 bin	
Description:	Sets the configuration for flux setpoint control			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Flux setpoint soft starting active	Yes	No
	01	Flux setpoint differentiation active	Yes	No
	02	Flux build-up control active	Yes	No
	03	Flux characteristic, load-dependent	Yes	no
Note:	The load-dependent calculation of the flux characteristic is only available for separately-excited synchronous motors.			
p1402[0...n]	Closed-loop current control and motor model configuration / I_ctrl config			
SERVO	Can be changed: T		Access level: 3	
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: -	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0000 bin	
Description:	Sets the configuration for the closed-loop control and the motor model.			
Bit field:	Bit	Signal name	1 signal	0 signal
	01	Park encoder for n_act > p1404	Yes	No
Note:	Re bit 01: When the bit is set, the encoder is parked as soon as the actual speed is greater than the changeover speed (p1404). The encoder state is displayed in r0487.14.			
p1402[0...n]	Closed-loop current control and motor model configuration / I_ctrl config			
VECTOR (n/M)	Can be changed: U, T		Access level: 3	
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: -	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	0001 bin	
Description:	Sets the configuration for the closed-loop control and the motor model.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Speed-following error correction active	Yes	No
Note:	Re bit 01: When the bit is set, the speed following error is compensated that is obtained as a result of the smoothing time constant in p1441.			
p1404[0...n]	Sensorless operation changeover speed / Sensorl op n_chgov			
SERVO	Can be changed: T		Access level: 3	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1590, 5060	
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505	
	Min	Max	Factory setting	
	0.0 [1/min]	210000.0 [1/min]	210000.0 [1/min]	
Description:	Sets the speed to change over between operation with and without encoder. Above this speed, the drive system is automatically operated in the sensorless mode.			

Note: The changeover speed applies when changing over between operation with and without encoder.
 Separate speed controllers should be set when operating with and without encoder.
 Operation with encoder: p1460 (Kp), p1462 (Tn), p1461, p1463, p1457, p1458 (parameters for speed controller adaptation)
 Operation without encoder: p1470 (Kp), p1472 (Tn)
 For sensorless operation (p1404 = 0 or p1300 = 20), the following applies:
 - The condition must be fulfilled: $p1800 \geq n / (2 * p0115[0])$, $n = 1, 2, \dots$
 - For motors with a small power rating (< 300 W) we recommend to set $n \geq 2$.

p1404[0...n]		Sensorless operation changeover velocity / Sensorl op v_chgov		
SERVO (Lin)	Can be changed: T		Access level: 3	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1590, 5060	
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505	
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 1000.0 [m/min]	
Description:	Sets the velocity to change over between operation with and without encoder. Above this velocity, the drive system is automatically operated in the sensorless mode.			
Note:	The changeover speed applies when changing over between operation with and without encoder. Separate speed controllers should be set when operating with and without encoder. Operation with encoder: p1460 (Kp), p1462 (Tn), p1461, p1463, p1457, p1458 (parameters for speed controller adaptation) Operation without encoder: p1470 (Kp), p1472 (Tn) For sensorless operation (p1404 = 0 or p1300 = 20), the following applies: - The condition must be fulfilled: $p1800 \geq n / (2 * p0115[0])$, $n = 1, 2, \dots$ - For motors with a small power rating (< 300 W) we recommend to set $n \geq 2$. For sensorless operation (p1404 = 0 or p1300 = 20), the following applies: - The condition must be fulfilled: $p1800 \geq n / (2 * p0115[0])$, $n = 1, 2, \dots$ - For motors with a small power rating (< 300 W) we recommend to set $n \geq 2$.			

r1406		CO/BO: Control word speed controller / STW n_ctrl		
SERVO	Can be changed: -		Access level: 3	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1530, 2520	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the control word of the speed controller.			
Bit field:	Bit	Signal name	1 signal	0 signal
	08	Travel to fixed stop active	Yes	No
	12	Torque control active	Yes	No

r1406		CO/BO: Control word, velocity controller / STW v_ctrl		
SERVO (Lin)	Can be changed: -		Access level: 3	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1530, 2520	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the control word of the velocity controller.			
Bit field:	Bit	Signal name	1 signal	0 signal
	08	Travel to fixed stop active	Yes	No
	12	Torque control active	Yes	No

r1406 CO/BO: Control word speed controller / STW n_ctrl

VECTOR (n/M)	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: -
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays the control word of the speed controller.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	04	Holds speed controller I component	Yes	No	-
	05	Sets speed controller I component	Yes	No	-
	11	Enables droop	Yes	No	6030
	12	Torque control active	Yes	No	-

r1407 CO/BO: Status word speed controller / ZSW n_ctrl

SERVO	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: 1530, 2522
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays the status word of the speed controller.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	U/f control active	Yes	No	-
	01	Sensorless operation active	Yes	No	-
	02	Torque control active	Yes	No	-
	04	DSC active	Yes	No	-
	05	Speed controller I component held	Yes	No	-
	06	Speed controller I component set	Yes	No	-
	07	Torq limit reached	Yes	No	5610
	08	Upper torque limit active	Yes	No	5610
	09	Lower torque limit active	Yes	No	5610
	11	Speed setpoint limited	Yes	No	-
	13	Sensorless operation due to a fault	Yes	No	-

r1407 CO/BO: Status word, velocity controller / ZSW v_ctrl

SERVO (Lin)	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: 1530, 2522
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays the status word of the velocity controller.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	U/f control active	Yes	No	-
	01	Sensorless operation active	Yes	No	-
	02	Torque control active	Yes	No	-
	04	DSC active	Yes	No	-
	05	Speed controller I component held	Yes	No	-
	06	Speed controller I component set	Yes	No	-
	07	Torq limit reached	Yes	No	5610
	08	Upper torque limit active	Yes	No	5610
	09	Lower torque limit active	Yes	No	5610
	11	Speed setpoint limited	Yes	No	-
	13	Sensorless operation due to a fault	Yes	No	-

r1407 CO/BO: Status word speed controller / ZSW n_ctrl

VECTOR (n/M)

Can be changed: -**Access level:** 3**Data type:** Unsigned16**Dynamic index:** -**Function diagram:** 1530,
2522**P-Group:** Closed-loop control**Units group:** -**Unit selection:** -**Min****Max****Factory setting**
0000 bin**Description:** Displays the status word of the speed controller.**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
00	U/f control active	Yes	No	-
01	Sensorless operation active	Yes	No	-
02	Torque control active	Yes	No	6030
03	Speed control active	Yes	No	6040
05	Speed controller I component held	Yes	No	6040
06	Speed controller I component set	Yes	No	6040
07	Torq limit reached	Yes	No	6060
08	Upper torque limit active	Yes	No	-
09	Lower torque limit active	Yes	No	-
10	Droop enabled	Yes	No	6030
11	Speed setpoint limited	Yes	No	6030
12	Ramp-function generator set	Yes	No	-
13	Sensorless operation due to a fault	Yes	No	-
14	I/f control active	Yes	No	-

r1408 CO/BO: Status word closed-loop current control / ZSW curr ctrl

SERVO

Can be changed: -**Access level:** 3**Data type:** Unsigned16**Dynamic index:** -**Function diagram:** 2530,
5040**P-Group:** Closed-loop control**Units group:** -**Unit selection:** -**Min****Max****Factory setting**
0000 bin**Description:** Displays the status word of the closed-loop current control.**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
00	CI-loop curr ctrl	active	Not active	-
04	Limit Vd	active	Not active	-
05	Limit Vq	active	Not active	-
06	Positive limiting Iq	active	Not active	-
07	Negative limiting Iq	active	Not active	-
08	Limit iq_set	active	Not active	-
09	Limit id_set	active	Not active	-

Note: The selected current limit is taken into account by the upstream torque limiting; this is the reason that bits 6, 7 and 8 are only set for overshoots due to the current setpoint filter.

r1408	CO/BO: Status word closed-loop current control / ZSW curr ctrl			
VECTOR (n/M)	Can be changed: -			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: 2530
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the status word of the closed-loop current control.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Current ctrl act	active	Not active
	01	Id control, I-component limiting	active	Not active
	03	Voltage limiting	active	Not active
	10	Speed adaptation, limiting	active	Not active
	11	Speed adaptation, speed deviation	Out tolerance	In tolerance
	12	Motor stalled	Yes	No
				FP
				-
				-
				-
				6719
				6719,
				8018
p1412[0...n]	Speed setpoint filter, deadtime / n_set deadtime			
TM41	Can be changed: U, T			Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180		Function diagram: 9674
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min	Max		Factory setting
	0.000 [ms]	1.000 [ms]		0.000 [ms]
Description:	Sets the delay of the speed setpoint for the incremental encoder emulation.			
p1414[0...n]	Speed setpoint filter activation / n_set_filt active			
SERVO	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 5020
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Activates the speed setpoint filters 1 and 2.			
Recommendation:	If only one filter is required, filter 1 should be activated and filter 2 deactivated, to avoid excessive processing time.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Activate filter 1	Yes	No
	01	Activate filter 2	Yes	No
				FP
				-
				-
Dependency:	The speed setpoint filter is parameterized using p1415 ... p1420 and p1421 ... p1426.			
p1414[0...n]	Velocity setpoint filter activation / v_set_filt active			
SERVO (Lin)	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 5020
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Activates the velocity setpoint filters 1 and 2.			
Recommendation:	If only one filter is required, filter 1 should be activated and filter 2 deactivated, to avoid excessive processing time.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Activate filter 1	Yes	No
	01	Activate filter 2	Yes	No
				FP
				-
				-
Dependency:	The velocity setpoint filter is parameterized using p1415 ... p1420 and p1421 ... p1426.			

p1414[0...n]	Speed setpoint filter activation / n_set_filt active		
TM41	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 9674
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0000 bin
Description:	Activates speed setpoint filter 1 for the incremental encoder emulation.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Activate filter 1	Yes No 9674
Dependency:	The speed setpoint filter can be parameterized using p1417 and p1418. Refer to: p1417, p1418		
p1415[0...n]	Speed setpoint filter 1 type / n_set_filt 1 typ		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Sets the type for speed setpoint filter 1.		
Values:	0: Low pass: PT1 1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	PT1 low pass: p1416 PT2 low pass: p1417, p1418 General filter: p1417 - p1420		
p1415[0...n]	Velocity setpoint filter 1 type / n_set_filt 1 typ		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Sets the type for speed setpoint filter 1.		
Values:	0: Low pass: PT1 1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	PT1 low pass: p1416 PT2 low pass: p1417, p1418 General filter: p1417 - p1420		
p1416[0...n]	Speed setpoint filter 1 time constant / n_set_filt 1 T		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020, 6030
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 5000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant for the speed setpoint filter 1 (PT1).		
Dependency:	Refer to: p1414, p1415		
Note:	For SERVO (p0107) the following applies: This parameter is only effective if the speed filter is set as a PT1 low pass.		

p1416[0...n]	Velocity setpoint filter 1 time constant / v_set_filt 1 T		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020, 6030
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 5000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant for the velocity setpoint filter 1 (PT1).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the velocity filter is set as a PT1 low pass.		
p1417[0...n]	Speed setpoint filter 1 denominator natural frequency / n_set_filt 1 fn_d		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for the speed setpoint filter 1 (PT2, general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the speed filter is parameterized as a PT2 low pass or as general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		
p1417[0...n]	Velocity setpoint filter 1 denominator natural frequency / v_set_filt 1 fn_d		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for velocity setpoint filter 1 (PT2, general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the velocity filter is parameterized as a PT2 low pass or as general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		
p1417[0...n]	Speed setpoint filter 1 denominator natural frequency / n_set_filt 1 fn_d		
TM41	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 9674
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for the speed setpoint filter 1 (PT2) of the incremental encoder emulation.		
Dependency:	Refer to: p1414		
Note:	This parameter is only effective if the speed setpoint filter in p1414 is activated. The filter is only effective if the natural frequency is less than half of the sampling frequency.		

p1418[0...n]	Speed setpoint filter 1 denominator damping / n_set_filt 1 D_d		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for the speed setpoint filter 1 (PT2, general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the speed filter is parameterized as a PT2 low pass or as general filter.		
p1418[0...n]	Velocity setpoint filter 1 denominator damping / v_set_filt 1 D_d		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for the velocity setpoint filter 1 (PT2, general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the velocity filter is parameterized as a PT2 low pass or as general filter.		
p1418[0...n]	Speed setpoint filter 1 denominator damping / n_set_filt 1 D_d		
TM41	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 9674
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 1.000	Factory setting 0.700
Description:	Sets the denominator damping for the speed setpoint filter 1 (PT2) of the incremental encoder emulation.		
Dependency:	Refer to: p1414		
Note:	This parameter is only effective if the speed setpoint filter in p1414 is activated.		
p1419[0...n]	Speed setpoint filter 1 numerator natural frequency / n_set_filt 1 fn_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for speed setpoint filter 1 (general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the speed filter is set as a general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		

p1419[0...n]	Velocity setpoint filter 1 numerator natural frequency / v_set_filt 1 fn_n		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for velocity setpoint filter 1 (general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the velocity filter is set as a general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		
p1420[0...n]	Speed setpoint filter 1 numerator damping / n_set_filt 1 D_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for speed setpoint filter 1 (general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the speed filter is set as a general filter.		
p1420[0...n]	Velocity setpoint filter 1 numerator damping / v_set_filt 1 D_n		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for velocity setpoint filter 1 (general filter).		
Dependency:	Refer to: p1414, p1415		
Note:	This parameter is only effective if the velocity filter is set as a general filter.		
p1421[0...n]	Speed setpoint filter 2 type / n_set_filt 2 typ		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Sets the type for speed setpoint filter 2.		
Values:	0: Low pass: PT1 1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	PT1 low pass: p1422 PT2 low pass: p1423, p1424 General filter: p1423 - p1426		

p1421[0...n]	Velocity setpoint filter 2 type / n_set_filt 2 typ		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: 5020
	P-Group: Closed-loop control		Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Sets the type for speed setpoint filter 2.		
Values:	0: Low pass: PT1 1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	PT1 low pass: p1422 PT2 low pass: p1423, p1424 General filter: p1423 - p1426		
p1422[0...n]	Speed setpoint filter 2 time constant / n_set_filt 2 T		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5020
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00 [ms]	Max 5000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant for the speed setpoint filter 2 (PT1).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the speed filter is set as a PT1 low pass.		
p1422[0...n]	Velocity setpoint filter 2 time constant / v_set_filt 2 T		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5020
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00 [ms]	Max 5000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant for the velocity setpoint filter 2 (PT1).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the velocity filter is set as a PT1 low pass.		
p1423[0...n]	Speed setpoint filter 2 denominator natural frequency / n_set_filt 2 fn_d		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5020
	P-Group: Closed-loop control		Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for speed setpoint filter 2 (PT2, general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the speed filter is parameterized as a PT2 low pass or as general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		

p1423[0...n]	Velocity setpoint filter 2 denominator natural frequency / v_set_filt 2 fn_d		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for velocity setpoint filter 2 (PT2, general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the velocity filter is parameterized as a PT2 low pass or as general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		

p1424[0...n]	Speed setpoint filter 2 denominator damping / n_set_filt 2 D_d		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for speed setpoint filter 2 (PT2, general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the speed filter is parameterized as a PT2 low pass or as general filter.		

p1424[0...n]	Velocity setpoint filter 2 denominator damping / v_set_filt 2 D_d		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for velocity setpoint filter 2 (PT2, general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the velocity filter is parameterized as a PT2 low pass or as general filter.		

p1425[0...n]	Speed setpoint filter 2 numerator natural frequency / n_set_filt 2 fn_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for speed setpoint filter 2 (general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the speed filter is set as a general filter. The filter is only effective if the natural frequency is less than half of the sampling frequency.		

p1425[0...n]	Velocity setpoint filter 2 numerator natural frequency / v_set_filt 2 fn_n		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for velocity setpoint filter 2 (general filter).		
Dependency:	Refer to: p1414, p1421		

Note: This parameter is only effective if the velocity filter is set as a general filter.
The filter is only effective if the natural frequency is less than half of the sampling frequency.

p1426[0...n]	Speed setpoint filter 2 numerator damping / n_set_filt 2 D_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for speed setpoint filter 2 (general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the speed filter is set as a general filter.		

p1426[0...n]	Velocity setpoint filter 2 numerator damping / v_set_filt 2 D_n		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for velocity setpoint filter 2 (general filter).		
Dependency:	Refer to: p1414, p1421		
Note:	This parameter is only effective if the velocity filter is set as a general filter.		

p1428[0...n]	Speed precontrol symmetrizing deadtime / n_prectrSym t_dead		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0	Max 2.0	Factory setting 0.0
Description:	Sets the deadtime to symmetrize the speed setpoint for active torque precontrol. The selected multiplier refers to the speed controller clock cycle (deadtime= p1428 * p0115[1]).		
Dependency:	In conjunction with p1429, this parameter can simulate the characteristics of how the torque is established (dynamic response of closed current control loop). For VECTOR (r0107) the following applies: The parameter is only effective if the acceleration model is supplied using external acceleration signals (p1400.2 = 1). For p1400.2 = 0, a fixed deadtime is used. Refer to: p1429, p1511		

p1428[0...n]	Velocity precontrol symmetrizing deadtime / n_prectrSym t_dead		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0	Max 2.0	Factory setting 0.0
Description:	Sets the deadtime to symmetrize the velocity setpoint for active force precontrol. The selected multiplier refers to the velocity controller clock cycle (deadtime= p1428 * p0115[1]).		
Dependency:	In conjunction with p1429, this parameter can simulate the characteristics of how the force is established (dynamic response of closed current control loop). Refer to: p1429, p1511		

p1429[0...n]	Speed precontrol symmetrizing time constant / n_prectr sym T		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant (PT1) for symmetrizing the speed setpoint for active torque precontrol.		
Dependency:	In conjunction with p1428, this parameter can simulate the characteristics of how torque is established (dynamic response of the closed current control loop). For VECTOR (r0107) the following applies: The parameter is only effective if the acceleration model is supplied using external acceleration signals (p1400.2 = 1). For p1400.2 = 0, time constant p1442 (or p1452 for sensorless closed-loop vector control) is used. Refer to: p1428, p1511		
p1429[0...n]	Velocity precontrol symmetrizing time constant / n_prectr sym T		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant (PT1) for symmetrizing the velocity setpoint for active force precontrol.		
Dependency:	In conjunction with p1428, this parameter can simulate the characteristics of how the force is established (dynamic response of closed current control loop). Refer to: p1428, p1511		
p1430[0...n]	CI: Speed precontrol / n_prectrl		
SERVO	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1550, 1590, 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for speed precontrol channel (speed precontrol or torque precontrol).		
p1430[0...n]	CI: Velocity precontrol / v_prectrl		
SERVO (Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1550, 1590, 5020
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the velocity precontrol channel (velocity precontrol or force precontrol).		

r1432	CO: Speed precontrol after symmetrizing / n_prectr after sym		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5030
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed precontrol value after symmetrizing for the torque build-up (emulates the closed current control loop).		
Dependency:	Symmetrizing can be parameterized with p1428 and/or p1429.		
r1432	CO: Velocity precontrol after symmetrizing / n_prectr after sym		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5030
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity precontrol value after symmetrizing for the force build-up (emulates the closed current control loop).		
Dependency:	Symmetrizing can be parameterized with p1428 and/or p1429.		
p1433[0...n]	Speed controller reference model natural frequency / n_ctrl RefMod fn		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [Hz]	Max 8000.0 [Hz]	Factory setting 0.0 [Hz]
Description:	Sets the natural frequency of a PT2 element for the reference model of the speed controller.		
Recommendation:	The reference model is correctly set when the characteristics of p1439 (reference model output) and p1445 (actual speed value) are virtually identical when the I-component of the speed controller is disabled.		
Dependency:	Together with p1434 and p1435, the characteristics (in the time domain) of the closed-loop speed control (P) can be emulated. For VECTOR (r0107) the following applies: The reference model is activated with p1400.3 = 1. Refer to: p1434, p1435		
p1433[0...n]	Velocity controller reference model natural frequency / v_ctrl RefMod fn		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [Hz]	Max 8000.0 [Hz]	Factory setting 0.0 [Hz]
Description:	Sets the natural frequency of a PT2 element for the reference model of the velocity controller.		
Recommendation:	The reference model is correctly set when the characteristics of p1439 (reference model output) and p1445 (actual velocity value) are virtually identical when the I-component of the velocity controller is disabled.		
Dependency:	Together with p1434 and p1435, the characteristics (in the time domain) of the closed-loop velocity control (P) can be emulated. Refer to: p1434, p1435		

p1434[0...n]	Speed controller reference model damping / n_ctrl RefMod D		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 5.000	Factory setting 1.000
Description:	Sets the damping of a PT2 element for the reference model of the speed controller.		
Recommendation:	The reference model is correctly set when the characteristics of p1439 (reference model output) and p1445 (actual speed value) are virtually identical when the I-component of the speed controller is disabled.		
Dependency:	In conjunction with p1433 and p1435, the characteristics (in time) of the P-controlled speed control loop can be emulated. For VECTOR (r0107) the following applies: The reference model is activated with p1400.3 = 1. Refer to: p1433, p1435		
p1434[0...n]	Velocity controller reference model damping / v_ctrl RefMod D		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 5.000	Factory setting 1.000
Description:	Sets the damping of a PT2 element for the reference model of the velocity controller.		
Recommendation:	The reference model is correctly set when the characteristics of p1439 (reference model output) and p1445 (actual velocity value) are virtually identical when the I-component of the velocity controller is disabled.		
Dependency:	Together with p1433 and p1435, the characteristics (in the time domain) of the P-controlled velocity control loop can be emulated. Refer to: p1433, p1435		
p1435[0...n]	Speed controller reference model deadtime / n_ctrlRefMod t_dead		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point		Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00	Max 2.00	Factory setting 0.00
Description:	Sets the "fractional" deadtime for the reference model of the speed controller. This parameter emulates the computation deadtime of the proportionally controlled speed control loop. The selected multiplier refers to the speed controller clock cycle (deadtime= p1435 * p0115[1]).		
Recommendation:	The reference model is correctly set when the characteristics of p1439 (reference model output) and p1445 (actual speed value) are virtually identical when the I-component of the speed controller is disabled.		
Dependency:	In conjunction with p1433 and p1434, the characteristics (in time) of the P-controlled speed control loop can be emulated. For VECTOR (r0107) the following applies: The reference model is activated with p1400.3 = 1. Refer to: p0115, p1433, p1434		

p1435[0...n]	Velocity controller reference model deadtime / v_ctrRefMod t_dead		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00	Max 2.00	Factory setting 0.00
Description:	Sets the "fractional" deadtime for the reference model of the velocity controller. This parameter emulates the computation deadtime of the proportionally controlled velocity control loop. The selected multiplier refers to the velocity controller clock cycle (deadtime= p1435 * p0115[1]).		
Recommendation:	The reference model is correctly set when the characteristics of p1439 (reference model output) and p1445 (actual velocity value) are virtually identical when the I-component of the velocity controller is disabled.		
Dependency:	Together with p1433 and p1434, the characteristics (in the time domain) of the P-controlled velocity control loop can be emulated. Refer to: p0115, p1433, p1434		
r1436	CO: Speed controller reference model speed setpoint output / RefMod n_set outpt		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed setpoint at the output of the reference model.		
Dependency:	For VECTOR (r0107) the following applies: The reference model is activated with p1400.3 = 1.		
r1436	CO: Velocity controller, reference model velocity_setpoint output / RefMod v_set outpt		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5030, 6031
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity setpoint at the output of the reference model.		
Dependency:	For VECTOR (r0107) the following applies: The reference model is activated with p1400.3 = 1.		
p1437[0...n]	CI: Speed controller, reference model I component input / n_ctrRefMod I_comp		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1436[0]
Description:	Sets the signal source for speed setpoint for the integral component of the speed controller.		
Dependency:	The reference model is activated with p1400.3 = 1. Refer to: p1400		
Caution:	It should be ensured that a speed setpoint is selected as signal source that corresponds to the setpoint for the P component of the speed controller.		

r1438	CO: Speed controller, speed setpoint / n_ctrl n_set		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 1590, 3080, 5030, 5040, 5060, 5210, 5300, 6040
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed setpoint after setpoint limiting for the P component of the speed controller. For U/f operation, the value that is displayed is of no relevance.		
Dependency:	Refer to: r1439		
Note:	In the standard state (the reference model is de-activated), r1438 = r1439.		
r1438	CO: Velocity controller, velocity setpoint / v_ctrl v_set		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1550, 1590, 3080, 5030, 5040, 5060, 5210, 5300, 6040
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the speed setpoint after setpoint limiting for the P component of the velocity controller. For U/f operation, the value that is displayed is of no relevance.		
Dependency:	Refer to: r1439		
Note:	In the standard state (the reference model is de-activated), r1438 = r1439.		
r1439	Speed setpoint, I component / n_set I_comp		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 5030, 5040, 6031
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed setpoint for the I component of the speed controller (output of the reference model after the setpoint limiting).		
Dependency:	Refer to: r1438		
Note:	In the standard state (the reference model is de-activated), r1438 = r1439.		
r1439	Velocity setpoint, I component / v_set I_comp		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 5030, 5040, 6031
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity setpoint for the I component of the velocity controller (output of the reference model after the setpoint limiting).		
Dependency:	Refer to: r1438		
Note:	In the standard state (the reference model is de-activated), r1438 = r1439.		

p1441[0...n]	Actual speed smoothing time / n_act T_smooth		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4710, 4715
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 50.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the smoothing time constant (PT1) for the speed actual value.		
Dependency:	Refer to: r0063		
Note:	The speed actual value should be smoothed for encoders with a low pulse number or for resolvers. After this parameter has been changed, we recommend that the speed controller is adapted and/or the speed controller settings checked Kp (p1460) and Tn (p1462).		
p1441[0...n]	Actual velocity, smoothing time / v_act T_smooth		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4710, 4715
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 50.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the smoothing time constant (PT1) for the velocity actual value.		
Dependency:	Refer to: r0063		
Note:	The speed actual value should be smoothed for encoders with a low pulse number or for resolvers. After this parameter has been changed, we recommend that the velocity controller is adapted and/or the velocity controller settings checked Kp (p1460) and Tn (p1462).		
p1441[0...n]	Actual speed smoothing time / n_act T_smooth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4710, 4715
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 1000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the smoothing time constant (PT1) for the speed actual value.		
Dependency:	Refer to: r0063		
Notice:	Smoothing times above 20 ms are only possible if the drive is accelerated or braked with the appropriately long ramp-up/ramp-down times. Otherwise, significant torque errors can occur and there is the danger that the drive is powered-down (tripped) with F07902 (motor stalled).		
Note:	The speed actual value should be smoothed for encoders with a low pulse number or for resolvers. After this parameter has been changed, we recommend that the speed controller is adapted and/or the speed controller settings checked Kp (p1460) and Tn (p1462).		
p1442[0...n]	Speed controller speed actual value smoothing time / n_ctr n_act T_smth		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6040
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 32000.00 [ms]	Factory setting 4.00 [ms]
Description:	Sets the smoothing time for the actual speed value of the speed controller for closed-loop control with encoder.		
Note:	The smoothing must be increased if there is gear backlash. For longer smoothing times, the integral time of the speed controller must also be increased (e.g. using p0340 = 4).		

r1444	Speed controller, speed setpoint steady-state (static) / n_ctrl n_set stat		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5030
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the sum of all speed setpoints that are present. The following sources are available for the displayed setpoint: - setpoint at the ramp-function generator input (r1119). - speed setpoint 1 (p1155). - speed setpoint 2 (p1160). - speed setpoint for the speed precontrol (p1430). - setpoint from DSC (for DSC active). - setpoint via PC (for master control active, p3983).		
Dependency:	Refer to: r1119, p1155, p1160, p1430		
r1444	Velocity controller, velocity setpoint, total / v_ctrl v_set stat		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5030
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the sum of all velocity setpoints that are present. The following sources are available for the displayed setpoint: - setpoint at the ramp-function generator input (r1119). - velocity setpoint 1 (p1155). - velocity setpoint 2 (p1160). - velocity setpoint for the velocity precontrol (p1430). - setpoint from DSC (for DSC active). - setpoint via PC (for master control active, p3983).		
Dependency:	Refer to: r1119, p1155, p1160, p1430		
r1445	CO: Actual speed, smoothed / n_act smooth		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6040
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the smoothed actual speed for speed control.		
p1452[0...n]	Speed controller speed actual value smoothing time (SLVC) / n_C n_act T_s SLVC		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6040
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 32000.00 [ms]	Factory setting 10.00 [ms]
Description:	Sets the smoothing time for the actual speed of the speed controller for sensorless closed-loop speed control.		
Note:	The smoothing must be increased if there is gear backlash. For longer smoothing times, the integral time of the speed controller must also be increased (e.g. using p0340 = 4).		

r1454	CO: Speed controller system deviation I component / n_ctrl sys_dev Tn		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 3_1	Function diagram: 5040
	P-Group: Closed-loop control		Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the system deviation of the I component of the speed controller. When the reference model is inactive (p1433 = 0 Hz), this parameter corresponds to the system deviation of the complete PI controller (r1454 = r0064).		
r1454	CO: Velocity controller system deviation I component / v_ctrl sys_dev Tn		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 5040
	P-Group: Closed-loop control		Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the system deviation of the I component of the velocity controller. When the reference model is inactive (p1433 = 0 Hz), this parameter corresponds to the system deviation of the complete PI controller (r1454 = r0064).		
p1455[0...n]	CI: Speed controller P gain adaptation signal / n_ctrl Adpt_sig Kp		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 5050
	P-Group: Closed-loop control		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the source for the adaptation signal to additionally adapt the P gain of the speed controller.		
Dependency:	Refer to: p1456, p1457, p1458, p1459		
p1455[0...n]	CI: Velocity controller, P gain adaptation signal / v_ctrl Adpt_sig Kp		
SERVO (Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 5050
	P-Group: Closed-loop control		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the source for the adaptation signal to additionally adapt the P gain of the velocity controller.		
Dependency:	Refer to: p1456, p1457, p1458, p1459		
p1456[0...n]	Speed controller P gain adaptation lower starting point / n_ctrl AdaptKpLow.		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5050
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00 [%]	Max 400.00 [%]	Factory setting 0.00 [%]
Description:	Sets the lower starting point of the adaptation range for the additional adaptation of the P gain of the speed controller. The values are in % and refer to the set source of the adaptation signal.		
Dependency:	Refer to: p1455, p1457, p1458, p1459		

p1456[0...n]	Velocity controller P gain adaptation, lower starting point / n_ctrl AdaptKpLow.		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 400.00 [%]	Factory setting 0.00 [%]
Description:	Sets the lower starting point of the adaptation range for the additional adaptation of the P gain of the velocity controller. The values are in % and refer to the set source of the adaptation signal.		
Dependency:	Refer to: p1455, p1457, p1458, p1459		
p1456[0...n]	Speed controller P gain adaptation lower starting point / n_ctrl AdaptKpLow.		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 400.00 [%]	Factory setting 0.00 [%]
Description:	Sets the lower starting point of the adaptation range for the additional adaptation of the P gain of the speed controller. The values are in % and refer to the set source of the adaptation signal.		
Dependency:	Refer to: p1455, p1457, p1458, p1459		
Note:	If the upper transition point p1457 of the speed controller adaptation is set to lower values than the lower transition p1456, then the controller gain below p1457 is adapted with p1459 and above p1456, with p1458.		
p1457[0...n]	Speed controller P gain adaptation upper starting point / n_ctrl AdaptKp up.		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 400.00 [%]	Factory setting 0.00 [%]
Description:	Sets the upper starting point of the adaptation range for the additional adaptation of the P gain of the speed controller. The values are in % and refer to the set source of the adaptation signal.		
Dependency:	Refer to: p1455, p1456, p1458, p1459		
p1457[0...n]	Velocity controller P gain adaptation upper starting point / v_ctrl AdaptKp up.		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 400.00 [%]	Factory setting 0.00 [%]
Description:	Sets the upper starting point of the adaptation range for the additional adaptation of the P gain of the velocity controller. The values are in % and refer to the set source of the adaptation signal.		
Dependency:	Refer to: p1455, p1456, p1458, p1459		

p1457[0...n]	Speed controller P gain adaptation upper starting point / n_ctrl AdaptKp up.		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 400.00 [%]	Factory setting 0.00 [%]
Description:	Sets the upper starting point of the adaptation range for the additional adaptation of the P gain of the speed controller. The values are in % and refer to the set source of the adaptation signal.		
Dependency:	Refer to: p1455, p1456, p1458, p1459		
Note:	If the upper transition point p1457 of the speed controller adaptation is set to lower values than the lower transition p1456, then the controller gain below p1457 is adapted with p1459 and above p1456, with p1458.		
p1458[0...n]	Adaptation factor, lower / Adapt_factor lower		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the adaptation factor before the adaptation range (0 % ... p1456) to additionally adapt the P gain of the speed/velocity controller.		
Dependency:	Refer to: p1455, p1456, p1457, p1459		
p1458[0...n]	Adaptation factor, lower / Adapt_factor lower		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the adaptation factor before the adaptation range (0 % ... p1456) to additionally adapt the P gain of the speed/velocity controller.		
Dependency:	Refer to: p1455, p1456, p1457, p1459		
Note:	If the upper transition point p1457 of the speed controller adaptation is set to lower values than the lower transition p1456, then the controller gain below p1457 is adapted with p1459 and above p1456, with p1458.		
p1459[0...n]	Adaptation factor, upper / Adapt_factor upper		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the adaptation factor after the adaptation range (> p1457) to additionally adapt the P gain of the speed/velocity controller.		
Dependency:	Refer to: p1455, p1456, p1457, p1458		

p1459[0...n]	Adaptation factor, upper / Adapt_factor upper		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the adaptation factor after the adaptation range (> p1457) to additionally adapt the P gain of the speed/velocity controller.		
Dependency:	Refer to: p1455, p1456, p1457, p1458		
Note:	If the upper transition point p1457 of the speed controller adaptation is set to lower values than the lower transition p1456, then the controller gain below p1457 is adapted with p1459 and above p1456, with p1458.		
p1460[0...n]	Speed controller P gain adaptation speed, lower / n_ctrl Kp n lower		
SERVO	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5040
	P-Group: Closed-loop control	Units group: 17_1	Unit selection: p0505
	Min 0.000 [Nms/rad]	Max 999999.000 [Nms/rad]	Factory setting 0.300 [Nms/rad]
Description:	Sets the P gain of the speed controller before the adaptation speed range (0 ... p1464). This value corresponds to the basic setting of the P gain of the speed controller without adaptation (p1461 = 100 %).		
Dependency:	Refer to: p1461, p1464, p1465		
Note:	When automatically calculating the speed controller, only the motor moment of inertia is taken into account (p0341). For higher load moments of inertia (p0342 > 1 or p1498 > 0) we recommend that the speed controller gain is checked.		
p1460[0...n]	Velocity controller, P gain adaptation velocity, lower / v_ctrl Kp n lower		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5040
	P-Group: Closed-loop control	Units group: 24_2	Unit selection: p0505
	Min 0.000 [Ns/m]	Max 999999.000 [Ns/m]	Factory setting 10.000 [Ns/m]
Description:	Sets the P gain of the velocity controller before the adaptation velocity range (0 ... p1464). This value corresponds to the basic setting of the P gain of the velocity controller without adaptation (p1461 = 100 %).		
Dependency:	Refer to: p1461, p1464, p1465		
Note:	When automatically calculating the velocity controller, only the motor inertia is taken into account (p0341). For higher inertias (p0342 > 1 or p1498 > 0) we recommend that the velocity controller gain is checked.		
p1460[0...n]	Speed controller P gain adaptation speed, lower / n_ctrl Kp n lower		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6040
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 999999.000	Factory setting 0.300
Description:	Sets the P gain of the speed controller before the adaptation speed range (0 ... p1464). This value corresponds to the basic setting of the P gain of the speed controller without adaptation (p1461 = 100 %).		
Dependency:	For p0528 = 1, the speed controller gain is represented without any dimensions. Refer to: p1461, p1464, p1465		

p1461[0...n]	Speed controller Kp adaptation speed, upper scaling / n_ctrl Kp n upper		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the P gain of the speed controller for the upper adaptation speed range (> p1465). The entry is made referred to the P gain for the lower adaptation speed range of the speed controller (% referred to p1460).		
Dependency:	Refer to: p1460, p1464, p1465		
Note:	When automatically calculating the speed controller, only the motor moment of inertia is taken into account (p0341). For higher load moments of inertia (p0342 > 1 or p1498 > 0) we recommend that the speed controller gain is checked.		
p1461[0...n]	Velocity controller, P gain adaptation velocity, upper / v_ctrl Kp n upper		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the P gain of the velocity controller for the upper adaptation velocity range (> p1465). The entry is made referred to the P gain for the lower adaptation velocity range of the velocity controller (% referred to p1460).		
Dependency:	Refer to: p1460, p1464, p1465		
Note:	When automatically calculating the velocity controller, only the motor inertia is taken into account (p0341). For higher inertias (p0342 > 1 or p1498 > 0) we recommend that the velocity controller gain is checked.		
p1461[0...n]	Speed controller Kp adaptation speed, upper scaling / n_ctrl Kp n upper		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the P gain of the speed controller for the upper adaptation speed range (> p1465). The entry is made referred to the P gain for the lower adaptation speed range of the speed controller (% referred to p1460).		
Dependency:	Refer to: p1460, p1464, p1465		
Note:	If the upper transition point p1465 of the speed controller adaptation is set to lower values than the lower transition p1464, then the controller gain below p1465 is adapted with p1461. This means that an adaptation can be implemented for low speeds without having to change the controller parameters.		
p1462[0...n]	Speed controller integral time adaptation speed, lower / n_ctrl Tn n lower		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5040, 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100000.00 [ms]	Factory setting 20.00 [ms]
Description:	Sets the integration time of the speed controller before the adaptation speed range (0 ... p1464). This value corresponds to the basic setting of the integral time of the speed controller without adaptation (p1461 = 100 %).		
Dependency:	Refer to: p1463, p1464, p1465		

p1462[0...n]	Velocity contr., integral act. time adaptation velocity, lower / v_ctrl Tn n lower		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5040, 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100000.00 [ms]	Factory setting 20.00 [ms]
Description:	Sets the integration time of the velocity controller before the adaptation velocity range (0 ... p1464). This value corresponds to the basic setting of the integral time of the velocity controller without adaptation (p1461 = 100 %).		
Dependency:	Refer to: p1463, p1464, p1465		
p1463[0...n]	Speed controller Tn adaptation speed, upper scaling / n_ctrl Tn n upper		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the integral time of the speed controller after the adaptation speed range (> p1465). The entry is made referred to the integral time for the lower adaptation speed range of the speed controller (% referred to p1462).		
Dependency:	Refer to: p1462, p1464, p1465		
p1463[0...n]	Velocity contr., integral act. time adaptation velocity, upper / v_ctrl Tn n upper		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the integral time of the velocity controller after the adaptation velocity range (> p1465). The entry is made referred to the integral time for the lower adaptation velocity range of the velocity controller (% referred to p1462).		
Dependency:	Refer to: p1462, p1464, p1465		
p1463[0...n]	Speed controller Tn adaptation speed, upper scaling / n_ctrl Tn n upper		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the integral time of the speed controller after the adaptation speed range (> p1465). The entry is made referred to the integral time for the lower adaptation speed range of the speed controller (% referred to p1462).		
Dependency:	Refer to: p1462, p1464, p1465		
Note:	If the upper transition point p1465 of the speed controller adaptation is set to lower values than the lower transition point p1464, then the controller integral time below p1465 is adapted with p1463. This means that an adaptation can be implemented for low speeds without having to change the controller parameters.		

p1464[0...n]	Speed controller adaptation speed, lower / n_ctrl n lower		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the lower adaptation speed of the speed controller. No adaptation is effective below this speed.		
Dependency:	Refer to: p1460, p1461, p1462, p1463, p1465		
p1464[0...n]	Velocity controller adaptation velocity, lower / v_ctrl n lower		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.00 [m/min]
Description:	Sets the lower adaptation velocity of the velocity controller. No adaptation is effective below this velocity.		
Dependency:	Refer to: p1460, p1461, p1462, p1463, p1465		
p1464[0...n]	Speed controller adaptation speed, lower / n_ctrl n lower		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the lower adaptation speed of the speed controller. No adaptation is effective below this speed.		
Dependency:	Refer to: p1460, p1461, p1462, p1463, p1465		
Note:	If the upper transition point p1465 of the speed controller adaptation is set to values less than the lower transition point p1464, then the controller below p1465 is adapted with p1461 or p1463. This means that an adaptation can be implemented for low speeds without having to change the controller parameters.		
p1465[0...n]	Speed controller adaptation speed, upper / n_ctrl n upper		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 210000.00 [1/min]
Description:	Sets the upper adaptation speed of the speed controller. No adaptation is effective above this speed. For P gain, p1460 * p1461 is effective. For the integral time, p1462 * p1463 is effective.		
Dependency:	Refer to: p1460, p1461, p1462, p1463, p1464		
p1465[0...n]	Velocity controller adaptation velocity, upper / v_ctrl n upper		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5050
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 1000.00 [m/min]
Description:	Sets the upper adaptation velocity of the velocity controller. No adaptation is effective above this velocity. For P gain, p1460 * p1461 is effective. For the integral time, p1462 * p1463 is effective.		
Dependency:	Refer to: p1460, p1461, p1462, p1463, p1464		

p1465[0...n]	Speed controller adaptation speed, upper / n_ctrl n upper		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6050
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 210000.00 [1/min]
Description:	Sets the upper adaptation speed of the speed controller. No adaptation is effective above this speed. For P gain, p1460 * p1461 is effective. For the integral time, p1462 * p1463 is effective.		
Dependency:	Refer to: p1460, p1461, p1462, p1463, p1464		
Note:	If the upper transition point p1465 of the speed controller adaptation is set to values less than the lower transition point p1464, then the controller below p1465 is adapted with p1461 or p1463. This means that an adaptation can be implemented for low speeds without having to change the controller parameters.		
p1466[0...n]	CI: Speed controller P-gain scaling / n_ctrl Kp Scal		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the scaling of the P gain of the speed controller. This also makes the effective P gain (including adaptations) scalable.		
p1466[0...n]	CI: Velocity controller P gain scaling / v_ctrl Kp scal		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the scaling of the P gain of the velocity controller. This also makes the effective P gain (including adaptations) scalable.		
r1468	Speed controller P-gain effective / n_ctrl Kp eff		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3080, 5040, 5210
	P-Group: Closed-loop control	Units group: 17_1	Unit selection: p0505
	Min - [Nms/rad]	Max - [Nms/rad]	Factory setting - [Nms/rad]
Description:	Displays the effective P gain of the speed controller.		
r1468	Velocity controller, P gain effective / v_ctrl Kp eff		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 3080, 5040, 5210
	P-Group: Closed-loop control	Units group: 24_2	Unit selection: p0505
	Min - [Ns/m]	Max - [Ns/m]	Factory setting - [Ns/m]
Description:	Displays the effective P gain of the velocity controller.		

r1468	CO: Speed controller P-gain effective / n_ctrl Kp eff		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 6040
	P-Group: Closed-loop control		Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the effective P gain of the speed controller.		
Dependency:	For p0528 = 1, the speed controller gain is represented without any dimensions. In this case, connector output signal r1468 is increased by a factor of 100 in order to improve the resolution.		
r1469	Speed controller integral time effective / n_ctrl Tn eff		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5040
	P-Group: Closed-loop control		Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the effective integral time of the speed controller.		
r1469	Velocity controller integral time effective / v_ctrl Tn eff		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 5040
	P-Group: Closed-loop control		Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the effective integral time of the velocity controller.		
p1470[0...n]	Speed controller sensorless operation P-gain / n_ctrl SLVC Kp		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 17_1	Function diagram: 5210
	P-Group: Closed-loop control		Unit selection: p0505
	Min 0.000 [Nms/rad]	Max 999999.000 [Nms/rad]	Factory setting 0.300 [Nms/rad]
Description:	Sets the P gain for sensorless operation for the speed controller.		
Note:	When automatically calculating the speed controller, only the motor moment of inertia is taken into account (p0341). For higher load moments of inertia (p0342 > 1 or p1498 > 0) we recommend that the speed controller gain is checked.		
p1470[0...n]	Velocity controller sensorless operation P-gain / v_ctrl SLVC Kp		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 24_2	Function diagram: 5210
	P-Group: Closed-loop control		Unit selection: p0505
	Min 0.000 [Ns/m]	Max 999999.000 [Ns/m]	Factory setting 10.000 [Ns/m]
Description:	Sets the P gain for sensorless operation for the velocity controller.		
Note:	When automatically calculating the velocity controller, only the motor inertia is taken into account (p0341). For higher inertias (p0342 > 1 or p1498 > 0) we recommend that the velocity controller gain is checked.		

p1470[0...n]	Speed controller sensorless operation P-gain / n_ctrl SLVC Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6040, 6050
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 999999.000	Factory setting 0.300
Description:	Sets the P gain for sensorless operation for the speed controller.		
Dependency:	For p0528 = 1, the speed controller gain is represented without any dimensions.		
Note:	The product p0341 * p0342 is taken into account when automatically calculating the speed controller (p0340 = 1, 3, 4).		
p1472[0...n]	Speed controller sensorless operation integral time / n_ctrl SLVC Tn		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 100000.0 [ms]	Factory setting 20.0 [ms]
Description:	Set the integral time for sensorless operation for the speed controller.		
p1472[0...n]	Velocity controller sensorless operation integral time / v_ctrl SLVC Tn		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 100000.0 [ms]	Factory setting 20.0 [ms]
Description:	Set the integral time for sensorless operation for the velocity controller.		
p1476[0...n]	BI: Speed controller hold integrator / n_ctrl integ stop		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5040
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to hold the integrator for the speed controller.		
p1476[0...n]	BI: Velocity controller, hold integrator / v_ctrl integ stop		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5040
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to hold the integrator for the velocity controller.		

p1477[0...n]	BI: Speed controller set integrator value / n_ctrl integ set		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to set the integrator setting value (p1478).		
Note:	For the interface mode "SIMODRIVE 611 universal" (p2038 = 1), p1477 and p1478 are used for the signal STW2.6 (integrator inhibit, speed controller).		
p1477[0...n]	BI: Set velocity controller integrator value / v_ctrl integ set		
SERVO (Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to set the integrator setting value (p1478).		
Note:	For the interface mode "SIMODRIVE 611 universal" (p2038 = 1), p1477 and p1478 are used for the signal STW2.6 (integrator inhibit, speed controller).		
p1478[0...n]	CI: Speed controller integrator setting value / n_ctrl integ_setVal		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the integrator setting value for the velocity controller. The signal to set this integrator setting value is interconnected via p1477.		
Dependency:	For VECTOR (r0107) the following applies: The setting value of the speed controller integrator is weighted with the scaling factor of the signal source in p1479.		
Note:	For the interface mode "SIMODRIVE 611 universal" (p2038 = 1), p1477 and p1478 are used for the signal STW2.6 (integrator inhibit, speed controller).		
p1478[0...n]	CI: Velocity controller, integrator value / v_ctrl integ_setVal		
SERVO (Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the integrator setting value for the velocity controller. The signal to set this integrator setting value is interconnected via p1477.		
Dependency:	For VECTOR (r0107) the following applies: The setting value of the speed controller integrator is weighted with the scaling factor of the signal source in p1479.		
Note:	For the interface mode "SIMODRIVE 611 universal" (p2038 = 1), p1477 and p1478 are used for the signal STW2.6 (integrator inhibit, speed controller).		

p1479[0...n]	CI: Speed controller integrator setting value scaling / n_ctrl I_val scal		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for scaling the integrator setting value (p1478) of the speed controller.		
Dependency:	Refer to: p1478		
r1480	CO: Speed controller PI torque output / n_ctrl PI-M_output		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1590, 5040, 5060, 5210
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque setpoint at the output of the PI speed controller.		
r1480	CO: Velocity controller PI force output / v_ctrl PI-F_output		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1590, 5040, 5060, 5210
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the force setpoint at the output of the PI velocity controller.		
r1481	CO: Speed controller P torque output / n_ctrl P-M_output		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque setpoint at the output of the P speed controller.		
r1481	CO: Velocity controller P force output / v_ctrl P-F_output		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the force setpoint at the output of the P velocity controller.		

r1482	CO: Speed controller I torque output / n_ctrl I-M_output		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 5040, 5210, 6040
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque setpoint at the output of the I speed controller.		
r1482	CO: Velocity controller I force output / v_ctrl I-F_output		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 5040, 5210, 6040
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the force setpoint at the output of the I velocity controller.		
p1488[0...n]	Droop input source / Droop input,source		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16		Function diagram: 6030
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	Sets the source for droop feedback.		
Values:	0: Droop feedback not connected 1: Droop from torque setpoint 2: Droop from speed controller output 3: Droop from integral output, speed controller		
Dependency:	Refer to: p1489, r1490, p1492		
p1489[0...n]	Droop feedback scaling / Droop scaling		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 6030
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 0.500	Factory setting 0.050
Description:	Sets the scaling for the droop feedback		
Dependency:	Refer to: p1488, r1490, p1492		
Note:	Example: A value of 0.05 means that for a torque equal to the rated motor torque, the rated motor speed is reduced by 5 %.		
r1490	CO: Droop feedback speed reduction / Droop n_reduction		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 6030
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the output signal of the droop calculation. The droop feedback result is subtracted from the speed setpoint when activated (p1492).		
Dependency:	Refer to: p1488, p1489, p1492		

p1492[0...n]	BI: Droop feedback enable / Enables droop		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Enables the droop to be applied to the speed/velocity setpoint.		
Dependency:	Refer to: p1488, p1489, r1490		
Note:	Even when not enabled, the droop speed is calculated but not subtracted from the setpoint speed. This makes it possible to subtract the result of this calculation from the speed of another drive.		
p1494[0...n]	Speed controller integrator feedback time constant / n_ctr integ_fdbk T		
SERVO	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 1000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant of the PT1 filter for integrator feedback. The integrator of the speed/velocity controller is re-parameterized to become a PT1 filter through a feedback element (1st Order low pass filter characteristics). The following applies: p1494 < 0.25 (2 * p0115[1]) --> the PT1 filter is not active - the pure integrator is effective. p1494 >= 0.25 (2 * p0115[1]) --> the PT1 filter is active and has replaced the pure integrator.		
Note:	Applications: Motion at zero setpoint and dominant stiction can be suppressed but this has a negative impact on the remaining setpoint-actual value difference. This can be used, for example, to avoid oscillation of a position-controlled axis at standstill (stick-slip effect) or overshoot when traversing (moving) in micrometer steps. Also prevents tension/stressing for axes that are mechanically and rigidly coupled with one another (e.g. for synchronous spindles, master - slave axes).		
p1494[0...n]	Velocity controller integrator feedback time constant / v_ctr integ_fdbk T		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5040, 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 1000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant of the PT1 filter for integrator feedback. The integrator of the speed/velocity controller is re-parameterized to become a PT1 filter through a feedback element (1st Order low pass filter characteristics). The following applies: p1494 < 0.25 (2 * p0115[1]) --> the PT1 filter is not active - the pure integrator is effective. p1494 >= 0.25 (2 * p0115[1]) --> the PT1 filter is active and has replaced the pure integrator.		
Note:	Applications: Motion at zero setpoint and dominant stiction can be suppressed but this has a negative impact on the remaining setpoint-actual value difference. This can be used, for example, to avoid oscillation of a position-controlled axis at standstill (stick-slip effect) or overshoot when traversing (moving) in micrometer steps. Also prevents tension/stressing for axes that are mechanically and rigidly coupled with one another (e.g. for synchronous spindles, master - slave axes).		

p1495[0...n]	CI: Acceleration pre-control, speed change each 1 s / a_prectrl dn/1s		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the speed change per second for the acceleration pre-control.		
Dependency:	The signal source for the acceleration is activated with p1400.2 = 1. For p1400.2 = 0, the acceleration pre-control is calculated from the speed setpoint change from r0062. For p1400.2 = 0 and activate reference model (p1400.3 = 1) the acceleration pre-control is switched-out. Refer to: p1400, p1496		
Note:	If the acceleration is entered as external signal, then the accelerating torque is calculated as follows (r1518): $r1518 = \text{acceleration (\% of p2000)} / 100 \% * p2000 / p0311 * r0345 / 1 \text{ s} * r0333$		
p1496[0...n]	Acceleration pre-control scaling / a_before scaling		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6031
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 10000.0 [%]	Factory setting 0.0 [%]
Description:	Sets the scaling for the acceleration pre-control of the speed/velocity controller.		
Dependency:	When the reference model is activate (p1400.3 = 1) and for an internal acceleration pre-control (p1400.2 = 0), the acceleration pre-control is switched-out (disabled). The reference model (p1400.3 = 1) and external acceleration pre-control (p1400.2 = 1) can be operated together. Refer to: p0341, p0342		
Note:	The parameter is set to 100% by the rotating measurement (refer to p1960). The acceleration pre-control may not be used if the speed setpoint manifests significant ripple (e.g. analog setpoint) and the rounding-off in the speed ramp-function generator is disabled. We also recommend that the pre-control mode is not used if there is gearbox backlash.		
p1498[0...n]	Load moment of inertia / Load mom of inert		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 25_1	Unit selection: p0100
	Min 0.00000 [kgm ²]	Max 100000.00000 [kgm ²]	Factory setting 0.00000 [kgm ²]
Description:	Sets the load moment of inertia.		
Note:	(p0341 * p0342) + p1498 influence the speed/torque precontrol in sensorless operation.		
p1498[0...n]	Load mass / Load mass		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 27_1	Unit selection: p0100
	Min 0.00000 [kg]	Max 10000.00000 [kg]	Factory setting 0.00000 [kg]
Description:	Sets the mass.		
Note:	(p0341 * p0342) + p1498 influence the velocity/force precontrol in sensorless operation.		

p1499[0...n]	Accelerating for torque control, scaling / a for M_ctrl scal		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 400.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling for the acceleration integrator at low speeds (only for sensorless torque control).		
Dependency:	Refer to: p0341, p0342		
p1500[0...n]	Macro Connector Inputs (CI) for torque setpoints / Macro CI M_set		
SERVO, VECTOR	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0	Max 999999	Factory setting 0
Description:	Runs the appropriate ACX file on the CompactFlash card. The Connector Inputs (CI) for the torque setpoints of the appropriate Command Data Set (CDS) are appropriately interconnected. The selected ACX file must be located in the following directory: ... /PMACROS/<drive object>/P1500/PMxxxxxx.ACX Example: p1500 = 6 --> the file PM000006.ACX is run.		
Dependency:	The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card. Refer to: p0015, p0700, p1000, r8573		
Notice:	No errors were issued during fast commissioning (p3900 = 1) when writing to parameters of the QUICK_IBN group!		
Note:	The macros in the specified directory are displayed in r8573. Macros available as standard are described in the technical documentation of the particular product. CI: Connector Input		
p1500[0...n]	Macro Connector Inputs (CI) for force setpoints / Macro CI F_set		
SERVO (Lin)	Can be changed: C2(1), T		Access level: 1
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0	Max 999999	Factory setting 0
Description:	Runs the appropriate ACX file on the CompactFlash card. The Connector Inputs (CI) for the torque setpoints of the appropriate Command Data Set (CDS) are appropriately interconnected. The selected ACX file must be located in the following directory: ... /PMACROS/<drive object>/P1500/PMxxxxxx.ACX Example: p1500 = 6 --> the file PM000006.ACX is run.		
Dependency:	The ACX file to be run must be created according to the definition for ACX macros and must be saved in the directory intended on the CompactFlash card. Refer to: p0015, p0700, p1000, r8573		
Notice:	No errors were issued during fast commissioning (p3900 = 1) when writing to parameters of the QUICK_IBN group!		
Note:	The macros in the specified directory are displayed in r8573. Macros available as standard are described in the technical documentation of the particular product. CI: Connector Input		

p1501[0...n]	BI: Change over between closed-loop speed/torque control / Changeov n/M_ctrl		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2520, 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for toggling between speed and torque control.		
Dependency:	The input connectors to enter the torque are provided using p1511, p1512 and p1513. Refer to: p1300		
Caution:	If the closed-loop torque control is not activated (p1300) and a change is made to closed-loop torque control (p1501), OFF1 (p0840) does not have its own braking response but pulse cancellation when standstill is detected (p1226, p1227).		
Note:	0 signal: Closed-loop speed control 1 signal: Closed-loop torque control		
p1501[0...n]	BI: Changeover velocity/force control / Changeov n/F_ctrl		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2520, 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for toggling between velocity and force control.		
Dependency:	The input connectors to enter the force are provided using p1511, p1512 and p1513. Refer to: p1300		
Caution:	If the closed-loop force control is not activated (p1300) and a change is made to closed-loop force control (p1501), OFF1 (p0840) does not have its own braking response but pulse cancellation when standstill is detected (p1226, p1227).		
Note:	0 signal: Velocity control 1 signal: Force control		
p1503[0...n]	CI: Torque setpoint / M_set		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the torque setpoint for torque control.		
Note:	A change is made to closed-loop torque control if, in p1300, closed-loop torque control was selected or if the selection was made using the changeover source in p1501. it is also possible to change over in operation using p1501.		

r1508	CO: Torque setpoint before supplementary torque / M_set bef. M_suppl		
VECTOR (n/M)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 6060, 6722
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque setpoint before entering the supplementary torque. For closed-loop speed control, r1508 corresponds to the speed controller output; for closed-loop torque control, r1508 corresponds to the torque setpoint of the signal source assigned in p1503.		
r1509	CO: Torque setpoint before torque limiting / M_set before M_lim		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1590, 5060, 5610
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the total torque setpoint before the torque limiting (sum from the controller output, supplementary torque and if required, the precontrol torque, sensorless operation). In the closed-loop speed controlled mode, p1509 = p1480 + r1515 + pre-controlled torque, sensorless operation. p1509 and p1515 are identical for the closed-loop torque control.		
r1509	CO: Force setpoint before force limiting / F_set before F_lim		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1590, 5060, 5610
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the total torque setpoint before the force limiting (sum from the controller output, supplementary force and if required, the precontrol force, sensorless operation). In the closed-loop speed controlled mode, p1509 = p1480 + r1515 + precontrol force, sensorless operation. p1509 and p1515 are identical for the closed-loop force control.		
p1511[0...n]	CI: Supplementary torque 1 / M_suppl 1		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for supplementary torque 1.		

p1511[0...n]	CI: Supplementary force 1 / F_suppl 1		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for supplementary force 1.		
p1512[0...n]	CI: Supplementary torque 1 scaling / M_suppl 1 scal		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for scaling the supplementary torque 1.		
p1512[0...n]	CI: Supplementary force 1 scaling / F_suppl 1 scal		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for scaling the supplementary force 1.		
p1513[0...n]	CI: Supplementary torque 2 / M_suppl 2		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for supplementary torque 2.		
p1513[0...n]	CI: Supplementary force 2 / F_suppl 2		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5060, 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for supplementary force 2.		


p1514[0...n]	Supplementary torque 2 scaling / M_suppl 2 scal	
VECTOR (n/M)	Can be changed: U, T	Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180
	P-Group: Closed-loop control	Units group: -
	Min -2000.0 [%]	Max 2000.0 [%]
		Function diagram: 6060
		Unit selection: -
		Factory setting 100.0 [%]
Description:	Sets the scaling for supplementary torque 2.	


r1515	Supplementary torque total / M_suppl total	
SERVO, VECTOR (n/M)	Can be changed: -	Access level: 2
	Data type: Floating Point	Dynamic index: -
	P-Group: Closed-loop control	Units group: 7_1
	Min - [Nm]	Max - [Nm]
		Function diagram: 5040, 5060
		Unit selection: p0505
		Factory setting - [Nm]
Description:	Displays the total supplementary torque. The displayed value is the sum of supplementary torque values 1 and 2 (refer to p1511, p1512, p1513, p1514).	


r1515	Supplementary force, total / F_suppl total	
SERVO (Lin)	Can be changed: -	Access level: 2
	Data type: Floating Point	Dynamic index: -
	P-Group: Closed-loop control	Units group: 8_1
	Min - [N]	Max - [N]
		Function diagram: 5040, 5060
		Unit selection: p0505
		Factory setting - [N]
Description:	Displays the total supplementary force. The displayed value is the sum of supplementary forces 1 and 2 ($p1515 = p1511 * p1512 + p1513$).	




r1516	Supplementary and accelerating torque / M_suppl + M_accel	
VECTOR (n/M)	Can be changed: -	Access level: 2
	Data type: Floating Point	Dynamic index: -
	P-Group: Closed-loop control	Units group: 7_1
	Min - [Nm]	Max - [Nm]
		Function diagram: 5060
		Unit selection: p0505
		Factory setting - [Nm]
Description:	Displays the total supplementary torque and the accelerating torque. The displayed value is the sum of the smoothed supplementary torque and the accelerating torque ($p1516 = p1518[1] + p1515$).	

p1517[0...n]	Accelerating torque smoothing time constant / M_accel T_smooth	
SERVO, VECTOR (n/M)	Can be changed: U, T	Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180
	P-Group: Closed-loop control	Units group: -
	Min 0.00 [ms]	Max 100.00 [ms]
		Function diagram: 5210
		Unit selection: -
		Factory setting 4.00 [ms]
Description:	Sets the smoothing time constant of the accelerating torque.	
Note:	For servo drives, the parameter is only effective in sensorless operation. For vector drives, the acceleration pre-control is inhibited if the smoothing is set to the maximum value.	

p1517[0...n]	Acceleration force smoothing time constant / F_accel T_smooth		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5210
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100.00 [ms]	Factory setting 4.00 [ms]
Description:	Sets the smoothing time constant of the accelerating force.		
Note:	For servo drives, the parameter is only effective in sensorless operation.		
r1518[0...1]	CO: Accelerating torque / M_accel		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6060
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the accelerating torque for pre-control of the speed controller.		
Index:	[0] = Unsmoothed [1] = Smoothed		
Dependency:	Refer to: p0341, p0342, p1496		
p1520[0...n]	CO: Torque limit, upper/motoring / M_max upper/mot		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min -1000000.00 [Nm]	Max 10000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the fixed upper torque limit or the torque limit when motoring.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating The factory setting depends on p0500. p0500 = 101 --> set to the maximum value Otherwise --> set to the rated value Refer to: p1521, p1522, p1523, p1532, r1538, r1539		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Negative values when setting the upper torque limit (p1520 < 0) can result in the motor accelerating in an uncontrollable fashion.		
			
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	For vector drives (refer to p0107): The torque limit is limited to 400% of the rated motor torque. When automatically calculating the motor/closed-loop control parameters (refer to p0340), the torque limit is set so that it matches the current limit p0640.		




p1520[0...n]	CO: Force limit upper/motoring / F_max upper/mot	
SERVO (Lin)	Can be changed: U, T	Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180
	P-Group: Closed-loop control	Units group: 8_1
	Min -1000000.00 [N]	Max 10000000.00 [N]
Description:	Sets the fixed upper or force limit when motoring.	
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating The factory setting depends on p0500. p0500 = 101 --> set to the maximum value Otherwise --> set to the rated value Refer to: p1521, p1522, p1523, p1532, r1538, r1539 For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Negative values when setting the upper torque limit (p1520 < 0) can result in the motor accelerating in an uncontrollable fashion.	
Danger:		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.	
Note:	For vector drives (refer to p0107): The torque limit is limited to 400% of the rated motor torque. When automatically calculating the motor/closed-loop control parameters (refer to p0340), the torque limit is set so that it matches the current limit p0640.	


p1521[0...n]	CO: Torque limit, lower/regenerative / M_max lower/regen	
SERVO, VECTOR (n/M)	Can be changed: U, T	Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180
	P-Group: Closed-loop control	Units group: 7_1
	Min -1000000.00 [Nm]	Max 10000000.00 [Nm]
Description:	Sets the fixed lower torque limit or the torque limit when regenerating.	
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating The factory setting depends on p0500. p0500 = 101 --> set to the maximum value Otherwise --> set to the rated value Refer to: p1520, p1522, p1523, p1532	
Danger:		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.	
Note:	For vector drives (refer to p0107): The torque limit is limited to 400% of the rated motor torque. When automatically calculating the motor/closed-loop control parameters (refer to p0340), the torque limit is set so that it matches the current limit p0640.	


p1521[0...n]	CO: Force limit, lower/regenerative / F_max lower/regen		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point		Function diagram: 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 10000000.00 [N]	Factory setting 0.00 [N]
Description:	Sets the fixed lower or force limit when regenerating.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating The factory setting depends on p0500. p0500 = 101 --> set to the maximum value Otherwise --> set to the rated value Refer to: p1520, p1522, p1523, p1532		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Positive values when setting the lower torque limit (p1521 < 0) can result in the motor accelerating in an uncontrollable fashion.		
			
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	For vector drives (refer to p0107): The torque limit is limited to 400% of the rated motor torque. When automatically calculating the motor/closed-loop control parameters (refer to p0340), the torque limit is set so that it matches the current limit p0640.		
p1522[0...n]	CI: Torque limit, upper/motoring / M_max upper/mot		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1610, 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1520[0]
Description:	Sets the signal source for the upper or torque/force limit when motoring.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating Refer to: p1520, p1521, p1523, p1532		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Negative values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			
p1523[0...n]	CI: Torque limit, lower/regenerative / M_max lower/regen		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1610, 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1521[0]
Description:	Sets the signal source for the lower or torque/force limit when regenerating.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating Refer to: p1520, p1521, p1522, p1532		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Positive values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			


p1524[0...n]	CO: Torque limit, upper/motoring, scaling / M_max up/mot scal		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -2000.0 [%]	Max 2000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling for the upper torque limit or the torque limit when motoring.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	This parameter can be freely interconnected. The value has the above significance if it is interconnected from connector input p1528.		
p1524[0...n]	CO: Force limit upper/motoring scaling / F_max up/mot scal		
SERVO (Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -2000.0 [%]	Max 2000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling for the upper force limit or the force limit when motoring.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	This parameter can be freely interconnected. The value has the above significance if it is interconnected from connector input p1528.		
p1525[0...n]	CO: Torque limit, lower/regenerating scaling / M_max low/gen scal		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -2000.0 [%]	Max 2000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling for the lower torque limit or the torque limit when regenerating.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	This parameter can be freely interconnected. The value has the above significance if it is interconnected from connector input p1528.		

p1525[0...n]	CO: Force limit, lower/regenerative scaling / F_max low/gen scal		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5620, 5630, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -2000.0 [%]	Max 2000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling for the lower for limit or the force limit when regenerating.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	This parameter can be freely interconnected. The value has the above significance if it is interconnected from connector input p1528.		
r1526	Torque limit, upper/motoring without offset / M_max up. w/o offs		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5620, 5630, 6630, 6640
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the upper torque limit of all torque limits without offset.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating Refer to: p1520, p1521, p1522, p1523, p1528, p1529		
r1526	Force limit, upper/motoring without offset / F_max up. w/o offs		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5620, 5630, 6630, 6640
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the upper force limit of all force limits without offset.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating Refer to: p1520, p1521, p1522, p1523, p1528, p1529		
r1527	Torque limit, lower/regenerative without offset / M_max low w/o offs		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5620, 5630, 6630, 6640
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the lower torque limit of all torque limits without offset.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating Refer to: p1520, p1521, p1522, p1523, p1528, p1529		

r1527	Force limit, lower/regenerative without offset / F_max low w/o offs		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 5620, 5630, 6630, 6640
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the lower force limit of all force limits without offset.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating Refer to: p1520, p1521, p1522, p1523, p1528, p1529		
p1528[0...n]	CI: Torque limit, upper/motoring, scaling / M_max up/mot scal		
SERVO	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1610, 5620, 5630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1524[0]
Description:	Sets the signal source for the scaling of the upper or motoring torque limit in p1522.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Negative values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			
p1528[0...n]	CI: Force limit upper/motoring scaling / F_max up/mot scal		
SERVO (Lin)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 1610, 5620, 5630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1524[0]
Description:	Sets the signal source for the scaling of the upper or motoring force limit in p1522.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Negative values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			
p1528[0...n]	CI: Torque limit upper scaling / M_max upper scal		
VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1524[0]
Description:	Sets the signal source for the scaling of the upper torque limit in p1522.		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Negative values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			

p1529[0...n]	CI: Torque limit, lower/regenerating scaling / M_max low/gen scal		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 1610, 5620, 5630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1525[0]
Description:	Sets the signal source for the scaling of the lower torque limit or the regenerative torque limit in p1523.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Positive values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			

p1529[0...n]	CI: Force limit, lower/regenerative scaling / F_max low/gen scal		
SERVO (Lin)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 1610, 5620, 5630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1525[0]
Description:	Sets the signal source for the scaling of the lower force limit or the regenerative force limit in p1523.		
Dependency:	p1400 bit 4 = 0: Upper / lower p1400 bit 4 = 1: Motoring / generating		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Positive values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			

p1529[0...n]	CI: Torque limit lower scaling / M_max lower scal		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1525[0]
Description:	Sets the signal source for the scaling of the lower torque limit in p1523.		
Danger:	For p1400.4 = 0 (torque limiting, upper/lower) the following applies: Positive values. that are obtained as a result of the signal source and the scaling can cause the motor to accelerate in an uncontrollable fashion.		
			

p1530[0...n]	Power limit, motoring / P_max mot		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 2 Function diagram: 5640, 6640
	P-Group: Closed-loop control	Units group: 14_5	Unit selection: p0505
	Min 0.00 [kW]	Max 100000.00 [kW]	Factory setting 0.00 [kW]
Description:	Sets the power limit when motoring.		
Dependency:	The factory setting depends on p0500. p0500 = 101 --> set to the maximum value Otherwise --> set to the rated value Refer to: p1531		
Note:	For vector drives (refer to p0107): The power limit is limited to 300% rated motor power.		
p1531[0...n]	Power limit, regenerating / P_max gen		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 2 Function diagram: 5640, 6640
	P-Group: Closed-loop control	Units group: 14_5	Unit selection: p0505
	Min -100000.00 [kW]	Max -0.01 [kW]	Factory setting -0.01 [kW]
Description:	Sets the regenerative power limit.		
Dependency:	The factory setting depends on p0500. p0500 = 101 --> set to the maximum value Otherwise --> set to the rated value Refer to: p1530		
Note:	For vector drives (refer to p0107): The power limit is limited to 300% rated motor power.		
p1532[0...n]	CO: Torque limit, offset / M_max offset		
SERVO	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 3 Function diagram: 5620, 5630, 8012
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min -100000.00 [Nm]	Max 100000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the torque offset for the torque limit.		
Dependency:	Refer to: p1520, p1521, p1522, p1523, p1528, p1529		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p1532[0...n]	CO: Force offset, force limit / F_max offset		
SERVO (Lin)	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 3 Function diagram: 5620, 5630, 8012
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min -100000.00 [N]	Max 100000.00 [N]	Factory setting 0.00 [N]
Description:	Sets the force offset for the force limit.		
Dependency:	Refer to: p1520, p1521, p1522, p1523, p1528, p1529		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

r1533	Current limit, torque-generating, total / Iq_max total		
SERVO, VECTOR (n/M)	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 5640, 5722, 6640
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the maximum torque/force generating current as a result if all current limits.		
r1534	CO: Torque limit, upper total / M_max upper total		
SERVO	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 1610, 5620, 5630, 5640
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the upper torque limit of all torque limits.		
Dependency:	Refer to: p1520, p1521, p1522, p1523, p1528, p1529, p1532		
r1534	CO: Force limit, upper, total / F_max upper total		
SERVO (Lin)	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 1610, 5620, 5630, 5640
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the upper force limit of all force limits.		
Dependency:	Refer to: p1520, p1521, p1522, p1523, p1528, p1529, p1532		
r1535	CO: Torque limit, lower total / M_max lower total		
SERVO	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 1610, 5620, 5630, 5640
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the lower torque limit of all torque limits.		
Dependency:	Refer to: p1520, p1521, p1522, p1523, p1528, p1529, p1532		
r1535	CO: Force limit, lower, total / F_max lower total		
SERVO (Lin)	Can be changed: - Data type: Floating Point	Dynamic index: -	Access level: 3 Function diagram: 1610, 5620, 5630, 5640
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the lower force limit of all force limits.		
Dependency:	Refer to: p1520, p1521, p1522, p1523, p1528, p1529, p1532		

r1536	Torque limit, torque-generating, maximum / Isq_max		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6640, 6710
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the maximum limit for the torque-generating current component.		
r1537	Torque limit, torque-generating, minimum / Isq_min		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6640, 6710
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the minimum limit for the torque-generating current component.		
r1538	CO: Upper effective torque limit / M_max upper eff		
SERVO, VECTOR (n/M)	Can be changed: -	Access level: 2	
	Data type: Floating Point	Dynamic index: -	Function diagram: 1590, 1610, 1750, 5610, 5650, 5714, 6040, 6060, 6640, 8012
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the actually effective upper torque limit.		
Note:	The effective upper torque limit is reduced with respect to the upper torque limit p1520, if the current limit p0640 is reduced or the rated magnetizing current of the induction motor p0320 is increased. For vector drives (refer to p0107), this is possibly the case for rotating measurements (refer to p1960). The torque limit p1520 can be re-calculated using p0340 = 1, 3 or 5.		
r1538	CO: Upper force limit effective / F_max upper eff		
SERVO (Lin)	Can be changed: -	Access level: 2	
	Data type: Floating Point	Dynamic index: -	Function diagram: 1590, 1610, 1750, 5610, 5650, 5714, 6040, 6060, 6640, 8012
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the actually effective upper force limit.		
Note:	The effective, upper force limit is reduced with respect to the selected upper force limit p1520 if the current limit p0640 is reduced. The force limit p1520 can be re-calculated using p0340 = 1, 3 or 5.		

r1539	CO: Lower effective torque limit / M_max lower eff		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 1590, 1610, 1750, 5610, 5650, 5714, 6040, 6060, 6640, 8012
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the actually effective lower torque limit.		
Note:	The effective lower torque limit is reduced with respect to the selected lower torque limit p1521 if the current limit p0640 is reduced or the rated magnetizing current of the induction motor p0320 is increased. For vector drives (refer to p0107), this is possibly the case for rotating measurements (refer to p1960). The torque limit p1520 can be re-calculated using p0340 = 1, 3 or 5.		
r1539	CO: Lower force limit effective / F_max lower eff		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 1590, 1610, 1750, 5610, 5650, 5714, 6040, 6060, 6640, 8012
	P-Group: Closed-loop control	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the actually effective lower force limit.		
Note:	The effective, lower force limit is reduced with respect to the selected lower force limit p1521 if the current limit p0640 is reduced. The force limit p1520 can be re-calculated using p0340 = 1, 3 or 5.		
p1540[0...n]	CI: Torque limit, speed controller upper scaling / M_max n-ctr upScal		
VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the scaling of the upper torque limiting to limit the speed controller output.		
p1541[0...n]	CI: Torque limit. speed controller lower scaling / M_max nctr lowScal		
VECTOR (n/M)	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the scaling of the lower torque limiting to limit the speed controller output.		
p1542[0...n]	CI: Travel to a fixed endstop, torque reduction / TfS M_red		
SERVO	Can be changed: T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 5610
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the torque/force reduction when traversing to a fixed endstop. This value is converted into a factor and is interconnected to the scaling of the torque/force limits.		
Dependency:	Refer to: p1528, p1529, r1543, p1544, p1545		

r1543	CO: Travel to fixed stop, torque scaling / TfS M scal		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5610
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the internally converted factor to interconnect to the scaling of the torque/force limits.		
Dependency:	Refer to: p1528, p1529, p1542, p1544, p1545		
p1544	Travel to fixed stop evaluation, torque reduction / TfS M_red eval		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5610
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [%]	Max 65535 [%]	Factory setting 100 [%]
Description:	Sets the evaluation for the torque/force reduction when traversing to a fixed endstop.		
Dependency:	Refer to: p1528, p1529, p1542, r1543, p1545		
Note:	4000 hex (16384 dec) in the MOMRED control word corresponds to a reduction by the percentage specified in this parameter.		
p1545[0...n]	BI: Activates travel to a fixed endstop / TfS activation		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2444, 2520
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to activate/de-activate the "travel to fixed stop" function 1: Travel to fixed stop is active 0: Travel to fixed stop is inactive		
Dependency:	Refer to: p1542, r1543, p1544		
p1546	Speed threshold, motoring/regenerating / n_thresh mot/regen		
SERVO	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 20.0 [1/min]
Description:	Sets the speed threshold for the motoring/regenerating limit. For speeds where the absolute value is less than p1546, then the following applies: - For p1400.13 = 0: Motoring limit (speed threshold is compared to the speed actual value). - For p1400.13 = 1: Regenerative limiting (speed threshold is compared to the speed setpoint).		

p1546	Velocity threshold motoring/regenerating / v_thresh mot/regen		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 0.2 [m/min]
Description:	Sets the velocity threshold for the motoring/regenerating limit. For velocities where the absolute value is less than p1546, then the following applies: - For p1400.13 = 0: Motoring limit (velocity threshold is compared to the velocity actual value). - For p1400.13 = 1: Regenerative limiting (velocity threshold is compared to the velocity setpoint).		
r1547[0...1]	Torque limit for speed controller output / M_max outp n_ctrl		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque limit to limit the speed controller output.		
Index:	[0] = Upper limit [1] = Lower limit		
r1548[0...1]	Stall current limit, torque-generating, maximum / Isq_max stall		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the limit for the torque-generating current component using the stall calculation, the current limit of the Motor Module as well as the parameterization in p0640.		
Index:	[0] = Upper limit [1] = Lower limit		
p1550[0...n]	BI: Transfer actual torque as torque offset / Accept act. torque		
SERVO	Can be changed: T		Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 9718.23
Description:	For a positive edge, the actual torque (r0079[0]) at this instant in time is used instead of the torque offset from p1532 as long as p1550 remains at 1.		

p1551[0...n]	BI: Torque limit, variable/fixed signal source / M_lim var/fixS_src		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 5620, 5630, 6060, 6630
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source to change over the torque limits between variable and fixed torque limit. 1 signal from BI: p1551: The variable torque limit applies (fixed torque limit + scaling). 0 signal from BI: p1551: The fixed torque limit applies. Example: In order that for a fast stop (OFF3) the fixed torque limit is effective, BI: p1551 must be interconnected to r0899.5.		
p1552[0...n]	CI: Torque limit, upper scaling without offset / M_max up offs scal		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the scaling of the upper torque limiting to limit the speed controller output without taking into account the current and power limits.		
p1554[0...n]	CI: Torque limit, lower scaling without offset / M_max low offsScal		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6060
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the scaling of the lower torque limiting to limit the speed controller output without taking into account the current and power limits.		
p1555[0...n]	CI: Power limit / P_max		
VECTOR (n/M)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6640
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the motoring and negative regenerative power limit.		
Dependency:	Refer to: p1530, p1531		
Note:	The resulting power limit when motoring is the minimum from p1530 and the signal that is read-in, the resulting regenerative power limit is the maximum from p1531 and the negative signal that is read-in.		

p1556[0...n]	Power limit scaling / P_max_scale		
VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6640
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00	Max 340.28235E36	Factory setting 0.00
Description:	Sets the scaling of the signal source for the motoring and negative regenerative power limit. 0 signifies no power limiting.		
p1569[0...n]	Cl: Supplementary torque 3 / M_suppl 3		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7010
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 3841[0]
Description:	Sets the signal source for supplementary torque 3.		
Dependency:	Refer to: p3842		
Notice:	The signal input is after the torque limit (refer to r1538, r1539). For vector drives, the signals that are entered are only limited by the current and power limits.		
Note:	The signal input is preferably used to enter the friction characteristic. The friction compensation is also effective if the speed controller output reaches its torque limits, but the current limits have still not been reached (this only applies to vector drives).		
p1570[0...n]	CO: Flux setpoint / Flux setpoint		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 50.0 [%]	Max 200.0 [%]	Factory setting 100.0 [%]
Description:	Sets the flux setpoint referred to rated motor flux.		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	For p1570 > 100 %, the flux setpoint increases as a function of the load from 100 % (no-load operation) to the setting in p1570 (above rated motor torque).		
p1572[0...n]	Supplementary flux setpoint / Suppl flux setp		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 100.0 [%]	Factory setting 0.0 [%]
Description:	Sets the supplementary flux setpoint for the flux controller. The value is referred to the rated motor flux.		
Notice:	The parameter should be set back to 0% again for normal closed-loop control operation.		
Note:	The parameter is used to optimize the flux controller. The current model is not influenced by the setting.		

p1574[0...n]	Voltage reserve dynamic / U_reserve dyn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6723, 6724
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min 0.0 [Veff]	Max 150.0 [Veff]	Factory setting 10.0 [Veff]
Description:	Sets a dynamic voltage reserve.		
Note:	In the field weakening range, it must be expected that the control dynamic performance is somewhat restricted due to the limited possibilities of controlling/adjusting the voltage. This can be improved by increasing the voltage margin (reserve). Increasing the reserve reduces the steady-state maximum output voltage (r0071).		
p1576[0...n]	Flux boost, adaptation speed, lower / Flux boost n lower		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the lower adaptation speed of the flux boost. Below this speed, p1570 is set as reference (setpoint) flux.		
p1577[0...n]	Flux boost adaptation speed, upper / Flux boost n upper		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 100.0 [1/min]	Max 10000.0 [1/min]	Factory setting 200.0 [1/min]
Description:	Sets the upper adaptation speed of the flux boost. Above this speed, the rated motor flux (100%) is set as reference (setpoint) flux.		
Dependency:	The parameter value refers to the lower adaptation speed of the flux boost. Refer to: p1576		
p1580[0...n]	Efficiency optimization / Efficiency opt.		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [%]	Max 100 [%]	Factory setting 0 [%]
Description:	Sets the efficiency optimization. When optimizing the efficiency, the flux setpoint of the closed-loop control is adapted as a function of the load. For p1580 = 100 %, under no-load operating conditions, the flux setpoint is reduced to 50 % of the rated motor flux.		
Note:	It only makes sense to activate this function if the dynamic response requirements of the speed controller are low. In order to avoid oscillations, if required, the speed controller parameters should be adapted (increase Zn, reduce Kp). Further, the smoothing time of the flux setpoint filter (p1582) should be increased.		

p1582[0...n]	Flux setpoint smoothing time / Flux setp T_smth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 4 [ms]	Max 5000 [ms]	Factory setting 15 [ms]
Description:	Sets the smoothing time for the flux setpoint.		
r1583	Flux setpoint smoothed / Flux setp smooth		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6722, 6723
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the smoothed flux setpoint. The value is referred to the rated motor flux.		
p1584[0...n]	Field weakening operation, flux setpoint smoothing time / Field weak T_smth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [ms]	Max 20000 [ms]	Factory setting 0 [ms]
Description:	Sets the smoothing time for the flux setpoint in the field-weakening range		
Recommendation:	Smoothing should be especially used if there is no regenerative feedback into the line supply. This means that the DC link voltage can quickly increase in regenerative operation		
Note:	Only the flux setpoint rise is smoothed		
p1585[0...n]	Flux actual value, smoothing time / Flux actVal T_smth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 0 [ms]
Description:	Sets the smoothing time for the flux actual value.		
r1589	Field-weakening current, pre-control value / FieldWkCurrPrectrl		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6724
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the pre-control value for the field weakening current.		

p1590[0...n]	Flux controller P gain / Flux controller Kp		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [A/Vs]	Max 999999.0 [A/Vs]	Factory setting 10.0 [A/Vs]
Description:	Sets the proportional gain of the flux controller.		
Note:	For synchronous motors, this parameters has no effect. The value is automatically pre-assigned dependent on the motor when the drive system is first commissioned. When calculating controller parameter (p0340 = 4), this value is re-calculated.		

p1590[0...n]	Flux controller P gain / Flux controller Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0	Max 999999.0	Factory setting 10.0
Description:	Sets the proportional gain of the flux controller.		
Note:	The value is automatically pre-assigned dependent on the motor when the drive system is first commissioned. When calculating controller parameter (p0340 = 4), this value is re-calculated.		

p1592[0...n]	Flux controller integral.action time / Flux controller Tn		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [ms]	Max 10000 [ms]	Factory setting 30 [ms]
Description:	Sets the integral time of the flux controller.		
Note:	For synchronous motors, this parameters has no effect. The value is automatically pre-assigned dependent on the motor when the drive system is first commissioned. When calculating controller parameter (p0340 = 4), this value is re-calculated.		

p1592[0...n]	Flux controller integral.action time / Flux controller Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [ms]	Max 10000 [ms]	Factory setting 30 [ms]
Description:	Sets the integral time of the flux controller.		
Note:	The value is automatically pre-assigned dependent on the motor when the drive system is first commissioned. When calculating controller parameter (p0340 = 4), this value is re-calculated.		

r1593[0...1]	Field weakening/flux controller output / Field flx_ctr outp		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6724, 6726
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the output of the field weakening controller or the output of the flux controller for separately-excited synchronous motors (FEM).		
Index:	[0] = PI output [1] = I output		
p1594[0...n]	Field-weakening controller, P gain / Field_ctrl Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6724
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00	Max 1000.00	Factory setting 0.00
Description:	Sets the P gain of the field-weakening controller.		
p1596[0...n]	Field weakening controller integral-action time / Field_ctrl Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6723, 6724
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10 [ms]	Max 10000 [ms]	Factory setting 50 [ms]
Description:	Sets the integral-action time of the field-weakening controller.		
r1597	Field weakening controller output / Field_ctrl output		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6723
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the output of the field weakening controller. The value is referred to the rated motor flux.		
r1598	CO: Total flux setpoint / Flux setpt total		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6714, 6723
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the effective flux setpoint. The value is referred to the rated motor flux.		

p1599[0...n]	Flux controller, excitation current difference / Flux ctr I_excDiff		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 100.0 [%]	Factory setting 3.0 [%]
Description:	Sets the permissible difference between the actual excitation current and the excitation current setpoint. The excitation current flux controller is active within this difference. If the difference lies outside the specified limit value, then the I component of the excitation current flux controller is kept. Instead of this, for the flux controller of the field-generating current, an additional I controller is switched-in (integral time according to p1592). If the difference again lies within the bandwidth, the I component of the excitation current flux controller is re-activated and the I component of the flux controller of the field-generating current is reduced as an exponential function with respect to time. The reduction of the I component over time depends on the rotor time constant (r0384).		
p1600[0...n]	P flux controller, P gain / P flux ctrl Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0	Max 999999.0	Factory setting 10.0
Description:	Sets the proportional gain of the P flux controller for separately-excited synchronous motors.		
Note:	The value is automatically pre-assigned dependent on the motor when the drive system is first commissioned. When calculating controller parameter (p0340 = 4), this value is re-calculated.		
r1602	Flux controller P output / Flux ctrl P output		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the output of the P flux controller for separately-excited synchronous motors (FEM).		
p1609[0...n]	Current setpoint for I/f operation / I_set I/f oper		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the stator current setpoint for operation of separately-excited synchronous motors (FEM) in the operating mode I/f (p1300 = 18).		

p1610[0...n]	Torque setpoint static (SLVC) / M_set static		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 50.0 [%]
Description:	Sets the static torque setpoint for sensorless vector control (SLVC). This parameter is entered as a percentage referred to the rated motor torque (r0333). For sensorless closed-loop vector control, when the motor model is shut down, an absolute current is impressed. p1610 represents the maximum load that occurs at a constant setpoint speed.		
Notice:	p1610 should always be set to at least 10 % higher than the maximum steady-state load that can occur.		
Note:	For p1610 = 0%, a current setpoint is calculated that corresponds to the no-load case (rated magnetizing current). For p1610 = 100 %, a current setpoint is calculated that corresponds to the rated motor torque.		
p1611[0...n]	Supplementary accelerating torque (SLVC) / M_suppl_accel		
VECTOR (n/M)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 0.0 [%]
Description:	Enters the dynamic torque setpoint for the low-speed range for sensorless vector control (SLVC). This parameter is entered as a percentage referred to the rated motor torque (r0333).		
Note:	When accelerating and braking p1611 is added to p1610 and the resulting total torque is converted into an appropriate current setpoint and controlled. For pure accelerating torques, it is always favorable to use the torque precontrol of the speed controller (p1496).		
p1612[0...n]	Current setpoint, open-loop control, sensorless / I_setCtrSensorless		
SERVO	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the current setpoint for controlled (open-loop) sensorless operation.		
p1616[0...n]	Current setpoint smoothing time / I_set T_smooth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6722
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 4 [ms]	Max 10000 [ms]	Factory setting 40 [ms]
Description:	Sets the smoothing time for the current setpoint. The current setpoint is generated from p1610 and p1611.		
Note:	This parameter is only effective in the range where current is impressed for sensorless vector control.		
r1618	Current model controller, pre-control / I_mod_ctr pre-ctr		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the pre-control value of the current model controller. It involves a magnetizing current in the de-direction.		

p1619[0...n]	Setpoint/actual value tracking threshold / SetAct track thrsh		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min 0.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Threshold for setpoint - actual value tracking of the stator current in the q direction of the current model.		
p1620[0...n]	Stator current, minimum / I_stator min		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min -10000.00 [Aeff]	Max 10000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets the minimum stator current for separately-excited synchronous motors (FEM). A negative value means that the field-generating stator current (d-axis) has a negative sign. The valid value is internally limited to 50% of the rated motor current (p0305).		
p1621[0...n]	Changeover speed, inner cos phi = 1 / n_chngov cos phi=1		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the speed where a change is made from the inner to the outer cos phi = 1. If the value that is entered exceeds the rated speed, then a change is made to the inner cos phi = 1 over the complete speed range.		
p1622[0...n]	Field-generating current setpoint smoothing time constant / Id_setp T_smth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.1 [ms]	Max 200.0 [ms]	Factory setting 20.0 [ms]
Description:	Sets the smoothing time constant for the setpoint of the field-generating current components. The current filtered in this way is included in the calculation of the cos phi.		
r1623	Field-generating current setpoint (steady-state) / Id_set stationary		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 6723
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the steady-state field generating current setpoint (Id_set).		

r1624	Field-generating current setpoint, total / Id_setp total		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 4
	Data type: Floating Point		Function diagram: 6640, 6723, 6724, 6727
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the limited field-generating current setpoint (Id_set). This value comprises the steady-state field-generating current setpoint r1623 and a dynamic component that is only set when changes are made to the flux setpoint.		
p1625[0...n]	Excitation current setpoint calibration / I_exc_setp cal		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10.0 [%]	Max 200.0 [%]	Factory setting 100.0 [%]
Description:	Gain factor to weight the excitation current setpoint.		
r1626	CO: Excitation current setpoint / I_exc_set		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the calculated excitation current setpoint.		
Dependency:	Refer to: p0390		
r1627	Current model load angle / I_mod load angle		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the load angle of the current model.		
p1628[0...n]	Current model controller, dynamic factor / I_mod_ctr dyn_fact		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 6727
	P-Group: Functions	Units group: -	Unit selection: -
	Min 1 [%]	Max 400 [%]	Factory setting 50 [%]
Description:	Dynamic factor of the model controller in the current model		

p1629[0...n]	Current model controller P gain / I_mod_ctrl Kp		
VECTOR (n/M)	Can be changed: U, T	Access level: 4	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 100000.000	Factory setting 0.000
Description:	Sets the proportional gain of the current model controller. This value is automatically preset using p3900 or p0340 when commissioning has been completed.		
p1630[0...n]	Current model controller integral time / I_ctrl Tn		
VECTOR (n/M)	Can be changed: U, T	Access level: 4	
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the proportional gain of the current model controller. This value is automatically preset using p3900 or p0340 when commissioning has been completed.		
r1631	Current model controller, P gain effective / I_mod ctrl Kp eff		
VECTOR (n/M)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the effective P gain of the current model controller.		
r1632	Current model controller integral time effective / I_mod_ctrl Tn eff		
VECTOR (n/M)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the effective integral time of the current model controller.		
r1633	Current model, flux setpoint / I_mod flux setp		
VECTOR (n/M)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the effective flux setpoint of the current model. The value is referred to the rated motor flux.		
r1634	Current model, flux actual value / I_mod flux act val		
VECTOR (n/M)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the effective flux actual value of the current model. The value is referred to the rated motor flux.		

r1635	Current model controller, I component / I_mod_ctrl I_comp		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the I component of the current model controller.		
r1636	Current model controller output / I_mod_ctrl outp		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the output of the current model controller.		
r1637	Current model, magnetizing current, d axis / I_mod I_mag d-ax		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the magnetizing current of the current model in the d-axis.		
r1638	Current model, magnetizing current, q axis / I_mod I_mag q-ax		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the magnetizing current of the current model in the q-axis.		
r1639	Current model Isq after actual value tracking / I_mod Isq track		
VECTOR (n/M)	Can be changed: -	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: 6727
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the stator current in the q axis after current actual value tracking.		
p1640[0...n]	CI: Excitation current actual value / Excit curr act val		
VECTOR (n/M)	Can be changed: T	Access level: 3	
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 6727
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the excitation current actual value		

r1641	Excitation current actual value / I_exc_act		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 6727
	P-Group: Closed-loop control		Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the excitation current actual value that is read-in.		
Dependency:	Refer to: p0390		
p1642[0...n]	Minimum excitation current / Min I_exc		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 4
	Data type: Floating Point	Units group: -	Function diagram: 6727
	P-Group: Closed-loop control		Unit selection: -
	Min 0.1 [%]	Max 50.0 [%]	Factory setting 5.0 [%]
Description:	Sets the minimum excitation current. This means that negative excitation currents can be avoided.		
p1643[0...n]	Gain factor, minimum excitation current closed-loop control / Min I_exc Kp		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 4
	Data type: Floating Point	Units group: -	Function diagram: 6727
	P-Group: Closed-loop control		Unit selection: -
	Min 0.00	Max 5.00	Factory setting 0.40
Description:	Sets the gain factor for the minimum excitation current, closed-loop control. This is active if the excitation current is below 75% of p1642.		
Dependency:	Refer to: p1642		
r1644	Excitation current monitoring output / I_exc monit output		
VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 4
	Data type: Floating Point	Units group: 6_2	Function diagram: 6727
	P-Group: Closed-loop control		Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the output of the excitation current monitoring for separately excited synchronous motors.		
p1645[0...4]	BI: Excitation feedback signals signal source / Exc FS S_src		
VECTOR (n/M)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 6495
	P-Group: Commands		Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the individual feedback signals from the excitation.		
Index:	[0] = Excitation ready to be powered-up [1] = Excitation ready [2] = Excitation operational [3] = Excitation group signal fault [4] = Excitation group signal alarm		
Dependency:	Refer to: r1649		

p1646	Excitation monitoring time / Excit t_monit			
VECTOR (n/M)	Can be changed: T			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 6495
	P-Group: Commands	Units group: -		Unit selection: -
	Min 2.0 [s]	Max 1300.0 [s]		Factory setting 20.0 [s]
Description:	Sets the monitoring time of the excitation. After an ON command, the feedback signal must be received within this monitoring time.			
Note:	After the on command for the excitation (r1648.0 = 1), its feedback signal must be available at r1649.1 within this monitoring time (Bl: p1645[1]). The same monitoring time is effective after the excitation is enabled for operation (r1648.3 = 1) up to the feedback signal "excitation in operation" (r1649.2 = 1, Bl: p1645[2]).			
p1647	Excitation switch-out delay time / Exc t_off			
VECTOR (n/M)	Can be changed: T			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 6495
	P-Group: Commands	Units group: -		Unit selection: -
	Min 0.5 [s]	Max 5.0 [s]		Factory setting 0.8 [s]
Description:	Sets the switch-off delay time to shut-down the excitation equipment.			
Note:	The delay time starts if, when powering-down, r0863.0 = 0. r1648.0 and r1648.3 are reset at the end of the delay time.			
r1648	CO/BO: Excitation, control word / Excitation STW			
VECTOR (n/M)	Can be changed: -			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: 6495
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the control word for the excitation equipment.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Power-up excitation	Yes	No
	01	Excitation no OFF2	Yes	No
	02	Excitation no OFF3	Yes	No
	03	Enable excitation operation	Yes	No
	07	Excitation acknowledge fault	Yes	No
	10	Control from excitation equipment	Yes	No
				FP
				-
				-
				-
				-
				-
				-
				-
r1649	CO/BO: Excitation status word / Excitation ZSW			
VECTOR (n/M)	Can be changed: -			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: 6495
	P-Group: Displays, signals	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the status word of the excitation equipment.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Excitation ready to be powered-up, feedback signal	Yes	No
	01	Excitation ready feedback signal	Yes	No
	02	Excitation in operation feedback signal	Yes	No
	03	Excitation group signal fault	Yes	No
	07	Excitation, group signal alarm	Yes	No
				FP
				-
				-
				-
				-
Dependency:	Refer to: p1645			

r1650	Current setpoint torque-generating before filter / Iq_set before filt		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5710
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the torque generating current setpoint Iqset after the torque limits and the clock cycle interpolation is front of the current setpoint filters.		
r1650	Current setpoint force-generating before filter / Iq_set before filt		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 5710
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the force generating current setpoint Iqset after the force limits and the clock cycle interpolation is front of the current setpoint filters.		
r1651	CO: Torque setpoint, function generator / M_set FG		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 7_1	Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque setpoint of the function generator.		
r1651	CO: Force setpoint, function generator / F_set FG		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 8_1	Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the force setpoint of the function generator.		
p1653[0...n]	Current setpoint torque-generating minimum smoothing time / Isq_s T_smth_min		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.1 [ms]	Max 20.0 [ms]	Factory setting 0.1 [ms]
Description:	Sets the minimum smoothing time constant for the setpoint of the torque-generating current components.		
p1654[0...n]	Curr. setpoint torque-gen. smoothing time field weakening range / Isq_s T_smth FW		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.1 [ms]	Max 50.0 [ms]	Factory setting 4.8 [ms]
Description:	Sets the smoothing time constant for the setpoint of the torque-generating current components.		
Note:	The smoothing time does not become effective until the field-weakening range is reached.		

p1655[0...1]	CI: Current setpoint filter natural frequency tuning / I_set_filt f_n		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for tuning the natural frequency of the current setpoint filter.		
Index:	[0] = Filter 1 [1] = Filter 2		

p1656[0...n]	Activates current setpoint filter / I_set_filt active				
SERVO	Can be changed: U, T		Access level: 3		
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 5710		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0001 bin		
Description:	Activates current setpoint filters 1 to 4.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Filter 1	active	not active	-
	01	Filter 2	active	not active	-
	02	Filter 3	active	not active	-
	03	Filter 4	active	not active	-
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.				
Note:	If not all of the filters are required, then the filters should be used consecutively starting from filter 1.				

p1656[0...n]	Activates current setpoint filter / I_set_filt active				
VECTOR (n/M)	Can be changed: U, T		Access level: 3		
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 6710		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0001 bin		
Description:	Activates current setpoint filters 1 to 2.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Filter 1	active	not active	-
	01	Filter 2	active	not active	-
Dependency:	The current setpoint filters are parameterized with p1656 to p1666.				
Note:	If not all of the filters are required, then the filters should be used consecutively starting from filter 1.				

p1657[0...n]	Current setpoint filter 1 type / I_set_filt 1 Typ		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16		Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Sets the current setpoint filter 1 as low pass (PT2) or as extended general 2nd-order filter.		
Values:	1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
Note:	For an extended general 2nd order filter, by inserting the same natural frequency in both the numerator and in the denominator, i.e. bandstop frequency, a bandstop filter is implemented. If the numerator damping of zero is selected, the bandstop frequency is completely suppressed. The denominator damping can be determined from the equation for the 3 dB bandwidth: $f_{3dB} \text{ bandwidth} = 2 * D_{denominator} * f_{bandstop} \text{ frequency}$		
p1658[0...n]	Current setpoint filter 1 denominator natural frequency / I_set_filt 1 fn_n		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the denominator natural frequency for current setpoint filter 1 (PT2, general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1659[0...n]	Current setpoint filter 1 denominator damping / I_set_filt 1 D_n		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.001	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for current setpoint filter 1.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1660[0...n]	Current setpoint filter 1 numerator natural frequency / I_set_filt 1 fn_z		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the numerator natural frequency for current setpoint filter 1 (general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1661[0...n]	Current setpoint filter 1 numerator damping / I_set_filt 1 D_z		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 3 Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for current setpoint filter 1.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1662[0...n]	Current setpoint filter 2 type / I_set_filt 2 Typ		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Integer16	Dynamic index: DDS, p0180	Access level: 3 Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Sets the current setpoint filter 2 as low pass (PT2) or as extended general 2nd-order filter.		
Values:	1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
Note:	For an extended general 2nd order filter, by inserting the same natural frequency in both the numerator and in the denominator, i.e. bandstop frequency, a bandstop filter is implemented. If the numerator damping of zero is selected, the bandstop frequency is completely suppressed. The denominator damping can be determined from the equation for the 3 dB bandwidth: $f_{3dB} \text{ bandwidth} = 2 * D_{denominator} * f_{bandstop} \text{ frequency}$		
p1663[0...n]	Current setpoint filter 2 denominator natural frequency / I_set_filt 2 fn_n		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 3 Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the denominator natural frequency for current setpoint filter 2 (PT2, general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1664[0...n]	Current setpoint filter 2 denominator damping / I_set_filt 2 D_n		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Floating Point	Dynamic index: DDS, p0180	Access level: 3 Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.001	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for current setpoint filter 2.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1665[0...n]	Current setpoint filter 2 numerator natural frequency / I_set_filt 2 fn_z		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the numerator natural frequency for current setpoint filter 2 (general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1666[0...n]	Current setpoint filter 2 numerator damping / I_set_filt 2 D_z		
SERVO, VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710, 6710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for current setpoint filter 2.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1667[0...n]	Current setpoint filter 3 type / I_set_filt 3 Typ		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16		Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Sets the current setpoint filter 3 as low pass (PT2) or as extended general 2nd-order filter.		
Values:	1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1668[0...n]	Current setpoint filter 3 denominator natural frequency / I_set_filt 3 fn_n		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the denominator natural frequency for current setpoint filter 3 (PT2, general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1669[0...n]	Current setpoint filter 3 denominator damping / I_set_filt 3 D_n		
SERVO	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.001	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for current setpoint filter 3.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1670[0...n]	Current setpoint filter 3 numerator natural frequency / I_set_filt 3 fn_z		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the numerator natural frequency for current setpoint filter 3 (general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1671[0...n]	Current setpoint filter 3 numerator damping / I_set_filt 3 D_z		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for current setpoint filter 3.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1672[0...n]	Current setpoint filter 4 type / I_set_filt 4 Typ		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 1
Description:	Sets the current setpoint filter 4 as low pass (PT2) or as extended general 2nd-order filter.		
Values:	1: Low pass: PT2 2: General 2nd-order filter		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1673[0...n]	Current setpoint filter 4 denominator natural frequency / I_set_filt 4 fn_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the denominator natural frequency for current setpoint filter 4 (PT2, general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1674[0...n]	Current setpoint filter 4 denominator damping / I_set_filt 4 D_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.001	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for current setpoint filter 4.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		

p1675[0...n]	Current setpoint filter 4 numerator natural frequency / I_set_filt 4 fn_n		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 1999.0 [Hz]
Description:	Sets the numerator natural frequency for current setpoint filter 4 (general filter).		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1676[0...n]	Current setpoint filter 4 numerator damping / I_set_filt 4 D_z		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5710
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for current setpoint filter 4.		
Dependency:	The current setpoint filters are parameterized with p1656 to p1676.		
p1699	Filter data transfer / Filt data transfer		
SERVO, VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Activates data transfer for parameter changes for the filter. p1699 = 0: The new filter data are immediately transferred. p1699 = 1: The new filter data are only transferred when this parameter is reset.		
Dependency:	Refer to: p1414, p1415, p1416, p1417, p1418, p1419, p1420, p1421, p1422, p1423, p1424, p1425, p1426, p1656, p1657, p1658, p1659, p1660, p1661, p1662, p1663, p1664, p1665, p1666, p1667, p1668, p1669, p1670, p1671, p1672, p1673, p1674, p1675, p1676		
p1701[0...n]	Current controller reference model deadtime / I_ctrRefMod t_dead		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5714
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0	Max 1.0	Factory setting 1.0
Description:	Sets the fractional deadtime for the current controller reference model. This parameter emulates the computation deadtime of the proportionally controlled current control loop.		
Note:	Deadtime = p1701 * p0115[0]		
p1702[0...n]	Isd current controller pre-control scaling / Isd_ctr_prectrScal		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6714
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 70.0 [%]
Description:	Sets the scaling of the dynamic current controller pre-control for the flux-generating current component Isd.		

p1703[0...n]	Isq current controller pre-control scaling / Isq_ctr_prectrScal		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6714
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 70.0 [%]
Description:	Sets the scaling of the dynamic current controller pre-control for the torque/force-generating current component Isq.		
p1704[0...n]	EMF scaling of the Isq current controller pre-control / EMF scal Isq_ctrl		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling of the EMF pre-control for the Isq current controller.		
p1705[0...n]	Flux setpoint/actual value tracking threshold / Flux track thresh		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 100.0 [%]	Factory setting 100.0 [%]
Description:	Threshold for the setpoint - actual value tracking of the EMF pre-control of the Isq current controller.		
p1715[0...n]	Current controller P gain / I_ctrl Kp		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5714, 6714
	P-Group: Closed-loop control	Units group: 18_1	Unit selection: p0505
	Min 0.000 [V/A]	Max 100000.000 [V/A]	Factory setting 0.000 [V/A]
Description:	Sets the proportional gain of the current controller for the lower adaptation current range. This value is automatically preset using p3900 or p0340 when commissioning has been completed.		
Dependency:	p0391, p0392 and p0393 are only available for SERVO.		
	Refer to: p0391, p0392, p0393		
Note:	For p0393 = 100 %, the current controller adaptation is disabled and p1715 is effective over the entire range.		
p1715[0...n]	Current controller P gain / I_ctrl Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 5714, 6714
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 100000.000	Factory setting 0.000
Description:	Sets the proportional gain of the current controller for the lower adaptation current range. This value is automatically preset using p3900 or p0340 when commissioning has been completed.		
Dependency:	p0391, p0392 and p0393 are only available for SERVO.		
	Refer to: p0391, p0392, p0393		
Note:	For p0393 = 100 %, the current controller adaptation is disabled and p1715 is effective over the entire range.		

p1717[0...n]	Current controller integral-action time / I_ctrl Tn		
SERVO, VECTOR (n/M)	Can be changed: U, T Data type: Floating Point P-Group: Closed-loop control Min 0.00 [ms]	Dynamic index: DDS, p0180 Units group: - Max 1000.00 [ms]	Access level: 3 Function diagram: 5714, 6714 Unit selection: - Factory setting 2.00 [ms]
Description:	Sets the integral-action time of the current controller.		
Dependency:	Refer to: p1715		
r1718	CO: Isq controller output / Isq_ctrl outp		
VECTOR (n/M)	Can be changed: - Data type: Floating Point P-Group: Closed-loop control Min - [Veff]	Dynamic index: - Units group: 5_1 Max - [Veff]	Access level: 4 Function diagram: 6714 Unit selection: p0505 Factory setting - [Veff]
Description:	Displays the actual output of the Isq current controller (torque/force generating current, PI controller). The value contains the proportional and integral components of the PI controller.		
r1719	Isq controller integral component / Isq_ctrl I_comp		
VECTOR (n/M)	Can be changed: - Data type: Floating Point P-Group: Closed-loop control Min - [Veff]	Dynamic index: - Units group: 5_1 Max - [Veff]	Access level: 4 Function diagram: - Unit selection: p0505 Factory setting - [Veff]
Description:	Displays the integral component of the Isq current controller (torque/force-generating current, PI controller).		
r1723	CO: Isd controller output / Isd_ctrl output		
VECTOR (n/M)	Can be changed: - Data type: Floating Point P-Group: Closed-loop control Min - [Veff]	Dynamic index: - Units group: 5_1 Max - [Veff]	Access level: 4 Function diagram: 6714 Unit selection: p0505 Factory setting - [Veff]
Description:	Displays the actual output of the Isd current controller (flux-generating current, PI controller). The value contains the proportional and integral components of the PI controller.		
r1724	Isd controller integral component / Isd_ctrl I_comp		
VECTOR (n/M)	Can be changed: - Data type: Floating Point P-Group: Closed-loop control Min - [Veff]	Dynamic index: - Units group: 5_1 Max - [Veff]	Access level: 4 Function diagram: - Unit selection: p0505 Factory setting - [Veff]
Description:	Displays the integral component of the Isd current controller (flux-generating current, PI controller).		

r1725	Isd controller integral component limit / Isd_ctrl I_limit		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the limit value for the integral component of the Isd current controller.		
p1726[0...n]	Quadrature arm decoupling, scaling / Transv_decpl scal		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 75.0 [%]
Description:	Sets the scaling of the quadrature arm decoupling		
Note:	This parameter is ineffective for sensorless vector control. In this case, p1727 is always used. If p1726 is set to 0, then the quadrature de-coupling is de-activated. The integral component of the Isd current controller remains effective if the complete speed control range. For the closed-loop control of synchronous motors p1726 is used to scale the current controller de-coupling.		
p1727[0...n]	Quadrature arm decoupling at voltage limit, scaling / TrnsvDecplVmaxScal		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 200.0 [%]	Factory setting 50.0 [%]
Description:	Sets the scaling of quadrature arm decoupling when the voltage limit is reached.		
r1728	De-coupling voltage, in-line axis / U_dir-axis_decoupl		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the actual output of the quadrature channel de-coupling for the d axis.		
r1729	De-coupling voltage, quadrature axis / U_quad_decoupl		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the actual output of the quadrature channel de-coupling for the q axis.		

r1732	Direct-axis voltage setpoint / U_direct-axis_set		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1630, 5714, 6714, 5718
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the direct-axis voltage setpoint Ud.		
r1733	Quadrature-axis voltage setpoint / U_quad_set		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 1630, 5714, 5718, 6714, 6719
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the quadrature-axis component of voltage setpoint Uq.		
p1740[0...n]	Gain resonance damping for sensorless closed loop control / Gain res_damp		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.025
Description:	Defines the gain of the controller for resonance damping for operation with sensorless vector control in the range that current is impressed.		
p1744[0...n]	Motor model speed threshold stall detection / MotMod n_thr stall		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 100.00 [1/min]
Description:	Sets the speed threshold value to detect a stalled motor. If the adaptation controller output exceeds the parameterized speed difference, then bit 11 in status word p1408 is set.		
Dependency:	If a stalled drive is detected (p1408.11 set), fault 7902 is output after the delay time in p2178. Refer to: p2178		
Note:	Speed monitoring is only effective in operation with a speed encoder (refer to p1300).		
p1745[0...n]	Motor model error threshold stall detection / MotMod ThreshStall		
VECTOR (n/M)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 1000.0 [%]	Factory setting 5.0 [%]
Description:	Sets the fault threshold in order to detect a motor that has stalled. If the error signal (r1746) exceeds the parameterized error threshold, then bit 12 in status word p1408 is set.		
Dependency:	If a stalled drive is detected (p1408.12 set), fault 7902 is output after the delay time set in p2178. Refer to: p2178		
Note:	Monitoring is only effective in the low-speed range (below p1755 * p1756).		

r1746 Motor model error signal stall detection / MotMod sig stall

VECTOR (n/M)	Can be changed: -	Access level: 4
	Data type: Floating Point	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: -
	Units group: -	Unit selection: -
	Min - [%]	Max - [%]
Description:	Signal to initiate stall detection	
Note:	The signal is not calculated while magnetizing and only in the low speed range (below p1755 * p1756).	

p1750[0...n] Motor model configuration / MotMod config

VECTOR (n/M)	Can be changed: U, T	Access level: 3			
	Data type: Unsigned8	Dynamic index: DDS, p0180			
	P-Group: Closed-loop control	Function diagram: -			
	Units group: -	Unit selection: -			
	Min -	Max -			
Description:	Sets the configuration of the motor model.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Controlled start	Yes	No	-
	01	Controlled through 0 Hz	Yes	No	-
	02	Set motor model	Yes	No	-

r1751 Motor model status / MotMod status

VECTOR (n/M)	Can be changed: -	Access level: 3			
	Data type: Unsigned16	Dynamic index: -			
	P-Group: Closed-loop control	Function diagram: -			
	Units group: -	Unit selection: -			
	Min -	Max -			
Description:	Displays the status of the motor model.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Controlled operation	active	not active	-
	01	Set ramp-function generator	active	not active	-
	02	Stop RsLh adaptation	Yes	No	-
	03	Feedback	active	not active	-
	04	Encoder operation	active	not active	-
	05	Holding angle	Yes	No	-
	06	Acceleration criteria	active	not active	-
	07	Set angular integrator PEM	No	Yes	-
	08	Stop Kt adaptation PEM	No	Yes	-
	09	PollD active PEM SLVC	No	Yes	-
	10	I injection PEM	No	Yes	-
	12	Rs adapt waits	Yes	No	-
	13	Motor operation	Yes	No	-
	14	Stator frequency sign	Positive	Negative	-
	15	Torque sign	Motor mode	Regenerative mode	-

p1752[0...n] Motor model changeover speed operation with encoder / MotMod n_chgov enc

SERVO, VECTOR	Can be changed: U, T	Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180
	P-Group: Closed-loop control	Function diagram: -
	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]
Description:	Sets the speed to change over the motor model for operation with encoder.	
Dependency:	Refer to: p1756	

p1752[0...n]	Motor model with encoder changeover velocity / MotMod v_chgov enc		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 1000.0 [m/min]
Description:	Sets the velocity to change over the motor model for operation with encoder.		
Dependency:	Refer to: p1756		
p1754[0...n]	Flux angle difference smoothing time / Angle diff T_smth		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.1 [ms]	Max 100.0 [ms]	Factory setting 5.0 [ms]
Description:	Sets the smoothing time constant to filter the main flux angle difference from the voltage and current models. The filtered value is included in the calculation of the total flux angle.		
p1755[0...n]	Motor model changeover speed sensorless operation / MotMod n_chgSnsorl		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 210000.0 [1/min]
Description:	Sets the speed to change over the motor model to sensorless operation (without encoder).		
Dependency:	Refer to: p1756		
Note:	The changeover speed applies for the changeover between open-loop and closed-loop control mode.		
p1755[0...n]	Motor model changeover velocity sensorless operation / MotMod v_chgSnsorl		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 4_1	Unit selection: p0505
	Min 0.0 [m/min]	Max 1000.0 [m/min]	Factory setting 1000.0 [m/min]
Description:	Sets the velocity to change over the motor model to sensorless operation (without encoder).		
Dependency:	Refer to: p1756		
Note:	The changeover velocity applies for the changeover between open-loop and closed-loop control mode.		
p1755[0...n]	Motor model changeover speed sensorless operation / MotMod n_chgSnsorl		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min 0.0 [1/min]	Max 210000.0 [1/min]	Factory setting 210000.0 [1/min]
Description:	Sets the speed to change over the motor model to sensorless operation (without encoder).		
Dependency:	Refer to: p1756		
Notice:	The changeover speed represents the steady-state minimum speed up to which the motor model can be used in steady-state operation without encoder (sensorless operation).		
	If the stability is not adequate close to the changeover speed, it may make sense to increase the parameter value.		
Note:	The changeover speed applies for the changeover between open-loop and closed-loop control mode.		

p1756	Motor model changeover speed hysteresis / MotMod n_chgov.Hys		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 90.0 [%]	Factory setting 5.0 [%]
Description:	Sets the hysteresis for the changeover speed/velocity of the motor model.		
Dependency:	Refer to: p1752, p1755		
Note:	The value is entered relative to p1404, p1752 or p1755.		
p1757[0...n]	Motor model w/o enc. op./cl.-loop controlled stab. controller Kp / MotMod w/o enc Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.01	Max 10.00	Factory setting 0.70
Description:	Sets the gain of the transient response controller when the motor model changes over from open-loop controlled operation to closed-loop controlled operation.		
Note:	Only for ASM and PSM in sensorless operation: The settling range starts at $0.5 * p1755 * p1756$. For ASM it ends at $p1755 * p1756$ or at p1755, if p1759 is at the maximum value. For PSM it always ends at $p1755 * p1756$.		
p1758[0...n]	Motor model changeover delay time, closed/open-loop control / MotMod t_cl_op		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 100 [ms]	Max 2000 [ms]	Factory setting 1000 [ms]
Description:	Sets the minimum time for falling below the changeover speed when changing from closed-loop controlled operation to open-loop controlled operation.		
Dependency:	Refer to: p1755, p1756		
p1759[0...n]	Motor model changeover delay time open/closed loop control / MotMod t_op_cl		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [ms]	Max 2000 [ms]	Factory setting 0 [ms]
Description:	Sets the minimum time for exceeding the changeover speed when changing from open-loop controlled operation to closed-loop controlled operation.		
Dependency:	Refer to: p1755, p1756		
p1760[0...n]	Motor model with encoder speed adaptation Kp / MotMod wE n_ada Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 100000.000	Factory setting 1000.000
Description:	Sets the proportional gain of the controller for speed adaptation with encoder		

p1761[0...n]	Motor model with encoder speed adaptation Tn / MotMod wE n_ada Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 4 [ms]
Description:	Sets the integral-action time of the controller for speed adaptation with encoder		
r1762	Motor model deviation component 1 / MotMod dev comp 1		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Induction motor (ASM): Displays the referred imaginary system deviation for the adaptation circuit of the motor model. Permanent magnet synchronous motor (PEM): Displays the system deviation referred to PI for the speed adaptation.		
r1763	Motor model deviation component 2 / MotMod dev comp 2		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Induction motor (ASM): Displays the referred real system deviation for the adaptation circuit of the motor model. Permanent magnet synchronous motor (PEM): Not used.		
p1764[0...n]	Motor model without encoder speed adaptation Kp / MotMod woE n_adaKp		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6730
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 100000.000	Factory setting 1000.000
Description:	Sets the proportional gain of the controller for speed adaptation without encoder.		
r1765	Motor model, speed adaptation Kp effective / MotM n_ada Kp act		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the effective proportional gain of the controller for the speed adaptation.		

p1767[0...n]	Motor model without encoder speed adaptation Tn / MotMod woE n_adaTn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6730
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1 [ms]	Max 200 [ms]	Factory setting 4 [ms]
Description:	Sets the integral time of the controller for speed adaptation without encoder		
r1768	Motor model, speed adaptation Vi effective / MotM n_ada Vi act		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the effective gain of the integral component of the controller for speed adaptation.		
r1770	Motor model speed adaptation proportional component / MotMod n_adapt Kp		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6730
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the P component of the controller for speed adaptation.		
r1771	Motor model speed adaptation I comp. / MotMod n_adapt Tn		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6730
	P-Group: Closed-loop control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the I component of the controller for speed adaptation.		
p1774[0...n]	Motor model, offset voltage compensation alpha / MotMod offs comp A		
VECTOR (n/M)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -5.000 [V]	Max 5.000 [V]	Factory setting 0.000 [V]
Description:	Sets the offset voltage in the alpha direction; this compensates the offset voltages of the drive converter/inverter at low speeds. The value is valid for the rated (nominal) pulse frequency of the Motor Module.		
Note:	The value is pre-set during the rotating measurement.		

p1775[0...n]	Motor model, offset voltage compensation beta / MotMod offs comp B			
VECTOR (n/M)	Can be changed: U, T			Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min -5.000 [V]	Max 5.000 [V]		Factory setting 0.000 [V]
Description:	Sets the offset voltage in the beta direction; this compensates the offset voltages of the drive converter/inverter at low speeds. The value is valid for the rated (nominal) pulse frequency of the Motor Module.			
Note:	The value is pre-set during the rotating measurement.			
r1778	Motor model flux angle difference / MotMod ang. diff.			
SERVO, VECTOR (n/M)	Can be changed: -			Access level: 4
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min - [°]	Max - [°]		Factory setting - [°]
Description:	Induction motor (ASM): Displays the difference between the motor model flux angle and the transformation angle. Permanent magnet synchronous motor (PEM): Displays the difference between the motor model angle and the encoder angle.			
r1779	Motor model absolute flux / MotMod abs flux			
VECTOR (n/M)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min - [%]	Max - [%]		Factory setting - [%]
Description:	Displays the absolute value of the flux of the motor model.			
p1780[0...n]	Motor model adaptation configuration / MotMod adapt conf			
SERVO	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0010 0000 bin
Description:	Sets the configuration for the adaptation circuit of the motor model. Induction motor (ASM): Rs, Rr (only for operation with encoder), Lh and offset compensation. Permanent magnet synchronous motor (PEM): kT			
Bit field:	Bit	Signal name	1 signal	0 signal
	03	Select motor model PEM KT adaptation	Yes	No
	05	Select ASM Rr adaptation (only with encoder)	Yes	No
	07	Select T(valve) with Rs adaptation	Yes	No
	08	Compensation of voltage emulation error in the drive converter	Yes	No
Note:	ASM: Induction motor PEM: Permanent magnet synchronous motor			

p1780[0...n]		Motor/converter model adaptation configuration / MotMod adapt conf			
SERVO (Exp M_ctrl)	Can be changed: U, T			Access level: 3	
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: -	
	P-Group: Closed-loop control	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 0001 0010 1000 bin	
Description:	Sets the configuration for the adaptation circuit of the motor model. Induction motor (ASM): Rs, Rr (only for operation with encoder), Lh and offset compensation. Permanent magnet synchronous motor (PEM): kT				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	03	Select motor model PEM KT adaptation	Yes	No	-
	05	Select ASM Rr adaptation (only with encoder)	Yes	No	-
	07	Select T(valve) with Rs adaptation	Yes	No	-
	08	Compensation of voltage emulation error in the drive converter	Yes	No	-
Note:	ASM: Induction motor PEM: Permanent magnet synchronous motor - the kT adaptation is only active at a speed greater than the changeover speed with encoder (p1752). - beforehand, an identification of the voltage emulation error must be started (p1909.14=1). If the electrical configuration/structure (motor module, cabling etc.) or the pulse frequency (p1800) changes, then a new identification run must be made.				

p1780[0...n]		Motor model adaptation configuration / MotMod adapt conf			
VECTOR	Can be changed: U, T			Access level: 3	
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: -	
	P-Group: Closed-loop control	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0111 1100 bin	
Description:	Sets the configuration for the adaptation circuit of the motor model. Induction motor (ASM): Rs, Rr (only for operation with encoder), Lh and offset compensation. Permanent magnet synchronous motor (PEM): kT				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Select motor model ASM Rs adaptation	Yes	No	-
	02	Select motor model ASM Lh adaptation	Yes	No	-
	03	Select motor model PEM KT adaptation	Yes	No	-
	04	Select motor model, offset adaptation	Yes	No	-
	05	Select ASM Rr adaptation (only with encoder)	Yes	No	-
	06	Select pole wheel identification PEM sensorless	Yes	No	-
	07	Select T(valve) with Rs adaptation	Yes	No	-
Note:	ASM: Induction motor PEM: Permanent magnet synchronous motor The following applies for the vector closed-loop control type: When selecting the compensation of the valve interlocking via Rs (bit 7), the compensation in the gating unit is deactivated and is instead taken into account in the motor model.				

p1781[0...n]	Motor model ASM Rs adaptation integral time / MotMod Rs Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10 [ms]	Max 10000 [ms]	Factory setting 100 [ms]
Description:	Sets the integral time for the Rs adaptation of the motor model for an induction motor (ASM).		
r1782	Motor model ASM Rs adaptation correction value / MotMod Rs corr		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the correction value for the Rs adaptation of the motor model for an induction motor (ASM).		
p1783[0...n]	Motor model ASM Rs adaptation Kp / MotMod Rs Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 1.000	Factory setting 0.100
Description:	Sets the proportional gain for the Rs adaptation of the motor model for an induction motor (ASM).		
p1785[0...n]	Motor model ASM Lh adaptation Kp / MotMod Lh Kp		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 1.000	Factory setting 0.100
Description:	Sets the proportional gain for the Lh adaptation of the motor model for an induction motor (ASM).		
p1786[0...n]	Motor model ASM Lh adaptation integral time / MotMod Lh Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10 [ms]	Max 10000 [ms]	Factory setting 100 [ms]
Description:	Sets the integral time for the Lh adaptation of the motor model for an induction motor (ASM).		
r1787	Motor model ASM Lh adaptation correction value / MotMod Lh corr		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the correction value for the Lh adaptation of the motor model for an induction motor (ASM).		

r1789	Motor model ASM Rs adaptation switch-on frequency / MotMod Rs f_on		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the power-on stator frequency for the Rs adaptation for the induction motor (ASM).		
r1790	Motor model ASM Rs adaptation switch-on slip / MotMod Rs fslip		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the power-on slip frequency for the Rs adaptation for the induction motor (ASM).		
r1791	Motor model ASM Lh adaptation switch-on frequency / MotMod Lh f_on		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the power-on stator frequency/ primary section frequency for the Lh adaptation for the induction motor (ASM).		
r1792	Motor model ASM Lh adaptation switch-on slip / MotMod Lh fslip		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the power-on slip frequency for the Lh adaptation for the induction motor (ASM).		
p1795[0...n]	Motor model PEM kT adaptation smoothing time / MotMod kT T_smth		
SERVO (Exp M_ctrl)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1 [ms]	Max 10000 [ms]	Factory setting 100 [ms]
Description:	Sets the smoothing time of the kT adaptation of the motor model for a permanent-magnet synchronous motor (PEM).		
Dependency:	Refer to: p1780, r1797		
p1795[0...n]	Motor model PEM kT adaptation integral time / MotMod kT Tn		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 6731
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10 [ms]	Max 10000 [ms]	Factory setting 100 [ms]
Description:	Sets the integral time of the kT adaptation of the motor model for a permanent-magnet synchronous motor (PEM).		

r1797	Motor model PEM kT adaptation correction value / MotMod kT corr		
SERVO (Exp M_ctrl)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Nm/A]	Max - [Nm/A]	Factory setting - [Nm/A]
Description:	Displays the correction value of the kT adaptation of the motor model for a permanent-magnet synchronous motor (PEM).		
Dependency:	Refer to: p1780, p1795		
r1797	Motor model PEM kT adaptation correction value / MotMod kT corr		
SERVO (Exp M_ctrl, Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [N/Aeff]	Max - [N/Aeff]	Factory setting - [N/Aeff]
Description:	Displays the correction value of the kT adaptation of the motor model for a permanent-magnet synchronous motor (PEM).		
Dependency:	Refer to: p1780, p1795		
r1797	Motor model PEM kT adaptation correction value / MotMod kT corr		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 6731
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [Nm/A]	Max - [Nm/A]	Factory setting - [Nm/A]
Description:	Displays the correction value of the kT adaptation of the motor model for a permanent-magnet synchronous motor (PEM).		
p1800[0...n]	Pulse frequency / Pulse frequency		
SERVO	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 1.000 [kHz]	Max 16.000 [kHz]	Factory setting 4.000 [kHz]
Description:	Sets the drive converter switching frequency. This parameter is preset to the rated converter value when the drive is first commissioned.		
Dependency:	The pulse frequency can, depending on the current controller sampling time (p0115[0]) assume the following values. $p1800 = 1 / (p0115[0] * n)$ or $p1800 = n / p0115[0]$ With $n = 1, 2, 3, \dots$ The minimum and maximum pulse frequencies of the power unit must be taken into account (r0114). Example: $p0115[0] = 125 \mu s \rightarrow p1800 = 2, 2.6, 4, 8, 16 \text{ kHz}$ Refer to: r0110, r0111, p0112, p0113, r0114, p0115, p0230, p1817		

Note: The maximum possible pulse frequency is also determined by the power unit being used. When the pulse frequency is increased, depending on the particular power unit, the maximum output current can be reduced (de-rating, refer to r0067).
If a sinusoidal filter is parameterized as output filter (p0230 = 3), then the pulse frequency cannot be changed below the minimum value required for the filter.
If p1800 is changed while commissioning (p0009, p0010 > 0), then it is possible that the old value will no longer be able to be set. The reason for this is that the dynamic limits of p1800 have been changed by a parameter that was set when the drive was commissioned (e.g. p1082).
For sensorless operation (p1404 = 0 or p1300 = 20), the following applies:
- The condition must be fulfilled: $p1800 \geq n / (2 * p0115[0])$, $n = 1, 2, \dots$
- For motors with a small power rating (< 300 W) we recommend to set $n \geq 2$.

p1800[0...n]	Pulse frequency / Pulse frequency		
VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 1.000 [kHz]	Max 16.000 [kHz]	Factory setting 4.000 [kHz]
Description:	Sets the drive converter switching frequency. This parameter is preset to the rated converter value when the drive is first commissioned.		
Dependency:	The pulse frequency can, depending on the current controller sampling time (p0115[0]) assume the following values. $p1800 = 1 / (p0115[0] * n)$ or $p1800 = n / p0115[0]$ With $n = 1, 2, 3, \dots$ The minimum and maximum pulse frequencies of the power unit must be taken into account (r0114). Example: $p0115[0] = 125 \mu s \rightarrow p1800 = 2, 2.6, 4, 8, 16 \text{ kHz}$ Refer to: r0110, r0111, p0112, p0113, r0114, p0115, p0230, p1817		
Note:	The maximum possible pulse frequency is also determined by the power unit being used. When the pulse frequency is increased, depending on the particular power unit, the maximum output current can be reduced (de-rating, refer to r0067). If a sinusoidal filter is parameterized as output filter (p0230 = 3), then the pulse frequency cannot be changed below the minimum value required for the filter. If p1800 is changed while commissioning (p0009, p0010 > 0), then it is possible that the old value will no longer be able to be set. The reason for this is that the dynamic limits of p1800 have been changed by a parameter that was set when the drive was commissioned (e.g. p1082).		

r1801	Actual pulse frequency / Pulse freq actual		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [kHz]	Max - [kHz]	Factory setting - [kHz]
Description:	Displays the actual converter switching frequency.		
Note:	The selected pulse frequency (p1800) may be reduced if the drive converter has overload condition (refer to p0290). The following applies for vector drives (refer to p0107): The pulse frequency can also be reduced when changing-over the modulator to an optimized pulse pattern. This is used to avoid overdriving.		

p1802[0...n]		Modulator mode / Modulator mode		
VECTOR	Can be changed: T	Dynamic index: DDS, p0180	Access level: 3	
	Data type: Integer16	Units group: -	Function diagram: -	
	P-Group: Modulation		Unit selection: -	
	Min 0	Max 9	Factory setting 0	
Description:	Sets the modulator mode.			
Values:	0: Automatic changeover SVM/FLB 1: Flat top modulation (FLB) 2: Space vector modulation (SVM) 3: SVM without overmodulation 4: SVM/FLB without overcontrol 5: SVM with pulse frequency reduction 6: SVM/FLB with pulse frequency reduction 7: No edge modulation up to 100 Hz 8: No edge modulation up to 60 Hz 9: Edge modulation			
Dependency:	If a sinusoidal filter is parameterized as output filter (p0230 = 3, 4), or if the power unit firmware is not able to calculate edge modulation (r0192 bit0 = 0), then only space vector modulation without overcontrol can be set as modulation type (p1802 = 3). Refer to: r0192, p0230, p7003			
Note:	When modulation modes are enabled that could lead to overmodulation (p1802 = 0, 1, 2, 5, 6), the modulation depth must be limited using p1803. The higher the overmodulation, the greater the current ripple and torque ripple. When changing p1802[x], the values for all of the other existing indices are also changed. p1802 = 7, 8 should be used if the drive is operated below 100 Hz or 60 Hz, and it is necessary to avoid changing over to edge modulation. Above these output frequencies, the modulation depth remains limited so that there the full output voltage of the edge modulation is not reached.			
p1803[0...n]		Maximum modulation depth / Modulat depth max		
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3	
	Data type: Floating Point	Units group: -	Function diagram: 6723	
	P-Group: Modulation		Unit selection: -	
	Min 20.0 [%]	Max 150.0 [%]	Factory setting 100.0 [%]	
Description:	Defines the maximum modulation depth.			
Note:	p1803 = 100 % is the overcontrol limit for space vector modulation (or an ideal drive converter without any switching delay). If an optimized pulse pattern is enabled (edge modulation), then the modulation depth is limited to below the output frequency of 28 Hz as there is no optimized pulse pattern in this range.			
p1804[0...n]		Filter time constant smoothed modulation index / T_filt mod_idxSmth		
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 4	
	Data type: Floating Point	Units group: -	Function diagram: -	
	P-Group: Modulation		Unit selection: -	
	Min 0.0 [ms]	Max 10000.0 [ms]	Factory setting 10.0 [ms]	
Description:	Filter time constant for the smoothed modulation index to change over the modulator mode.			

p1806[0...n]	Filter time constant Vdc correction / T_filt Vdc_corr		
VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 10000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the filter time constant of the DC link voltage used to calculate the modulation depth.		
r1807	Actual DC-link voltage to calculate the modulation depth / VdcActValMod_depth		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 5_2	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	DC link voltage that is used to convert the setpoint voltage into an equivalent modulation depth.		
Note:	p1737 can be used for filtering.		
r1808	DC link voltage actual value for V_max calculation / Vdc act val U_max		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 5_2	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	DC link voltage used to determine the maximum possible output voltage.		
r1809	Modulator mode actual / Modulator mode act		
VECTOR	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 1	Max 8	Factory setting 1
Description:	Displays the effective modulator mode.		
Values:	1: Flat top modulation (FLB) 2: Space vector modulation (SVM) 3: Edge modulation from 28 Hz; 23:3 4: Edge modulation from 28 Hz; 19:1 5: Edge modulation from 60 Hz; 17:3 6: Edge modulation from 60 Hz; 17:1 7: Edge modulation from 100 Hz; 9:2 8: Edge modulation from 100 Hz; 9:1		
p1817	Minimum ratio, pulse frequency to the output frequency / Min f_puls / f_max		
VECTOR	Can be changed: C2(2)		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 8.3	Max 15.0	Factory setting 12.0
Description:	Sets the minimum ratio between the pulse frequency and the output frequency.		
Notice:	If the ratio between the pulse frequency and the output frequency is reduced, then oscillations can occur in the output current that can result in significant levels of current ripple with the appropriate negative effects.		
Note:	When the maximum speed is changed, the pulse frequency p1800 is automatically limited to this minimum ratio. It is not permissible to reduce the pulse frequency if this would result in this ratio being fallen below.		

p1820[0...n]	Output phase direction of rotation / Phase revers. outp		
VECTOR	Can be changed: C2(3)		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Direction of rotation reversal of the Motor Module output phases without changing the speed setpoint.		
Values:	0: Off 1: On		
Note:	It is not possible to reverse the phases while the pulses are enabled. When a speed encoder is being used, it may be necessary to also invert the encoder actual value (refer to p0410).		
p1821[0...n]	Direction reversal / Direction reversal		
SERVO, VECTOR	Can be changed: C2(3)		Access level: 3
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the direction of reversal of the motor.		
Values:	0: No direction of reversal 1: Direction reversal		
Dependency:	Refer to: F07434		
Notice:	For a drive data set changeover with differently set direction reversal and pulse enable, an appropriate fault is output.		
Note:	If the parameter is changed, it reverses the direction of rotation of the motor without changing the setpoint. For direction of rotation reversal, the rotating field direction of the current controller is reversed. The speed actual value (e.g. r0063) is also reversed so that the control sense is kept and internally causing the direction of rotation to be reversed with the same setpoint. Further, the position actual values of the actual encoder are reversed (e.g. r0482[0...2]).		
p1825	Converter valve threshold voltage / Threshold voltage		
VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.0 [Veff]	Max 100.0 [Veff]	Factory setting 0.6 [Veff]
Description:	Sets the threshold voltage drop of the valves (power semiconductor devices) to be compensated.		
Note:	The value is automatically calculated in the motor data identification routine.		
p1827	Infeed compensation valve lockout time operating mode / INFcomp t_lockMode		
A_INF, S_INF	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the operating mode for the compensation of the valve lockout time.		
Values:	0: Compensation valve lockout time de-activated 1: Compensation valve lockout time activated		
Note:	The compensation is always active, independent of the value of this parameter if the closed-loop control is activated to suppress circulating currents (p7035) for power units are connected in parallel.		

p1828	Compensation valve lockout time phase U / Comp t_lock ph U		
VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 1000000.00 [µs]	Factory setting 0.00 [µs]
Description:	Sets the valve lockout time to compensate for phase U.		
Note:	The value is automatically calculated in the motor data identification routine.		
p1829	Compensation valve lockout time phase V / Comp t_lock ph V		
VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 1000000.00 [µs]	Factory setting 0.00 [µs]
Description:	Sets the valve lockout time to compensate for phase V.		
p1830	Compensation valve lockout time phase W / Comp t_lock ph W		
VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 1000000.00 [µs]	Factory setting 0.00 [µs]
Description:	Sets the valve lockout time to compensate for phase W.		
p1832	Deadtime compensation current level / t_dead_comp I_lev		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.0 [Aeff]	Max 10000.0 [Aeff]	Factory setting 0.0 [Aeff]
Description:	Above the current level, the deadtime - resulting from the converter switching delays - is compensated by a previously calculated, constant value . If the relevant phase current setpoint falls below the absolute value defined by p1832, the correction value for this phase is continuously reduced.		
Dependency:	The factor setting of p1832 is automatically set to 0.02 * rated drive converter current (r0207). If the actual operating frequency exceeds the value of p1831, then p1832 is not applied!		

p1846[0...n]	Actual value correction damping factor / ActV_corr D_factor		
VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00	Max 10.00	Factory setting 1.00
Description:	Sets the damping factor for the actual value correction. The factor multiplies the T0/Tsig ratio in the feedback branch of the LR element		

r1848[0...5]	Actual value correction, phase currents / ActVal_corr I_corr		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays phase correction currents as well as the drive converter phase currents		
Index:	[0] = Harmonics, phase U [1] = Harmonics, phase V [2] = Harmonics, phase W [3] = Meas. val. phase U [4] = Meas. val. phase V [5] = Meas. val. phase W		


r1849[0...5]	Actual value correction, phase voltages / ActVal_corr V_corr		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the phase correction voltages and and the drive converter phase voltages		
Index:	[0] = Harmonics, phase U [1] = Harmonics, phase V [2] = Harmonics, phase W [3] = Meas. val. phase U [4] = Meas. val. phase V [5] = Meas. val. phase W		

p1900		Motor data identification and rotating measurement / Mot ID rot meas	
VECTOR	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	2	2
Description:	<p>Sets the motor data identification and speed/velocity controller optimization.</p> <p>p1900 = 0: Function inhibited.</p> <p>p1900 = 1: Induction motors --> set p1910 = 1 and p1960 = 0, 1, 2 depending on p1300 Permanent-magnet or separately-excited synchronous motors --> set p1910 = 1 and p1990 = 1 and p1960 = 0, 1, 2 depending on p1300</p> <p>When the drive enable signals are present, a motor data identification routine is carried-out at standstill with the next power-on command. Current flows through the motor which means that it can align itself by up to a quarter of a revolution.</p> <p>For permanent-magnet or separately-excited synchronous motors, the encoder is adjusted with the next power-on command. The motor must be free to rotate and rotates through 1.5 revolutions of the motor encoder.</p> <p>With the following power-on command, a rotating motor data identification routine is carried-out - and for vector, in addition, a speed/velocity controller optimization by making measurements at different motor speeds/velocities.</p> <p>p1900 = 2: Induction motors --> set p1910 = 1 and p1960 = 0 Permanent-magnet or separately-excited synchronous motors --> set p1910 = 1, p1990 = 1 and p1960 = 0</p> <p>When the drive enable signals are present, a motor data identification routine is carried-out at standstill with the next power-on command. Current flows through the motor which means that it can align itself by up to a quarter of a revolution.</p> <p>For permanent-magnet or separately-excited synchronous motors, the encoder is adjusted with the next power-on command. The motor must be free to rotate and rotates through 1.5 revolutions of the motor encoder.</p>		
Values:	<p>0: Inhibited</p> <p>1: Motor data identification for rotating motor</p> <p>2: Motor data identification at standstill</p>		
Dependency:	<p>In the simulation mode, the parameter cannot be written into. When selecting the motor data identification routine, the drive data set changeover is suppressed.</p> <p>Refer to: p1272, p1300, p1910, p1960, p1990</p> <p>Refer to: A07980, A07981, F07982, F07983, F07984, F07985, F07986, A07987, F07988, F07990, A07991</p>		
Notice:	<p>In order to permanently accept the determined settings they must be saved in a non-volatile fashion (p0971, p0977).</p>		
Note:	<p>An appropriate alarm is output when the parameter is set.</p> <p>The power-on command must remain set during a measurement and after the measurement has been completed, the drive automatically resets it.</p> <p>The duration of the measurements can lie between 0.3 s and several minutes. This time is, for example, influenced by the motor size and the mechanical conditions.</p> <p>p1900 is automatically set to 0 after the motor data identification routine has been completed.</p>		

p1909[0...n]		Motor data identification control word / MotID STW		
SERVO	Can be changed: T			Access level: 3
	Data type: Unsigned16	Dynamic index: MDS, p0130		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0010 0111 0000 0000 bin
Description:	Sets the configuration of the motor data identification.			
Bit field:	Bit	Signal name	1 signal	0 signal
	08	Measure D inductance	Yes	No
	09	Measure Q inductance	Yes	No
	10	Magnetizing field inductance and measure rotor resistance	Yes	No
	13	Measure commutation angle	Yes	No
	14	Determining the voltage emulation error	Yes	No
Dependency:	Refer to: p1910, r1912, r1913, r1915, r1925, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953			
Note:	Re bit 14: After the voltage emulation error has been successfully determined, the display of various values is significantly more accurate (e.g. r0089[0...2] phase voltage actual value).			

p1909[0...n]		Motor data identification control word / MotID STW		
SERVO (Exp M_ctrl)	Can be changed: T			Access level: 3
	Data type: Unsigned16	Dynamic index: MDS, p0130		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0110 0111 0000 0000 bin
Description:	Sets the configuration of the motor data identification.			
Bit field:	Bit	Signal name	1 signal	0 signal
	08	Measure D inductance	Yes	No
	09	Measure Q inductance	Yes	No
	10	Magnetizing field inductance and measure rotor resistance	Yes	No
	13	Measure commutation angle	Yes	No
	14	Determining the voltage emulation error	Yes	No
Dependency:	Refer to: p1910, r1912, r1913, r1915, r1925, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953			
Note:	Re bit 14: After the voltage emulation error has been successfully determined, the display of various values is significantly more accurate (e.g. r0089[0...2] phase voltage actual value).			

p1909[0...n]	Motor data identification control word / MotID STW			
VECTOR	Can be changed: T			Access level: 4
	Data type: Unsigned16	Dynamic index: MDS, p0130		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Sets the configuration of the motor data identification.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Estimates the stator inductance, no measurement	Yes	No
	01	Cl.-loop current control w/ dead-beat controller	Yes	No
	02	Estimates the rotor time constant, no measurement	Yes	No
	03	Estimates the leakage inductance, no measurement	Yes	No
	04	Activates the identification dynamic leakage inductance	Yes	No
	05	Determine Tr. Lsig evaluation in the time range	Yes	No
	06	Activates vibration damping	Yes	No
	07	De-activates the vibration detection	Yes	No
	11	De-activate pulse measurement Lq Ld	Yes	No
	12	De-activate rotor resistance Rr measurement	Yes	No
	15	Only measure stator resistance and valve voltage error	Yes	No
Note:	<p>Note for PEM:</p> <p>Without de-selection in bit 11, in the closed-loop control mode, the direct inductance LD and the quadrature inductance Lq are measured at a low current.</p> <p>When de-selecting with bit 11 or in the U/f mode, the stator inductance is measured at half the rated motor current.</p> <p>If the stator is inductance is not measured but is to be estimated, then bit 0 should be set and bit 11 should be de-selected.</p>			

p1910	Motor data identification routine, stationary (standstill) / MotID standstill			
SERVO	Can be changed: T			Access level: 2
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-2	1		0
Description:	Setting to control the motor data identification with the motor stationary.			
Values:	<p>-2: Acknowledge encoder inversion actual value (F07993)</p> <p>-1: Start motor data identification without acceptance</p> <p>0: Inactive/inhibit</p> <p>1: Start motor data identification with acceptance</p>			
Recommendation:	For motors with brakes, the brake should be opened before carrying-out the stationary motor data identification routine (p1215 = 2) as long as this can be done without incurring any danger. This means that other data are identified.			
Dependency:	Refer to: p1909, r1912, r1913, r1915, r1925, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953 Refer to: F07990, A07991, F07993			
Caution:	For motors without brake or with the brake open (p1215 = 2), for the stationary (zero speed) measurement, the motor may rotate slightly.			
				
Note:	<p>After a started motor identification is ended, the parameter is automatically reset to 0.</p> <p>A motor data identification that is presently be carried-out can be terminated with p1910 = 0.</p>			

p1910		Motor data identification selection / MotID selection		
VECTOR	Can be changed: T Data type: Integer16 P-Group: Motor identification Min 0 Max 20	Dynamic index: - Units group: -	Access level: 2 Function diagram: - Unit selection: - Factory setting 1	
Description:	Sets the motor data identification routine. The motor data identification routine is carried-out after the next power-on command. p1910 = 1: All motor data and the drive converter characteristics are identified and then transferred to the following parameters: p0350, p0354, p0356, p0357, p0358, p0360, p1825, p1828, p1829, p1830			
Values:	0: Inhibited 1: Complete identification (ID) and acceptance of motor data 2: Complete identification (ID) of motor data without acceptance 3: ID of the saturation characteristic and acceptance 4: ID of the saturation characteristic without acceptance 5: ID of dynamic leakage inductance Lsig (r1920) without acceptance 6: ID of lockout time (r1926) without acceptance 7: ID of stator resistance Rs (r1912) without acceptance 8: ID of stator inductance Ls (r1915) without acceptance 9: ID of rotor time constant Tr (r1913) without acceptance 10: ID of static leakage inductance Lsig (r1914) without acceptance 20: Voltage vector input			
Dependency:	"Quick commissioning" must be carried-out (p0010 = 1) before executing the motor data identification routine! In the simulation mode, the parameter cannot be written into. When selecting the motor data identification routine, the drive data set changeover is suppressed. Refer to: p1272, p1900			
Caution:	After the motor data identification (p1910 > 0) has been selected, alarm A07991 is output and a motor data identification routine is carried-out as follows at the next power-on command: - current flows through the motor and a voltage is present at the drive converter output terminals. - during the identification routine, the motor shaft can rotate through a maximum of half a revolution. - however, no torque torque is generated.			
Notice:	In order to permanently accept the determined settings they must be saved in a non-volatile fashion (p0971, p0977).			
Note:	When setting p1910, the following should be observed: 1. "With transfer" means: The parameters specified in the description are overwritten with the identified values and therefore have an influence on the controller setting. 2. "Without transfer" means: The identified parameters are only displayed in the range r1912 ... r1926. The controller settings remain unchanged.			
p1911		Number of phases to be identified / Phases to be ident		
VECTOR	Can be changed: T Data type: Integer16 P-Group: Motor identification Min 1 Max 3	Dynamic index: - Units group: -	Access level: 4 Function diagram: - Unit selection: - Factory setting 1	
Description:	Selects the number of phases to be identified. The accuracy of the identification routine is higher if several phases are identified - however, the time required to make the measurements also increases.			
Values:	1: 1 phase U 2: 2 phases U, V 3: 3 phases U, V, W			

r1912	Stator resistance identified / R_stator ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the identified stator resistance.		
Dependency:	Refer to: p1909, p1910, r1913, r1915, r1925, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953		
r1912[0...2]	Identified stator resistance / R_stator ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the identified stator resistance.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1913	Rotor time constant identified / T_rotor ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the identified rotor time constant.		
Dependency:	Refer to: p1909, p1910, r1912, r1915, r1925, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953		
r1913[0...2]	Identified rotor time constant / T_rotor ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the identified rotor time constant.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1914[0...2]	Identified total leakage inductance / L_total_leak ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the identified total leakage inductance.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		

r1915	Stator inductance identified / L_stator ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the identified stator inductance.		
Dependency:	Refer to: p1909, p1910, r1912, r1913, r1925, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953		

r1915[0...2]	Identified nominal stator inductance / L_stator ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the nominal stator inductance identified.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		

r1916[0...2]	Identified stator inductance 1 / L_stator 1 ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the nominal stator inductance identified for the 1st point of the saturation characteristic.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		

r1917[0...2]	Identified stator inductance 2 / L_stator 2 ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the nominal stator inductance identified for the 2nd point of the saturation characteristic.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		

r1918[0...2]	Identified stator inductance 3 / L_stator 3 ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the nominal stator inductance identified for the 3rd point of the saturation characteristic.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1919[0...2]	Identified stator inductance 4 / L_stator 4 ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the nominal stator inductance identified for the 4th point of the saturation characteristic.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1920[0...2]	Identified dynamic leakage inductance / L_leak dyn ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the identified dynamic total leakage inductance.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1921[0...2]	Identified dynamic leakage inductance 1 / L_leak 1 dyn id		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1922[0...2]	Identified dynamic leakage inductance 2 / L_leak 2 dyn id		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		

r1923[0...2]	Identified dynamic leakage inductance 3 / L_leak 3 dyn id		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1924[0...2]	Identified dynamic leakage inductance 4 / L_leak 4 dyn id		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1925	Threshold voltage identified / U_threshold ident		
SERVO	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the identified threshold voltage of the power unit.		
Dependency:	Refer to: p1909, p1910, r1912, r1913, r1915, r1927, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953		
r1925[0...2]	Identified threshold voltage / U_threshold ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the identified IGBT threshold voltage.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1926[0...2]	Identified active valve lockout time / t_lock_valve id		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [µs]	Max - [µs]	Factory setting - [µs]
Description:	Displays the identified effective valve lockout time.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		

r1927	Rotor resistance identified / R_rotor ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the identified rotor resistance.		
Dependency:	Refer to: p1909, p1910, r1912, r1913, r1915, r1925, r1932, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953		
r1927[0...2]	Identified rotor resistance / R_rotor ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the identified rotor resistance		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1929[0...2]	Identified cable resistance / R_cable ident		
VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Ohm]	Max - [Ohm]	Factory setting - [Ohm]
Description:	Displays the identified cable resistance.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
r1932[0...19]	d inductance identified / Ld ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the identified (differential) d-inductance.		
Dependency:	Refer to: p1909, p1910, r1912, r1913, r1915, r1925, r1927, r1933, r1934, r1935, r1936, r1950, r1951, p1952, p1953		
Note:	The Ld characteristic consists of the value pairs from p1932 and p1933 with the same index. This value corresponds to the value of the total leakage inductance (r0377).		
r1933[0...19]	d inductance identification current / Ld I_ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the identification current of the d inductance.		

Dependency: Refer to: p1909, p1910, r1912, r1913, r1915, r1925, r1927, r1932, r1934, r1935, r1936, r1950, r1951, p1952, p1953

Note: The Ld characteristic consists of the value pairs from p1932 and p1933 with the same index.

r1934[0...9] q inductance identified / Lq ident

SERVO	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor identification		Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]

Description: Displays the identified (differential) q-inductance.

Dependency: Refer to: p1909, p1910, r1932, r1933

Note: The Lq characteristic consists of the value pairs from p1934 and p1935 with the same index.
This value corresponds to the value of the total leakage inductance (r0377).

r1935[0...9] q inductance identification current / Lq I_ident

SERVO	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor identification		Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]

Description: Displays the identification current of the q inductance.

Dependency: Refer to: p1909, p1910, r1934, p1959, p1960

Note: The Lq characteristic consists of the value pairs from p1934 and p1935 with the same index.

r1936 Magnetizing inductance identified / L_H ident

SERVO	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Motor identification		Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]

Description: Displays the identified magnetizing inductance(gamma equivalent circuit diagram).

Dependency: Refer to: p1909, p1910, r1913, r1915, r1927, p1959, p1960, r1962, r1963

Note: This value corresponds to the value of the transformed magnetizing inductance (r0382).

r1937[0...9] Torque constant identified / kT ident

SERVO	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 28_1	Function diagram: -
	P-Group: Motor identification		Unit selection: p0100
	Min - [Nm/A]	Max - [Nm/A]	Factory setting - [Nm/A]

Description: Displays the identified torque constant.

Dependency: Refer to: r1938, r1939, p1959, p1960, r1969

Note: The value in r1937[0] corresponds to the torque constant (p0316). If indices 1 to 9 are not equal to zero, they show the identified values of the torque constant for the current in r1935 with the same index.

r1937[0...9]	Forced constant identified / kT ident		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: 29_1	Unit selection: p0100
	Min - [N/Aeff]	Max - [N/Aeff]	Factory setting - [N/Aeff]
Description:	Displays the identified force constant.		
Dependency:	Refer to: r1938, r1939, p1959, p1960, r1969		
Note:	This value corresponds to the force constant (p0316).		

r1938	Voltage constant identified / kE ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the identified voltage constant.		
Dependency:	Refer to: r1937, r1939, p1959, p1960, r1969		
Note:	This value corresponds to the voltage constant (p0317).		

r1938	Voltage constant identified / kE ident		
SERVO (Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Veff s/m]	Max - [Veff s/m]	Factory setting - [Veff s/m]
Description:	Displays the identified voltage constant.		
Dependency:	Refer to: r1937, r1939, p1959, p1960, r1969		
Note:	This value corresponds to the voltage constant (p0317).		

r1939	Reluctance torque constant identified / kT_reluct. ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the identified reluctance torque constant.		
Dependency:	Refer to: r1937, r1938, p1959, p1960, r1969		
Note:	This value corresponds to the reluctance torque constant (p0328).		


r1947	Optimum load angle identified / phi_load ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the identified, optimum load angle.		
Note:	This value corresponds to the optimum load angle (p0327).		

r1948	Magnetizing current identified / I_mag ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the identified magnetizing current.		
Dependency:	Refer to: r1936, p1959, p1960		
Note:	This value corresponds to the magnetizing current (p0320 / r0331).		
r1950[0...19]	Voltage emulation error voltage values / U_error U_values		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	The identified characteristic of the voltage emulation error is displayed r1950[0...19] and r1951[0...19].		
Dependency:	Refer to: r1951		
r1951[0...19]	Voltage emulation error current values / U_error I_error		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	The identified characteristic of the voltage emulation error is displayed r1950[0...19] and r1951[0...19].		
Dependency:	Refer to: r1950		
p1952[0...n]	Voltage emulation error, final value / U_error final val		
SERVO	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0.000 [V]	Max 100.000 [V]	Factory setting 0.000 [V]
Description:	Sets the final value to compensate the voltage emulation error.		
Dependency:	Refer to: p1953		
Note:	The voltage emulation error is calculated and compensated for every phase according to the following formula: $u_error = u0 * i / (abs(i)-i0)$ u0: This is set in p1952. i0: This is set in p1953. i: Phase current to which the emulation error u_error belongs.		
p1953[0...n]	Voltage emulation error current offset / U_error I_offset		
SERVO	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0.000 [A]	Max 100.000 [A]	Factory setting 0.000 [A]
Description:	Sets the current offset to compensate the voltage emulation error.		
Dependency:	Refer to: p1952		

Note: The voltage emulation error is calculated and compensated for every phase according to the following formula:
 $u_error = u0 * i / (abs(i)-i0)$
 u0: This is set in p1952.
 i0: This is set in p1953.
 i: Phase current to which the emulation error u_error belongs.

p1958[0...n]		Motor data identification ramp-up/ramp-down time / MotID t_up_down		
SERVO	Can be changed: T			Access level: 2
	Data type: Floating Point	Dynamic index: MDS, p0130		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min -1.00 [s]	Max 999999.00 [s]		Factory setting -1.00 [s]
Description:	Sets the ramp-up/ramp-down time for the rotating motor data identification. The following applies for negative values: When the function module "extended setpoint channel" is activated (r0108.8 = 1), the ramp-up/ramp-down time of the setpoint channel becomes effective. When this function module is inactive, then no ramp-up/ramp-down time is effective. The following applies for positive values: The selected ramp-up/ramp-down time becomes effective.			
Recommendation:	A ramp-up/ramp-down time should not be activated for the motor data identification (p1958 = 0) as long as this can be done without incurring any danger. This means that the identification is complete and more accurate. When the ramp-up/ramp-down time is activated, then the rotating motor data identification can only be partially carried-out.			
Dependency:	Refer to: p1959, p1960			

p1959[0...n]		Rotating measurement configuration / Rot meas config			
SERVO	Can be changed: T				Access level: 3
	Data type: Unsigned16	Dynamic index: MDS, p0130			Function diagram: -
	P-Group: Motor identification	Units group: -			Unit selection: -
	Min -	Max -			Factory setting 0000 0110 1110 0110 bin
Description:	Sets the configuration of the rotating measurement.				
Recommendation:	A direction inhibit should not be activated for the motor data identification (p1959.14 = 1 and p1959.15 = 1) as long as this can be done without incurring any danger. This means that the identification is complete and more accurate. When the direction inhibit is activated, then the rotating motor data identification can only be partially carried-out.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Identifying the saturation characteristic	Yes	No	-
	02	Identifying the moment of inertia	Yes	No	-
	05	Identifying the q inductance	Yes	No	-
	06	Identifying the torque constant	Yes	No	-
	07	Identifying the reluctance torque constant	Yes	No	-
	08	Identifying the q inductance at the test stand	Yes	No	-
	09	Identifying the magnetizing current / magnetizing inductance	Yes	No	-
	10	Identifying the commutation angle	Yes	No	-
	14	Clockwise direction of rotation permitted	Yes	No	-
	15	Counter-clockwise direction of rotation permitted	Yes	No	-
Dependency:	Refer to: p1958, p1960				
Note:	Re bit 14 and 15: The following applies for bit 14 and 15 = 0: When the function module "extended setpoint channel" is activated (r0108.8 = 1), the direction inhibit of the setpoint channel becomes effective. No direction of inhibit is effective if the function module is inactive. The following applies for minimum bit 14 = 1 or bit 15 = 1: The selected direction inhibit becomes effective.				

p1959[0...n]		Rotating measurement configuration / Rot meas config		
VECTOR (n/M)	Can be changed: T			Access level: 2
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0001 1111 bin
Description:	Sets the configuration of the rotating measurement.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Enc test active	Yes	No
	01	Saturation characteristic identification	Yes	No
	02	Moment of inertia identification	Yes	No
	03	Recalculates the speed controller parameters	Yes	No
	04	Speed controller optimization, (vibration test)	Yes	No
Dependency:	Refer to: F07988			
Note:	The encoder is only tested if the rotating measurement with encoder is selected (p1960 = 2). The following parameters are influenced for the individual optimization steps: Bit 00: None Bit 01: p0320, p0360, p0362 ... p0369 Bit 02: p0341, p0342 Bit 03: p1400.0, p1458, p1459, p1460, p1462, p1462, p1463, p1470, p1472, p1496 Bit 04: Dependent on p1960 p1960 = 1, 3: p1400.0, p1458, p1459, p1470, p1472, p1496 p1960 = 2, 4: p1458, p1459, p1460, p1461, p1462, p1463, p1496			
p1960		Rotating measurement selection / Rot meas sel		
SERVO	Can be changed: T			Access level: 2
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-2	1		0
Description:	Activates the rotating measurement.			
Values:	-2: Acknowledge encoder inversion actual value (F07993) -1: Start motor data identification without acceptance 0: Inactive/inhibit 1: Start motor data identification with acceptance			
Dependency:	Refer to: r1934, r1935, r1936, r1937, r1938, r1939, r1947, r1948, p1958, p1959, r1962, r1963, r1969 Refer to: F07990, A07991, F07993			
Danger:	For the rotating measurement, the motor is accelerated up to the maximum speed. Only the parameterized current limit (p0640) and the maximum speed (p1082) are effective. The behavior of the motor can be influenced using the direction inhibit (p1959.14, p1959.15) and the ramp-up/ramp-down time (p1958).			
				
Caution:	In order to permanently accept the determined settings they must be saved in a non-volatile fashion (p0971, p0977).			
Note:	When the rotating measurement is activated (p1960 = 1), the parameters should not be saved (p0971, p0977), as this can result in inconsistent data.			

p1960	Rotating measurement selection / Rot meas sel		
VECTOR	Can be changed: T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0	Max 4	Factory setting 0
Description:	Sets the rotating measurement. The rotating measurement is carried-out after the next power-on command. The setting possibilities of the parameter depend on the open-loop/closed-loop control mode (p1300): p1300 < 20 (U/f control): It is not possible to select rotating measurement or speed controller optimization. p1300 = 20, 22 (sensorless operation): Only rotating measurement or speed controller optimization can be selected in the sensorless mode. p1300 = 21, 23 (operation with encoder): Both versions (sensorless and with encoder) of the rotating measurement or speed controller optimization can be selected.		
Values:	0: Inhibited 1: Rotating measurement in sensorless operation 2: Rotating measurement with encoder 3: Speed controller optimization for sensorless operation 4: Speed controller optimization with encoder		
Dependency:	In the simulation mode, a value of 1 cannot be written into the parameter. When selecting the rotating measurement, the drive data set changeover is suppressed. Refer to: p1272, p1300, p1900, p1959 Refer to: A07987		
Notice:	In order to permanently accept the determined settings they must be saved in a non-volatile fashion (p0971, p0977).		
Note:	When the rotating measurement is activated, it is not possible to save the parameters (p0971, p0977). Parameter changes are automatically made for the rotating measurement (e.g. p1120); this is the reason that up to the end of the measurement, and if no faults are present, no manual changes should be made. The ramp-up and ramp-down times (p1120, p1121) are limited, for the rotating measurement, to 900s.		
p1961	Saturation characteristic speed to determine / Sat_char n determ		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 26 [%]	Max 75 [%]	Factory setting 30 [%]
Description:	Sets the speed to determine the saturation characteristic and the encoder test. The percentage value is referred to p0310 (rated motor frequency).		
Dependency:	Refer to: p0310, p1959 Refer to: F07983		
Note:	The saturation characteristics should be determined at an operating point with the lowest possible load.		
r1962[0...9]	Saturation characteristic magnetizing current identified / Sat_char l_mag		
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the magnetizing currents of the identified saturation characteristic. The values are referred to r0331.		
Dependency:	Refer to: p1959, p1960, r1963		
Note:	The saturation characteristic consists of the value pairs from p1962 and p1963 with the same index.		

r1962[0...4]		Saturation characteristic, magnetizing current / Sat_char I_mag	
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the magnetizing currents of the identified saturation characteristic. The values are referred to r0331. After they have been determined, the values are transferred to p0366 ... p0369.		
Index:	[0] = Value 1 [1] = Value 2 [2] = Value 3 [3] = Value 4 [4] = Value 5		
Dependency:	Refer to: r0331		

r1963[0...9]		Saturation characteristic stator inductance identified / Sat_char L_stator	
SERVO	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the stator inductances of the identified saturation characteristic. The values are referred to the stator inductance at the magnetizing current (r0331).		
Dependency:	Refer to: p1959, p1960, r1962		
Note:	The saturation characteristic consists of the value pairs from p1962 and p1963 with the same index.		

r1963[0...4]		Saturation characteristic, magnetizing inductance / Sat_char L_main	
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the magnetizing inductances of the identified saturation characteristic. The values are referred to r0382.		
Index:	[0] = Value 1 [1] = Value 2 [2] = Value 3 [3] = Value 4 [4] = Value 5		
Dependency:	Refer to: r0382		

r1964[0...4]	Saturation characteristic, rotor flux / Sat_char rot flux		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the rotor flux values of the identified saturation characteristic. After they have been determined, the values are transferred to p0362 ... p0365.		
Index:	[0] = Value 1 [1] = Value 2 [2] = Value 3 [3] = Value 4 [4] = Value 5		
p1965	Speed_ctrl_opt speed / n_opt speed		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 10 [%]	Max 75 [%]	Factory setting 50 [%]
Description:	Sets the speed for the identification of the moment of inertia and the vibration test. Induction motor: The percentage value is referred to p0310 (rated motor frequency). Synchronous motor: The percentage value is referred to the minimum from p0310 (rated motor frequency) and p1082 (maximum speed).		
Dependency:	Refer to: p0310, p1959 Refer to: F07984, F07985		
Note:	In order to calculate the inertia, sudden speed changes are carried-out - the specified value corresponds to the lower speed setpoint. This value is increased by 10 % for the upper speed value.		
p1967	Speed_ctrl_opt dynamic factor / n_opt dyn_factor		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 1 [%]	Max 400 [%]	Factory setting 100 [%]
Description:	Sets the dynamic response factor for speed controller optimization.		
Dependency:	Refer to: p1959 Refer to: F07985		
Note:	For a rotating measurement, this parameter can be used to optimize the speed controller. p1967 = 100 % --> speed controller optimization according to a symmetric optimum. p1967 > 100 % --> optimization with a higher dynamic response (Kp higher, Tn lower).		
r1968	Speed_ctrl_opt dynamic factor actual / n_opt dyn_fact act		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the dynamic factor which is actually achieved for the vibration test		

Dependency: Refer to: p1959, p1967
Refer to: F07985

Note: This dynamics factor only refers to the control mode of the speed controller set in p1960.

r1969 **Moment of inertia identified / M_inertia ident**

SERVO **Can be changed:** - **Access level:** 3

Data type: Floating Point **Dynamic index:** - **Function diagram:** -

P-Group: Motor identification **Units group:** 25_1 **Unit selection:** p0100

Min **Max** **Factory setting**

 - [kgm²] - [kgm²] - [kgm²]

Description: Displays the identified moment of inertia.

Dependency: Refer to: p0341, p0342, p1498, p1959, p1960

r1969 **High load inertia identified / High load inert id**

SERVO (Lin) **Can be changed:** - **Access level:** 3

Data type: Floating Point **Dynamic index:** - **Function diagram:** -

P-Group: Motor identification **Units group:** 27_1 **Unit selection:** p0100

Min **Max** **Factory setting**

 - [kg] - [kg] - [kg]

Description: Displays the identified high load inertia.

Dependency: Refer to: p0341, p0342, p1498, p1959, p1960

r1969 **Speed_ctrl_opt moment of inertia determined / n_opt M_inert det**

VECTOR (n/M) **Can be changed:** - **Access level:** 4

Data type: Floating Point **Dynamic index:** - **Function diagram:** -

P-Group: Motor identification **Units group:** 25_1 **Unit selection:** p0100

Min **Max** **Factory setting**

 - [kgm²] - [kgm²] - [kgm²]

Description: Displays the determined moment of inertia of the drive.
After it has been determined, the value is transferred to p0341, p0342.

Dependency: Refer to: p0341, p0342, p1959
Refer to: F07984

r1970[0...1] **Speed_ctrl_opt vibration test vibration frequency determined / n_opt f_vibration**

VECTOR (n/M) **Can be changed:** - **Access level:** 4

Data type: Floating Point **Dynamic index:** - **Function diagram:** -

P-Group: Motor identification **Units group:** - **Unit selection:** -

Min **Max** **Factory setting**

 - [Hz] - [Hz] - [Hz]

Description: Displays the vibration frequencies determined by the vibration test.

Index: [0] = Frequency low
[1] = Frequency high

Dependency: Refer to: p1959
Refer to: F07985

r1971[0...1]	Speed_ctrl_opt vibration test standard deviation determined / n_opt std. deviat.		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the standard deviations of the vibration frequencies determined by the vibration test		
Index:	[0] = Standard deviation of low frequency [1] = Standard deviation of high frequency		
Dependency:	Refer to: p1959 Refer to: F07985		
r1972[0...1]	Speed_ctrl_opt vibration test number of periods determined / n_opt period qty		
VECTOR (n/M)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the number of periods determined by the vibration test.		
Index:	[0] = No. of periods of the low frequency [1] = No. of periods of the high frequency		
Dependency:	Refer to: p1959 Refer to: F07985		
r1973	Encoder, pulse number identified / Pulse No. ident		
SERVO	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the identified encoder pulse number (per revolution). For linear motors: Encoder pulse number per meter. Grid division = 1/p1973 [meter]. Due to the measuring accuracy (approx. 5%) only the approximate value is shown in p1973 and may not be directly transferred into p0407 or p0408. An incorrect pole pair number (r0313, p0314) results in an incorrect value in p1973.		
Note:	A negative signal indicates an incorrect polarity of the encoder signal.		
r1973	Rotating measurement, encoder test pulse number determined / n_opt pulse No.		
VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the number of pulses determined during the vibration test.		
Note:	A negative signal indicates an incorrect polarity of the encoder signal.		

r1979 BO: Speed_ctrl_opt status / n_opt status

VECTOR (n/M)

Can be changed: -**Data type:** Unsigned16**P-Group:** Motor identification**Min**

-

Dynamic index: -**Units group:** -**Max**

-

Access level: 4**Function diagram:** -**Unit selection:** -**Factory setting**

0000 bin

Description:

Displays the status to check and monitor the states of speed controller optimization.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Speed controller optimization activated	Yes	No	-
01	Speed controller optimization completed	Yes	No	-
02	Speed controller optimization interrupted	Yes	No	-
04	Enc test active	Yes	No	-
05	Saturation char. identification active	Yes	No	-
06	Moment of inertia identification active	Yes	No	-
07	Recalc. speed controller parameters active	Yes	No	-
08	Speed controller vibration test active	Yes	No	-
09	Magnetizing induction adapt. active	Yes	No	-
10	Operation with encoder after sensorless operation	Yes	No	-

p1980[0...n] Pole position identification technique / PolID technique

SERVO

Can be changed: U, T**Data type:** Integer16**P-Group:** Motor identification**Min**

0

Dynamic index: MDS, p0130**Units group:** -**Max**

99

Access level: 3**Function diagram:** -**Unit selection:** -**Factory setting**

99

Description:

Sets the pole position identification technique.

Values:

0: Saturation-based 1st+ 2nd harmonics
 1: Saturation-based 1st harmonics
 4: Saturation-based, 2-stage
 10: Motion-based
 99: No technique selected

Dependency:

Refer to: p0325, p0329, p1981, p1982, p1983, r1984, r1985, r1987

Notice:

If the incorrect technique is applied, this can cause the motor to accelerate in an uncontrolled fashion.

Note:

When commissioning a list motor, the technique is automatically selected depending on the motor type being used. The following applies for 1FN3 motors: A technique with 2nd harmonic may not be used (do not use p1980 = 1, 4). For 1FN7 motors, the following applies:
 A two-stage technique may not be used (do not use p1980 = 4).
 The automatically set value in p0329 may not be changed.

p1980[0...n] Pole position identification technique / PolID technique

VECTOR

Can be changed: U, T**Data type:** Integer16**P-Group:** Motor identification**Min**

1

Dynamic index: MDS, p0130**Units group:** -**Max**

10

Access level: 3**Function diagram:** -**Unit selection:** -**Factory setting**

4

Description:

Sets the pole position identification technique.

Values:

1: Voltage pulsing, first harmonic
 4: Voltage pulsing, 2-stage
 10: DC current impression

Dependency:

In the simulation mode, the parameter cannot be written into.
 Refer to: p1272

Note:

Voltage pulse technique (p1980 = 1 or 4) cannot be applied to separately-excited synchronous motors (p0300 = 5) and for operation with sinusoidal output filters (refer to p230).

p1981[0...n]	Pole position identification maximum distance / PolID distance max		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0 [°]	Max 90 [°]	Factory setting 10 [°]
Description:	Sets the maximum distance (electrical angle) when carrying-out the pole position identification routine. If this distance (travel) is exceeded, an appropriate fault is output.		
Dependency:	Refer to: p0325, p0329, p1980, p1982, p1983, r1984, r1985, r1987, p1990 Refer to: F07995		
p1982[0...n]	Pole position identification selection / PolID selection		
SERVO	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Activates the pole position identification routine to determine the commutation angle and to carry-out a plausibility check.		
Values:	0: Pole position identification off 1: Pole position identification for commutation 2: Pole position identification for plausibility check		
Recommendation:	Re p1982 = 1: This is used for synchronous motors with motor encoder without absolute data. The information/data regarding the absolute commutation angle is supplied via a track C/D, Hall sensors, an absolute encoder or from the pole position identification routine. Re p1982 = 2: This is used for synchronous motor with motor encoder with absolute data to check this data.		
Dependency:	Refer to: p0325, p0329, p1980, p1981, p1983, r1984, r1985, r1987, p1990		
p1982[0...n]	Pole position identification selection / PolID selection		
VECTOR	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Activates the pole position identification routine to determine the commutation angle and to carry-out a plausibility check.		
Values:	0: Pole position identification off 1: Pole position identification for commutation 2: Pole position identification for plausibility check		
Recommendation:	Re p1982 = 1: This is used for synchronous motors with motor encoder without absolute data. The information/data regarding the absolute commutation angle is supplied via a track C/D, Hall sensors, an absolute encoder or from the pole position identification routine. Re p1982 = 2: This is used for synchronous motor with motor encoder with absolute data to check this data. For VECTOR, the following applies: With p1982 = 2, each time the pulses are enabled it is checked as to whether the absolute position supplied from the encoder does not exceed a deviation of 45 degrees to the identified pole wheel position.		
Dependency:	Refer to: p0325, p0329, p1980, p1981, p1983, r1984, r1985, r1987, p1990		
Note:	For sensorless operation, the pole position identification routine is selected with P1780.6		

p1983	Pole position identification, test / PolID test		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Start the pole position identification routine for test purposes. p1983 = 1: Start - is automatically set to zero after being carried-out.		
Dependency:	Refer to: p0325, p0329, p1980, p1981, p1982, r1984, r1985, r1987, p1990		
Notice:	For p1983 = 1 and if the pulses are not enabled, then the function is only executed the next time that the pulses are enabled.		
Note:	When this test is executed, it does not influence the commutation angle.		
r1984	Pole position identification, angular difference / PolID ang diff		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the angular difference between the actual electrical commutation angle and the angle determined by the pole position identification.		
Dependency:	Refer to: p0325, p0329, p1980, p1981, p1982, p1983, r1985, r1987, p1990		
Note:	When the pole position identification routine is executed several times using p1983, then using this value, then the spread of the measured values can be determined using this value. At the same position, the spread should be less than 2 degrees electrical.		
r1985	Pole position identification, saturation characteristic / PolID sat_char		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the saturation characteristic of the pole position identification routine. The values for the characteristic of the last saturation-based pole position identification routine are output every 1 ms in order to record signals (e.g. trace).		
Dependency:	Refer to: p0325, p0329, p1980, p1981, p1982, p1983, r1984, r1987, p1990		
r1987	Pole position identification trigger characteristic / PolID trig_char		
SERVO, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the trigger characteristic of the pole position identification routine. The values for the characteristic of the last pole position identification routine are output every 1 ms in order to record signals (e.g. trace). The values for the trigger characteristic and the saturation characteristic are always output in synchronism from a time perspective.		
Dependency:	Refer to: p0325, p0329, p1980, p1981, p1982, p1983, r1984, r1985		
Note:	The following information and data can be taken from the trigger characteristic. - the value -100% marks the angle at the start of the measurement. - the value +100 % marks the commutation angle determined from the pole position identification routine.		

p1990		Angular commutation offset, commissioning support / Ang_com offs COMM		
SERVO	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min 0	Max 1		Factory setting 0
Description:	<p>Activates the commissioning help to determine the angular commutation offset for the active motor. This function can be started when commissioning a build-in motor for the first time or after the encoder has been replaced.</p> <p>p1990 = 1: Activates the routine to determine the angular commutation offset</p> <p>Alarm A07971 is output while the angular commutation offset is being determined.</p> <p>p1990 is automatically set to 0 after the angular commutation offset has been determined.</p>			
Dependency:	<p>Refer to: p0325, p0329, p0431, p1980, p1981, p1982, p1983, r1984, r1985, r1987, p1999</p> <p>Refer to: A07971</p>			
Caution:	<p>In order to prevent an incorrect orientation of the electrical pole position (uncontrolled motor movement), the automatically determined angular commutation offset (p0431) should, for reasons of safety, be checked using one of the following recommendations:</p> <p>Recommendation 1:</p> <p>Set encoderless operation (p1300 = 20 or p1404 = 0), operate under no-load conditions with a speed > p1755, read the angular error in r1778; the result in r1778 should be approximately 0, for r1778 > 2 degrees, add the value to p0431 - taking into account the sign - and enter in p0431.</p> <p>Recommendation 2:</p> <p>Set the current limit to 0 (p0640 = 0), activate travel to fixed stop (p1545 = 1), record r0089[0] (phase voltage) and r0093 (electrically normalized pole position) (e.g. trace) while the motor is externally moved; in this case, the rising zero crossover of the phase voltage must coincide with the 360 ° --> 0 ° step (jump) from r0093.</p> <p>Recommendation 3:</p> <p>Measure the phase voltage U (measure phase U with respect to the virtual star point using 3 resistors) and r0093 (electrically normalized pole position); the rising zero crossover of the phase voltage must coincide with the 360 ° --> 0 ° step (jump) of r0093.</p> <p>Recommendation 4:</p> <p>Determine the average value from several results of a pole position identification routine executed as test (p1983) at various electrical angles and add the value to p0431 - taking into account the sign and enter into p0431.</p>			
Notice:	<p>For p1990 = 1 and with the pulses not enabled, the function is only executed the next time that the pulses are enabled.</p>			
Note:	<p>If fault F07414 is present, the following applies:</p> <p>First set p1990 to 1, then acknowledge the fault and then issue the enable signals.</p>			
p1990		Encoder adjustment selection / Encod adjust sel		
VECTOR	Can be changed: T			Access level: 2
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Motor identification	Units group: -		Unit selection: -
	Min 0	Max 2		Factory setting 0
Description:	<p>Setting to active the automatic encoder adjustment.</p> <p>With p1990 = 1, the angular commutation offset is saved in p0431.</p> <p>With p1990 = 2, the adjustment is checked, for deviations of greater than 6 degrees electrical, fault F07413 is issued.</p>			
Values:	<p>0: Encoder adjustment de-activated</p> <p>1: Enc adjust. active</p> <p>2: Check encoder adjustment</p>			
Dependency:	<p>In the simulation mode, the parameter cannot be written into. When selecting the encoder adjustment, the drive data set changeover is suppressed.</p> <p>Refer to: p0431, p1272, p1900</p>			

Caution:



When the encoder is being adjusted, the motor must be operated without a load - and if a motor holding brake is being used, this must be opened.

Note:

p1990 is automatically set to 0 after the encoder has been adjusted.

p1991[0...n] Motor changeover, angular commutation correction / Ang_com corr

SERVO, VECTOR

Can be changed: T

Access level: 3

Data type: Floating Point

Dynamic index: MDS, p0130

Function diagram: -

P-Group: -

Units group: -

Unit selection: -

Min

Max

Factory setting

-180 [°]

180 [°]

0 [°]

Description:

Sets the angle that is added to the commutating angle.

Caution:



If the angular correction is not correctly set, when changing over and with closed-loop torque control, the motor can accelerate to high speeds in spite of the fact that a setpoint of zero has been entered.

Notice:

For vector drives (refer to r0107), the following applies:

A fast star/delta changeover while the motor is rotating is not possible, because after an intermediate pulse inhibit, the system must first wait for the de-magnetization time (p0347) and after the "flying restart" (refer to p1200) of the motor, the excitation time (p0346) must first expire before the closed-loop control is completely operational again.

Note:

When changing-over between star and delta operation, 0° (motor data set for star operation) or 30/-30° (motor data set for delta operation) is set.

r1992 Pole position identification diagnostics / PolID diag

SERVO

Can be changed: -

Access level: 3

Data type: Unsigned16

Dynamic index: -

Function diagram: -

P-Group: -

Units group: -

Unit selection: -

Min

Max

Factory setting

-

-

0000 bin

Description:

Displays diagnostics information for the pole position identification routine.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Critical encoder fault occurred	Yes	No	-
02	Enc parking active	Yes	No	-
05	Encoder fault, Class 1	Yes	No	-
06	Encoder fault, Class 2	Yes	No	-
07	Pole position identification for encoder carried-out	Yes	No	-
08	Fine synchronization carried-out	Yes	No	-
09	Coarse synchronization carried-out	Yes	No	-
10	Commutation information available	Yes	No	-
11	Speed information available	Yes	No	-
12	Position information available	Yes	No	-
15	Zero mark passed	Yes	No	-

p1993[0...n] Pole position identification current, motion-based / PolID I mot_bas

SERVO

Can be changed: U, T

Access level: 3

Data type: Floating Point

Dynamic index: MDS, p0130

Function diagram: -

P-Group: Motor identification

Units group: -

Unit selection: -

Min

Max

Factory setting

0.00 [Aeff]

20000.00 [Aeff]

0.00 [Aeff]

Description:

Sets the current when executing the motion-based pole position identification.

Dependency:

Refer to: p1980, p1982, p1994

p1994[0...n]	Pole position identification rise time, motion-based / PolID T mot_bas		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0 [ms]	Max 2500 [ms]	Factory setting 100 [ms]
Description:	Sets the rise time of the current when executing the motion-based pole position identification.		
Dependency:	Refer to: p1980, p1982, p1993		
p1995[0...n]	Pole position identification gain, motion-based / PolID kp mot_bas		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: 17_1	Unit selection: p0505
	Min 0.000 [Nms/rad]	Max 999999.000 [Nms/rad]	Factory setting 0.300 [Nms/rad]
Description:	Sets the gain when executing the motion-based pole position identification.		
p1995[0...n]	Pole position identification gain, motion-based / PolID kp mot_bas		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: 24_2	Unit selection: p0505
	Min 0.000 [Ns/m]	Max 999999.000 [Ns/m]	Factory setting 10.000 [Ns/m]
Description:	Sets the gain when executing the motion-based pole position identification.		
p1996[0...n]	Pole position identification, integral time, motion-based / PolID Tn mot_bas		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 1.0 [ms]	Max 500.0 [ms]	Factory setting 2.0 [ms]
Description:	Sets the integral time when executing the motion-based pole position identification.		
p1997[0...n]	Pole position identification, smoothing time, motion-based / PolID t_sm mot_bas		
SERVO	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Motor identification	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 50.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the smoothing time when executing the motion-based pole position identification.		

p1999[0...n]	Ang. commutation offset calibr. and pole position ID - scaling / ComOffsCalib scal		
VECTOR (n/M)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: MDS, p0130	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10 [%]	Max 5000 [%]	Factory setting 100 [%]
Description:	Sets the scaling for the runtime of the automatic encoder calibration and the current-impressing technique for the pole position identification routine.		
Dependency:	Refer to: p0341, p0342		
Note:	For high moments of inertia, it is practical to scale the runtime of the calibration higher.		
p2000	Reference frequency / Ref freq		
A_INF, B_INF, S_INF	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0.10 [Hz]	Max 1000.00 [Hz]	Factory setting 50.00 [Hz]
Description:	Sets the reference quantity for the frequency. All frequencies specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex. The following applies: Reference frequency (in Hz)		
p2000	Reference speed reference frequency / Ref_n Ref_f		
SERVO, TM41, VEC- TOR	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 6.00 [1/min]	Max 210000.00 [1/min]	Factory setting 3000.00 [1/min]
Description:	Sets the reference quantity for speed and frequency. All speeds or frequencies specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex. The following applies: Reference frequency (in Hz) = reference speed (in (RPM) / 60)		
Dependency:	Refer to: p2001, p2002, p2003, r2004		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. Example 1: The signal of an analog input (e.g. r4055[0]) is connected to a speed setpoint (e.g. p1070[0]). The actual percentage input value is cyclically converted into the absolute speed setpoint using the reference speed (p2000). Example 2: The setpoint from PROFIBUS (r2050[1]) is connected to a speed setpoint (e.g. p1070[0]). The current input value is cyclically converted into a percentage value via the pre-specified normalization 4000H. This percentage value is converted to the absolute speed setpoint via reference speed (p2000).		

p2000	Reference velocity, reference frequency / Ref_v Ref_f		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0.60 [m/min]	Max 600.00 [m/min]	Factory setting 120.00 [m/min]
Description:	Sets the reference quantity for velocity and frequency. All velocities or frequencies specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex. The following applies: Reference frequency (in Hz) = reference velocity (in (m/min) / 60)		
Dependency:	Refer to: p2001, p2002, p2003, r2004		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. Example 1: The signal of an analog input (e.g. r4055[0]) is connected to a velocity setpoint (e.g. p1070[0]). The actual percentage input value is cyclically converted into the absolute velocity setpoint using the reference velocity (p2000). Example 2: The setpoint from PROFIBUS (r2050[1]) is connected to a velocity setpoint (e.g. p1070[0]). The current input value is cyclically converted into a percentage value via the pre-specified normalization 4000H. This percentage value is converted to the absolute velocity setpoint via reference velocity (p2000).		
p2001	Reference voltage / Reference voltage		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 10 [Veff]	Max 100000 [Veff]	Factory setting 1000 [Veff]
Description:	Sets the reference quantity for voltages. All voltages specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex.		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. For infeed units, the parameterized device supply voltage (p0210) is pre-assigned as the reference quantity. Example: The actual value of the DC link voltage (r0070) is connected to a test socket (e.g. p0771[0]). The actual voltage value is cyclically converted into a percentage of the reference voltage (p2001) and output according to the parameterized scaling.		
p2002	Reference current / Reference current		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0.10 [Aeff]	Max 100000.00 [Aeff]	Factory setting 100.00 [Aeff]
Description:	Sets the reference quantity for currents. All currents specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex.		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. For infeed units, the rated line current, that is obtained from the rated power and parameterized rated line supply voltage (p2002 = r0206 / p0210 / 1.73) is pre-assigned as the reference quantity. Example: The actual value of a phase current (r0069[0]) is connected to a test socket (e.g. p0771[0]). The actual current value is cyclically converted into a percentage of the reference current (p2002) and output according to the parameterized scaling.		

p2003	Reference torque / Reference torque		
SERVO, TM41, VEC-TOR	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 7_2	Function diagram: -
	P-Group: Communications		Unit selection: p0505
	Min 0.01 [Nm]	Max 1000000.00 [Nm]	Factory setting 1.00 [Nm]
Description:	Sets the reference quantity for torques. All torques specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex.		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. Example: The actual value of the total torque (r0079j) is connected to a test socket (e.g. p0771[0]). The actual torque is cyclically converted into a percentage of the reference torque (p2003) and output according to the parameterized scaling.		
p2003	Reference force / Reference force		
SERVO (Lin)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 8_2	Function diagram: -
	P-Group: Communications		Unit selection: p0505
	Min 0.01 [N]	Max 1000000.00 [N]	Factory setting 100.00 [N]
Description:	Sets the reference quantity for forces. All forces specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex.		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. Example: The actual value of the total force (r0079j) is connected to a test socket (e.g. p0771[0]). The actual force is cyclically converted into a percentage of the reference force (p2003) and output according to the parameterized scaling.		
r2004	Reference power / Reference power		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: 14_10	Function diagram: -
	P-Group: Communications		Unit selection: p0505
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the reference quantity for power ratings. All power ratings specified as relative value are referred to this reference quantity. The reference quantity in this parameter corresponds to 100% or 4000 hex or 4000 0000 hex.		
Dependency:	This value is calculated as voltage x current for the infeed and as torque x speed for closed-loop controls. Refer to: p2000, p2001, p2002, p2003		
Note:	If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor. The reference power is calculated as follows: - $2 * \text{Pi} * \text{reference speed} / 60 * \text{reference torque}$ (motor) - $\text{reference voltage} * \text{reference current} * \text{root}(3)$ (infeed)		

r2032		Master control, control word effective / PcCtrl STW eff		
A_INF, B_INF, S_INF	Can be changed: -		Dynamic index: -	Access level: 2
	Data type: Unsigned16		Units group: -	Function diagram: -
	P-Group: Displays, signals			Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the effective control word 1 (STW1) of the drive for the master control.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	ON/OFF1	Yes	No
	01	OC / OFF2	Yes	No
	03	Enable operation	Yes	No
	07	Acknowledge fault	Yes	No
	10	Master ctrl by PLC	Yes	No
Notice:	The master control only influences control word 1 and speed setpoint 1. Other control words/setpoints can be transferred from another automation device.			
Note:	The master control is used from the commissioning software (drive control panel) and from the Advanced Operator Panel (AOP, LOCAL mode).			

r2032		Master control, control word effective / PcCtrl STW eff		
SERVO, VECTOR	Can be changed: -		Dynamic index: -	Access level: 2
	Data type: Unsigned16		Units group: -	Function diagram: -
	P-Group: Displays, signals			Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the effective control word 1 (STW1) of the drive for the master control.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	ON/OFF1	Yes	No
	01	OC / OFF2	Yes	No
	02	OC / OFF3	Yes	No
	03	Enable operation	Yes	No
	04	Enables the ramp-function generator	Yes	No
	05	Start ramp-function generator	Yes	No
	06	Enable speed setpoint	Yes	No
	07	Acknowledge fault	Yes	No
	08	Jog bit 0	Yes	No
	09	Jog bit 1	Yes	No
	10	Master ctrl by PLC	Yes	No
Notice:	The master control only influences control word 1 and speed setpoint 1. Other control words/setpoints can be transferred from another automation device.			
Note:	The master control is used from the commissioning software (drive control panel) and from the Advanced Operator Panel (AOP, LOCAL mode).			

p2037		PROFIBUS STW1.10 = 0 mode / PB STW1.10=0 mode		
SERVO, TM41, VEC-TOR	Can be changed: T		Dynamic index: -	Access level: 3
	Data type: Integer16		Units group: -	Function diagram: -
	P-Group: Communications			Unit selection: -
	Min	Max		Factory setting
	0	2		0
Description:	Sets the processing mode for PROFIBUS STW1.10 "Control from PLC". Generally, control word 1 is received with the first PROFIBUS receive word (PZD1) (this is in conformance to the PROFIdrive profile). The behavior of STW1.10 = 0 corresponds to that of the PROFIdrive profile. For other applications that deviate from this, the behavior can be adapted using this particular parameter.			

Values: 0: Freeze setpoints and continue to process sign-of-life
 1: Freeze setpoints and sign-of-life
 2: Setpoints are not frozen

Note: If the STW1 is not transferred according to the PROFIdrive with PZD1 (with bit 10 "control by the PLC"), then p2037 should be set to 2.

p2038 PROFIBUS STW/ZSW interface mode / PB STW/ZSW interf

SERVO, VECTOR **Can be changed:** T **Access level:** 3
Data type: Integer16 **Dynamic index:** - **Function diagram:** -
P-Group: Communications **Units group:** - **Unit selection:** -

Min	Max	Factory setting
0	2	0

Description: Sets the interface mode of the PROFIBUS control and status words.
 When selecting a telegram via p0922, this parameter influences the device-specific assignment of the bits in the control and status words.

Values: 0: SINAMICS
 1: SIMODRIVE 611 universal
 2: VIK-NAMUR

Dependency: Refer to: p0922

Note: For p0922 = 100 ... 199, p2038 is automatically set to 1 and p2038 can no longer be changed. This means that for these telegrams, the "SIMODRIVE 611 universal" interface mode is set and cannot be changed.

p2038 PROFIBUS STW/ZSW interface mode / PB STW/ZSW interf

SERVO (EPOS),
 SERVO (Pos ctrl),
 VECTOR (EPOS),
 VECTOR (Pos ctrl) **Can be changed:** T **Access level:** 3
Data type: Integer16 **Dynamic index:** - **Function diagram:** -
P-Group: Communications **Units group:** - **Unit selection:** -

Min	Max	Factory setting
0	0	0

Description: Sets the interface mode of the PROFIBUS control and status words.
 When selecting a telegram via p0922, this parameter influences the device-specific assignment of the bits in the control and status words.

Values: 0: SINAMICS

Dependency: Refer to: p0922

Note: For p0922 = 100 ... 199, p2038 is automatically set to 1 and p2038 can no longer be changed. This means that for these telegrams, the "SIMODRIVE 611 universal" interface mode is set and cannot be changed.

p2039 Select debug monitor interface / Sel. debug monitor

CU_S **Can be changed:** U, T **Access level:** 4
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** -
P-Group: Communications **Units group:** - **Unit selection:** -

Min	Max	Factory setting
0	1	0

Description: The serial interface for the debug monitor is COM1 (X140) or COM2 (internal).
 Value = 0: COM2 (internal)
 Value = 1: COM1 (X140), PPI is de-activated

p2040	COMM INT monitoring time / C INT t_monit			
CU_LINK	Can be changed: U, T			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 0 [ms]	Max 65535000 [ms]		Factory setting 20 [ms]
Description:	Sets the monitoring time to monitor the process data received via COMM BOARD. If no process data is received within this time, an appropriate message is output.			
Dependency:	Refer to: F08501			
Note:	0: The monitoring is deactivated.			
p2041[0...4]	PROFIBUS detail settings / PROFIBUS detail			
CU_S	Can be changed: U, T			Access level: 4
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 0	Max 65535		Factory setting 0
p2042	PROFIBUS Ident Number / PB Ident No.			
CU_S	Can be changed: C1(1)			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 0	Max 1		Factory setting 0
Description:	Sets the PROFIBUS Ident Number (PNO-ID). SINAMICS can be operated with various identities on PROFIBUS. This allows the use of a PROFIBUS GSD that is independent of the device (e.g. PROFIdrive VIK-NAMUR with Ident Number 3AA0 hex).			
Values:	0: SINAMICS S/G 1: VIK-NAMUR			
Note:	A new setting only becomes effective after POWER ON, reset or download.			
r2043	BO: PROFIBUS PZD status / PB PZD state			
CU_S	Can be changed: -			Access level: 3
	Data type: Unsigned8	Dynamic index: -		Function diagram: 2410
	P-Group: Communications	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the PROFIBUS PZD state.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Setpoint failure	Yes	No
				FP -
Dependency:	Refer to: p2044			
Note:	When using the "setpoint failure" signal, PROFIBUS can be monitored and an application-specific response triggered when the setpoint fails.			

p2044	PROFIBUS fault delay / PB fault delay		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0 [s]	Max 100 [s]	Factory setting 0 [s]
Description:	Sets the delay time to initiate fault F01910 after a PROFIBUS setpoint failure. The time until the fault is initiated can be used by the application. This means that it is possible to respond to the failure while the drive is still operational (e.g. emergency retraction).		
Dependency:	Refer to: r2043 Refer to: F01910		
p2045	CI: PROFIBUS clock-cycle synchr. master sign-of-life, signal source / PB mast-SoS_src		
CU_S, SERVO, TM41, VECTOR (n/M)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Connector input for the sign-of-life of the clock synchronous PROFIBUS master. The sign-of-life is expected at bits 12 to 15. Bits 0 to 11 are not evaluated. The sign-of-life signal is normally received in PZD4 (control word 2) from the PROFIBUS master.		
Dependency:	Refer to: p0925, r2065		
r2050[0...4]	CO: PROFIBUS PZD receive word / PB PZD recv word		
A_INF, B_INF, CU_S, S_INF, TB30, TM15DI_DO, TM31	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Connector output to interconnect PZD (setpoints) with word format received from the PROFIBUS master.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5		

r2050[0...15]	CO: PROFIBUS PZD receive word / PB PZD rcv word		
SERVO, TM41	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 2440, 2460
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Connector output to interconnect PZD (setpoints) with word format received from the PROFIBUS master.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16		
Dependency:	Refer to: r2060		

r2050[0...31]	CO: PROFIBUS PZD receive word / PB PZD rcv word		
VECTOR	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 2440, 2460
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Connector output to interconnect PZD (setpoints) with word format received from the PROFIBUS master.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19 [19] = PZD 20 [20] = PZD 21 [21] = PZD 22		

[22] = PZD 23
 [23] = PZD 24
 [24] = PZD 25
 [25] = PZD 26
 [26] = PZD 27
 [27] = PZD 28
 [28] = PZD 29
 [29] = PZD 30
 [30] = PZD 31
 [31] = PZD 32

Dependency: Refer to: r2060

p2051[0...14] CI: PROFIBUS PZD send word / PB PZD send word

CU_S	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Communications		Unit selection: -
	Min	Max	Factory setting
	-	-	0

Description: Selects the PZD (actual values) with word format to be sent to the PROFIBUS master.

Index:

[0] = PZD 1
 [1] = PZD 2
 [2] = PZD 3
 [3] = PZD 4
 [4] = PZD 5
 [5] = PZD 6
 [6] = PZD 7
 [7] = PZD 8
 [8] = PZD 9
 [9] = PZD 10
 [10] = PZD 11
 [11] = PZD 12
 [12] = PZD 13
 [13] = PZD 14
 [14] = PZD 15

p2051[0...4] CI: PROFIBUS PZD send word / PB PZD send word

A_INF, B_INF, S_INF, TB30, TM15DI_DO, TM31	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Communications		Unit selection: -
	Min	Max	Factory setting
	-	-	0

Description: Selects the PZD (actual values) with word format to be sent to the PROFIBUS master.

Index:

[0] = PZD 1
 [1] = PZD 2
 [2] = PZD 3
 [3] = PZD 4
 [4] = PZD 5

p2051[0...18]	CI: PROFIBUS PZD send word / PB PZD send word		
SERVO, TM41	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects the PZD (actual values) with word format to be sent to the PROFIBUS master.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19		
Dependency:	Refer to: p2061		

p2051[0...31]	CI: PROFIBUS PZD send word / PB PZD send word		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects the PZD (actual values) with word format to be sent to the PROFIBUS master.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19 [19] = PZD 20 [20] = PZD 21		

[21] = PZD 22
 [22] = PZD 23
 [23] = PZD 24
 [24] = PZD 25
 [25] = PZD 26
 [26] = PZD 27
 [27] = PZD 28
 [28] = PZD 29
 [29] = PZD 30
 [30] = PZD 31
 [31] = PZD 32

Dependency: Refer to: p2061

r2053[0...14] PROFIBUS diagnostics send PZD word / PB diag send word

CU_S

Can be changed: -

Access level: 3

Data type: Unsigned16

Dynamic index: -

Function diagram: -

P-Group: Communications

Units group: -

Unit selection: -

Min

Max

Factory setting

-

-

0000 bin

Description:

Displays the PZD (actual values) with word format sent to the PROFIBUS master.

Index:

[0] = PZD 1
 [1] = PZD 2
 [2] = PZD 3
 [3] = PZD 4
 [4] = PZD 5
 [5] = PZD 6
 [6] = PZD 7
 [7] = PZD 8
 [8] = PZD 9
 [9] = PZD 10
 [10] = PZD 11
 [11] = PZD 12
 [12] = PZD 13
 [13] = PZD 14
 [14] = PZD 15

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Bit 0	On	Off	-
01	Bit 1	On	Off	-
02	Bit 2	On	Off	-
03	Bit 3	On	Off	-
04	Bit 4	On	Off	-
05	Bit 5	On	Off	-
06	Bit 6	On	Off	-
07	Bit 7	On	Off	-
08	Bit 8	On	Off	-
09	Bit 9	On	Off	-
10	Bit 10	On	Off	-
11	Bit 11	On	Off	-
12	Bit 12	On	Off	-
13	Bit 13	On	Off	-
14	Bit 14	On	Off	-
15	Bit 15	On	Off	-

r2053[0...4]	PROFIBUS diagnostics send PZD word / PB diag send word				
A_INF, B_INF, S_INF, TB30, TM15DI_DO, TM31	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned16		Function diagram: -		
	P-Group: Communications	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the PZD (actual values) with word format sent to the PROFIBUS master.				
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-

r2053[0...18]		PROFIBUS diagnostics send PZD word / PB diag send word			
SERVO, TM41	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 2450, 2470	
	P-Group: Communications	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the PZD (actual values) with word format sent to the PROFIBUS master.				
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: p2051, p2061				

r2053[0...31] PROFIBUS diagnostics send PZD word / PB diag send word					
VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16		Dynamic index: -	Function diagram: 2450, 2470	
	P-Group: Communications		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Displays the PZD (actual values) with word format sent to the PROFIBUS master.				
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19 [19] = PZD 20 [20] = PZD 21 [21] = PZD 22 [22] = PZD 23 [23] = PZD 24 [24] = PZD 25 [25] = PZD 26 [26] = PZD 27 [27] = PZD 28 [28] = PZD 29 [29] = PZD 30 [30] = PZD 31 [31] = PZD 32				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: p2051, p2061				

r2054	PROFIBUS status / PB status		
CU_S	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	4	0
Description:	Status display for the PROFIBUS interface.		
Values:	0: Off 1: No connection (baud rate search) 2: Connection O. K. (baud rate found) 3: Cyclic connection with master (data exchange) 4: Cyclic data O. K.		
Note:	Re r2054 = 3: In state 3 (the LED flashes green), a cyclic connection has been established to the PROFIBUS master; however, one of the following prerequisites is missing for cyclic operation: - No setpoints are being received as the PROFIBUS master is in the STOP condition. Only for clock-cycle synchronous operation, the following applies: - The drive is not in synchronism as the global control (GC) has an error. Re r2054 = 4: In the status 4 (LED green), the cyclic connection to the PROFIBUS master has been established and setpoints are being received. The clock cycle synchronization is OK, the global control (GC) is error-free. This state does not provide any statement regarding the quality of the clock cycle synchronous sign-of-life characters on the drive objects.		
r2054	COMM INT state / C INT state		
CU_LINK	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	255	0
Description:	Status display for the internal communications interface.		
Values:	0: No initialization 1: Fatal Error 2: Initialization 3: Send configuration 4: Receive configuration 5: Non-cyclic communication 6: Cyclic communications but no setpoints (stop/no clock cycle) 255: Cyclic communication		
r2055[0...2]	PROFIBUS diagnostics standard / PB diag standard		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Diagnostics display for the PROFIBUS interface.		
Index:	[0] = Master bus address [1] = Master input total length bytes [2] = Master output total length bytes		

r2056[0...19]	PROFIBUS diagnostics expert / PB diag experts		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
r2057	PROFIBUS address switch, diagnostics / PB addr diagn		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the setting of the PROFIBUS address switch "DP ADDRESS" on the Control Unit.		
Dependency:	Refer to: p0918		
r2058[0...139]	COMM INT receive configuration data / C INT E_config_dat		
CU_LINK	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the configuration data received via COMM BOARD.		
r2059[0...7]	COMM INT identification data / C INT ident_dat		
CU_LINK	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the identification data of the COMM BOARD.		
Note:	Index 0: CB data structure version (e.g.: 100 = V1.00). Index 1: CB driver version (e.g.: 100 = V1.00). Index 2: Company, (e.g.: 42 = Siemens). Index 3: Device type Index 4: Firmware version. Index 5: Firmware date (year). Index 6: Firmware date (day/month).		
r2060[0...14]	CO: PROFIBUS PZD receive double word / PB PZD recv DW		
SERVO, TM41	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: 2440, 2460
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Connector output to interconnect PZD (setpoints) with double word format received from the PROFIBUS master.		

Index:

- [0] = PZD 1 + 2
- [1] = PZD 2 + 3
- [2] = PZD 3 + 4
- [3] = PZD 4 + 5
- [4] = PZD 5 + 6
- [5] = PZD 6 + 7
- [6] = PZD 7 + 8
- [7] = PZD 8 + 9
- [8] = PZD 9 + 10
- [9] = PZD 10 + 11
- [10] = PZD 11 + 12
- [11] = PZD 12 + 13
- [12] = PZD 13 + 14
- [13] = PZD 14 + 15
- [14] = PZD 15 + 16

Dependency: Refer to: r2050

r2060[0...30] CO: PROFIBUS PZD receive double word / PB PZD recv DW

VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Integer32		Function diagram: 2440, 2460
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Connector output to interconnect PZD (setpoints) with double word format received from the PROFIBUS master.

Index:

- [0] = PZD 1 + 2
- [1] = PZD 2 + 3
- [2] = PZD 3 + 4
- [3] = PZD 4 + 5
- [4] = PZD 5 + 6
- [5] = PZD 6 + 7
- [6] = PZD 7 + 8
- [7] = PZD 8 + 9
- [8] = PZD 9 + 10
- [9] = PZD 10 + 11
- [10] = PZD 11 + 12
- [11] = PZD 12 + 13
- [12] = PZD 13 + 14
- [13] = PZD 14 + 15
- [14] = PZD 15 + 16
- [15] = PZD 16 + 17
- [16] = PZD 17 + 18
- [17] = PZD 18 + 19
- [18] = PZD 19 + 20
- [19] = PZD 20 + 21
- [20] = PZD 21 + 22
- [21] = PZD 22 + 23
- [22] = PZD 23 + 24
- [23] = PZD 24 + 25
- [24] = PZD 25 + 26
- [25] = PZD 26 + 27
- [26] = PZD 27 + 28
- [27] = PZD 28 + 29
- [28] = PZD 29 + 30
- [29] = PZD 30 + 31
- [30] = PZD 31 + 32

Dependency: Refer to: r2050

p2061[0...14]	CI: PROFIBUS PZD send double word / PB PZD send DW		
SERVO, TM41	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects the PZD (actual values) with double word format to be sent to the PROFIBUS master.		
Index:	[0] = PZD 1 + 2 [1] = PZD 2 + 3 [2] = PZD 3 + 4 [3] = PZD 4 + 5 [4] = PZD 5 + 6 [5] = PZD 6 + 7 [6] = PZD 7 + 8 [7] = PZD 8 + 9 [8] = PZD 9 + 10 [9] = PZD 10 + 11 [10] = PZD 11 + 12 [11] = PZD 12 + 13 [12] = PZD 13 + 14 [13] = PZD 14 + 15 [14] = PZD 15 + 16		
Dependency:	Refer to: p2051		

p2061[0...30]	CI: PROFIBUS PZD send double word / PB PZD send DW		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2470
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects the PZD (actual values) with double word format to be sent to the PROFIBUS master.		
Index:	[0] = PZD 1 + 2 [1] = PZD 2 + 3 [2] = PZD 3 + 4 [3] = PZD 4 + 5 [4] = PZD 5 + 6 [5] = PZD 6 + 7 [6] = PZD 7 + 8 [7] = PZD 8 + 9 [8] = PZD 9 + 10 [9] = PZD 10 + 11 [10] = PZD 11 + 12 [11] = PZD 12 + 13 [12] = PZD 13 + 14 [13] = PZD 14 + 15 [14] = PZD 15 + 16 [15] = PZD 16 + 17 [16] = PZD 17 + 18 [17] = PZD 18 + 19 [18] = PZD 19 + 20 [19] = PZD 20 + 21 [20] = PZD 21 + 22 [21] = PZD 22 + 23 [22] = PZD 23 + 24 [23] = PZD 24 + 25 [24] = PZD 25 + 26		

[25] = PZD 26 + 27
 [26] = PZD 27 + 28
 [27] = PZD 28 + 29
 [28] = PZD 29 + 30
 [29] = PZD 30 + 31
 [30] = PZD 31 + 32

Dependency: Refer to: p2051

r2063[0...14] PROFIBUS diagnostics PZD send double word / PB diag send DW

SERVO, TM41

Can be changed: -

Access level: 3

Data type: Unsigned32

Dynamic index: -

Function diagram: 2450,
2470

P-Group: Communications

Units group: -

Unit selection: -

Min

Max

Factory setting

-

-

0000 bin

Description: Displays the PZD (actual values) with double word format sent to the PROFIBUS master.

Index:

[0] = PZD 1 + 2
 [1] = PZD 2 + 3
 [2] = PZD 3 + 4
 [3] = PZD 4 + 5
 [4] = PZD 5 + 6
 [5] = PZD 6 + 7
 [6] = PZD 7 + 8
 [7] = PZD 8 + 9
 [8] = PZD 9 + 10
 [9] = PZD 10 + 11
 [10] = PZD 11 + 12
 [11] = PZD 12 + 13
 [12] = PZD 13 + 14
 [13] = PZD 14 + 15
 [14] = PZD 15 + 16

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Bit 0	On	Off	-
01	Bit 1	On	Off	-
02	Bit 2	On	Off	-
03	Bit 3	On	Off	-
04	Bit 4	On	Off	-
05	Bit 5	On	Off	-
06	Bit 6	On	Off	-
07	Bit 7	On	Off	-
08	Bit 8	On	Off	-
09	Bit 9	On	Off	-
10	Bit 10	On	Off	-
11	Bit 11	On	Off	-
12	Bit 12	On	Off	-
13	Bit 13	On	Off	-
14	Bit 14	On	Off	-
15	Bit 15	On	Off	-
16	Bit 16	On	Off	-
17	Bit 17	On	Off	-
18	Bit 18	On	Off	-
19	Bit 19	On	Off	-
20	Bit 20	On	Off	-
21	Bit 21	On	Off	-

22	Bit 22	On	Off	-
23	Bit 23	On	Off	-
24	Bit 24	On	Off	-
25	Bit 25	On	Off	-
26	Bit 26	On	Off	-
27	Bit 27	On	Off	-
28	Bit 28	On	Off	-
29	Bit 29	On	Off	-
30	Bit 30	On	Off	-
31	Bit 31	On	Off	-

r2063[0...30] PROFIBUS diagnostics PZD send double word / PB diag send DW

VECTOR

Can be changed: -**Access level:** 3**Data type:** Unsigned32**Dynamic index:** -**Function diagram:** 2450,
2470**P-Group:** Communications**Units group:** -**Unit selection:** -**Min****Max****Factory setting**
0000 bin**Description:**

Displays the PZD (actual values) with double word format sent to the PROFIBUS master.

Index:

[0] = PZD 1 + 2
 [1] = PZD 2 + 3
 [2] = PZD 3 + 4
 [3] = PZD 4 + 5
 [4] = PZD 5 + 6
 [5] = PZD 6 + 7
 [6] = PZD 7 + 8
 [7] = PZD 8 + 9
 [8] = PZD 9 + 10
 [9] = PZD 10 + 11
 [10] = PZD 11 + 12
 [11] = PZD 12 + 13
 [12] = PZD 13 + 14
 [13] = PZD 14 + 15
 [14] = PZD 15 + 16
 [15] = PZD 16 + 17
 [16] = PZD 17 + 18
 [17] = PZD 18 + 19
 [18] = PZD 19 + 20
 [19] = PZD 20 + 21
 [20] = PZD 21 + 22
 [21] = PZD 22 + 23
 [22] = PZD 23 + 24
 [23] = PZD 24 + 25
 [24] = PZD 25 + 26
 [25] = PZD 26 + 27
 [26] = PZD 27 + 28
 [27] = PZD 28 + 29
 [28] = PZD 29 + 30
 [29] = PZD 30 + 31
 [30] = PZD 31 + 32

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Bit 0	On	Off	-
01	Bit 1	On	Off	-
02	Bit 2	On	Off	-
03	Bit 3	On	Off	-
04	Bit 4	On	Off	-
05	Bit 5	On	Off	-
06	Bit 6	On	Off	-
07	Bit 7	On	Off	-
08	Bit 8	On	Off	-
09	Bit 9	On	Off	-

10	Bit 10	On	Off	-
11	Bit 11	On	Off	-
12	Bit 12	On	Off	-
13	Bit 13	On	Off	-
14	Bit 14	On	Off	-
15	Bit 15	On	Off	-
16	Bit 16	On	Off	-
17	Bit 17	On	Off	-
18	Bit 18	On	Off	-
19	Bit 19	On	Off	-
20	Bit 20	On	Off	-
21	Bit 21	On	Off	-
22	Bit 22	On	Off	-
23	Bit 23	On	Off	-
24	Bit 24	On	Off	-
25	Bit 25	On	Off	-
26	Bit 26	On	Off	-
27	Bit 27	On	Off	-
28	Bit 28	On	Off	-
29	Bit 29	On	Off	-
30	Bit 30	On	Off	-
31	Bit 31	On	Off	-

r2064[0...7] PROFIBUS diagnostics clock synchronous mode / PB diag clock sync

CU_S	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the last parameter received from the PROFIBUS master for clock synchronism. The parameters for clock synchronism are created when configuring the bus and are transferred at the start of cyclic operation from the PROFIBUS master to the slave.

Index:
 [0] = Clock synchronous mode activated
 [1] = Bus cycle time (Tdp) [μs]
 [2] = Master cycle time (Tmapc) [μs]
 [3] = Instant of actual value acquisition (Ti) [μs]
 [4] = Instant of setpoint acquisition (To) [μs]
 [5] = Data exchange interval (Tdx) [μs]
 [6] = PLL window (Tpll-w) [1/12 μs]
 [7] = PLL delay time (Tpll-d) [1/12 μs]

r2065 PROFIBUS master sign-of-life, diagnostics / PB master SoL diag

CU_S, SERVO, TM41, VECTOR (n/M)	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 2410
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays how often the sign-of-life from the clock synchronous PROFIBUS master failed. An appropriate fault is output when the tolerance, specified in p0925, is exceeded.

Dependency: Refer to: F01912

r2074[0...4]	PROFIBUS diagnostics bus address PZD receive / PB diag addr recv		
A_INF, B_INF, CU_S, S_INF, TB30, TM15DI_DO, TM31	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PROFIBUS address of sender from which the PZD is received.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5		
Note:	Value range: 0 - 125: Bus address of the sender 255: Not occupied		

r2074[0...15]	PROFIBUS diagnostics bus address PZD receive / PB diag addr recv		
SERVO, TM41	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PROFIBUS address of sender from which the PZD is received.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16		
Note:	Value range: 0 - 125: Bus address of the sender 255: Not occupied		

r2074[0...31]	PROFIBUS diagnostics bus address PZD receive / PB diag addr recv		
VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PROFIBUS address of sender from which the PZD is received.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19 [19] = PZD 20 [20] = PZD 21 [21] = PZD 22 [22] = PZD 23 [23] = PZD 24 [24] = PZD 25 [25] = PZD 26 [26] = PZD 27 [27] = PZD 28 [28] = PZD 29 [29] = PZD 30 [30] = PZD 31 [31] = PZD 32		
Note:	Value range: 0 - 125: Bus address of the sender 255: Not occupied		

r2075[0...4]	PROFIBUS diagnostics telegram offset PZD receive / PB diag offs recv		
A_INF, B_INF, CU_S, S_INF, TB30, TM15DI_DO, TM31	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Communications	Unit selection: -	
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS receive telegram (master output).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5		
Note:	Value range: 0 - 242: Byte offset 255: Not occupied		

r2075[0...15]	PROFIBUS diagnostics telegram offset PZD receive / PB diag offs recv		
SERVO, TM41	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Communications	Unit selection: -	
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS receive telegram (master output).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16		
Note:	Value range: 0 - 242: Byte offset 255: Not occupied		

r2075[0...31] PROFIBUS diagnostics telegram offset PZD receive / PB diag offs recv			
VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS receive telegram (master output).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19 [19] = PZD 20 [20] = PZD 21 [21] = PZD 22 [22] = PZD 23 [23] = PZD 24 [24] = PZD 25 [25] = PZD 26 [26] = PZD 27 [27] = PZD 28 [28] = PZD 29 [29] = PZD 30 [30] = PZD 31 [31] = PZD 32		
Note:	Value range: 0 - 242: Byte offset 255: Not occupied		

r2076[0...6] PROFIBUS PZD diagnostics telegram offset send / PB diag offs send			
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS send telegram (master input).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7		

Note: Value range:
0 - 242: Byte offset
255: Not occupied

r2076[0...4]	PROFIBUS PZD diagnostics telegram offset send / PB diag offs send		
A_INF, B_INF, S_INF, TB30, TM15DI_DO, TM31	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS send telegram (master input).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5		
Note:	Value range: 0 - 242: Byte offset 255: Not occupied		

r2076[0...18]	PROFIBUS PZD diagnostics telegram offset send / PB diag offs send		
SERVO, TM41	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS send telegram (master input).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19		
Note:	Value range: 0 - 242: Byte offset 255: Not occupied		

r2076[0...31] PROFIBUS PZD diagnostics telegram offset send / PB diag offs send			
VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	PZD byte offset in the PROFIBUS send telegram (master input).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16 [16] = PZD 17 [17] = PZD 18 [18] = PZD 19 [19] = PZD 20 [20] = PZD 21 [21] = PZD 22 [22] = PZD 23 [23] = PZD 24 [24] = PZD 25 [25] = PZD 26 [26] = PZD 27 [27] = PZD 28 [28] = PZD 29 [29] = PZD 30 [30] = PZD 31 [31] = PZD 32		
Note:	Value range: 0 - 242: Byte offset 255: Not occupied		

r2077[0...15] PROFIBUS diagnostics peer-to-peer data transfer addresses / PB diag peer addr			
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the addresses of the slaves (peers) where peer-to-peer data transfer has been configured via PROFIBUS.		

p2079	PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
CU_S	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 390	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded. If, with p922, a value not equal to 999 is set, then p2079 has the same value and is inhibited. All of the interconnections contained in the telegram are inhibited. Also expansions are inhibited. If p922 is set to 999, then p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set. If p922 = 999, and with p2079, a value is set that is not equal to 999, then the interconnections contained in the telegram are inhibited, but the telegram can be expanded.		
Values:	390: SIEMENS telegram 390, PZD-1/1 391: SIEMENS telegram 391, PZD-3/7 392: SIEMENS telegram 392, PZD-3/15 999: Free telegram configuration with BICO		
p2079	PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
A_INF, B_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 370	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded. For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited. For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set. For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.		
Values:	370: SIEMENS telegram 370, PZD-1/1 999: Free telegram configuration with BICO		
Dependency:	Refer to: p0922		
p2079	PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
SERVO	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 2	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded. For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited. For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set. For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.		

Values:	2: Standard telegram 2, PZD-4/4
	3: Standard telegram 3, PZD-5/9
	4: Standard telegram 4, PZD-6/14
	5: Standard telegram 5, PZD-9/9
	6: Standard telegram 6, PZD-10/14
	102: SIEMENS telegram 102, PZD-6/10
	103: SIEMENS telegram 103, PZD-7/15
	105: SIEMENS telegram 105, PZD-10/10
	106: SIEMENS telegram 106, PZD-11/15
	116: SIEMENS telegram 116, PZD-11/19
	999: Free telegram configuration with BICO
Dependency:	Refer to: p0922

p2079 PROFIBUS PZD telegram selection extended / PB PZD tlg exten.

SERVO (Pos ctrl)	Can be changed: T	Access level: 3
	Data type: Integer16	Dynamic index: -
	P-Group: Communications	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	999	999
		Factory setting
		999

Description: Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded.

For p0922 < 999 the following applies:
p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited.

For p0922 = 999 the following applies:
p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set.

For p0922 = 999 and p2079 < 999 the following applies:
The interconnections contained in the telegram are inhibited. However, the telegram can be extended.

Values:	999: Free telegram configuration with BICO
Dependency:	Refer to: p0922

p2079 PROFIBUS PZD telegram selection extended / PB PZD tlg exten.

SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Access level: 3
	Data type: Integer16	Dynamic index: -
	P-Group: Communications	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	7	999
		Factory setting
		999

Description: Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded.

For p0922 < 999 the following applies:
p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited.

For p0922 = 999 the following applies:
p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set.

For p0922 = 999 and p2079 < 999 the following applies:
The interconnections contained in the telegram are inhibited. However, the telegram can be extended.

Values:	7: Standard telegram 7, PZD-2/2
	110: SIEMENS telegram 110, PZD-12/7
	999: Free telegram configuration with BICO
Dependency:	Refer to: p0922

p2079		PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
SERVO (Extended setp.)	Can be changed: T			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 1	Max 999		Factory setting 999
Description:	<p>Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded.</p> <p>For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited.</p> <p>For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set.</p> <p>For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.</p>			
Values:	<ul style="list-style-type: none"> 1: Standard telegram 1, PZD-2/2 2: Standard telegram 2, PZD-4/4 3: Standard telegram 3, PZD-5/9 4: Standard telegram 4, PZD-6/14 5: Standard telegram 5, PZD-9/9 6: Standard telegram 6, PZD-10/14 102: SIEMENS telegram 102, PZD-6/10 103: SIEMENS telegram 103, PZD-7/15 105: SIEMENS telegram 105, PZD-10/10 106: SIEMENS telegram 106, PZD-11/15 116: SIEMENS telegram 116, PZD-11/19 999: Free telegram configuration with BICO 			
Dependency:	Refer to: p0922			

p2079		PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
VECTOR	Can be changed: T			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 1	Max 999		Factory setting 999
Description:	<p>Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded.</p> <p>For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited.</p> <p>For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set.</p> <p>For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.</p>			
Values:	<ul style="list-style-type: none"> 1: Standard telegram 1, PZD-2/2 2: Standard telegram 2, PZD-4/4 20: Standard telegram 20, PZD-2/6 352: SIEMENS telegram 352, PZD-6/6 999: Free telegram configuration with BICO 			
Dependency:	Refer to: p0922			

p2079		PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
VECTOR (n/M)	Can be changed: T			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 1	Max 999		Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded. For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited. For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set. For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.			
Values:	1: Standard telegram 1, PZD-2/2 2: Standard telegram 2, PZD-4/4 3: Standard telegram 3, PZD-5/9 4: Standard telegram 4, PZD-6/14 20: Standard telegram 20, PZD-2/6 352: SIEMENS telegram 352, PZD-6/6 999: Free telegram configuration with BICO			
Dependency:	Refer to: p0922			

p2079		PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
VECTOR (Pos ctrl)	Can be changed: T			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Communications	Units group: -		Unit selection: -
	Min 2	Max 999		Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded. For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited. For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set. For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.			
Values:	2: Standard telegram 2, PZD-4/4 999: Free telegram configuration with BICO			
Dependency:	Refer to: p0922			

p2079	PROFIBUS PZD telegram selection extended / PB PZD tlg exten.		
TM41	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 3	Max 999	Factory setting 999
Description:	Sets the send and receive telegram for PROFIBUS. Contrary to p922, a telegram can be selected using p2079 and subsequently expanded. For p0922 < 999 the following applies: p2079 has the same value and is inhibited. All of the interconnections and extensions contained in the telegram are inhibited. For p0922 = 999 the following applies: p2079 can be freely set. If p2079 is also set to 999, then all of the interconnections can be set. For p0922 = 999 and p2079 < 999 the following applies: The interconnections contained in the telegram are inhibited. However, the telegram can be extended.		
Values:	3: Standard telegram 3, PZD-5/9 999: Free telegram configuration with BICO		
Dependency:	Refer to: p0922		
p2080[0...15]	BI: PROFIBUS send status word 1 / PB STW1 bit sel.		
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2472
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Selects bits to be sent to the PROFIBUS master. The individual bits are combined to form status word 1.		
Index:	[0] = Bit 0 [1] = Bit 1 [2] = Bit 2 [3] = Bit 3 [4] = Bit 4 [5] = Bit 5 [6] = Bit 6 [7] = Bit 7 [8] = Bit 8 [9] = Bit 9 [10] = Bit 10 [11] = Bit 11 [12] = Bit 12 [13] = Bit 13 [14] = Bit 14 [15] = Bit 15		
Dependency:	Refer to: p2088, r2089		

p2081[0...15]	BI: PROFIBUS send status word 2 / PB STW2 bit sel.		
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 2472
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Selects bits to be sent to the PROFIBUS master. The individual bits are combined to form status word 2.		
Index:	[0] = Bit 0 [1] = Bit 1 [2] = Bit 2 [3] = Bit 3 [4] = Bit 4 [5] = Bit 5 [6] = Bit 6 [7] = Bit 7 [8] = Bit 8 [9] = Bit 9 [10] = Bit 10 [11] = Bit 11 [12] = Bit 12 [13] = Bit 13 [14] = Bit 14 [15] = Bit 15		
Dependency:	Refer to: p2088, r2089		
Note:	When using the clock synchronous (isochronous) PROFIBUS with sign-of-life in status word 2, bit 12 to 15 are reserved to transfer the sign-of-life and may not be freely interconnected.		
p2082[0...15]	BI: PROFIBUS send free status word 3 / PB ZSW3 bit sel.		
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 2472
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Selects bits to be sent to the PROFIBUS master. The individual bits are combined to form free status word 3.		
Index:	[0] = Bit 0 [1] = Bit 1 [2] = Bit 2 [3] = Bit 3 [4] = Bit 4 [5] = Bit 5 [6] = Bit 6 [7] = Bit 7 [8] = Bit 8 [9] = Bit 9 [10] = Bit 10 [11] = Bit 11 [12] = Bit 12 [13] = Bit 13 [14] = Bit 14 [15] = Bit 15		
Dependency:	Refer to: p2088, r2089		

p2083[0...15]	BI: PROFIBUS send free status word 4 / PB ZSW4 bit sel.		
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 2472
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Selects bits to be sent to the PROFIBUS master. The individual bits are combined to form free status word 4.		
Index:	[0] = Bit 0 [1] = Bit 1 [2] = Bit 2 [3] = Bit 3 [4] = Bit 4 [5] = Bit 5 [6] = Bit 6 [7] = Bit 7 [8] = Bit 8 [9] = Bit 9 [10] = Bit 10 [11] = Bit 11 [12] = Bit 12 [13] = Bit 13 [14] = Bit 14 [15] = Bit 15		
Dependency:	Refer to: p2088, r2089		

p2088[0...3]	PROFIBUS invert status word / Invert PB ZSW				
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T	Dynamic index: -	Access level: 3		
	Data type: Unsigned16		Function diagram: 2472		
	P-Group: Communications	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Setting to invert the individual binector inputs of the binector connector converter.				
Index:	[0] = Status word 1 [1] = Status word 2 [2] = Free status word 3 [3] = Free status word 4				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	Inverted	Not inverted	-
	01	Bit 1	Inverted	Not inverted	-
	02	Bit 2	Inverted	Not inverted	-
	03	Bit 3	Inverted	Not inverted	-
	04	Bit 4	Inverted	Not inverted	-
	05	Bit 5	Inverted	Not inverted	-

06	Bit 6	Inverted	Not inverted	-
07	Bit 7	Inverted	Not inverted	-
08	Bit 8	Inverted	Not inverted	-
09	Bit 9	Inverted	Not inverted	-
10	Bit 10	Inverted	Not inverted	-
11	Bit 11	Inverted	Not inverted	-
12	Bit 12	Inverted	Not inverted	-
13	Bit 13	Inverted	Not inverted	-
14	Bit 14	Inverted	Not inverted	-
15	Bit 15	Inverted	Not inverted	-

Dependency: Refer to: p2080, p2081, p2082, p2083, r2089

r2089[0...3] CO: PROFIBUS send status word / Send PB ZSW

A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR

Can be changed: - **Access level:** 3

Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 2472

P-Group: Communications **Units group:** - **Unit selection:** -

Min **Max** **Factory setting**

- - -

Description: Connector output to interconnect the status words to a PROFIBUS PZD send word.

Index: [0] = Status word 1
[1] = Status word 2
[2] = Free status word 3
[3] = Free status word 4

Dependency: Refer to: p2051, p2080, p2081, p2082, p2083

Note: r2089 together with p2080 to p2083 forms four binector-connector converters.

r2090 BO: PROFIBUS PZD1 receive bit-serial / PB PZD1 recv bitw

A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR

Can be changed: - **Access level:** 3

Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 2460

P-Group: Communications **Units group:** - **Unit selection:** -

Min **Max** **Factory setting**

- - 0000 bin

Description: Binector output for bit-serial interconnection of PZD1 (normally control word 1) received from the PROFIBUS master.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-

r2091		BO: PROFIBUS PZD2 received bit-serial / PB PZD2 rcv bitw			
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned16		Function diagram: 2460		
	P-Group: Communications	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Binector output for bit-serial interconnection of PZD2 received from the PROFIBUS master.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-

r2092		BO: PROFIBUS PZD3 received bit-serial / PB PZD3 rcv bitw			
SERVO, TM41, VEC- TOR	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned16		Function diagram: 2460		
	P-Group: Communications	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Binector output for bit-serial interconnection of PZD3 received from the PROFIBUS master.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-

r2093		BO: PROFIBUS PZD4 received bit-serial / PB PZD4 rcv bitw			
SERVO, TM41, VEC-TOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16		Dynamic index: -	Function diagram: 2460	
	P-Group: Communications		Units group: -	Unit selection: -	
	Min -		Max -	Factory setting 0000 bin	
Description:	Binector output for bit-serial interconnection of PZD4 (normally control word 2) received from the PROFIBUS master.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
r2094		BO: PROFIBUS PZD received bit-serial / PB PZD rcv bitw			
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16		Dynamic index: -	Function diagram: 2460	
	P-Group: Communications		Units group: -	Unit selection: -	
	Min -		Max -	Factory setting 0000 bin	
Description:	Binector output for bit-serial onward interconnection of a PZD word received from the PROFIBUS master . The PZD is selected via p2099[0].				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: p2099				

r2095		BO: PROFIBUS PZD received bit-serial / PB PZD rcv bitw			
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: -	Data type: Unsigned16	Dynamic index: -	Access level: 3 Function diagram: 2460	
	P-Group: Communications	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Binector output for bit-serial interconnection of a PZD word received from the PROFIBUS master. The PZD is selected via p2099[1].				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: p2099				

p2098[0...1] Invert connector-binector converter bit-serial / CI_BO conv inv					
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T			Access level: 3	
	Data type: Unsigned16		Dynamic index: -	Function diagram: 2460	
	P-Group: Communications		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Setting to invert the individual binector outputs of the connector-binector converter. Using p2098[0], the signals of CI: p2099[0] are influenced. Using p2098[1], the signals of CI: p2099[1] are influenced.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	Inverted	Not inverted	-
	01	Bit 1	Inverted	Not inverted	-
	02	Bit 2	Inverted	Not inverted	-
	03	Bit 3	Inverted	Not inverted	-
	04	Bit 4	Inverted	Not inverted	-
	05	Bit 5	Inverted	Not inverted	-
	06	Bit 6	Inverted	Not inverted	-
	07	Bit 7	Inverted	Not inverted	-
	08	Bit 8	Inverted	Not inverted	-
	09	Bit 9	Inverted	Not inverted	-
	10	Bit 10	Inverted	Not inverted	-
	11	Bit 11	Inverted	Not inverted	-
	12	Bit 12	Inverted	Not inverted	-
	13	Bit 13	Inverted	Not inverted	-
	14	Bit 14	Inverted	Not inverted	-
	15	Bit 15	Inverted	Not inverted	-
Dependency:	Refer to: r2094, r2095, p2099				
Note:	Bit x = 1: Inverts the appropriate binector output. Bit x = 0: No inversion.				

p2099[0...1] CI: PROFIBUS PZD selection receive bit-serial / Select CO_BO conv					
A_INF, B_INF, CU_S, SERVO, S_INF, TB30, TM15DI_DO, TM31, TM41, VECTOR	Can be changed: U, T			Access level: 3	
	Data type: Unsigned32		Dynamic index: -	Function diagram: 2460	
	P-Group: Communications		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0	
Description:	Selects a PROFIBUS PZD receive word for bit-serial interconnection.				
Dependency:	Refer to: r2094, r2095				
Note:	p2099 together with r2094 and r2095 forms two connector-binector converters: Connector input p2099[0] to binector outputs in r2094 Connector input p2099[1] to binector outputs in r2095				

p2100[0...19] Setting the fault number for fault response / F_no F response			
All objects	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1750, 8075
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting [0] 0 [1] 0 [2] 0 [3] 0 [4] 0 [5] 0 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0
Description:	Selects the faults for which the fault response should be changed		
Dependency:	The fault is selected and the required response is set under the same index. Refer to: p2101		
Notice:	For the following cases, it is not possible to re-parameterize the fault response to a fault: - if there is no existing fault number. - the message type is not "fault" (F). - when a fault is present.		

p2101[0...19] Setting the fault response / Fault response			
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Integer16	Dynamic index: -	Access level: 3 Function diagram: 1750, 8075
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 0	Factory setting [0] 0 [1] 0 [2] 0 [3] 0 [4] 0 [5] 0 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0
Description:	Sets the fault response for the selected fault.		
Values:	0: NONE		
Dependency:	The fault is selected and the required response is set under the same index.		

p2101[0...19] Setting the fault response / Fault response			
A_INF, B_INF, S_INF	Can be changed: U, T Data type: Integer16	Dynamic index: -	Access level: 3 Function diagram: 1750, 8075
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting [0] 0 [1] 0 [2] 0 [3] 0 [4] 0 [5] 0 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0
Description:	Sets the fault response for the selected fault.		

Values:
 0: NONE
 1: OFF1
 2: OFF2

Dependency: The fault is selected and the required response is set under the same index.

p2101[0...19] Setting the fault response / Fault response

SERVO, TM41, VEC-TOR	Can be changed: U, T Data type: Integer16 P-Group: Messages Min 0	Dynamic index: - Units group: - Max 7	Access level: 3 Function diagram: 1750, 8075 Unit selection: - Factory setting [0] 0 [1] 0 [2] 0 [3] 0 [4] 0 [5] 0 [6] 0 [7] 0 [8] 0 [9] 0 [10] 0 [11] 0 [12] 0 [13] 0 [14] 0 [15] 0 [16] 0 [17] 0 [18] 0 [19] 0
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Description: Sets the fault response for the selected fault.

Values:
 0: NONE
 1: OFF1
 2: OFF2
 3: OFF3
 4: STOP1 (being developed)
 5: STOP2
 6: DCBRAKE (being developed)
 7: ENCODER (p0491)

Dependency: The fault is selected and the required response is set under the same index.
 Refer to: p2100

Notice: It is not possible to re-parameterize the response to a specific fault for faults that are already present (queued).

Note:
 OFF1:
 Braking along the ramp-function generator down ramp followed by a pulse inhibit.
 OFF2:
 Internal/external pulse inhibit.
 OFF3:
 Braking along the OFF3 down ramp followed by a pulse inhibit.
 STOP2:
 n_set = 0
 The fault response can only be changed for faults with the appropriate identification.
 Example:
 F12345 and fault response = NONE (OFF1, OFF2) --> The NONE fault response can be changed to either OFF1 or OFF2.

p2102	BI: Acknowledge all faults / Ackn all faults		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2546, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to acknowledge all faults at all drive objects of the drive system.		
Note:	A fault acknowledgment is triggered with a 0/1 signal.		
p2103	BI: 1. Acknowledge faults / 1. Acknowledge		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the first signal source to acknowledge faults.		
Note:	A fault acknowledgment is triggered with a 0/1 signal.		
p2103[0...n]	BI: 1. Acknowledge faults / 1. Acknowledge		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2441, 2442, 2443, 2448, 2475, 2546, 8060, 9220
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the first signal source to acknowledge faults.		
Note:	A fault acknowledgment is triggered with a 0/1 signal.		
p2104	BI: 2. Acknowledge faults / 2. Acknowledge		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the second signal source to acknowledge faults.		
Note:	A fault acknowledgment is triggered with a 0/1 signal.		
p2104[0...n]	BI: 2. Acknowledge faults / 2. Acknowledge		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 2546, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the second signal source to acknowledge faults.		
Note:	A fault acknowledgment is triggered with a 0/1 signal.		

p2105	BI: 3. Acknowledge faults / 3. Acknowledge			
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -	
	P-Group: Messages	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the third signal source to acknowledge faults.			
Note:	A fault acknowledgment is triggered with a 0/1 signal.			
p2105[0...n]	BI: 3. Acknowledge faults / 3. Acknowledge			
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T Data type: Unsigned32	Dynamic index: CDS, p0170	Access level: 3 Function diagram: 2546, 8060	
	P-Group: Messages	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the third signal source to acknowledge faults.			
Note:	A fault acknowledgment is triggered with a 0/1 signal.			
p2106	BI: External fault 1 / External fault 1			
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -	
	P-Group: Messages	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 1	
Description:	Sets the signal source for external fault 1.			
Dependency:	Refer to: F07860			
Note:	An external fault is triggered with a 1/0 signal. If this fault is output at the Control Unit, then it is transferred to all existing drive objects.			
p2106[0...n]	BI: External fault 1 / External fault 1			
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T Data type: Unsigned32	Dynamic index: CDS, p0170	Access level: 3 Function diagram: 2546	
	P-Group: Messages	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 1	
Description:	Sets the signal source for external fault 1.			
Dependency:	Refer to: F07860			
Note:	An external fault is triggered with a 1/0 signal. If this fault is output at the Control Unit, then it is transferred to all existing drive objects.			

p2107	BI: External fault 2 / External fault 2		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external fault 2.		
Dependency:	Refer to: F07861		
Note:	An external fault is triggered with a 1/0 signal. If this fault is output at the Control Unit, then it is transferred to all existing drive objects.		
p2107[0...n]	BI: External fault 2 / External fault 2		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T Data type: Unsigned32	Dynamic index: CDS, p0170	Access level: 3 Function diagram: 2546
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external fault 2.		
Dependency:	Refer to: F07861		
Note:	An external fault is triggered with a 1/0 signal. If this fault is output at the Control Unit, then it is transferred to all existing drive objects.		
p2108	BI: External fault 3 / External fault 3		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external fault 3. External fault 3 is initiated by the following AND logic operation: - BI: p2108 negated - BI: p3111 - BI: p3112 negated		
Dependency:	Refer to: p3110, p3111, p3112 Refer to: F07862		
Note:	An external fault is triggered with a 1/0 signal. If this fault is output at the Control Unit, then it is transferred to all existing drive objects.		

p2108[0...n]	BI: External fault 3 / External fault 3		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32		Function diagram: 2546
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external fault 3. External fault 3 is initiated by the following AND logic operation: - BI: p2108 negated - BI: p3111 - BI: p3112 negated		
Dependency:	Refer to: p3110, p3111, p3112 Refer to: F07862		
Note:	An external fault is triggered with a 1/0 signal. If this fault is output at the Control Unit, then it is transferred to all existing drive objects.		

r2109[0...63]	Fault time removed in milliseconds / t_flt resolved ms		
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 1750, 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the system runtime in milliseconds when the fault was removed.		
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2114, r2130, r2133, r2136		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r2110[0...63]	Alarm number / Alarm number		
All objects	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16		Function diagram: 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	This parameter is identical to r2122.		

p2111	Alarm counter / Alarm counter		
All objects	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: 1750, 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Number of alarms that have occurred after the last reset.		
Dependency:	When p2111 is set to 0, the following is initiated: - all of the alarms of the alarm buffer that have gone [0...7] are transferred into the alarm history [8...63]. - the alarm buffer [0...7] is deleted. Refer to: r2110, r2122, r2123, r2124, r2125		
Note:	The parameter is reset to 0 at POWER ON.		

p2112	BI: External alarm 1 / External alarm 1		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external alarm 1.		
Dependency:	Refer to: A07850		
Note:	An external alarm is triggered with a 1/0 signal.		
p2112[0...n]	BI: External alarm 1 / External alarm 1		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T Data type: Unsigned32	Dynamic index: CDS, p0170	Access level: 3 Function diagram: 2546
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external alarm 1.		
Dependency:	Refer to: A07850		
Note:	An external alarm is triggered with a 1/0 signal.		
r2114[0...1]	System runtime total / t_System total		
CU_S	Can be changed: - Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the total system runtime for the drive unit. Index 0 indicates the system runtime in milliseconds after reaching 86.400.000 ms (24 hours), the value is reset. Index 1 indicates the system runtime in days.		
Dependency:	Refer to: r0948, r2109, r2123, r2125, r2130, r2136, r2145, r2146		
Note:	The time in r2114 is used to display the fault and alarm times. At power-off the counter value is saved. After the drive unit is powered-up, the counter continues to run with the value that was saved the last time that the drive unit was powered-down.		
p2116	BI: External alarm 2 / External alarm 2		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for external alarm 2.		
Dependency:	Refer to: A07851		
Note:	An external alarm is triggered with a 1/0 signal.		

p2116[0...n]	BI: External alarm 2 / External alarm 2		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T	Data type: Unsigned32	Dynamic index: CDS, p0170
	P-Group: Messages	Units group: -	Access level: 3
	Min -	Max -	Function diagram: 2546
			Unit selection: -
			Factory setting 1
Description:	Sets the signal source for external alarm 2.		
Dependency:	Refer to: A07851		
Note:	An external alarm is triggered with a 1/0 signal.		

p2117	BI: External alarm 3 / External alarm 3		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T	Data type: Unsigned32	Dynamic index: -
	P-Group: Messages	Units group: -	Access level: 3
	Min -	Max -	Function diagram: -
			Unit selection: -
			Factory setting 1
Description:	Sets the signal source for external alarm 3.		
Dependency:	Refer to: A07852		
Note:	An external alarm is triggered with a 1/0 signal.		

p2117[0...n]	BI: External alarm 3 / External alarm 3		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T	Data type: Unsigned32	Dynamic index: CDS, p0170
	P-Group: Messages	Units group: -	Access level: 3
	Min -	Max -	Function diagram: 2546
			Unit selection: -
			Factory setting 1
Description:	Sets the signal source for external alarm 3.		
Dependency:	Refer to: A07852		
Note:	An external alarm is triggered with a 1/0 signal.		

p2118[0...19]	Sets the message number for message type. / Msg_no Msg_type		
All objects	Can be changed: U, T	Data type: Unsigned16	Dynamic index: -
	P-Group: Messages	Units group: -	Access level: 3
	Min 0	Max 65535	Function diagram: 1750, 8075
			Unit selection: -
			Factory setting 0
Description:	Selects faults or alarms for which the message type should be changed.		
Dependency:	Selects the fault or alarm selection and sets the required type of message realized under the same index. Refer to: p2119		
Notice:	It is not possible to re-parameterize the message type in the following cases: - if there is no existing message number. - if a message is present.		

p2119[0...19] Setting the message type / Message type	
All objects	Can be changed: U, T Data type: Integer16 P-Group: Messages Min 1 Max 3 Dynamic index: - Units group: - Access level: 3 Function diagram: 1750, 8075 Unit selection: - Factory setting 1
Description:	Sets the message type for the selected fault or alarm.
Values:	1: Fault (F) 2: Alarm (A) 3: No message (N)
Dependency:	Selects the fault or alarm selection and sets the required type of message realized under the same index. Refer to: p2118
Notice:	It is not possible to re-parameterize the message type for the existing faults or alarms.
Note:	The message type can only be changed for messages with the appropriate identification. Example: F12345(A) --> Fault F12345 can be changed to alarm A12345. In this case, the message number that may be possibly entered in p2100[0...19] and p2126[0...19] is automatically removed.

r2120 Sum of fault and alarm buffer changes / Sum buffer changed	
All objects	Can be changed: - Data type: Unsigned16 P-Group: Messages Min - Max - Dynamic index: - Units group: - Access level: 4 Function diagram: 8065 Unit selection: - Factory setting -
Description:	Displays the sum of all of the fault and alarm buffer changes in the drive unit.
Dependency:	Refer to: r0944, r2121

r2121 Counter, alarm buffer changes / Alrm buff changed	
All objects	Can be changed: - Data type: Unsigned16 P-Group: Messages Min - Max - Dynamic index: - Units group: - Access level: 3 Function diagram: 8065 Unit selection: - Factory setting -
Description:	This counter is incremented every time the alarm buffer changes.
Dependency:	Refer to: r2110, r2122, r2123, r2124, r2125

r2122[0...63]		Alarm code / Alarm code	
All objects	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16		Function diagram: 1750, 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of alarms that have occurred.		
Dependency:	Refer to: r2110, r2123, r2124, r2125, r2134, r2145, r2146		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139). Alarm buffer structure (general principle): r2122[0], r2124[0], r2123[0], r2125[0] --> alarm 1 (the oldest) . . . r2122[7], r2124[7], r2123[7], r2125[7] --> Alarm 8 (the latest) When the alarm buffer is full, the alarms that have gone are entered into the alarm history: r2122[8], r2124[8], r2123[8], r2125[8] --> Alarm 1 (the latest) . . . r2122[63], r2124[63], r2123[63], r2125[63] --> alarm 56 (the oldest)		
r2123[0...63]		Alarm time received in milliseconds / t_alarm rcv ms	
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 1750, 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the system runtime in milliseconds when the alarm occurred.		
Dependency:	Refer to: r2110, r2114, r2122, r2124, r2125, r2134, r2145, r2146		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		
r2124[0...63]		Alarm value / Alarm value	
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Integer32		Function diagram: 1750, 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays additional information about the active alarm (as integer number).		
Dependency:	Refer to: r2110, r2122, r2123, r2125, r2134, r2145, r2146		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r2125[0...63]	Alarm time removed in milliseconds / t_alarm res ms		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1750, 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the system runtime in milliseconds when the alarm was cleared.		
Dependency:	Refer to: r2110, r2114, r2122, r2123, r2124, r2134, r2145, r2146		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		
p2126[0...19]	Setting fault number for acknowledge mode / Fault_no ackn_mode		
All objects	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1750, 8075
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Selects the faults for which the acknowledge mode is to be changed		
Dependency:	Selects the faults and sets the required acknowledge mode realized under the same index Refer to: p2127		
Notice:	It is not possible to re-parameterize the acknowledge mode of a fault in the following cases: - if there is no existing fault number. - the message type is not "fault" (F). - when a fault is present.		
p2127[0...19]	Sets acknowledgment mode / Acknowledge mode		
All objects	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 1750, 8075
	P-Group: Messages	Units group: -	Unit selection: -
	Min 1	Max 3	Factory setting 1
Description:	Sets the acknowledge mode for selected fault.		
Values:	1: Acknowledgment only using POWER ON 2: IMMEDIATE acknowledged after the fault cause has been removed 3: Acknowledgement only for PULSE INHIBIT		
Dependency:	Selects the faults and sets the required acknowledge mode realized under the same index Refer to: p2126		
Notice:	It is not possible to re-parameterize the acknowledge mode of a fault in the following cases: - if there is no existing fault number. - the message type is not "fault" (F). - when a fault is present.		
Note:	The acknowledge mode can only be changed for faults with the appropriate identification. Example: F12345 and acknowledge mode = POWER ON (IMMEDIATELY) --> The acknowledge mode can be changed from POWER ON to IMMEDIATELY.		

p2128[0...15]	Selecting fault/alarm code for trigger / Message trigger		
All objects	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1750, 8070
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Selects faults or alarms which can be used as trigger.		
Dependency:	Refer to: r2129		

r2129	CO/BO: Trigger word for faults and alarms / Trigger word		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 1530, 8070
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0000 bin

Description: Trigger signal for the selected faults and alarms

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Trigger signal p2128[0]	On	Off	-
	01	Trigger signal p2128[1]	On	Off	-
	02	Trigger signal p2128[2]	On	Off	-
	03	Trigger signal p2128[3]	On	Off	-
	04	Trigger signal p2128[4]	On	Off	-
	05	Trigger signal p2128[5]	On	Off	-
	06	Trigger signal p2128[6]	On	Off	-
	07	Trigger signal p2128[7]	On	Off	-
	08	Trigger signal p2128[8]	On	Off	-
	09	Trigger signal p2128[9]	On	Off	-
	10	Trigger signal p2128[10]	On	Off	-
	11	Trigger signal p2128[11]	On	Off	-
	12	Trigger signal p2128[12]	On	Off	-
	13	Trigger signal p2128[13]	On	Off	-
	14	Trigger signal p2128[14]	On	Off	-
	15	Trigger signal p2128[15]	On	Off	-

Dependency: If one of the faults or alarms selected in p2128[n] occurs, then the particular bit of this binector output is set.
Refer to: p2128

Note: CO: r2129 = 0 --> None of the selected messages has occurred.
CO: r2129 > 0 --> At least one of the selected messages has occurred.

r2130[0...63]	Fault time received in days / t_fault recv days		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Displays the system runtime in days when the fault occurred.

Dependency: Refer to: r0945, r0947, r0948, r0949, r2109, r2114, r2133, r2136

Note: The buffer parameters are cyclically updated in the background (refer to status signal in r2139).

r2131	CO: Actual fault code / Actual fault code		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the code of the oldest active fault.		
Note:	0: No fault present.		

r2132	CO: Actual alarm code / Actual alarm code		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the code of the last alarm that occurred.		
Note:	0: No alarm present.		

r2133[0...63]	Fault value for float values / Fault val float		
All objects	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8060
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays additional information about the fault that occurred for float values.		
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2130, r2136		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r2134[0...63]	Alarm value for float values / Alarm value float		
All objects	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays additional information about the active alarm for float values.		
Dependency:	Refer to: r2110, r2122, r2123, r2124, r2125, r2145, r2146		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r2135	CO/BO: Status word faults/alarms 2 / ZSW fault/alarm 2				
A_INF, B_INF, CU_LINK, CU_S, DMC20, SERVO, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: -	Data type: Unsigned16	Dynamic index: -	Access level: 2 Function diagram: 1530, 2548	
	P-Group: Displays, signals	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the second status word of faults and alarms.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fault, encoder 1	Yes	No	-
	01	Fault, encoder 2	Yes	No	-
	02	Fault, encoder 3	Yes	No	-
	10	Fault transformer overtemperature	Yes	No	-
	11	Alarm, transformer overtemperature	Yes	No	-
	12	Fault motor overtemperature	Yes	No	-
	13	Fault thermal overload power unit	Yes	No	-
	14	Alarm, motor overtemperature	Yes	No	-
	15	Alarm, power unit thermal overload	Yes	No	-

r2135	CO/BO: Status word faults/alarms 2 / ZSW fault/alarm 2				
VECTOR	Can be changed: -	Data type: Unsigned16	Dynamic index: -	Access level: 2 Function diagram: 1530, 2548	
	P-Group: Displays, signals	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the second status word of faults and alarms.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fault, encoder 1	Yes	No	-
	01	Fault, encoder 2	Yes	No	-
	02	Fault, encoder 3	Yes	No	-
	12	Fault motor overtemperature	Yes	No	-
	13	Fault thermal overload power unit	Yes	No	-
	14	Alarm, motor overtemperature	Yes	No	-
	15	Alarm, power unit thermal overload	Yes	No	-

r2136[0...63]	Fault time removed in days / t_fit resolv. days			
All objects	Can be changed: -	Data type: Unsigned16	Dynamic index: -	Access level: 3 Function diagram: 8060
	P-Group: Messages	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting -	
Description:	Displays the system runtime in days when the fault was removed.			
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2114, r2130, r2133			
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).			

r2138 CO/BO: Control word faults/alarms / STW fault/alarm

All objects **Can be changed:** - **Access level:** 2
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 1530, 2546
P-Group: Displays, signals **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the control word of the faults and alarms.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	07	Acknowledge fault	Yes (0/1 edge)	No	-
	10	External alarm 1 (A07850)	No	Yes (1/0 edge)	-
	11	External alarm 2 (A07851)	No	Yes (1/0 edge)	-
	12	External alarm 3 (A07852)	No	Yes (1/0 edge)	-
	13	External fault 1 (F07860)	No	Yes (1/0 edge)	-
	14	External fault 2 (F07861)	No	Yes (1/0 edge)	-
	15	External fault 3 (F07862)	No	Yes (1/0 edge)	-

Dependency: Refer to: p2103, p2104, p2105, p2106, p2107, p2108, p2112, p2116, p2117, p3110, p3111, p3112

r2139 CO/BO: Status word faults/alarms 1 / ZSW fault/alarm 1

All objects **Can be changed:** - **Access level:** 2
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** 1530, 2548
P-Group: Displays, signals **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the first status word of faults and alarms.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Ackn. running	Yes	No	-
	03	Fault present	Yes	No	-
	06	Internal message 1 present	Yes	No	-
	07	Alarm present	Yes	No	-
	08	Internal message 2 present	Yes	No	-

Note: Re bit 03, 07:

These bits are set if at least one fault/alarm occurs. Data is entered into the fault/alarm buffer with delay. This is the reason that the fault/alarm buffer should only be read if, after "fault present"/"alarm present" has occurred, a change in the buffer was also detected (r0944, r2121).

p2140[0...n] Hysteresis speed 2 / n_hysteresis 2

SERVO, VECTOR **Can be changed:** U, T **Access level:** 3
Data type: Floating Point **Dynamic index:** DDS, p0180 **Function diagram:** 8010
P-Group: Messages **Units group:** 3_1 **Unit selection:** p0505
Min **Max** **Factory setting**
 0.00 [1/min] 300.00 [1/min] 90.00 [1/min]

Description: Sets the hysteresis speed (bandwidth) for the following signals:
 "|n_act| <= speed threshold value 2" (BO: r2197.1)
 "|n_act| > speed threshold value 2" (BO: r2197.2)

Dependency: Refer to: p2155, r2197

p2140[0...n]	Hysteresis velocity 2 / v_hysteresis 2		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 10.00 [m/min]	Factory setting 0.90 [m/min]
Description:	Sets the hysteresis velocity (bandwidth) for the following signals: " n_act <= speed threshold value 2" (BO: r2197.1) " n_act > speed threshold value 2" (BO: r2197.2)		
Dependency:	Refer to: p2155, r2197		
p2141[0...n]	Speed threshold 1 / n_thresh val 1		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 5.00 [1/min]
Description:	Sets the speed threshold value for the signal "f or n comparison value reached or exceeded" (BO: r2199.1).		
Dependency:	Refer to: p2142, r2199		
p2141[0...n]	Velocity threshold value 1 / v_thresh val 1		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.05 [m/min]
Description:	Sets the velocity threshold value for the signal "f or n comparison value reached or exceeded" (BO: r2199.1).		
Dependency:	Refer to: p2142, r2199		
p2142[0...n]	Hysteresis speed 1 / n_hysteresis 1		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 300.00 [1/min]	Factory setting 2.00 [1/min]
Description:	Sets the hysteresis speed (bandwidth) for the signal "f or n / v comparison value reached or exceeded" (BO: r2199.1).		
Dependency:	Refer to: p2141, r2199		
p2142[0...n]	Hysteresis velocity 1 / v_hysteresis 1		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 10.00 [m/min]	Factory setting 0.02 [m/min]
Description:	Sets the hysteresis velocity (bandwidth) for the signal "f or n / v comparison value reached or exceeded" (BO: r2199.1).		
Dependency:	Refer to: p2141, r2199		

r2145[0...63]	Alarm time received in days / t_alarm rcv days		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the system runtime in days when the alarm occurred.		
Dependency:	Refer to: r2110, r2114, r2122, r2123, r2124, r2125, r2134, r2146		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r2146[0...63]	Alarm time removed in days / t_alarm res days		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 8065
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the system runtime in days when the alarm was cleared.		
Dependency:	Refer to: r2110, r2114, r2122, r2123, r2124, r2125, r2134, r2145		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

p2147	Delete fault buffer of all drive objects / Del fault buffer		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: 8060
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Is used to delete (clear) the fault buffer of all of the existing drive objects.		
Values:	0: not active 1: Start to delete the fault buffer of all drive objects		
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2130, r2133, r2136		
Note:	p2147 is automatically set to 0 after execution.		

p2148[0...n]	BI: Ramp-function generator active / HLG active		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the signal "ramp-function generator active" for the following signals/messages: "Speed setpoint - actual value deviation within tolerance t_on" (BO: r2199.4) "Ramp-up/ramp-down completed" (BO: r2199.5)		
Note:	The binector input is automatically pre-assigned to r1199.2. The following applies for SERVO: The pre-assignment is only made when the function module "setpoint channel" is activated (r0108.8 = 1).		

p2149[0...n]	Monitoring, configuration / Monit config			
SERVO	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 8010
	P-Group: Messages	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Configuration word for messages and monitoring functions.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Enable alarm A07903	Yes	No
	01	Load monitoring only in the 1st quadrants	Yes	No
				FP
				8010
				8010
Dependency:	Refer to: r2197 Refer to: A07903			
Note:	Re bit 00: Alarm A07903 is output when the bit is set with p2197.7 = 0 (n_set <> n_act). Re bit 01: When the bit is set, the load monitoring is only carried-out in the 1st quadrant as a result of the positive characteristic parameters (p2182 ... p2190).			

p2149[0...n]	Monitoring, configuration / Monit config			
VECTOR	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180		Function diagram: 8010
	P-Group: Messages	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0001 bin
Description:	Configuration word for messages and monitoring functions.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Enable alarm A07903	Yes	No
	01	Load monitoring only in the 1st quadrants	Yes	No
				FP
				8010
				8010
Dependency:	Refer to: r2197 Refer to: A07903			
Note:	Re bit 00: Alarm A07903 is output when the bit is set with p2197.7 = 0 (n_set <> n_act). Re bit 01: When the bit is set, the load monitoring is only carried-out in the 1st quadrant as a result of the positive characteristic parameters (p2182 ... p2190).			

p2150[0...n]	Hysteresis speed 3 / n_hysteresis 3			
SERVO, VECTOR	Can be changed: U, T			Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180		Function diagram: 8010
	P-Group: Messages	Units group: 3_1		Unit selection: p0505
	Min	Max		Factory setting
	0.00 [1/min]	300.00 [1/min]		2.00 [1/min]
Description:	Sets the hysteresis speed (bandwidth) for the following signals: "n_act < speed threshold value 3" (BO: r2199.0) "n_set >= 0" (BO: r2198.5) "n_act >= 0" (BO: r2197.3)			
Dependency:	Refer to: p2161, r2197, r2199			

p2150[0...n]	Hysteresis velocity 3 / v_hysteresis 3		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 3.00 [m/min]	Factory setting 0.02 [m/min]
Description:	Sets the hysteresis velocity (bandwidth) for the following signals: " n_act < speed threshold value 3" (BO: r2199.0) "n_set >= 0" (BO: r2198.5) "n_act >= 0" (BO: r2197.3)		
Dependency:	Refer to: p2161, r2197, r2199		
p2151[0...n]	CI: Speed setpoint for messages/signals / n_set for msg		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1438[0]
Description:	Sets the signal source for the speed setpoint for the following messages: "Speed setpoint - actual value deviation within tolerance t_off" (BO: r2197.7) "Ramp-up/ramp-down completed" (BO: r2199.5) " n_set < p2161" (BO: r2198.4) "n_set > 0" (BO: r2198.5)		
Dependency:	Refer to: r2197, r2198, r2199		
p2151[0...n]	CI: Speed setpoint for messages/signals / n_set for msg		
VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1170[0]
Description:	Sets the signal source for the speed setpoint for the following messages: "Speed setpoint - actual value deviation within tolerance t_off" (BO: r2197.7) "Ramp-up/ramp-down completed" (BO: r2199.5) " n_set < p2161" (BO: r2198.4) "n_set > 0" (BO: r2198.5)		
Dependency:	Refer to: r2197, r2198, r2199		
p2153[0...n]	Speed actual value filter time constant / n_act_filt T		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000000 [ms]	Factory setting 0 [ms]
Description:	Sets the time constant of the PT1 element to smooth the speed / velocity actual value. The smoothed actual speed/velocity is compared with the threshold values and is only used for messages and signals.		
Dependency:	Refer to: r2169		

p2154[0...n]	CI: Speed setpoint 2 / n_set 2		
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for speed setpoint 2. The sum of CI: p2151 and CI: p2154 is used for the following messages/signals: "Speed setpoint - actual value deviation within tolerance t_off" (BO: r2197.7) "Speed setpoint - actual value deviation within tolerance t_on" (BO: r2199.4) "Ramp-up/ramp-down completed" (BO: r2199.5)		
Dependency:	Refer to: p2151, r2197, r2199		
p2155[0...n]	Speed threshold 2 / n_thresh val 2		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 900.00 [1/min]
Description:	Sets the speed threshold value for the following messages: " n_act <= speed threshold value 2" (BO: r2197.1) " n_act > speed threshold value 2" (BO: r2197.2)		
Dependency:	Refer to: p2140, r2197		
p2155[0...n]	Velocity threshold value 2 / v_thresh val 2		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 9.00 [m/min]
Description:	Sets the velocity threshold value for the following messages: " n_act <= speed threshold value 2" (BO: r2197.1) " n_act > speed threshold value 2" (BO: r2197.2)		
Dependency:	Refer to: p2140, r2197		
p2156[0...n]	On delay, comparison value reached / t_on cmp val rchd		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 10000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the switch-in delay time for the signal "comparison value reached" (BO: r2199.1).		
Dependency:	Refer to: p2141, p2142, r2199		

p2161[0...n]	Speed threshold 3 / n_thresh val 3		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 5.00 [1/min]
Description:	Sets the speed threshold value for the signal " n_act < speed threshold value 3" (BO: r2199.0).		
Dependency:	Refer to: p2150, r2199		
p2161[0...n]	Velocity threshold value 3 / v_thresh val 3		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.05 [m/min]
Description:	Sets the velocity threshold value for the signal " v_act < velocity threshold value 3" (BO: r2199.0).		
Dependency:	Refer to: p2150, r2199		
p2162[0...n]	Hysteresis speed n_act > n_max / Hyst n_act>n_max		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 60000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the hysteresis speed (bandwidth) for the signal "n_act > n_max" (BO: r2197.6).		
Dependency:	Refer to: r1084, r1087, r2197		
Notice:	For p0322 = 0, the following applies: p2162 <= 0.1 * p0311 For p0322 > 0, the following applies: p1082 + p2162 <= 1.02 * p0322 If one of the conditions is violated, p2162 is appropriately and automatically reduced when exiting the commissioning mode.		
Note:	For a negative speed limit (r1087) the hysteresis is effective below the limit value and for a positive speed limit (r1084) above the limit value.		
p2162[0...n]	Hysteresis velocity v_act > v_max / Hyst v_act>v_max		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 6.00 [m/min]
Description:	Sets the hysteresis velocity (bandwidth) for the signal "v_act > v_max" (BO: r2197.6).		
Dependency:	Refer to: r1084, r1087, r2197		
Notice:	For p0322 = 0, the following applies: p2162 <= 0.1 * p0311 For p0322 > 0, the following applies: p1082 + p2162 <= 1.02 * p0322 If one of the conditions is violated, p2162 is appropriately and automatically reduced when exiting the commissioning mode.		
Note:	For a negative velocity limit (r1087) the hysteresis is effective below the limit value and for a positive velocity limit (r1084) above the limit value.		

p2163[0...n]	Speed threshold 4 / n_thresh val 4		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 90.00 [1/min]
Description:	Sets the speed threshold value for the "speed setpoint - actual value deviation in tolerance t_off" signal/message (BO: r2197.7).		
Dependency:	Refer to: p2164, p2166, r2197		
p2163[0...n]	Velocity threshold value 4 / v_thresh val 4		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.90 [m/min]
Description:	Sets the velocity threshold value for the "speed setpoint - actual value deviation in tolerance t_off" signal/message (BO: r2197.7).		
Dependency:	Refer to: p2164, p2166, r2197		
p2164[0...n]	Hysteresis speed 4 / n_hysteresis 4		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 200.00 [1/min]	Factory setting 2.00 [1/min]
Description:	Sets the hysteresis speed (bandwidth) for the "speed setpoint - actual value deviation in tolerance t_off" signal/message (BO: r2197.7).		
Dependency:	Refer to: p2163, p2166, r2197		
p2164[0...n]	Hysteresis velocity 4 / v_hysteresis 4		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 10.00 [m/min]	Factory setting 0.02 [m/min]
Description:	Sets the hysteresis velocity (bandwidth) for the "speed setpoint - actual value deviation in tolerance t_off" signal/message (BO: r2197.7).		
Dependency:	Refer to: p2163, p2166, r2197		
p2166[0...n]	Off delay n_act = n_set / t_del_off n_i=n_so		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 10000.0 [ms]	Factory setting 200.0 [ms]
Description:	Sets the power-off delay time for the "speed setpoint - actual value deviation in tolerance t_off" signal/message (BO: r2197.7).		
Dependency:	Refer to: p2163, p2164, r2197		

p2167[0...n]	Switch-on delay $n_{act} = n_{set} / t_{on}$ $n_{act}=n_{set}$		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8010
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 10000.0 [ms]	Factory setting 200.0 [ms]
Description:	Sets the switch-in delay for the "speed setpoint - actual value deviation in tolerance t_{on} " signal/message (BO: r2199.4).		
r2169	CO: Speed actual value smoothed signals / n_{act} smth message		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 1750, 8010, 8012, 8013
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the smoothed actual speed for messages/signals.		
Dependency:	Refer to: p2153		
r2169	CO: Velocity actual value, smoothed signals / v_{act} smth message		
SERVO (Lin)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 1750, 8010, 8012, 8013
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the smoothed actual velocity for messages/signals.		
Dependency:	Refer to: p2153		
p2174[0...n]	Torque threshold value 1 / M_{thresh} val 1		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8012
	P-Group: Messages	Units group: 7_1	Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 5.13 [Nm]
Description:	Sets the torque threshold value for the signal "Torque setpoint < torque threshold value 1" (BO: r2198.10).		
Dependency:	Refer to: p2195, r2198		
p2174[0...n]	Force threshold value 1 / F_{thresh} val 1		
SERVO (Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8012
	P-Group: Messages	Units group: 8_1	Unit selection: p0505
	Min 0.00 [N]	Max 99999.00 [N]	Factory setting 1000.00 [N]
Description:	Sets the force threshold value for the signal "Torque setpoint < torque threshold value 1" (BO: r2198.10).		
Dependency:	Refer to: p2195, r2198		

p2175[0...n]	Motor locked speed threshold / Mot lock n_thresh		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8012
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 120.00 [1/min]
Description:	Sets the speed threshold for the message "Motor locked" (BO: r2198.6).		
Dependency:	Refer to: p2177, r2198		
p2175[0...n]	Motor locked, velocity threshold / Mot lock v_thresh		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8012
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 1.20 [m/min]
Description:	Sets the velocity threshold for the message "Motor locked" (BO: r2198.6).		
Dependency:	Refer to: p2177, r2198		
p2177[0...n]	Motor locked delay time / Mot lock t_del		
SERVO, VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8012
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 65.000 [s]	Factory setting 1.000 [s]
Description:	Sets the delay time for the message "Motor locked" (BO: r2198.6). If "Motor locked" is identified within this time, then ZSW2.6 is set and an appropriate fault is output.		
Dependency:	Refer to: p2175, r2198		
p2178[0...n]	Motor stalled delay time / Mot stall t_del		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8012
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 10.000 [s]	Factory setting 0.010 [s]
Description:	Sets the delay time for the message "Motor stalled" (BO: r2198.7). If "Motor stalled" is identified within this time, then ZSW2.7 is set and an appropriate fault is output.		
Dependency:	Refer to: r2198		

p2181[0...n]	Load monitoring, response / Load monit. resp.		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16		Function diagram: 8013
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 6	Factory setting 0
Description:	Sets the response when evaluating the load monitoring.		
Values:	0: Load monitoring disabled 1: A07920 for torque/speed too low 2: A07921 for torque/speed too high 3: A07922 for torque/speed out of tolerance 4: F07923 for torque/speed too low 5: F07924 for torque/speed too high 6: F07925 for torque/speed out of tolerance		
Dependency:	Refer to: p2182, p2183, p2184, p2185, p2186, p2187, p2188, p2189, p2190, r2198 Refer to: A07920, A07921, A07922, F07923, F07924, F07925		
Note:	The response to the faults F07923 ... F07925 can be set.		

p2182[0...n]	Load monitoring, speed threshold value 1 / n_thresh 1		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 8013
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 150.00 [1/min]
Description:	Sets the speed/torque envelop curve for the load monitoring. The envelope curve (upper and lower envelope curve) is defined as follows based on 3 speed thresholds: p2182 (n_threshold 1) --> p2185 (M_threshold 1, upper), p2186 (M_threshold 1, lower) p2183 (n_threshold 2) --> p2187 (M_threshold 2, upper), p2188 (M_threshold 2, lower) p2184 (n_threshold 3) --> p2189 (M_threshold 3, upper), p2190 (M_threshold 3, lower)		
Dependency:	The following applies: p2182 < p2183 < p2184 Refer to: p2183, p2184, p2185, p2186 Refer to: A07926		

p2182[0...n]	Load monitoring, velocity threshold 1 / n_thresh 1		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point		Function diagram: 8013
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.05 [m/min]
Description:	Sets the speed/torque envelop curve for the load monitoring. The envelope curve (upper and lower envelope curve) is defined as follows based on 3 speed thresholds: p2182 (n_threshold 1) --> p2185 (M_threshold 1, upper), p2186 (M_threshold 1, lower) p2183 (n_threshold 2) --> p2187 (M_threshold 2, upper), p2188 (M_threshold 2, lower) p2184 (n_threshold 3) --> p2189 (M_threshold 3, upper), p2190 (M_threshold 3, lower)		
Dependency:	The following applies: p2182 < p2183 < p2184 Refer to: p2183, p2184, p2185, p2186 Refer to: A07926		

p2183[0...n]	Load monitoring, speed threshold value 2 / n_thresh 2		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8013
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 900.00 [1/min]
Description:	Sets the speed/torque envelop curve for the load monitoring. The envelope curve (upper and lower envelope curve) is defined as follows based on 3 speed thresholds: p2182 (n_threshold 1) --> p2185 (M_threshold 1, upper), p2186 (M_threshold 1, lower) p2183 (n_threshold 2) --> p2187 (M_threshold 2, upper), p2188 (M_threshold 2, lower) p2184 (n_threshold 3) --> p2189 (M_threshold 3, upper), p2190 (M_threshold 3, lower)		
Dependency:	The following applies: p2182 < p2183 < p2184 Refer to: p2182, p2184, p2187, p2188 Refer to: A07926		

p2183[0...n]	Load monitoring, velocity threshold 2 / n_thresh 2		
SERVO (Extended msg, Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8013
	P-Group: Messages	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.05 [m/min]
Description:	Sets the speed/torque envelop curve for the load monitoring. The envelope curve (upper and lower envelope curve) is defined as follows based on 3 speed thresholds: p2182 (n_threshold 1) --> p2185 (M_threshold 1, upper), p2186 (M_threshold 1, lower) p2183 (n_threshold 2) --> p2187 (M_threshold 2, upper), p2188 (M_threshold 2, lower) p2184 (n_threshold 3) --> p2189 (M_threshold 3, upper), p2190 (M_threshold 3, lower)		
Dependency:	The following applies: p2182 < p2183 < p2184 Refer to: p2182, p2184, p2187, p2188 Refer to: A07926		

p2184[0...n]	Load monitoring, speed threshold value 3 / n_thresh 3		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 8013
	P-Group: Messages	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 1500.00 [1/min]
Description:	Sets the speed/torque envelop curve for the load monitoring. The envelope curve (upper and lower envelope curve) is defined as follows based on 3 speed thresholds: p2182 (n_threshold 1) --> p2185 (M_threshold 1, upper), p2186 (M_threshold 1, lower) p2183 (n_threshold 2) --> p2187 (M_threshold 2, upper), p2188 (M_threshold 2, lower) p2184 (n_threshold 3) --> p2189 (M_threshold 3, upper), p2190 (M_threshold 3, lower)		
Dependency:	The following applies: p2182 < p2183 < p2184 Refer to: p2182, p2183, p2189, p2190 Refer to: A07926		

p2184[0...n]	Load monitoring, velocity threshold 3 / n_thresh 3		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 4_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [m/min]	Max 1000.00 [m/min]	Factory setting 0.05 [m/min]
Description:	Sets the speed/torque envelop curve for the load monitoring. The envelope curve (upper and lower envelope curve) is defined as follows based on 3 speed thresholds: p2182 (n_threshold 1) --> p2185 (M_threshold 1, upper), p2186 (M_threshold 1, lower) p2183 (n_threshold 2) --> p2187 (M_threshold 2, upper), p2188 (M_threshold 2, lower) p2184 (n_threshold 3) --> p2189 (M_threshold 3, upper), p2190 (M_threshold 3, lower)		
Dependency:	The following applies: p2182 < p2183 < p2184 Refer to: p2182, p2183, p2189, p2190 Refer to: A07926		
p2185[0...n]	Load monitoring torque threshold 1, upper / M_thresh 1 upper		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 99999.00 [Nm]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2185 > p2186 Refer to: p2182, p2186 Refer to: A07926		
Note:	The upper envelope curve is defined by p2185, p2187 and p2189.		
p2185[0...n]	Load monitoring force threshold 1, upper / M_thresh 1 upper		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 8_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [N]	Max 100000.00 [N]	Factory setting 100000.00 [N]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2185 > p2186 Refer to: p2182, p2186 Refer to: A07926		
Note:	The upper envelope curve is defined by p2185, p2187 and p2189.		
p2186[0...n]	Load monitoring torque threshold 1, lower / M_thresh 1 lower		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2186 < p2185 Refer to: p2182, p2185, Refer to: A07926		
Note:	The lower envelope curve is defined by p2186, p2188 and p2190.		

p2186[0...n]	Load monitoring force threshold 1, lower / M_thresh 1 lower		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 8_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [N]	Max 100000.00 [N]	Factory setting 0.00 [N]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2186 < p2185 Refer to: p2182, p2185 Refer to: A07926		
Note:	The lower envelope curve is defined by p2186, p2188 and p2190.		
p2187[0...n]	Load monitoring torque threshold 2, upper / M_thresh 2 upper		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 99999.00 [Nm]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2187 > p2188 Refer to: p2183, p2188 Refer to: A07926		
Note:	The upper envelope curve is defined by p2185, p2187 and p2189.		
p2187[0...n]	Load monitoring force threshold 2, upper / M_thresh 2 upper		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 8_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [N]	Max 100000.00 [N]	Factory setting 100000.00 [N]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2187 > p2188 Refer to: p2183, p2188 Refer to: A07926		
Note:	The upper envelope curve is defined by p2185, p2187 and p2189.		
p2188[0...n]	Load monitoring torque threshold 2, lower / M_thresh 2 lower		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2188 < p2187 Refer to: p2183, p2187 Refer to: A07926		
Note:	The lower envelope curve is defined by p2186, p2188 and p2190.		

p2188[0...n]	Load monitoring force threshold 2, lower / M_thresh 2 lower		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 8_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [N]	Max 100000.00 [N]	Factory setting 0.00 [N]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2188 < p2187 Refer to: p2183, p2187 Refer to: A07926		
Note:	The lower envelope curve is defined by p2186, p2188 and p2190.		
p2189[0...n]	Load monitoring torque threshold 3, upper / M_thresh 3 upper		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 99999.00 [Nm]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2189 > p2190 Refer to: p2184, p2190 Refer to: A07926		
Note:	The upper envelope curve is defined by p2185, p2187 and p2189.		
p2189[0...n]	Load monitoring force threshold 3, upper / M_thresh 3 upper		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 8_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [N]	Max 100000.00 [N]	Factory setting 100000.00 [N]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2189 > p2190 Refer to: p2184, p2190 Refer to: A07926		
Note:	The upper envelope curve is defined by p2185, p2187 and p2189.		
p2190[0...n]	Load monitoring torque threshold 3, lower / M_thresh 3 lower		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2190 < p2189 Refer to: p2184, p2189 Refer to: A07926		
Note:	The lower envelope curve is defined by p2186, p2188 and p2190.		

p2190[0...n]	Load monitoring force threshold 3, lower / M_thresh 3 lower		
SERVO (Extended msg, Lin)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 8_1	Function diagram: 8013
	P-Group: Messages		Unit selection: p0505
	Min 0.00 [N]	Max 100000.00 [N]	Factory setting 0.00 [N]
Description:	Sets the speed/torque / velocity/force envelope curve for the load monitoring.		
Dependency:	The following applies: p2190 < p2189 Refer to: p2184, p2189 Refer to: A07926		
Note:	The lower envelope curve is defined by p2186, p2188 and p2190.		
p2192[0...n]	Load monitoring, delay time / Load monit t_del		
SERVO (Extended msg), VECTOR (Extended msg)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 8013
	P-Group: Messages		Unit selection: -
	Min 0.00 [s]	Max 65.00 [s]	Factory setting 10.00 [s]
Description:	Sets the delay time to evaluate the load monitoring.		
p2194[0...n]	Torque threshold value 2 / M_thresh val 2		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 8012
	P-Group: Messages		Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]	Factory setting 90.00 [%]
Description:	Sets the torque/force threshold value for the signal "Torque utilization < torque threshold value 2" (BO: r2199.11). The message "torque setpoint < p2174" (BO: r2198.10) and "torque utilization < p2194" (BO: r2199.11) are only evaluated after the run-up and the delay time has expired.		
Dependency:	Refer to: r0033, p2195, r2199		
p2195[0...n]	Torque utilization switch-off delay / M_util t_off		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 8012
	P-Group: Messages		Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 800.0 [ms]
Description:	Sets the power-down delay time for the negated signal "run-up completed". The message "torque setpoint < p2174" (BO: r2198.10) and "torque utilization < p2194" (BO: r2199.11) are only evaluated after the run-up and the delay time has expired.		
Dependency:	Refer to: p2174, p2194		
r2197	CO/BO: Status word monitoring 1 / ZSW monitor 1		
SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: 1530, 2534
	P-Group: Messages		Unit selection: -
	Min -	Max -	Factory setting 0000 bin
Description:	Displays the first status word for monitoring functions.		

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	n_act <= speed threshold value 2	Yes	No	8010
	02	n_act > speed threshold value 2	Yes	No	8010
	03	n_act >= 0	Yes	No	8010
	06	n_act > n_max	Yes	No	8010
	07	Speed setp - act val deviation in tolerance t_off	Yes	No	8010

Note: Re bit 01, 02:
The speed threshold value 2 is set in p2155.

r2198 CO/BO: Status word monitoring 2 / ZSW monitor 2

SERVO, VECTOR	Can be changed: -	Access level: 2
	Data type: Unsigned16	Dynamic index: -
	P-Group: Messages	Function diagram: 1530, 2536
	Min	Units group: -
	-	Unit selection: -
	Max	Factory setting
	-	0000 bin

Description: Displays the second status word for monitoring functions.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	04	n_set < p2161	Yes	No	8010
	05	n_set > 0	Yes	No	8010
	06	Motor locked	Yes	No	8012
	07	Motor stalled	Yes	No	8012
	10	Torque setpoint < torque threshold value 1	Yes	No	8012
	11	Load monitoring signals an alarm	Yes	No	8013
	12	Load monitoring signals a fault condition	Yes	No	8013

Note: Re bit 10:
The torque threshold value 1 is set in p2174.
Re bit 07:
For servo drives, bit 07 is not used and is always inactive.

r2199 CO/BO: Status word monitoring 3 / ZSW monitor 3

SERVO, VECTOR	Can be changed: -	Access level: 2
	Data type: Unsigned16	Dynamic index: -
	P-Group: Messages	Function diagram: 1530, 2536
	Min	Units group: -
	-	Unit selection: -
	Max	Factory setting
	-	0000 bin

Description: Displays the third status word for monitoring functions.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	n_act < speed threshold value 3	Yes	No	8010
	01	f or n comparison value reached or exceeded	Yes	No	8010
	04	Speed setp - act val deviation in tolerance t_on	Yes	No	8010
	05	Ramp-up/ramp-down completed	Yes	No	8010
	06	Current below the zero current threshold	Yes	No	-
	11	Torque utilization < torque threshold value 2	Yes	No	8012

Note: Re bit 00:
The speed threshold value 3 is set in p2161.
Re bit 01:
The comparison value is set in p2141.
Re bit 11:
The torque threshold value 2 is set in p2194.

p2200[0...n]	BI: Technology controller enable / Tec_ctr enable		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 2
	Data type: Unsigned32	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to switch-in/switch-out the technology controller. The technology controller is switched-in with a 1 signal.		
p2201[0...n]	CO: Technology controller, fixed value 1 / Tec_ctr fix val 1		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7950
	P-Group: Technology		Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 10.00 [%]
Description:	Sets the value for fixed value 1 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2202[0...n]	CO: Technology controller, fixed value 2 / Tec_ctr fix val 2		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7950
	P-Group: Technology		Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 20.00 [%]
Description:	Sets the value for fixed value 2 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2203[0...n]	CO: Technology controller, fixed value 3 / Tec_ctr fix val 3		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7950
	P-Group: Technology		Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 30.00 [%]
Description:	Sets the value for fixed value 3 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2204[0...n]	CO: Technology controller, fixed value 4 / Tec_ctr fix val 4		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7950
	P-Group: Technology		Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 40.00 [%]
Description:	Sets the value for fixed value 4 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2205[0...n]	CO: Technology controller, fixed value 5 / Tec_ctr fix val 5		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 50.00 [%]
Description:	Sets the value for fixed value 5 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2206[0...n]	CO: Technology controller, fixed value 6 / Tec_ctr fix val 6		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 60.00 [%]
Description:	Sets the value for fixed value 6 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2207[0...n]	CO: Technology controller, fixed value 7 / Tec_ctr fix val 7		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 70.00 [%]
Description:	Sets the value for fixed value 7 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2208[0...n]	CO: Technology controller, fixed value 8 / Tec_ctr fix val 8		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 80.00 [%]
Description:	Sets the value for fixed value 8 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2209[0...n]	CO: Technology controller, fixed value 9 / Tec_ctr fix val 9		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 90.00 [%]
Description:	Sets the value for fixed value 9 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2210[0...n]	CO: Technology controller, fixed value 10 / Tec_ctr fix val 10		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 100.00 [%]
Description:	Sets the value for fixed value 10 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2211[0...n]	CO: Technology controller, fixed value 11 / Tec_ctr fix val 11		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 110.00 [%]
Description:	Sets the value for fixed value 11 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2212[0...n]	CO: Technology controller, fixed value 12 / Tec_ctr fix val 12		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 120.00 [%]
Description:	Sets the value for fixed value 12 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2213[0...n]	CO: Technology controller, fixed value 13 / Tec_ctr fix val 13		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 130.00 [%]
Description:	Sets the value for fixed value 13 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2214[0...n]	CO: Technology controller, fixed value 14 / Tec_ctr fix val 14		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 140.00 [%]
Description:	Sets the value for fixed value 14 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		

p2215[0...n]	CO: Technology controller, fixed value 15 / Tec_ctr fix val 15		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7950
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 150.00 [%]
Description:	Sets the value for fixed value 15 of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222, p2223, r2224, r2229		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
p2220[0...n]	BI: Technology controller fixed value selection bit 0 / Tec_ctr sel bit 0		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7950
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed value of the technology controller.		
Dependency:	Refer to: p2221, p2222, p2223		
p2221[0...n]	BI: Technology controller fixed value selection bit 1 / Tec_ctr sel bit 1		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7950
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed value of the technology controller.		
Dependency:	Refer to: p2220, p2222, p2223		
p2222[0...n]	BI: Technology controller fixed value selection bit 2 / Tec_ctr sel bit 2		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7950
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed value of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2223		
p2223[0...n]	BI: Technology controller fixed value selection bit 3 / Tec_ctr sel bit 3		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7950
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the fixed value of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2222		

r2224	CO: Technology controller, fixed value effective / Tec_ctr FixVal eff			
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 7950
	P-Group: Technology	Units group: 9_1		Unit selection: p0595
	Min - [%]	Max - [%]		Factory setting - [%]
Description:	Displays the selected and effective fixed value of the technology controller.			
Dependency:	Refer to: r2229			
r2229	Technology controller current number / Tec_ctrl No. act			
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 7950
	P-Group: Technology	Units group: -		Unit selection: -
	Min -	Max -		Factory setting -
Description:	Displays the number of the selected fixed setpoint of the technology controller.			
Dependency:	Refer to: r2224			
p2230[0...n]	Technology controller motorized potentiometer configuration / Tec_ctr mop config			
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T			Access level: 3
	Data type: Unsigned32	Dynamic index: DDS, p0180		Function diagram: 7954
	P-Group: Technology	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0110 bin
Description:	Sets the configuration for the motorized potentiometer of the technology controller.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Data save active	Yes	No
	02	Initial rounding-off active	Yes	No
	03	Non-volatile data save active for p2230.0 = 1	Yes	No
Dependency:	Refer to: r2231, p2240			
Note:	Re bit 00: 0: The setpoint for the motorized potentiometer is not saved and after ON is entered using p2240. 1: The setpoint for the motorized potentiometer is saved and after ON is entered using r2231. In order to save in a non-volatile fashion, bit 03 should be set to 1.			
	Re bit 02: 0: Without initial rounding-off 1: With initial rounding-off. The selected ramp-up/down time is correspondingly exceeded.			
	Re bit 03: 0: Non-volatile data save de-activated. 1: The setpoint for the motorized potentiometer is saved in a non-volatile fashion (for p2230.0 = 1). The following prerequisites must be fulfilled in order to be able to save the setpoint in a non-volatile fashion: - Firmware with V2.3 or higher. - Control Unit 320 (CU320) with hardware version C or higher (module with NVRAM).			

r2231	Technology controller motorized potentiometer setpoint memory / Tec_ctrl mop mem		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: - Data type: Floating Point P-Group: Technology	Dynamic index: - Units group: -	Access level: 2 Function diagram: 7954 Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the setpoint memory for the motorized potentiometer of the technology controller. For p2230.0 = 1, the last setpoint that was saved is entered after ON.		
Dependency:	Refer to: p2230		
p2235[0...n]	BI: Technology controller motorized potentiometer, raise setpoint / Tec_ctr mop raise		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T Data type: Unsigned32 P-Group: Commands	Dynamic index: CDS, p0170 Units group: -	Access level: 3 Function diagram: 7954 Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to increase the setpoint for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: p2236		
p2236[0...n]	BI: Technology controller motorized potentiometer, lower setpoint / Tec_ctr mop lower		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T Data type: Unsigned32 P-Group: Commands	Dynamic index: CDS, p0170 Units group: -	Access level: 3 Function diagram: 7954 Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to reduce the setpoint for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: p2235		
p2237[0...n]	Technology controller motorized potentiometer maximum value / Tec_ctr mop max		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T Data type: Floating Point P-Group: Technology	Dynamic index: DDS, p0180 Units group: 9_1	Access level: 2 Function diagram: 7954 Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 100.00 [%]
Description:	Sets the maximum value for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: p2238		
p2238[0...n]	Technology controller motorized potentiometer minimum value / Tec_ctr mop min		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T Data type: Floating Point P-Group: Technology	Dynamic index: DDS, p0180 Units group: 9_1	Access level: 2 Function diagram: 7954 Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting -100.00 [%]
Description:	Sets the minimum value for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: p2237		

p2240[0...n]	Technology controller motorized potentiometer starting value / Tec_ctrl mop start		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7954
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Sets the starting value for the motorized potentiometer of the technology controller. For p2230.0 = 0, this setpoint is entered after ON.		
Dependency:	Refer to: p2230		
r2245	CO: Technology controller mot. potentiometer setpoint before RFG / Tec_ctr mop b. RFG		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 7954
	P-Group: Technology	Units group: 9_1	Unit selection: p0595
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Sets the effective setpoint in front of the internal motorized potentiometer ramp-function generator of the technology controller.		
Dependency:	Refer to: r2250		
p2247[0...n]	Technology controller motorized potentiometer ramp-up time / Tec_ctr mop t_r-up		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7954
	P-Group: Technology	Units group: -	Unit selection: -
	Min 0.0 [s]	Max 1000.0 [s]	Factory setting 10.0 [s]
Description:	Sets the ramp-up time for the internal ramp-function generator for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: p2248		
Note:	The time is referred to 100 %. When the initial rounding-off is activated (p2230.2 = 1) the ramp-up is correspondingly extended.		
p2248[0...n]	Technology controller motorized potentiometer ramp-down time / Tec_ctrMop t_rdown		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7954
	P-Group: Technology	Units group: -	Unit selection: -
	Min 0.0 [s]	Max 1000.0 [s]	Factory setting 10.0 [s]
Description:	Sets the ramp-down time for the internal ramp-function generator for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: p2247		
Note:	The time is referred to 100 %. When the initial rounding-off is activated (p2230.2 = 1) the ramp-down is correspondingly extended.		

r2250	CO: Technology controller motorized potentiometer setpoint after RFG / Tec_ctr mop a. RFG		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7954
	P-Group: Technology		Unit selection: p0595
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the effective setpoint after the internal ramp-function generator for the motorized potentiometer of the technology controller.		
Dependency:	Refer to: r2245		
p2253[0...n]	CI: Technology controller setpoint 1 / Tec_ctr setpoint 1		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 2
	Data type: Unsigned32	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setpoint 1 of the technology controller.		
Dependency:	Refer to: p2254, p2255		
p2254[0...n]	CI: Technology controller setpoint 2 / Tec_ctr setpoint 2		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setpoint 2 of the technology controller.		
Dependency:	Refer to: p2253, p2256		
p2255	Technology controller setpoint 1 scaling / Tec_ctr set1 scal.		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]	Factory setting 100.00 [%]
Description:	Sets the scaling for the setpoint 1 of the technology controller.		
Dependency:	Refer to: p2253		
p2256	Technology controller setpoint 2 scaling / Tec_ctr set2 scal.		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]	Factory setting 100.00 [%]
Description:	Sets the scaling for the setpoint 2 of the technology controller.		
Dependency:	Refer to: p2254		

p2257	Technology controller, ramp-up time / Tec_ctr t_ramp-up		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T Data type: Floating Point P-Group: Technology	Dynamic index: - Units group: -	Access level: 2 Function diagram: 7958 Unit selection: -
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 1.00 [s]
Description:	Sets the ramp-up time of the technology controller.		
Dependency:	Refer to: p2258		
Note:	The ramp-up time is referred to 100 %.		
p2258	Technology controller ramp-down time / Tec_ctr t_ramp-dn		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T Data type: Floating Point P-Group: Technology	Dynamic index: - Units group: -	Access level: 2 Function diagram: 7958 Unit selection: -
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 1.00 [s]
Description:	Sets the ramp-down time of the technology controller.		
Dependency:	Refer to: p2257		
Note:	The ramp-down time is referred to 100 %.		
r2260	CO: Technology controller setpoint after ramp-function generator / Tec_ctr set a. RFG		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: - Data type: Floating Point P-Group: Technology	Dynamic index: - Units group: 9_1	Access level: 2 Function diagram: 7958 Unit selection: p0595
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Sets the setpoint after the ramp-function generator of the technology controller.		
p2261	Technology controller setpoint filter time constant / Tec_ctr set T		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T Data type: Floating Point P-Group: Technology	Dynamic index: - Units group: -	Access level: 3 Function diagram: 7958 Unit selection: -
	Min 0.00 [s]	Max 60.00 [s]	Factory setting 0.00 [s]
Description:	Sets the time constant for the setpoint filter (PT1) of the technology controller.		
r2262	CO: Technology controller setpoint after filter / Tec_ctr set a. flt		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: - Data type: Floating Point P-Group: Technology	Dynamic index: - Units group: 9_1	Access level: 3 Function diagram: 7958 Unit selection: p0595
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the smoothed setpoint after the setpoint filter (PT1) of the technology controller.		

p2263	Technology controller type / Tec_ctr type		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the technology controller type.		
Values:	0: D component in the actual value signal; 1:D component in the fault signal		
p2264[0...n]	CI: Technology controller actual value / Tec_ctr act val		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 2
	Data type: Unsigned32	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the actual value of the technology controller.		
p2265	Technology controller actual value filter time constant / Tec_ctr act T		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0.00 [s]	Max 60.00 [s]	Factory setting 0.00 [s]
Description:	Sets the time constant for the actual value filter (PT1) of the technology controller.		
r2266	CO: Technology controller actual value after filter / Tec_ctr act a. flt		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7958
	P-Group: Technology		Unit selection: p0595
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the smoothed actual value after the filter (PT1) of the technology controller		
r2273	CO: Technology controller error / Tec_ctr error		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: 9_1	Function diagram: 7958
	P-Group: Technology		Unit selection: p0595
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the error (system deviation) between the setpoint and actual value of the technology controller.		
Dependency:	Refer to: p2263		
p2274	Technology controller differentiation, time constant / Tec_ctr T diff		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0.000 [s]	Max 60.000 [s]	Factory setting 0.000 [s]
Description:	Sets the time constant for the differentiation (D component) of the technology controller.		
Note:	p2274 = 0: Differentiation is disabled.		

p2280	Technology controller proportional gain / Tec_ctr Kp		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0.000	Max 1000.000	Factory setting 1.000
Description:	Sets the proportional gain (P component) of the technology controller.		
Note:	p2280 = 0: The proportional gain is disabled.		

p2285	Technology controller integral time / Tec_ctr Tn		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min 0.000 [s]	Max 60.000 [s]	Factory setting 0.000 [s]
Description:	Sets the integral time (I component, integrating time constant) of the technology controller.		
Note:	p2285 = 0: The integral time is disabled.		

p2289[0...n]	CI: Technology controller pre-control signal / Tec_ctr prectrl		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 2
	Data type: Unsigned32	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the pre-control signal of the technology controller.		

p2291	CO: Technology controller maximum limiting / Tec_ctr max_lim		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 100.00 [%]
Description:	Sets the maximum limit of the technology controller.		
Dependency:	Refer to: p2292		
Caution:	The maximum limit must always be greater than the minimum limit (p2291 > p2292).		



p2292	CO: Technology controller minimum limiting / Tec_ctr min_lim		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: 7958
	P-Group: Technology		Unit selection: -
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Sets the minimum limit of the technology controller.		
Dependency:	Refer to: p2291		
Caution:	The maximum limit must always be greater than the minimum limit (p2291 > p2292).		




p2293	Technology controller ramp-up/ramp-down time / Tec_ctr ramp up/dn		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7958
	P-Group: Technology	Units group: -	Unit selection: -
	Min 0.00 [s]	Max 100.00 [s]	Factory setting 1.00 [s]
Description:	Sets the ramp-up and ramp-down time for the maximum and minimum limiting (p2291 and p2292) of the technology controller.		
Dependency:	Refer to: p2291, p2292		
Note:	The ramp-up/ramp-down times are referred to 100 %.		
r2294	CO: Technology controller output signal / Tec_ctr outp_sig		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 7958
	P-Group: Technology	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the output signal of the technology controller.		
Dependency:	Refer to: p2295		
p2295	CO: Technology controller output scaling / Tec_ctr outp_scal		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7958
	P-Group: Technology	Units group: -	Unit selection: -
	Min -100.00 [%]	Max 100.00 [%]	Factory setting 100.00 [%]
Description:	Sets the scaling for the output signal of the technology controller.		
p2296[0...n]	CI: Technology controller output scaling / Tec_ctr outp_scal		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7958
	P-Group: Technology	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2295[0]
Description:	Sets the signal source for the scaling value of the technology controller.		
Dependency:	Refer to: p2295		
p2297[0...n]	CI: Technology controller maximum limiting / Tec_ctr max_limit		
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7958
	P-Group: Technology	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2291[0]
Description:	Sets the signal source for the maximum limiting of the technology controller.		
Dependency:	Refer to: p2291		

p2298[0...n]	CI: Technology controller minimum limiting / Tec_ctr min_lim			
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 2	
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: 7958	
	P-Group: Technology	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 2292[0]	
Description:	Sets the signal source for the minimum limiting of the technology controller.			
Dependency:	Refer to: p2292			
r2349	CO/BO: Technology controller status word / Tec_ctr stat word			
SERVO (Tech_ctrl), VECTOR (Tech_ctrl)	Can be changed: -		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: 7958	
	P-Group: Technology	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the status word of the technology controller.			
Bit field:	Bit	Signal name	1 signal	0 signal FP
	00	Technology controller de-activated	Yes	No -
	01	Technology controller limited	Yes	No -
	02	Technology controller, motorized potentiometer limited max.	Yes	No -
	03	Technology controller, motorized potentiometer limited min.	Yes	No -
p2369	BI: Staging control word / Staging STW			
VECTOR (Tech_ctrl)	Can be changed: U, T		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: -	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the signal source to select the "staging" function.			
p2502[0...n]	LR encoder assignment / Encoder assignment			
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: C2(25)		Access level: 1	
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 4010	
	P-Group: Closed loop position control	Units group: -	Unit selection: -	
	Min 0	Max 3	Factory setting 1	
Description:	Sets the assigned encoder. The actual value conditioning and the closed-loop position control are carried-out using the assigned encoder.			
Values:	0: No encoder 1: Encoder 1 2: Encoder 2 3: Encoder 3			
Dependency:	Refer to: p0187, p0188, p0189			
Notice:	For the setting p2502 = 0 (no encoder), closed-loop position control is not possible. This setting is only practical as supportive measure to implement sensorless closed-loop speed control (e.g. if the motor encoder is defective).			
Note:	The assigned encoder (p2502 = 1, 2, 3) must be allocated an encoder data set (p0187, p0188, p0189).			


p2503[0...n]	LR length unit LU per 10 mm / LU per 10 mm		
SERVO (APC, Pos ctrl), VECTOR (Pos ctrl)	Can be changed: C2(25)	Dynamic index: DDS, p0180	Access level: 1
	Data type: Unsigned32		Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 1 [LU]	Max 2147483647 [LU]	Factory setting 10000 [LU]
Description:	Sets the neutral length units LU per 10 mm. Therefore, for a linear scale, a reference is established between the physical arrangement and the neutral length units LU used in the drive. Example: Linear scale, 10 mm should be broken down to units of μm (i.e. 1 LU = 1 μm). --> p2503 = 10000		
Note:	The assignment to the grid spacing can be achieved using this for a rotary axis with linear encoder.		
p2504[0...n]	LR motor/load motor revolutions / Mot/load motor rev		
SERVO (APC, Pos ctrl), VECTOR (Pos ctrl)	Can be changed: C2(25)	Dynamic index: DDS, p0180	Access level: 1
	Data type: Unsigned32		Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 1	Max 1048576	Factory setting 1
Description:	Sets the motor revolutions for the gearbox factor between the motor shaft and load shaft. Gearbox factor = motor revolutions (p2504) / load revolutions (p2505)		
Dependency:	Refer to: p0432, p0433, p2505		
Note:	The gearbox factor between the encoder shaft and the motor shaft is set using p0432 and p0433.		
p2505[0...n]	LR motor/load motor revolutions / Mot/load motor rev		
SERVO (APC, Pos ctrl), VECTOR (Pos ctrl)	Can be changed: C2(25)	Dynamic index: DDS, p0180	Access level: 1
	Data type: Integer32		Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -1048576	Max 1048576	Factory setting 1
Description:	Sets the load revolutions for the gearbox factor between the motor shaft and load shaft. Gearbox factor = motor revolutions (p2504) / load revolutions (p2505)		
Dependency:	Refer to: p0432, p0433, p2504		
Note:	The gearbox factor between the encoder shaft and the motor shaft is set using p0432 and p0433.		

p2506[0...n]	LR length unit LU per load revolution / LU per load rev	
SERVO (APC, Pos ctrl), VECTOR (Pos ctrl)	Can be changed: C2(25)	Access level: 1
	Data type: Unsigned32	Dynamic index: DDS, p0180
	P-Group: Closed loop position control	Function diagram: 4010
	Units group: -	Unit selection: -
	Min 1 [LU]	Max 2147483647 [LU]
		Factory setting 10000 [LU]
Description:	Sets the neutral length units LU per load revolution. Therefore, for a rotary encoder, a reference is established between the physical arrangement and the neutral length units LU used in the drive. Example: Rotary encoder, ballscrew with 10 mm/revolution, 10 mm should be broken down to units of μm (i.e. 1 LU = 1 μm). --> One load revolution corresponds to 10000 LU --> p2506 = 10000	

p2507[0...n]	LR absolute encoder adjustment status / Abs_enc_adj stat	
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Access level: 1
	Data type: Integer16	Dynamic index: EDS, p0140
	P-Group: Closed loop position control	Function diagram: 4010
	Units group: -	Unit selection: -
	Min 0	Max 3
		Factory setting 1
Description:	Activating the adjustment and display of the status of the adjustment for absolute encoders.	
Values:	0: Error occurred while adjusting 1: Absolute encoder not adjusted 2: Absolute encoder not adjusted and encoder adjustment initiated 3: Absolute encoder adjusted	
Dependency:	Refer to: p2525, p2598, p2599	
Caution:	After the encoder has been adjusted, it must be ensure that over the complete traversing range the absolute encoder does not overflow. For an overflow condition, there is no clear reference between the encoder actual value and the mechanical system. In order to permanently accept the values, the offset of the encoder adjustment (p2525) must be saved in a non-volatile fashion (p0971, p0977).	
		
Note:	The encoder adjustment is initiated with p2507 = 2. The status is displayed using the other values. This adjustment can only be initiated for absolute encoders.	

p2508	BI: LR activate reference mark search / Ref_mark act	
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Access level: 1
	Data type: Unsigned32	Dynamic index: -
	P-Group: Closed loop position control	Function diagram: 4010
	Units group: -	Unit selection: -
	Min -	Max -
		Factory setting 0
Description:	Sets the signal source for the function "activate reference mark search".	
Dependency:	Refer to: p0490, p0495, p2509, r2684 Refer to: A07495	
Notice:	When activating the function "set position actual value" while the function "reference mark search" is activated, then the function "reference mark search" is automatically de-activated.	
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2508 = r2684.0 The function can only be activated using a 0/1 signal transition if no reference function is active (refer to r2526.2). If "reference mark search" and "measuring probe evaluation" are simultaneously activated, then no function is activated and the actual function is interrupted.	

p2509	BI: LR activating measuring probe evaluation / MP_eval act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the function "activating the measuring probe evaluation". 0/1 signal: The function "activate measuring probe evaluation" is started.		
Dependency:	Refer to: p0488, p0489, p0490, p2508, p2510, p2511 Refer to: A07495		
Notice:	When the "set position actual value" is activated while the function "measuring probe evaluation" is activated, then the function "measuring probe evaluation" is automatically de-activated.		
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2509 = r2684.1 The function can only be activated using a 0/1 signal transition if no reference function is active (refer to r2526.2). If "reference mark search" and "measuring probe evaluation" are simultaneously activated, then no function is activated and the actual function is interrupted.		
p2510	BI: LR selecting measuring probe evaluation / MP_eval select		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to select the measuring probe. 1 signal = measuring probe 2 is activated for BI: p2509 = 0/1 edge. 0 signal = measuring probe 1 is activated for BI: p2509 = 0/1 edge.		
Dependency:	Refer to: p2509, p2511		
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2509 = r2684.1 The measuring probe is selected at the 0/1 signal transition at r2684.1 (flying referencing active).		
p2511	BI: LR measuring probe evaluation edge / MP_eval edge		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the edge evaluation of the measuring probe. 1 signal = falling edge of the measuring probe (p2510) is activated for BI: p2509 = 0/1 edge. 0 signal = rising edge of the measuring probe (p2510) is activated for BI: p2509 = 0/1 edge.		
Dependency:	Refer to: p2509, p2510		

p2512	BI: LR pos. actual value conditioning activate corr. value (edge) / ActVal_condCorrAct		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32		Function diagram: 4010, 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the function "activate position actual value conditioning, correction value (edge)". 0/1 signal: The correction value available through CI: p2513 is activated.		
Dependency:	Refer to: p2513, r2684		
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2512 = r2684.7		
p2513	CI: LR Position actual value conditioning, correction value / Act val_cond corr		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32		Function diagram: 4010, 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the correction value for position actual value conditioning.		
Dependency:	Refer to: p2512, r2521, r2685		
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: CI: p2513 = r2685 For BI: p2512 = 0/1 signal, the position actual value (CO: r2521) is corrected corresponding to the value via CI: p2513. In so doing, the sign of the correction value present is taken into account.		
p2514	BI: LR activate position actual value setting / s_act setting act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32		Function diagram: 4010
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to activate the function "set position actual value".		
Dependency:	Refer to: p2515 Refer to: A07495		
Warning:	As long as the position actual value is set, encoder increments that are received are not evaluated. In this state, any position difference cannot be corrected!		
			
Notice:	When the function "set position actual value" is activated while the function "reference mark search" or "measuring probe evaluation" is activated, then the corresponding function is de-activated.		
Note:	1 signal: The position actual value is set to the setting value in CI: p2515. Alarm F7497 "position setting value activated" is output. Increments that are received in the meantime, are not taken into account. 1/0 signal: The position actual value conditioning is activated and is based on the setting value.		

p2515	CI: LR position actual setting, setting value / s_act set setVal				
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T			Access level: 1	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 4010	
	P-Group: Closed loop position control	Units group: -		Unit selection: -	
	Min -	Max -		Factory setting 0	
Description:	Sets the signal source for the setting value of the function "setting position actual value".				
Dependency:	Refer to: p2514				
p2516	CI: LR position offset / Position offset				
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T			Access level: 1	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 4010	
	P-Group: Closed loop position control	Units group: -		Unit selection: -	
	Min -	Max -		Factory setting 0	
Description:	Sets the signal source for the position offset.				
Dependency:	Refer to: r2667				
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: CI: p2516 = r2667				
r2520[0...2]	CO: LR Position actual value conditioning, encoder control word / ActVal_cond STW				
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -			Access level: 1	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 4010	
	P-Group: Closed loop position control	Units group: -		Unit selection: -	
	Min -	Max -		Factory setting 0000 bin	
Description:	Displays the encoder control word generated by the position actual value conditioning.				
Index:	[0] = Encoder 1 [1] = Encoder 2 [2] = Encoder 3				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Request function 1	Yes	No	-
	01	Request function 2	Yes	No	-
	02	Request function 3	Yes	No	-
	03	Request function 4	Yes	No	-
	04	Request command bit 0	Yes	No	-
	05	Request command bit 1	Yes	No	-
	06	Request command bit 2	Yes	No	-
	07	Mode flying measurement / search for reference	Flying measurement	Reference marks	-
	13	Request absolute value cyclic	Yes	No	-
	14	Request parking encoder	Yes	No	-
	15	Request acknowledge encoder fault	Yes	No	-
Dependency:	Refer to: p0480				

r2521	CO: LR position actual value / s_act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 4010
	P-Group: Closed loop position control		Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the actual position actual value determined by the position actual value conditioning.		
Dependency:	Refer to: r2526		
Note:	r2526.0 = 1 --> The position actual value in r2521 is valid.		
r2522	CO: LR velocity actual value / v_act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: -
	P-Group: Closed loop position control		Unit selection: -
	Min - [1000 LU/min]	Max - [1000 LU/min]	Factory setting - [1000 LU/min]
Description:	Displays the velocity actual value determined by the position actual value conditioning.		
Dependency:	Refer to: r2526		
Note:	r2526.0 = 1 --> The velocity actual value in r2522 is valid.		
r2523	CO: LR measured value / Measured value		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: -
	P-Group: Closed loop position control		Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the value determined by the function "reference mark search" and "measuring probe evaluation".		
Dependency:	Refer to: r2526		
Note:	r2526.2 = 1 --> The measured value in r2523 is valid.		
r2524	CO: LR LU/revolution / LU/revolution		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 4010
	P-Group: Closed loop position control		Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the internal length units LU/motor revolution.		
Dependency:	Refer to: p0404		
r2524	CO: LR LU/mm / LU/mm		
SERVO (Lin, Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 4010
	P-Group: Closed loop position control		Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the internal length units LU/mm.		
Dependency:	Refer to: p0404		

p2525[0...n]	CO: LR encoder adjustment, offset / Enc_adj offset			
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 4	
	Data type: Unsigned32	Dynamic index: EDS, p0140	Function diagram: 4010	
	P-Group: Closed loop position control	Units group: -	Unit selection: -	
	Min 0 [LU]	Max 4294967295 [LU]	Factory setting 0 [LU]	
Description:	For the absolute encoder adjustment, a drive determines the position offset.			
Dependency:	Refer to: p0404			
Note:	The position offset is only relevant for absolute encoders. The drive determines it when making the adjustment and the user should not change it.			
p2526	CO/BO: LR status word / ZSW			
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -		Access level: 1	
	Data type: Unsigned16	Dynamic index: -	Function diagram: -	
	P-Group: Closed loop position control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the status word of the position controller.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Pos act val valid	Yes	No
	01	Referencing active	Yes	No
	02	Meas val valid	Yes	No
	03	Closed-loop position control active	Yes	No
	06	Position controller output limited	Yes	No
	07	Request tracking operation	Yes	No
				FP
				4010
				4010
				4010
				4015
				4015
				-
Dependency:	Refer to: r2521, r2522, r2523			
p2530	CI: LR position setpoint / s_set			
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1	
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4015	
	P-Group: Closed loop position control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the signal source for the position setpoint of the position controller.			
Dependency:	Refer to: r2665			
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2530 = r2665			
p2531	CI: LR velocity setpoint / v_set			
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1	
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4015	
	P-Group: Closed loop position control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the signal source for the velocity setpoint of the position controller.			
Dependency:	Refer to: r2666			
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2531 = r2666			


p2532	CI: LR position actual value / s_act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2521[0]
Description:	Sets the signal source for the position actual value of the position controller.		
Dependency:	Refer to: r2521		
p2533[0...n]	LR position setpoint filter, time constant / s_set_filt T		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 1000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the time constant for the position setpoint filter (PT1).		
Note:	The effective Kv factor (position loop gain) is reduced with the filter. This allows a softer control behavior with improved tolerance with respect to noise/disturbances.		
	Applications:		
	- reduces the pre-control dynamic response.		
	- jerk limiting.		
p2534[0...n]	LR speed precontrol factor / n_prectrl fact		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Setting to activate and weight the speed precontrol value. Value = 0 % --> The precontrol is de-activated.		
Dependency:	Refer to: p2535, p2536		
Note:	When the axis control loop is optimally set as well as a precisely determined equivalent time constant of the speed control loop, the precontrol factor is 100%.		
p2535[0...n]	LR speed precontrol symmetrizing filter deadtime / n_ffCtr flt t_dead		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00	Max 2.00	Factory setting 0.00
Description:	Sets the "fractional" deadtime to emulate the timing behavior of the speed control loop. The selected multiplier refers to the position controller clock cycle (deadtime= p2535 * p0115[4]).		
Dependency:	Refer to: p0115, p2536		
Notice:	When speed pre-control is active (p2534 > 0 %), the following applies: In addition to the set deadtime (p2535), internally two position controller clock cycles are effective. When speed pre-control is inactive (p2534 = 0 %), the following applies: No deadtime is effective (p2535 and internal).		
Note:	Together with p2536, the timing behavior of the closed-loop control loop can be emulated.		


p2536[0...n]	LR speed precontrol, symmetrizing filter PT1 / n_prectrl filt PT1		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets a PT1 filter to emulate the timing behavior of the closed-speed control loop.		
Dependency:	Refer to: p2535		
Notice:	When speed pre-control is inactive (p2534 = 0 %), the following applies: If a PT1 filter has been set, it is not effective.		
Note:	Together with p2535, the timing behavior of the closed-loop control loop can be emulated.		
p2537	CI: LR position controller adaptation / Adaptation		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the adaptation of the proportional gain of the position controller.		
Dependency:	Refer to: p2538		
p2538[0...n]	LR proportional gain / Kp		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [1000/min]	Max 300.000 [1000/min]	Factory setting 1.000 [1000/min]
Description:	Sets the proportional gain (P gain, position loop gain, Kv factor) of the position controller.		
Dependency:	Refer to: p2537, p2539, r2557, r2558		
Note:	The proportional gain is used define at which traversing velocity which following error is obtained (without precontrol) Low proportional gain: Slow response to a setpoint - actual value difference, the following error becomes large. High proportional gain: Fast response to the setpoint - actual value difference, the following error becomes small.		
p2539[0...n]	LR integral time / Tn		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100000.00 [ms]	Factory setting 0.00 [ms]
Description:	Setting to activate the integral time of the position controller. Value = 0 ms --> The I component of the position controller is de-activated.		
Dependency:	Refer to: p2538, r2559		

p2540	CO: LR position controller output, speed limit / LR_output limit		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 3_1	Unit selection: p0505
	Min 0.000 [1/min]	Max 210000.000 [1/min]	Factory setting 210000.000 [1/min]
Description:	Sets the speed limit of the position controller output.		
Dependency:	Refer to: p2541		
p2540	CO: LR position controller output, velocity limit / LR_output limit		
SERVO (Lin, Pos ctrl)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 4_1	Unit selection: p0505
	Min 0.000 [m/min]	Max 1000.000 [m/min]	Factory setting 1000.000 [m/min]
Description:	Sets the velocity limit of the position controller output.		
Dependency:	Refer to: p2541		
p2541	CI: LR position controller output, speed limit signal source / LR_outp lim S_src		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2540[0]
Description:	Sets the signal source for the position controller output limit.		
Dependency:	Refer to: p2540		
p2542	LR standstill window / Standstill window		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4020
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 200 [LU]
Description:	Sets the standstill window for the standstill monitoring function. After the standstill monitoring time expires, it is cyclically checked as to whether the difference between the setpoint and actual position is located within the standstill window and if required an appropriate fault is output. Value = 0 --> The standstill monitoring is de-activated.		
Dependency:	Refer to: p2543, p2544 Refer to: F07450		
Note:	The following applies for the setting of the standstill and positioning window: Standstill window (p2542) >= positioning window (p2544)		

p2543	LR standstill monitoring time / t_standstill_monit		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4020
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100000.00 [ms]	Factory setting 200.00 [ms]
Description:	Sets the standstill monitoring time for the standstill monitoring function. After the standstill monitoring time expires, it is cyclically checked as to whether the difference between the setpoint and actual position is located within the standstill window and if required, an appropriate fault is output.		
Dependency:	Refer to: p2542, p2545 Refer to: F07450		
Note:	The following applies for the setting of the standstill and positioning monitoring time: Standstill monitoring time (p2543) <= positioning monitoring time (p2545)		
p2544	LR positioning window / Pos_window		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 4020
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 40 [LU]
Description:	Sets the positioning window for the positioning monitoring function. After the positioning monitoring time expires, it is checked once as to whether the difference between the setpoint and actual position lies within the positioning window and if required an appropriate fault is output. Value = 0 --> The positioning monitoring function is de-activated.		
Dependency:	Refer to: p2542, p2545, r2684 Refer to: F07451		
Note:	The following applies for the setting of the standstill and positioning window: Standstill window (p2542) >= positioning window (p2544)		
p2545	LR positioning monitoring time / t_pos_monit		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4020
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100000.00 [ms]	Factory setting 1000.00 [ms]
Description:	Sets the positioning monitoring time for the positioning monitoring. After the positioning monitoring time expires, it is checked once as to whether the difference between the setpoint and actual position lies within the positioning window and if required an appropriate fault is output.		
Dependency:	Refer to: p2543, p2544, r2684 Refer to: F07451		
Note:	The following applies for the setting of the standstill and positioning monitoring time: Standstill monitoring time (p2543) <= positioning monitoring time (p2545)		

p2546[0...n]	LR dynamic following error monitoring tolerance / s_delta_monit tol		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 4025
	P-Group: Closed loop position control		Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 1000 [LU]
Description:	Sets the tolerance for the dynamic following error monitoring. If this maximum permissible deviation between the measured and the calculated position actual value is exceeded, an appropriate fault is output. Value = 0 --> The dynamic following error monitoring is de-activated.		
Dependency:	Refer to: r2563, r2684 Refer to: F07452		
Note:	The tolerance bandwidth is intended to prevent the dynamic following error monitoring incorrectly responding due to operational control sequences (e.g. during load surges).		

p2547	LR cam switching position 1 / Cam position 1		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 4025
	P-Group: Closed loop position control		Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets the cam switching position 1.		
Dependency:	Refer to: p2548, r2683		
Caution:	Only after the axis has been referenced can it be guaranteed that the cam switching signals when output have a "true" position reference.		
			
Note:	Position actual value <= cam switching position 1 --> r2683.8 = 1 signal Position actual value > cam switching position 1 --> r2683.8 = 0 signal		

p2548	LR cam switching position 2 / Cam position 2		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 4025
	P-Group: Closed loop position control		Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets the cam switching position 2.		
Dependency:	Refer to: p2547, r2683		
Caution:	Only after the axis has been referenced can it be guaranteed that the cam switching signals when output have a "true" position reference.		
			
Note:	Position actual value <= cam switching position 2 --> r2683.9 = 1 signal Position actual value > cam switching position 2 --> r2683.9 = 0 signal		

p2549	BI: LR enable 1 / Enable 1		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 4015
	P-Group: Closed loop position control		Unit selection: -
	Min	Max	Factory setting
	-	-	899.2
Description:	Sets the signal source for enable 1 of the position controller.		
Dependency:	Refer to: r0899, p2550		
Note:	The position controller is enabled by ANDing BI: p2549 and BI: p2550.		
p2550	BI: LR enable 2 / Enable 2		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 4015
	P-Group: Closed loop position control		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the position controller enable 2.		
Dependency:	Refer to: p2549		
Note:	The position controller is enabled by ANDing BI: p2549 and BI: p2550. When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2550 = 1		
p2551	BI: LR setpoint signal present / Sig s_set pres		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 4020
	P-Group: Closed loop position control		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the "setpoint present" signal. BI: p2551 = 1 signal: The end of the positioning operation on the setpoint side is signaled and the positioning and standstill monitoring activated. BI: p2551 = 0 signal: The start of a positioning operation or tracking operation on the setpoint side is signaled and the positioning and standstill monitoring de-activated.		
Dependency:	Refer to: p2554, r2683		
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2551 = r2683.2		
p2554	BI: LR signal, travel command active / Sig trav_cmnd act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 4020
	P-Group: Closed loop position control		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the signal "travel command active". BI: p2554 = 1 signal: It is signaled that positioning is active and therefore the positioning monitoring is not activated with the signal "setpoint present" (p2551).		
Dependency:	Refer to: p2551, r2684		
Note:	When the function module "basic positioner" (r0108.4 = 1) is activated, the following BICO interconnection is established: BI: p2554 = r2684.15		

p2555	CI: LR LU/revolution LU/mm / LU/rev LU/mm		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: T Data type: Unsigned32 P-Group: Closed loop position control Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: 4015 Unit selection: - Factory setting 2524[0]
Description:	Sets the signal source for the reference of the internal length units LU to motor revolution for rotary encoders and to mm for linear encoders.		
Dependency:	Refer to: p0404, r2524		
r2556	CO: LR position setpoint after setpoint smoothing / s_set after interp		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: - Data type: Integer32 P-Group: Closed loop position control Min - [LU]	Dynamic index: - Units group: - Max - [LU]	Access level: 1 Function diagram: 4015 Unit selection: - Factory setting - [LU]
Description:	Displays the position setpoint after the setpoint smoothing.		
r2557	CO: LR position controller input, system deviation / LR_input sys dev		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: - Data type: Integer32 P-Group: Closed loop position control Min - [LU]	Dynamic index: - Units group: - Max - [LU]	Access level: 1 Function diagram: 4015 Unit selection: - Factory setting - [LU]
Description:	Displays the difference between the position setpoint and the position actual value at the position controller input.		
r2558	CO: LR position controller output, P component / LR_output P comp		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: - Data type: Floating Point P-Group: Closed loop position control Min - [1/min]	Dynamic index: - Units group: 3_1 Max - [1/min]	Access level: 1 Function diagram: 4015 Unit selection: p0505 Factory setting - [1/min]
Description:	Displays the P component at the output of the position controller for the speed setpoint.		
r2558	CO: LR position controller output, P component / LR_output P comp		
SERVO (Lin, Pos ctrl)	Can be changed: - Data type: Floating Point P-Group: Closed loop position control Min - [m/min]	Dynamic index: - Units group: 4_1 Max - [m/min]	Access level: 1 Function diagram: 4015 Unit selection: p0505 Factory setting - [m/min]
Description:	Displays the P component at the output of the position controller for the velocity setpoint.		
r2559	CO: LR position controller output, I component / LR_output I comp		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: - Data type: Floating Point P-Group: Closed loop position control Min - [1/min]	Dynamic index: - Units group: 3_1 Max - [1/min]	Access level: 1 Function diagram: 4015 Unit selection: p0505 Factory setting - [1/min]
Description:	Displays the I component at the output of the position controller for the speed setpoint.		

r2559	CO: LR position controller output, I component / LR_output I comp		
SERVO (Lin, Pos ctrl)	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the I component at the output of the position controller for the velocity setpoint.		
r2560	CO: LR speed setpoint / n_set		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed setpoint after limiting (CI: p2541).		
r2560	CO: LR velocity setpoint / v_set		
SERVO (Lin, Pos ctrl)	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity setpoint after limiting (CI: p2541).		
r2561	CO: LR speed precontrol value / n_prectrl val		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed setpoint due to the precontrol.		
r2561	CO: LR velocity precontrol value / v_prectrl val		
SERVO (Lin, Pos ctrl)	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity setpoint due to the precontrol.		
r2562	CO: LR total speed setpoint / n_set total		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 4015
	P-Group: Closed loop position control	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the total speed setpoint This value is obtained from the sum of the speed precontrol and position controller output.		
Dependency:	Refer to: r2560, r2561		

r2562	CO: LR velocity setpoint, total / v_set total		
SERVO (Lin, Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: 4_1	Function diagram: 4015
	P-Group: Closed loop position control		Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the total velocity setpoint. This value is obtained from the sum of the velocity precontrol and position controller output.		
Dependency:	Refer to: r2560, r2561		
r2563	CO: LR following error, dynamic model / Follow error dyn		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 4025
	P-Group: Closed loop position control		Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the following error of the dynamic model. This value is the deviation, corrected by the velocity-dependent component, between the position setpoint and the position actual value.		
r2564	CO: LR torque pre-control value / M_pre-ctrl value		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: 7_1	Function diagram: -
	P-Group: Closed loop position control		Unit selection: p0505
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Displays the torque pre-control value.		
Dependency:	Refer to: p1511, p1512		
Note:	The torque pre-control value is the derivation over time of the speed precontrol value and is referred to a moment of inertia of 1 kgm ² /2 PI. When using the pre-control, then this should be evaluated corresponding to the actual moment of inertia.		
r2564	CO: LR force precontrol value / F_prectrl val		
SERVO (Lin, Pos ctrl)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: 8_1	Function diagram: -
	P-Group: Closed loop position control		Unit selection: p0505
	Min - [N]	Max - [N]	Factory setting - [N]
Description:	Displays the force precontrol value.		
Dependency:	Refer to: p1511, p1512		
Note:	The force precontrol value is the derivation over time of the velocity precontrol value and is referred to a high inertia mass of 1000.0 kg. When using the precontrol, then this should be evaluated corresponding to the actual mass.		


r2565	CO: LR actual following error / Following err act		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: - Data type: Integer32 P-Group: Closed loop position control	Dynamic index: - Units group: -	Access level: 1 Function diagram: 4015 Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the actual following error. This value is the deviation between the position setpoint - after fine interpolation - and the position actual value.		
Notice:	When speed pre-control is active (p2534 > 0 %), the following applies: To calculate this value, the position setpoint is delayed by two position controller clock cycles. When speed pre-control is inactive (p2534 = 0 %), the following applies: To calculate this value, the position setpoint is delayed by two position controller clock cycles.		
r2566	LR speed input pre-control / n_pre-ctrl input		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: - Data type: Floating Point P-Group: Closed loop position control	Dynamic index: - Units group: 3_1	Access level: 1 Function diagram: - Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speed at the input of the speed pre-control channel. Used for diagnostics even when the pre-control is inactive (p2534 = 0%).		
r2566	LR velocity input pre-control / v_pre-ctrl input		
SERVO (Lin, Pos ctrl)	Can be changed: - Data type: Floating Point P-Group: Closed loop position control	Dynamic index: - Units group: 4_1	Access level: 1 Function diagram: - Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocity at the input of the pre-control channel. Used for diagnostics even when the pre-control is inactive (p2534 = 0%).		
p2568	BI: EPOS STOP cam activation / STOP cam activ.		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T Data type: Unsigned32 P-Group: Basic positioner	Dynamic index: - Units group: -	Access level: 1 Function diagram: - Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to activate the function "STOP cam". BI: p2568 = 1 signal --> The evaluation of the STOP cam minus (BI: p2569) and STOP cam plus (BI: p2570) is active.		
Dependency:	Refer to: p2569, p2570		
Note:	The traversing range can also be limited using software limit switches.		

p2569	BI: EPOS STOP cam minus / STOP cam minus		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the STOP cam in the negative direction of travel.		
Recommendation:	Set the OFF3 ramp-down time (p1135), so that the axis, after reaching the STOP cam at the maximum velocity, does not move through a higher braking travel than is actually available. A07491 as alarm: Set the maximum deceleration (p2573), so that the axis, after reaching the STOP cam at the maximum velocity, does not move through a higher braking travel than is actually available.		
Dependency:	Refer to: p1135, p2568, p2570, p2573, r2684 Refer to: F07491		
Caution:	The STOP cams are low active. A0791 as fault: For a 0 signal, the axis is stopped with the OFF3 ramp-down time (p1135), status signal r2684.13 is set to 1, saved and the appropriate fault is output. After the alarm has been acknowledged, only motion moving away from the STOP cam is permitted. For a 0/1 signal and valid travel direction, when the stop cam is exited, this is detected and the status signal r2684.13 is reset. A07491 as alarm: For a 0 signal, the axis is stopped with the maximum deceleration (p2573), status signal r2684.13 is set to 1, saved and an appropriate alarm is output. Only motion away from the STOP cam is permitted. For a 0/1 signal and valid travel direction, when the stop cam is exited, this is detected and the status signal r2684.13 and the alarm are reset.		

p2570	BI: EPOS STOP cam plus / STOP cam plus		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the STOP cam in the positive direction of travel.		
Recommendation:	Set the OFF3 ramp-down time (p1135), so that the axis, after reaching the STOP cam at the maximum velocity, does not move through a higher braking travel than is actually available. A07492 as alarm: Set the maximum deceleration (p2573), so that the axis, after reaching the STOP cam at the maximum velocity, does not move through a higher braking travel than is actually available.		
Dependency:	Refer to: p1135, p2568, p2569, p2573, r2684 Refer to: F07492		
Caution:	The STOP cams are low active. A07492 as fault: For a 0 signal, the axis is stopped with the OFF3 ramp-down time (p1135), status signal r2684.14 is set to 1, saved and the appropriate alarm is output. After the alarm has been acknowledged, only motion moving away from the STOP cam is permitted. For a 0/1 signal and valid travel direction, when the stop cam is exited, this is detected and the status signal r2684.14 is reset. A07492 as alarm: For a 0 signal, the axis is stopped with the maximum deceleration (p2573), status signal r2684.14 is set to 1, saved and an appropriate alarm is output. Only motion away from the STOP cam is permitted. For a 0/1 signal and valid travel direction, when the stop cam is exited, this is detected and the status signal r2684.14 and the alarm are reset.		

p2571	EPOS maximum velocity / v_max		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3630
	P-Group: Basic positioner		Unit selection: -
	Min 1 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 30000 [1000 LU/min]
Description:	Sets the maximum velocity for the function module "basic positioner" (r0108.4).		
Dependency:	Refer to: r1084, r1087, p2503, p2504, p2505, p2506		
Note:	The maximum velocity is active in all of the operating modes of the basic positioner. The maximum velocity for the basic positioner should be aligned with the maximum speed/velocity of the speed/velocity controller: Rotary encoders: p2571[1000 LU/min] = min(r1084, r1087)[RPM] x p2505/p2504 x p2506/1000 Linear encoders: p2571[1000 LU/min] = min(r1084, r1087)[m/min] x p2503/10[m]		
p2572	EPOS maximum acceleration / a_max		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3630
	P-Group: Basic positioner		Unit selection: -
	Min 1 [1000 LU/s ²]	Max 2000000 [1000 LU/s ²]	Factory setting 100 [1000 LU/s ²]
Description:	Sets the maximum acceleration for the function module "basic positioner" (r0108.4).		
Dependency:	Refer to: p2619, p2644		
Note:	The maximum acceleration appears to exhibit jumps (without jerk). "Traversing blocks" operating mode: The programmed acceleration override (p2619) acts on the maximum acceleration. "Direct setpoint input/MDI" mode: The acceleration override is effective (p2644, 4000 hex = 100 %). "Jog" and "search for reference" modes No acceleration override is active. The axis starts with the maximum acceleration.		
p2573	EPOS maximum deceleration / -a_max		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3630
	P-Group: Basic positioner		Unit selection: -
	Min 1 [1000 LU/s ²]	Max 2000000 [1000 LU/s ²]	Factory setting 100 [1000 LU/s ²]
Description:	Sets the maximum deceleration for the function module "basic positioner" (r0108.4).		
Dependency:	Refer to: p2620, p2645		
Note:	The maximum deceleration appears to exhibit jumps (without jerk). "Traversing blocks" operating mode: The programmed deceleration override (p2620) acts on the maximum deceleration. "Direct setpoint input/MDI" mode: The deceleration override is effective (p2645, 4000 hex = 100 %). "Jog" and "search for reference" modes No deceleration override is effective. The axis breaks with the maximum deceleration.		

p2576	EPOS modulo correction, modulo range / Modulo corr range		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3635
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1 [LU]	Max 2147483647 [LU]	Factory setting 360000 [LU]
Description:	Sets the modulo range for axes with modulo correction.		
Dependency:	Refer to: p2577		
p2577	BI: EPOS modulo correction activation / Modulo corr act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3635
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to activate modulo correction.		
Dependency:	Refer to: p2576		
Note:	When the signal state changes at the binector input, this only becomes effective in the "ready to power-up" state. Selecting modulo correction: The actual position actual value in the modulo range is corrected. De-selecting modulo correction: It is based on the actual position actual value.		
p2578	CI: EPOS software limit switch minus signal source / SW limSw Min S_src		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2580[0]
Description:	Sets the signal source for the software limit switch minus.		
Dependency:	Refer to: p2579, p2580, p2581, p2582 Refer to: A07469, A07477, A07479, F07481		
Notice:	A change to the software limit switch becomes immediately effective. If the software limit switch is changed, then this results in the positions in the traversing blocks being checked.		
Note:	The following applies for the setting of the software limit switch: Software limit switch minus < software limit switch plus		
p2579	CI: EPOS software limit switch plus signal source / SW limSwPlus S_src		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3630
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2581[0]
Description:	Sets the signal source for the software limit switch plus.		
Dependency:	Refer to: p2578, p2580, p2581, p2582 Refer to: A07470, A07478, A07480, F07482		
Notice:	A change to the software limit switch becomes immediately effective. If the software limit switch is changed, then this results in the positions in the traversing blocks being checked.		
Note:	The following applies for the setting of the software limit switch: Software limit switch minus < software limit switch plus		

p2580	CO: EPOS software limit switch minus / SW limSwitch minus		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3630
	P-Group: Basic positioner		Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting -2147483648 [LU]
Description:	Sets the software limit switch in the negative direction of travel.		
Dependency:	Refer to: p2578, p2579, p2581, p2582		
p2581	CO: EPOS software limit switch plus / SW lim switch plus		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3630
	P-Group: Basic positioner		Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting 2147483647 [LU]
Description:	Sets the software limit switch in the positive direction of travel.		
Dependency:	Refer to: p2578, p2579, p2580, p2582		
p2582	BI: EPOS software limit switch activation / SW lim sw act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3630
	P-Group: Basic positioner		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to activate the "software limit switch".		
Dependency:	Refer to: p2578, p2579, p2580, p2581		
Caution:	Software limit switch effective: - axis is referenced (r2684.11 = 1) and BI: p2582 = 1 signal. Software limit switch ineffective: - modulo correction active (BI: p2577 = 1 signal). - search for reference is executed.		
			
Notice:	Target position for relative positioning outside software limit switch: The traversing block is started and the axis comes to a standstill at the software limit switch. An appropriate alarm is output and the traversing block is interrupted. Traversing blocks with valid position can be activated. Target position for absolute positioning outside software limit switch: In the "traversing blocks" mode, the traversing block is not started and an appropriate fault is output. Axis outside the valid traversing range: If the axis is already outside the valid traversing range, then an appropriate fault is output. The fault can be acknowledged at standstill. Traversing blocks with valid position can be activated.		
Note:	The traversing range can also be limited using STOP cams.		

p2583	EPOS backlash compensation / Backlash comp		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3635
	P-Group: Basic positioner		Unit selection: -
	Min -200000 [LU]	Max 200000 [LU]	Factory setting 0 [LU]
Description:	Sets the amount of play (backlash) for positive or negative play. 0: The backlash compensation is de-activated. >0: Positive backlash (normal case) When the direction is reversed, the encoder actual value leads the actual value. <0: Negative backlash When the direction is reversed, the actual value leads the encoder actual value.		
Dependency:	If a stationary axis is referenced by setting the reference point, or an adjusted with absolute encoder is powered-up, then the setting of p2604 is relevant for entering the compensation value. p2604 = 1: Traveling in the positive direction -> A compensation value is immediately entered. Traveling in the negative direction -> A compensation value is not entered p2604 = 0: Traveling in the positive direction -> A compensation value is not entered Traveling in the negative direction -> A compensation value is immediately entered. When again setting the reference point (a referenced axis) or for "flying referencing", p2604 is not relevant but instead the history of the axis. Refer to: p2604, r2667		
p2585	EPOS jogging 1 setpoint velocity / Jog 1 v_set		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min -40000000 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting -300 [1000 LU/min]
Description:	Sets the setpoint velocity for jogging 1.		
Dependency:	Refer to: p2587, p2589, p2591		
p2586	EPOS jogging 2 setpoint velocity / Jog 2 v_set		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min -40000000 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 300 [1000 LU/min]
Description:	Sets the setpoint velocity for jogging 2.		
Dependency:	Refer to: p2588, p2590, p2591		
p2587	EPOS jogging 1 traversing distance / Jog 1 distance		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min 0 [LU]	Max 4294967295 [LU]	Factory setting 1000 [LU]
Description:	Sets the traversing distance for incremental jogging 1.		
Dependency:	Refer to: p2585, p2589, p2591		
Note:	Incremental jogging 1 is started with BI: p2591 = 1 signal and BI: p2589 = 0/1 signal.		

p2588	EPOS jogging 2 traversing distance / Jog 2 distance		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min 0 [LU]	Max 4294967295 [LU]	Factory setting 1000 [LU]
Description:	Sets the traversing distance for incremental jogging 2.		
Dependency:	Refer to: p2586, p2590, p2591		
Note:	Incremental jogging 2 is started with BI: p2591 = 1 signal and BI: p2590 = 0/1 signal.		
p2589	BI: EPOS jogging 1 signal source / Jog 1 S_src		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for jog 1.		
Dependency:	When jogging, the axis is accelerated or braked with the maximum acceleration/deceleration (p2572/p2573). BI: p2591 = 0 signal The axis endlessly moves with the setpoint velocity, jog 1 (p2585). BI: p2591 = 1 signal The axis traverses through a parameterized distance (p2585) with the setpoint velocity, jog 1 (p2587). Refer to: p2572, p2573, p2585, p2587, p2591		
p2590	BI: EPOS jogging 2 signal source / Jog 2 S_src		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for jog 2.		
Dependency:	When jogging, the axis is accelerated or braked with the maximum acceleration/deceleration (p2572/p2573). BI: p2591 = 0 signal The axis endlessly moves with the setpoint velocity, jog 2 (p2586). BI: p2591 = 1 signal The axis traverses through a parameterized distance (p2586) with the setpoint velocity, jog 2 (p2588). Refer to: p2572, p2573, p2586, p2588, p2591		
p2591	BI: EPOS jogging incremental / Jog incr		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3610
	P-Group: Basic positioner		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for jogging incremental.		
Dependency:	Refer to: p2585, p2586, p2587, p2588, p2589, p2590		


p2595	BI: EPOS referencing start / Ref start		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T Data type: Unsigned32 P-Group: Basic positioner Min - Max -	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3612 Unit selection: - Factory setting 0
Description:	Sets the signal source to start the "search for reference" or "flying referencing". BI: p2595 = 0/1 signal Referencing is started. BI: p2595 = 1/0 signal Referencing is interrupted.		
Dependency:	Refer to: p2597, p2598, p2599, r2684		
Note:	Search for reference (BI: p2597 = 0 signal): With the start, where relevant, the state signal "reference point set" (r2684.11) is reset. Flying referencing (BI: p2597 = 1 signal): With the start, the state signal "reference point set" (r2684.11) is not reset.		

p2596	BI: EPOS set reference point / Set ref_pt		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T Data type: Unsigned32 P-Group: Basic positioner Min - Max -	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3612, 3625 Unit selection: - Factory setting 0
Description:	Sets the signal source for the "set reference point".		
Dependency:	Refer to: p2598, p2599, r2684		
Note:	Set reference point is only effective in the initial state. The position control must be enabled as the necessary prerequisite for the standard wiring.		

p2597	BI: EPOS referencing type selection / Ref_typ select		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T Data type: Unsigned32 P-Group: Basic positioner Min - Max -	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3612 Unit selection: - Factory setting 0
Description:	Sets the signal source to select referencing type. 1 signal: Flying referencing 0 signal: Search for reference		
Dependency:	Refer to: p2595		
Note:	Referencing is activated as follows: - Select the referencing type (BI: p2597) - Start referencing (BI: p2595 = 0/1 signal)		

p2598	CI: EPOS reference point coordinate, signal source / Ref_pt coord S_src		
SERVO (EPOS, Pos ctrl), VECTOR (EPOS, Pos ctrl)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3612
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 2599[0]
Description:	Sets the signal source for the reference point coordinate. This value is used as reference for the following referencing operations: - search for reference - set reference point - flying referencing - absolute value adjustment		
Dependency:	Refer to: p2507, p2595, p2596, p2597, p2599		
Note:	Incremental measuring system: After the reference point is reached, the drive accepts the actual axis position from the position received via the connector input. Absolute encoder: When adjusting the encoder, the position received via the connector input is set as the actual axis position. The position offset to the actual encoder value is displayed in r2525.		
p2599	CO: EPOS reference point coordinate value / Ref_pt coord val		
SERVO (Pos ctrl), VECTOR (Pos ctrl)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3612
	P-Group: Closed loop position control	Units group: -	Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets the position value for the reference point coordinate. This value is set as the actual axis position after referencing or adjustment.		
Dependency:	Refer to: p2507, p2525, p2595, p2596, p2597, p2598		
p2600	EPOS search for reference, reference point offset / Ref_pt offset		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets the reference point offset for search for reference.		
Dependency:	Refer to: p2598		
p2601	EPOS flying referencing, inner window / Inner window		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3614
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets the inner window for flying referencing. Value = 0: The evaluation of the inner window is de-activated.		
Dependency:	Refer to: p2597, p2602, r2684		
Notice:	The inner window must be set so that it is smaller than the outer window.		
Note:	If the difference between the reference point coordinate and detected actual position is less than the inner window, then no offset is executed for a referenced axis. If the difference between the reference point coordinate and detected actual position is greater than the inner window and less than the outer window (p2602), then an offset is executed for a referenced axis.		

p2602	EPOS flying referencing, outer window / Outer window		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3614
	P-Group: Basic positioner		Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets the outer window for flying referencing. Value = 0: The evaluation of the outer window is de-activated.		
Dependency:	Refer to: p2597, r2684 Refer to: A07489		
Notice:	The inner window must be set so that it is smaller than the outer window.		
Note:	If the difference between the reference point coordinate and detected actual position is greater than the outer window, then no offset is executed for the referenced axis. Further, an appropriate message is output and r2684.3 is set to 1.		
p2603	EPOS flying referencing, positioning mode, relative / Pos_mode relative		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3635
	P-Group: Basic positioner		Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Sets the relative positioning mode for flying referencing. Value = 1: The corrected setpoint is not calculated into the traversing distance. Value = 0: The corrected setpoint is calculated into the traversing distance.		
Dependency:	Refer to: p2597, p2623, p2648		
Caution:	For p2603 = 0 the direction can change.		
p2604	BI: EPOS search for reference, start direction / Srch for ref dir		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3612
	P-Group: Basic positioner		Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal sources for the start direction of the search for reference. 1 signal: Start in the negative direction. 0 signal: Start in the positive direction.		
Dependency:	Refer to: p2583, p2595, p2597		

p2605	EPOS search for reference, approach velocity, reference cam / v_appr ref_cam		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 5000 [1000 LU/min]
Description:	Sets the approach velocity to the reference cam for the search for reference.		
Dependency:	The search for reference only starts with the approach velocity to the reference cam when there is a reference cam (p2607 = 1). Refer to: p2595, p2597, p2604, p2606, p2607		
Note:	When traversing to the reference cam, the velocity override is effective. If, at the start of the search for reference, the axis is already at the reference cam, then the axis immediately starts to traverse to the zero mark.		
p2606	EPOS search for reference, reference cam, maximum distance / Ref_cam max s		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 2147483647 [LU]
Description:	Sets the maximum distance after the start of the search for reference when traversing to the reference cam.		
Dependency:	Refer to: p2595, p2597, p2604, p2605, p2607 Refer to: F07458		
Note:	When using a reversing cam, the maximum distance must be set appropriately long.		
p2607	EPOS search for reference, reference cam present / Ref_cam pres		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned8	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Sets whether or not a reference cam is present for the search for reference. Value = 1: Reference cam present. Value = 0: No reference cam present.		
Dependency:	Refer to: p2595, p2597, p2604, p2605, p2606		
p2608	EPOS search for reference, approach velocity, zero mark / v_appr ref_ZM		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 300 [1000 LU/min]
Description:	Sets the approach velocity after detecting the reference cam to search for the zero mark for the the search for reference.		
Dependency:	If there is no reference cam (p2607 = 0), the search for reference immediately starts with the axis traversing to the zero mark. Refer to: p2595, p2597, p2604, p2607, p2609, p2610		
Caution:	If the reference cam is not adjusted so that at each search for reference the same zero mark for synchronization is detected, then an "incorrect" axis reference point is obtained. After the reference cam has been left, the search for the zero mark is activated with a time delay due to internal factors. This is the reason that the reference cam should be adjusted in this center between two zero marks and the approach velocity should be adapted to the distance between two zero marks.		
			
Note:	The velocity override is not effective when traversing to the zero mark.		

p2609	EPOS search for reference, max. distance ref. cam and zero mark / Max s ref_cam ZM		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 10000 [LU]
Description:	Sets the maximum distance after leaving the reference cam when traversing to the zero mark.		
Dependency:	Refer to: p2595, p2597, p2604, p2607, p2608, p2610 Refer to: F07459		
p2610	EPOS search for ref., tol. bandwidth for distance to zero mark / Tol_band too ZM		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 0 [LU]	Max 2147483647 [LU]	Factory setting 2147483647 [LU]
Description:	Sets the tolerance bandwidth for the distance to the zero mark The zero mark is evaluated within the maximum distance between the reference cam and zero mark (p2609) minus the tolerance bandwidth for the distance to the zero mark (p2610).		
Dependency:	Refer to: p2609		
p2611	EPOS search for reference, approach velocity, reference point / v_appr ref_pt		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 300 [1000 LU/min]
Description:	Sets the approach velocity after detecting the zero mark to approach the reference point.		
Dependency:	Refer to: p2595, p2597, p2604, p2607, p2609, p2610		
Note:	When traversing to the reference point, the velocity override is not effective.		
p2612	BI: EPOS search for reference, reference cam / Ref_cam		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the reference cam.		
Dependency:	Refer to: p2607		
p2613	BI: EPOS search for reference, reversing cam minus / Revers cam minus		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the reversing cam in the negative direction of travel. 1 signal: Reversing cam not reached. 0 signal: Reversing cam reached.		
Dependency:	Refer to: p2614		

Note: If, during the search for reference from the reversing cam minus and plus, a 0 signal is detected, then the axis remains stationary (at standstill).

p2614	BI: EPOS search for reference, reversing cam plus / Reversing cam plus		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1

Description: Sets the signal source for the reversing cam in the negative direction of travel.
1 signal: Reversing cam not reached.
0 signal: Reversing cam reached.

Dependency: Refer to: p2613

Note: If, during the search for reference from the reversing cam minus and plus, a 0 signal is detected, then the axis remains stationary (at standstill).

p2615	EPOS maximum number of traversing blocks / Trav_block qty max		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: C2(17)		Access level: 1
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	1	64	64

Description: Sets the maximum number of traversing blocks that are available.

Dependency: Refer to: p2616, p2617, p2618, p2619, p2620, p2621, p2622, p2623, p2624

p2616[0...n]	EPOS traversing block, block number / Trav_blk, blkNo.		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Integer16	Dynamic index: p2615	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-1	63	-1

Description: Sets a block number.
-1: Invalid block number. These blocks are not taken into account.
0 ... 63: Valid block number.

Dependency: The number of indices depends on p2615.

Refer to: p2615, p2617, p2618, p2619, p2620, p2621, p2622, p2623, p2624

p2617[0...n]	EPOS traversing block position / Trav_block pos		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Integer32	Dynamic index: p2615	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-2147483648 [LU]	2147483647 [LU]	0 [LU]

Description: Sets the target position for the traversing block.

Dependency: The number of indices depends on p2615.

Refer to: p2615, p2616, p2618, p2619, p2620, p2621, p2622, p2623, p2624

Note: The target position is approached in either relative or absolute terms depending on p2623.

p2618[0...n]	EPOS traversing block velocity / Trav_block v		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Integer32	Dynamic index: p2615	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 600 [1000 LU/min]
Description:	Sets the velocity for the traversing block.		
Dependency:	The number of indices depends on p2615. Refer to: p2615, p2616, p2617, p2619, p2620, p2621, p2622, p2623, p2624, p2646		
Note:	The velocity can be influenced using the velocity override (p2646).		
p2619[0...n]	EPOS traversing block acceleration override / Trav_block a_over		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: p2615	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1.0 [%]	Max 100.0 [%]	Factory setting 100.0 [%]
Description:	Sets the acceleration override for the traversing block. The override refers to the maximum acceleration (p2572).		
Dependency:	The number of indices depends on p2615. Refer to: p2572, p2615, p2616, p2617, p2618, p2620, p2621, p2622, p2623, p2624		
p2620[0...n]	EPOS traversing deceleration override / Trav_block -a_over		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: p2615	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1.0 [%]	Max 100.0 [%]	Factory setting 100.0 [%]
Description:	Sets the deceleration override for the traversing block. The override refers to the maximum deceleration (p2573).		
Dependency:	The number of indices depends on p2615. Refer to: p2573, p2615, p2616, p2617, p2618, p2619, p2621, p2622, p2623, p2624		
p2621[0...n]	EPOS traversing block task / Trav_block task		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T		Access level: 1
	Data type: Integer16	Dynamic index: p2615	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 1	Max 8	Factory setting 1
Description:	Sets the required task for the traversing block.		
Values:	1: POSITIONING 3: ENDLESS_POS 4: ENDLESS_NEG 5: WAITING 6: GOTO 7: SET_O 8: RESET_O		
Dependency:	The number of indices depends on p2615. Refer to: p2615, p2616, p2617, p2618, p2619, p2620, p2622, p2623, p2624		

p2622[0...n]	EPOS traversing block task parameter / Trav_blk task_par		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: p2615	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3616
	P-Group: Basic positioner		Unit selection: -
	Min -2147483648	Max 2147483647	Factory setting 0
Description:	Sets additional information/data of the appropriate task for the traversing block.		
Dependency:	The number of indices depends on p2615. Refer to: p2615, p2616, p2617, p2618, p2619, p2620, p2621, p2623, p2624		
Note:	The following should be set depending on the task: WAIT: Waiting time in ms GOTO: Block number SET_O: 1, 2 or 3 - set direct output 1, 2 or 3 (both) RESET_O: 1, 2 or 3 - set direct output 1, 2 or 3 (both)		
p2623[0...n]	EPOS traversing block, task mode / Trav_block mode		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: p2615	Access level: 1
	Data type: Unsigned16	Units group: -	Function diagram: 3616
	P-Group: Basic positioner		Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the influence of the task for the traversing block. Value = 0000 cccc bbbb aaaa cccc: Positioning mode cccc = 0000 --> ABSOLUTE cccc = 0001 --> RELATIVE cccc = 0010 --> ABS_POS (only for a rotary axis with modulo correction) cccc = 0011 --> ABS_NEG (only for a rotary axis with modulo correction) bbbb: Progression condition bbbb = 0000 --> END bbbb = 0001 --> CONTINUE WITH STOP bbbb = 0010 --> CONTINUE FLYING aaaa: IDs aaaa = 0001 --> Skip block		
Dependency:	The number of indices depends on p2615. Refer to: p2615, p2616, p2617, p2618, p2619, p2620, p2621, p2622, p2624		
p2624	EPOS traversing block, sorting / Trav_block sort		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Unsigned16	Units group: -	Function diagram: 3616
	P-Group: Basic positioner		Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the traversing blocks for sorting corresponding to their block number. p2624 = 0 --> 1: The sorting is started and the parameters are automatically reset to 0 after the sorting operation has been completed.		
Dependency:	Refer to: p2615, p2616, p2617, p2618, p2619, p2620, p2621, p2622, p2623		
Note:	After sorting, the traversing blocks are written at the beginning of the memory in increasing sequence without any gaps.		

p2625	BI: EPOS block selection, bit 0 / Block sel bit 0		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3640
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for block selection, bit 0.		
Dependency:	Binector inputs p2625, p2626, p2627, p2628, p2629 and p2630 are used to select one of the maximum of 64 traversing blocks. Refer to: p2626, p2627, p2628, p2629, p2630		
p2626	BI: EPOS block selection, bit 1 / Block sel bit 1:		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3640
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for block selection, bit 1.		
Dependency:	Binector inputs p2625, p2626, p2627, p2628, p2629 and p2630 are used to select one of the maximum of 64 traversing blocks. Refer to: p2625, p2627, p2628, p2629, p2630		
p2627	BI: EPOS block selection, bit 2 / Block sel bit 2		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3640
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for block selection, bit 2.		
Dependency:	Binector inputs p2625, p2626, p2627, p2628, p2629 and p2630 are used to select one of the maximum of 64 traversing blocks. Refer to: p2625, p2626, p2628, p2629, p2630		
p2628	BI: EPOS block selection, bit 3 / Block sel bit 3		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3640
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for block selection, bit 3.		
Dependency:	Binector inputs p2625, p2626, p2627, p2628, p2629 and p2630 are used to select one of the maximum of 64 traversing blocks. Refer to: p2625, p2626, p2627, p2629, p2630		

p2629	BI: EPOS block selection, bit 4 / Block sel bit 4		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3640
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for block selection, bit 4.		
Dependency:	Binector inputs p2625, p2626, p2627, p2628, p2629 and p2630 are used to select one of the maximum of 64 traversing blocks. Refer to: p2625, p2626, p2627, p2628, p2630		
p2630	BI: EPOS block selection, bit 5 / Block sel bit 5		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3640
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for block selection, bit 5.		
Dependency:	Binector inputs p2625, p2626, p2627, p2628, p2629 and p2630 are used to select one of the maximum of 64 traversing blocks. Refer to: p2625, p2626, p2627, p2628, p2629		
p2631	BI: EPOS activate traversing task (0 -> 1) / Trav_task act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3640
	P-Group: -		Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for "activating traversing task". BI: p2631 = 0/1 signal The traversing task, selected using BI: p2625 ... p2630, is started.		
Dependency:	Refer to: p2625, p2626, p2627, p2628, p2629, p2630, p2640, p2641		
Note:	To start a traversing block, the axis must be referenced (r2684.11 = 1). The status signal r2684.12 = 0/1 signal is used for acknowledgement. A traversing task can be influenced using the following signals: - intermediate stop via BI: p2640. - reject traversing task via BI: p2641.		

p2640	BI: EPOS intermediate stop (0 signal) / Intermediate stop		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the "no intermediate stop/intermediate stop". BI: p2640 = 1 signal No intermediate stop. BI: p2640 = 0 signal Intermediate stop.		
Dependency:	Refer to: p2631, p2641, p2647		
Note:	This signal is only effective in the modes "traversing blocks" and "direct setpoint input/MDI". When activating the intermediate stop, the axis brakes with the parameterized deceleration (p2620 or p2645). BI:p2649 = 1 signal : Motion starts without it being explicitly controlled.		
p2641	BI: EPOS reject traversing task (0 signal) / Trav_task reject		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for "do not reject traversing task/reject traversing task". BI: p2641 = 1 signal Do not reject traversing task. BI: p2641 = 0 signal Reject traversing task.		
Dependency:	Refer to: p2631, p2640, p2647		
Note:	This signal is only effective in the modes "traversing blocks" and "direct setpoint input/MDI". When activating reject traversing tasks, then the axis brakes with the maximum deceleration (p2573). BI:p2649 = 1 signal : Motion starts without it being explicitly controlled.		
p2642	CI: EPOS direct setpoint input/MDI position setpoint / MDI s_set		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3618
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	2690[0]
Description:	Sets the signal source for the position setpoint in the mode "direct setpoint input/MDI".		
Dependency:	Refer to: p2648, p2649, p2650, p2690		
Note:	Depending on p2649, the position setpoint is either transferred continuously or edge-triggered. The position setpoint input is interpreted as length unit [LU].		
p2643	CI: EPOS direct setpoint input/MDI velocity setpoint / MDI v_set		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3618
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	2691[0]
Description:	Sets the signal source for the velocity setpoint in the "direct setpoint input/MDI mode".		

Dependency: Refer to: p2649, p2650, p2691
Note: Depending on p2649, the velocity setpoint is either transferred continuously or edge-triggered.
The velocity setpoint input is interpreted as [1000 LU/min].

p2644 **CI: EPOS direct setpoint input/MDI acceleration override / MDI a_over**

SERVO (EPOS),
VECTOR (EPOS) **Can be changed:** T **Access level:** 1
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 3618
P-Group: Basic positioner **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
- - 2692[0]

Description: Sets the signal source for the acceleration override in the operating mode "direct setpoint input/MDI".
Dependency: Refer to: p2649, p2650, p2692
Note: Depending on p2649, the acceleration override is either transferred continuously or edge-triggered.
The signal value 4000 hex (16384 dec) corresponds to 100 %.

p2645 **CI: EPOS direct setpoint input/MDI deceleration override / MDI -a_over**

SERVO (EPOS),
VECTOR (EPOS) **Can be changed:** T **Access level:** 1
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 3618
P-Group: Basic positioner **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
- - 2693[0]

Description: Sets the signal source for the deceleration override in the operating mode "direct setpoint input/MDI".
Dependency: Refer to: p2649, p2650, p2693
Note: Depending on p2649, the deceleration override is either transferred continuously or edge-triggered.
The signal value 4000 hex (16384 dec) corresponds to 100 %.

p2646 **CI: EPOS velocity override / v_over**

SERVO (EPOS),
VECTOR (EPOS) **Can be changed:** T **Access level:** 1
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 3630
P-Group: Basic positioner **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
- - 1

Description: Sets the signal source for the velocity override.
This velocity override is effective in the following operating modes "direct setpoint input/MDI", "traversing blocks", "jogging" and "search for reference" (when approaching the reference cam).
Dependency: Refer to: p2571, p2585, p2586, p2605, p2618, p2643, r2681
Note: The effective override (r2681) can differ from the specified override due to limits (e.g. maximum velocity).

p2647 **BI: EPOS direct setpoint input/MDI selection / MDI selection**

SERVO (EPOS),
VECTOR (EPOS) **Can be changed:** T **Access level:** 1
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 3640
P-Group: Basic positioner **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
- - 0

Description: Sets the signal source for selecting the operating mode "direct setpoint input/MDI".
Dependency: Refer to: p2640, p2641, p2642, p2643, p2644, p2645, p2646, p2648, p2649, p2650, p2651, p2652, p2653
Note: In this mode, using BI: p2653 it is possible to make a flying changeover between setting-up and positioning.
In this mode, even if the axis is not referenced (r2684.11 = 0) relative positioning is possible.

p2648	BI: EPOS direct setpoint input/MDI positioning type / MDI pos_type		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the positioning type in the mode "direct setpoint input/MDI". BI: p2648 = 1 signal Absolute positioning is selected. BI: p2648 = 0 signal Relative positioning is selected.		
Dependency:	Refer to: p2649, p2650, p2654 Refer to: A07461, F07488		
Notice:	Absolute positioning: To traverse, the reference point must be set (r2684.11 = 1). Relative positioning: To traverse, it is not necessary that the reference point is set.		
Note:	Depending on p2649, the positioning type is either transferred continuously or edge-triggered.		
p2649	BI: EPOS direct setpoint input/MDI transfer type selection / MDI trans_type sel		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to define how values are transferred in the operating mode "direct setpoint input/MDI". BI: p2649 = 1 signal Values are continually transferred (refer to parameter under dependency). Motion starts without it being explicitly controlled. BI: p2649 = 0 signal The values are transferred for BI: p2650 = 0/1 signal.		
Dependency:	Refer to: p2642, p2643, p2644, p2645, p2648, p2650, p2651, p2652		
p2650	BI: EPOS direct setpoint input/MDI setpoint transfer edge / MDI setpt_transfer		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to transfer the values for edge-triggered selection (BI: p2649 = 0 signal) in the operating mode "direct setpoint input/MDI". BI: p2650 = 0/1 signal and BI: p2649 = 0 signal Values are transferred, edge-triggered (refer to parameter under dependency).		
Dependency:	Refer to: p2640, p2641, p2642, p2643, p2644, p2645, p2648, p2649, p2651, p2652, r2684		
Note:	The status signal r2684.12 = 0/1 signal is used for acknowledgement. The operating mode "direct setpoint input/MDI" can be influenced via the following signals: - intermediate stop via BI: p2640. - reject traversing task via BI: p2641.		

p2651	BI: EPOS direct setpoint input/MDI direction selection, positive / MDI dir_sel pos		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the positive direction selection in the operating mode "direct setpoint input/MDI".		
Dependency:	Refer to: p2576, p2648, p2649, p2650, p2652, p2653, p2654		
Note:	<p>The following applies for "setting-up":</p> <ul style="list-style-type: none"> - the traversing direction can be entered using this binector input. - if both directions (p2651, p2652) are selected one after the other, then the last selection remains active. - if both directions (p2561, p2652) are selected simultaneously, then the axis remains stationary (zero speed). <p>The following applies for "positioning":</p> <p>Using binector inputs p2651 and p2652, when the modulo correction (BI: p2576 = 1 signal) is activated and for absolute positioning (BI: p2648 = 1 signal), the traversing direction is specified as follows:</p> <p>BI: p2651 / BI: p2652</p> <ul style="list-style-type: none"> 0 signal / 0 signal: Absolute positioning through the shortest distance. 1 signal / 0 signal: Absolute positioning in the positive direction. 0 signal / 1 signal: Absolute positioning in the negative direction. 1 signal / 1 signal: Absolute positioning through the shortest distance. 		
p2652	BI: EPOS direct setpoint input/MDI direction selection, negative / MDI dir_sel neg		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the negative direction selection in the operating mode "direct setpoint input/MDI".		
Dependency:	Refer to: p2576, p2648, p2649, p2650, p2651, p2653, p2654		
Note:	<p>The following applies for "setting-up":</p> <ul style="list-style-type: none"> - the traversing direction can be entered using this binector input. - if both directions (p2651, p2652) are selected one after the other, then the last selection remains active. - if both directions (p2561, p2652) are selected simultaneously, then the axis remains stationary (zero speed). <p>The following applies for "positioning":</p> <p>Using binector inputs p2651 and p2652, when the modulo correction (BI: p2576 = 1 signal) is activated and for absolute positioning (BI: p2648 = 1 signal), the traversing direction is specified as follows:</p> <p>BI: p2651 / BI: p2652</p> <ul style="list-style-type: none"> 0 signal / 0 signal: Absolute positioning through the shortest distance. 1 signal / 0 signal: Absolute positioning in the positive direction. 0 signal / 1 signal: Absolute positioning in the negative direction. 1 signal / 1 signal: Absolute positioning through the shortest distance. 		

p2653	BI: EPOS direct setpoint input/MDI setting-up selection / MDI setting-up sel		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for setting-up in the operating mode "direct setpoint input/MDI". BI: p2653 = 1 signal Setting-up selected. BI: p2653 = 0 signal Positioning selected.		
Note:	In the operating mode "direct setpoint input/MDI", it is possible to make a flying changeover between setting-up and positioning.		
p2654	CI: EPOS direct setpoint input/MDI mode adaptation / MDI mode adapt		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to interconnect the MDI mode to the operating mode "direct setpoint input MDI" via PROFIBUS telegram 110. CI: p2654 = 0 The binector inputs listed below are evaluated. CI: p2654 > 0 The following binector inputs are not evaluated: - BI: p2648 (positioning type) - BI: p2651 (direction selection, positive) - BI: p2652 (direction selection, negative) In this case, the following definitions apply: Signal via CI: p2654 = xx0x hex -> absolute Signal via CI: p2654 = xx1x hex -> relative Signal via CI: p2654 = xx2x hex -> abs_pos (only for modulo correction) Signal via CI: p2654 = xx3x hex -> abs_neg (only for modulo correction)		
Dependency:	Refer to: p2648, p2651, p2652		

p2655[0...1]	BI: EPOS select tracking mode / Sel tracking mode		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3635
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	[0] 1 [1] 2526.7
Description:	Sets the signal source to select tracking mode. BI: p2655[0] or BI: p2655[1] = 1 signal Tracking operation after withdrawing the enable signal from EPOS (BI: p2656 = 0 signal). BI: p2655 and BI: p2655[1] = 0 signal No tracking operation after withdrawing the enable signal from EPOS (BI: p2656 = 0 signal).		
Dependency:	Refer to: p2656		
Note:	For the following events, independent of the signal that is present, tracking operation is selected: - after booting. - after a 0/1 signal at BI: p2658 (EPOS position actual value, valid feedback signal). - while a fault is present.		
p2656	BI: EPOS enable basic positioner / EPOS enable		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 3635
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	2526.3
Description:	Sets the signal source to enable the basic positioner. BI: p2656 = 1 signal The basic positioner is enabled. BI: p2656 = 0 signal The basic positioner is not enabled.		
Dependency:	Refer to: r2526, p2655		
p2657	CI: EPOS position actual value/position setting value / Pos act/set value		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 3610, 3635
	P-Group: Basic positioner		Unit selection: -
	Min	Max	Factory setting
	-	-	2521[0]
Description:	Sets the signal source for the position actual value/position setting value.		
Dependency:	Refer to: r2521, p2658		
Note:	In the tracking mode, the position setpoint is taken from this connector input.		

p2658	BI: EPOS pos. actual value valid, feedback signal / Pos valid feedback		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3635
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	2526.0
Description:	Sets the signal source for the feedback signal "position actual value is valid". BI: p2658 = 1 signal The position actual value received via CI: p2657 is valid. BI: p2658 = 0 signal The position actual value received via CI: p2657 is invalid.		
Dependency:	Refer to: r2526, p2657		
Note:	While a 0 signal is present, the position setpoint (p2665) is held at the value of 0.		
p2659	BI: EPOS referencing active feedback signal / Ref act fdbk		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	2526.1
Description:	Sets the signal source for the feedback signal "referencing active". BI: p2659 = 1 signal Referencing is active. BI: p2659 = 0 signal Referencing is not active.		
Dependency:	Refer to: r2526		
p2660	CI: EPOS measured value referencing / Meas val ref		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	2523[0]
Description:	Sets the signal source for the measured value for the function "referencing".		
Dependency:	Refer to: r2523		
p2661	BI: EPOS measured value valid, feedback signal / MeasVal valid fdbk		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	2526.2
Description:	Sets the signal source for the feedback signal "measured value valid". BI: p2661 = 1 signal The measured value received via CI: p2660 is valid. BI: p2661 = 0 signal The measured value received via CI: p2660 is invalid.		
Dependency:	Refer to: r2526		

r2665	CO: EPOS position setpoint / s_set		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: - Data type: Integer32 P-Group: Basic positioner	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3635 Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the actual absolute position setpoint.		
Dependency:	Refer to: p2530		
Note:	As standard, the following BICO interconnection is established: CI: p2530 = r2665		
r2666	CO: EPOS velocity setpoint / v_set		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: - Data type: Integer32 P-Group: Basic positioner	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3635 Unit selection: -
	Min - [1000 LU/min]	Max - [1000 LU/min]	Factory setting - [1000 LU/min]
Description:	Displays the actual velocity setpoint.		
Dependency:	Refer to: p2531		
Note:	As standard, the following BICO interconnection is established: CI: p2531 = r2666		
r2667	CO: EPOS backlash compensation value / Backlash value		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: - Data type: Integer32 P-Group: Basic positioner	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3635 Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the currently effective value for backlash compensation.		
Dependency:	Refer to: p2516		
Note:	As standard, the following BICO interconnection is established: CI: p2516 = r2667		
r2669	CO: EPOS actual operating mode / Op mode act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: - Data type: Integer32 P-Group: Basic positioner	Dynamic index: - Units group: -	Access level: 1 Function diagram: 3630 Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the actual, active operating mode. Value = 00 hex -> no operating mode active Value = 01 hex -> jogging active Value = 02 hex -> search for reference active Value = 04 hex -> traversing blocks active Value = 08 hex -> Positioning for direct setpoint input/MDI active Value = 10 hex -> Setting-up for direct setpoint input/MDI active Value = 20 hex -> flying referencing active		
Dependency:	Refer to: p2589, p2590, p2595, p2631, p2647, p2653		

r2670		CO/BO: EPOS status word, active traversing block / ZSW act trav_block		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 3650
	P-Group: Basic positioner	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the status word for the active traversing block. r2670.0: Active traversing block, bit 0 ... r2670.5: Active traversing block, bit 5 r2670.15: MDI active			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Active traversing block, bit 0	active	Not active
	01	Active traversing block, bit 1	active	Not active
	02	Active traversing block, bit 2	active	Not active
	03	Active traversing block, bit 3	active	Not active
	04	Active traversing block, bit 4	active	Not active
	05	Active traversing block, bit 5	active	Not active
	15	MDI active	active	Not active
Dependency:	Refer to: p2631, p2647			
Note:	Re bit 00 ... 05: Displays the active traversing block in the traversing blocks operating mode. Re bit 15: For a 1 signal, the operating mode - direct setpoint input/MDI - is active			

r2671		CO: EPOS actual position setpoint / s_set act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -			Access level: 1
	Data type: Integer32	Dynamic index: -		Function diagram: 3610, 3616, 3620
	P-Group: Basic positioner	Units group: -		Unit selection: -
	Min - [LU]	Max - [LU]		Factory setting - [LU]
Description:	Displays the position setpoint presently being processed.			
Note:	A position of zero is displayed for non position-related tasks (e.g. ENDLESS_POS, ENDLESS_NEG).			

r2672		CO: EPOS actual velocity setpoint / v_set act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -			Access level: 1
	Data type: Integer32	Dynamic index: -		Function diagram: 3610, 3612, 3616, 3620
	P-Group: Basic positioner	Units group: -		Unit selection: -
	Min - [1000 LU/min]	Max - [1000 LU/min]		Factory setting - [1000 LU/min]
Description:	Displays the velocity setpoint presently being processed.			

r2673		CO: EPOS actual acceleration override / a_over act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -			Access level: 1
	Data type: Floating Point	Dynamic index: -		Function diagram: 3610, 3612, 3616, 3620
	P-Group: Basic positioner	Units group: -		Unit selection: -
	Min - [%]	Max - [%]		Factory setting - [%]
Description:	Displays the acceleration override presently being processed.			
Note:	An override of 100% is effective in the "jogging" and "search for reference" operating modes.			

r2674	CO: EPOS actual deceleration override / -a_over act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point		Function diagram: 3610, 3612, 3616, 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the deceleration override presently being processed.		
Note:	An override of 100% is effective in the "jogging" and "search for reference" operating modes.		

r2675	CO: EPOS actual task / Task act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer16		Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min 0	Max 8	Factory setting 0
Description:	Displays the task presently being processed in the "traversing blocks" operating mode.		
Values:	0: inactive 1: POSITIONING 3: ENDLESS_POS 4: ENDLESS_NEG 5: WAITING 6: GOTO 7: SET_O 8: RESET_O		
Dependency:	Refer to: p2621		

r2676	CO: EPOS actual task parameter / Task para act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32		Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the task parameter presently being processed in the "traversing blocks" operating mode.		
Dependency:	Refer to: p2622		
Note:	The following is displayed depending on the task: WAIT: Waiting time in ms GOTO: Block number SET_O: 1, 2 or 3 - direct output 1, 2 or 3 (both) is set RESET_O: 1, 2 or 3 - direct output 1, 2 or 3 (both) is set		

r2677	CO: EPOS actual task mode / Task mode act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Unsigned16		Function diagram: 3616
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the task mode presently being processed.		
Dependency:	Refer to: p2623		

r2678	CO: EPOS external block change / Ext BlckChg s_act		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32		Function diagram: 3616, 3620
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the actual position for an external block change. "Jog" operating mode: Displays the actual position that is present at the external block change (BI: p2589 = 0/1 signal or BI: p2590 = 0/1 signal). "Referencing" operating mode: Displays the actual position that is present at the external block change (BI: p2595 = 0/1 signal). "Traversing blocks" operating mode: Displays the actual position that is present at the external block change (BI: p2631 = 0/1 signal). "Direct setpoint input/MDI" mode: Displays the actual position that is present at the external block change (BI: p2650 = 0/1 signal).		
Dependency:	Refer to: p2589, p2590, p2595, p2631, p2650		
r2680	CO: EPOS clearance, reference cam and zero mark / Clearance cam/ZM		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32		Function diagram: 3612
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the clearance determined between the reference cam and zero mark in the search for reference.		
r2681	CO: EPOS velocity override effective / v_over effective		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Floating Point		Function diagram: 3630
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the currently effective velocity override.		
Dependency:	Refer to: p2571, p2646		
Note:	The effective override can differ from the specified override due to limits (e.g. p2571, maximum velocity).		
r2682	CO: EPOS residual distance to go / Residual distance		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32		Function diagram: 3635
	P-Group: Basic positioner	Units group: -	Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the actual residual distance. The remaining distance is the distance to still to be moved through up to the end of the current positioning task.		
Dependency:	Refer to: r2665, r2671, r2678		

r2683 CO/BO: EPOS status word 1 / PosZSW1SERVO (Pos ctrl),
VECTOR (Pos ctrl)**Can be changed:** -**Data type:** Unsigned16**P-Group:** Closed loop position control**Min**

-

Dynamic index: -**Units group:** -**Max**

-

Access level: 1**Function diagram:** 3645**Unit selection:** -**Factory setting**

0000 bin

Description: Displays status word 1 for the basic positioner (EPOS).**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
00	Tracking operation active	Yes	No	3635
01	Velocity limiting active	Yes	No	3630
02	Setpoint available	Yes	No	3635
04	Axis moves forwards	Yes	No	3635
05	Axis moves backwards	Yes	No	3635
06	Software limit switch minus reached	Yes	No	3635
07	Software limit switch plus reached	Yes	No	3635
08	Position actual value <= cam switching position 1	Yes	No	4025
09	Position actual value <= cam switching position 2	Yes	No	4025
10	Direct output 1 via traversing block	Yes	No	3616
11	Direct output 2 via traversing block	Yes	No	3616

Dependency: Refer to: r2684**Note:** Re bit 08, 09:

These signals are generated in the "closed-loop position control" function module.

r2684 CO/BO: EPOS status word 2 / PosZSW2SERVO (Pos ctrl),
VECTOR (Pos ctrl)**Can be changed:** -**Data type:** Unsigned16**P-Group:** Closed loop position control**Min**

-

Dynamic index: -**Units group:** -**Max**

-

Access level: 1**Function diagram:** 3646**Unit selection:** -**Factory setting**

0000 bin

Description: Displays status word 2 for the basic positioner (EPOS).**Bit field:**

Bit	Signal name	1 signal	0 signal	FP
00	Search for reference active	active	Not active	3612, 3614
01	Flying referencing active	active	Not active	3614
02	Referencing active	active	Not active	3614
03	Printing mark outside outer window	Yes	No	3614
04	Axis accelerating	Yes	No	3635
05	Axis decelerating	Yes	No	3635
07	Activate correction	Yes	No	3635
08	Follow err in tol	Yes	No	-
10	Target position reached	Yes	No	4020
11	Reference point set	Yes	No	3612, 3614
12	Acknowledgment, traversing block activated	Yes	No	3616
13	STOP cam minus active	Yes	No	3630
14	STOP cam plus active	Yes	No	3630
15	Travel command active	Yes	No	3635

Note: Re bit 02:

The "referencing active" signal is an OR logic operation of "search for reference active" and "flying referencing active".

Re bit 00 ... 07 and 11 ... 14:

These signals are generated in the function module "basic positioner".

Re bit 08:

The signal is generated in the "closed-loop position control" function module.

r2685	CO: EPOS correction value / Correction value		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3635
	P-Group: Basic positioner		Unit selection: -
	Min - [LU]	Max - [LU]	Factory setting - [LU]
Description:	Displays the correction value for the position actual value.		
Dependency:	Refer to: r2684		
Note:	As standard, the following BICO interconnection is established: CI: p2513 = r2685 Using this value, e.g. modulo corrections are carried-out.		
p2690	CO: EPOS position fixed setpoint / Pos fixed value		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer32	Units group: -	Function diagram: 3618
	P-Group: Basic positioner		Unit selection: -
	Min -2147483648 [LU]	Max 2147483647 [LU]	Factory setting 0 [LU]
Description:	Sets a fixed setpoint for the position.		
Dependency:	Refer to: p2642		
Note:	As standard, the following BICO interconnection is established: CI: p2642 = r2690		
p2691	CO: EPOS velocity fixed setpoint / v fixed value		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Unsigned32	Units group: -	Function diagram: 3618
	P-Group: Basic positioner		Unit selection: -
	Min 1 [1000 LU/min]	Max 40000000 [1000 LU/min]	Factory setting 600 [1000 LU/min]
Description:	Sets a fixed setpoint for the velocity.		
Dependency:	Refer to: p2643		
Note:	As standard, the following BICO interconnection is established: CI: p2643 = r2691		
p2692	CO: EPOS acceleration override, fixed setpoint / a_over fixed val		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 3618
	P-Group: Basic positioner		Unit selection: -
	Min 0 [%]	Max 100 [%]	Factory setting 100 [%]
Description:	Sets a fixed setpoint for the acceleration override.		
Dependency:	Refer to: p2572, p2644		
Note:	As standard, the following BICO interconnection is established: CI: p2644 = r2692 The percentage value refers to the maximum acceleration (p2572).		

p2693	CO: EPOS deceleration override, fixed setpoint / -a_over fixed val		
SERVO (EPOS), VECTOR (EPOS)	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Floating Point	Units group: -	Function diagram: 3618
	P-Group: Basic positioner		Unit selection: -
	Min 0 [%]	Max 100 [%]	Factory setting 100 [%]
Description:	Sets a fixed setpoint for the deceleration override.		
Dependency:	Refer to: p2573, p2645		
Note:	As standard, the following BICO interconnection is established: CI: p2645 = r2693 The percentage value refers to the maximum deceleration (p2573).		
p2900[0...n]	CO: Fixed value 1 [%] / Fixed value 1 [%]		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 1021
	P-Group: Free function blocks		Unit selection: -
	Min -10000.00 [%]	Max 10000.00 [%]	Factory setting 0.00 [%]
Description:	Sets a fixed percentage.		
Dependency:	Refer to: p2901, p2930		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	The value can be used to interconnect a scaling function (e.g. scaling of the main setpoint)		
p2901[0...n]	CO: Fixed value 2 [%] / Fixed value 2 [%]		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 1021
	P-Group: Free function blocks		Unit selection: -
	Min -10000.00 [%]	Max 10000.00 [%]	Factory setting 0.00 [%]
Description:	Sets a fixed percentage.		
Dependency:	Refer to: p2900, p2930		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	The value can be used to interconnect a scaling function (e.g. scaling of the supplementary setpoint)		
p2930[0...n]	CO: Fixed value M [Nm] / Fixed value M [Nm]		
SERVO, VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Floating Point	Units group: 7_1	Function diagram: 1021
	P-Group: Free function blocks		Unit selection: p0505
	Min -100000.00 [Nm]	Max 100000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets a fixed value for torque.		
Dependency:	Refer to: p2900, p2901		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	The value can, for example, be used to interconnect a supplementary torque.		

p2930[0...n]	CO: Fixed value F [N] / Fixed value F [N]		
SERVO (Lin)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 1021
	P-Group: Free function blocks	Units group: 8_1	Unit selection: p0505
	Min -100000.00 [N]	Max 100000.00 [N]	Factory setting 0.00 [N]
Description:	Sets a fixed value for force.		
Dependency:	Refer to: p2900, p2901		
Notice:	A BICO interconnection to a parameter that belongs to a drive objects always acts on the effective data set.		
Note:	The value can, for example, be used to interconnect a supplementary force.		
p3100	RTC time stamp mode / RTC t_stamp mode		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the mode for the time stamp p3100 = 0: Time stamp, operating hours p3100 = 1: Time stamp, UTC format		
Note:	RTC: Real Time Clock UTC: Universal Time Coordinates The UTC time started, according to the definition on 01.01.1970 at 00:00:00 and is output in days and milliseconds.		
p3101[0...1]	RTC set UTC time / RTC set UTC		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Setting the UTC time. This means that the drive system is synchronized to the time specified by the time master. To start p3101[1] must be written to followed by p3101[0]. After writing to p3101[0], the UTC time is accepted. p3101[0]: Milliseconds p3101[1]: Days		
r3102[0...1]	RTC read UTC time / RTC read UTC		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the actual UTC time in the drive system. p3102[0]: Milliseconds p3102[1]: Days		

p3103	RTC synchronization source / RTC sync_source		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	Sets the synchronization source/technique.		
Values:	0: PROFIBUS 1: PROFINET 2: PPI 3: PROFINET PTP		
p3104	BI: RTC real time synchronization PING / RTC PING		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the PING event to set the UTC time.		
r3108[0...1]	RTC last synchronization deviation / RTC sync_dev		
CU_S	Can be changed: -		Access level: 3
	Data type: Signed32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the last synchronization deviation that was determined. r3108[0]: Milliseconds r3108[1]: Days		
p3109	RTC real time synchronization, tolerance window / RTC sync tol		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 100 [ms]
Description:	Sets the tolerance window for time synchronization. When this tolerance window is exceeded, an appropriate alarm is output.		
Dependency:	Refer to: A01099		
p3110	External fault 3, power-up delay / Ext fault 3 t_on		
All objects	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 2546
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 0 [ms]
Description:	Sets the delay time for external fault 3.		
Dependency:	Refer to: p2108, p3111, p3112 Refer to: F07862		

p3111	BI: External fault 3, enable / Ext fault 3 enab		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: 2546
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the enable signal of external fault 3. External fault 3 is initiated by the following AND logic operation: - BI: p2108 negated - BI: p3111 - BI: p3112 negated		
Dependency:	Refer to: p2108, p3110, p3112 Refer to: F07862		

p3111[0...n]	BI: External fault 3, enable / Ext fault 3 enab		
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T Data type: Unsigned32	Dynamic index: CDS, p0170	Access level: 3 Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source for the enable signal of external fault 3. External fault 3 is initiated by the following AND logic operation: - BI: p2108 negated - BI: p3111 - BI: p3112 negated		
Dependency:	Refer to: p2108, p3110, p3112 Refer to: F07862		

p3112	BI: External fault 3 enable negated / Ext flt 3 enab neg		
CU_LINK, CU_S, DMC20, TB30, TM15, TM15DI_DO, TM17, TM31	Can be changed: U, T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: 2546
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the negated enable signal of external fault 3. External fault 3 is initiated by the following AND logic operation: - BI: p2108 negated - BI: p3111 - BI: p3112 negated		
Dependency:	Refer to: p2108, p3110, p3111 Refer to: F07862		

p3112[0...n]	BI: External fault 3 enable negated / Ext flt 3 enab neg				
A_INF, B_INF, SERVO, S_INF, TM41, VECTOR	Can be changed: U, T	Dynamic index: CDS, p0170	Access level: 3		
	Data type: Unsigned32		Function diagram: -		
	P-Group: Messages	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0		
Description:	Sets the signal source for the negated enable signal of external fault 3. External fault 3 is initiated by the following AND logic operation: - BI: p2108 negated - BI: p3111 - BI: p3112 negated				
Dependency:	Refer to: p2108, p3110, p3111 Refer to: F07862				
r3113	CO/BO: NAMUR message bit bar / NAMUR bit bar				
All objects	Can be changed: -	Dynamic index: -	Access level: 3		
	Data type: Unsigned16		Function diagram: -		
	P-Group: Messages	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the status of NAMUR signal bit bar. The faults or alarms are assigned to the appropriate signaling/message classes and influence a specific message bit.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fault, drive converter data electronics / software error	Yes	No	-
	01	Line supply fault	Yes	No	-
	02	DC link overvoltage	Yes	No	-
	03	Fault, drive converter power electronics	Yes	No	-
	04	Drive converter overtemperature	Yes	No	-
	05	Ground fault	Yes	No	-
	06	Motor overload	Yes	No	-
	07	Bus error	Yes	No	-
	08	External safety-relevant shutdown	Yes	No	-
	09	Mot encoder fault	Yes	No	-
	10	Error, internal communications	Yes	No	-
	11	Infeed fault	Yes	No	-
	15	Other faults	Yes	No	-
p3201[0...n]	Excitation current outside the tolerance threshold value / I_exc n.Tol thresh				
VECTOR	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3		
	Data type: Floating Point		Function diagram: -		
	P-Group: Messages	Units group: -	Unit selection: -		
	Min 0.1 [%]	Max 100.0 [%]	Factory setting 10.0 [%]		
Description:	Sets the threshold value for the "excitation current outside tolerance" message for the excitation current monitoring. If the absolute value of the difference between the excitation current setpoint and actual value (r1641 - r1626) exceeds the threshold value and the hysteresis is longer than the selected delay time, then fault F07913 is output. This fault is withdrawn when the threshold voltage is fallen below.				
Dependency:	Refer to: r1626, r1641, p3202, p3203 Refer to: F07913				
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5).				

p3202[0...n]	Excitation current outside the tolerance hysteresis / I_exc n.Tol hyst		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.1 [%]	Max 100.0 [%]	Factory setting 10.0 [%]
Description:	Sets the hysteresis for the "excitation current outside tolerance" message for the excitation current monitoring.		
Dependency:	Refer to: p3201, p3203 Refer to: F07913		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5).		
p3203[0...n]	Excitation current outside the tolerance delay time / I_exc n.Tol t_del		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.0 [s]	Max 10.0 [s]	Factory setting 1.0 [s]
Description:	Sets the delay time for the "excitation current outside tolerance" message for the excitation current monitoring.		
Dependency:	Refer to: p3201, p3202 Refer to: F07913		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5).		
p3204[0...n]	Flux outside the tolerance threshold value / Flux n. tol thresh		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.1 [%]	Max 100.0 [%]	Factory setting 10.0 [%]
Description:	Sets the threshold value for the "flux outside the tolerance" message for the flux monitoring. If the absolute value of the difference between the flux setpoint and actual value (r0083 - r0084) falls below the threshold value with hysteresis longer than the selected delay time, then fault F07914 is output. This fault is withdrawn when the threshold voltage is fallen below.		
Dependency:	Refer to: r0083, r0084, p3205, p3206 Refer to: F07914		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5). The flux monitoring is only active after magnetization (r0056.4 = 1).		
p3205[0...n]	Flux outside the tolerance hysteresis / Flux n. tol hyst		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.1 [%]	Max 50.0 [%]	Factory setting 10.0 [%]
Description:	Sets the hysteresis for the "flux outside tolerance" message for the flux monitoring.		
Dependency:	Refer to: p3204, p3206 Refer to: F07914		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5). The flux monitoring is only active after magnetization (r0056.4 = 1).		

p3206[0...n]	Flux outside tolerance delay time / Flux n. tol t_del		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.0 [s]	Max 10.0 [s]	Factory setting 5.0 [s]
Description:	Sets the delay time for the "flux outside tolerance" message for the flux monitoring.		
Dependency:	Refer to: p3204, p3205 Refer to: F07914		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5). The flux monitoring is only active after magnetization (r0056.4 = 1).		
p3207[0...n]	Zero current signal, threshold value / I_0_sig thresh		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: 6_2	Unit selection: p0505
	Min 0.01 [Aeff]	Max 10000.00 [Aeff]	Factory setting 1.00 [Aeff]
Description:	Sets the threshold value for the zero current signal for the zero current monitoring. If the absolute current falls below the threshold value then r2199.6 is set to 1 after the delay time has expired. The bit is reset if the threshold value and the hysteresis are exceeded again.		
Dependency:	Refer to: r2199, p3208, p3209		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5). The monitoring is only carried-out for speeds less than the speed threshold value in p2161 (r2199.0 = 1).		
p3208[0...n]	Zero current signal, hysteresis / I_0_sig hyst		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: 6_2	Unit selection: p0505
	Min 0.01 [Aeff]	Max 10000.00 [Aeff]	Factory setting 1.00 [Aeff]
Description:	Sets the hysteresis for the zero current signal for the zero current monitoring.		
Dependency:	Refer to: p3207, p3209		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5). The monitoring is only carried-out for speeds less than the speed threshold value in p2161 (r2199.0 = 1).		
p3209[0...n]	Zero current signal, delay time / I_0_sig t_del		
VECTOR	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0.00 [s]	Max 10.00 [s]	Factory setting 0.02 [s]
Description:	Sets the delay time for the zero current signal for the zero current monitoring.		
Dependency:	Refer to: p3207, p3208		
Note:	The monitoring function is only carried-out for separately-excited synchronized motors (p0300 = 5). The monitoring is only carried-out for speeds less than the speed threshold in p2161 (r2199.0 = 1).		

p3400		Infeed configuration word / INF config word		
A_INF, S_INF	Can be changed: T			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: 8940
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		1010 bin
Description:	Sets the configuration word of the infeed.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Smart Mode	On	Off
	01	Flat-top mode	On	Off
	03	Vdc controller	On	Off
	05	Line supply voltage sensing with VSM	On	Off
Dependency:	Refer to: p0210			
Note:	Re bit 00: In the smart mode, the DC link voltage is not controlled - however, infeed can still regenerate. The magnitude of the DC link voltage depends on the actual line supply voltage and the DC link load. For drive units belonging to the 400 V voltage class, for a drive unit supply voltage (p0210) greater than 415 V, the infeed is always operated in the smart mode. This means that the 660 V limit can be maintained for the steady-state DC link voltage (p0280) up to a line supply voltage of 480 V.			
	Re bit 01: If the flat top mode is deactivated, switching losses are higher. This means that the full power is no longer continuously available. For p3400.0 = 1, this bit is not effective.			
	Re bit 03: If the Vdc controller is switched-out, overvoltage or undervoltage conditions occur in the DC link if no other voltage-regulating component is located in the DC link. For p3400.0 = 1, this bit is not effective.			
	Re bit 05: VSM: Voltage Sensing Module If a VSM is detected when commissioning the system, this bit is automatically set. When the bit is set, the line supply voltage input of the VSM must be connected (connected at the line side of the commutating reactor).			

r3402		Infeed internal status / INF status int		
A_INF, S_INF	Can be changed: -			Access level: 2
	Data type: Integer16	Dynamic index: -		Function diagram: 8832, 8932
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min	Max		Factory setting
	0	11		0
Description:	Displays the internal status of the infeed module.			
Values:	0: Initialization 1: Fault 2: No ON command 3: Offset measurement running 4: ON delay active 5: Precharg. running 6: No pulse enable 7: Synchronization running 8: Voltage ramp-up active 9: Operation 10: Shutdown running 11: Identification running			

r3402 Infeed status internal BIC / INF status int

B_INF	Can be changed: -	Access level: 2
	Data type: Integer16	Dynamic index: -
	P-Group: Closed-loop control	Function diagram: 8932
		Unit selection: -
	Min	Max
	0	11
		Factory setting
		0
Description:	Displays the internal status of the infeed module.	
	0: Initialization	
	1: Fault	
	2: No ON command	
	4: ON delay active	
	5: Precharg. running	
	6: Operation	
Values:	0: Initialization	
	1: Fault	
	2: No ON command	
	3: Offset measurement running	
	4: ON delay active	
	5: Precharg. running	
	6: No pulse enable	
	7: Synchronization running	
	8: Voltage ramp-up active	
	9: Operation	
	10: Shutdown running	
	11: Identification running	

r3405 CO/BO: Status word infeed / INF ZSW

A_INF, S_INF	Can be changed: -	Access level: 2			
	Data type: Unsigned16	Dynamic index: -			
	P-Group: Closed-loop control	Function diagram: 8928			
		Unit selection: -			
	Min	Max			
	-	-			
		Factory setting			
		0000 bin			
Description:	Status word of the infeed.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Smart mode active	Yes	No	-
	01	Vdc-ctrl active	Yes	No	-
	02	Phase failure detected	Yes	No	-
	03	Current limit reached	Yes	No	-
	04	Infeed operates regenerating/motoring	Regenerative mode	Motor mode	-
	05	Motor operation inhibited	Yes	No	-
	06	Regenerative operation inhibited	Yes	No	-

Note: Re bit 02:
The bit indicates the alarm A6205 that is present.
The bit is set when a phase failure has been detected. The signal is reset, if
- the infeed has reached the normal operating state again (p3402 = 9) after a phase failure has been bypassed/buffered
- the pulse enable is withdrawn due to a fault or powering-down with OFF1/OFF2.

p3410		Infeed identification method / INF Ident_type	
A_INF, S_INF	Can be changed: C2(1), T		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 5	Factory setting 5
Description:	Sets the line and DC link parameter identification routine for the infeed module.		
Values:	0: Identification (Id) off 1: Activate identification (Id) 2: Set controller settings 3: Save identification and controller settings 4: Save identification and controller settings with L adaptation 5: Reset, save Id and controller setting with L adaptation		
Dependency:	Refer to: r3411, r3412, p3415, p3416, p3417, p3421, p3422 Refer to: A06400		
Notice:	For p3410 = 1, 3, 4, 5, alarm A06400 is output and designates that the selected identification will take place the next time that the pulses are enabled.		
Note:	<p>When p3410 = 1 an identification run for the total inductance and DC link capacitance is initiated when the pulses are next enabled. The results are displayed in r3411, r3412. The infeed then goes into the power-on state. For p3410 = 2, the data (r3411 and r3412) determined during the identification run (p3410 = 1) is transferred into p3421 and p3422. Calculations for the controller are then repeated. The user must save the new parameters in a non-volatile fashion in order to permanently select the new controller setting.</p> <p>When p3410 = 3 an identification run for the total inductance and DC link capacitance is initiated when the pulses are next enabled. The data determined during identification (r3411 and r3412) are transferred into p3421 and p3422 and the controller parameters recalculated. All of the parameters for the infeed module are then automatically stored in a non-volatile memory. The infeed continues to operate without any interruption with the new controller parameters.</p> <p>When p3410 = 4 an identification run for the total inductance and DC link capacitance is initiated when the pulses are next enabled. The data determined during identification (r3411 and r3412) are transferred into p3421 and p3422 and the controller parameters recalculated. The identification is then repeated at an increased current level (p3415[1]). If the inductance measured the second time is lower, the parameters are written to the current controller adaptation (p3620, p3622).. All of the parameters for the infeed module are then automatically stored in a non-volatile memory. The infeed continues to operate without any interruption with the new controller parameters.</p> <p>For p3410 = 5, the same measurements and write operations are always carried-out as for p3410 = 4. However, for the first identification run, initially the controller setting is reset by setting p3421 to p0223 and p3422 to p0227. Further, before the measurements are carried-out, a brief identification run is executed to coarsely set the controller. p3410 is automatically set to 0 after an identification run has been successfully completed.</p>		
r3411[0...1]		Infeed identified inductance / INF L ident	
A_INF, S_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [mH]	Max - [mH]	Factory setting - [mH]
Description:	Displays the identified total inductance. The value corresponds to the total inductance between the rigid line supply and the infeed input terminals.		
Index:	[0] = Result run 1 [1] = Result run 2		
Dependency:	Refer to: p3410		
Note:	<p>The value measured in the first identification run is displayed in r3411[0] (if p3410 = 1, 3, 4, 5). This value is transferred to p3421.</p> <p>The value measured in the second identification run (if p3410 = 4, 5) is displayed in r3411[1] - this value is used to set the current controller adaptation (p3622).</p>		


r3412[0...1]	Infeed DC-link capacitance identified / INF C_DClink ident		
A_INF, S_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [mF]	Max - [mF]	Factory setting - [mF]
Description:	Displays the identified total DC link capacitance.		
Index:	[0] = Result run 1 [1] = Result run 2		
Dependency:	Refer to: p3410		
Note:	The value measured in the first identification run (if p3410 = 1, 3, 4, 5) is displayed in r3412[0]. For p3410 = 1, 3, this value is transferred to p3422. The DC link capacitance is not measured at the second identification run.		
p3415[0...1]	Infeed excitation current L identification / INF I_exc L_Ident		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]	Factory setting [0] 30.00 [%] [1] 48.00 [%]
Description:	Sets the magnitude of the excitation frequency for the L identification. The setting is made as a percentage of the maximum power unit current (r0209).		
Index:	[0] = Result run 1 [1] = Result run 2		
Dependency:	Refer to: p3410, r3411, p3421, p3620, p3622		
Notice:	In order to correctly identify the current level (p3410 = 4, 5) depending on the reactor inductance, the following must apply: p3415[0] < p3415[1]		
Note:	The reactive current for identification run 1 is set in p3415[0] (basic controller setting). The reactive current for identification run 2 is set in p3415[1] (adaptation of the current controller when reducing the reactor inductance with increasing current magnitude).		
p3416	Infeed excitation amplitude C identification / INF exc_amp C_Id		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.10 [%]	Max 20.00 [%]	Factory setting 2.00 [%]
Description:	Sets the level of the excitation frequency for identification of the total DC link capacitance. The amplitude is indicated as a percentage of the DC voltage setpoint (V _{dc} = p0210 * p3510).		
Dependency:	Refer to: p3410, r3412, p3422		
p3417	Infeed excitation frequency C identification / INF f_exc C_ID		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 10.00 [Hz]	Max 200.00 [Hz]	Factory setting 50.00 [Hz]
Description:	Sets the level of the excitation frequency for identification of the total DC link capacitance.		
Dependency:	Refer to: p3410, r3412, p3422		

p3421	Infeed inductance / INF Inductance			
A_INF, S_INF	Can be changed: T			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min 0.00 [mH]	Max 1000.00 [mH]		Factory setting 2.00 [mH]
Description:	Sets the total line supply inductance. This value is preset to the sum of the values in p0223 and p0225.			
Dependency:	Refer to: p0223, p0225, p3410, p3622			
Note:	The controller setting is derived from this value. The value can be automatically determined using the identification run (p3410). For a parallel circuit, the value corresponds to the inductance of a power unit.			
p3422	Infeed DC link capacitance / INF C_DCL			
A_INF, S_INF	Can be changed: T			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min 0.20 [mF]	Max 1000.00 [mF]		Factory setting 2.00 [mF]
Description:	Sets the DC link capacitance. This value is preset to p0227.			
Dependency:	Refer to: p0227, p3410			
Note:	The controller setting is derived from this value. The value can be automatically determined using the identification run (p3410). The total DC link capacitance of a DC link group comprises the sum of the sub-capacitances of all motor/infeed modules and the additional DC link capacitors.			
p3440	Smart mode configuration / SLM configuration			
A_INF, S_INF	Can be changed: T			Access level: 4
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0001 bin
Description:	Sets the configuration of the smart mode.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Soft pulse mode	On	Off
Note:	Re bit 00: When the pulsed mode for the smart mode is de-activated, when regenerating, higher phase current gradients occur.			
r3452	Infeed PLL status / INF PLL status			
A_INF, S_INF	Can be changed: -			Access level: 4
	Data type: Integer16	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min 0000 bin	Max 0111 bin		Factory setting 0001 bin
Description:	Displays the status of the line supply PLL.			
Values:	0:	Initialization running		
	1:	Error when synchronizing		
	2:	Anal. line supply		
	3:	Calculation line data		
	4:	No pulse enable		
	5:	PLL calculation		
	6:	Final status controlled / smart mode		
	7:	Reserved		

p3458	Infeed PLL smoothing time / INF PLL t_smooth		
A_INF, S_INF	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 2.0 [ms]	Max 1000.0 [ms]	Factory setting 50.0 [ms]
Description:	Sets the smoothing time for the line supply PLL.		
Note:	It may be necessary to reduce the smoothing time for weak line supplies with high frequency fluctuations. There is otherwise a risk of brief orientation errors and the infeed could fail.		
r3460	Infeed PLL system deviation / INF PLL ctrl_dev		
A_INF, S_INF	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the PLL system deviation.		
r3461	Infeed PLL system deviation after filtering / INF PLL ctrl_devSm		
A_INF, S_INF	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the PLL system deviation after filtering.		
Dependency:	Refer to: p3458		
p3463	Infeed, line angle change, phase failure detection / INF Phi phase fail		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -180.0 [°]	Max 180.0 [°]	Factory setting 15.0 [°]
Description:	If the line supply angle (angle between the line supply phases) suddenly changes by this value, then a phase failure is assumed. The pulses are then inhibited for 10 ms.		
Dependency:	Refer to: A06205		
p3469[0...n]	Latch delay time correction, zero crossover detection / t_latch corr PLL		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -10000.0 [µs]	Max 10000.0 [µs]	Factory setting 0.0 [µs]
Description:	Calibration value for the RC filter of the zero crossover detection of the line supply voltage in the power unit. For p3469 = 0, a new calibration is carried-out at the next identification run with p3410 = 4 or p3410 = 5.		
Note:	The calibration value is saved in the EEPROM of the power unit (not on the CompactFlash card), as it involves a characteristic/feature of the power unit.		

r3470	Infeed active current filter / INF I_act filter		
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the active current requirement due to the line filter.		
Dependency:	Refer to: r0038, p0221, p0222		
Note:	With respect to the line supply, the sum of the active currents of the power unit (p0078) and line filter (p3470) are effective. The active current demand of the line filter is taken into account when calculating the power factor (r0038). The magnitude of the line filter active current depends on the capacitance (p0221) and the resistance (p0222) of the line filter.		
r3471	Infeed reactive current filter / INF I_reactiveFilt		
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the reactive current requirement as a result of the line filter.		
Dependency:	Refer to: r0038, p0221, p0222		
Note:	With respect to the line supply, the sum of the reactive currents of the power unit (p0076) and line filter (p3471) are effective. The reactive current requirement of the line filter is taken into account when calculating the power factor (r0038). The magnitude of the line filter reactive current depends on the capacitance (p0221) and the resistance (p0222) of the line filter.		
p3480	Infeed modulation depth limit / INF mod_depth lim		
A_INF	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 50.0 [%]	Max 110.0 [%]	Factory setting 97.0 [%]
Description:	Sets the maximum steady-state modulation depth. When this limit is reached, the DC link voltage is boosted to maintain the control margin. This means that the control reserve is maintained.		
Dependency:	Refer to: p3481, r3485		
p3481	Infeed standby controller dynamic response / INF res_ctrl dyn		
A_INF	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 7.5 [ms]
Description:	Sets the dynamic response of the reserve controller for the modulation depth. As the smoothing time increases, the response of the DC link voltage tracking becomes slower.		
Dependency:	Refer to: p3480, r3485		

r3485	Infeed standby controller output / INF res_ctrl outpt		
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the reserve controller output for the modulation depth. The DC link voltage is increased by this voltage value - the summed setpoint for the DC link voltage is output in r0088. The summed setpoint is limited to the maximum steady-stage DC link voltage (p0280).		
Dependency:	Refer to: p3480, p3481		
p3490	Infeed OFF command delay time / INF t_del OFF		
A_INF, B_INF, S_INF	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8932
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the delay time for the ON/OFF1 command of the infeed. After ON/OFF1 = 0 the infeed remains in operation for the specified time		
Dependency:	Refer to: p0840		
Notice:	The ON/OFF1 command of the infeed can be interrupted.		
Note:	This parameter is only relevant if a Motor Module and the infeed are controlled by the same OFF command. In this case, the delay time and the stop ramp time of the motor can be coordinated with one another.		
p3491	Infeed I-offset measurement monitoring time / INF I_offs t_monit		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 8932
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0 [ms]	Max 65000 [ms]	Factory setting 2000 [ms]
Description:	Sets the monitoring time for the current-offset measurement of the power unit. The time is started with the normal end of the measurement. If the measurement is invalid and if no valid measurement can be taken within the monitoring period (phase currents too high), an appropriate message is generated.		
Note:	Set this parameter to 0 to allow variations in the delay when running-up.		
p3492	Infeed, line supply undervoltage delay time / INF V_line t_del		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0 [s]	Max 300 [s]	Factory setting 0 [s]
Description:	Sets the delay time for shutdown due to a line supply undervoltage condition (A06100). After the fault occurs, the power unit is only tripped (shut down) after this delay has expired. If the fault is removed during this design time, then the power unit is not tripped (shut down).		
Dependency:	Refer to: p0283, Refer to: F06100		
Note:	The degree of ruggedness of the infeed with respect to fluctuations in the line supply voltage can be increased by parameterizing this delay value. However, the following should be noted: - the infeed power decreases proportionally (linearly) with the line supply voltage. - when other components are connected, for low line supply voltage, operating faults or damage can occur. In this case, the specifications of the connected electrical components should always be carefully observed.		

p3510	Infeed DC link voltage setpoint / INF Vdc setp		
A_INF	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: 1774, 8940
	P-Group: Closed-loop control	Units group: 5_2	Unit selection: p0505
	Min 300.00 [V]	Max 1600.00 [V]	Factory setting 600.00 [V]
Description:	Sets the setpoint for the DC link voltage.		
Dependency:	Refer to: p0210, p0280, p3511		
Warning:	Before increasing the voltage limit for pulsed operation of a controlled booksize infeed with line supply voltages p0210 > 415 V it should be checked whether the motors, connected to the DC link, are specified for the higher motor voltages.		
	The warning information associated with p0210 must be carefully observed.		
Note:	The permissible range of the DC link voltage depends on the parameterized unit supply voltage (p0210). The following applies for booksize units: $1.42 * p0210 < p3510 < 1.6 * p0210$. The following applies for chassis units: $1.42 * p0210 < p3510 < 2.0 * p0210$.		
p3511	CI: Infeed DC link voltage supplementary setpoint / INF Vdc Z_set		
A_INF	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the supplementary setpoint for the DC link voltage.		
Dependency:	Refer to: p3510		
p3513	BI: Inhibit voltage-controlled operation / Inhib U_ctrl mode		
A_INF	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for inhibiting the voltage-controlled mode of the infeed.		
Dependency:	Refer to: p3400, r3405		
Notice:	The DC link voltage must be controlled by a different component at the DC link; otherwise this results in an overvoltage or undervoltage condition.		
Note:	The current controller remains active and can be controlled by means of its setpoint inputs (p3515, p3610).		
p3514	Infeed supplementary active current steady-state / INF I_sup_eff stat		
A_INF	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: 8940
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min -1000.00 [Aeff]	Max 1000.00 [Aeff]	Factory setting 0.00 [Aeff]
Description:	Sets a steady-state supplementary setpoint for the active line supply current.		
Dependency:	Refer to: p3515		

p3515	CI: Infeed supplementary active current / INF I_suppl eff		
A_INF	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the supplementary setpoint of the active current.		
Dependency:	Refer to: p3514		
Note:	For a master-slave infeed, the master can enter the current setpoint via this connector input.		
p3516	Infeed current distribution factor (parallel connection) / INF I_distr_factor		
A_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]	Factory setting 100.00 [%]
Description:	Sets the factor to be multiplied by the active current setpoint for the current controller. For a master slave infeed configuration, the value reduced in this way can be distributed to the slave axes. The overall gain from the perspective of the voltage controller remains the same.		
r3517	Infeed active current controller unlimited setpoint / INF I_act ctrl set		
A_INF	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the unlimited setpoint of the active current controller. For a master-slave infeed configuration, the master retrieves this setpoint and distributes it to all of the slaves. The slaves operate in the current-controlled mode.		
p3520[0...3]	CI: Infeed power pre-control / INF pre-control P		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for power pre-control.		
Dependency:	Refer to: p3521		
Note:	Closed-loop control of the DC link voltage is improved by pre-controlling the power required for the other modules. A non-normalized quantity is expected so that the various power reference values (r2004) of the drive objects do not have to be taken into account. The scaling factors are used to adapt the scaling (p3521).		
p3521[0...3]	Infeed pre-control power scaling / INF pre-ctr P scal		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -100000.00000 [%]	Max 100000.00000 [%]	Factory setting 100.00000 [%]
Description:	Sets the scaling factor for the power pre-control.		
Dependency:	Refer to: p3520		

p3530	Infeed current limit, motoring / INF I_limit mot		
A_INF	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min 1.00 [Aeff]	Max 100000.00 [Aeff]	Factory setting 10000.00 [Aeff]
Description:	Sets the motoring limit for the active line current. The currently effective current limit is displayed in r0067[0].		
Dependency:	Refer to: r0067, p3532		
Caution:	If this limit is selected lower than the maximum current permissible for the power unit (r0067), the infeed can no longer provide its full controlled power. Operating faults of the infeed can occur due to the resulting DC link undervoltage.		
Notice:	For self-commutated infeeds, the DC link voltage decreases if more power is drawn from the DC link by the connected load than can be supplied by the line because of the power unit maximum current or a limit in p3530. If the DC link voltage decreases down to the rectified value, then the complete current - necessary to cover the required active power - flows, uncontrolled into the rectifier circuit via the diodes. This is the reason that, for physical reasons, the value in p3530 cannot act as current limit that is always maintained. The value forms a current threshold from which point onwards the DC link energy is used as buffer for brief power fluctuations.		
p3531	Infeed current limit, regenerating / INF I_limit regen		
A_INF	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min -100000.00 [Aeff]	Max -1.00 [Aeff]	Factory setting -10000.00 [Aeff]
Description:	Sets the limit for the active line supply current when regenerating. The currently effective current limit is displayed in r0067[1].		
Dependency:	Refer to: r0067, p3533		
Caution:	If this limit is selected lower than the maximum current permissible for the power unit (r0067), the infeed can no longer provide its full controlled power. This can result in an overvoltage condition in the DC link.		
Notice:	For self-commutated infeeds, the DC link voltage increases if more power is input to the DC link through the connected source than can be fed to the line because of the maximum power unit current or a limit in p3531 If the DC link voltage exceeds the permissible threshold (p0297), defined by the hardware, then the unit is tripped due to overvoltage. The value in p3531 represents a current limit that is always maintained - however, this can result in overvoltage conditions in the DC link. The value in p3531 represents a current limit from which point onwards the capacitance of the DC link can be used as buffer for brief power fluctuations.		

p3532	BI: Infeed, inhibit motoring / INF mot op inhibit		
A_INF	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8920
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for inhibiting the motoring mode of the infeed.		
Dependency:	Refer to: r3405, p3530		
Notice:	If the motor mode is inhibited although power is withdrawn from the DC link, then the DC link voltage drops to the rectified value. In this state, the DC link is post-charged through the diodes and motoring power is fed to the power unit in spite of the motoring inhibit.		
Note:	The inhibit only becomes active after operation has been enabled and the Vdc has been ramped-up (r0863.0 = 1).		
p3533	BI: Infeed, inhibit regenerative operation / INF regen op inhib		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8920
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to inhibit the regenerating mode of the infeed.		
Dependency:	Refer to: r3405, p3531		
Notice:	The DC link voltage will increase if regenerative operation is inhibited even though power is being regenerated into the DC link.		
Note:	The inhibit only becomes active after operation has been enabled and the Vdc has been ramped-up (r0863.0 = 1).		
r3554	Infeed Vdc controller integral component / INF Vdc_ctr I_comp		
A_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the integral action component of the DC link voltage controller (Vdc controller).		
p3560	Infeed Vdc controller proportional gain / INF Vdc_ctrl Kp		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.01 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalized proportional gain for the DC link voltage controller (Vdc controller).		
Note:	A value of 100 % corresponds to the basic setting derived from loop control parameters (p3421, p3422).		
p3562	Infeed,Vdc controller integral time / INF Vdc_ctrl Tn		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8940
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.10 [%]	Max 100000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalized integral time for the DC-link voltage controller (Vdc).		
Note:	A value of 100 % corresponds to the basic setting derived from loop control parameters (p3421, p3422).		

p3564	Infeed Vdc monitor, time constant / INF Vdc_observe T		
A_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 100.0 [ms]	Factory setting 0.2 [ms]
Description:	Sets the filter time constant for the DC link voltage monitor (Vdc).		
p3566	Infeed Vdc ramp duration / INF Vdc t_ramp		
A_INF	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8932
	P-Group: Commands	Units group: -	Unit selection: -
	Min 40 [ms]	Max 1000 [ms]	Factory setting 100 [ms]
Description:	Sets the ramp time for the DC link voltage (Vdc) when powering-up and powering-down. Powering-up (pulses enabled, r0898.3 = 1): During this time, the DC link voltage is increased from the rectifier value after pre-charging to the voltage setpoint (p3510, p3511). The voltage setpoint is increased, when necessary, so that the modulation depth reserve (p3481) is maintained. The reactive current is set to the value 0 while ramping. Powering-down (inhibit pulses, r0898.3 = 0): During this time, the DC link voltage is reduced to the rectified value ($\sqrt{2}$ * line supply voltage). The reactive current value is set to the value 0 when the ramp starts.		
r3602	Infeed control status / INF ctrl state		
A_INF	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0000 bin	Max 1000 bin	Factory setting 0000 bin
Description:	Displays the status of the closed-loop infeed control.		
Values:	0: Initialization running 1: No pulse enable 2: Ramp-up, DC-link voltage 3: Ramp-up reactive current 4: Shutdown running 5: Reset identification 6: Operation 7: Identification running 8: Smart mode running		
p3603	Infeed current pre-control factor D-action / INF I_ctrl Dfactor		
A_INF	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 500.00 [%]	Factory setting 100.00 [%]
Description:	The D component of the current pre-control is determined from the device data of the filter. p3603 can be used to weigh the pre-calculated D component. If no dynamic pre-control is to be used, set the factor to zero.		

r3606	Infeed active current controller system deviation / INF I_act ctrl dev		
A_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the system deviation of the active current controller.		
r3608	Infeed reactive current controller system deviation / INF I_reactvCtrDev		
A_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the system deviation of the reactive current controller.		
p3610	Infeed reactive current fixed setpoint / INF I_reactv F_set		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 1774, 8946
	P-Group: Closed-loop control	Units group: 6_2	Unit selection: p0505
	Min -10000.0 [Aeff]	Max 10000.0 [Aeff]	Factory setting 0.0 [Aeff]
Description:	Sets the fixed setpoint for the reactive current.		
p3611	CI: Infeed reactive current supplementary setpoint / INF I_reactv Z_set		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the supplementary setpoint of the reactive current.		
p3615	Infeed current controller P gain / INF I_ctrl Kp		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalized P gain for closed-loop current control of the infeed.		
Note:	A value of 100 % corresponds to the basic setting derived from loop control parameters (p3421, p3422).		
p3617	Infeed current controller integral time / INF I_ctrl Tn		
A_INF	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.10 [%]	Max 100000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalized integral time for the infeed current controller.		
Note:	A value of 100 % corresponds to the basic setting derived from loop control parameters (p3421, p3422).		

r3618	Infeed active current controller, integral component / INF I_act_ctrl Tn		
A_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the integral component of the active current controller.		
r3619	Infeed reactive current controller integral component / INF I_reactv_ctrTn		
A_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8946
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the integral action component of the reactive current controller.		
p3620	Infeed current controller adaptation lower application threshold / INF I_adptLowThrsh		
A_INF	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]	Factory setting 0.00 [%]
Description:	Sets the switch-in threshold for the current controller adaptation. The value refers to the maximum power modular current (r0209). From the starting threshold onwards, the inductance value (p3421) used for current control is reduced linearly as a function of the current value. The inductance value for the maximum power unit current is therefore $p3421 * p3622$.		
Dependency:	Refer to: p3410, p3415, p3622		
Note:	For the identification with $p3410 = 4, 5$, the parameter is automatically set to 80% of the current magnitude for run 1 (p3415[0]).		
p3622	Infeed current controller adaptation reduction factor / INF I_adapt factor		
A_INF	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.01 [%]	Max 100.00 [%]	Factory setting 100.00 [%]
Description:	Sets the inductance of the commutating reactor at the maximum power unit current (r0209) as a percentage of the inductance (p3421) at the application threshold (p3620).		
Dependency:	Refer to: p3410, p3415, p3620		
Note:	This parameter can be set automatically using the identification function ($p3410 = 4, 5$).		

p3624[0...1]	Infeed harmonics controller order / INF harm_ctr order		
A_INF	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min 5	Max 13	Factory setting [0] 5 [1] 7
Description:	Sets the Order of the line harmonics for the current harmonics controller. p3624[0]: Order of the line harmonics for the first harmonics controller. p3624[1]: Order of the line harmonics for the second harmonics controller.		
Dependency:	Refer to: p3625, r3626		
Note:	Harmonics in the line supply voltage can cause harmonics in the converter current. These types of current harmonics can be reduced by activating additional controller modules. Example: For a 50 Hz line supply harmonics at 250 Hz in the phase currents can be reduced by activating a harmonic controller with Order 5 (p3624[0] = 5).		
p3625[0...1]	Infeed harmonics controller scaling / INF harm_ctrl scal		
A_INF	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Closed-loop control		Unit selection: -
	Min 0.0 [%]	Max 300.0 [%]	Factory setting 100.0 [%]
Description:	Sets the gain of the harmonics controller. p3625[0]: Gain of the first harmonics controller p3625[1]: Gain of the second harmonics controller 0 %: Controller is de-activated 100 %: Controller is activated with default gain setting		
Dependency:	Refer to: p3624, r3626		
Note:	The harmonics controller corrects the power unit voltages so that the line-side current harmonics are reduced. The order of a current harmonic, that is to be dampened using a harmonics controller, is defined using p3624.		
r3626[0...1]	Infeed harmonics control output / INF harm_ctrl outp		
A_INF	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: 5_1	Function diagram: -
	P-Group: Closed-loop control		Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the output voltages of the harmonics controller. r3626[0]: RMS value of the 5th harmonic of the controller output voltage r3626[1]: RMS value of the 7th harmonic of the controller output voltage The harmonics controller corrects the power unit voltages so that the line-side current harmonics are reduced.		
Dependency:	Refer to: p3624, p3625		

r3632			
Infeed input voltage Vsd (active component) / INF U_input Usd			
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1774, 8946, 8950
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the voltage Vsd (active component) at the 3-phase line supply input of the power unit.		
r3633			
Infeed input voltage Vsq (reactive component) / INF U_input Usq			
A_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 1774, 8946, 8950
	P-Group: Closed-loop control	Units group: 5_1	Unit selection: p0505
	Min - [Veff]	Max - [Veff]	Factory setting - [Veff]
Description:	Displays the voltage Vsq (reactive component) at the 3-phase line supply input of the power unit.		
r3635			
Infeed output voltage angle / INF U_output angle			
A_INF	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 8950
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the output voltage angle (relative to the line angle).		
p3660			
VSM input line supply voltage, voltage scaler / VSM input U_scaler			
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 100000.00 [%]	Factory setting 0.00 [%]
Description:	Sets the voltage scaler for the Voltage Sensing Module (VSM).		
Note:	When the 690 V input is used (X522) without voltage scaler, 0 % should be entered.		
	When the 100 V input (X521) is used with voltage scaler to measure medium voltages, the dividing (scaling) factor multiplied by 100% should be entered.		
	Example:		
	1000 V line supply voltage, voltage scaling, 10:1		
	--> voltage at the VSM input is 100 V		
	--> p3660 = 10 * 100 % = 1000 %		

p3660[0...n]	VSM input line supply voltage, voltage scaler / VSM input U_scaler		
VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 100000.00 [%]	Factory setting 0.00 [%]
Description:	Sets the voltage scaler for the Voltage Sensing Module (VSM).		
Note:	When the 690 V input is used (X522) without voltage scaler,, 0 % should be entered. When the 100 V input (X521) is used with voltage scaler to measure medium voltages, the dividing (scaling) factor multiplied by 100% should be entered. Example: 1000 V line supply voltage, voltage scaling, 10:1 --> voltage at the VSM input is 100 V --> p3660 = 10 * 100 % = 1000 %		
r3661	CO: VSM input line supply voltage u1 - u2 / VSM input u1-u2		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8850, 8950, 9880
	P-Group: Closed-loop control	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the voltage between L1 and L2.		
Dependency:	Refer to: p3660		
Note:	X521.1 or X522.1: Connection of L1 X521.2 or X522.2: Connection of L2		
r3661[0...n]	CO: VSM input line supply voltage u1 - u2 / VSM input u1-u2		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the voltage between L1 and L2.		
Dependency:	Refer to: p3660		
Note:	X521.1 or X522.1: Connection of L1 X521.2 or X522.2: Connection of L2		
r3662	CO: VSM input line supply voltage u2 - u3 / VSM input u2-u3		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 8850, 8950, 9880
	P-Group: Closed-loop control	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the voltage between L2 and L3.		
Dependency:	Refer to: p3660		
Note:	X521.2 or X522.2: Connection of L2 X521.3 or X522.3: Connection of L3		

r3662[0...n]	CO: VSM input line supply voltage u2 - u3 / VSM input u2-u3		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the voltage between L2 and L3.		
Dependency:	Refer to: p3660		
Note:	X521.2 or X522.2: Connection of L2 X521.3 or X522.3: Connection of L3		

r3664	BO: VSM temperature evaluation, status / VSM temp status			
A_INF, S_INF	Can be changed: -		Access level: 3	
	Data type: Unsigned16	Dynamic index: -	Function diagram: -	
	P-Group: Terminals	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the status of the temperature evaluation of the Voltage Sensing Module (VSM). This displays as to whether the temperature actual value has exceeded the fault/alarm threshold.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Temperature alarm threshold exceeded	Yes	No
	01	Temperature fault threshold exceeded	Yes	No
Dependency:	Refer to: p3665, r3666, p3667, p3668			

r3664[0...n]	CO: VSM temperature evaluation, status / VSM temp status			
VECTOR	Can be changed: -		Access level: 3	
	Data type: Unsigned16	Dynamic index: p0150	Function diagram: -	
	P-Group: Terminals	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the status of the temperature evaluation of the Voltage Sensing Module (VSM). This displays as to whether the temperature actual value has exceeded the fault/alarm threshold.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Temperature alarm threshold exceeded	Yes	No
	01	Temperature fault threshold exceeded	Yes	No
Dependency:	Refer to: p3665, r3666, p3667, p3668			

p3665[0...n]	VSM temperature evaluation, sensor type / VSM TempSensorType		
A_INF, S_INF, VECTOR	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: p0140	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	Setting of the temperature sensor for the Voltage Sensing Module (VSM). The temperature sensor is connected to terminals X520.5 and X520.6 of the VSM.		
Values:	0: No sensor 1: PTC 2: KTY84		

r3666	CO: VSM temperature KTY / VSM temp KTY		
A_INF, S_INF	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the temperature actual value of a KTY84 temperature sensor connected to the Voltage Sensing Module (VSM). Prerequisite: A KTY84 sensor is connected and p3665 is set to 2.		
Dependency:	Refer to: p3665		
Note:	For sensor type PTC (p3665 = 1), the following applies: - below the nominal response temperature, r3666 = -50°C. - above the nominal response temperature, r3666 = 199.9 °C.		
r3666[0...n]	CO: VSM temperature KTY / VSM temp KTY		
VECTOR	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the temperature actual value of a KTY84 temperature sensor connected to the Voltage Sensing Module (VSM). Prerequisite: A KTY84 sensor is connected and p3665 is set to 2.		
Dependency:	Refer to: p3665		
Note:	For sensor type PTC (p3665 = 1), the following applies: - below the nominal response temperature, r3666 = -50°C. - above the nominal response temperature, r3666 = 199.9 °C.		
p3667	VSM line filter overtemperature alarm threshold / VSMfilt_T A_thresh		
A_INF, S_INF	Can be changed: T	Access level: 4	
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: 21_1	Unit selection: p0505
	Min 0.00 [°C]	Max 301.00 [°C]	Factory setting 150.00 [°C]
Description:	Sets the alarm threshold for the KTY temperature sensor of the Voltage Sensing Module (VSM) to monitor the line filter temperature. Prerequisite: A KTY84 sensor is connected and p3665 is set to 2.		
Dependency:	Refer to: p3665 Refer to: F34207		

p3667[0...n]	VSM line filter overtemperature alarm threshold / VSMfilt_T A_thresh		
VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: -	Units group: 21_1	Unit selection: p0505
	Min 0.00 [°C]	Max 301.00 [°C]	Factory setting 150.00 [°C]
Description:	Sets the alarm threshold for the KTY temperature sensor of the Voltage Sensing Module (VSM) to monitor the line filter temperature. Prerequisite: A KTY84 sensor is connected and p3665 is set to 2.		
Dependency:	Refer to: p3665 Refer to: F34207		
p3668	VSM line filter overtemperature shutdown threshold / VSM filt_T F_thresh		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: 21_1	Unit selection: p0505
	Min 0.00 [°C]	Max 301.00 [°C]	Factory setting 180.00 [°C]
Description:	Sets the shutdown threshold for the KTY temperature sensor of the VSM to monitor the line filter temperature.		
Dependency:	Refer to: p3667 Refer to: A34211		
p3668[0...n]	VSM line filter overtemperature shutdown threshold / VSM filt_T F_thresh		
VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: -	Units group: 21_1	Unit selection: p0505
	Min 0.00 [°C]	Max 301.00 [°C]	Factory setting 180.00 [°C]
Description:	Sets the shutdown threshold for the KTY temperature sensor of the VSM to monitor the line filter temperature.		
Dependency:	Refer to: p3667 Refer to: A34211		
p3669	VSM line filter overtemperature hysteresis / VSM filt_T hyst		
A_INF, S_INF	Can be changed: T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 1.00 [K]	Max 50.00 [K]	Factory setting 3.00 [K]
Description:	Sets the hysteresis for the alarm threshold of the VSM to monitor the line filter temperature.		
Dependency:	Refer to: p3667		
p3669[0...n]	VSM line filter overtemperature hysteresis / VSM filt_T hyst		
VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: -	Units group: 21_2	Unit selection: p0505
	Min 1.00 [K]	Max 50.00 [K]	Factory setting 3.00 [K]
Description:	Sets the hysteresis for the alarm threshold of the VSM to monitor the line filter temperature.		
Dependency:	Refer to: p3667		

p3670	VSM 10 V input CT gain / VSM CT_gain		
A_INF, S_INF	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000 [A]	Max 1000.000 [A]	Factory setting 1.000 [A]
Description:	Sets CT gain of the CT connected at the 10 V input of the Voltage Sensing Module (VSM). The parameter specifies the current magnitude in [A] referred to the input voltage at the VSM in [V]. Example: CT with 1 V per 200 A. --> p3670 = 200		
Dependency:	Refer to: r3671, r3672		
Note:	The CT for phase 1 is connected at terminals X520.1 and X520.2 of the VSM. The CT for phase 2 is connected at terminals X520.3 and X520.4 of the VSM.		
p3670[0...n]	VSM 10 V input CT gain / VSM CT_gain		
VECTOR	Can be changed: T		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000 [A]	Max 1000.000 [A]	Factory setting 1.000 [A]
Description:	Sets CT gain of the CT connected at the 10 V input of the Voltage Sensing Module (VSM). The parameter specifies the current magnitude in [A] referred to the input voltage at the VSM in [V]. Example: CT with 1 V per 200 A. --> p3670 = 200		
Dependency:	Refer to: r3671, r3672		
Note:	The CT for phase 1 is connected at terminals X520.1 and X520.2 of the VSM. The CT for phase 2 is connected at terminals X520.3 and X520.4 of the VSM.		
r3671	CO: VSM 10 V input CT 1 actual value / VSM CT 1 I_act		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the current actual value from current transducer (CT) 1 at the 10 V input of the Voltage Sensing Module (VSM).		
Dependency:	Refer to: p3670		
Note:	The CT for phase 1 is connected at terminals X520.1 and X520.2 of the VSM.		
r3671[0...n]	CO: VSM 10 V input CT 1 actual value / VSM CT 1 I_act		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the current actual value from current transducer (CT) 1 at the 10 V input of the Voltage Sensing Module (VSM).		
Dependency:	Refer to: p3670		
Note:	The CT for phase 1 is connected at terminals X520.1 and X520.2 of the VSM.		

r3672	CO: VSM 10 V input CT 2 actual value / VSM CT 2 I_act		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the current actual value from current transducer (CT) 2 at the 10 V input of the Voltage Sensing Module (VSM).		
Dependency:	Refer to: p3670		
Note:	The CT for phase 2 is connected at terminals X520.3 and X520.4 of the VSM.		
r3672[0...n]	CO: VSM 10 V input CT 2 actual value / VSM CT 2 I_act		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the current actual value from current transducer (CT) 2 at the 10 V input of the Voltage Sensing Module (VSM).		
Dependency:	Refer to: p3670		
Note:	The CT for phase 2 is connected at terminals X520.3 and X520.4 of the VSM.		
r3673	CO: VSM 10 V input 1 actual value / VSM input 1 U_act		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual value of the voltage measured at the 10 V input 1 of the Voltage Sensing Modules (VSM).		
Dependency:	Refer to: p3670		
Note:	10 V input 1: Terminals X520.1 and X520.2		
r3673[0...n]	CO: VSM 10 V input 1 actual value / VSM input 1 U_act		
VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0150	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual value of the voltage measured at the 10 V input 1 of the Voltage Sensing Modules (VSM).		
Dependency:	Refer to: p3670		
Note:	10 V input 1: Terminals X520.1 and X520.2		
r3674	CO: VSM 10 V input 2 actual value / VSM input 2 U_act		
A_INF, S_INF	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual value of the voltage measured at the 10 V input 2 of the Voltage Sensing Modules (VSM).		
Dependency:	Refer to: p3670		
Note:	10 V input 2: Terminals X520.3 and X520.4		

r3674[0...n]	CO: VSM 10 V input 2 actual value / VSM input 2 U_act			
VECTOR	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: p0150		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min - [V]	Max - [V]		Factory setting - [V]
Description:	Displays the actual value of the voltage measured at the 10 V input 2 of the Voltage Sensing Modules (VSM).			
Dependency:	Refer to: p3670			
Note:	10 V input 2: Terminals X520.3 and X520.4			
p3676	VSM line filter capacitance alarm threshold / VSMfilt C A_thresh			
A_INF, S_INF	Can be changed: T			Access level: 4
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min 0.00 [%]	Max 100.00 [%]		Factory setting 0.00 [%]
Description:	Sets the alarm threshold for the change of the capacitance of the line filter. The filter capacitance monitoring function is de-activated with p3676 = 0.00 %.			
Dependency:	Refer to: p3670 Refer to: A06250			
Note:	Prerequisite for monitoring the filter capacitance: The phase currents must be measured at two capacitors of the line filter. To do this, CTs should be connected at the 10 V inputs of the VSM.			
r3677[0...2]	VSM line filter capacitance / VSM filt C			
A_INF, S_INF	Can be changed: -			Access level: 4
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min - [µF]	Max - [µF]		Factory setting - [µF]
Description:	Displays the capacitance of the line filter (for a star circuit configuration).			
Index:	[0] = Phase U [1] = Phase V [2] = Phase W			
Dependency:	Refer to: p3676			
Note:	Prerequisite: The filter capacitance monitoring is activated.			
p3700	APC configuration / APC config			
SERVO (APC)	Can be changed: U, T			Access level: 2
	Data type: Unsigned16	Dynamic index: -		Function diagram: 7012
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Sets the configuration for APC (Advanced Positioning Control).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Activating APC	Yes	No
	08	Activating pulse de-coupling	Yes	No
				FP
				-
				-

Note: Re bit 0:
For a 1 signal, the acceleration filter output is added to the speed setpoint.
For a 0 signal, the value 0 is added. This must be used to evaluate the filter frequency characteristics.
Re bit 8:
For bit 0 = 1 and activated pulse de-coupling (bit 8 = 1), the speed of the direct measuring system (p3701) selected for APC is used as the actual value for the closed-loop speed control.

p3701	APC enc sel / APC enc sel		
SERVO (APC)	Can be changed: C1(4), U		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Data sets	Units group: -	Unit selection: -
	Min	Max	Factory setting
	2	3	2
Description:	Sets the number of the encoder used for for APC (Advanced Positioning Control).		
Values:	2: Encoder 2 3: Encoder 3		
Note:	Encoder 1 is the motor encoder and cannot be used for APC as APC requires a load measuring system. An encoder used for APC is, regarding its fault messages, treated just like a motor encoder - this means that its fault messages are assigned to the drive.		

p3704[0...n]	APC filter activation / APC filter activ.				
SERVO (APC)	Can be changed: U, T		Access level: 3		
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 7012		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Setting to activate the filter for APC (Advanced Positioning Control).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Activating filter 1.1	Yes	No	-
	04	Activating filter 2.1	Yes	No	-
	05	Activating filter 2.2	Yes	No	-
	08	Activating filter 3.1	Yes	No	-
	09	Activating filter 3.2	Yes	No	-

p3705[0...n]	APC filter type / APC filter type				
SERVO (APC)	Can be changed: U, T		Access level: 3		
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 7012		
	P-Group: Closed-loop control	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the filter type for the filter for APC (Advanced Positioning Control).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Filter 1.1 type	A. Filter 2nd ord.	Low pass (PT2)	-
	04	Filter 2.1 type	A. Filter 2nd ord.	Low pass (PT2)	-
	05	Filter 2.2 type	A. Filter 2nd ord.	Low pass (PT2)	-
	08	Filter 3.1 type	A. Filter 2nd ord.	Low pass (PT2)	-
	09	Filter 3.2 type	A. Filter 2nd ord.	Low pass (PT2)	-

p3706[0...n]	APC sub-sampling, filter 2.x / APC sub-samp. 2.x		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1	Max 64	Factory setting 1
Description:	Sets the factor for the sub-sampling in the branch of filter 2.1 and 2.2 for APC (Advanced Positioning Control).		
Note:	The values are integer multiples of the speed controller clock cycle (p0115[1]).		
p3707[0...n]	APC sub-sampling, filter 3.x / APC sub-samp. 3.x		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 1	Max 64	Factory setting 1
Description:	Sets the factor for the sub-sampling in the branch of filter 3.1 and 3.2 for APC (Advanced Positioning Control).		
Note:	The values are integer multiples of the speed controller clock cycle (p0115[1]).		
p3711[0...n]	APC filter 1.1 denominator natural frequency / APC Filt 1.1 fn_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for filter 1.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3712[0...n]	APC filter 1.1 denominator damping / APC Filt 1.1 D_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for filter 1.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3713[0...n]	APC filter 1.1 numerator natural frequency / APC Filt 1 fn_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for filter 1.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		

p3714[0...n]	APC filter 1.1 numerator damping / APC Filt 1.1 D_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for filter 1.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3721[0...n]	APC filter 2.1 denominator natural frequency / APC Filt 2.1 fn_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for filter 2.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3722[0...n]	APC filter 2.1 denominator damping / APC Filt 2.1 D_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for filter 2.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3723[0...n]	APC filter 2.1 numerator natural frequency / APC Filt 2.1 fn_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for filter 2.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3724[0...n]	APC filter 2.1 numerator damping / APC Filt 2.1 D_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for filter 2.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		

p3726[0...n]	APC filter 2.2 denominator natural frequency / APC Filt 2.2 fn_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for filter 2.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3727[0...n]	APC filter 2.2 denominator damping / APC Filt 2.2 D_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for filter 2.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3728[0...n]	APC filter 2.2 numerator natural frequency / APC Filt 2.2 fn_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for filter 2.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3729[0...n]	APC filter 2.2 numerator damping / APC Filt 2.2 D_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7029
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for filter 2.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3731[0...n]	APC filter 3.1 denominator natural frequency / APC Filt 2.1 fn_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for filter 3.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		

p3732[0...n]	APC filter 3.1 denominator damping / APC Filt 3.1 D_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for filter 3.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3733[0...n]	APC filter 3.1 numerator natural frequency / APC Filt 2.1 fn_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for filter 3.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3734[0...n]	APC filter 3.1 numerator damping / APC Filt 3.1 D_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for filter 3.1 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3736[0...n]	APC filter 3.2 denominator natural frequency / APC Filt 3.2 fn_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the denominator natural frequency for filter 3.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3737[0...n]	APC filter 3.2 denominator damping / APC Filt 3.2 D_d		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.050	Max 10.000	Factory setting 0.700
Description:	Sets the denominator damping for filter 3.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		

p3738[0...n]	APC filter 3.2 numerator natural frequency / APC Filt 3.2 fn_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.5 [Hz]	Max 16000.0 [Hz]	Factory setting 2000.0 [Hz]
Description:	Sets the numerator natural frequency for filter 3.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3739[0...n]	APC filter 3.2 numerator damping / APC Filt 3.2 D_n		
SERVO (APC)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min 0.000	Max 10.000	Factory setting 0.700
Description:	Sets the numerator damping for filter 3.2 (PT2, general 2nd Order filter) for APC (Advanced Positioning Control).		
Dependency:	Refer to: p3704, p3705		
p3760[0...n]	APC load speed controller 1 P gain / APC n_load ctr1 Kp		
SERVO (APC)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -100.000	Max 100.000	Factory setting 0.000
Description:	Sets the proportional gain of the load speed controller 1 for APC (Advanced Positioning Control). The gain acts on the difference between the speed setpoint and load speed in the branch for filter 2.1 and 2.2.		
p3760[0...n]	APC load velocity controller 1 P gain / APC v_load ctr1 Kp		
SERVO (APC, Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -100.000	Max 100.000	Factory setting 0.000
Description:	Sets the proportional gain of the load velocity controller 1 for APC (Advanced Positioning Control). The gain acts on the difference between the velocity setpoint and load velocity in the branch for filter 2.1 and 2.2.		
p3761[0...n]	APC load speed controller 1 rate time / APC n_load ctr1 Tv		
SERVO (APC)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -500.00 [ms]	Max 500.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the rate time of the load speed controller 1 for APC (Advanced Positioning Control). The rate time acts on the load acceleration in the branch for filter 2.1 and 2.2.		

p3761[0...n]	APC load velocity controller 1 rate time / APC v_load ctr1 Tv		
SERVO (APC, Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -500.00 [ms]	Max 500.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the rate time of the load velocity controller 1 for APC (Advanced Positioning Control). The rate time acts on the load acceleration in the branch for filter 2.1 and 2.2.		
p3765[0...n]	APC load speed controller 2 P gain / APC n_load ctr2 Kp		
SERVO (APC)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -100.000	Max 100.000	Factory setting 0.000
Description:	Sets the proportional gain of the load speed controller 2 for APC (Advanced Positioning Control). The gain acts on the difference between the speed setpoint and load speed in the branch for filter 3.1 and 3.2.		
p3765[0...n]	APC load velocity controller 2 P gain / APC v_load ctr2 Kp		
SERVO (APC, Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -100.000	Max 100.000	Factory setting 0.000
Description:	Sets the proportional gain of the load velocity controller 2 for APC (Advanced Positioning Control). The gain acts on the difference between the velocity setpoint and load velocity in the branch for filter 3.1 and 3.2.		
p3766[0...n]	APC load speed controller 2 rate time / APC n_load ctr2 Tv		
SERVO (APC)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -500.00 [ms]	Max 500.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the rate time of the load speed controller 2 for APC (Advanced Positioning Control). The rate time acts on the load acceleration in the branch for filter 3.1 and 3.2.		
p3766[0...n]	APC load velocity controller 2 rate time / APC v_load ctr2 Tv		
SERVO (APC, Lin)	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7012
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min -500.00 [ms]	Max 500.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the rate time of the load velocity controller 2 for APC (Advanced Positioning Control). The rate time acts on the load acceleration in the branch for filter 3.1 and 3.2.		

r3770	CO: APC load speed / APC n_load		
SERVO (APC)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the load speed for APC (Advanced Positioning Control).		
Dependency:	Refer to: r3771		
r3770	CO: APC load velocity / APC v_load		
SERVO (APC, Lin)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the load velocity for APC (Advanced Positioning Control).		
Dependency:	Refer to: r3771		
r3771	CO: APC load speed smoothed / APC n_load smth		
SERVO (APC)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the smoothed load speed for APC (Advanced Positioning Control).		
Dependency:	Refer to: p1441, r3770		
r3771	CO: APC load velocity smoothed / APC v_load smth		
SERVO (APC, Lin)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the smoothed load velocity for APC (Advanced Positioning Control).		
Dependency:	Refer to: p1441, r3770		
r3772[0...1]	APC filter branch 2 display values / APC branch 2 val		
SERVO (APC)	Can be changed: -	Access level: 3	
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speeds in filter branch 2.		
Index:	[0] = Filter 2.1 input value [1] = Filter 2.2 output value		

r3772[0...1]	APC filter branch 2 display values / APC branch 2 val		
SERVO (APC, Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocities in filter branch 2.		
Index:	[0] = Filter 2.1 input value [1] = Filter 2.2 output value		
r3773[0...1]	APC filter branch 3 display values / APC branch 3 val		
SERVO (APC)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speeds in filter branch 3.		
Index:	[0] = Filter 3.1 input value [1] = Filter 3.2 output value		
r3773[0...1]	APC filter branch 3 display values / APC branch 3 val		
SERVO (APC, Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocities in filter branch 3.		
Index:	[0] = Filter 3.1 input value [1] = Filter 3.2 output value		
r3777[0...1]	CO: APC filter branch 1 display values / APC branch 1 val		
SERVO (APC)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 3_1	Unit selection: p0505
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the speeds in filter branch 1.		
Index:	[0] = Filter 1.1 input value [1] = Filter 1.1 output value		
r3777[0...1]	CO: APC filter branch 1 display values / APC branch 1 val		
SERVO (APC, Lin)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 7012
	P-Group: Setpoints	Units group: 4_1	Unit selection: p0505
	Min - [m/min]	Max - [m/min]	Factory setting - [m/min]
Description:	Displays the velocities in filter branch 1.		
Index:	[0] = Filter 1.1 input value [1] = Filter 1.1 output value		

p3784[0...n]	BI: Sync line-drive external increase voltage / Sync ext U incr		
VECTOR	Can be changed: T		Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to increase the voltage for external line-drive synchronization. The voltage is increased for a 1 signal.		
Note:	Only SINAMICS GL150/GM150.		
p3785[0...n]	BI: Sync line-drive external decrease voltage / Sync ext U decr		
VECTOR	Can be changed: T		Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to decrease the voltage for external line-drive synchronization. The voltage is decreased for a 1 signal.		
Note:	Only SINAMICS GL150/GM150.		
p3800[0...n]	Sync line-drive activation / Sync activ.		
VECTOR	Can be changed: T		Access level: 2
	Data type: Integer16	Dynamic index: DDS, p0180	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the activation for the line-drive synchronization.		
Values:	0: Sync line-drive de-activated 1: Sync line-drive activated VSM-INT		
Dependency:	Refer to: p3801, p3802		
Note:	VSM: Voltage Sensing Module. When the ground fault monitoring initiates a fault for overlapping synchronizing the threshold value p0287[1] for the motor module and the associated infeed must be appropriately increased, e.g. p0287[1] = 100 %. For p3800 = 1, the INTERNAL voltage actual values are used for synchronization. The effects that a (sinusoidal) filter - that is connected between the Motor Module and motor - has on the voltage actual values are taken into account (theoretically) by appropriately selecting p0230.		
p3801[0...n]	Sync line-drive, drive object number / Sync DO_No.		
VECTOR	Can be changed: T		Access level: 2
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min 1	Max 62	Factory setting 1
Description:	Sets the drive object number of the Voltage Sensing Module (VSM) used for the line-drive synchronization.		
Dependency:	Refer to: p3800, p3802		
Note:	VSM: Voltage Sensing Module		

p3802[0...n]	BI: Sync line-drive enable / Sync enable			
VECTOR	Can be changed: T			Access level: 2
	Data type: Unsigned32	Dynamic index: CDS, p0170		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0
Description:	Sets the signal source to switch-in/switch-out for the line-drive synchronization. Line-drive synchronization is switched-in with a 1 signal.			
Dependency:	Refer to: p3800, p3801			
r3803	CO/BO: Sync line-drive control word / Sync STW			
VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Functions	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the control word for the line-drive synchronization.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Sync line-drive selected	Yes	No
Note:	Re bit 00: For a 1 signal, p3800 > 0 is set.			
r3804	CO: Sync line-drive target frequency / Sync f_target			
VECTOR	Can be changed: -			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min - [Hz]	Max - [Hz]		Factory setting - [Hz]
Description:	Displays the target frequency for the line-drive synchronization.			
Dependency:	Refer to: A07941			
r3805	CO: Sync line-drive frequency difference / Sync f_diff			
VECTOR	Can be changed: -			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min - [Hz]	Max - [Hz]		Factory setting - [Hz]
Description:	Displays the frequency difference between the measured target frequency and output frequency of the gating unit of the closed-loop control for line-drive synchronization.			
p3806[0...n]	Sync line-drive frequency difference threshold value / Sync f_diff thresh			
VECTOR	Can be changed: U, T			Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min 0.00 [Hz]	Max 1.00 [Hz]		Factory setting 0.10 [Hz]
Description:	Sets the threshold value of the frequency difference to activate the closed-loop phase control for line-drive synchronization. The closed-loop phase control is activated (r3819.6 = 1), if the frequency difference is less than the threshold value.			

r3808	CO: Sync line-drive phase difference / Sync phase diff		
VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min - [°]	Max - [°]	Factory setting - [°]
Description:	Displays the phase difference between the measured target phase and phase of the gating unit of the closed-loop control for line-drive synchronization.		
p3809[0...n]	Sync line-drive phase setpoint / Sync phase setp		
VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min -180.00 [°]	Max 179.90 [°]	Factory setting 0.00 [°]
Description:	Sets the phase setpoint for the line-drive synchronization.		
p3811[0...n]	Sync line-drive frequency limiting / Sync f_lim		
VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 1.00 [Hz]	Factory setting 0.50 [Hz]
Description:	Sets the frequency limiting of the phase controller output for the line-drive synchronization.		
r3812	CO: Sync line-drive correction frequency / Sync f_corr		
VECTOR	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min - [Hz]	Max - [Hz]	Factory setting - [Hz]
Description:	Displays the correction frequency for the line-drive synchronization.		
p3813[0...n]	Sync line-drive phase synchronism threshold value / Sync Ph_sync thrsh		
VECTOR	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7020
	P-Group: Functions	Units group: -	Unit selection: -
	Min 1.00 [°]	Max 20.00 [°]	Factory setting 2.00 [°]
Description:	Sets the threshold value of the phase synchronism for the line-drive synchronization. A prerequisite for synchronism is achieved if the phase difference is lower than the threshold value.		
Note:	Synchronism is reached (r3819.2 = 1), if the AND logic operation of the results from the phase measurement (p3813) and voltage measurement (p3815) is fulfilled.		

p3814	CO: Sync line-drive voltage difference / Sync U_diff			
VECTOR	Can be changed: -			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min - [Veff]	Max - [Veff]		Factory setting - [Veff]
Description:	Displays the voltage difference between the measured target voltage and output voltage of the gating unit of the closed-loop control for line-drive synchronization.			
p3815[0...n]	Sync line-drive voltage difference threshold value / Sync U_diff thresh			
VECTOR	Can be changed: U, T			Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min 0.00 [%]	Max 10.00 [%]		Factory setting 10.00 [%]
Description:	Sets the threshold value of the voltage difference for the line-drive synchronization. A prerequisite for synchronism is reached if the voltage difference is less than the threshold value.			
Note:	Synchronism is reached ($r3819.2 = 1$), if the AND logic operation of the results from the phase measurement (p3813) and voltage measurement (p3815) is fulfilled. For voltage manipulated quantity margin (reserve) of the drive converter, the amplitude difference (r3814) between the setpoint and actual value is controlled (corrected) to zero.			
r3819	CO/BO: Sync line-drive status word / Sync ZSW			
VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 7020
	P-Group: Functions	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the status word for the line-drive synchronization.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Sync line-drive enabled	Yes	No
	02	Sync line-drive synchronism reached	Yes	No
	03	Sync line-drive synchronizing error	Yes	No
	05	Sync line-drive frequency measurement active	Yes	No
	06	Sync line-drive phase control active	Yes	No
	07	Sync line-drive without drive	Yes	No
				FP
				-
				-
				-
				-
				-
				-
				-
p3820[0...n]	Friction characteristic, value n0 / Friction n0			
SERVO, VECTOR (n/M)	Can be changed: T			Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180		Function diagram: 7010
	P-Group: Functions	Units group: 3_1		Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]		Factory setting 15.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 1st value pair of the friction characteristic.			
Dependency:	Refer to: p3830, p3845			

p3820[0...n]	Friction characteristic, value v0 / Friction v0		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 1.50 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 1st value pair of the friction characteristic.		
Dependency:	Refer to: p3830, p3845		
p3821[0...n]	Friction characteristic, value n1 / Friction n1		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 30.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 2nd value pair of the friction characteristic.		
Dependency:	Refer to: p3831, p3845		
p3821[0...n]	Friction characteristic, value v1 / Friction v1		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 3.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 2nd value pair of the friction characteristic.		
Dependency:	Refer to: p3831, p3845		
p3822[0...n]	Friction characteristic, value n2 / Friction n2		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 60.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 3rd value pair of the friction characteristic.		
Dependency:	Refer to: p3832, p3845		
p3822[0...n]	Friction characteristic, value v2 / Friction v2		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 6.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 3rd value pair of the friction characteristic.		
Dependency:	Refer to: p3832, p3845		

p3823[0...n]	Friction characteristic, value n3 / Friction n3		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 120.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 4th value pair of the friction characteristic.		
Dependency:	Refer to: p3833, p3845		
p3823[0...n]	Friction characteristic, value v3 / Friction v3		
SERVO (Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 12.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 4th value pair of the friction characteristic.		
Dependency:	Refer to: p3833, p3845		
p3824[0...n]	Friction characteristic, value n4 / Friction n4		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 150.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 5th value pair of the friction characteristic.		
Dependency:	Refer to: p3834, p3845		
p3824[0...n]	Friction characteristic, value v4 / Friction v4		
SERVO (Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 4_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 15.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 5th value pair of the friction characteristic.		
Dependency:	Refer to: p3834, p3845		
p3825[0...n]	Friction characteristic, value n5 / Friction n5		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 3_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 300.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 6th value pair of the friction characteristic.		
Dependency:	Refer to: p3835, p3845		

p3825[0...n]	Friction characteristic, value v5 / Friction v5		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 30.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 6th value pair of the friction characteristic.		
Dependency:	Refer to: p3835, p3845		
p3826[0...n]	Friction characteristic, value n6 / Friction n6		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 600.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 7th value pair of the friction characteristic.		
Dependency:	Refer to: p3836, p3845		
p3826[0...n]	Friction characteristic, value v6 / Friction v6		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 60.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 7th value pair of the friction characteristic.		
Dependency:	Refer to: p3836, p3845		
p3827[0...n]	Friction characteristic, value n7 / Friction n7		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 1200.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 8th value pair of the friction characteristic.		
Dependency:	Refer to: p3837, p3845		
p3827[0...n]	Friction characteristic, value v7 / Friction v7		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 120.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 8th value pair of the friction characteristic.		
Dependency:	Refer to: p3837, p3845		

p3828[0...n]	Friction characteristic, value n8 / Friction n8		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 1500.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 9th value pair of the friction characteristic.		
Dependency:	Refer to: p3838, p3845		

p3828[0...n]	Friction characteristic, value v8 / Friction v8		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 150.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 9th value pair of the friction characteristic.		
Dependency:	Refer to: p3838, p3845		

p3829[0...n]	Friction characteristic, value n9 / Friction n9		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 3_1	Unit selection: p0505
	Min 0.00 [1/min]	Max 210000.00 [1/min]	Factory setting 3000.00 [1/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the n coordinate of the 10th value pair of the friction characteristic.		
Dependency:	Refer to: p3839, p3845		

p3829[0...n]	Friction characteristic, value v9 / Friction v9		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 4_1	Unit selection: p0505
	Min 0.00 [m/min]	Max 21000.00 [m/min]	Factory setting 300.00 [m/min]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the v coordinate of the 10th value pair of the friction characteristic.		
Dependency:	Refer to: p3839, p3845		

p3830[0...n]	Friction characteristic, value M0 / Friction M0		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 7_1	Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 1st value pair of the friction characteristic.		
Dependency:	Refer to: p3820, p3845		

p3830[0...n]	Friction characteristic, value F0 / Friction F0		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 1st value pair of the friction characteristic.		
Dependency:	Refer to: p3820, p3845		
p3831[0...n]	Friction characteristic, value M1 / Friction M1		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 7_1	Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 2nd value pair of the friction characteristic.		
Dependency:	Refer to: p3821, p3845		
p3831[0...n]	Friction characteristic, value F1 / Friction F1		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 2nd value pair of the friction characteristic.		
Dependency:	Refer to: p3821, p3845		
p3832[0...n]	Friction characteristic, value M2 / Friction M2		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 7_1	Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 3rd value pair of the friction characteristic.		
Dependency:	Refer to: p3822, p3845		
p3832[0...n]	Friction characteristic, value F2 / Friction F2		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 3rd value pair of the friction characteristic.		
Dependency:	Refer to: p3822, p3845		

p3833[0...n]	Friction characteristic, value M3 / Friction M3		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 7_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 4th value pair of the friction characteristic.		
Dependency:	Refer to: p3823, p3845		
p3833[0...n]	Friction characteristic, value F3 / Friction F3		
SERVO (Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 8_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 4th value pair of the friction characteristic.		
Dependency:	Refer to: p3823, p3845		
p3834[0...n]	Friction characteristic, value M4 / Friction M4		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 7_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 5th value pair of the friction characteristic.		
Dependency:	Refer to: p3824, p3845		
p3834[0...n]	Friction characteristic, value F4 / Friction F4		
SERVO (Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 8_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 5th value pair of the friction characteristic.		
Dependency:	Refer to: p3824, p3845		
p3835[0...n]	Friction characteristic, value M5 / Friction M5		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 7_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 6th value pair of the friction characteristic.		
Dependency:	Refer to: p3825, p3845		

p3835[0...n]	Friction characteristic, value F5 / Friction F5		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 6th value pair of the friction characteristic.		
Dependency:	Refer to: p3825, p3845		
p3836[0...n]	Friction characteristic, value M6 / Friction M6		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 7_1	Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 7th value pair of the friction characteristic.		
Dependency:	Refer to: p3826, p3845		
p3836[0...n]	Friction characteristic, value F6 / Friction F6		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 7th value pair of the friction characteristic.		
Dependency:	Refer to: p3826, p3845		
p3837[0...n]	Friction characteristic, value M7 / Friction M7		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 7_1	Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 8th value pair of the friction characteristic.		
Dependency:	Refer to: p3827, p3845		
p3837[0...n]	Friction characteristic, value F7 / Friction F7		
SERVO (Lin)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: 8_1	Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 8th value pair of the friction characteristic.		
Dependency:	Refer to: p3827, p3845		

p3838[0...n]	Friction characteristic, value M8 / Friction M8		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 7_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 9th value pair of the friction characteristic.		
Dependency:	Refer to: p3828, p3845		

p3838[0...n]	Friction characteristic, value F8 / Friction F8		
SERVO (Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 8_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 9th value pair of the friction characteristic.		
Dependency:	Refer to: p3828, p3845		

p3839[0...n]	Friction characteristic, value M9 / Friction M9		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 7_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the M coordinate of the 10th value pair of the friction characteristic.		
Dependency:	Refer to: p3829, p3845		

p3839[0...n]	Friction characteristic, value F9 / Friction F9		
SERVO (Lin)	Can be changed: T	Dynamic index: DDS, p0180	Access level: 2
	Data type: Floating Point	Units group: 8_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min -1000000.00 [N]	Max 1000000.00 [N]	Factory setting 0.00 [N]
Description:	The friction characteristic is defined by 10 value pairs. This parameter specifies the F coordinate of the 10th value pair of the friction characteristic.		
Dependency:	Refer to: p3829, p3845		

r3840	CO/BO: Friction characteristic, status word / Friction ZSW		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned32	Units group: -	Function diagram: 7010
	P-Group: Functions		Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Displays the state of the friction characteristic.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Friction characteristic OK	Yes	No	-
	01	Friction characteristic plot activated	Yes	No	-
	02	Friction characteristic plot completed	Yes	No	-
	03	Friction characteristic plot aborted	Yes	No	-
	08	Friction characteristic direction of rotation, positive	Yes	No	-

r3841	CO: Friction characteristic output / Friction output		
SERVO, VECTOR (n/M)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: 7_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]

Description: Displays the torque of the friction characteristic dependent on the speed.

Dependency: Refer to: p1569, p3842

r3841	CO: Friction characteristic output / Friction output		
SERVO (Lin)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point	Units group: 8_1	Function diagram: 7010
	P-Group: Functions		Unit selection: p0505
	Min	Max	Factory setting
	- [N]	- [N]	- [N]

Description: Displays the force of the friction characteristic dependent on the velocity.

Dependency: Refer to: p1569, p3842

p3842	Friction characteristic activation / Activate friction		
SERVO, VECTOR (n/M)	Can be changed: T	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: 7010
	P-Group: Functions		Unit selection: -
	Min	Max	Factory setting
	0	1	0

Description: Setting to activate and de-activate the friction characteristic.


Values:
 0: Friction characteristic de-activated
 1: Friction characteristic activated


Dependency: Refer to: p1569, r3841, p3845

p3845	Friction characteristic plot activation / Friction plot act		
SERVO, VECTOR	Can be changed: T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: 7010
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	Setting for the friction characteristic plot. After the next power-on command, the friction characteristic is automatically plotted.		
Values:	0: Friction characteristic plot de-activated 1: Friction char. plot activated for all directions of rotation 2: Friction char. plot activated for a pos. direction of rotation 3: Friction char. plot activated for a neg. direction of rotation		
Dependency:	When selecting the friction characteristic measurement, the drive data set changeover is suppressed.		
Notice:	In order to permanently accept the determined settings they must be saved in a non-volatile fashion (p0971, p0977).		
Note:	When the friction characteristic plot is active, it is not possible to save the parameters (p0971, p0977). When the friction characteristic plot is active (p3845 > 0), it is not possible to change p3820 ... p3829, p3830 ... p3839, p3842, p3846 and p3847. When plotting the friction characteristic, in addition to the friction, the motor losses are also determined (e.g. iron losses, eddy current losses and re-magnetization losses). A differentiation is not made between these individual loss components. We recommend that a motor temperature sensor is used because torque deviations can also be emulated/mapped on the characteristic due to the thermal influence.		




p3846[0...n]	Friction characteristic plot ramp-up/ramp-down time / Fric plot t_RFG		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 999999.000 [s]	Factory setting 10.000 [s]
Description:	Sets the ramp-up/ramp-down time of the ramp-up/ramp-down function generator to automatically plot the friction characteristic. The drive is accelerated from standstill (setpoint = 0) up to the maximum speed/velocity (p1082) in this time.		
Dependency:	Refer to: p3845		

p3847[0...n]	Friction characteristic plot warm-up time / Frict plot t_warm		
SERVO, VECTOR (n/M)	Can be changed: T		Access level: 2
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: 7010
	P-Group: Functions	Units group: -	Unit selection: -
	Min 0.000 [s]	Max 3600.000 [s]	Factory setting 0.000 [s]
Description:	Sets the warm-up time. For an automatic trace (plot) to start, the highest selected speed (p3829) is approached and this time is held. After this, the measurement is started with the highest speed.		
Dependency:	Refer to: p3829, p3845		

p3860	Number of Braking Modules connected in parallel / BM count				
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: C2(2)		Access level: 3		
	Data type: Unsigned8	Dynamic index: -	Function diagram: -		
	P-Group: Converter	Units group: -	Unit selection: -		
	Min 1	Max 8	Factory setting 1		
Description:	Sets the number of Braking Modules connected in parallel in a DC link. The parameter can only be written to if the infeed is in the commissioning phase (p0010 = 2).				
r3861	BO: Inhibit Braking Module/fault acknowledgement / BM fault ackn				
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: -		Access level: 3		
	Data type: Unsigned32	Dynamic index: -	Function diagram: -		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Signal to energize terminal X21.1 "inhibit/acknowledgement" on the Braking Module. This binector output is used as signal source to interconnect to a digital output. For "booksize" drive units the digital output must be connected to terminal X21.1 and for "chassis" drive units the digital output must be connected to terminal X21.5 of the particular Braking Module.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Inhibit/acknowledge Braking Module 1	High	Low	-
	01	Inhibit/acknowledge Braking Module 2	High	Low	-
	02	Inhibit/acknowledge Braking Module 3	High	Low	-
	03	Inhibit/acknowledge Braking Module 4	High	Low	-
	04	Inhibit/acknowledge Braking Module 5	High	Low	-
	05	Inhibit/acknowledge Braking Module 6	High	Low	-
	06	Inhibit/acknowledge Braking Module 7	High	Low	-
	07	Inhibit/acknowledge Braking Module 8	High	Low	-
Warning:	It must be carefully ensured that the binector outputs BO: p3861.n are correctly connected and also that the appropriate digital outputs are correctly connected-up. If the interconnections/connections are incorrect and if the Braking Module develops a fault condition, then the software could execute a different (incorrect) function via the binector outputs BO: p3861.n.				
					
p3862	Braking Module DC link fast discharge delay time / BM DC-dischg t_del				
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: C1(3), T		Access level: 3		
	Data type: Unsigned32	Dynamic index: -	Function diagram: -		
	P-Group: Communications	Units group: -	Unit selection: -		
	Min 500 [ms]	Max 4294967295 [ms]	Factory setting 1000 [ms]		
Description:	Sets the delay time for switching-in the DC link fast discharge.				
Dependency:	Refer to: p3863, r3864				
Note:	DC link fast discharge is only possible for "booksize" Braking Modules; "chassis" units do not support this function.				


p3863		BI: Activating Braking Module DC link fast discharge / BM DC-dischg act			
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: T		Dynamic index: -	Access level: 3	
	Data type: Unsigned32			Function diagram: -	
	P-Group: -		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0	
Description:	Sets the signal source to activate the DC link fast discharge. The DC link fast discharge is started later with delay time (p3862) when the following conditions apply: - BI: p3863 = 1 signal. - an external line contactor is opened via r0863.1 "energize contactor". The DC link fast discharge is interrupted when the following conditions apply: - BI: p3863 = 0 signal. - ON command for the infeed.				
Recommendation:	The DC link fast discharge should be activated if there is an external line contactor and is correctly interconnected (r0863.1, p0860). If the DC link fast discharge is not activated together with an external line contactor, then faults could occur when pre-charging (e.g. F300027).				
Dependency:	Refer to: r3864 Refer to: F30027				
Note:	DC link fast discharge is only possible for "booksize" Braking Modules; "chassis" units do not support this function.				
r3864		BO: Braking Module DC link fast discharge / BM DC link dischg			
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: -		Dynamic index: -	Access level: 3	
	Data type: Unsigned32			Function diagram: -	
	P-Group: Commands		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Signal to control (energize) terminal X21.2 "DC link fast discharge" on the Braking Module. This binector output is used as signal source to interconnect to a digital output. The digital output must be connected to terminal X21.2 of the particular Braking Module.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fast discharge Braking Module 1	High	Low	-
	01	Fast discharge Braking Module 2	High	Low	-
	02	Fast discharge Braking Module 3	High	Low	-
	03	Fast discharge Braking Module 4	High	Low	-
	04	Fast discharge Braking Module 5	High	Low	-
	05	Fast discharge Braking Module 6	High	Low	-
	06	Fast discharge Braking Module 7	High	Low	-
	07	Fast discharge Braking Module 8	High	Low	-
Dependency:	Refer to: p3863 Refer to: F30027				
Warning:	It must be carefully ensured that the binector outputs BO: p3864.n are correctly interconnected and also that the appropriate digital outputs are correctly connected-up. If the interconnection/connection is incorrect, in the case of an active DC link fast discharge, the software could execute another function (incorrect function) via binector outputs BO: p3864.n or could also permanently control the DC link fast discharge even if the line contactor is closed.				
					
Note:	DC link fast discharge is only possible for "booksize" Braking Modules; "chassis" units do not support this function.				

p3865[0...7]	BI: Braking Module pre-warning I*t shutdown / BM I*t shutdown			
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: T			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0
Description:	Sets the signal source for the signal "pre-alarm I*t shutdown (X21.3) of the Braking Module. BI: p3865[0...7] = 0 signal --> no pre-alarm, I*t shutdown BI: p3865[0...7] = 1 signal --> pre-alarm I*t shutdown (A06901)			
Dependency:	Refer to: A06901			
Note:	The I*t shutdown pre-alarm is only possible for "booksize" Braking Modules; "chassis" units do not support this function.			
p3866[0...7]	BI: Braking Module fault / BM fault			
A_INF (Brk_Mod), B_INF (Brk_Mod), S_INF (Brk_Mod)	Can be changed: T			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0
Description:	Sets the signal source for the "fault" signal of the Braking Module (X21.4 for "booksize" units and X21.3 for "chassis" units). BI: p3866[0...7] = 0 signal --> no fault BI: p3866[0...7] = 1 signal --> fault (A06900) For a 1 signal, an acknowledgement via BO: r3861 is automatically carried-out at certain time intervals.			
Dependency:	Refer to: A06900			
p3870	Long stator configuration / Long stator config			
SERVO	Can be changed: U, T			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Sets the configuration when operating a long stator motor.			
Bit field:	Bit	Signal name	1 signal	0 signal FP
	00	Activate long stator help functions	active	not active -
	01	Suppress Gx_ZSW.14	active	not active -
Dependency:	Refer to: p3871, p3872, p3873, p3874, r3875, p3876, p3878, p3879			
Notice:	The following restrictions apply to this function: - it is not permissible to change over the drive data set. - the encoder/drive may not be parked using a PROFIBUS telegram. - a maximum of 4 drives may be connected to the Control Unit. - it is not permissible to commutate with the zero mark (p0404).			
Note:	Re bit 00: All of the help functions for long stator motors can be enabled/disabled using this bit. Re bit 01: Bit 14 (parking encoder active) is always set to 0 in the encoder status word GX_ZSW independent of whether the encoder is parked or not.			

p3871	BI: Set long stator signal source commutation angle (p3872) / Set S_src com_ang		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to set the commutation angle from CI: p3872.		
Dependency:	Refer to: p3870, p3872, p3873, p3874, r3875, p3876, p3878, p3879		
Danger:	If an incorrect commutation angle is set, this can result in instability in the closed-loop control and in turn injure personnel or cause damage to the machine !		
			
Note:	Setting takes place for a 0/1 signal edge.		
p3872	CI: Long stator signal source commutation angle / S_src com_angle		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	3878[0]
Description:	Sets the signal source for the commutation angle. This angle is set for a 0/1 signal edge via BI: p3871.		
Dependency:	Refer to: p3870, p3871, p3873, r3875, p3876, p3878, p3879		
Danger:	If an incorrect commutation angle is set, this can result in instability in the closed-loop control and in turn injure personnel or cause damage to the machine !		
			
p3873	BI: Long stator sig. source to change over to cl.-loop ctrl w/ enc. / S_src ctrl w/ enc		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Functions	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to change over to closed-loop control with encoder.		
Dependency:	Refer to: p3870, p3871, p3872, p3874, r3875, p3876, p3878, p3879		
Danger:	If an incorrect commutation angle is set, this can result in instability in the closed-loop control and in turn injure personnel or cause damage to the machine !		
			
Note:	= 1 --> closed-loop control with encoder = 0 --> sensorless closed-loop control For a 0/1 edge, the commutation angle is set from CI: p3874.		
p3874	CI: Long stator signal source comm. angle oper. with encoder / S_src com_ang enc		
SERVO	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	3879[0]
Description:	Sets the signal source for the commutation angle for operation with encoder.		
Dependency:	Refer to: p3870, p3871, p3872, p3873, r3875, p3876, p3878, p3879		
Note:	This angle is set for a 0/1 signal edge via BI: p3873.		

r3875	CO/BO: Long stator status word / ZSW		
SERVO	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays the status word for long stator motors.		
Bit field:	Bit	Signal name	1 signal
	00	Encoder module is unparked	Yes
	01	Closed-loop speed control with encoder requested	active
			0 signal
			No
			not active
			FP
			-
			-
Dependency:	Refer to: p3870, p3871, p3872, p3873, p3874, p3876, p3878, p3879		
Note:	The display is updated with a sampling time of 1 ms. Re bit 00 = 1: The encoder is parked. Contrary to r0481.14, parking is also displayed here if the suppression of the parking bit is active in r481.14 (p3870.1 = 1). Re bit 01 = 1: The long-stator functions requested closed-loop speed control with encoder. Read r1407.2 to identify whether an encoder is actually being used for closed-loop control.		
p3876	BI: Unpark long stator signal source 1 encoder / S_src enc_unpark 1		
SERVO	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source 1 to unpark the encoder.		
Dependency:	Refer to: p3870, p3871, p3872, p3873, p3874, r3875, p3878, p3879		
Note:	= 1 --> Encoder is unparked = 0 --> Encoder is parked		
p3878	CO: Long stator commutation angle 1 / Commut_ang 1		
SERVO	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-180 [°]	180 [°]	0 [°]
Description:	Enters the commutation angle 1 for long stator motors.		
Dependency:	Refer to: p3870, p3871, p3872, p3873, p3874, r3875, p3876, p3879		
p3879	CO: Long stator commutation angle 2 / Commut_ang 2		
SERVO	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-180 [°]	180 [°]	0 [°]
Description:	Enters the commutation angle 2 for long stator motors.		
Dependency:	Refer to: p3870, p3871, p3872, p3873, p3874, r3875, p3876, p3878		

p3900	Completion of quick commissioning / End quick_comm		
A_INF, B_INF, S_INF	Can be changed: C2(1)	Dynamic index: -	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	<p>Exits the quick commissioning (p0010 = 1) with automatic calculation of all of the parameters that depend on the entries made during the quick commissioning.</p> <p>p3900 = 1 initially includes a parameter reset (factory setting, the same as p0970 = 1) for all parameters of the drive object; however, without overwriting the entries made during the quick commissioning. The interconnections of PROFIBUS PZD telegram selection (p0922) and the interconnections via p0700 are re-established and all of the dependent filter and closed-loop control parameters are calculated (corresponding to p0340 = 1).</p> <p>p3900 = 2 includes the restoration of the interconnections of PROFIBUS PZD telegram selection (p0922) and the interconnections via p0700 and the calculations corresponding to p0340 = 1.</p> <p>p3900 = 3 only includes the end of the fast commissioning.</p>		
Values:	<p>0: No quick parameterization</p> <p>1: Quick parameterization after parameter reset</p> <p>2: Quick param. (only) for controller parameters and reset for BIC</p> <p>3: Completion of quick commissioning</p>		
Note:	When the calculations have been completed, p3900 and p0010 are automatically reset to a value of 0.		
p3900	Completion of quick commissioning / End quick_comm		
SERVO, VECTOR	Can be changed: C2(1)	Dynamic index: -	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Displays, signals		Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	<p>Exits the quick commissioning (p0010 = 1) with automatic calculation of all of the parameters that depend on the entries made during the quick commissioning.</p> <p>p3900 = 1 initially includes a parameter reset (factory setting, the same as p0970 = 1) for all parameters of the drive object; however, without overwriting the entries made during the quick commissioning.</p> <p>The interconnections of PROFIBUS PZD telegram selection (p0922) and the interconnections via p0700, p1000 and p1500 are re-established and all of the dependent motor, open-loop and control-loop control parameters are calculated (corresponding to p0340 = 1).</p> <p>p3900 = 2 includes the restoration of the interconnections of PROFIBUS PZD telegram selection (p0922) and the interconnections via p0700, p1000 and p1500 and the calculations corresponding to p0340 = 1.</p> <p>p3900 = 3 only includes the calculations associated with the motor, open-loop and closed-loop control parameters corresponding to p0340 = 1.</p>		
Values:	<p>0: No quick parameterization</p> <p>1: Quick parameterization after parameter reset</p> <p>2: Quick parameterization (only) for BICO and motor parameters</p> <p>3: Quick parameterization for motor parameters (only)</p>		
Note:	<p>When the calculations have been completed, p3900 and p0010 are automatically reset to a value of 0.</p> <p>When calculating motor, open-loop and closed-loop control parameters (such as for p0340 = 1) parameters associated with a selected Siemens list motor are not overwritten.</p>		

p3902[0...n]	Power unit EEPROM Vdc calibration / LT EEPROM Vdc_cal		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: C1, C2(1), T	Dynamic index: PDS, p0120	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Calibration factor for the DC link voltage measurement.		
Caution:	Incorrect use of the calibration can have a negative impact on the closed-loop control. The parameter influences the upper and lower voltage detection.		
			
Note:	Parameter entries are directly saved in the DRIVE-CLiQ component involved. Only values from 100 ... 10000 are accepted. All other entries are not saved and are therefore also not displayed. The parameter only has an effect for chassis-type power units. Calculation rule: $p3902_new = p3902_old * r0026 / Vdc_measured \text{ value}$		

r3925[0...n]	Identification final display / Ident final_disp				
VECTOR	Can be changed: -	Dynamic index: DDS, p0180	Access level: 3		
	Data type: Unsigned32		Function diagram: -		
	P-Group: Motor	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the commissioning steps that have been carried-out.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Automatic parameterization carried-out (p0340 = 1, p3900 > 0)	Yes	No	-
	02	Motor data identification carried-out at standstill (p1910 = 1)	Yes	No	-
	03	Rotating measurement carried-out (p1960 = 1 or 2)	Yes	No	-
	04	Motor encoder adjustment carried-out (p1990 = 1)	Yes	No	-
	15	Motor equivalent circuit diagram parameters changed	Changed	Not changed	-
Note:	When motor rating plate parameters are changed, the final display is reset. When setting the individual bits, all of the most significant bits are reset. Bit 00 = Automatic parameterization (p0340 = 1, p3900 > 0). Bit 02 = Motor data identification (p1910 = 1) successfully completed. Bit 03 = Rotating measurement (p1960 = 1, 2) successfully completed. Bit 04 = Motor encoder adjustment (p1990 = 1) successfully completed. Bit 15 = Equivalent circuit diagram parameters of the motor were subsequently manually changed.				

r3927[0...n]		Motor data identification control word / MotID STW			
VECTOR	Can be changed: -	Access level: 3			
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: -		
	P-Group: Motor identification	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Successfully completed component of the last motor data identification carried-out.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Estimates the stator inductance, no measurement	Yes	No	-
	01	Cl.-loop current control w/ dead-beat controller	Yes	No	-
	02	Estimates the rotor time constant, no measurement	Yes	No	-
	03	Estimates the leakage inductance, no measurement	Yes	No	-
	04	Activates the identification dynamic leakage inductance	Yes	No	-
	05	Determine Tr. Lsig evaluation in the time range	Yes	No	-
	06	Activates vibration damping	Yes	No	-
	07	De-activates the vibration detection	Yes	No	-
	11	De-activate pulse measurement Lq Ld	Yes	No	-
	12	De-activate rotor resistance Rr measurement	Yes	No	-
	15	Only measure stator resistance and valve voltage error	Yes	No	-
Dependency:	Refer to: r3925				
Note:	The parameter is a copy of p1909.				
r3928[0...n]		Rotating measurement configuration / Rot meas config			
VECTOR (n/M)	Can be changed: -	Access level: 3			
	Data type: Unsigned16	Dynamic index: DDS, p0180	Function diagram: -		
	P-Group: Motor identification	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0001 1111 bin		
Description:	Successfully completed component of the last rotating measurement carried-out.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enc test active	Yes	No	-
	01	Saturation characteristic identification	Yes	No	-
	02	Moment of inertia identification	Yes	No	-
	03	Recalculates the speed controller parameters	Yes	No	-
	04	Speed controller optimization, (vibration test)	Yes	No	-
Dependency:	Refer to: r3925				
Note:	The parameter is a copy of p1959.				
p3950		Service parameter / Service parameter			
CU_S	Can be changed: C1, U, T	Access level: 4			
	Data type: Unsigned16	Dynamic index: -	Function diagram: -		
	P-Group: -	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	For service personnel only.				

r3977	BICO counter, topology / BICO counter topo		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the BICO interconnections that have been parameterized in the complete (overall) topology. The counter is incremented by one for each modified BICO interconnection.		
Dependency:	Refer to: r3978, r3979		
r3978	BICO CounterDevice / BICO CounterDevice		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	For each modified BICO interconnection of this device, the counter is incremented by one. Displays this counter.		
r3979	BICO counter, drive object / BICO counter DO		
A_INF, B_INF, CU_LINK, DMC20, SERVO, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VEC- TOR	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	For each modified BICO interconnection of this drive object, the counter is incremented by one. Displays this counter.		
p3981	Faults, acknowledge drive object / Faults ackn DO		
All objects	Can be changed: U, T		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: 2501
	P-Group: Messages	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Acknowledges all active faults of a drive object.		
Note:	Parameter should be set from 0 to 1 to acknowledge. After acknowledgement, the parameter is automatically reset to 0.		
p3985	Master control mode selection / PcCtrl mode select		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the mode to change over the master control / LOCAL mode.		
Values:	0: Change master control for STW1.0 = 0 1: Change master control in operation		

Danger:



When changing the master control in operation, the drive can manifest undesirable behavior - e.g. it can accelerate up to another setpoint.

r3986

Parameter count / Parameter count

All objects

Can be changed: -

Access level: 3

Data type: Unsigned16

Dynamic index: -

Function diagram: -

P-Group: -

Units group: -

Unit selection: -

Min

Max

Factory setting

-

-

-

Description:

Displays the number of parameters for this drive unit.
The number comprises the device-specific and the drive-specific parameters.

Dependency:

Refer to: r0980, r0981, r0989

r3988

Ramp-up state / Ramp-up state

CU_S

Can be changed: -

Access level: 4

Data type: Integer16

Dynamic index: -

Function diagram: -

P-Group: -

Units group: -

Unit selection: -

Min

Max

Factory setting

0

800

0

Description:

Displays the ramp-up state.

Values:

- 0: Not active
- 1: Fatal fault
- 10: Fault
- 20: Reset all parameters
- 30: Drive object modified
- 40: Download using commissioning software
- 90: Reset Control Unit and delete drive objects
- 100: Start initialization
- 110: Instantiate Control Unit basis
- 150: Wait until actual topology determined
- 160: Evaluate topology
- 170: Instantiate Control Unit rest
- 180: Initialization YDB configuration information
- 200: First commissioning
- 210: Create drive packages
- 250: Wait for topology acknowledge
- 325: Wait for input of drive type
- 350: Determine drive type
- 360: Write into topology-dependent parameters
- 370: Wait until p0009 = 0 is set
- 380: Check topology
- 550: Call conversion functions for parameter
- 625: Wait non-cyclic starting DRIVE CLiQ
- 650: Start cyclic operation
- 660: Evaluate drive commissioning status
- 680: Wait for CU link slaves
- 700: Save parameters
- 725: Wait until DRIVE-CLiQ cyclic
- 740: Check the ability to operate
- 750: Interrupt enable
- 800: Initialization finished

r3996	Parameter write inhibit status / Par_write inhib st			
All objects	Can be changed: -			Access level: 1
	Data type: Unsigned8	Dynamic index: -		Function diagram: -
	P-Group: -	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays whether writing to parameters is inhibited. r3996 = 0: Write to parameter is not inhibited. 0 < r3996 < 100: Write to parameter is inhibited. The value shows how the calculations are progressing.			
r4021	TB30 digital inputs terminal actual value / TB30 DI act value			
TB30	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 9100
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the actual value at the digital inputs. This means that the actual input signal can be checked at terminal DI x prior to switching from the simulation mode (p4095.x = 1) to the terminal mode (p4095.x = 0). The input signal of terminal DI x is displayed in bit x of r4021.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X481.1)	High	Low
	01	DI 1 (X481.2)	High	Low
	02	DI 2 (X481.3)	High	Low
	03	DI 3 (X481.4)	High	Low
				FP
				-
				-
				-
				-
Note:	DI: Digital input			
r4021	TM31 digital inputs terminal actual value / TM31 DI act value			
TM31	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 1840, 9550, 9552, 9560, 9562
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the actual value at the digital inputs. This means that the actual input signal can be checked at terminal DI x or DI/DO x prior to switching from the simulation mode (p4095.x = 1) to terminal mode (p4095.x = 0). The input signal at terminal DI x or DI/DO x is displayed in bit x of r4021.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X520.1)	High	Low
	01	DI 1 (X520.2)	High	Low
	02	DI 2 (X520.3)	High	Low
	03	DI 3 (X520.4)	High	Low
	04	DI 4 (X530.1)	High	Low
	05	DI 5 (X530.2)	High	Low
	06	DI 6 (X530.3)	High	Low
	07	DI 7 (X530.4)	High	Low
	08	DI/DO 8 (X541.2)	High	Low
	09	DI/DO 9 (X541.3)	High	Low
	10	DI/DO 10 (X541.4)	High	Low
	11	DI/DO 11 (X541.5)	High	Low
				FP
				-
				-
				-
				-
				-
Note:	If a DI/DO is parameterized as output (p4028.x = 1), then r4021.x = 0 is displayed. DI: Digital input DI/DO: Bidirectional Digital Input/Output			

r4021		TM41 digital inputs terminal actual value / TM41 DI act val			
TM41	Can be changed: -			Access level: 2	
	Data type: Unsigned32		Dynamic index: -	Function diagram: -	
	P-Group: Commands		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Displays the actual value at the digital inputs. This means that the actual input signal can be checked at terminal DI x or DI/DO x prior to switching from the simulation mode (p4095.x = 1) to terminal mode (p4095.x = 0). The input signal at terminal DI x or DI/DO x is displayed in bit x of r4021.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X522.1)	High	Low	-
	01	DI 1 (X522.2)	High	Low	-
	02	DI 2 (X522.3)	High	Low	-
	03	DI 3 (X522.4)	High	Low	-
	08	DI/DO 0 (X521.1)	High	Low	-
	09	DI/DO 1 (X521.2)	High	Low	-
	10	DI/DO 2 (X521.3)	High	Low	-
	11	DI/DO 3 (X521.4)	High	Low	-
Note:	If a DI/DO is parameterized as output (p4028.x = 1), then r4021.x = 0 is displayed. DI: Digital input DI/DO: Bidirectional Digital Input/Output				

r4021		TM15DI/DO digital inputs, terminal actual value / TM15D DI act val			
TM15DI_DO	Can be changed: -			Access level: 2	
	Data type: Unsigned32		Dynamic index: -	Function diagram: 9400, 9401, 9402	
	P-Group: Commands		Units group: -	Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Displays the actual value at the digital inputs. This means that the actual input signal can be checked at terminal DI x or DI/DO x prior to switching from the simulation mode (p4095.x = 1) to terminal mode (p4095.x = 0). The input signal at terminal DI x or DI/DO x is displayed in bit x of r4021.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	High	Low	-
	01	DI/DO 1 (X520.3)	High	Low	-
	02	DI/DO 2 (X520.4)	High	Low	-
	03	DI/DO 3 (X520.5)	High	Low	-
	04	DI/DO 4 (X520.6)	High	Low	-
	05	DI/DO 5 (X520.7)	High	Low	-
	06	DI/DO 6 (X520.8)	High	Low	-
	07	DI/DO 7 (X520.9)	High	Low	-
	08	DI/DO 8 (X521.2)	High	Low	-
	09	DI/DO 9 (X521.3)	High	Low	-
	10	DI/DO 10 (X521.4)	High	Low	-
	11	DI/DO 11 (X521.5)	High	Low	-
	12	DI/DO 12 (X521.6)	High	Low	-
	13	DI/DO 13 (X521.7)	High	Low	-

14	DI/DO 14 (X521.8)	High	Low	-
15	DI/DO 15 (X521.9)	High	Low	-
16	DI/DO 16 (X522.2)	High	Low	-
17	DI/DO 17 (X522.3)	High	Low	-
18	DI/DO 18 (X522.4)	High	Low	-
19	DI/DO 19 (X522.5)	High	Low	-
20	DI/DO 20 (X522.6)	High	Low	-
21	DI/DO 21 (X522.7)	High	Low	-
22	DI/DO 22 (X522.8)	High	Low	-
23	DI/DO 23 (X522.9)	High	Low	-

Note: If a DI/DO is parameterized as output (p4028.x = 1), then r4021.x = 0 is displayed.
DI/DO: Bidirectional Digital Input/Output

r4022 CO/BO: TB30 digital inputs, status / TB30 DI status

TB30 **Can be changed:** - **Access level:** 1
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 1790, 9100
P-Group: Commands **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the status of the digital inputs of the Terminal Board 30 (TB30).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X481.1)	High	Low	-
	01	DI 1 (X481.2)	High	Low	-
	02	DI 2 (X481.3)	High	Low	-
	03	DI 3 (X481.4)	High	Low	-

Dependency: Refer to: r4023

Note: DI: Digital input

r4022 CO/BO: TM31 digital inputs, status / TM31 DI status

TM31 **Can be changed:** - **Access level:** 1
Data type: Unsigned32 **Dynamic index:** - **Function diagram:** 1840, 9550, 9552, 9560, 9562
P-Group: Commands **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Displays the status of the digital inputs of terminal module 31 (TM31).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X520.1)	High	Low	-
	01	DI 1 (X520.2)	High	Low	-
	02	DI 2 (X520.3)	High	Low	-
	03	DI 3 (X520.4)	High	Low	-
	04	DI 4 (X530.1)	High	Low	-
	05	DI 5 (X530.2)	High	Low	-
	06	DI 6 (X530.3)	High	Low	-
	07	DI 7 (X530.4)	High	Low	-
	08	DI/DO 8 (X541.2)	High	Low	-
	09	DI/DO 9 (X541.3)	High	Low	-
	10	DI/DO 10 (X541.4)	High	Low	-
	11	DI/DO 11 (X541.5)	High	Low	-

Dependency: Refer to: r4023

Note: DI: Digital input

DI/DO: Bidirectional Digital Input/Output

r4022		CO/BO: TM41 digital inputs, status / TM41 DI status		
TM41	Can be changed: -			Access level: 1
	Data type: Unsigned32		Dynamic index: -	Function diagram: 1840, 9550, 9552, 9560, 9562
	P-Group: Commands		Units group: -	Unit selection: -
	Min		Max	Factory setting
	-		-	0000 bin
Description:	Displays the status of the digital inputs of terminal module 41 (TM41).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X522.1)	High	Low
	01	DI 1 (X522.2)	High	Low
	02	DI 2 (X522.3)	High	Low
	03	DI 3 (X522.4)	High	Low
	08	DI/DO 0 (X521.1)	High	Low
	09	DI/DO 1 (X521.2)	High	Low
	10	DI/DO 2 (X521.3)	High	Low
	11	DI/DO 3 (X521.4)	High	Low
Dependency:	Refer to: r4023			
Note:	DI: Digital input, DI/DO: Bidirectional Digital Input/Output			

r4022		CO/BO: TM15DI/DO digital inputs, status / TM15D DI status		
TM15DI_DO	Can be changed: -			Access level: 1
	Data type: Unsigned32		Dynamic index: -	Function diagram: 9400, 9401, 9402
	P-Group: Commands		Units group: -	Unit selection: -
	Min		Max	Factory setting
	-		-	0000 bin
Description:	Displays the status of the digital inputs of terminal module 15 (TM15).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI/DO 0 (X520.2)	High	Low
	01	DI/DO 1 (X520.3)	High	Low
	02	DI/DO 2 (X520.4)	High	Low
	03	DI/DO 3 (X520.5)	High	Low
	04	DI/DO 4 (X520.6)	High	Low
	05	DI/DO 5 (X520.7)	High	Low
	06	DI/DO 6 (X520.8)	High	Low
	07	DI/DO 7 (X520.9)	High	Low
	08	DI/DO 8 (X521.2)	High	Low
	09	DI/DO 9 (X521.3)	High	Low
	10	DI/DO 10 (X521.4)	High	Low
	11	DI/DO 11 (X521.5)	High	Low
	12	DI/DO 12 (X521.6)	High	Low
	13	DI/DO 13 (X521.7)	High	Low
	14	DI/DO 14 (X521.8)	High	Low
	15	DI/DO 15 (X521.9)	High	Low
	16	DI/DO 16 (X522.2)	High	Low
	17	DI/DO 17 (X522.3)	High	Low
	18	DI/DO 18 (X522.4)	High	Low
	19	DI/DO 19 (X522.5)	High	Low
	20	DI/DO 20 (X522.6)	High	Low
	21	DI/DO 21 (X522.7)	High	Low
	22	DI/DO 22 (X522.8)	High	Low
	23	DI/DO 23 (X522.9)	High	Low
Dependency:	Refer to: r4023, r4024, r4025			
Notice:	For the BICO interconnection of the connector output (CO) only bit 00 ... bit 15 are transferred.			
Note:	DI/DO: Bidirectional Digital Input/Output			

r4023	BO: TB30 digital inputs, status inverted / TB30 DI status inv				
TB30	Can be changed: -		Access level: 1		
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1790, 9100		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the inverted status of the digital inputs of the Terminal Board 30 (TB30).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X481.1)	High	Low	-
	01	DI 1 (X481.2)	High	Low	-
	02	DI 2 (X481.3)	High	Low	-
	03	DI 3 (X481.4)	High	Low	-
Dependency:	Refer to: r4022				
Note:	DI: Digital input				

r4023	CO/BO: TM31 digital inputs, status inverted / TM31 DI status inv				
TM31	Can be changed: -		Access level: 1		
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9550, 9552, 9560, 9562		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Displays the inverted status of the digital inputs of terminal module 31 (TM31).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X520.1)	High	Low	-
	01	DI 1 (X520.2)	High	Low	-
	02	DI 2 (X520.3)	High	Low	-
	03	DI 3 (X520.4)	High	Low	-
	04	DI 4 (X530.1)	High	Low	-
	05	DI 5 (X530.2)	High	Low	-
	06	DI 6 (X530.3)	High	Low	-
	07	DI 7 (X530.4)	High	Low	-
	08	DI/DO 8 (X541.2)	High	Low	-
	09	DI/DO 9 (X541.3)	High	Low	-
	10	DI/DO 10 (X541.4)	High	Low	-
	11	DI/DO 11 (X541.5)	High	Low	-
Dependency:	Refer to: r4022				
Note:	DI: Digital input DI/DO: Bidirectional Digital Input/Output				

r4023		BO: TM41 digital inputs, status inverted / TM41 DI status inv		
TM41	Can be changed: -		Dynamic index: -	Access level: 1
	Data type: Unsigned32			Function diagram: 1840, 9550, 9552, 9560, 9562
	P-Group: Commands		Units group: -	Unit selection: -
	Min		Max	Factory setting
	-		-	0000 bin
Description:	Displays the inverted status of the digital inputs of terminal module 41 (TM41).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X522.1)	High	Low
	01	DI 1 (X522.2)	High	Low
	02	DI 2 (X522.3)	High	Low
	03	DI 3 (X522.4)	High	Low
	08	DI/DO 0 (X521.1)	High	Low
	09	DI/DO 1 (X521.2)	High	Low
	10	DI/DO 2 (X521.3)	High	Low
	11	DI/DO 3 (X521.4)	High	Low
Dependency:	Refer to: r4022			
Note:	DI: Digital input, DI/DO: Bidirectional Digital Input/Output			

r4023		CO/BO: TM15DI/DO digital inputs, status inverted / TM15D DI stat inv		
TM15DI_DO	Can be changed: -		Dynamic index: -	Access level: 1
	Data type: Unsigned32			Function diagram: 9400, 9401, 9402
	P-Group: Commands		Units group: -	Unit selection: -
	Min		Max	Factory setting
	-		-	0000 bin
Description:	Displays the inverted status of the digital inputs of terminal module 15 (TM15).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI/DO 0 (X520.2)	High	Low
	01	DI/DO 1 (X520.3)	High	Low
	02	DI/DO 2 (X520.4)	High	Low
	03	DI/DO 3 (X520.5)	High	Low
	04	DI/DO 4 (X520.6)	High	Low
	05	DI/DO 5 (X520.7)	High	Low
	06	DI/DO 6 (X520.8)	High	Low
	07	DI/DO 7 (X520.9)	High	Low
	08	DI/DO 8 (X521.2)	High	Low
	09	DI/DO 9 (X521.3)	High	Low
	10	DI/DO 10 (X521.4)	High	Low
	11	DI/DO 11 (X521.5)	High	Low
	12	DI/DO 12 (X521.6)	High	Low
	13	DI/DO 13 (X521.7)	High	Low
	14	DI/DO 14 (X521.8)	High	Low
	15	DI/DO 15 (X521.9)	High	Low
	16	DI/DO 16 (X522.2)	High	Low
	17	DI/DO 17 (X522.3)	High	Low
	18	DI/DO 18 (X522.4)	High	Low
	19	DI/DO 19 (X522.5)	High	Low
	20	DI/DO 20 (X522.6)	High	Low
	21	DI/DO 21 (X522.7)	High	Low
	22	DI/DO 22 (X522.8)	High	Low
	23	DI/DO 23 (X522.9)	High	Low
Dependency:	Refer to: r4022, r4024, r4025			
Notice:	For the BICO interconnection of the connector output (CO) only bit 00 ... bit 15 are transferred.			
Note:	DI/DO: Bidirectional Digital Input/Output			

r4024		CO: TM15DI/DO digital inputs 16 ... 23 status / TM15D DI 16-23 St		
TM15DI_DO	Can be changed: -			Access level: 1
	Data type: Unsigned16	Dynamic index: -		Function diagram: 9402
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the status of digital inputs 16 ... 23 of terminal module 15 (TM15).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI/DO 16 (X522.2)	On	Off
	01	DI/DO 17 (X522.3)	On	Off
	02	DI/DO 18 (X522.4)	On	Off
	03	DI/DO 19 (X522.5)	On	Off
	04	DI/DO 20 (X522.6)	On	Off
	05	DI/DO 21 (X522.7)	On	Off
	06	DI/DO 22 (X522.8)	On	Off
	07	DI/DO 23 (X522.9)	On	Off
Dependency:	Refer to: r4022, r4023, r4025			
Note:	DI: Digital input			

r4025		CO: TM15DI/DO digital inputs 16 ... 23 status inverted / TM15D DI 16-23 inv		
TM15DI_DO	Can be changed: -			Access level: 1
	Data type: Unsigned16	Dynamic index: -		Function diagram: 9402
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the inverted status of digital inputs 16 ... 23 of terminal module 15 (TM15).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI/DO 16 (X522.2)	On	Off
	01	DI/DO 17 (X522.3)	On	Off
	02	DI/DO 18 (X522.4)	On	Off
	03	DI/DO 19 (X522.5)	On	Off
	04	DI/DO 20 (X522.6)	On	Off
	05	DI/DO 21 (X522.7)	On	Off
	06	DI/DO 22 (X522.8)	On	Off
	07	DI/DO 23 (X522.9)	On	Off
Dependency:	Refer to: r4022, r4023, r4024			
Note:	DI: Digital input			

p4028		TM31 set input or output / TM31 DI or DO		
TM31	Can be changed: T			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 1840, 9560, 9562
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Sets the bidirectional digital inputs/outputs as input or output on the terminal module 31 (TM31).			
Bit field:	Bit	Signal name	1 signal	0 signal
	08	DI/DO 8 (X541.2)	Output	Input
	09	DI/DO 9 (X541.3)	Output	Input
	10	DI/DO 10 (X541.4)	Output	Input
	11	DI/DO 11 (X541.5)	Output	Input

p4028		TM41 set input or output / TM41 DI or DO			
TM41	Can be changed: T			Access level: 1	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 1840, 9560, 9562	
	P-Group: Commands	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Sets the bidirectional digital inputs/outputs on the terminal module 41 (TM41) as input or output.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	08	DI/DO 0 (X521.1)	Output	Input	-
	09	DI/DO 1 (X521.2)	Output	Input	-
	10	DI/DO 2 (X521.3)	Output	Input	-
	11	DI/DO 3 (X521.4)	Output	Input	-

p4028		TM17 set input or output / TM17 DI or DO			
TM17	Can be changed: T			Access level: 2	
	Data type: Unsigned32	Dynamic index: -		Function diagram: -	
	P-Group: Commands	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Sets the bidirectional digital inputs/outputs on the terminal module 17 (TM17) as input or output.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Output	Input	-
	01	DI/DO 1 (X520.3)	Output	Input	-
	02	DI/DO 2 (X520.5)	Output	Input	-
	03	DI/DO 3 (X520.6)	Output	Input	-
	04	DI/DO 4 (X520.8)	Output	Input	-
	05	DI/DO 5 (X520.9)	Output	Input	-
	06	DI/DO 6 (X521.2)	Output	Input	-
	07	DI/DO 7 (X521.3)	Output	Input	-
	08	DI/DO 8 (X521.8)	Output	Input	-
	09	DI/DO 9 (X521.9)	Output	Input	-
	10	DI/DO 10 (X522.2)	Output	Input	-
	11	DI/DO 11 (X522.3)	Output	Input	-
	12	DI/DO 12 (X522.5)	Output	Input	-
	13	DI/DO 13 (X522.6)	Output	Input	-
	14	DI/DO 14 (X522.8)	Output	Input	-
	15	DI/DO 15 (X522.9)	Output	Input	-

Note: DI/DO: Bidirectional Digital Input/Output

p4028 TM15 set input or output / TM15 DI or DO

TM15	Can be changed: T	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Sets the bidirectional digital inputs/outputs on the terminal module 15 (TM15) as input or output.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Output	Input	-
	01	DI/DO 1 (X520.3)	Output	Input	-
	02	DI/DO 2 (X520.4)	Output	Input	-
	03	DI/DO 3 (X520.5)	Output	Input	-
	04	DI/DO 4 (X520.6)	Output	Input	-
	05	DI/DO 5 (X520.7)	Output	Input	-
	06	DI/DO 6 (X520.8)	Output	Input	-
	07	DI/DO 7 (X520.9)	Output	Input	-
	08	DI/DO 8 (X521.2)	Output	Input	-
	09	DI/DO 9 (X521.3)	Output	Input	-
	10	DI/DO 10 (X521.4)	Output	Input	-
	11	DI/DO 11 (X521.5)	Output	Input	-
	12	DI/DO 12 (X521.6)	Output	Input	-
	13	DI/DO 13 (X521.7)	Output	Input	-
	14	DI/DO 14 (X521.8)	Output	Input	-
	15	DI/DO 15 (X521.9)	Output	Input	-
	16	DI/DO 16 (X522.2)	Output	Input	-
	17	DI/DO 17 (X522.3)	Output	Input	-
	18	DI/DO 18 (X522.4)	Output	Input	-
	19	DI/DO 19 (X522.5)	Output	Input	-
	20	DI/DO 20 (X522.6)	Output	Input	-
	21	DI/DO 21 (X522.7)	Output	Input	-
	22	DI/DO 22 (X522.8)	Output	Input	-
	23	DI/DO 23 (X522.9)	Output	Input	-

Note: DI/DO: Bidirectional Digital Input/Output

p4028 TM15DI/DO set input or output / TM15D DI or DO

TM15DI_DO	Can be changed: T	Access level: 1
	Data type: Unsigned32	Dynamic index: -
	P-Group: Commands	Function diagram: 9400, 9401, 9402
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Sets the bidirectional digital inputs/outputs on the terminal module 15 (TM15) as input or output.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Output	Input	-
	01	DI/DO 1 (X520.3)	Output	Input	-
	02	DI/DO 2 (X520.4)	Output	Input	-
	03	DI/DO 3 (X520.5)	Output	Input	-
	04	DI/DO 4 (X520.6)	Output	Input	-
	05	DI/DO 5 (X520.7)	Output	Input	-
	06	DI/DO 6 (X520.8)	Output	Input	-
	07	DI/DO 7 (X520.9)	Output	Input	-
	08	DI/DO 8 (X521.2)	Output	Input	-
	09	DI/DO 9 (X521.3)	Output	Input	-
	10	DI/DO 10 (X521.4)	Output	Input	-
	11	DI/DO 11 (X521.5)	Output	Input	-
	12	DI/DO 12 (X521.6)	Output	Input	-
	13	DI/DO 13 (X521.7)	Output	Input	-

14	DI/DO 14 (X521.8)	Output	Input	-
15	DI/DO 15 (X521.9)	Output	Input	-
16	DI/DO 16 (X522.2)	Output	Input	-
17	DI/DO 17 (X522.3)	Output	Input	-
18	DI/DO 18 (X522.4)	Output	Input	-
19	DI/DO 19 (X522.5)	Output	Input	-
20	DI/DO 20 (X522.6)	Output	Input	-
21	DI/DO 21 (X522.7)	Output	Input	-
22	DI/DO 22 (X522.8)	Output	Input	-
23	DI/DO 23 (X522.9)	Output	Input	-

Note: DI/DO: Bidirectional Digital Input/Output

p4030 BI: TB30 signal source for terminal DO 0 / TB30 S_src DO 0

TB30	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1790, 9102
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0

Description: Sets the signal source for digital output DO 0 (X481.5) of the Terminal Board 30 (TB30).

Note: DO: Digital Output

p4030 BI: TM31 signal source for terminal DO 0 / TM31 S_src DO 0

TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9556
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0

Description: Sets the signal source for the digital output DO 0 (X542.1, X542.2, X542.3) of terminal module 31 (TM31).
Digital output 0 of TM31 is a relay output.

If the signal at the binector input p4030 is low, then terminal COM 0 (X542.2) is connected to NC 0 (X542.1). This connection also matches the mechanical quiescent setting of the relay.

If the signal at the binector input p4030 is high, then terminal COM 0 (X542.2) is connected to NO 0 (X542.3).

Note: DO: Digital Output

NC: Normally Closed contact

NO: Normally Open contact

p4030 BI: TM15DI/DO signal source for terminal DI/DO 0 / TM15D S_srcDI/DO 0

TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0

Description: Sets the signal source for terminal DI/DO 0 (X520.2) of terminal module 15 (TM15).

Note: Prerequisite: The DI/DO must be set as an output (p4028.0 = 1).

DI/DO: Bidirectional Digital Input/Output

p4031	BI: TB30 signal source for terminal DO 1 / TB30 S_src DO 1		
TB30	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9102
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DO 1 (X481.6) of the Terminal Board 30 (TB30).		
Note:	DO: Digital Output		

p4031	BI: TM31 signal source for terminal DO 1 / TM31 S_src DO 1		
TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9556
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the digital output DO 1 (X542.4, X542.5, X542.6) of terminal module 31 (TM31). Digital output 1 of TM31 is a relay output. If the signal at the binector input p4031 is low, then terminal COM 1 (X542.5) is connected to NC 1 (X542.4). This connection also matches the mechanical quiescent setting of the relay. If the signal at the binector input p4031 is high, then terminal COM 1 (X542.5) is connected to NO 1 (X542.6).		
Note:	DO: Digital Output NC: Normally Closed contact NO: Normally Open contact		

p4031	BI: TM15DI/DO signal source for terminal DI/DO 1 / TM15D S_srcDI/DO 1		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 1 (X520.3) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.1 = 1). DI/DO: Bidirectional Digital Input/Output		

p4032	BI: TB30 signal source for terminal DO 2 / TB30 S_src DO 2		
TB30	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9102
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DO 2 (X481.7) of the Terminal Board 30 (TB30).		
Note:	DO: Digital Output		

p4032	BI: TM15DI/DO signal source for terminal DI/DO 2 / TM15D S_srcDI/DO 2		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 2 (X520.4) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.2 = 1). DI/DO: Bidirectional Digital Input/Output		

p4033	BI: TB30 signal source for terminal DO 3 / TB30 S_src DO 3		
TB30	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1790, 9102
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DO 3 (X481.8) of the Terminal Board 30 (TB30).		
Note:	DO: Digital Output		

p4033	BI: TM15DI/DO signal source for terminal DI/DO 3 / TM15D S_srcDI/DO 3		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 3 (X520.5) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.3 = 1). DI/DO: Bidirectional Digital Input/Output		

p4034	BI: TM15DI/DO signal source for terminal DI/DO 4 / TM15D S_srcDI/DO 4		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 4 (X520.6) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.4 = 1). DI/DO: Bidirectional Digital Input/Output		

p4035	BI: TM15DI/DO signal source for terminal DI/DO 5 / TM15D S_srcDI/DO 5		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 5 (X520.7) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.5 = 1). DI/DO: Bidirectional Digital Input/Output		

p4036	BI: TM15DI/DO signal source for terminal DI/DO 6 / TM15D S_srcDI/DO 6		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 6 (X520.8) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.6 = 1). DI/DO: Bidirectional Digital Input/Output		
p4037	BI: TM15DI/DO signal source for terminal DI/DO 7 / TM15D S_srcDI/DO 7		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 7 (X520.9) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.7 = 1). DI/DO: Bidirectional Digital Input/Output		
p4038	BI: TM31 signal source for terminal DI/DO 8 / TM31 S_src DI/DO 8		
TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9560
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 8 (X541.2) of terminal module 31 (TM31).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.8 = 1). DI/DO: Bidirectional Digital Input/Output		
p4038	BI: TM41 signal source for terminal DI/DO 0 / TM41 S_src DI/DO 0		
TM41	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9661
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 0 (X521.1) of terminal module 41 (TM41).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.8 = 1). DI/DO: Bidirectional Digital Input/Output		
p4038	BI: TM15DI/DO signal source for terminal DI/DO 8 / TM15D S_srcDI/DO 8		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 8 (X521.2) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.8 = 1). DI/DO: Bidirectional Digital Input/Output		

p4039	BI: TM31 signal source for terminal DI/DO 9 / TM31 S_src DI/DO 9		
TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9560
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 9 (X541.3) of terminal module 31 (TM31).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.9 = 1). DI/DO: Bidirectional Digital Input/Output		

p4039	BI: TM41 signal source for terminal DI/DO 1 / TM41 S_src DI/DO 1		
TM41	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9661
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 1 (X541.2) of terminal module 41 (TM41).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.9 = 1). DI/DO: Bidirectional Digital Input/Output		

p4039	BI: TM15DI/DO signal source for terminal DI/DO 9 / TM15D S_srcDI/DO 9		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 9 (X521.3) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.9 = 1). DI/DO: Bidirectional Digital Input/Output		

p4040	BI: TM31 signal source for terminal DI/DO 10 / TM31 S_src DI/DO 10		
TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9562
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 10 (X541.4) of terminal module 31 (TM31).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.10 = 1). DI/DO: Bidirectional Digital Input/Output		

p4040	BI: TM41 signal source for terminal DI/DO 2 / TM41 S_src DI/DO 2		
TM41	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9662
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 2 (X521.3) of terminal module 41 (TM41).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.10 = 1). DI/DO: Bidirectional Digital Input/Output		


p4040	BI: TM15DI/DO signal source for terminal DI/DO 10 / TM15D S_srcDI/DO10		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 10 (X521.4) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.10 = 1). DI/DO: Bidirectional Digital Input/Output		

p4041	BI: TM31 signal source for terminal DI/DO 11 / TM31 S_src DI/DO11		
TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9562
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 11 (X541.5) of terminal module 31 (TM31).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.11 = 1). DI/DO: Bidirectional Digital Input/Output		

p4041	BI: TM41 signal source for terminal DI/DO 3 / TM41 S_src DI/DO 3		
TM41	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9662
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 3 (X521.4) of terminal module 41 (TM41).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.11 = 1). DI/DO: Bidirectional Digital Input/Output		

p4041	BI: TM15DI/DO signal source for terminal DI/DO 11 / TM15D S_srcDI/DO11		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 11 (X521.5) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.11 = 1). DI/DO: Bidirectional Digital Input/Output		

p4042	BI: TM15DI/DO signal source for terminal DI/DO 12 / TM15D S_srcDI/DO12		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 12 (X521.6) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.12 = 1). DI/DO: Bidirectional Digital Input/Output		

p4043	BI: TM15DI/DO signal source for terminal DI/DO 13 / TM15D S_srcDI/DO13		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 13 (X521.7) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.13 = 1). DI/DO: Bidirectional Digital Input/Output		
p4044	BI: TM15DI/DO signal source for terminal DI/DO 14 / TM15D S_srcDI/DO14		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 14 (X521.8) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.14 = 1). DI/DO: Bidirectional Digital Input/Output		
p4045	BI: TM15DI/DO signal source for terminal DI/DO 15 / TM15D S_srcDI/DO15		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9401
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 15 (X521.9) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.15 = 1). DI/DO: Bidirectional Digital Input/Output		
p4046	TM31 digital outputs, limit current / TM31 DO limit curr		
TM31	Can be changed: T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: 9560
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the limit for the total output voltage of terminals X541.1, X541.2, X541.3 and X541.4 (DI/DO 8 ... 11) of terminal module 31 (TM31).		
Values:	0: 0.1 A total current limit DI/DO 8 ... 11 1: 1.0 A total current limit DI/DO 8 ... 11		
Dependency:	Refer to: p4028		
Warning:	Since the sum of the output currents at terminals X541.1, X541.2, X541.3 and X541.4 is limited, an overcurrent or short circuit at one output terminal can cause a dip in the signal at the other terminals.		
			

r4047	TB30 digital outputs status / TB30 DO status		
TB30	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9102
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays the status of the digital outputs of the Terminal Board 30 (TB30).		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	DO 0 (X481.5)	High Low -
	01	DO 1 (X481.6)	High Low -
	02	DO 2 (X481.7)	High Low -
	03	DO 3 (X481.8)	High Low -
Note:	Inversion using p4048 has been taken into account. DO: Digital Output		

r4047	TM31 digital outputs status / TM31 DO status		
TM31	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9556, 9560, 9562
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays the status of the digital outputs of terminal module 31 (TM31).		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	DO 0 (X542.1 - 3)	High Low -
	01	DO 1 (X542.4 - 6)	High Low -
	08	DI/DO 8 (X541.2)	High Low -
	09	DI/DO 9 (X541.3)	High Low -
	10	DI/DO 10 (X541.4)	High Low -
	11	DI/DO 11 (X541.5)	High Low -
Note:	Inversion using p4048 has been taken into account. The setting of the DI/DO as either input or output is of no significance (p4028). DO: Digital Output DI/DO: Bidirectional Digital Input/Output		

r4047	TM41 digital outputs status / TM41 DO status		
TM41	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9556, 9560, 9562
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Displays the status of the digital outputs of terminal module 41 (TM41).		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	08	DI/DO 0 (X521.1)	High Low -
	09	DI/DO 1 (X521.2)	High Low -
	10	DI/DO 2 (X521.3)	High Low -
	11	DI/DO 3 (X521.4)	High Low -
Note:	Inversion using p4048 has been taken into account. The setting of the DI/DO as either input or output is of no significance (p4028). DO: Digital Output DI/DO: Bidirectional Digital Input/Output		

r4047 TM15DI/DO digital outputs, status / TM15D DO status

TM15DI_DO	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Unsigned32		Function diagram: 9400, 9401, 9402
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Displays the status of the digital outputs of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	High	Low	-
	01	DI/DO 1 (X520.3)	High	Low	-
	02	DI/DO 2 (X520.4)	High	Low	-
	03	DI/DO 3 (X520.5)	High	Low	-
	04	DI/DO 4 (X520.6)	High	Low	-
	05	DI/DO 5 (X520.7)	High	Low	-
	06	DI/DO 6 (X520.8)	High	Low	-
	07	DI/DO 7 (X520.9)	High	Low	-
	08	DI/DO 8 (X521.2)	High	Low	-
	09	DI/DO 9 (X521.3)	High	Low	-
	10	DI/DO 10 (X521.4)	High	Low	-
	11	DI/DO 11 (X521.5)	High	Low	-
	12	DI/DO 12 (X521.6)	High	Low	-
	13	DI/DO 13 (X521.7)	High	Low	-
	14	DI/DO 14 (X521.8)	High	Low	-
	15	DI/DO 15 (X521.9)	High	Low	-
	16	DI/DO 16 (X522.2)	High	Low	-
	17	DI/DO 17 (X522.3)	High	Low	-
	18	DI/DO 18 (X522.4)	High	Low	-
	19	DI/DO 19 (X522.5)	High	Low	-
	20	DI/DO 20 (X522.6)	High	Low	-
	21	DI/DO 21 (X522.7)	High	Low	-
	22	DI/DO 22 (X522.8)	High	Low	-
	23	DI/DO 23 (X522.9)	High	Low	-

Note: Inversion using p4048 has been taken into account.
The setting of the DI/DO as either input or output is of no significance (p4028).
DI/DO: Bidirectional Digital Input/Output

p4048 TB30 invert digital outputs / TB30 DO invert

TB30	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Unsigned32		Function diagram: 9102
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Setting to invert the signals at the digital outputs of the Terminal Board 30 (TB30).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DO 0 (X481.5)	Inverted	Not inverted	-
	01	DO 1 (X481.6)	Inverted	Not inverted	-
	02	DO 2 (X481.7)	Inverted	Not inverted	-
	03	DO 3 (X481.8)	Inverted	Not inverted	-

Note: DO: Digital Output

p4048		TM31 invert digital outputs / TM31 DO invert		
TM31	Can be changed: U, T			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 9556, 9560, 9562
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Setting to invert the signals at the digital outputs of terminal module 31 (TM31).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DO 0 (X542.1 - 3)	Inverted	Not inverted
	01	DO 1 (X542.4 - 6)	Inverted	Not inverted
	08	DI/DO 8 (X541.2)	Inverted	Not inverted
	09	DI/DO 9 (X541.3)	Inverted	Not inverted
	10	DI/DO 10 (X541.4)	Inverted	Not inverted
	11	DI/DO 11 (X541.5)	Inverted	Not inverted
Note:	DO: Digital Output DI/DO: Bidirectional Digital Input/Output			

p4048		TM41 invert digital outputs / TM41 DO invert		
TM41	Can be changed: U, T			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 9556, 9560, 9562
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Setting to invert the signals at the digital outputs of terminal module 41 (TM41).			
Bit field:	Bit	Signal name	1 signal	0 signal
	08	DI/DO 0 (X521.1)	Inverted	Not inverted
	09	DI/DO 1 (X521.2)	Inverted	Not inverted
	10	DI/DO 2 (X521.3)	Inverted	Not inverted
	11	DI/DO 3 (X521.4)	Inverted	Not inverted
Note:	DO: Digital Output DI/DO: Bidirectional Digital Input/Output			

p4048		TM17 invert digital inputs/outputs / TM17 DI/DO invert		
TM17	Can be changed: U, T			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Setting to invert the signals at the digital inputs/outputs of terminal module 17 (TM17).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI/DO 0 (X520.2)	Inverted	Not inverted
	01	DI/DO 1 (X520.3)	Inverted	Not inverted
	02	DI/DO 2 (X520.5)	Inverted	Not inverted
	03	DI/DO 3 (X520.6)	Inverted	Not inverted
	04	DI/DO 4 (X520.8)	Inverted	Not inverted
	05	DI/DO 5 (X520.9)	Inverted	Not inverted

06	DI/DO 6 (X521.2)	Inverted	Not inverted	-
07	DI/DO 7 (X521.3)	Inverted	Not inverted	-
08	DI/DO 8 (X521.8)	Inverted	Not inverted	-
09	DI/DO 9 (X521.9)	Inverted	Not inverted	-
10	DI/DO 10 (X522.2)	Inverted	Not inverted	-
11	DI/DO 11 (X522.3)	Inverted	Not inverted	-
12	DI/DO 12 (X522.5)	Inverted	Not inverted	-
13	DI/DO 13 (X522.6)	Inverted	Not inverted	-
14	DI/DO 14 (X522.8)	Inverted	Not inverted	-
15	DI/DO 15 (X522.9)	Inverted	Not inverted	-

Note: DI/DO: Bidirectional Digital Input/Output

p4048 TM15 invert digital inputs/outputs / TM15 DI/DO invert

TM15	Can be changed: U, T	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Min	Unit selection: -
	-	Factory setting
		0000 bin

Description: Setting to invert the signals at the digital inputs/outputs of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Inverted	Not inverted	-
	01	DI/DO 1 (X520.3)	Inverted	Not inverted	-
	02	DI/DO 2 (X520.4)	Inverted	Not inverted	-
	03	DI/DO 3 (X520.5)	Inverted	Not inverted	-
	04	DI/DO 4 (X520.6)	Inverted	Not inverted	-
	05	DI/DO 5 (X520.7)	Inverted	Not inverted	-
	06	DI/DO 6 (X520.8)	Inverted	Not inverted	-
	07	DI/DO 7 (X520.9)	Inverted	Not inverted	-
	08	DI/DO 8 (X521.2)	Inverted	Not inverted	-
	09	DI/DO 9 (X521.3)	Inverted	Not inverted	-
	10	DI/DO 10 (X522.4)	Inverted	Not inverted	-
	11	DI/DO 11 (X521.5)	Inverted	Not inverted	-
	12	DI/DO 12 (X521.6)	Inverted	Not inverted	-
	13	DI/DO 13 (X521.7)	Inverted	Not inverted	-
	14	DI/DO 14 (X521.8)	Inverted	Not inverted	-
	15	DI/DO 15 (X521.9)	Inverted	Not inverted	-
	16	DI/DO 16 (X522.2)	Inverted	Not inverted	-
	17	DI/DO 17 (X522.3)	Inverted	Not inverted	-
	18	DI/DO 18 (X522.4)	Inverted	Not inverted	-
	19	DI/DO 19 (X522.5)	Inverted	Not inverted	-
	20	DI/DO 20 (X522.6)	Inverted	Not inverted	-
	21	DI/DO 21 (X522.7)	Inverted	Not inverted	-
	22	DI/DO 22 (X522.8)	Inverted	Not inverted	-
	23	DI/DO 23 (X522.9)	Inverted	Not inverted	-

Note: DI/DO: Bidirectional Digital Input/Output

p4048		TM15DI/DO invert digital outputs / TM15D DO invert			
TM15DI_DO	Can be changed: U, T	Dynamic index: -	Access level: 1		
	Data type: Unsigned32		Function diagram: 9400, 9401, 9402		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Setting to invert the signals at the digital outputs of terminal module 15 (TM15).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Inverted	Not inverted	-
	01	DI/DO 1 (X520.3)	Inverted	Not inverted	-
	02	DI/DO 2 (X520.4)	Inverted	Not inverted	-
	03	DI/DO 3 (X520.5)	Inverted	Not inverted	-
	04	DI/DO 4 (X520.6)	Inverted	Not inverted	-
	05	DI/DO 5 (X520.7)	Inverted	Not inverted	-
	06	DI/DO 6 (X520.8)	Inverted	Not inverted	-
	07	DI/DO 7 (X520.9)	Inverted	Not inverted	-
	08	DI/DO 8 (X521.2)	Inverted	Not inverted	-
	09	DI/DO 9 (X521.3)	Inverted	Not inverted	-
	10	DI/DO 10 (X521.4)	Inverted	Not inverted	-
	11	DI/DO 11 (X521.5)	Inverted	Not inverted	-
	12	DI/DO 12 (X521.6)	Inverted	Not inverted	-
	13	DI/DO 13 (X521.7)	Inverted	Not inverted	-
	14	DI/DO 14 (X521.8)	Inverted	Not inverted	-
	15	DI/DO 15 (X521.9)	Inverted	Not inverted	-
	16	DI/DO 16 (X522.2)	Inverted	Not inverted	-
	17	DI/DO 17 (X522.3)	Inverted	Not inverted	-
	18	DI/DO 18 (X522.4)	Inverted	Not inverted	-
	19	DI/DO 19 (X522.5)	Inverted	Not inverted	-
	20	DI/DO 20 (X522.6)	Inverted	Not inverted	-
	21	DI/DO 21 (X522.7)	Inverted	Not inverted	-
	22	DI/DO 22 (X522.8)	Inverted	Not inverted	-
	23	DI/DO 23 (X522.9)	Inverted	Not inverted	-
Note:	DI/DO: Bidirectional Digital Input/Output				

p4049		TM17 digital inputs/outputs, set the mode / TM17 DI/DO mode			
TM17	Can be changed: T	Dynamic index: -	Access level: 2		
	Data type: Unsigned32		Function diagram: -		
	P-Group: Commands	Units group: -	Unit selection: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the mode of the DI/DO of terminal module 17 (TM17).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	I/O with time	I/O	-
	01	DI/DO 1 (X520.3)	I/O with time	I/O	-
	02	DI/DO 2 (X520.5)	I/O with time	I/O	-
	03	DI/DO 3 (X520.6)	I/O with time	I/O	-
	04	DI/DO 4 (X520.8)	I/O with time	I/O	-
	05	DI/DO 5 (X520.9)	I/O with time	I/O	-

06	DI/DO 6 (X521.2)	I/O with time	I/O	-
07	DI/DO 7 (X521.3)	I/O with time	I/O	-
08	DI/DO 8 (X521.8)	I/O with time	I/O	-
09	DI/DO 9 (X521.9)	I/O with time	I/O	-
10	DI/DO 10 (X522.2)	I/O with time	I/O	-
11	DI/DO 11 (X522.3)	I/O with time	I/O	-
12	DI/DO 12 (X522.5)	I/O with time	I/O	-
13	DI/DO 13 (X522.6)	I/O with time	I/O	-
14	DI/DO 14 (X522.8)	I/O with time	I/O	-
15	DI/DO 15 (X522.9)	I/O with time	I/O	-

Note: DI/DO: Bidirectional Digital Input/Output

p4049 TM15 digital inputs/outputs, set the mode / TM15 DI/DO mode

TM15	Can be changed: T	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Min	Units group: -
	-	Unit selection: -
	Max	Factory setting
	-	0000 bin

Description: Sets the mode of the DI/DOs of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	I/O with time	I/O	-
	01	DI/DO 1 (X520.3)	I/O with time	I/O	-
	02	DI/DO 2 (X520.4)	I/O with time	I/O	-
	03	DI/DO 3 (X520.5)	I/O with time	I/O	-
	04	DI/DO 4 (X520.6)	I/O with time	I/O	-
	05	DI/DO 5 (X520.7)	I/O with time	I/O	-
	06	DI/DO 6 (X520.8)	I/O with time	I/O	-
	07	DI/DO 7 (X520.9)	I/O with time	I/O	-
	08	DI/DO 8 (X521.2)	I/O with time	I/O	-
	09	DI/DO 9 (X521.3)	I/O with time	I/O	-
	10	DI/DO 10 (X522.4)	I/O with time	I/O	-
	11	DI/DO 11 (X521.5)	I/O with time	I/O	-
	12	DI/DO 12 (X521.6)	I/O with time	I/O	-
	13	DI/DO 13 (X521.7)	I/O with time	I/O	-
	14	DI/DO 14 (X521.8)	I/O with time	I/O	-
	15	DI/DO 15 (X521.9)	I/O with time	I/O	-
	16	DI/DO 16 (X522.2)	I/O with time	I/O	-
	17	DI/DO 17 (X522.3)	I/O with time	I/O	-
	18	DI/DO 18 (X522.4)	I/O with time	I/O	-
	19	DI/DO 19 (X522.5)	I/O with time	I/O	-
	20	DI/DO 20 (X522.6)	I/O with time	I/O	-
	21	DI/DO 21 (X522.7)	I/O with time	I/O	-
	22	DI/DO 22 (X522.8)	I/O with time	I/O	-
	23	DI/DO 23 (X522.9)	I/O with time	I/O	-

Note: DI/DO: Bidirectional Digital Input/Output

r4052[0...1] TB30 analog inputs, actual input voltage / TB30 AI input_U

TB30	Can be changed: -	Access level: 1
	Data type: Floating Point	Dynamic index: -
	P-Group: Terminals	Function diagram: 9104
	Min	Units group: -
	- [V]	Unit selection: -
	Max	Factory setting
	- [V]	- [V]


Description: Displays the actual input voltage at the analog inputs of the Terminal Board 30 (TB30).

Index: [0] = AI 0 (X482.1/X482.2)
[1] = AI 1 (X482.3/X482.4)

Note: AI: Analog Input

r4052[0...1]	TM31 analog inputs, actual input voltage/current / TM31 AI input_U/I		
TM31	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the actual input voltage in V when set as voltage input. Displays the actual input current in mA when set as current input and with the load resistor switched-in.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Dependency:	The type of analog input AI x (voltage or current input) is set using p4056. Refer to: r4056, p4056		
Note:	AI: Analog Input		
r4052[0...0]	TB41 analog inputs, actual input voltage / TM41 AI input_U		
TM41	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the actual input voltage in V.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	AI: Analog Input		
p4053[0...1]	TB30 analog inputs, smoothing time constant / TB30 AI T_smooth		
TB30	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the smoothing time constant of the 1st-order low pass filter for the analog inputs of the Terminal Board 30 (TB30).		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Note:	AI: Analog Input		
p4053[0...1]	TM31 analog inputs, smoothing time constant / TM31 AI T_smooth		
TM31	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the smoothing time constant of the 1st-order low pass filter for the analog inputs of terminal module 31 (TM31).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Note:	AI: Analog Input		

p4053[0...0]	TM41 analog inputs, smoothing time constant / TM41 AI T_smooth		
TM41	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the smoothing time constant of the 1st-order low pass filter for the analog inputs of terminal module 41 (TM41).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	AI: Analog Input		
r4055[0...1]	CO: TB30 analog inputs, actual value in percent / TB30 AI value in %		
TB30	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 1790, 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the currently referred input value of the analog inputs of Terminal Board 30 (TB30). When interconnected, the signals are referred to the reference quantities p200x and p205x.		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Note:	AI: Analog Input		
r4055[0...1]	CO: TB31 analog inputs, actual value in percent / TM31 AI value in %		
TM31	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 1840, 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the currently referred input value of the analog inputs of terminal module 31 (TM31). When interconnected, the signals are referred to the reference quantities p200x and p205x.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Note:	AI: Analog Input		
r4055[0...0]	CO: TB41 analog inputs, actual value in percent / TM41 AI value in %		
TM41	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 1840, 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the currently referred input value of the analog inputs of terminal module 41 (TM41). When interconnected, the signals are referred to the reference quantities p200x and p205x.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	AI: Analog Input		

r4056[0...1]	TB30 analog inputs, type / TB30 AI type		
TB30	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min 4	Max 4	Factory setting 4
Description:	Displays the type of analog inputs.		
Values:	4: Bipolar voltage input (-10 V ... +10 V)		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
p4056[0...1]	TM31 analog inputs, type / TM31 AI type		
TM31	Can be changed: U, T	Dynamic index: -	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: 9566, 9568
	P-Group: Terminals		Unit selection: -
	Min 0	Max 5	Factory setting 4
Description:	Sets the type of analog inputs of terminal module 31 (TM31). p4056[x] = 0, 4 correspond to a voltage input (r4052, p4057, p4059 are displayed in V). p4056[x] = 2, 3, 5 correspond to a current input (r4052, p4057, p4059 are displayed in mA). In addition, the associated switch S5 must be switched. For a voltage input, S5.1 or S5.2 must be switched to setting V. For a current input, S5.1 and S5.2 must be switched into setting I (load resistor = 250 Ohm is switched-in).		
Values:	0: Unipolar voltage input (0 V ... +10 V) 2: Unipolar current input (0 mA ... +20 mA) 3: Unipolar current input monitored (4 mA ... +20 mA) 4: Bipolar voltage input (-10 V ... +10 V) 5: Bipolar current input (-20 mA ... +20 mA)		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Warning:	The maximum voltage difference between the analog input terminals AI+, AI- and the ground of the TM31 (X520.6, X530.3) may not exceed 35 V. For operation with the load resistor switched-in, the voltage between the differential inputs AI+ and AI- may not exceed 15 V or the impressed current of 60 mA; if this is not carefully observed, the input will be damaged.		
			
Notice:	For use as voltage input, switch S500 must be set to 0 for the input involved. Switch S500 is located on the front panel of the TM31 above terminal block X521.		
Note:	When changing p4056, the parameters of the normalization characteristic (p4057, p4058, p4059, p4060) are overwritten with the following default values: For p4056 = 0, 4, p4057 is set to 0.0 V, p4058 to 0.0 %, p4059 to 10.0 V and p4060 to 100.0 %. For p4056 = 2, 5, p4057 is set to 0.0 mA, p4058 to 0.0 %, p4059 to 20.0 mA and p4060 to 100.0 %. For p4056 = 3, p4057 is set to 4.0 mA, p4058 to 0.0 %, p4059 to 20.0 mA and p4060 to 100.0 %.		
r4056	TM41 analog input, type / TM41 AI type		
TM41	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Terminals		Unit selection: -
	Min 4	Max 4	Factory setting 4
Description:	Displays the type of the analog input.		
Values:	4: Bipolar voltage input (-10 V ... +10 V)		

p4057[0...1]	TB30 analog inputs, characteristic value x1 / TB30 AI char x1		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -11.000 [V]	Max 11.000 [V]	Factory setting 0.000 [V]
Description:	Sets the normalization characteristic for the analog inputs of Terminal Board 30 (TB30). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the x coordinate (input voltage in V) of the 1st value pair of the characteristic.		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Note:	The parameters for the characteristic do not limit.		
p4057[0...1]	TM31 analog inputs, characteristic value x1 / TM31 AI char x1		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000
Description:	Sets the normalization characteristic for the analog inputs of terminal module 31 (TM31). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the x coordinate (input voltage in V or input current in mA) of the 1st value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Dependency:	The units of this parameter (V or mA) depend on the analog input type. Refer to: r4056, p4056		
Notice:	This parameter is automatically overwritten when the analog input type (p4056) is modified.		
Note:	The parameters for the characteristic do not limit.		
p4057[0...0]	TM41 analog input, characteristic value x1 / TM41 AI char x1		
TM41	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000
Description:	Sets the normalization characteristic for the analog inputs of terminal module 41 (TM41). The normalization characteristic for the analog input is defined using 2 points. This parameter specifies the x coordinate (input voltage in V or input current in mA) of the 1st value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	The parameters for the characteristic do not limit.		

p4058[0...1]	TB30 analog inputs, characteristic value y1 / TB30 AI char y1		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 0.00 [%]
Description:	Sets the normalization characteristic for the analog inputs of Terminal Board 30 (TB30). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the y coordinate (percentage) of the 1st value pair of the characteristic.		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Note:	The parameters for the characteristic do not limit.		
p4058[0...1]	TM31 analog inputs, characteristic value y1 / TM31 AI char y1		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 0.00 [%]
Description:	Sets the normalization characteristic for the analog inputs of terminal module 31 (TM31). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the y coordinate (percentage) of the 1st value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Notice:	This parameter is automatically overwritten when the analog input type (p4056) is modified.		
Note:	The parameters for the characteristic do not limit.		
p4058[0...0]	TM41 analog input, characteristic value y1 / TM41 AI char y1		
TM41	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 0.00 [%]
Description:	Sets the normalization characteristic for the analog input of terminal module 41 (TM41). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the y coordinate (percentage) of the 1st value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	The parameters for the characteristic do not limit.		

p4059[0...1]	TB30 analog inputs, characteristic value x2 / TB30 AI char x2		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -11.000 [V]	Max 11.000 [V]	Factory setting 10.000 [V]
Description:	Sets the normalization characteristic for the analog inputs of Terminal Board 30 (TB30). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the x coordinate (input voltage in V) of the 2nd value pair of the characteristic.		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Note:	The parameters for the characteristic do not limit.		
p4059[0...1]	TM31 analog inputs, characteristic value x2 / TM31 AI char x2		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 10.000
Description:	Sets the normalization characteristic for the analog inputs of terminal module 31 (TM31). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the x coordinate (input voltage in V or input current in mA) of the 2nd value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Dependency:	The units of this parameter (V or mA) depend on the analog input type. Refer to: r4056, p4056		
Notice:	This parameter is automatically overwritten when the analog input type (p4056) is modified.		
Note:	The parameters for the characteristic do not limit.		
p4059[0...0]	TM41 analog input, characteristic value x2 / TM41 AI char x2		
TM41	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 10.000
Description:	Sets the normalization characteristic for the analog input of terminal module 41 (TM41). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the x coordinate (input voltage in V or input current in mA) of the 2nd value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	The parameters for the characteristic do not limit.		

p4060[0...1]	TB30 analog inputs, characteristic value y2 / TB30 AI char y2		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalization characteristic for the analog inputs of Terminal Board 30 (TB30). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the y coordinate (percentage) of the 2nd value pair of the characteristic.		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Note:	The parameters for the characteristic do not limit.		
p4060[0...1]	TM31 analog inputs, characteristic value y2 / TM31 AI char y2		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalization characteristic for the analog inputs of terminal module 31 (TM31). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the y coordinate (percentage) of the 2nd value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Notice:	This parameter is automatically overwritten when the analog input type (p4056) is modified.		
Note:	The parameters for the characteristic do not limit.		
p4060[0...0]	TM41 analog input, characteristic value y2 / TM41 AI char y2		
TM41	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalization characteristic for the analog input of terminal module 41 (TM41). The normalization characteristic for the analog inputs is defined using two points. This parameter specifies the y coordinate (percentage) of the 2nd value pair of the characteristic.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Note:	The parameters for the characteristic do not limit.		
p4061[0...1]	TM31 analog inputs, wire breakage monit. response threshold / TM31 WireBrkThresh		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.00 [mA]	Max 20.00 [mA]	Factory setting 2.00 [mA]
Description:	Sets the response threshold for wire-breakage monitoring of the analog inputs of terminal module 31 (TM31).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		

Dependency: The wire breakage monitoring is active for the following type of analog input: p4056[x] = 3 (current input unipolar, monitored 4 mA ... 20 mA).
Refer to: r4056, p4056

p4062[0...1]	TM31 analog inputs, wire breakage monitoring, delay time / TM31 wirebrk t_del		
TM31	Can be changed: U, T		Access level: 2
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0 [ms]	Max 1000 [ms]	Factory setting 100 [ms]

Description: Sets the delay time for wire-breakage monitoring of the analog inputs on terminal module 31 (TM31).

Index:
[0] = AI 0 (X521.1/X521.2, S5.0)
[1] = AI 1 (X521.3/X521.4, S5.1)

p4063[0...1]	TB30 analog inputs offset / TB30 AI offset		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000 [V]	Max 20.000 [V]	Factory setting 0.000 [V]

Description: Sets the offset for the analog inputs of Terminal Board 30 (TB30).
The offset is added to the input signal before the normalization characteristic.

Index:
[0] = AI 0 (X482.1/X482.2)
[1] = AI 1 (X482.3/X482.4)

p4063[0...1]	TM31 analog inputs offset / TM31 AI offset		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000

Description: Sets the offset for the analog inputs of terminal module 31 (TM31).
The offset is added to the input signal before the normalization characteristic.

Index:
[0] = AI 0 (X521.1/X521.2, S5.0)
[1] = AI 1 (X521.3/X521.4, S5.1)

p4063[0...0]	TM41 analog input, offset / TM41 AI offset		
TM41	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000

Description: Sets the offset for the analog input of terminal module 41 (TM41).
The offset is added to the input signal before the normalization characteristic.

Index:
[0] = AI 0 (X521.1/X521.2, S5.0)

p4066[0...1]	TB30 analog inputs, activate absolute value generation / TB30 AI absVal act		
TB30	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Activates the absolute value generation for the analog input signals of the Terminal Board 30 (TB30).		
Values:	0: No absolute value generation 1: Absolute value generation switched-in		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
p4066[0...1]	TM31 analog inputs, activate absolute value generation / TM31 AI absVal act		
TM31	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Activates the absolute value generation for the analog input signals of terminal module 31 (TM31).		
Values:	0: No absolute value generation 1: Absolute value generation switched-in		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
p4066[0...0]	TM41 analog input, activate absolute value generation / TM41 AI absVal act		
TM41	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Activates the absolute value generation of the analog input signal of terminal module 41 (TM41).		
Values:	0: No absolute value generation 1: Absolute value generation switched-in		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
p4067[0...1]	BI: TB30 analog inputs, signal source for inversion / TB30 AI invert		
TB30	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to invert the analog input signals of the Terminal Board 30 (TB30).		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		

p4067[0...1]	BI: TM31 analog inputs, signal source for inversion / TM31 AI invert		
TM31	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to invert the analog inputs signals of terminal module 31 (TM31).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0), [1] = AI 1 (X521.3/X521.4, S5.1)		
p4067[0...0]	BI: TM41 analog input, signal source for inversion / TM41 AI invert		
TM41	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to invert the analog input signal of terminal module 41 (TM41).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
p4068[0...1]	TB30 analog inputs, window to suppress noise / TB30 AI window		
TB30	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 20.00 [%]	Factory setting 0.00 [%]
Description:	Sets the noise suppression window for the analog inputs of Terminal Board 30 (TB30). Changes less than the window are suppressed.		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
p4068[0...1]	TM31 analog inputs, window to suppress noise / TM31 AI window		
TM31	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 20.00 [%]	Factory setting 0.00 [%]
Description:	Sets the window for noise suppression for the analog inputs of terminal module 31 (TM31). Changes less than the window are suppressed.		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
p4068[0...0]	TM41 analog input, window to suppress noise / TM41 AI window		
TM41	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 20.00 [%]	Factory setting 0.00 [%]
Description:	Sets the noise suppression window for the analog input of terminal module 41 (TM41). Changes less than the window are suppressed.		

Index: [0] = AI 0 (X521.1/X521.2, S5.0)

p4069[0...1]	BI: TB30 analog inputs, signal source for enable / TB30 AI enable		
TB30	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for enabling the analog inputs of the Terminal Board 30 (TB30).		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		

p4069[0...1]	BI: TM31 analog inputs, signal source for enable / TM31 AI enable		
TM31	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the enable signal of the analog inputs of terminal module 31 (TM31).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		

p4069[0...0]	BI: TM41 analog input, signal source for enable / TM41 AI enable		
TM41	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the enable signal of the analog input of terminal module 41 (TM41).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		

p4071[0...1]	CI: TB30 analog outputs, signal source / TB30 AO sig_source		
TB30	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1790, 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the analog outputs of the Terminal Board 30 (TB30).		
Index:	[0] = AO 0 (X482.5/X482.6), [1] = AO 1 (X482.7/X482.8)		
Note:	AO: Analog Output		

p4071[0...1]	CI: TM31 analog outputs, signal source / TM31 AO sig_source		
TM31	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the analog outputs of terminal module 31 (TM31).		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3), [1] = AO 1 (X522.4, X522.5, X522.6)		

Note: AO: Analog Output

r4072[0...1] TB30 analog outputs, output value actually referred / TB30 AO output_val			
TB30	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the actual referred output value of the analog outputs of the Terminal Board 30 (TB30).		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
r4072[0...1] TM31 analog outputs, output value actually referred / TM31 AO output_val			
TM31	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the actual referred output value of the analog outputs of terminal module 31 (TM31).		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
p4073[0...1] TB30 analog outputs, smoothing time constant / TB30 AO T_smooth			
TB30	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the smoothing time constant of the 1st order low pass filter for the analog outputs of the Terminal Board 30 (TB30).		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
p4073[0...1] TM31 analog outputs, smoothing time constant / TM31 AO T_smooth			
TM31	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 0.0 [ms]
Description:	Sets the smoothing time constant of the 1st-order low pass filter for the analog outputs of terminal module 31 (TM31).		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
r4074[0...1] TB30 analog outputs, actual output voltage / TB30 AO U_smooth			
TB30	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual output voltage at the analog outputs of the Terminal Board 30 (TB30).		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		

r4074[0...1]	TM31 analog outputs, actual output voltage/current / TM31 AO U/I_output		
TM31	Can be changed: -		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual output voltage in V when set as voltage output. Displays the actual output voltage in mA when set as current output.		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
Dependency:	The type of the analog output AO x (voltage or current output) is set using p4076. Refer to: r4076, p4076		
Note:	AO: Analog Output		
p4075[0...1]	TB30 analog outputs, activate absolute value generation / TB30 AO absVal act		
TB30	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Activates the absolute value generation for the analog outputs of the Terminal Board 30 (TB30).		
Values:	0: No absolute value generation 1: Absolute value generation switched-in		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
p4075[0...1]	TM31 analog outputs, activate absolute value generation / TM31 AO absVal act		
TM31	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Activates the absolute value generation for the analog outputs of terminal module 31 (TM31).		
Values:	0: No absolute value generation 1: Absolute value generation switched-in		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
r4076[0...1]	TB30 analog outputs, type / TB30 AO type		
TB30	Can be changed: -		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	4	4	4
Description:	Displays the type of analog outputs of the Terminal Board 30 (TB30).		
Values:	4: Voltage output (-10 V ... +10 V)		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		

p4076[0...1]		TM31 analog outputs, type / TM31 AO type		
TM31	Can be changed: U, T			Access level: 1
	Data type: Integer16	Dynamic index: -		Function diagram: 9572
	P-Group: Terminals	Units group: -		Unit selection: -
	Min 0	Max 4		Factory setting 4
Description:	Sets the type of analog outputs of terminal module 31 (TM31). p4076[x] = 1, 4 correspond to a voltage output (p4074, p4078, p4080, p4083 are displayed in V). p4076[x] = 0, 2, 3 correspond to a current output (p4074, p4078, p4080, p4083 are displayed in mA).			
Values:	0: Current output (0 mA ... +20 mA) 1: Voltage output (0 V ... +10 V) 2: Current output (4 mA ... +20 mA) 3: Current output (-20 mA ... +20 mA) 4: Voltage output (-10 V ... +10 V)			
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)			
Dependency:	Refer to: p4077, p4078, p4079, p4080			
Note:	When changing p4076, the parameters of the normalization characteristic (p4077, p4078, p4079, p4080) are overwritten with the following default values: For p4076 = 0, 3, p4077 is set to 0.0 %, p4078 to 0.0 mA, p4079 to 100.0 % and p4080 to 20.0 mA. For p4076 = 1, 4, p4077 is set to 0.0 %, p4078 to 0.0 V, p4079 to 100.0 % and p4080 to 10.0 V. For p4076 = 2, p4077 is set to 0.0 %, p4078 to 4.0 mA, p4079 to 100.0 % and p4080 to 20.0 mA.			
p4077[0...1]		TB30 analog outputs, characteristic value x1 / TB30 AO char x1		
TB30	Can be changed: U, T			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 9106
	P-Group: Terminals	Units group: -		Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]		Factory setting 0.00 [%]
Description:	Sets the normalization characteristic for the analog outputs of Terminal Board 30 (TB30). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the x coordinate (percentage) of the 1st value pair of the characteristic.			
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)			
Note:	The parameters for the characteristic do not limit.			
p4077[0...1]		TM31 analog outputs, characteristic value x1 / TM31 AO char x1		
TM31	Can be changed: U, T			Access level: 2
	Data type: Floating Point	Dynamic index: -		Function diagram: 9572
	P-Group: Terminals	Units group: -		Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]		Factory setting 0.00 [%]
Description:	Sets the normalization characteristic for the analog outputs of terminal module 31 (TM31). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the x coordinate (percentage) of the 1st value pair of the characteristic.			
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)			
Dependency:	The units of this parameter (V or mA) depend on the analog input type. Refer to: r4076, p4076			
Notice:	This parameter is automatically overwritten when the analog output type is changed (p4076).			
Note:	This parameter is automatically overwritten if p4076 (type of analog output) is changed. The parameters for the characteristic do not limit.			

p4078[0...1]	TB30 analog outputs, characteristic value y1 / TB30 AO char y1		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -11.000 [V]	Max 11.000 [V]	Factory setting 0.000 [V]
Description:	Sets the normalization characteristic for the analog outputs of Terminal Board 30 (TB30). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the y coordinate (output voltage in V) of the 1st value pair of the characteristic.		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
Note:	The parameters for the characteristic do not limit.		
p4078[0...1]	TM31 analog outputs, characteristic value y1 / TM31 AO char y1		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000 [V]	Max 20.000 [V]	Factory setting 0.000 [V]
Description:	Sets the normalization characteristic for the analog outputs of terminal module 31 (TM31). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the y coordinate (output voltage in V or output current in mA) of the 1st value pair of the characteristic.		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
Dependency:	The units of this parameter (V or mA) depend on the analog input type. Refer to: r4076, p4076		
Notice:	This parameter is automatically overwritten when the analog output type is changed (p4076).		
Note:	This parameter is automatically overwritten if p4076 (type of analog output) is changed. The parameters for the characteristic do not limit.		
p4079[0...1]	TB30 analog outputs, characteristic value x2 / TB30 AO char x2		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalization characteristic for the analog outputs of Terminal Board 30 (TB30). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the x coordinate (percentage) of the 2nd value pair of the characteristic.		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
Note:	The parameters for the characteristic do not limit.		

p4079[0...1]	TM31 analog outputs, characteristic value x2 / TM31 AO char x2		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -1000.00 [%]	Max 1000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the normalization characteristic for the analog outputs of terminal module 31 (TM31). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the x coordinate (percentage) of the 2nd value pair of the characteristic.		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
Dependency:	Refer to: r4076, p4076		
Notice:	This parameter is automatically overwritten when the analog output type is changed (p4076).		
Note:	This parameter is overwritten if p4076 (type of analog output) is changed. The parameters for the characteristic do not limit.		
p4080[0...1]	TB30 analog outputs, characteristic value y2 / TB30 AO char y2		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -11.000 [V]	Max 11.000 [V]	Factory setting 10.000 [V]
Description:	Sets the normalization characteristic for the analog outputs of Terminal Board 30 (TB30). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the y coordinate (output voltage in V) of the 2nd value pair of the characteristic.		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
Note:	The parameters for the characteristic do not limit.		
p4080[0...1]	TM31 analog outputs, characteristic value y2 / TM31 AO char y2		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000 [V]	Max 20.000 [V]	Factory setting 10.000 [V]
Description:	Sets the normalization characteristic for the analog outputs of terminal module 31 (TM31). The normalization characteristic for the analog outputs is defined using 2 points. This parameter specifies the y coordinate (output voltage in V or output current in mA) of the 2nd value pair of the characteristic.		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
Dependency:	The units of this parameter (V or mA) depend on the analog input type. Refer to: r4076, p4076		
Notice:	This parameter is automatically overwritten when the analog output type is changed (p4076).		
Note:	This parameter is overwritten if p4076 (type of analog output) is changed. The parameters for the characteristic do not limit.		

p4082[0...1]	BI: TB30 analog outputs, signal source for inversion / TB30 AO invert		
TB30	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for inverting the analog output signals of the Terminal Board 30 (TB30).		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
p4082[0...1]	BI: TM31 analog outputs, signal source for inversion / TM31 AO invert		
TM31	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to invert the analog output signals of terminal module 31 (TM31).		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
p4083[0...1]	TB30 analog outputs, offset / TB30 AO offset		
TB30	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9106
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -10.000	Max 10.000	Factory setting 0.000
Description:	Sets the offset for the analog outputs of Terminal Board 30 (TB30). The offset is added to the output signal after the normalization characteristic.		
Index:	[0] = AO 0 (X482.5/X482.6) [1] = AO 1 (X482.7/X482.8)		
p4083[0...1]	TM31 analog outputs, offset / TM31 AO offset		
TM31	Can be changed: U, T		Access level: 1
	Data type: Floating Point	Dynamic index: -	Function diagram: 9572
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000
Description:	Sets the offset for the analog outputs of terminal module 31 (TM31). The offset is added to the output signal after the normalization characteristic.		
Index:	[0] = AO 0 (X522.1, X522.2, X522.3) [1] = AO 1 (X522.4, X522.5, X522.6)		
Dependency:	The units of this parameter (V or mA) depend on the analog input type. Refer to: r4076, p4076		
Note:	This means, for example, the offset of a downstream isolating amplifier can be compensated.		

p4086	BI: TM15DI/DO signal source for terminal DI/DO 16 / TM15D S_srcDI/DO16		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9402
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 16 (X522.2) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.16 = 1). DI/DO: Bidirectional Digital Input/Output		
p4087	BI: TM15DI/DO signal source for terminal DI/DO 17 / TM15D S_srcDI/DO17		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9402
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 17 (X522.3) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.17 = 1). DI/DO: Bidirectional Digital Input/Output		
p4088	BI: TM15DI/DO signal source for terminal DI/DO 18 / TM15D S_srcDI/DO18		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9402
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 18 (X522.4) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.18 = 1). DI/DO: Bidirectional Digital Input/Output		
p4089	BI: TM15DI/DO signal source for terminal DI/DO 19 / TM15D S_srcDI/DO19		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9402
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 19 (X522.5) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.19 = 1). DI/DO: Bidirectional Digital Input/Output		
p4090	BI: TM15DI/DO signal source for terminal DI/DO 20 / TM15D S_srcDI/DO20		
TM15DI_DO	Can be changed: U, T		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9402
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for terminal DI/DO 20 (X522.6) of terminal module 15 (TM15).		
Note:	Prerequisite: The DI/DO must be set as an output (p4028.20 = 1). DI/DO: Bidirectional Digital Input/Output		

p4091	BI: TM15DI/DO signal source for terminal DI/DO 21 / TM15D S_srcDI/DO21			
TM15DI_DO	Can be changed: U, T			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 9402
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0
Description:	Sets the signal source for terminal DI/DO 21 (X522.7) of terminal module 15 (TM15).			
Note:	Prerequisite: The DI/DO must be set as an output (p4028.21 = 1). DI/DO: Bidirectional Digital Input/Output			
p4092	BI: TM15DI/DO signal source for terminal DI/DO 22 / TM15D S_srcDI/DO22			
TM15DI_DO	Can be changed: U, T			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 9402
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0
Description:	Sets the signal source for terminal DI/DO 22 (X522.8) of terminal module 15 (TM15).			
Note:	Prerequisite: The DI/DO must be set as an output (p4028.22 = 1). DI/DO: Bidirectional Digital Input/Output			
p4093	BI: TM15DI/DO signal source for terminal DI/DO 23 / TM15D S_srcDI/DO23			
TM15DI_DO	Can be changed: U, T			Access level: 1
	Data type: Unsigned32	Dynamic index: -		Function diagram: 9402
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0
Description:	Sets the signal source for terminal DI/DO 23 (X522.9) of terminal module 15 (TM15).			
Note:	Prerequisite: The DI/DO must be set as an output (p4028.23 = 1). DI/DO: Bidirectional Digital Input/Output			
p4095	TB30 digital inputs, simulation mode / TB30 DI sim_mode			
TB30	Can be changed: U, T			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 1790, 9100
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Sets the simulation mode for the digital inputs of the Terminal Board 30 (TB30).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI 0 (X481.1)	Simulation	Terminal eval.
	01	DI 1 (X481.2)	Simulation	Terminal eval.
	02	DI 2 (X481.3)	Simulation	Terminal eval.
	03	DI 3 (X481.4)	Simulation	Terminal eval.
				FP
				-
				-
				-
				-
Dependency:	The setpoint for the input signals is specified using p4096. Refer to: p4096			
Note:	This parameter is not saved when data is backed-up (p0971, p0977). DI: Digital input			

p4095 TM31 digital inputs, simulation mode / TM31 DI sim_mode

TM31	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1840, 9550, 9552, 9560, 9562
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0000 bin

Description: Sets the simulation mode for the digital inputs of terminal module 31 (TM31).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X520.1)	Simulation	Terminal eval.	-
	01	DI 1 (X520.2)	Simulation	Terminal eval.	-
	02	DI 2 (X520.3)	Simulation	Terminal eval.	-
	03	DI 3 (X520.4)	Simulation	Terminal eval.	-
	04	DI 4 (X530.1)	Simulation	Terminal eval.	-
	05	DI 5 (X530.2)	Simulation	Terminal eval.	-
	06	DI 6 (X530.3)	Simulation	Terminal eval.	-
	07	DI 7 (X530.4)	Simulation	Terminal eval.	-
	08	DI/DO 8 (X541.2)	Simulation	Terminal eval.	-
	09	DI/DO 9 (X541.3)	Simulation	Terminal eval.	-
	10	DI/DO 10 (X541.4)	Simulation	Terminal eval.	-
	11	DI/DO 11 (X541.5)	Simulation	Terminal eval.	-

Dependency: The setpoint for the input signals is specified using p4096.

Refer to: p4096

Note: This parameter is not saved when data is backed-up (p0971, p0977).

DI: Digital input

DI/DO: Bidirectional Digital Input/Output

p4095 TM41 digital inputs, simulation mode / TM41 DI sim_mode

TM41	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0000 bin

Description: Sets the simulation mode for the digital inputs of terminal module 41 (TM41).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X522.1)	Simulation	Terminal eval.	-
	01	DI 1 (X522.2)	Simulation	Terminal eval.	-
	02	DI 2 (X522.3)	Simulation	Terminal eval.	-
	03	DI 3 (X522.4)	Simulation	Terminal eval.	-
	08	DI/DO 0 (X521.1)	Simulation	Terminal eval.	-
	09	DI/DO 1 (X521.2)	Simulation	Terminal eval.	-
	10	DI/DO 2 (X521.3)	Simulation	Terminal eval.	-
	11	DI/DO 3 (X521.4)	Simulation	Terminal eval.	-

Dependency: The setpoint for the input signals is specified using p4096.

Refer to: p4096

Note: This parameter is not saved when data is backed-up (p0971, p0977).

DI: Digital input

DI/DO: Bidirectional Digital Input/Output

p4095 TM15DI/DO digital inputs, simulation mode / TM15D DI sim_mode

TM15DI_DO	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9400, 9401, 9402
	P-Group: Terminals	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Sets the simulation mode for the digital inputs of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Simulation	Terminal eval.	-
	01	DI/DO 1 (X520.3)	Simulation	Terminal eval.	-
	02	DI/DO 2 (X520.4)	Simulation	Terminal eval.	-
	03	DI/DO 3 (X520.5)	Simulation	Terminal eval.	-
	04	DI/DO 4 (X520.6)	Simulation	Terminal eval.	-
	05	DI/DO 5 (X520.7)	Simulation	Terminal eval.	-
	06	DI/DO 6 (X520.8)	Simulation	Terminal eval.	-
	07	DI/DO 7 (X520.9)	Simulation	Terminal eval.	-
	08	DI/DO 8 (X521.2)	Simulation	Terminal eval.	-
	09	DI/DO 9 (X521.3)	Simulation	Terminal eval.	-
	10	DI/DO 10 (X521.4)	Simulation	Terminal eval.	-
	11	DI/DO 11 (X521.5)	Simulation	Terminal eval.	-
	12	DI/DO 12 (X521.6)	Simulation	Terminal eval.	-
	13	DI/DO 13 (X521.7)	Simulation	Terminal eval.	-
	14	DI/DO 14 (X521.8)	Simulation	Terminal eval.	-
	15	DI/DO 15 (X521.9)	Simulation	Terminal eval.	-
	16	DI/DO 16 (X522.2)	Simulation	Terminal eval.	-
	17	DI/DO 17 (X522.3)	Simulation	Terminal eval.	-
	18	DI/DO 18 (X522.4)	Simulation	Terminal eval.	-
	19	DI/DO 19 (X522.5)	Simulation	Terminal eval.	-
	20	DI/DO 20 (X522.6)	Simulation	Terminal eval.	-
	21	DI/DO 21 (X522.7)	Simulation	Terminal eval.	-
	22	DI/DO 22 (X522.8)	Simulation	Terminal eval.	-
	23	DI/DO 23 (X522.9)	Simulation	Terminal eval.	-

Dependency: The setpoint for the input signals is specified using p4096.

Refer to: p4096

Note: This parameter is not saved when data is backed-up (p0971, p0977).

DI/DO: Bidirectional Digital Input/Output

p4096 TB30 digital inputs, simulation mode setpoint / TB30 DI sim setpt

TB30	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 1790, 9100
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0000 bin

Description: Sets the setpoint for the input signals in the simulation mode of the digital inputs of the Terminal Board 30 (TB30).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X481.1)	High	Low	-
	01	DI 1 (X481.2)	High	Low	-
	02	DI 2 (X481.3)	High	Low	-
	03	DI 3 (X481.4)	High	Low	-

Dependency: The simulation of a digital input is selected using p4095.

Refer to: p4095

Note: This parameter is not saved when data is backed-up (p0971, p0977).

DI: Digital input

p4096		TM31 digital inputs, simulation mode setpoint / TM31 DI sim setpt			
TM31	Can be changed: U, T			Access level: 2	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 1840, 9550, 9552, 9560, 9562	
	P-Group: Terminals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Sets the setpoint for the input signals in the simulation mode of the digital inputs of terminal module 31 (TM31).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X520.1)	High	Low	-
	01	DI 1 (X520.2)	High	Low	-
	02	DI 2 (X520.3)	High	Low	-
	03	DI 3 (X520.4)	High	Low	-
	04	DI 4 (X530.1)	High	Low	-
	05	DI 5 (X530.2)	High	Low	-
	06	DI 6 (X530.3)	High	Low	-
	07	DI 7 (X530.4)	High	Low	-
	08	DI/DO 8 (X541.2)	High	Low	-
	09	DI/DO 9 (X541.3)	High	Low	-
	10	DI/DO 10 (X541.4)	High	Low	-
	11	DI/DO 11 (X541.5)	High	Low	-
Dependency:	The simulation of a digital input is selected using p4095. Refer to: p4095				
Note:	This parameter is not saved when data is backed-up (p0971, p0977). DI: Digital input DI/DO: Bidirectional Digital Input/Output				

p4096		TM41 digital inputs, simulation mode setpoint / TM41 DI sim setpt			
TM41	Can be changed: U, T			Access level: 2	
	Data type: Unsigned32	Dynamic index: -		Function diagram: -	
	P-Group: Terminals	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Sets the setpoint for the input signals in the simulation mode of the digital inputs of terminal module 41 (TM41).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (X522.1)	High	Low	-
	01	DI 1 (X522.2)	High	Low	-
	02	DI 2 (X522.3)	High	Low	-
	03	DI 3 (X522.4)	High	Low	-
	08	DI/DO 0 (X521.1)	High	Low	-
	09	DI/DO 1 (X521.2)	High	Low	-
	10	DI/DO 2 (X521.3)	High	Low	-
	11	DI/DO 3 (X521.4)	High	Low	-
Dependency:	The simulation of a digital input is selected using p4095. Refer to: p4095				
Note:	This parameter is not saved when data is backed-up (p0971, p0977). DI: Digital input DI/DO: Bidirectional Digital Input/Output				

p4096		TM15DI/DO digital inputs, simulation mode, setpoint / TM15D DI sim setpt		
TM15DI_DO	Can be changed: U, T			Access level: 2
	Data type: Unsigned32		Dynamic index: -	Function diagram: 9400, 9401, 9402
	P-Group: Terminals		Units group: -	Unit selection: -
	Min		Max	Factory setting
	-		-	0000 bin
Description:	Sets the setpoint for the input signals in the simulation mode of the digital inputs of terminal module 15 (TM15).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	DI/DO 0 (X520.2)	High	Low
	01	DI/DO 1 (X520.3)	High	Low
	02	DI/DO 2 (X520.4)	High	Low
	03	DI/DO 3 (X520.5)	High	Low
	04	DI/DO 4 (X520.6)	High	Low
	05	DI/DO 5 (X520.7)	High	Low
	06	DI/DO 6 (X520.8)	High	Low
	07	DI/DO 7 (X520.9)	High	Low
	08	DI/DO 8 (X521.2)	High	Low
	09	DI/DO 9 (X521.3)	High	Low
	10	DI/DO 10 (X521.4)	High	Low
	11	DI/DO 11 (X521.5)	High	Low
	12	DI/DO 12 (X521.6)	High	Low
	13	DI/DO 13 (X521.7)	High	Low
	14	DI/DO 14 (X521.8)	High	Low
	15	DI/DO 15 (X521.9)	High	Low
	16	DI/DO 16 (X522.2)	High	Low
	17	DI/DO 17 (X522.3)	High	Low
	18	DI/DO 18 (X522.4)	High	Low
	19	DI/DO 19 (X522.5)	High	Low
	20	DI/DO 20 (X522.6)	High	Low
	21	DI/DO 21 (X522.7)	High	Low
	22	DI/DO 22 (X522.8)	High	Low
	23	DI/DO 23 (X522.9)	High	Low
Dependency:	The simulation of a digital input is selected using p4095. Refer to: p4095			
Note:	This parameter is not saved when data is backed-up (p0971, p0977). DI/DO: Bidirectional Digital Input/Output			

p4097[0...1]		TB30 analog inputs simulation mode / TB30 AI sim_mode		
TB30	Can be changed: U, T			Access level: 2
	Data type: Integer16		Dynamic index: -	Function diagram: 9104
	P-Group: Terminals		Units group: -	Unit selection: -
	Min		Max	Factory setting
	0		1	0
Description:	Sets the simulation mode for the analog inputs of the Terminal Board 30 (TB30).			
Values:	0: No simulation mode for analog input x 1: Simulation mode for analog input x			
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)			
Dependency:	The setpoint for the input voltage is specified via p4098. Refer to: p4098			
Note:	This parameter is not saved when data is backed-up (p0971, p0977). AI: Analog Input			

p4097[0...1]	TM31 analog inputs simulation mode / TM31 AI sim_mode		
TM31	Can be changed: U, T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the simulation mode for the analog inputs of terminal module 31 (TM31).		
Values:	0: No simulation mode for analog input x 1: Simulation mode for analog input x		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Dependency:	The setpoint for the input voltage is specified via p4098. Refer to: p4098		
Note:	This parameter is not saved when data is backed-up (p0971, p0977). AI: Analog Input		
p4097[0...0]	TM41 analog input, simulation mode / TM41 AI sim_mode		
TM41	Can be changed: U, T		Access level: 2
	Data type: Integer16	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Sets the simulation mode for the analog input of terminal module 41 (TM41).		
Values:	0: No simulation mode for analog input x 1: Simulation mode for analog input x		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Dependency:	The setpoint for the input voltage is specified via p4098. Refer to: p4098		
Note:	This parameter is not saved when data is backed-up (p0971, p0977). AI: Analog Input		
p4098[0...1]	TB30 analog inputs simulation mode setpoint / TB30 AI sim setpt		
TB30	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9104
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -11.000 [V]	Max 11.000 [V]	Factory setting 0.000 [V]
Description:	Sets the setpoint for the input voltage in the simulation mode of the analog inputs of Terminal Board 30 (TB30).		
Index:	[0] = AI 0 (X482.1/X482.2) [1] = AI 1 (X482.3/X482.4)		
Dependency:	The simulation of an analog input is selected using p4097. Refer to: p4097		
Note:	This parameter is not saved when data is backed-up (p0971, p0977). AI: Analog Input		

p4098[0...1]	TM31 analog inputs simulation mode setpoint / TM31 AI sim setpt		
TM31	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000
Description:	Sets the setpoint for the input value in simulation mode of the analog inputs of terminal module 31 (TM31).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0) [1] = AI 1 (X521.3/X521.4, S5.1)		
Dependency:	The simulation of an analog input is selected using p4097. If AI x is parameterized as voltage input (p4056), then the setpoint is a voltage in V. If AI x is parameterized as current input (p4056), then the setpoint is current in mA. Refer to: r4056, p4056, p4097		
Note:	This parameter is not saved when data is backed-up (p0971, p0977). AI: Analog Input		
p4098[0...0]	TM41 analog input, simulation mode setpoint / TM41 AI sim setpt		
TM41	Can be changed: U, T		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: 9566, 9568
	P-Group: Terminals	Units group: -	Unit selection: -
	Min -20.000	Max 20.000	Factory setting 0.000
Description:	Sets the setpoint for the input value in simulation mode of the analog input of terminal module 41 (TM41).		
Index:	[0] = AI 0 (X521.1/X521.2, S5.0)		
Dependency:	The simulation of the analog input is selected using p4097. If AI x is parameterized as voltage input (p4056), then the setpoint is a voltage in V. If AI x is parameterized as current input (p4056), then the setpoint is current in mA. Refer to: p4097		
Note:	This parameter is not saved when data is backed-up (p0971, p0977). AI: Analog Input		
p4099[0...2]	TB30 inputs/outputs, sampling time / TB30 I/O t_sample		
TB30	Can be changed: C1(3)		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 9100, 9102, 9104, 9106
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 5000.00 [µs]	Factory setting [0] 4000.00 [µs] [1] 4000.00 [µs] [2] 4000.00 [µs]
Description:	Sets the sampling time for the inputs and outputs of the Terminal Board 30 (TB30).		
Index:	[0] = Digital inputs/outputs (DI/DO) [1] = Analog inputs (AI) [2] = Analog outputs (AO)		
Dependency:	The parameter can only be modified for p0009 = 3, 29. The sampling times can only be set as an integer multiple of the basic sampling time (p0110, p0111). Refer to: p0009, r0110, r0111		

Note: The modified sampling time is not effective until the drive unit is powered-up again.
For clock cycle synchronous PROFIBUS operation, the TB30 hardware (e.g. A/D converter) is operated with the PROFIBUS clock cycle (r2064[1]). This clock cycle is also kept after the PROFIBUS connection has been exited up to the next time that the Control Unit is powered-down. In this case, a faster sampling time than the PROFIBUS clock cycle is not practical in p4099[0...2].

p4099[0...2] TM31 inputs/outputs, sampling time / TM31 I/O t_sample

TM31	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 9550
	P-Group: Commands		Unit selection: -
	Min 0.00 [µs]	Max 5000.00 [µs]	Factory setting 4000.00 [µs]

Description: Sets the sampling time for the inputs and outputs of terminal module 31 (TM31).

Index:
[0] = Digital inputs/outputs (DI/DO)
[1] = Analog inputs (AI)
[2] = Analog outputs (AO)

Dependency: The parameter can only be modified for p0009 = 3, 29.
The sampling times can only be set as an integer multiple of the basic sampling time (p0110, p0111).
Refer to: p0009, r0110, r0111

Notice: The sampling times entered in index 0 (digital inputs/outputs) and index 2 (analog outputs) must always be greater than or equal to the sampling time in index 1 (analog inputs).

Note: The modified sampling time is not effective until the drive unit is powered-up again.

p4099[0...3] TM41 inputs/outputs, sampling time / TM41 I/O t_sample

TM41	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: 9550
	P-Group: Commands		Unit selection: -
	Min 0.00 [µs]	Max 5000.00 [µs]	Factory setting [0] 4000.00 [µs] [1] 4000.00 [µs] [2] 0.00 [µs] [3] 125.00 [µs]

Description: Sets the sampling time for the inputs and outputs of terminal module 41 (TM41).

Index:
[0] = Digital inputs/outputs (DI/DO)
[1] = Analog inputs (AI)
[2] = Does not exist
[3] = Encoder emulation

Dependency: The parameter can only be modified for p0009 = 3, 29.
The sampling times for the digital inputs/outputs and analog inputs can only be set as a multiple of the basic sampling time (p0110, p0111).
The sampling time of the encoder emulation must be set the same as the basic sampling time p0110[0] (p0111).
Refer to: p0009, r0110, r0111

Note: The modified sampling time is not effective until the drive unit is powered-up again.

p4099 TM17 inputs/outputs, sampling time / TM17 I/O t_sample

TM17	Can be changed: C1(3)	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Commands		Unit selection: -
	Min 31.25 [µs]	Max 400.00 [µs]	Factory setting 125.00 [µs]

Description: Sets the sampling time for the inputs and outputs of the terminal module 17 (TM17).

Dependency: The parameter can only be modified for p0009 = 3, 29.
The sampling time must be set the same as the basic sampling time p0110[0].
Refer to: r0110

Note: The modified sampling time is not effective until the drive unit is powered-up again.

p4099 TM15 inputs/outputs, sampling time / TM15 I/O t_sample

TM15	Can be changed: C1(3)	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Commands	Function diagram: -
		Unit selection: -
	Min 31.25 [µs]	Max 400.00 [µs]
		Factory setting 125.00 [µs]

Description: Sets the sampling time for the inputs and outputs of terminal module 15 (TM15).

Dependency: The parameter can only be modified for p0009 = 3, 29.
The sampling time must be set the same as the basic sampling time p0110[0].
Refer to: r0110

Note: The modified sampling time is not effective until the drive unit is powered-up again.

p4099 TM15DI/DO inputs/outputs, sampling time / TM15D I/O t_sampl

TM15DI_DO	Can be changed: C1(3)	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Commands	Function diagram: 9400, 9401, 9402
		Unit selection: -
	Min 0.00 [µs]	Max 5000.00 [µs]
		Factory setting 4000.00 [µs]

Description: Sets the sampling time for the inputs and outputs of terminal module 15 (TM15).

Dependency: The parameter can only be modified for p0009 = 3, 29.
The sampling times can only be set as an integer multiple of the basic sampling time (p0110, p0111).
Refer to: p0009, r0110, r0111

Note: The modified sampling time is not effective until the drive unit is powered-up again.

p4100 TM31 temperature evaluation, sensor type / TM31 temp sens_typ

TM31	Can be changed: T	Access level: 1
	Data type: Integer16	Dynamic index: -
	P-Group: -	Function diagram: 9576, 9577
		Unit selection: -
	Min 0	Max 2
		Factory setting 0

Description: Sets the temperature evaluation of terminal module 31 (TM31).

This means that the temperature sensor type is selected and the evaluation is switched-in.

Values:
0: Evaluation disabled
1: PTC thermistor
2: KTY84

Note: The temperature sensor is connected at terminals X522.7(+) and X522.8(-).

r4101 TM31 temperature evaluation, sensor resistance / TM31 temp R_sensor

TM31	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Terminals	Function diagram: 9576, 9577
		Unit selection: -
	Min - [Ohm]	Max - [Ohm]
		Factory setting - [Ohm]

Description: Displays the actual resistance value of the temperature sensor connected at terminal module 31 (TM31).

Note: The temperature sensor is connected at terminals X522.7(+) and X522.8(-).

The maximum measurable resistance value is approx. 1700 Ohm.

r4154	TM41 diagnostics speed setpoint non-filtered / n_set non-filt		
TM41	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the unfiltered speed setpoint N_SETPT in revolutions per minute for diagnostic purposes. In contrast to p1155, the value is updated in each DRIVE-CLiQ basic clock cycle and displayed with sign.		
Dependency:	Refer to: r4155		
r4155	TM41 diagnostics speed setpoint / TM41 DIAG n_set		
TM41	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 9674
	P-Group: -	Units group: -	Unit selection: -
	Min - [1/min]	Max - [1/min]	Factory setting - [1/min]
Description:	Displays the filtered speed setpoint N_SETPT in revolutions per minute for diagnostic purposes. In contrast to p1155, the value is updated in each DRIVE-CLiQ basic clock cycle and displayed with sign.		
Dependency:	Refer to: r4154		
r4201	TM17 system time for synchronization / TM17 t_system sync		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Is used to synchronize the timer of terminal module 17 (TM17) with the system time of the DP master. To do this, the sign-of-life of the DP master is transferred in the form of a counter in bits 12 to 15. At each cycle of the system of the DP master, bit 0 (SYN signal) is set for the duration of a DP master clock cycle.		
r4201	TM15 system time for synchronization / TM15 t_system sync		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Is used to synchronize the timer of terminal module 15 (TM15) with the system time of the DP master. To do this, the sign-of-life of the DP master is transferred in the form of a counter in bits 12 to 15. At each cycle of the system of the DP master, bit 0 (SYN signal) is set for the duration of a DP master clock cycle.		
r4204	TM17 control digital output 0 ... 15 / TM17 ctrl DO 0-15		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0000 bin
Description:	Used to control digital output 0 ... 15 of terminal module 17 (TM17).		

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	On	Off	-
	01	DI/DO 1 (X520.3)	On	Off	-
	02	DI/DO 2 (X520.5)	On	Off	-
	03	DI/DO 3 (X520.6)	On	Off	-
	04	DI/DO 4 (X520.8)	On	Off	-
	05	DI/DO 5 (X520.9)	On	Off	-
	06	DI/DO 6 (X521.2)	On	Off	-
	07	DI/DO 7 (X521.3)	On	Off	-
	08	DI/DO 8 (X521.8)	On	Off	-
	09	DI/DO 9 (X521.9)	On	Off	-
	10	DI/DO 10 (X522.2)	On	Off	-
	11	DI/DO 11 (X522.3)	On	Off	-
	12	DI/DO 12 (X522.5)	On	Off	-
	13	DI/DO 13 (X522.6)	On	Off	-
	14	DI/DO 14 (X522.8)	On	Off	-
	15	DI/DO 15 (X522.9)	On	Off	-

Note: DI/DO: Bidirectional Digital Input/Output

r4204 TM15 control digital output 0 ... 15 / TM15 ctrl DO 0-15

TM15	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Min	Unit selection: -
	-	Factory setting
		0000 bin
	Max	
	-	

Description: Used to control digital output 0 ... 15 of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	On	Off	-
	01	DI/DO 1 (X520.3)	On	Off	-
	02	DI/DO 2 (X520.4)	On	Off	-
	03	DI/DO 3 (X520.5)	On	Off	-
	04	DI/DO 4 (X520.6)	On	Off	-
	05	DI/DO 5 (X520.7)	On	Off	-
	06	DI/DO 6 (X520.8)	On	Off	-
	07	DI/DO 7 (X520.9)	On	Off	-
	08	DI/DO 8 (X521.2)	On	Off	-
	09	DI/DO 9 (X521.3)	On	Off	-
	10	DI/DO 10 (X522.4)	On	Off	-
	11	DI/DO 11 (X521.5)	On	Off	-
	12	DI/DO 12 (X521.6)	On	Off	-
	13	DI/DO 13 (X521.7)	On	Off	-
	14	DI/DO 14 (X521.8)	On	Off	-
	15	DI/DO 15 (X521.9)	On	Off	-

Note: DI/DO: Bidirectional Digital Input/Output

r4205 TM15 control digital output 16 ... 23 / TM15 ctrl DO 16-23

TM15	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Min	Unit selection: -
	-	Factory setting
		0000 bin
	Max	
	-	

Description: Used to control digital output 16 ... 23 of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 16 (X522.2)	On	Off	-
	01	DI/DO 17 (X522.3)	On	Off	-
	02	DI/DO 18 (X522.4)	On	Off	-
	03	DI/DO 19 (X522.5)	On	Off	-
	04	DI/DO 20 (X522.6)	On	Off	-
	05	DI/DO 21 (X522.7)	On	Off	-
	06	DI/DO 22 (X522.8)	On	Off	-
	07	DI/DO 23 (X522.9)	On	Off	-
Note:	DI/DO: Bidirectional Digital Input/Output				

r4211 **TM17 edge mode digital input 0 ... 7 / TM17 EdgMd DI 0-7**

TM17	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Min	Unit selection: -
	-	Factory setting
	Max	-
	-	-

Description: Displays the edge mode for digital input 0 ... 7 of terminal module 17 (TM17).

Assignment of the digital inputs to the bits:

DI 0: r4211.1 ... 0

DI 1: r4211.3 ... 2

DI 2: r4211.5 ... 4

DI 3: r4211.7 ... 6

DI 4: r4211.9 ... 8

DI 5: r4211.11 ... 10

DI 6: r4211.13 ... 12

DI 7: r4211.15 ... 14

Possible edge modes:

Bit x, y = 0, 0 --> no edge detection

Bit x, y = 0, 1 --> rising - rising edge

Bit x, y = 1, 0 --> falling - falling edge

Bit x, y = 1, 1 --> rising - falling edge or falling - rising edge

Note: DI: Digital input

r4211 TM15 edge mode digital input 0 ... 7 / TM15 EdgMd DI0-7

TM15	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Commands		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the edge mode for digital input 0 ... 7 of terminal module 15 (TM15).
Assignment of the digital inputs to the bits:
DI 0: r4211.1 ... 0
DI 1: r4211.3 ... 2
DI 2: r4211.5 ... 4
DI 3: r4211.7 ... 6
DI 4: r4211.9 ... 8
DI 5: r4211.11 ... 10
DI 6: r4211.13 ... 12
DI 7: r4211.15 ... 14
Possible edge modes:
Bit x, y = 0, 0 --> no edge detection
Bit x, y = 0, 1 --> rising - rising edge
Bit x, y = 1, 0 --> falling - falling edge
Bit x, y = 1, 1 --> rising - falling edge or falling - rising edge

Note: DI: Digital input

r4212 TM17 edge mode digital input 8 ... 15 / TM17 EdgMd DI 8-15

TM17	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Commands		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the edge mode for digital input 8 ... 15 of terminal module 17 (TM17).
Assignment of the digital inputs to the bits:
DI 8: r4212.1 ... 0
DI 9: r4212.3 ... 2
DI 10: r4212.5 ... 4
DI 11: r4212.7 ... 6
DI 12: r4212.9 ... 8
DI 13: r4212.11 ... 10
DI 14: r4212.13 ... 12
DI 15: r4212.15 ... 14
Possible edge modes:
Bit x, y = 0, 0 --> no edge detection
Bit x, y = 0, 1 --> rising - rising edge
Bit x, y = 1, 0 --> falling - falling edge
Bit x, y = 1, 1 --> rising - falling edge or falling - rising edge

Note: DI: Digital input

r4212	TM15 edge mode digital input 8 ... 15 / TM15 EdgMd DI8-15		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the edge mode for digital input 8 ... 15 of terminal module 15 (TM15). Assignment of the digital inputs to the bits: DI 8: r4212.1 ... 0 DI 9: r4212.3 ... 2 DI 10: r4212.5 ... 4 DI 11: r4212.7 ... 6 DI 12: r4212.9 ... 8 DI 13: r4212.11 ... 10 DI 14: r4212.13 ... 12 DI 15: r4212.15 ... 14 Possible edge modes: Bit x, y = 0, 0 --> no edge detection Bit x, y = 0, 1 --> rising - rising edge Bit x, y = 1, 0 --> falling - falling edge Bit x, y = 1, 1 --> rising - falling edge or falling - rising edge		
Note:	DI: Digital input		

r4213	TM15 edge mode digital input 16 ... 23 / TM15 EdgMd DI16-23		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the edge mode for digital input 16 ... 23 of terminal module 15 (TM15). Assignment of the digital inputs to the bits: DI 16: r4213.1 ... 0 DI 17: r4213.3 ... 2 DI 18: r4213.5 ... 4 DI 19: r4213.7 ... 6 DI 20: r4213.9 ... 8 DI 21: r4213.11 ... 10 DI 22: r4213.13 ... 12 DI 23: r4213.15 ... 14 Possible edge modes: Bit x, y = 0, 0 --> no edge detection Bit x, y = 0, 1 --> rising - rising edge Bit x, y = 1, 0 --> falling - falling edge Bit x, y = 1, 1 --> rising - falling edge or falling - rising edge		
Note:	DI: Digital input		

p4220 TM17 enable DI/DO 0 ... 5 / TM17 enable 0-5

TM17	Can be changed: T	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Sets the enable signal with bits 0 ... 5 for DI/DO 0 ... 5 of terminal module 17 (TM17).
 Sets the triggering of the enable signal with bits 8 ... 13.
 The following assignment applies:
 Enable signal for DI/DO 0, 1, 2, 3, 4 or 5 via DI/DO 10, 11, 12, 13, 14 or 15.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	With enable	Without enable	-
	01	DI/DO 1 (X520.3)	With enable	Without enable	-
	02	DI/DO 2 (X520.5)	With enable	Without enable	-
	03	DI/DO 3 (X520.6)	With enable	Without enable	-
	04	DI/DO 4 (X520.8)	With enable	Without enable	-
	05	DI/DO 5 (X520.9)	With enable	Without enable	-
	08	DI/DO 10 (X522.2)	Level-triggered	Edge-triggered	-
	09	DI/DO 11 (X522.3)	Level-triggered	Edge-triggered	-
	10	DI/DO 12 (X522.5)	Level-triggered	Edge-triggered	-
	11	DI/DO 13 (X522.6)	Level-triggered	Edge-triggered	-
	12	DI/DO 14 (X522.8)	Level-triggered	Edge-triggered	-
	13	DI/DO 15 (X522.9)	Level-triggered	Edge-triggered	-

Note: DI/DO: Bidirectional Digital Input/Output

p4221 TM17 smoothing time constant, digital input 0 ... 15 / TM17 smooth DI

TM17	Can be changed: U, T	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Sets the smoothing time constant for digital input 0 ... 15 of terminal module 17 (TM17).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Smoothing 1 µs	Smoothing 125 µs	-
	01	DI/DO 1 (X520.3)	Smoothing 1 µs	Smoothing 125 µs	-
	02	DI/DO 2 (X520.5)	Smoothing 1 µs	Smoothing 125 µs	-
	03	DI/DO 3 (X520.6)	Smoothing 1 µs	Smoothing 125 µs	-
	04	DI/DO 4 (X520.8)	Smoothing 1 µs	Smoothing 125 µs	-
	05	DI/DO 5 (X520.9)	Smoothing 1 µs	Smoothing 125 µs	-
	06	DI/DO 6 (X521.2)	Smoothing 1 µs	Smoothing 125 µs	-
	07	DI/DO 7 (X521.3)	Smoothing 1 µs	Smoothing 125 µs	-
	08	DI/DO 8 (X521.8)	Smoothing 1 µs	Smoothing 125 µs	-
	09	DI/DO 9 (X521.9)	Smoothing 1 µs	Smoothing 125 µs	-
	10	DI/DO 10 (X522.2)	Smoothing 1 µs	Smoothing 125 µs	-
	11	DI/DO 11 (X522.3)	Smoothing 1 µs	Smoothing 125 µs	-
	12	DI/DO 12 (X522.5)	Smoothing 1 µs	Smoothing 125 µs	-
	13	DI/DO 13 (X522.6)	Smoothing 1 µs	Smoothing 125 µs	-
	14	DI/DO 14 (X522.8)	Smoothing 1 µs	Smoothing 125 µs	-
	15	DI/DO 15 (X522.9)	Smoothing 1 µs	Smoothing 125 µs	-

Note: DI/DO: Bidirectional Digital Input/Output
 DI: Digital input

p4222		TM17 time, absolute/relative for digital output 0 ... 15 / TM17 abs/rel 0-15			
TM17	Can be changed: T			Access level: 2	
	Data type: Unsigned32	Dynamic index: -		Function diagram: -	
	P-Group: Commands	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Sets as absolute or relative timing with bit 0 ... 15 for digital output 0 ... 15 of terminal module 17 (TM17).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	Relative time	Absolute time	-
	01	DI/DO 1 (X520.3)	Relative time	Absolute time	-
	02	DI/DO 2 (X520.5)	Relative time	Absolute time	-
	03	DI/DO 3 (X520.6)	Relative time	Absolute time	-
	04	DI/DO 4 (X520.8)	Relative time	Absolute time	-
	05	DI/DO 5 (X520.9)	Relative time	Absolute time	-
	06	DI/DO 6 (X521.2)	Relative time	Absolute time	-
	07	DI/DO 7 (X521.3)	Relative time	Absolute time	-
	08	DI/DO 8 (X521.8)	Relative time	Absolute time	-
	09	DI/DO 9 (X521.9)	Relative time	Absolute time	-
	10	DI/DO 10 (X522.2)	Relative time	Absolute time	-
	11	DI/DO 11 (X522.3)	Relative time	Absolute time	-
	12	DI/DO 12 (X522.5)	Relative time	Absolute time	-
	13	DI/DO 13 (X522.6)	Relative time	Absolute time	-
	14	DI/DO 14 (X522.8)	Relative time	Absolute time	-
	15	DI/DO 15 (X522.9)	Relative time	Absolute time	-
Note:	DI/DO: Bidirectional Digital Input/Output DO: Digital Output				

r4250		TM17 set/reset time, digital output 0 / TM17 t_set DO 0		
TM17	Can be changed: -			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the time to set and reset for digital output 0 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.			
Note:	DO: Digital Output			

r4250		TM15 set/reset time, digital output 0 / TM15 t_set DO 0		
TM15	Can be changed: -			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Commands	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the time to set and reset for digital output 0 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.			
Note:	DO: Digital Output			

r4251	TM17 set/reset time, digital output 1 / TM17 t_set DO 1		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 1 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		
r4251	TM15 set/reset time, digital output 1 / TM15 t_set DO 1		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 1 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		
r4252	TM17 set/reset time, digital output 2 / TM17 t_set DO 2		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 2 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		
r4252	TM15 set/reset time, digital output 2 / TM15 t_set DO 2		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 2 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		
r4253	TM17 set/reset time, digital output 3 / TM17 t_set DO 3		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 3 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		

r4253	TM15 set/reset time, digital output 3 / TM15 t_set DO 3		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 3 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 μ s.		
Note:	DO: Digital Output		
r4254	TM17 set/reset time, digital output 4 / TM17 t_set DO 4		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 4 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 μ s.		
Note:	DO: Digital Output		
r4254	TM15 set/reset time, digital output 4 / TM15 t_set DO 4		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 4 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 μ s.		
Note:	DO: Digital Output		
r4255	TM17 set/reset time, digital output 5 / TM17 t_set DO 5		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 5 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 μ s.		
Note:	DO: Digital Output		
r4255	TM15 set/reset time, digital output 5 / TM15 t_set DO 5		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 5 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 μ s.		
Note:	DO: Digital Output		

r4256	TM17 set/reset time, digital output 6 / TM17 t_set DO 6		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 6 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		
r4256	TM15 set/reset time, digital output 6 / TM15 t_set DO 6		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 6 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		
r4257	TM17 set/reset time, digital output 7 / TM17 t_set DO 7		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 7 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		
r4257	TM15 set/reset time, digital output 7 / TM15 t_set DO 7		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 7 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		
r4258	TM17 set/reset time, digital output 8 / TM17 t_set DO 8		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 8 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		

r4258	TM15 set/reset time, digital output 8 / TM15 t_set DO 8		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 8 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 μ s.		
Note:	DO: Digital Output		

r4259	TM17 set/reset time, digital output 9 / TM17 t_set DO 9		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 9 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 μ s.		
Note:	DO: Digital Output		

r4259	TM15 set/reset time, digital output 9 / TM15 t_set DO 9		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 9 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 μ s.		
Note:	DO: Digital Output		

r4260	TM17 set/reset time, digital output 10 / TM17 t_set DO 10		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 10 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 μ s.		
Note:	DO: Digital Output		

r4260	TM15 set/reset time, digital output 10 / TM15 t_set DO 10		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 10 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 μ s.		
Note:	DO: Digital Output		

r4261	TM17 set/reset time, digital output 11 / TM17 t_set DO 11		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 11 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		

r4261	TM15 set/reset time, digital output 11 / TM15 t_set DO 11		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 11 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4262	TM17 set/reset time, digital output 12 / TM17 t_set DO 12		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 12 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		

r4262	TM15 set/reset time, digital output 12 / TM15 t_set DO 12		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 12 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4263	TM17 set/reset time, digital output 13 / TM17 t_set DO 13		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 13 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		

r4263	TM15 set/reset time, digital output 13 / TM15 t_set DO 13		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 13 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		
r4264	TM17 set/reset time, digital output 14 / TM17 t_set DO 14		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 14 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		
r4264	TM15 set/reset time, digital output 14 / TM15 t_set DO 14		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 14 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		
r4265	TM17 set/reset time, digital output 15 / TM17 t_set DO 15		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 15 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DO: Digital Output		
r4265	TM15 set/reset time, digital output 15 / TM15 t_set DO 15		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 15 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4266	TM15 set/reset time, digital output 16 / TM15 t_set DO 16		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 16 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4267	TM15 set/reset time, digital output 17 / TM15 t_set DO 17		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 17 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4268	TM15 set/reset time, digital output 18 / TM15 t_set DO 18		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 18 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4269	TM15 set/reset time, digital output 19 / TM15 t_set DO 19		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 19 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4270	TM15 set/reset time, digital output 20 / TM15 t_set DO 20		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 20 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4271	TM15 set/reset time, digital output 21 / TM15 t_set DO 21		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 21 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4272	TM15 set/reset time, digital output 22 / TM15 t_set DO 22		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 22 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4273	TM15 set/reset time, digital output 23 / TM15 t_set DO 23		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time to set and reset for digital output 23 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DO: Digital Output		

r4301	TM17 module synchronization / TM17 Module sync		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Is used to synchronize the timer of terminal module 17 (TM17) with the system time of the DP master. Bit 12 ... 15: After synchronization with the DP master, the module sends its sign-of-life in the form of a counter. Bit 0: This SYNC signal is set if the module has aligned its time to the system time of the DP master. Bit 9: This bit is set if a fault has occurred on the module (r0945).		

r4301 TM15 module synchronization / TM15 module sync

TM15	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		-

Description: Is used to synchronize the timer of terminal module 15 (TM15) with the system time of the DP master.
 Bit 12 ... 15:
 After synchronization with the DP master, the module sends its sign-of-life in the form of a counter.
 Bit 0:
 This SYNC signal is set if the module has aligned its time to the system time of the DP master.
 Bit 9:
 This bit is set if a fault has occurred on the module (r0945).

r4304 TM17 status, digital input 0 ... 15 / TM17 St DI 0-15

TM17	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays status for digital input 0 ... 15 of terminal module 17 (TM17).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	On	Off	-
	01	DI/DO 1 (X520.3)	On	Off	-
	02	DI/DO 2 (X520.5)	On	Off	-
	03	DI/DO 3 (X520.6)	On	Off	-
	04	DI/DO 4 (X520.8)	On	Off	-
	05	DI/DO 5 (X520.9)	On	Off	-
	06	DI/DO 6 (X521.2)	On	Off	-
	07	DI/DO 7 (X521.3)	On	Off	-
	08	DI/DO 8 (X521.8)	On	Off	-
	09	DI/DO 9 (X521.9)	On	Off	-
	10	DI/DO 10 (X522.2)	On	Off	-
	11	DI/DO 11 (X522.3)	On	Off	-
	12	DI/DO 12 (X522.5)	On	Off	-
	13	DI/DO 13 (X522.6)	On	Off	-
	14	DI/DO 14 (X522.8)	On	Off	-
	15	DI/DO 15 (X522.9)	On	Off	-

Note: DI/DO: Bidirectional Digital Input/Output

r4304 TM15 status, digital input 0 ... 15 / TM15 St DI 0-15

TM15	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
		Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays status for digital input 0 ... 15 of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 0 (X520.2)	On	Off	-
	01	DI/DO 1 (X520.3)	On	Off	-
	02	DI/DO 2 (X520.4)	On	Off	-
	03	DI/DO 3 (X520.5)	On	Off	-
	04	DI/DO 4 (X520.6)	On	Off	-
	05	DI/DO 5 (X520.7)	On	Off	-
	06	DI/DO 6 (X520.8)	On	Off	-
	07	DI/DO 7 (X520.9)	On	Off	-
	08	DI/DO 8 (X521.2)	On	Off	-
	09	DI/DO 9 (X521.3)	On	Off	-
	10	DI/DO 10 (X522.4)	On	Off	-
	11	DI/DO 11 (X521.5)	On	Off	-
	12	DI/DO 12 (X521.6)	On	Off	-
	13	DI/DO 13 (X521.7)	On	Off	-
	14	DI/DO 14 (X521.8)	On	Off	-
	15	DI/DO 15 (X521.9)	On	Off	-

Note: DI/DO: Bidirectional Digital Input/Output

r4305 TM15 status, digital input 16 ... 23 / TM15 St DI 16-23

TM15	Can be changed: -	Access level: 3
	Data type: Unsigned16	Dynamic index: -
	P-Group: Commands	Function diagram: -
	Min	Unit selection: -
	-	Factory setting
	Max	0000 bin
	-	

Description: Displays status for digital input 16 ... 23 of terminal module 15 (TM15).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI/DO 16 (X522.2)	On	Off	-
	01	DI/DO 17 (X522.3)	On	Off	-
	02	DI/DO 18 (X522.4)	On	Off	-
	03	DI/DO 19 (X522.5)	On	Off	-
	04	DI/DO 20 (X522.6)	On	Off	-
	05	DI/DO 21 (X522.7)	On	Off	-
	06	DI/DO 22 (X522.8)	On	Off	-
	07	DI/DO 23 (X522.9)	On	Off	-

Note: DI/DO: Bidirectional Digital Input/Output

r4311 TM17 edge status digital input 0 ... 7 / TM17 EdgSt DI 0-7

TM17	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Commands		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the edge status for digital input 0 ... 7 of terminal module 17 (TM17).
Assignment of the digital inputs to the bits:
DI 0: r4311.1 ... 0
DI 1: r4311.3 ... 2
DI 2: r4311.5 ... 4
DI 3: r4311.7 ... 6
DI 4: r4311.9 ... 8
DI 5: r4311.11 ... 10
DI 6: r4311.13 ... 12
DI 7: r4311.15 ... 14
Possible edge states:
Bit x, y = 0, 0 --> no edge detection
Bit x, y = 0, 1 --> 1st edge detected
Bit x, y = 1, 0 --> 2nd edge detected
Bit x, y = 1, 1 --> both edges detected

Note: DI: Digital input

r4311 TM15 edge status digital input 0 ... 7 / TM15 EdgSt DI 0-7

TM15	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Commands		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the edge status for digital input 0 ... 7 of terminal module 15 (TM15).
Assignment of the digital inputs to the bits:
DI 0: r4311.1 ... 0
DI 1: r4311.3 ... 2
DI 2: r4311.5 ... 4
DI 3: r4311.7 ... 6
DI 4: r4311.9 ... 8
DI 5: r4311.11 ... 10
DI 6: r4311.13 ... 12
DI 7: r4311.15 ... 14
Possible edge states:
Bit x, y = 0, 0 --> no edge detection
Bit x, y = 0, 1 --> 1st edge detected
Bit x, y = 1, 0 --> 2nd edge detected
Bit x, y = 1, 1 --> both edges detected

Note: DI: Digital input

r4312		TM17 edge status digital input 8 ... 15 / TM17 EdgSt DI 8-15	
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the edge status for digital input 8 ... 15 of terminal module 17 (TM17). Assignment of the digital inputs to the bits: DI 8: r4312.1 ... 0 DI 9: r4312.3 ... 2 DI 10: r4312.5 ... 4 DI 11: r4312.7 ... 6 DI 12: r4312.9 ... 8 DI 13: r4312.11 ... 10 DI 14: r4312.13 ... 12 DI 15: r4312.15 ... 14 Possible edge states: Bit x, y = 0, 0 --> no edge detection Bit x, y = 0, 1 --> 1st edge detected Bit x, y = 1, 0 --> 2nd edge detected Bit x, y = 1, 1 --> both edges detected		
Note:	DI: Digital input		

r4312		TM15 edge status digital input 8 ... 15 / TM15 EdgSt DI 8-15	
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the edge status for digital input 8 ... 15 of terminal module 15 (TM15). Assignment of the digital inputs to the bits: DI 8: r4312.1 ... 0 DI 9: r4312.3 ... 2 DI 10: r4312.5 ... 4 DI 11: r4312.7 ... 6 DI 12: r4312.9 ... 8 DI 13: r4312.11 ... 10 DI 14: r4312.13 ... 12 DI 15: r4312.15 ... 14 Possible edge states: Bit x, y = 0, 0 --> no edge detection Bit x, y = 0, 1 --> 1st edge detected Bit x, y = 1, 0 --> 2nd edge detected Bit x, y = 1, 1 --> both edges detected		
Note:	DI: Digital input		

r4313		TM15 edge status digital input 16 ... 23 / TM15 EdgSt DI16-23		
TM15	Can be changed: - Data type: Unsigned16 P-Group: Commands Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: - Unit selection: - Factory setting -	
Description:	Displays the edge status for digital input 16 ... 23 of terminal module 15 (TM15). Assignment of the digital inputs to the bits: DI 16: r4313.1 ... 0 DI 17: r4313.3 ... 2 DI 18: r4313.5 ... 4 DI 19: r4313.7 ... 6 DI 20: r4313.9 ... 8 DI 21: r4313.11 ... 10 DI 22: r4313.13 ... 12 DI 23: r4313.15 ... 14 Possible edge states: Bit x, y = 0, 0 --> no edge detection Bit x, y = 0, 1 --> 1st edge detected Bit x, y = 1, 0 --> 2nd edge detected Bit x, y = 1, 1 --> both edges detected			
Note:	DI: Digital input			
r4350		TM17 edge times digital input 0 / TM17 edge_t DI 0		
TM17	Can be changed: - Data type: Unsigned32 P-Group: Commands Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: - Unit selection: - Factory setting -	
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 0 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.			
Note:	DI: Digital input			
r4350		TM15 edge times digital input 0 / TM15 edge_t DI 0		
TM15	Can be changed: - Data type: Unsigned16 P-Group: Commands Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: - Unit selection: - Factory setting -	
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 0 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.			
Note:	DI: Digital input			

r4351	TM17 edge times digital input 1 / TM17 edge_t DI 1		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 1 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4351	TM15 edge times digital input 1 / TM15 edge_t DI 1		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 1 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4352	TM17 edge times digital input 2 / TM17 edge_t DI 2		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 2 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4352	TM15 edge times digital input 2 / TM15 edge_t DI 2		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 2 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4353	TM17 edge times digital input 3 / TM17 edge_t DI 3		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 3 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4353	TM15 edge times digital input 3 / TM15 edge_t DI 3		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 3 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4354	TM17 edge times digital input 4 / TM17 edge_t DI 4		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 4 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4354	TM15 edge times digital input 4 / TM15 edge_t DI 4		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 4 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4355	TM17 edge times digital input 5 / TM17 edge_t DI 5		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 5 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4355	TM15 edge times digital input 5 / TM15 edge_t DI 5		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 5 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4356	TM17 edge times digital input 6 / TM17 edge_t DI 6		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 6 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4356	TM15 edge times digital input 6 / TM15 edge_t DI 6		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 6 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4357	TM17 edge times digital input 7 / TM17 edge_t DI 7		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 7 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4357	TM15 edge times digital input 7 / TM15 edge_t DI 7		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 7 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4358	TM17 edge times digital input 8 / TM17 edge_t DI 8		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 8 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4358	TM15 edge times digital input 8 / TM15 edge_t DI 8		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 8 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4359	TM17 edge times digital input 9 / TM17 edge_t DI 9		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 9 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4359	TM15 edge times digital input 9 / TM15 edge_t DI 9		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 9 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4360	TM17 edge times digital input 10 / TM17 edge_t DI 10		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 10 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4360	TM15 edge times digital input 10 / TM15 edge_t DI 10		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 10 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4361	TM17 edge times digital input 11 / TM17 edge_t DI 11		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 11 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		
r4361	TM15 edge times digital input 11 / TM15 edge_t DI 11		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 11 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
r4362	TM17 edge times digital input 12 / TM17 edge_t DI 12		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 12 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		
r4362	TM15 edge times digital input 12 / TM15 edge_t DI 12		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 12 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
r4363	TM17 edge times digital input 13 / TM17 edge_t DI 13		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 13 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		

r4363	TM15 edge times digital input 13 / TM15 edge_t DI 13		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 13 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
r4364	TM17 edge times digital input 14 / TM17 edge_t DI 14		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 14 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		
r4364	TM15 edge times digital input 14 / TM15 edge_t DI 14		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 14 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
r4365	TM17 edge times digital input 15 / TM17 edge_t DI 15		
TM17	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 15 of terminal module 17 (TM17). The two times are specified as 16 bit values with a resolution of 0.25 µs.		
Note:	DI: Digital input		
r4365	TM15 edge times digital input 15 / TM15 edge_t DI 15		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 15 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4366	TM15 edge times digital input 16 / TM15 edge_t DI 16		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 16 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4367	TM15 edge times digital input 17 / TM15 edge_t DI 17		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 17 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4368	TM15 edge times digital input 18 / TM15 edge_t DI 18		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 18 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4369	TM15 edge times digital input 19 / TM15 edge_t DI 19		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 19 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4370	TM15 edge times digital input 20 / TM15 edge_t DI 20		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 20 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		

r4371	TM15 edge times digital input 21 / TM15 edge_t DI 21		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 21 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
r4372	TM15 edge times digital input 22 / TM15 edge_t DI 22		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 22 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
r4373	TM15 edge times digital input 23 / TM15 edge_t DI 23		
TM15	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the time when detecting the 1st and 2nd edge for digital input 23 of terminal module 15 (TM15). The two times are specified as 8 bit values with a resolution of 64 µs.		
Note:	DI: Digital input		
p4400	TM41 incremental encoder emulation operating mode / Enc_emulat mode		
TM41	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9674, 9676
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the operating mode for the incremental encoder emulation. 0 -> Encoder emulation using the speed setpoint (p1155) 1 -> Encoder emulation using the encoder position actual value (p4420)		
Values:	0: Speed setpoint input 1: Position setpoint input		
Note:	A change only becomes effective after the next boot.		

p4401	TM41 incremental encoder emulation mode / Enc_emulat mode			
TM41	Can be changed: U, T		Access level: 3	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9674, 9676	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0001 bin	
Description:	Sets the mode for the incremental encoder emulation.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Enable zero mark	Yes	No
				FP 9674
r4402	TM41 incremental encoder emulation, status / Enc_emulat status			
TM41	Can be changed: -		Access level: 3	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9674, 9676	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0000 bin	
Description:	Displays the status of the incremental encoder emulation on terminal module 41 (TM41).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Zero mark enabled	Yes	No
	01	Tracks A/B enabled	Yes	No
	02	Interface encoder emulation enabled	Yes	No
				FP -
r4403	Incremental encoder emulation mode active / Enc_emul mode act			
TM41	Can be changed: -		Access level: 3	
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9674, 9676	
	P-Group: Closed-loop control	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting -	
Description:	Displays the actual operating mode of Terminal Module 41 (TM41).			
Dependency:	Refer to: p4400			
p4420	CI: TM41 incremental encoder emulation position actual value / Enc_emul s_act			
TM41	Can be changed: T		Access level: 3	
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9676	
	P-Group: Setpoints	Units group: -	Unit selection: -	
	Min -	Max -	Factory setting 0	
Description:	Sets the signal source for the position actual value.			
Dependency:	Refer to: p4400, r4403			
Note:	Prerequisites for the signal source: For the incremental encoder emulation, an encoder is required that supplies precisely one zero mark per revolution. The following BICO interconnection should be preferably set: CI: p4420 = r0479. An encoder actual value (r0479) can only be interconnected once on a TM41. The zero mark of the incremental encoder is output at the encoder interface after successful internal, automatic synchronization. If an absolute encoder is connected to the TM41, then a zero mark is always output at the zero revolution at the encoder interface of the TM41. The same behavior applies even if no encoder parameter is interconnected.			

p4421	TM41 incremental encoder emulation deadtime compensation / Enc_emul t_dead		
TM41	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 9676
	P-Group: Setpoints	Units group: -	Unit selection: -
	Min -10.00	Max 10.00	Factory setting 0.00
Description:	This factor defines the multiplier in which the encoder position setpoint of the incremental encoder emulation is shifted depending on the velocity.		
Dependency:	Refer to: p4400		
p4422	TM41 position actual value inversion / TM41 s_act inv		
TM41	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 9676
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Setting to invert the position actual value for Terminal Module 41 (TM41). 0 -> Position actual value (CI: p4420) is evaluated as normal. 1 -> Position actual value (CI: p4420) is processed inverted.		
Dependency:	Refer to: p4420		
p4426	Incremental encoder emulation, pulses for zero mark / Enc_emul pulses ZM		
TM41	Can be changed: C2(4)		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9674
	P-Group: Encoder	Units group: -	Unit selection: -
	Min 0	Max 8192	Factory setting 0
Description:	Sets pulse number to output the zero mark for the incremental encoder simulation/emulation. Example: p0408 = 2048 (encoder pulses) p4426 = 512 (pulses for the zero mark) --> Position direction: The zero mark is output after 512 pulses. --> Negative direction: The zero mark is output after 1536 pulses.		
Dependency:	Refer to: p0408		
Note:	The pulses for the zero mark (p4426) must be less than the encoder pulse number (p0408). For p4400 = 1, this parameter has not effect.		

p4600[0...n]		SME motor temperature sensor 1 sensor type / MotTemp_sens typ 1		
SERVO, VECTOR	Can be changed: C2(3), U, T			Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140		Function diagram: 8016
	P-Group: Motor	Units group: -		Unit selection: -
	Min 0	Max 32		Factory setting 0
Description:	Sets the sensor type of the first temperature sensor for the motor temperature monitoring. The parameter can only be changed for SME120 or SME125.			
Values:	0: No sensor available 10: PTC fault 11: PTC alarm 12: PTC alarm and timer stage 20: KTY84 30: Bimetallic NC contact fault 31: Bimetallic NC contact alarm 32: Bimetallic NC contact alarm and timer stage			
Dependency:	Refer to: r0458, p0600, p0601			
Note:	PTC thermistor: Tripping resistance = 1650 Ohm.			

p4601[0...n]		SME motor temperature sensor 2 sensor type / MotTemp_sens typ 2		
SERVO, VECTOR	Can be changed: C2(3), U, T			Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140		Function diagram: 8016
	P-Group: Motor	Units group: -		Unit selection: -
	Min 0	Max 32		Factory setting 0
Description:	Sets the sensor type of the second temperature sensor for the motor temperature monitoring. The parameter can only be changed for SME120 or SME125.			
Values:	0: No sensor available 10: PTC fault 11: PTC alarm 12: PTC alarm and timer stage 20: KTY84 30: Bimetallic NC contact fault 31: Bimetallic NC contact alarm 32: Bimetallic NC contact alarm and timer stage			
Dependency:	Refer to: r0458, p0600, p0601			
Note:	PTC thermistor: Tripping resistance = 1650 Ohm.			

p4602[0...n]	SME motor temperature sensor 3 sensor type / MotTemp_sens typ 3		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140	Function diagram: 8016
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 32	Factory setting 0
Description:	Sets the sensor type of the third temperature sensor for the motor temperature monitoring. The parameter can only be changed for SME120 or SME125.		
Values:	0: No sensor available 10: PTC fault 11: PTC alarm 12: PTC alarm and timer stage 20: KTY84 30: Bimetallic NC contact fault 31: Bimetallic NC contact alarm 32: Bimetallic NC contact alarm and timer stage		
Dependency:	Refer to: r0458, p0600, p0601		
Note:	PTC thermistor: Tripping resistance = 1650 Ohm.		

p4603[0...n]	SME motor temperature sensor 4 sensor type / MotTemp_sens typ 4		
SERVO, VECTOR	Can be changed: C2(3), U, T		Access level: 2
	Data type: Integer16	Dynamic index: EDS, p0140	Function diagram: 8016
	P-Group: Motor	Units group: -	Unit selection: -
	Min 0	Max 32	Factory setting 0
Description:	Sets the sensor type of the fourth temperature sensor for the motor temperature monitoring. The parameter can only be changed for SME120 or SME125.		
Values:	0: No sensor available 10: PTC fault 11: PTC alarm 12: PTC alarm and timer stage 20: KTY84 30: Bimetallic NC contact fault 31: Bimetallic NC contact alarm 32: Bimetallic NC contact alarm and timer stage		
Dependency:	Refer to: r0458, p0600, p0601		
Note:	PTC thermistor: Tripping resistance = 1650 Ohm.		

r4620[0...3]	Motor temperatures SME / Mot Temp SME		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the actual temperatures in the motor, measured via an SME 120 or SME 125.		
Index:	[0] = SME temperature channel 1 [1] = SME temperature channel 2 [2] = SME temperature channel 3 [3] = SME temperature channel 4		
Note:	An invalid temperature is displayed using the value -200°C.		

p4700[0...1]	Trace control / Trace control		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Values:	0: Stop trace 1: Start trace		
Index:	[0] = Trace 0 [1] = Trace 1		

p4701	Measuring function, control / Meas fct ctrl		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Values:	0: Stop measuring function 1: Start measuring function 2: Measuring function, check parameterization		

r4705[0...1]	Trace status / Trace status		
CU_S	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 4	Factory setting 0
Description:	Displays the current status of the trace.		
Values:	0: Trace not active 1: Trace is recording presamples 2: Trace is waiting for trigger event 3: Trace is recording 4: Recording (trace) ended		
Index:	[0] = Trace 0 [1] = Trace 1		

r4706	Measuring function, status / Meas fct status		
CU_S	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 5	Factory setting 1
Values:	0: Measurement function inactive 1: Measuring function, parameterization checked 2: Measuring function waits for stabilizing time 3: Measuring function recording (tracing) 4: Measuring function, trace ended with error 5: Measuring function, trace successfully completed		

r4708[0...1]	Trace memory space required / Trace mem required		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the required memory in bytes for the actual parameterization.		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Refer to: r4799		
p4710[0...1]	Trace trigger condition / Trace Trig_cond		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 1	Max 7	Factory setting 2
Description:	Sets the trigger condition for the trace.		
Values:	1: Immediate start 2: Positive edge 3: Negative edge 4: Entry to hysteresis band 5: Leaving hysteresis band 6: Trigger at bit mask 7: Start with function generator		
Index:	[0] = Trace 0 [1] = Trace 1		
p4711[0...1]	Trace trigger signal / Trace trig_signal		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Selects the trigger signal for the trace. OR: Defines the data type of signal to be traced when selected using the physical address (p4789).		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only effective when p4710 does not equal 1.		
p4712[0...1]	Trace trigger threshold / Trace trig_thresh		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -340.28235E36	Max 340.28235E36	Factory setting 0.00
Description:	Sets the trigger threshold for the trace.		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only effective when p4710 = 2, 3.		

p4713[0...1]	Trace tolerance band trigger threshold / Trace trig thresh		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -340.28235E36	Max 340.28235E36	Factory setting 0.00
Description:	Sets the first trigger threshold for trigger via tolerance band.		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only effective when p4710 = 4, 5.		

p4714[0...1]	Trace tolerance band trigger threshold / Trace trig thresh		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -340.28235E36	Max 340.28235E36	Factory setting 0.00
Description:	Sets the second trigger threshold for trigger via tolerance band		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only effective when p4710 = 4, 5.		

p4715[0...1]	Trace bit mask trigger, bit mask / Trace trig mask		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Sets the bit mask for the bit mask trigger.		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only effective when p4710 = 6.		

p4716[0...1]	Trace, bit mask trigger, trigger condition / Trace Trig_cond		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Sets the trigger condition for bit mask trigger.		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only effective when p4710 = 6.		

p4717	Measuring function, number of averaging operations / Meas fct avg qty		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 255	Factory setting 0

p4718	Measuring function, number of stabilizing periods / MeasFct StabPerQty		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 255	Factory setting 0

r4719[0...1]	Trace trigger index / Trace Trig_index		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Displays the trigger index in the trace buffer. The trigger event occurred at this point.

Index:
[0] = Trace 0
[1] = Trace 1

Dependency: Only valid when p4705 = 4.

p4720[0...1]	Trace recording cycle / Trace record_cyc		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.000 [ms]	Max 60000.000 [ms]	Factory setting 1.000 [ms]

Description: Sets the recording cycle for the trace.

Index:
[0] = Trace 0
[1] = Trace 1

p4721[0...1]	Trace recording time / Trace record_time		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.000 [ms]	Max 3600000.000 [ms]	Factory setting 1000.000 [ms]

Description: Sets the recording time for the trace.

Index:
[0] = Trace 0
[1] = Trace 1

p4722[0...1]	Trace trigger delay / Trace trig_delay		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -3600000.000 [ms]	Max 3600000.000 [ms]	Factory setting 0.000 [ms]
Description:	Sets the trigger delay for the trace. Trigger delay < 0: Pretrigger: Tracing (recording) starts the selected time before the trigger event actually occurs. Trigger delay > 0: Post trigger: Tracing does not start until the set time after the trigger event.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4723[0...1]	Time slice cycle for trace / Trace cycle		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.03125 [ms]	Max 4.00000 [ms]	Factory setting 0.12500 [ms]
Description:	Sets the time slice cycle in which the trace is called.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4724[0...1]	Trace average in the time range / Trace average		
CU_S	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0000 bin	Max 0001 bin	Factory setting 0001 bin
Index:	[0] = Trace 0 [1] = Trace 1		
r4725[0...1]	Trace, data type 1 traced / Trace rec type 1		
CU_S	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Index:	[0] = Trace 0 [1] = Trace 1		
r4726[0...1]	Trace, data type 2 traced / Trace rec type 2		
CU_S	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Index:	[0] = Trace 0 [1] = Trace 1		

r4727[0...1]	Trace, data type 3 traced / Trace rec type 3		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Index:	[0] = Trace 0 [1] = Trace 1		
r4728[0...1]	Trace, data type 4 traced / Trace rec type 4		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Index:	[0] = Trace 0 [1] = Trace 1		
r4729[0...1]	Trace number of recorded values / Trace rec values		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of traced values for each signal.		
Index:	[0] = Trace 0 [1] = Trace 1		
Dependency:	Only valid when p4705 = 4.		
p4730[0...1]	Trace record signal 0 / Trace record sig 0		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects the first signal to be traced. For trace with a physical address (p4780), the data type of the signal to be traced (recorded) is set here.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4731[0...1]	Trace record signal 1 / Trace record sig 1		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects the second signal to be traced. For trace with a physical address (p4781), the data type of the signal to be traced (recorded) is set here.		
Index:	[0] = Trace 0 [1] = Trace 1		

p4732[0...1] Trace record signal 2 / Trace record sig 2

CU_S	Can be changed: U, T	Access level: 3
	Data type: Unsigned32	Dynamic index: -
	P-Group: Trace and function generator	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0

Description: Selects the third signal to be traced.
For trace with a physical address (p4782), the data type of the signal to be traced (recorded) is set here.

Index:
[0] = Trace 0
[1] = Trace 1

p4733[0...1] Trace record signal 3 / Trace record sig 3

CU_S	Can be changed: U, T	Access level: 3
	Data type: Unsigned32	Dynamic index: -
	P-Group: Trace and function generator	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0

Description: Selects the fourth signal to be traced.
For trace with a physical address (p4783), the data type of the signal to be traced (recorded) is set here.

Index:
[0] = Trace 0
[1] = Trace 1

r4740[0...16383] Trace 0 trace buffer signal 0 floating point / Trace 0 trace sig0

CU_S	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Trace and function generator	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		-

Description: Displays the trace buffer (record buffer) for trace 0 and signal 0.
The trace (record) buffer is sub-divided into memory banks, each containing 500 values. Parameter p4795 can be used to toggle between the individual banks.
Example A:
The first 500 values of signal 0, trace 0 are to be read-out.
In this case, memory bank 0 is set with p4795 = 0. The first 500 values can only be read-out using r4740[0] to r4740[499].
Example B:
The values 750 to 800 from signal 0, trace 0 are to be read-out.
In this case, memory bank 1 is set with p4795 = 1. The values can now be read out in r4740[250] to r4740[299].

Dependency: Refer to: p4795

r4741[0...16383] Trace 0 trace buffer signal 1 floating point / Trace 0 trace sig1

CU_S	Can be changed: -	Access level: 3
	Data type: Floating Point	Dynamic index: -
	P-Group: Trace and function generator	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		-

Description: Displays the trace buffer (record buffer) for trace 0 and signal 1.

Dependency: Refer to: r4740, p4795

r4742[0...16383] Trace 0 trace buffer signal 2 floating point / Trace 0 trace sig2

CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the trace buffer (record buffer) for trace 0 and signal 2.		
Dependency:	Refer to: r4740, p4795		

r4743[0...16383] Trace 0 trace buffer signal 3 floating point / Trace 0 trace sig3

CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the trace buffer (record buffer) for trace 0 and signal 3.		
Dependency:	Refer to: r4740, p4795		

r4750[0...16383] Trace 1 trace buffer signal 0 floating point / Trace 1 trace sig0

CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the trace buffer (record buffer) for trace 1 and signal 0.		
Dependency:	Refer to: r4740, p4795		

r4751[0...16383] Trace 1 trace buffer signal 1 floating point / Trace 1 trace sig1

CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the trace buffer (record buffer) for trace 1 and signal 1.		
Dependency:	Refer to: r4740, p4795		

r4752[0...16383] Trace 1 trace buffer signal 2 floating point / Trace 1 trace sig2

CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the trace buffer (record buffer) for trace 1 and signal 2.		
Dependency:	Refer to: r4740, p4795		

r4753[0...16383] Trace 1 trace buffer signal 3 floating point / Trace 1 trace sig3

CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the trace buffer (record buffer) for trace 1 and signal 3.		
Dependency:	Refer to: r4740, p4795		

r4760[0...16383] Trace 0 trace buffer signal 0 / Trace 0 trace sig0

CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

r4761[0...16383] Trace 0 trace buffer signal 1 / Trace 0 trace sig1

CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

r4762[0...16383] Trace 0 trace buffer signal 2 / Trace 0 trace sig2

CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

r4763[0...16383] Trace 0 trace buffer signal 3 / Trace 0 trace sig3

CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

p4780[0...1] Trace physical address signal 0 / Trace PhyAddr Sig0

CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex
Description:	Sets the physical address for the first signal to be traced. The data type is defined using p4730.		
Index:	[0] = Trace 0 [1] = Trace 1		

p4781[0...1]	Trace physical address signal 1 / Trace PhyAddr Sig1		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the physical address for the second signal to be traced. The data type is defined using p4731.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4782[0...1]	Trace physical address signal 2 / Trace PhyAddr Sig2		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the physical address for the third signal to be traced. The data type is defined using p4732.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4783[0...1]	Trace physical address signal 3 / Trace PhyAddr Sig3		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the physical address for the fourth signal to be traced. The data type is defined using p4733.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4789[0...1]	Trace physical address trigger signal / Trace PhyAddr Trig		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the physical address for the trigger signal. The data type is defined by making the appropriate selection in p4711.		
Index:	[0] = Trace 0 [1] = Trace 1		
p4795	Trace memory bank changeover / Trace mem changeov		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 500	Factory setting 0
Description:	Changes over the memory bank to read-out the contents of the trace buffer.		
Dependency:	Refer to: r4740, r4741, r4742, r4743, r4750, r4751, r4752, r4753		

r4799	Trace memory location free / Trace mem free		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the free memory for the trace in bytes.		
Dependency:	Refer to: r4708		

p4800	Function generator control / FG control		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	2	0
Description:	The function generator is started with p4800 = 1. The signal is only generated for a 1 signal of BI: p4819.		
Values:	0: Stop function generator 1: Start function generator 2: Check function generator parameterization		
Dependency:	Refer to: p4819		

r4805	Function generator status / FG status		
CU_S	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	6	0
Description:	Displays the actual status of the function generator.		
Values:	0: not active 1: Generate accelerating ramp to offset 2: Generate parameterized signal shape 3: Generate braking ramp 4: Function generator stopped due to missing enable signals 5: Function generator waits for BI: p4819 6: Function generator parameterization has been checked		
Dependency:	Refer to: p4800, p4819		

r4806	BO: Function generator status signal / FG status signal		
CU_S	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the status of the function generator. 0 signal: Function generator inactive 1 signal: Function generator running		

p4810	Function generator mode / FG operating mode		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 0
Description:	Sets the operating mode of the function generator.		
Values:	0: Connection at connector output r4818 1: Connection at current setpoint after filter and r4818 2: Connection as disturbing torque and r4818 3: Connection at speed setpoint after filter and r4818 4: Connection at current setpoint before filter and r4818 5: Connection at speed setpoint before filter and r4818 99: Connection at physical address and r4818		
p4812	Function generator physical address / FG phys address		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Sets the physical address where the function generator is to be connected.		
Dependency:	Only effective when p4810 = 99.		
p4813	Function generator physical address reference value / FG phys addr ref		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 1.00	Max 1000000.00	Factory setting 1.00
Description:	Sets the reference value for 100 % for referred inputs.		
Dependency:	Only effective when p4810 = 99.		
p4815[0...2]	Function generator drive number / FG drive number		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Selects the required drive where the function generator is to be connected.		
Index:	[0] = First drive for connection [1] = Second drive for connection [2] = Third drive for connection		
Dependency:	Only effective when p4810 = 1, 2, 3, 4 or 5.		
Note:	For the function generator, only type SERVO drives can be used.		

r4818	CO: Function generator output signal / FG output signal		
CU_S	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the output signal for the function generator.		
Dependency:	Refer to: p4810		
Note:	The value is displayed independently of the function generator mode. The signal is available as connector output for an ongoing interconnection.		
p4819	BI: Function generator control / FG control		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 1
Description:	Sets the signal source to control the function generator. When the function generator is running, signal generation is stopped with a 0 signal from BI: p4819 and p4800 is set to 0.		
Dependency:	Refer to: p4800		
p4820	Function generator signal shape / FG signal shape		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 1	Max 5	Factory setting 1
Description:	Sets the signal to be generated for the function generator.		
Values:	1: Square-wave 2: Staircase 3: Triangular 4: Binary noise - PRBS (Pseudo Random Binary Signal) 5: Sinusoidal		
p4821	Function generator period / FG period duration		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 60000.00 [ms]	Factory setting 1000.00 [ms]
Description:	Sets the period of the signal to be generated for the function generator.		
Dependency:	Ineffective when p4820 = 4 (PRBS).		
p4822	Function generator pulse width / FG pulse width		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 60000.00 [ms]	Factory setting 500.00 [ms]
Description:	Sets the pulse width for the signal to be generated for the function generator.		

Dependency: Only effective when p4820 = 1 (square-wave).

p4823	Function generator bandwidth / FG bandwidth		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.00 [Hz]	Max 16000.00 [Hz]	Factory setting 4000.00 [Hz]
Description:	Sets the bandwidth for the signal to be generated for the function generator.		
Dependency:	Only effective when p4820 = 4 (PRBS). Refer to: p4830 Refer to: A02041		
p4824	Function generator amplitude / FG amplitude		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -1600.00 [%]	Max 1600.00 [%]	Factory setting 5.00 [%]
Description:	Sets the amplitude for the signal to be generated for the function generator.		
Dependency:	Units are dependent on p4810. If p4810 = 1, 2, 4: The amplitude is referred to p2002 (rated motor current). If p4810 = 3, 5: The amplitude is referred to p2000 (rated motor speed).		
p4825	Function generator 2nd amplitude / FG 2nd amplitude		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -1600.00 [%]	Max 1600.00 [%]	Factory setting 7.00 [%]
Description:	Sets the second amplitude for the signal to be generated for the function generator.		
Dependency:	Only effective for p4820 = 2 (staircase). Units are dependent on p4810. If p4810 = 1, 2, 4: The amplitude is referred to p2002 (rated motor current). If p4810 = 3, 5: The amplitude is referred to p2000 (rated motor speed).		
p4826	Function generator offset / FG offset		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -1600.00 [%]	Max 1600.00 [%]	Factory setting 0.00 [%]
Description:	Sets the offset (DC component) of the signal to be generated for the function generator.		
Dependency:	Units are dependent on p4810. If p4810 = 1, 2, 4: The offset is referred to p2002 (rated motor current). If p4810 = 3, 5: The offset is referred to p2000 (rated motor speed). If p4810 = 2: In order to avoid effects of play (backlash), the offset does not act on the current setpoint, but instead on the speed setpoint.		

p4827	Function generator ramp-up time to offset / FG ramp-up offset		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 100000.00 [ms]	Factory setting 32.00 [ms]
Description:	Sets the ramp-up time to the offset for the function generator.		
p4828	Function generator lower limit / FG lower limit		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -10000.00 [%]	Max 0.00 [%]	Factory setting -100.00 [%]
Description:	Sets the lower limit for the function generator.		
Dependency:	For p4810 = 2 the limit only applies to the current setpoint, but not the speed setpoint (offset).		
p4829	Function generator upper limit / FG upper limit		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.00 [%]	Max 10000.00 [%]	Factory setting 100.00 [%]
Description:	Sets the upper limit for the function generator.		
Dependency:	For p4810 = 2 the limit only applies to the current setpoint, but not the speed setpoint (offset).		
p4830	Function generator time slice cycle / FG time slice		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.03125 [ms]	Max 2.00000 [ms]	Factory setting 0.12500 [ms]
Description:	Sets the time slice cycle in which the function generator is called.		
p4831	Function generator amplitude scaling / FG amplitude scal		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min 0.00000 [%]	Max 200.00000 [%]	Factory setting 100.00000 [%]
Description:	Sets the scaling for the amplitude of the signal waveforms for all output channels. The value can be changed while the function generator is running.		

p4832[0...2]	Function generator amplitude scaling / FG amplitude scal		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -340.28235E36 [%]	Max 340.28235E36 [%]	Factory setting 100.00000 [%]
Description:	Sets the scaling for the amplitude of the signal waveforms separately for each output channel. The value cannot be changed while the function generator is running.		
Index:	[0] = First drive for connection [1] = Second drive for connection [2] = Third drive for connection		

p4833[0...2]	Function generator offset scaling / FG offset scal		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Trace and function generator	Units group: -	Unit selection: -
	Min -340.28235E36 [%]	Max 340.28235E36 [%]	Factory setting 100.00000 [%]
Description:	Sets the scaling for the offset of the signal waveforms separately for each output channel. The value cannot be changed while the function generator is running.		
Index:	[0] = First drive for connection [1] = Second drive for connection [2] = Third drive for connection		

r4899	Status word sequence control / ZSW seq ctrl				
TM41	Can be changed: -		Access level: 2		
	Data type: Unsigned16	Dynamic index: -	Function diagram: -		
	P-Group: Displays, signals	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays the status word of the sequence control from terminal module 41 (TM41).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Ready to power up	Yes	No	-
	01	Ready	Yes	No	-
	02	Operation enabled	Yes	No	-
	03	Fault present	Yes	No	-
	04	Coast down active	No	Yes	-
	05	Fast stop active	No	Yes	-
	06	Power-on inhibit	Yes	No	-
	07	Alarm present	Yes	No	-
	09	Control requested	Yes	No	-
	14	Motor rotates forwards	Yes	No	-

r4950	OA application count / OA appl qty		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min 0	Max 10	Factory setting 0
Description:	Displays the number of OA applications installed on the CompactFlash card.		
Dependency:	Refer to: r4951, r4952, r4955, p4956, r4957, r4958, r4959, r4960		
Note:	OA: Open Architecture		

r4951	OA application identifier, total length / OA appl ID length		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min 0	Max 90	Factory setting 0
Description:	Displays the total length of the identifiers of all of the OA applications installed on the CompactFlash card. The identifier of an OA application comprises a maximum of 8 characters plus separator.		
Dependency:	Refer to: r4950, r4952, r4955, p4956, r4957, r4958, r4959, r4960		
r4952	OA application GUID, total length / OA applGUID length		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min 0	Max 180	Factory setting 0
Description:	Displays the total length of the GUIDs of all of the OA applications installed on the CompactFlash card. The GUID of an OA application comprises 16 characters plus 1 character major information plus 1 character, minor information.		
Dependency:	Refer to: r4950, r4951, r4955, p4956, r4957, r4958, r4959, r4960		
Note:	GUID: Globally Unique Identifier		
r4955[0...n]	OA application identifier / OA appl identifier		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned8	Dynamic index: r4951	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the identifiers of all of the OA applications installed on the CompactFlash card. r4955[0...8]: Identifier of OA application 1 r4955[9...17]: Identifier of OA application 2 etc.		
Dependency:	Refer to: r4950, r4951, r4952, p4956, r4957, r4958, r4959, r4960		
p4956[0...n]	OA application activation / OA appl act		
All objects	Can be changed: C1, T		Access level: 4
	Data type: Integer16	Dynamic index: r4950	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Setting to activate the OA applications installed on the CompactFlash card. r4956[0]: Activates OA application 1 r4956[1]: Activates OA application 2 etc.		
Values:	0: OA application inactive 1: OA application active		
Dependency:	Refer to: r4950, r4951, r4952, r4955, r4957, r4958, r4959, r4960		

r4957[0...n]	OA application version / OA appl version		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: r4950	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the version of OA applications installed on the CompactFlash card. r4957[0]: Version of OA application 1 r4957[1]: Version of OA application 2 etc.		
Dependency:	Refer to: r4950, r4951, r4952, r4955, p4956, r4958, r4959, r4960		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		

r4958[0...n]	OA application interface version / OA appl intfc_vers		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: r4950	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the interface version of the OA applications installed on the CompactFlash card. r4958[0]: Interface version of OA application 1 r4958[1]: Interface version of OA application 2 etc.		
Dependency:	Refer to: r4950, r4951, r4952, r4955, p4956, r4957, r4959, r4960		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		

r4959[0...n]	OA application GUID / OA appl GUID		
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned8	Dynamic index: r4952	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the GUIDs of OA applications installed on the CompactFlash card. r4959[0...15]: GUID of OA application 1 r4960[16]: Major information of OA application 1 r4960[16]: Minor information of OA application 1 r4959[18...33]: GUID of OA application 2 r4960[34]: Major information of OA application 2 r4960[35]: Minor information of OA application 2 etc.		
Dependency:	Refer to: r4950, r4951, r4952, r4955, p4956, r4957, r4958, r4960		

r4960[0...n]		OA application GUID drive object / OA appl GUID DO	
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned8	Dynamic index: r4952	Function diagram: -
	P-Group: OEM range	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the GUIDs of this drive object of the OA applications installed on the CompactFlash card. r4960[0...15]: GUID of this drive object of OA application 1 r4960[16]: Major information of this drive object of OA application 1 r4960[17]: Minor information of this drive object of OA application 1 r4960[18...33]: GUID of this drive object of OA application 2 r4960[34]: Major information of this drive object of OA application 2 r4960[35]: Minor information of this drive object of OA application 2 etc.		
Dependency:	Refer to: r4950, r4951, r4952, r4955, p4956, r4957, r4958, r4959		

p6651		BI: Test mode, signal source ON/OFF / Test s_src ON/OFF	
SERVO, VECTOR	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to switch-in/switch-out the test. The test mode is set using p6650.		

r7000		Par_circuit No. of active power units / Qty active LT	
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the active power units for a parallel circuit configuration.		
Dependency:	Refer to: p7001		

p7001[0...n]		Par_circuit enable power units / Enable LT	
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	1	1
Description:	Enables the power units in the parallel circuit configuration.		
Values:	0: Deactivated 1: Activated		
Dependency:	Refer to: r7000		

r7002[0...n]	Par_circuit status power units / Status LT		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Displays the status of the power units in the parallel circuit configuration.		
Values:	0: Pulses inhibited 1: Pulses enabled		
Dependency:	Refer to: r7000, p7001		
p7003	Par_circuit winding system / Winding system		
VECTOR (Parallel)	Can be changed: C2(2)	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Specifies the winding system for a parallel circuit configuration. The following limitations/restrictions are obtained depending on the setting: One winding system (p7003 = 0): - the motor data identification routine (p1910) determines the stator resistance and the cable resistance. - the current symmetrizing is activated as standard after the motor data identification routine (p7035 = 1). - individual Motor Modules can be activated and de-activated (p7001). - the edge modulation is not possible (p1802). Several separate winding systems or motors (p7003 = 1): - the motor data identification routine (p1910) determines the total (overall) resistance. - the current symmetrizing is de-activated as standard (p7035 = 0). - all Motor Modules are activated. It is not possible to de-activate a motor model. - the edge modulation can be activated (p1802).		
Values:	0: One winding system 1: Several separate winding systems or motors		
Dependency:	Refer to: p1802		
p7010	Par_circuit current dissymmetry alarm threshold / i_dissym A thresh		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 2 [%]	Max 100 [%]	Factory setting 20 [%]
Description:	Sets the alarm threshold to detect current dissymmetry in the parallel circuit configuration. The deviation between the measured values and average value is evaluated. The specified value is referred to the rated power unit current (p7251[0]).		
Dependency:	Refer to: r7251 Refer to: A05052		

p7011	Par_circuit DC link voltage dissymmetry, alarm threshold / Vdc_dissym A thrsh		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 2 [%]	Max 100 [%]	Factory setting 10 [%]
Description:	Sets the alarm threshold to detect dissymmetry of the DC link voltages in the parallel circuit configuration. The deviation between the measured values and average value is evaluated. The specified value is referred to the rated link voltage.		
Dependency:	Refer to: A05053		
r7020[0...n]	CO: Par_circuit deviation current in phase U / Phase U curr dev		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the deviation between the measured current actual value of phase U and the average value as peak value. The maximum deviation from the average value is displayed in r7025.		
Dependency:	Refer to: r7021, r7022, r7025		
r7021[0...n]	CO: Par_circuit deviation current in phase V / Phase V curr dev		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the deviation between the measured current actual value of phase V and the average value as peak value. The maximum deviation from the average value is displayed in r7026.		
Dependency:	Refer to: r7020, r7022, r7026		
r7022[0...n]	CO: Par_circuit deviation current in phase W / Phase W curr dev		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the deviation between the measured current actual value of phase W and the average value as peak value. The maximum deviation from the average value is displayed in r7027.		
Dependency:	Refer to: r7020, r7021, r7027		

r7025	CO: Par_circuit max. deviation currents phase U / Phase U Max i_dev		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the maximum absolute deviation of the measured current actual values of phase U from the average value as peak value. The deviation of the individual currents from the average value is displayed in r7020.		
Dependency:	Refer to: r7020, r7026, r7027 Refer to: A05052		
r7026	CO: Par_circuit max. deviation currents phase V / Phase V Max i_dev		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the maximum absolute deviation of the measured current actual values of phase V from the average value as peak value. The deviation of the individual currents from the average value is displayed in r7021.		
Dependency:	Refer to: r7021, r7025, r7027 Refer to: A05052		
r7027	CO: Par_circuit max. deviation currents phase W / Phase W Max i_dev		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the maximum absolute deviation of the measured current actual values of phase W from the average value as peak value. The deviation of the individual currents from the average value is displayed in r7022.		
Dependency:	Refer to: r7022, r7025, r7026 Refer to: A05052		
r7030[0...n]	CO: Par_circuit DC link voltage deviation / Vdc deviation		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the deviation of the measured DC link voltage from the average value. The maximum deviation from the average value is displayed in r7031.		
Dependency:	Refer to: r7031		

r7031	CO: Par_circuit DC link voltage, maximum deviation / Vdc deviation max.		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the maximum absolute deviation of the measured DC link voltage from the average value. The deviation of the individual voltages from the average value is displayed in r7030.		
Dependency:	Refer to: r7030 Refer to: A05053		
p7035	Infeed par_circuit circulating current control, operating mode / Circ_I mode		
A_INF (Parallel), S_INF (Parallel)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Sets the operating mode of the circulating current control. The circulating current control ensures symmetrical distribution of the total currents to the individual converters.		
Values:	0: Circulating current control de-activated 1: Circulating control control activated		
p7035[0...n]	Par_circuit circulating current control, operating mode / Circ_I mode		
VECTOR (Parallel)	Can be changed: U, T	Dynamic index: DDS, p0180	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	Sets the operating mode of the circulating current control. The circulating current control ensures symmetrical distribution of the total currents to the individual converters.		
Values:	0: Circulating current control de-activated 1: Circulating control control activated		
p7036	Infeed par_cct circulating current controller, proportional gain / Circ_I Kp		
A_INF (Parallel), S_INF (Parallel)	Can be changed: U, T	Dynamic index: -	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00000 [%]	Max 1000.00000 [%]	Factory setting 100.00000 [%]
Description:	Sets the normalized proportional gain for the circulating current controller.		
Note:	A value of 100 % corresponds to the basic setting derived from loop control parameters (p3421, p3622).		

p7036[0...n]	Par_circuit circulating current control, proportional gain / Circ_I Kp		
VECTOR (Parallel)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00000 [Ohm]	Max 20.00000 [Ohm]	Factory setting 0.00000 [Ohm]
Description:	Sets the proportional gain for the circulating current controller. The parameter is pre-set to the cable resistance.		

p7037	Infeed par_cct circulating current control, integral time / Circ_I TN		
A_INF (Parallel), S_INF (Parallel)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.0 [%]	Max 100000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the normalized integral time of the circulating current controller.		
Note:	A value of 100 % corresponds to the basic setting derived from the controller sampling time p0115[0]. The integral component of the controller is de-activated with p7037 = 0.		

p7037[0...n]	Par_circuit circulating current control, integral time / Circ_I TN		
VECTOR (Parallel)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 2.0	Max 1000.0	Factory setting 4.0
Description:	Sets the integral time of the circulating current controller. The parameter is referred to the current controller sampling time p0115[0].		
Dependency:	Refer to: p0115		

p7038	Infeed par_circuit circulating current control, limit / Circ_I limit		
A_INF (Parallel), S_INF (Parallel)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 1 [%]	Max 100 [%]	Factory setting 100 [%]
Description:	Sets the limit of the circulating current controller output values. The parameter is, depending on the phase, referred to the valve lockout times p1828, p1829 or p1830.		

p7038[0...n]	Par_circuit circulating current control, limit / Circ_I limit		
VECTOR (Parallel)	Can be changed: U, T		Access level: 3
	Data type: Floating Point	Dynamic index: DDS, p0180	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 1 [%]	Max 100 [%]	Factory setting 50 [%]
Description:	Sets the limit of the circulating current controller output values. The parameter is, depending on the phase, referred to the valve lockout times p1828, p1829 or p1830.		

p7040[0...n]	Par_circuit correction, valve lockout time phase U / Comp t_lockout U		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 1000000.00 [µs]	Factory setting 0.00 [µs]
Description:	For the particular Motor Module, the correction time must be added to the valve lockout time to be compensated for phase U (p1828). The correction value is used to compensate variations/spread in the valve lockout times of Motor Modules for a parallel circuit configuration.		
Dependency:	Refer to: p1828		
p7042[0...n]	Par_circuit correction, valve lockout time phase V / Comp t_lockout V		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 1000000.00 [µs]	Factory setting 0.00 [µs]
Description:	For the particular Motor Module, the correction time must be added to the valve lockout time to be compensated for phase V (p1829). The correction value is used to compensate variations/spread in the valve lockout times of Motor Modules for a parallel circuit configuration.		
Dependency:	Refer to: p1829		
p7044[0...n]	Par_circuit correction, valve lockout time phase W / Comp t_lockout W		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Modulation	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 1000000.00 [µs]	Factory setting 0.00 [µs]
Description:	For the particular Motor Module, the correction time must be added to the valve lockout time to be compensated for phase W (p1830). The correction value is used to compensate variations/spread in the valve lockout times of Motor Modules for a parallel circuit configuration.		
Dependency:	Refer to: p1830		
r7050[0...n]	Par_circuit circulating current phase U / Circ_I_phase U		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the circulating current of phase U as peak value.		

r7051[0...n] Par_circuit circulating current phase V / Circ_I_phase V

A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]

Description: Displays the circulating current of phase V as peak value.

r7052[0...n] Par_circuit circulating current phase W / Circ_I_phase W

A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]

Description: Displays the circulating current of phase W as peak value.

r7100[0...99] Par_circuit ring buffer fault/alarm code / Fault/alarm code

A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Ring buffer for faults and alarms that have occurred from power units connected in parallel (Motor Module, Active Line Infeed, Voltage Sensing Module).
Displays the fault/alarm code.

Dependency: Refer to: r7101, r7102, r7103

Note: The last fault case that occurred is documented in index 0.
The parameter is reset to 0 at POWER ON.

r7101[0...99] Par_circuit ring buffer data set number / Ring buffer Ds_No.

A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Ring buffer for faults and alarms that have occurred from power units connected in parallel (Motor Module, Active Line Infeed, Voltage Sensing Module).
p7101 < 100:
Displays the Power unit Data Set number (PDS).
p7101 >= 100:
Displays the Voltage Sensing Module Data Set number (VSMDS)

Dependency: Refer to: r7100, r7102, r7103

Note: The last fault case that occurred is documented in index 0.
The parameter is reset to 0 at POWER ON.

r7102[0...99]	Par_circuit ring buffer fault/alarm received / F/A received		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Ring buffer for faults and alarms that have occurred from power units connected in parallel (Motor Module, Active Line Infeed, Voltage Sensing Module). Displays the relative system runtime when the fault or alarm occurred.		
Dependency:	Refer to: r7100, r7101, r7103		
Note:	The last fault case that occurred is documented in index 0. The parameter is reset to 0 at POWER ON.		
r7103[0...99]	Par_circuit ring buffer fault/alarm gone / F/A gone		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Ring buffer for faults and alarms that have occurred from power units connected in parallel (Motor Module, Active Line Infeed, Voltage Sensing Module). Displays the relative system runtime when the fault or alarm was withdrawn.		
Dependency:	Refer to: r7100, r7101, r7102		
Note:	The last fault case that occurred is documented in index 0. The parameter is reset to 0 at POWER ON.		
r7200[0...n]	Par_circuit power unit overload I2T / LT overload I2T		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the overload of the particular power unit in a parallel circuit configuration calculated using the I2t function. The maximum value of all power units is displayed in r0036.		
r7201[0...n]	Par_circuit power unit temperatures max. inverter / LT temp max inv		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the maximum inverter temperature in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[0].		

r7202[0...n] Par_circuit power unit temperatures max. depletion layer / LT TempMaxDepLayer

A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]

Description: Displays the maximum depletion layer temperature in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[1].

r7203[0...n] Par_circuit power unit temperatures max. rectifier / LT temp max rect

A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]

Description: Displays the maximum rectifier temperature in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[2].

r7204[0...n] Par_circuit power unit temperatures air intake / LT temp air intake

A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]

Description: Displays the air intake temperature in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[3].

r7205[0...n] Par_circuit power unit temperatures electronics / LT temp electr

A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]

Description: Displays the temperature of the electronics module in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[4].

r7206[0...n]	Par_circuit power unit temperatures inverter 1 / LT temp inv 1		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the inverter temperature 1 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[5].		
r7207[0...n]	Par_circuit power unit temperatures inverter 2 / LT temp inv 2		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the inverter temperature 2 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[6].		
r7208[0...n]	Par_circuit power unit temperatures inverter 3 / LT temp inv 3		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the inverter temperature 3 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[7].		
r7209[0...n]	Par_circuit power unit temperatures inverter 4 / LT temp inv 4		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the inverter temperature 4 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[8].		

r7210[0...n]	Par_circuit power unit temperatures inverter 5 / LT temp inv 5		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the inverter temperature 5 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[9].		

r7211[0...n]	Par_circuit power unit temperatures inverter 6 / LT temp inv 6		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the inverter temperature 6 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[10].		

r7212[0...n]	Par_circuit power unit temperatures inverter 1 / LT temp rect 1		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays rectifier temperature 1 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[11].		

r7213[0...n]	Par_circuit power unit temperatures inverter 2 / LT temp rect 2		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: PDS, p0120	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays rectifier temperature 2 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[12].		

r7214[0...n]	Par_circuit power unit temperatures depletion layer 1 / LT temp DepLayer 1		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays depletion layer temperature 1 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[13].		

r7215[0...n]	Par_circuit power unit temperatures depletion layer 2 / LT temp DepLayer 2		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays depletion layer temperature 2 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[14].		

r7216[0...n]	Par_circuit power unit temperatures depletion layer 3 / LT temp DepLayer 3		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays depletion layer temperature 3 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[15].		

r7217[0...n]	Par_circuit power unit temperatures depletion layer 4 / LT temp DepLayer 4		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays depletion layer temperature 4 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[16].		

r7218[0...n]	Par_circuit power unit temperatures depletion layer 5 / LT temp DepLayer 5		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays depletion layer temperature 5 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[17].		
r7219[0...n]	Par_circuit power unit temperatures depletion layer 6 / LT temp DepLayer 6		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 21_1	Unit selection: p0505
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays depletion layer temperature 6 in the power unit for a parallel circuit configuration. The maximum value of all power units is displayed in r0037[18].		
r7220[0...n]	Infeed par_circuit absolute current value, motoring permissible / INF I_abs mot perm		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the currently permissible line-side absolute current when motoring. The minimum value of all power units multiplied by the number of Motor Modules is displayed in r0067[0].		
r7220[0...n]	CO: Par_circuit drive output current, maximum / Drv I_output max		
VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the maximum output current of the power unit. The minimum value of all power units multiplied by the number of Motor Modules is displayed in r0067.		
r7221[0...n]	Infeed par_circuit absolute current regenerating, permissible / INF I_absRegenPerm		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the currently permissible line-side absolute regenerative current. The minimum value of all power units multiplied by the number of Motor Modules is displayed in r0067[1].		

r7222[0...n]	CO: Par_circuit absolute current actual value / I_act abs.val.		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_2	Unit selection: p0505
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays actual absolute current. The summed value of all power units is displayed in r0068.		
r7223[0...n]	CO: Par_circuit phase current, actual value phase U / I_phase U act val		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured actual value of phase U as peak value. The summed value of all power units is displayed in r0069[0].		
r7224[0...n]	CO: Par_circuit phase current, actual value phase V / I_phase V act val		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured actual value of phase V as peak value. The summed value of all power units is displayed in r0069[1].		
r7225[0...n]	CO: Par_circuit phase current, actual value phase W / I_phase W act val		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured actual value of phase W as peak value. The summed value of all power units is displayed in r0069[2].		
r7226[0...n]	CO: Par_circuit phase current actual value, phase U offset / I_phase U offset		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured offset of phase U as peak value. The summed value of all power units is displayed in r0069[3].		

r7227[0...n]	CO: Par_circuit phase current, actual value, phase V offset / I_phase V offset		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured offset of phase V as peak value. The summed value of all power units is displayed in r0069[4].		

r7228[0...n]	CO: Par_circuit phase current, actual value, phase W offset / I_phase W offset		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured offset of phase W as peak value. The summed value of all power units is displayed in r0069[5].		

r7229[0...n]	CO: Par_circuit phase current actual value sum U, V, W / I_phase sum UVW		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 6_5	Unit selection: p0505
	Min - [A]	Max - [A]	Factory setting - [A]
Description:	Displays the measured sum of the currents in phases U, V and W as peak value. The summed value of all power units is displayed in r0069[6].		

r7230[0...n]	CO: Par_circuit DC link voltage actual value / Vdc_act		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 5_2	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the measured actual value of the DC link voltage. The average value of all power units is displayed in r0070.		

r7231[0...n]	CO: Par_circuit phase voltage, actual value phase U / U_phase U act val		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual voltage, phase U. The average value of all power units is displayed in r0089[0].		

r7232[0...n]	CO: Par_circuit phase voltage, actual value phase V / U_phase V act val		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual voltage, phase V. The average value of all power units is displayed in r0089[1].		

r7233[0...n]	CO: Par_circuit phase voltage, actual value phase W / U_phase W act val		
A_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: PDS, p0120	Function diagram: -
	P-Group: Displays, signals	Units group: 5_3	Unit selection: p0505
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual voltage, phase W. The average value of all power units is displayed in r0089[2].		

r7250[0...4]	Par_circuit power unit rated power / LT P_rated		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: 14_6	Unit selection: p0100
	Min - [kW]	Max - [kW]	Factory setting - [kW]
Description:	Displays the rated power of the individual power units connected in parallel for various load duty cycles. The sum of the rated powers of all power units connected in parallel is displayed in r0206.		
Index:	[0] = Rating plate [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 load duty cycle [4] = S6 load duty cycle		
Dependency:	The value is displayed in [kW] or [hp]. Refer to: p0100, p0205		

r7251[0...4]	Par_circuit power unit rated current / LT PI_rated		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the rated current of the individual power units connected in parallel for various load duty cycles. The sum of the rated currents of all power units connected in parallel is displayed in r0207.		
Index:	[0] = Rating plate [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 load duty cycle [4] = S6 load duty cycle		
Dependency:	Refer to: p0205		

r7252[0...4]	Par_circuit maximum power unit current / LT I_max		
A_INF (Parallel), B_INF (Parallel), S_INF (Parallel), VECTOR (Parallel)	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Floating Point		Function diagram: -
	P-Group: Converter	Units group: -	Unit selection: -
	Min - [Aeff]	Max - [Aeff]	Factory setting - [Aeff]
Description:	Displays the maximum output current of the individual power units connected in parallel. The sum of the maximum currents of all power units connected in parallel is displayed in r0209.		
Index:	[0] = Rating plate [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 load duty cycle [4] = S6 load duty cycle		
Dependency:	Refer to: p0205		
r7300[0...n]	CO: Par_circuit VSM input line voltage u1 - u2 / VSM input u1-u2		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -	Dynamic index: p0140	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the voltage between phases L1 and L2 of the particular Voltage Sensing Module (VSM) for a parallel circuit configuration. The average value of all VSM is displayed in r3661.		
Dependency:	Refer to: p3660		
Note:	X521.1 or X522.1: Connection of L1 X521.2 or X522.2: Connection of L2		
r7301[0...n]	CO: Par_circuit VSM input line voltage u2 - u3 / VSM input u2-u3		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -	Dynamic index: p0140	Access level: 3
	Data type: Floating Point		Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the voltage between phases L2 and L3 of the particular Voltage Sensing Module (VSM) for a parallel circuit configuration. The average value of all VSM is displayed in r3662.		
Dependency:	Refer to: p3660		
Note:	X521.2 or X522.2: Connection of L2 X521.3 or X522.3: Connection of L3		

r7305[0...n]	Par_circuit VSM temperature evaluation, status / VSM temp status			
A_INF (Parallel), S_INF (Parallel)	Can be changed: -			Access level: 3
	Data type: Unsigned16	Dynamic index: p0140		Function diagram: -
	P-Group: Terminals	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Displays the status of the temperature evaluation of the particular Voltage Sensing Module (VSM) for a parallel circuit configuration. This displays as to whether the temperature actual value has exceeded the fault/alarm threshold. The overall status of the temperature evaluation of all VSM is displayed in r3664.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Temperature alarm threshold exceeded	Yes	No
	01	Temperature fault threshold exceeded	Yes	No
Dependency:	Refer to: p3665, r3666, p3667, p3668			
r7306[0...n]	CO: Par_circuit VSM temperature KTY / VSM temp KTY			
A_INF (Parallel), S_INF (Parallel)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: p0140		Function diagram: -
	P-Group: Closed-loop control	Units group: 21_1		Unit selection: p0505
	Min - [°C]	Max - [°C]		Factory setting - [°C]
Description:	Displays the temperature actual value of the KTY84 temperature sensor connected to the Voltage Sensing Module (VSM) for a parallel circuit configuration. The maximum value of all VSM is displayed in r3666. Prerequisite: A KTY84 sensor is connected and p3665 is set to 2.			
Dependency:	Refer to: p3665			
r7310[0...n]	CO: Par_circuit VSM 10 V input CT1 actual value / VSM CT 1 I_act			
A_INF (Parallel), S_INF (Parallel)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: p0140		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min - [A]	Max - [A]		Factory setting - [A]
Description:	Displays the current actual value from current transducer (CT) 1 at the 10 V input of the particular Voltage Sensing Module (VSM) for a parallel circuit configuration. The average value of all VSM is displayed in r3671.			
Dependency:	Refer to: p3670			
Note:	The CT for phase 1 is connected at terminals X520.1 and X520.2 of the VSM.			
r7311[0...n]	CO: Par_circuit VSM 10 V input CT2 actual value / VSM CT 2 I_act			
A_INF (Parallel), S_INF (Parallel)	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: p0140		Function diagram: -
	P-Group: Closed-loop control	Units group: -		Unit selection: -
	Min - [A]	Max - [A]		Factory setting - [A]
Description:	Displays the current actual value from current transducer (CT) 2 at the 10 V input of the particular Voltage Sensing Module (VSM) for a parallel circuit configuration. The average value of all VSM is displayed in r3672.			
Dependency:	Refer to: p3670			
Note:	The CT for phase 2 is connected at terminals X520.3 and X520.4 of the VSM.			

r7315[0...n]	CO: Par_circuit VSM 10 V input 1 actual value / VSM input 1 U_act		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0140	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual value of the voltage measured at the 10 V input 1 of the Voltage Sensing Modules (VSM). The average value of all VSM is displayed in r3673.		
Dependency:	Refer to: p3670		
Note:	10 V input 1: Terminals X520.1 and X520.2		

r7316[0...n]	CO: Par_circuit VSM 10 V input 2 actual value / VSM input 2 U_act		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: p0140	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Displays the actual value of the voltage measured at the 10 V input 2 of the Voltage Sensing Modules (VSM). The average value of all VSM is displayed in r3674.		
Dependency:	Refer to: p3670		
Note:	10 V input 2: Terminals X520.3 and X520.4		

r7320[0...n]	Par_circuit VSM line filter capacitance phase U / VSM filt C phase U		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: p0140	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [µF]	Max - [µF]	Factory setting - [µF]
Description:	Displays the capacitance of the line filter, phase U of the particular Voltage Sensing Module (VSM). The average value of all VSM is displayed in r3677[0].		
Dependency:	Refer to: p3676		
Note:	Prerequisites: The filter capacitance monitoring is activated.		

r7321[0...n]	Par_circuit VSM line filter capacitance phase V / VSM filt C phase V		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: p0140	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [µF]	Max - [µF]	Factory setting - [µF]
Description:	Displays the capacitance of the line filter, phase V of the particular Voltage Sensing Module (VSM). The average value of all VSM is displayed in r3677[1].		
Dependency:	Refer to: p3676		
Note:	Prerequisites: The filter capacitance monitoring is activated.		

r7322[0...n]	Par_circuit VSM line filter capacitance phase W / VSM filt C phase W		
A_INF (Parallel), S_INF (Parallel)	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: p0140	Function diagram: -
	P-Group: Closed-loop control	Units group: -	Unit selection: -
	Min - [μF]	Max - [μF]	Factory setting - [μF]
Description:	Displays the capacitance of the line filter, phase W of the particular Voltage Sensing Module (VSM). The average value of all VSM is displayed in r3677[2].		
Dependency:	Refer to: p3676		
Note:	Prerequisites: The filter capacitance monitoring is activated.		
p7820	DRIVE-CLiQ component, component number / DLQ comp_no		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the component number of the DRIVE-CLiQ component whose parameters are to be accessed.		
Dependency:	Refer to: p7821, p7822, r7823		
p7821	DRIVE-CLiQ component, parameter number / DLQ para_no		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the parameter number to access a parameter of a DRIVE-CLiQ component.		
Dependency:	Refer to: p7820, p7822, r7823		
p7822	DRIVE-CLiQ component, parameter index / DLQ para_index		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the parameter index to access a parameter of a DRIVE-CLiQ component.		
Dependency:	Refer to: p7820, p7821, r7823		
r7823	DRIVE-CLiQ component, read parameter value / Read DLQ value		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the parameter value read from the DRIVE-CLiQ component.		
Dependency:	Refer to: p7820, p7821, p7822		

p7828	Firmware download component number / FW_download number		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 399	Factory setting 0
Description:	Component number of the DRIVE-CLiQ component for which a firmware download is to be made.		
Dependency:	Refer to: p0121, p0141, p0151, p7829		
Note:	For p7828 = 399, the firmware for all of the known components is downloaded. The firmware download is started with p7829 = 1.		

p7829	Activate firmware download / Act. FW_download		
CU_S	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 999	Factory setting 0
Description:	Activating the firmware download for the DRIVE-CLiQ components specified in p7828. 1: Activate download 0: Download successfully completed 1: Fault code 011: DRIVE-CLiQ component has detected a checksum error. 015: The selected DRIVE-CLiQ components did not accept the contents of the firmware file. 101: After several communication attempts, not response from the DRIVE-CLiQ component. 140: Firmware file for the DRIVE-CLiQ component not available on the CompactFlash card. 143: Component is not changed in the firmware download mode. 156: Component with the specified component number is not available. Additional values: Only for internal Siemens troubleshooting.		
Dependency:	Refer to: p7828		
Note:	p7829 is automatically set to 0 after the firmware has been successfully downloaded. The new firmware only becomes active at the next system run-up.		

p7830	Diagnostics telegram selection / Diag telegram		
SERVO, VECTOR	Can be changed: T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	Selects a telegram whose contents should be shown in p7831 ... p7836.		
Values:	0: Reserved 1: First cyclic receive telegram, sensor 1 2: First cyclic receive telegram, sensor 2 3: First cyclic receive telegram, sensor 3		
Dependency:	Refer to: r7831, r7832, r7833, r7834, r7835, r7836		

r7831[0...15] Telegram diagnostics signals / Tel diag signals		
SERVO, VECTOR	Can be changed: -	Access level: 4
	Data type: Integer16	Function diagram: -
	P-Group: -	Unit selection: -
	Min	Max
	0	10789
Description:	Displays the signals contained in the selected telegram (p7830).	
Values:	0: UNUSED 1: UNKNOWN 102: SAPAR_ID_DSA_ALARM 110: SAPAR_ALARMBITS_FLOAT_0 111: SAPAR_ALARMBITS_FLOAT_1 112: SAPAR_ALARMBITS_FLOAT_2 113: SAPAR_ALARMBITS_FLOAT_3 114: SAPAR_ALARMBITS_FLOAT_4 115: SAPAR_ALARMBITS_FLOAT_5 10500: ENC_ID_TIME_PRETRIGGER 10501: ENC_ID_TIME_SEND_TELEG_1 10502: ENC_ID_TIME_CYCLE_FINISHED 10503: ENC_ID_TIME_DELTA_FUNMAN 10504: ENC_ID_SUBTRACE_CALCTIMES 10505: ENC_ID_SYNO_PERIOD 10516: ENC_ID_ADC_TRACK_A 10517: ENC_ID_ADC_TRACK_B 10518: ENC_ID_ADC_TRACK_C 10519: ENC_ID_ADC_TRACK_D 10520: ENC_ID_ADC_TRACK_A_SAFETY 10521: ENC_ID_ADC_TRACK_B_SAFETY 10523: ENC_ID_ADC_TEMP_1 10532: ENC_ID_TRACK_AB_X 10533: ENC_ID_TRACK_AB_Y 10534: ENC_ID_OFFSET_CORR_AB_X 10535: ENC_ID_OFFSET_CORR_AB_Y 10536: ENC_ID_AB_ABS_VALUE 10537: ENC_ID_TRACK_CD_X 10538: ENC_ID_TRACK_CD_Y 10539: ENC_ID_TRACK_CD_ABS 10542: ENC_ID_AB_RAND_X 10543: ENC_ID_AB_RAND_Y 10544: ENC_ID_AB_RAND_ABS_VALUE 10545: ENC_ID_SUBTRACE_ABS_ARRAY 10546: ENC_ID_PROC_OFFSET_0 10547: ENC_ID_PROC_OFFSET_4 10564: ENC_SELFTEMP_ACT 10565: ENC_ID_MOTOR_TEMP_TOP 10566: ENC_ID_MOTOR_TEMP_1 10580: ENC_ID_RESISTANCE_1 10596: ENC_ID_AB_ANGLE 10597: ENC_ID_CD_ANGLE 10598: ENC_ID_MECH_ANGLE_HI 10599: ENC_ID_RM_POS_PHI_COMMU 10600: ENC_ID_PHI_COMMU 10612: ENC_ID_DIFF_CD_INC 10613: ENC_ID_RM_POS_PHI_COMMU_RFG 10628: ENC_ID_MECH_ANGLE 10629: ENC_ID_MECH_RM_POS 10644: ENC_ID_INIT_VECTOR 10645: FEAT_INIT_VEKTOR	
		Factory setting 111

10660: ENC_ID_SENSOR_STATE
 10661: ENC_ID_BASIC_SYSTEM
 10662: ENC_ID_REFMARK_STATUS
 10663: ENC_ID_DSA_STATUS1_SENSOR
 10664: ENC_ID_DSA_RMSTAT_HANDSHAKE
 10665: ENC_ID_DSA_CONTROL1_SENSOR
 10676: ENC_ID_COUNTCORR_SAW_VALUE
 10677: ENC_ID_COUNTCORR_ABS_VALUE
 10678: ENC_ID_SAWTOOTH_CORR
 10692: ENC_ID_RESISTANCE_CALIB_INSTANT
 10693: ENC_ID_SERPROT_POS
 10724: ENC_ID_ACT_FUNMAN_FUNCTION
 10725: ENC_ID_SAFETY_COUNTER_CRC
 10740: ENC_ID_POS_ABSOLUTE
 10741: ENC_ID_POS_REFMARK
 10742: ENC_ID_SAWTOOTH
 10743: ENC_ID_SAFETY_PULSE_COUNTER
 10756: ENC_ID_DSA_ACTUAL_SPEED
 10772: ENC_ID_DSA_POS_XIST1
 10788: ENC_ID_AB_CROSS_CORR
 10789: ENC_ID_AB_GAIN_Y_CORR

Index:
 [0] =
 [1] =
 [2] =
 [3] =
 [4] =
 [5] =
 [6] =
 [7] =
 [8] =
 [9] =
 [10] =
 [11] =
 [12] =
 [13] =
 [14] =
 [15] =

r7832[0...15] Telegram diagnostics numerical format / tel diag format

SERVO, VECTOR	Can be changed: -	Dynamic index: -	Access level: 4
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: -	Min	Unit selection: -
		Max	Factory setting
		-1	11
Description:	Indicates the original numerical format of the signals contained in the telegram. The associated signal number is represented at the appropriate index in r7831.		
Values:	-1: Unknown 0: Boolean 1: Signed 1 byte 2: Signed 2 byte 3: Signed 4 byte 4: Signed 8 byte 5: Unsigned 1 byte 6: Unsigned 2 byte 7: Unsigned 4 byte 8: Unsigned 8 byte 9: Float 4 byte		

10: Double 8 byte
 11: mm dd yy HH MM SS MS DOW
 12: ASCII string
 13: SIMUMERIK frame type
 14: SIMUMERIK axis type

Index:
 [0] =
 [1] =
 [2] =
 [3] =
 [4] =
 [5] =
 [6] =
 [7] =
 [8] =
 [9] =
 [10] =
 [11] =
 [12] =
 [13] =
 [14] =
 [15] =

r7833[0...15] Telegram diagnostics unsigned / Tel diag unsigned

SERVO, VECTOR

Can be changed: -**Data type:** Unsigned32**Dynamic index:** -**Access level:** 4**P-Group:** -**Units group:** -**Function diagram:** -**Unit selection:** -**Min****Max****Factory setting**

-

-

-

Description:

Parameter to display a DSA signal in the unsigned-integer format.

The associated signal number is represented at the appropriate index in r7831.

Index:

[0] =
 [1] =
 [2] =
 [3] =
 [4] =
 [5] =
 [6] =
 [7] =
 [8] =
 [9] =
 [10] =
 [11] =
 [12] =
 [13] =
 [14] =
 [15] =

r7834[0...15]	Telegram diagnostics signed / Tel diag signed		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Integer32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Parameter to display a DSA signal in the signed-integer format. The associated signal number is represented at the appropriate index in r7831.		
Index:	[0] = [1] = [2] = [3] = [4] = [5] = [6] = [7] = [8] = [9] = [10] = [11] = [12] = [13] = [14] = [15] =		

r7835[0...15]	Telegram diagnostics real / Tel diag real		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Parameter to display a DSA signal in the float format. The associated signal number is represented at the appropriate index in r7831.		
Index:	[0] = [1] = [2] = [3] = [4] = [5] = [6] = [7] = [8] = [9] = [10] = [11] = [12] = [13] = [14] = [15] =		

r7836[0...15] Telegram diagnostics unit / Tel diag unit		
SERVO, VECTOR	Can be changed: -	Access level: 4
	Data type: Integer16	Dynamic index: -
	P-Group: -	Units group: -
	Min	Max
	-1	147
		Function diagram: -
		Unit selection: -
		Factory setting
		131
Description:	Parameter to display the units of a DSA signal. The associated signal number is represented at the appropriate index in r7831.	
Values:	-1: Unknown 0: None 1: Millimeter or degrees 2: Millimeter 3: Degrees 4: mm/min or RPM 5: Millimeter / min 6: Revolutions / min 7: m/sec ² or V/sec ² 8: m/sec ² 9: V/sec ² 10: m/sec ³ or V/sec ³ 11: m/sec ³ 12: V/sec ³ 13: Sec 14: 16.667 / sec 15: mm / rev 16: ACX_UNIT_COMPENSATION_CORR 18: Newton 19: Kilogram 20: Kilogram meter ^2 21: Percent 22: Hertz 23: Volt peak-to-peak 24: Amps, peak-to-peak 25: Degrees Celsius 26: Degrees 28: Millimeter or degrees 29: Meters / minute 30: Meters / second 31: Ohm 32: Millihenry 33: Newton meter 34: Newton meter / Amps 35: Volt / Amp 36: Newton meter second / rad 38: 31.25 microseconds 39: Microseconds 40: Milliseconds 42: Kilowatt 43: Micro amps peak-to-peak 44: Volt seconds 45: Microvolt seconds 46: Micro Newton meter 47: Amps / Volt seconds 48: Per mille 49: Hertz / second	

53:	Micrometer or millidegrees
54:	Micrometer
55:	Millidegrees
59:	Nanometer
61:	Newton/Amps
62:	Volt seconds / meter
63:	Newton seconds / meter
64:	Micronewton
65:	Liters / minute
66:	Bar
67:	Cubic centimeters
68:	Millimeters / Volt minute
69:	Newton/Volt
80:	Millivolts, peak-to-peak
81:	Volt rms
82:	Millivolts, rms
83:	Amps rms
84:	Micro amps, rms
85:	Micrometers / revolution
90:	Tenths of a second
91:	Hundredths of a second
92:	10 microseconds
93:	Pulses
94:	256 pulses
95:	Tenth of a pulse
96:	Revolutions
97:	100 revolutions / minute
98:	10 revolutions / minute
99:	0.1 revolutions / minute
100:	Thousandth revolution / minute
101:	Pulses / second
102:	100 pulses / second
103:	10 revolutions / (minute * second)
104:	10000 pulses/second^2
105:	0.1 Hertz
106:	0.01 Hertz
107:	0.1 / seconds
108:	Factor 0.1
109:	Factor 0.01
110:	Factor 0.001
111:	Factor 0.0001
112:	0.1 Volt peak-to-peak
113:	0.1 Volt peak-to-peak
114:	0.1 amps, peak-to-peak
115:	Watt
116:	100 Watt
117:	10 Watt
118:	0.01 percent
119:	1 / second ^3
120:	0.01 percent/millisecond
121:	Pulses / revolution
122:	Microfarads
123:	Milliohm
124:	0.01 Newton meter
125:	Kilogram millimeter ^2
126:	Rad / (seconds newton meter)
127:	Henry
128:	Kelvin
129:	Hours
130:	Kilohertz
131:	Milliamperes, peak-to-peak
132:	Millifarads
133:	Meter
135:	Kilowatt hours

136: Percent
 137: Amps / Volt
 138: Volt
 139: Millivolts
 140: Microvolts
 141: Amps
 142: Milliampere
 143: Micro amp
 144: Milliampere, rms
 145: Millimeter
 146: Nanometer
 147: Joules

Index:
 [0] =
 [1] =
 [2] =
 [3] =
 [4] =
 [5] =
 [6] =
 [7] =
 [8] =
 [9] =
 [10] =
 [11] =
 [12] =
 [13] =
 [14] =
 [15] =

r7843[0...20] CompactFlash card serial number / CF serial number

CU_S

Can be changed: -**Access level:** 1**Data type:** Unsigned8**Dynamic index:** -**Function diagram:** -**P-Group:** -**Units group:** -**Unit selection:** -**Min****Max****Factory setting**

-

-

-

Description:

Displays the actual serial number of the CompactFlash card.

The individual characters of the serial number are displayed in the ASCII code in the indices.

Dependency:

Refer to: p9920, p9921

Notice:An ASCII table can be found, for example, in the following reference:
SINAMICS S120 Commissioning Manual**Note:**

Example for displaying a CompactFlash card serial number:

r7843[0] = 49 dec --> ASCII characters = "1" --> serial number, character 1
 r7843[1] = 49 dec --> ASCII characters = "1" --> serial number, character 2
 r7843[2] = 49 dec --> ASCII characters = "1" --> serial number, character 3
 r7843[3] = 57 dec --> ASCII characters = "9" --> serial number, character 4
 r7843[4] = 50 dec --> ASCII characters = "2" --> serial number, character 5
 r7843[5] = 51 dec --> ASCII characters = "3" --> serial number, character 6
 r7843[6] = 69 dec --> ASCII characters = "E" --> serial number, character 7
 r7843[7] = 0 dec --> ASCII characters = " " --> serial number, character 8

...

r7843[19] = 0 dec --> ASCII characters = " " --> serial number, character 20
 CompactFlash card serial number = 111923E

r7850[0...15]	Drive object operational/not operational / DO ready for oper		
CU_S	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -32786	Max 32767	Factory setting -32768
Description:	Displays whether, for an activated drive object, all activated topology components are available or not (or whether these can be addressed). 0: Drive object not ready for operation 1: Drive object ready for operation		
p7852	Number of indices for r7853 / Qty indices r7853		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 1	Max 200	Factory setting 1
Description:	Displays the number of indices for r7853[0...n]. This corresponds to the number of DRIVE-CLiQ components that are in the target topology.		
Dependency:	Refer to: r7853		
r7853[0...n]	Component available/not available / Comp present		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: p7852	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF hex	Factory setting 0000 hex
Description:	Displays the component and whether this component is currently present. High byte: Component number Low byte: 0/1 (not available/available)		
Dependency:	Refer to: p7852		
r7870[0...5]	Status/configuration changes, global / Config_chng global		
CU_S	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays status and configuration changes of all of the drive objects in the complete unit. Index 0: When changing one of the following indices, then the value in this index is incremented. Index 1: Drive object configuration. When changing r7871[0] on a drive object, the value in this index is incremented. Index 2: Drive object, configuration unit. When changing either p0101 or r0102, the value in this index is incremented. Index 3: PROFIBUS configuration unit. When changing p0978, the value in this index is incremented. Index 4: DRIVE-CLiQ actual topology. When changing either r9900 or r9901, the value in this index is incremented. Index 5: DRIVE-CLiQ target topology. When changing either p9902 or p9903, the value in this index is incremented.		
Dependency:	Refer to: r7871		

r7871[0...8]	Status/configuration changes, drive object / Config_chng DO		
A_INF, B_INF, CU_LINK, CU_S, DMC20, S_INF, TB30, TM15, TM15DI_DO, TM17, TM31, TM41	Can be changed: -	Dynamic index: -	Access level: 4
	Data type: Unsigned32		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	<p>Displays the status and configuration changes on the drive object.</p> <p>Index 0: When changing one of the following indices, then the value in this index is incremented.</p> <p>Index 1: Drive object configuration. When changing p0107, the value in this index is incremented.</p> <p>Index 2: Drive object name. When changing p0199, the value in this index is incremented.</p> <p>Index 3: Drive object structure. When changing a parameter that is relevant for the structure (e.g. number of data sets), the value in this index is incremented.</p> <p>Index 4: Drive objects, BICO interconnections. When changing r3977, the value in this index is incremented.</p> <p>Index 5: Drive objects, faults/alarms. When changing r0944 or r2121, the value in this index is incremented.</p> <p>Index 6: Drive object, data save. 0: There are not parameter changes to save. 1: There are parameter changes to save.</p> <p>Index 7: Drive object Safety. When changing r9744, the value in this index is incremented.</p> <p>Index 8: Drive object, changeover of units. When changing reference or changeover parameters (e.g. p2000, p0304...), the value in this index is incremented.</p>		
Dependency:	Refer to: r7870		

r7871[0...15] Status/configuration changes, drive object / Config_chng DO			
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	<p>Displays the status and configuration changes on the drive object.</p> <p>Index 0: When changing one of the following indices, then the value in this index is incremented.</p> <p>Index 1: Drive object configuration. When changing p0107, the value in this index is incremented.</p> <p>Index 2: Drive object name. When changing p0199, the value in this index is incremented.</p> <p>Index 3: Drive object structure. When changing a parameter that is relevant for the structure (e.g. number of data sets), the value in this index is incremented.</p> <p>Index 4: Drive objects, BICO interconnections. When changing r3977, the value in this index is incremented.</p> <p>Index 5: Drive objects, faults/alarms. When changing r0944 or r2121, the value in this index is incremented.</p> <p>Index 6: Drive object, data save.</p> <p>0: There are not parameter changes to save. 1: There are parameter changes to save.</p> <p>Index 7: Drive object Safety. When changing r9744, the value in this index is incremented.</p> <p>Index 8: Drive object, changeover of units. When changing reference or changeover parameters (e.g. p2000, p0304...), the value in this index is incremented.</p> <p>Index 9...14: Reserved.</p> <p>Index 15: SERVO/VECTOR configuration. When changing p0300, p0301 or p0400, the value in this index is incremented.</p>		
Dependency:	Refer to: r7870		
r7901[0...33] Time slice cycle times / Time slices t_cyc			
CU_S	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	- [µs]	- [µs]	- [µs]
Description:	<p>Displays the actual cycle times for all existing time slices.</p> <p>For r7901[x] = 0, the following applies: The time slice is not active.</p>		

p8500[0...7]	BI: CULINK infeed operation / INF operation		
CU_LINK	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 bin	Max 1111 1111 1111 1111 1111 1111 1111 1111 bin	Factory setting 0000 bin
Description:	Sets the signal source for the operating signal of the infeed (e.g. BO: r0863.0). These signals are transferred to another Control Unit and are located at BO: p8510 for further interconnection.		
Index:	[0] = Infeed operation 0 signal source [1] = Infeed operation 1 signal source [2] = Infeed operation 2 signal source [3] = Infeed operation 3 signal source [4] = Infeed operation 4 signal source [5] = Infeed operation 5 signal source [6] = Infeed operation 6 signal source [7] = Infeed operation 7 signal source		
Dependency:	Refer to: r8510		
Note:	SM150: The parameter is used to transfer the INF_RDY signal (863.0) from the ALM_MV (Cx32) via the CU-Link and p8510 to the feedback signal input (864.0) on the VECTOR_MV (D445).		

p8501[0...15]		BI: CULINK digital input / DI	
CU_LINK	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min 0000 bin	Max 1111 1111 1111 1111 1111 1111 1111 1111 bin	Factory setting [0] 0000 0010 1101 0010 0000 0100 0000 0000 bin [1] 0000 0010 1101 0010 0000 0100 0000 0001 bin [2] 0000 0010 1101 0010 0000 0100 0000 0010 bin [3] 0000 0010 1101 0010 0000 0100 0000 0011 bin [4] 0000 0010 1101 0010 0000 0100 0000 0100 bin [5] 0000 0010 1101 0010 0000 0100 0000 0101 bin [6] 0000 0010 1101 0010 0000 0100 0000 0110 bin [7] 0000 0010 1101 0010 0000 0100 0000 0111 bin [8] 0000 0010 1101 0010 0000 0100 0000 1000 bin [9] 0000 0010 1101 0010 0000 0100 0000 1001 bin [10] 0000 0010 1101 0010 0000 0100 0000 1010 bin [11] 0000 0010 1101 0010 0000 0100 0000 1011 bin [12] 0000 0010 1101 0010 0000 0100 0000 1100 bin [13] 0000 0010 1101 0010 0000 0100 0000 1101 bin [14] 0000 0010 1101 0010 0000 0100 0000 1110 bin [15] 0000 0010 1101 0010 0000 0100 0000 1111 bin
Description:	Sets the signal source for the signal of a digital input. These signals are transferred to another Control Unit and are located at BO: p8511 for further interconnection.		
Index:	[0] = Digital input 0 signal source [1] = Digital input 1 signal source [2] = Digital input 2 signal source [3] = Digital input 3 signal source [4] = Digital input 4 signal source [5] = Digital input 5 signal source [6] = Digital input 6 signal source [7] = Digital input 7 signal source [8] = Digital input 8 signal source [9] = Digital input 9 signal source [10] = Digital input 10 signal source [11] = Digital input 11 signal source [12] = Digital input 12 signal source [13] = Digital input 13 signal source [14] = Digital input 14 signal source [15] = Digital input 15 signal source		
Dependency:	Refer to: r8511		
Note:	SM150: The signal is used, among other things, to transfer the command INF_ON (r863.1) from VECTOR_MV (D445) via the CU-Link and p8511 to ON (p840) of the ALM_MV (Cx32).		

p8502	CI: CULINK signal value 0 / Signal value 0		
CU_LINK	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	BiCo signal drain with a process signal that is transferred from other Control Unit.		
Dependency:	Refer to: r8512		

p8503	CI: CULINK signal value 1 / Signal value 1		
CU_LINK	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	BiCo signal drain with a process signal that is transferred from other Control Unit.		
Dependency:	Refer to: r8513		

p8504	CI: CULINK signal value 2 / Signal value 2		
CU_LINK	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	BiCo signal drain with a process signal that is transferred from other Control Unit.		
Dependency:	Refer to: r8514		

p8505	CI: Signal value 3 / Signal value 3		
CU_LINK	Can be changed: U, T		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	BiCo signal drain with a process signal that is transferred from other Control Unit.		
Dependency:	Refer to: r8515		

r8510 BO: CULINK infeed operation / INF operation

CU_LINK	Can be changed: -	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: -	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Displays the operating signal of the infeeds.
These signals were transferred from another Control Unit.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Infeed operation 0	On	Off	-
	01	Infeed operation 1	On	Off	-
	02	Infeed operation 2	On	Off	-
	03	Infeed operation 3	On	Off	-
	04	Infeed operation 4	On	Off	-
	05	Infeed operation 5	On	Off	-
	06	Infeed operation 6	On	Off	-
	07	Infeed operation 7	On	Off	-

Dependency: Refer to: p8500

Note: SM150: Here, the INF_RDY signal of ALM_MV (Cx32) transferred via the CU-Link is received and connected to p864.0 of the VECTOR_MV (D445).

r8511 BO: CULINK digital input / DI

CU_LINK	Can be changed: -	Access level: 2
	Data type: Unsigned32	Dynamic index: -
	P-Group: -	Function diagram: -
	Units group: -	Unit selection: -
	Min	Max
	-	-
		Factory setting
		0000 bin

Description: Binector sources with the digital input terminal signals that are transferred from other Control Units.

[0] = Binector source with the signal of the first digital input terminal

...

[15] = Binector source with the signal of the 16th digital input terminal

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Digital input 0	On	Off	-
	01	Digital input 1	On	Off	-
	02	Digital input 2	On	Off	-
	03	Digital input 3	On	Off	-
	04	Digital input 4	On	Off	-
	05	Digital input 5	On	Off	-
	06	Digital input 6	On	Off	-
	07	Digital input 7	On	Off	-
	08	Digital input 8	On	Off	-
	09	Digital input 9	On	Off	-
	10	Digital input 10	On	Off	-
	11	Digital input 11	On	Off	-
	12	Digital input 12	On	Off	-
	13	Digital input 13	On	Off	-
	14	Digital input 14	On	Off	-
	15	Digital input 15	On	Off	-

Dependency: Refer to: p8501

Note: SM150: The INF_ON command transferred from VECTOR_MV (D445) using the CU-Link to ALM_MV (Cx32) is received here and connected to p840.

r8512	CO: CULINK signal value 0 / Signal value 0		
CU_LINK	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	BiCo source with a process signal that is transferred to another Control Unit.		
Dependency:	Refer to: p8502		

r8513	CO: CULINK signal value 1 / Signal value 1		
CU_LINK	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	BiCo source with a process signal that is transferred to another Control Unit.		
Dependency:	Refer to: p8503		

r8514	CO: CULINK signal value 2 / Signal value 2		
CU_LINK	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	BiCo source with a process signal that is transferred to another Control Unit.		
Dependency:	Refer to: p8504		

r8515	CO: Signal value 3 / Signal value 3		
CU_LINK	Can be changed: -		Access level: 2
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	BiCo source with a process signal that is transferred to another Control Unit.		
Dependency:	Refer to: p8505		

p8550	AOP LOCAL/REMOTE / AOP LOCAL/REMOTE			
CU_S	Can be changed: U, T		Access level: 4	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: -	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	1001 bin	
Description:	Is used to save the current configuration of the Advanced Operator Panels (AOP).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	LOCAL save	Yes	No
	01	Start in LOCAL	Yes	No
	02	Change in oper.	Yes	No
	03	OFF acts like OFF1	Yes	No
	04	OFF acts like OFF2	Yes	No
	05	OFF acts like OFF3	Yes	No
	07	CW/CCW active	Yes	No
	08	Jog active	Yes	No
	09	Save speed setpoint	Yes	No
	14	Inhibit operation	Yes	No
	15	Inhibit parameters	Yes	No

r8570[0...9]	Macro drive unit / Macro drv unit			
CU_S	Can be changed: -		Access level: 1	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: -	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Displays the ACX file saved in the appropriate directory of the CompactFlash card.			
Dependency:	Refer to: p0015			

r8570[0...9]	Macro drive object / Macro DO			
A_INF, B_INF, SERVO, S_INF, TM15DI_DO, TM31, VECTOR	Can be changed: -		Access level: 1	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: -	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Displays the ACX file saved in the appropriate directory of the CompactFlash card.			
Dependency:	Refer to: p0015			

r8571[0...9]	Macro Binector Input (BI) / Macro BI			
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 1	
	Data type: Unsigned32	Dynamic index: -	Function diagram: -	
	P-Group: -	Units group: -	Unit selection: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Displays the ACX file saved in the appropriate directory of the CompactFlash card.			
Dependency:	Refer to: p0700			

r8572[0...9]	Macro Connector Inputs (CI) for speed setpoints / Macro CI n_set		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the ACX file saved in the appropriate directory of the CompactFlash card.		
Dependency:	Refer to: p1000		

r8573[0...9]	Macro Connector Inputs (CI) for torque setpoints / Macro CI M_set		
A_INF, B_INF, SERVO, S_INF, VECTOR	Can be changed: -		Access level: 1
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the ACX file saved in the appropriate directory of the CompactFlash card.		
Dependency:	Refer to: p1500		

r8585	Actual macro actual / Actual macro		
A_INF, B_INF, CU_S, SERVO, S_INF, TM15DI_DO, TM31, VECTOR	Can be changed: -		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Indicates which macro is presently being run in the drive object.		
Dependency:	Refer to: p0015, p0700, p1000, p1500, r8570, r8571, r8572, r8573		

r8600	CBC device type / Device type		
CU_S (CAN)	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description:	Displays all of the devices connected to the CAN bus after run-up. r8600 = 00000000 hex: No drive recognized. = FFFF0192 hex: Several drives - drive 1 is an Active Line Module, servo drive or vector drive = FFFF0191 hex: Several drives - 1st drive us a Terminal Module = 00010192 hex: 1 Vector drive = 00020192 hex: 1 Servo drive = 01000192 hex: 1 Active Line Module = 00080191 hex: 1 Terminal Module
Note:	Corresponds to the CANopen object 1000 hex. For each detected drive, the device type is displayed in object 67FF hex + 800 hex * x (x: Drive number 0 ... 7).

r8601	CBC error register / Error register		
CU_S (CAN)	Can be changed: -		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	<p>Displays the error register for CANopen.</p> <p>Bit 0: Generic error</p> <p>0 signal: No error present</p> <p>1 signal: Generic error present</p> <p>Bit 1 ... 3: Not supported (always a 0 signal)</p> <p>Bit 4: Communications error</p> <p>0 signal: There is no message in the range 8700 ... 8799</p> <p>1 signal: There is at least one message (fault or alarm) in the range 8700 ... 8799</p> <p>Bit 5 ... 6: Not supported (always a 0 signal)</p> <p>Bit 7:; Fault outside the range 8700 ... 8799</p> <p>0 signal: There is no fault outside the range 8700 ... 8799</p> <p>1 signal: There is at least one fault outside the range 8700 ... 8799</p>		
Note:	Corresponds to the CANopen object 1001 hex.		
p8602	CBC SYNC object / SYNC object		
CU_S (CAN)	Can be changed: C1(1), T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0080 hex
Description:	<p>Sets the SYNC object parameter for the following CANopen objects:</p> <p>- 1005 hex: COB-ID</p>		
Note:	<p>SINAMICS operates as SYNC load.</p> <p>COB-ID: CAN object identification</p>		
p8603	CBC COB ID Emergency Message / COB ID EMCY Msg		
CU_S (CAN)	Can be changed: C1(1), T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex
Description:	<p>Sets the COB ID of the emergency message (error telegram). It corresponds to the CANopen objects:</p> <p>- 1014 hex: COB-ID</p>		
Note:	<p>If, when downloading, the pre-set value 0 is downloaded, then the CANopen pre-set value 80 hex + Node-ID is automatically set.</p> <p>Online, the value 0 is rejected as, according to the CANopen Standard, COB ID 0 is not permitted here.</p> <p>The changeover of the node ID using the hardware switch at the CU or per software has no effect on the COB-ID EMCY. The saved value remains effective.</p>		

p8604[0...1]	CBC node guarding / Node guarding		
CU_S (CAN)	Can be changed: T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Sets the node guarding parameter for the following CANopen objects: - 100C hex: Guard Time - 100D hex: Life Time Factor The life time is derived by multiplying guard time by the life time factor.		
Index:	[0] = Time interval [ms] for new node guarding telegram [1] = Factor for failure of the node guarding telegram		
Dependency:	Only adjustable if heartbeat time = 0 (heartbeat is disabled). Refer to: p8606		
Note:	For p8604[0] = 0 and/or p8604[1] = 0, the node guarding protocol is not used. Either node guarding or heartbeat can be used.		
p8606	CBC producer heartbeat time / Prod Heartb Time		
CU_S (CAN)	Can be changed: T		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0 [ms]	Max 65535 [ms]	Factory setting 0 [ms]
Description:	Sets the time [ms] to cyclically send heartbeat telegrams. The smallest cycle time is 100 ms. When a 0 is written, then heartbeat telegrams are not sent.		
Dependency:	Only adjustable if guard time = 0 (node guarding disabled). Refer to: p8604		
Note:	Corresponds to the CANopen object 1017 hex. Either node guarding or heartbeat can be used.		
r8607[0...3]	CBC identity object / Identity object		
CU_S (CAN)	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	General device information display.		
Index:	[0] = Vendor ID [1] = Product code [2] = Revision number [3] = Serial number		
Note:	Corresponds to the CANopen object 1018 hex.		
p8608	CBC clear bus off error / Clear bus off err		
CU_S (CAN)	Can be changed: U, T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	For a bus off error, the CAN bus is restarted with p8608 = 1 after the cause of the error has been removed.		
Values:	0: not active 1: Start CAN controller		
Note:	This parameter is automatically reset to 0 after start.		

p8609[0...1]	CBC error behavior / Error behavior		
CU_S (CAN)	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 1
Description:	Sets the behavior of the CAN node referred to the communications error or equipment fault.		
Values:	0: Pre-operational 1: No change 2: Stopped		
Index:	[0] = Behavior for communication errors [1] = Behavior for device faults		
Note:	Corresponds to the CANopen object 1029 hex.		
r8610[0...1]	CBC first server SDO / First server SDO		
CU_S (CAN)	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the identifier (client/server and server/client) of the SDO channel.		
Index:	[0] = Displays the COB ID from client to server [1] = Displays the COB ID from server to client		
Note:	Corresponds to the CANopen object 1200 hex. SDO: Service Data Object		
p8611[0...82]	CBC pre-defined error field / Pre_def err field		
CU_S (CAN)	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF 1000 hex	Factory setting 0000 hex
Description:	Displays the Pre-defined Error Field of the CAN node. It includes the number of all errors that have occurred, the number of errors that have occurred for each drive and the errors according to their history. The first 16 bits represent the CANopen error code and the second 16 bits the SINAMICS error code. Index 1 has the same structure - however, the CAN offset is in the second 16 bits instead of the SINAMICS error code. CANopen error code: 0000 hex: No error present 8110 hex: Alarm A08751 present 8120 hex: Alarm A08752 present 8130 hex: Alarm A08700(F) with alarm value = 2 present 1000 hex: Generic error 1 present (there is at least one fault outside the range 8700 ... 8799) 1001 hex: Generic error 2 present (there is at least one alarm in the range 8700 ... 8799 with the exception of A08751, A08752, A08700)		
Index:	[0] = Number of all faults in the drive unit [1] = Most recent drive number / fault number		

- [2] = Number of faults drive 1
- [3] = Fault 1/ drive 1
- [4] = Fault 2/ drive 1
- [5] = Fault 3/ drive 1
- [6] = Fault 4/ drive 1
- [7] = Fault 5/ drive 1
- [8] = Fault 6/ drive 1
- [9] = Fault 7/ drive 1
- [10] = Fault 8/ drive 1
- [11] = Number of faults drive 2
- [12] = Fault 1/ drive 2
- [13] = Fault 2/ drive 2
- [14] = Fault 3/ drive 2
- [15] = Fault 4/ drive 2
- [16] = Fault 5/ drive 2
- [17] = Fault 6/ drive 2
- [18] = Fault 7/ drive 2
- [19] = Fault 8/ drive 2
- [20] = Number of faults drive 3
- [21] = Fault 1/ drive 3
- [22] = Fault 2/ drive 3
- [23] = Fault 3/ drive 3
- [24] = Fault 4/ drive 3
- [25] = Fault 5/ drive 3
- [26] = Fault 6/ drive 3
- [27] = Fault 7/ drive 3
- [28] = Fault 8/ drive 3
- [29] = Number of faults drive 4
- [30] = Fault 1/ drive 4
- [31] = Fault 2/ drive 4
- [32] = Fault 3/ drive 4
- [33] = Fault 4/ drive 4
- [34] = Fault 5/ drive 4
- [35] = Fault 6/ drive 4
- [36] = Fault 7/ drive 4
- [37] = Fault 8/ drive 4
- [38] = Number of faults drive 5
- [39] = Fault 1/ drive 5
- [40] = Fault 2/ drive 5
- [41] = Fault 3/ drive 5
- [42] = Fault 4/ drive 5
- [43] = Fault 5/ drive 5
- [44] = Fault 6/ drive 5
- [45] = Fault 7/ drive 5
- [46] = Fault 8/ drive 5
- [47] = Number of faults drive 6
- [48] = Fault 1/ drive 6
- [49] = Fault 2/ drive 6
- [50] = Fault 3/ drive 6
- [51] = Fault 4/ drive 6
- [52] = Fault 5/ drive 6
- [53] = Fault 6/ drive 6
- [54] = Fault 7/ drive 6
- [55] = Fault 8/ drive 6
- [56] = Number of faults drive 7
- [57] = Fault 1/ drive 7
- [58] = Fault 2/ drive 7
- [59] = Fault 3/ drive 7
- [60] = Fault 4/ drive 7
- [61] = Fault 5/ drive 7
- [62] = Fault 6/ drive 7
- [63] = Fault 7/ drive 7
- [64] = Fault 8/ drive 7
- [65] = Number of faults drive 8

[66] = Fault 1/ drive 8
 [67] = Fault 2/ drive 8
 [68] = Fault 3/ drive 8
 [69] = Fault 4/ drive 8
 [70] = Fault 5/ drive 8
 [71] = Fault 6/ drive 8
 [72] = Fault 7/ drive 8
 [73] = Fault 8/ drive 8
 [74] = Number of faults Control Unit
 [75] = Fault 1/Control Unit
 [76] = Fault 2/Control Unit
 [77] = Fault 3/Control Unit
 [78] = Fault 4/Control Unit
 [79] = Fault 5/Control Unit
 [80] = Fault 6/Control Unit
 [81] = Fault 7/Control Unit
 [82] = Fault 8/Control Unit

p8620	CBC node ID / Node ID		
CU_S (CAN)	Can be changed: T		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 1	Max 126	Factory setting 126
Description:	Display or setting of the CANopen Node ID. The Node ID can be set as follows: 1) Using the DIP switch power-up the Control Unit. --> p8620 can then only be read and displays the selected Node ID. --> A change only becomes effective after a POWER ON. --> CANopen Node ID and PROFIBUS address are identical. 2) Using p8620 --> only if all of the DIP switches - from S1 to S7 - are either set to ON or OFF. --> the Node ID is set as standard to 126. --> A change only becomes effective after save and POWER ON.		
Note:	Every node ID change only becomes effective after a POWER ON. It is only possible to independently set CANopen node ID and the PROFIBUS address using p0918 and p8620 (pre-requisite: For DIP switches, all of the switches from S1 to S7 are either set to ON or OFF).		

p8622	CBC baud rate / Baud rate		
CU_S (CAN)	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 7	Factory setting 6
Description:	Setting the baud rate for the CAN bus. The appropriate bit timings are selected that are defined in p8623 in the associated sub-index.		
Values:	0: 1 Mbit/s 1: 800 kbit/s 2: 500 kbit/s 3: 250 kbit/s 4: 125 kbit/s 5: 50 kbit/s 6: 20 kbit/s 7: 10 kbit/s		
Recommendation:	Use the factory setting when setting the baud rate. Example: Baud rate = 20 kbit/s --> p8622 = 6 --> associated bit timing is in p8623[6].		
Dependency:	Refer to: p8623		

p8623[0...7]	CBC bit timing selection / Bit timing select		
CU_S (CAN)	Can be changed: T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 hex	Max 000F 7FFF hex	Factory setting [0] 1405 hex [1] 1605 hex [2] 1C05 hex [3] 1C0B hex [4] 1C17 hex [5] 1C3B hex [6] 0002 1C15 hex [7] 0004 1C2B hex
Description:	Sets the bit timing for the C_CAN controller to the associated and selected baud rate (p8622). Bits are distributed to the following parameters of the C_CAN controller in p8623[0...7]: Bit 0 ... 5: BRP (Baud Rate Prescaler) Bit 6 ... 7: SJW (Synchronization Jump Width) Bit 8 ... 11: TSEG1 (Time Segment 1, before the sampling point) Bit 12 ... 14: TSEG2 (Time Segment 2, after the sampling point) Bit 15: Reserved Bit 16 ... 19: BRPE (Baud Rate Prescaler Extension) Bit 20 ... 31: Reserved		
Index:	[0] = 1 Mbit/s [1] = 800 kbit/s [2] = 500 kbit/s [3] = 250 kbit/s [4] = 125 kbit/s [5] = 50 kbit/s [6] = 20 kbit/s [7] = 10 kbit/s		
Dependency:	Refer to: p8622		
Note:	Recommendation: You use the factory setting (refer to p8622) when setting the bit timing. Example: Baud rate = 20 kbit/s --> p8622 = 6 --> associated bit timing is in p8623[6] --> 0001 2FB6		

p8630[0...2]	CBC virtual objects / Virtual objects		
CU_S (CAN)	Can be changed: U, T Data type: Unsigned16 P-Group: Communications Min 0	Dynamic index: - Units group: - Max 65535	Access level: 3 Function diagram: - Unit selection: - Factory setting 0
Description:	Sets the drive object selection (index 0), the sub-index area (index 1) and the parameter area (index 2) when using virtual objects. This means that it is possible to access all SINAMICS parameters via CAN. Index 0 (drive object selection): 0: Not possible to access virtual CANopen objects 1: Device 2 ... 65535: Drive 1 ... 8 Index 1 (sub-index area): 0: 0 ... 255 1: 256 ... 511 2: 512 ... 767 3: 768 ... 1023 Index 2 (parameter area): 0: 1 ... 9999 1: 10000 ... 19999 2: 20000 ... 29999 3: 30000 ... 39999		
Index:	[0] = Drive object selection [1] = Sub-index range [2] = Parameter range		

p8641	CBC abort connection option code / Abort con opt code		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: T Data type: Integer16 P-Group: - Min 0	Dynamic index: - Units group: - Max 3	Access level: 3 Function diagram: - Unit selection: - Factory setting 3
Description:	Sets the drive behavior if a CAN communication error occurs.		
Values:	0: No response 1: OFF1 2: OFF2 3: OFF3		
Dependency:	Refer to: F08700		

r8680[0...36]	CBC diagnostics hardware / Diagnostics HW		
CU_S (CAN)	Can be changed: - Data type: Unsigned16 P-Group: Communications Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: - Unit selection: - Factory setting -
Description:	Displays the register of the CAN controller C_CAN: Register, Message Interface Register and Message Handler Register - referred to the CAN protocol.		

Index:	[0] = Control register
	[1] = Status register
	[2] = Error counter
	[3] = Bit timing register
	[4] = Interrupt register
	[5] = Test register
	[6] = Baud rate prescaler extension register
	[7] = Interface 1 command request register
	[8] = Interface 1 command mask register
	[9] = Interface 1 mask 1 register
	[10] = Interface 1 mask 2 register
	[11] = Interface 1 arbitration 1 register
	[12] = Interface 1 arbitration 2 register
	[13] = Interface 1 message control register
	[14] = Interface 1 data A1 register
	[15] = Interface 1 data A2 register
	[16] = Interface 1 data B1 register
	[17] = Interface 1 data B2 register
	[18] = Interface 2 command request register
	[19] = Interface 2 command mask register
	[20] = Interface 2 mask 1 register
	[21] = Interface 2 mask 2 register
	[22] = Interface 2 arbitration 1 register
	[23] = Interface 2 arbitration 2 register
	[24] = Interface 2 message control register
	[25] = Interface 2 data A1 register
	[26] = Interface 2 data A2 register
	[27] = Interface 2 data B1 register
	[28] = Interface 2 data B2 register
	[29] = Transmission request 1 register
	[30] = Transmission request 2 register
	[31] = New data 1 register
	[32] = New data 2 register
	[33] = Interrupt pending 1 register
	[34] = Interrupt pending 2 register
	[35] = Message valid 1 register
	[36] = Message valid 2 register

Note: A description of the individual registers of the C_CAN controller can be taken from "C_CAN User's Manual".

p8685	CBC NMT states / NMT states		
CU_S (CAN)	Can be changed: C1(1), U, T	Dynamic index: -	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: Communications		Unit selection: -
	Min	Max	Factory setting
	0	129	127
Description:	Sets and displays the CANopen NMT state.		
Values:	0: Initializing 4: Stopped 5: Operational 127: Pre-operational 128: Reset node 129: Reset Communication		
Note:	The value 0 (initialization) is only displayed and cannot be set.		

p8700[0...1]	CBC receive PDO 1 / Receive PDO 1		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex
Description:	Sets the communication parameters for CANopen receive process data object 1 (RPDO 1).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Note:	Corresponds to the CANopen object 1400 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8701[0...1]	CBC receive PDO 2 / Receive PDO 2		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex
Description:	Sets the communication parameters for CANopen receive process data object 2 (RPDO 2).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Note:	Corresponds to the CANopen object 1401 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8702[0...1]	CBC receive PDO 3 / Receive PDO 3		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex
Description:	Sets the communication parameters for CANopen receive process data object 3 (RPDO 3).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Note:	Corresponds to the CANopen object 1402 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		

p8703[0...1]	CBC receive PDO 4 / Receive PDO 4		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex
Description:	Sets the communication parameters for CANopen receive process data object 4 (RPDO 4).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Note:	Corresponds to the CANopen object 1403 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8704[0...1]	CBC receive PDO 5 / Receive PDO 5		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex
Description:	Sets the communication parameters for CANopen receive process data object 5 (RPDO 5).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Note:	Corresponds to the CANopen object 1404 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8705[0...1]	CBC receive PDO 6 / Receive PDO 6		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex
Description:	Sets the communication parameters for CANopen receive process data object 6 (RPDO 6).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Note:	Corresponds to the CANopen object 1405 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		

p8706[0...1] CBC receive PDO 7 / Receive PDO 7

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex

Description: Sets the communication parameters for CANopen receive process data object 7 (RPDO 7).

Index:
[0] = PDO COB-ID
[1] = PDO transmission type

Dependency: A valid COB-ID can only be set for the available (existing) channel.
Refer to: p8740, p8741

Note: Corresponds to the CANopen object 1406 hex + 40 hex * x (x: Drive number 0 ... 7).
Transmission types 0, 1, FE and FF can be set.
PDO: Process Data Object

p8707[0...1] CBC receive PDO 8 / Receive PDO 8

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max 8000 06DF hex	Factory setting [0] 8000 06DF hex [1] 00FE hex

Description: Sets the communication parameters for CANopen receive process data object 8 (RPDO 8).

Index:
[0] = PDO COB-ID
[1] = PDO transmission type

Dependency: A valid COB-ID can only be set for the available (existing) channel.
Refer to: p8740, p8741

Note: Corresponds to the CANopen object 1407 hex + 40 hex * x (x: Drive number 0 ... 7).
Transmission types 0, 1, FE and FF can be set.
PDO: Process Data Object

p8710[0...3] CBC receive mapping for RPDO 1 / Mapping RPDO 1

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204, 9206
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex

Description: Sets the mapping parameters for CANopen receive process data object 1 (RPDO 1).

Index:
[0] = Mapped object 1
[1] = Mapped object 2
[2] = Mapped object 3
[3] = Mapped object 4

Note: Corresponds to the CANopen object 1600 hex + 40 hex * x (x: Drive number 0 ... 7).
Dummy mapping not supported.

p8711[0...3] CBC receive mapping for RPDO 2 / Mapping RPDO 2

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 2 (RPDO 2).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1601 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		

p8712[0...3] CBC receive mapping for RPDO 3 / Mapping RPDO 3

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 3 (RPDO 3).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1602 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		

p8713[0...3] CBC receive mapping for RPDO 4 / Mapping RPDO 4

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 4 (RPDO 4).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1603 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		

p8714[0...3] CBC receive mapping for RPDO 5 / Mapping RPDO 5

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 5 (RPDO 5).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1604 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		

p8715[0...3] CBC receive mapping for RPDO 6 / Mapping RPDO 6

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 6 (RPDO 6).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1605 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		

p8716[0...3] CBC receive mapping for RPDO 7 / Mapping RPDO 7

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 7 (RPDO 7).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1606 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		

p8717[0...3] CBC receive mapping for RPDO 8 / Mapping RPDO 8			
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9204
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen receive process data object 8 (RPDO 8).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1607 hex + 40 hex * x (x: Drive number 0 ... 7). Dummy mapping not supported.		
p8720[0...4] CBC transmit PDO 1 / Transmit PDO 1			
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208, 9210
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex
Description:	Sets the communication parameters for CANopen transmit process data object 1 (TPDO 1).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type [2] = Inhibit time (in 100 µs) [3] = Reserved [4] = Event timer (in ms)		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Notice:	For inhibit time and even timer, the following apply: A value that is not a multiple integer of CANopen (4 ms) is rounded-off.		
Note:	Corresponds to the CANopen object 1800 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1 ... F0, FE and FF can be set. PDO: Process Data Object		

p8721[0...4] CBC transmit PDO 2 / Transmit PDO 2

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208, 9210
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex
Description:	Sets the communication parameters for CANopen transmit process data object 2 (TPDO 2).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type [2] = Inhibit time (in 100 µs) [3] = Reserved [4] = Event timer (in ms)		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Notice:	For inhibit time and even timer, the following apply: A value that is not a multiple integer of CANopen (4 ms) is rounded-off.		
Note:	Corresponds to the CANopen object 1801 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1 ... F0, FE and FF can be set. PDO: Process Data Object		

p8722[0...4] CBC transmit PDO 3 / Transmit PDO 3

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208, 9210
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex
Description:	Sets the communication parameters for CANopen transmit process data object 3 (TPDO 3).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type [2] = Inhibit time (in 100 µs) [3] = Reserved [4] = Event timer (in ms)		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Notice:	For inhibit time and even timer, the following apply: A value that is not a multiple integer of CANopen (4 ms) is rounded-off.		
Note:	Corresponds to the CANopen object 1802 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1 ... F0, FE and FF can be set. PDO: Process Data Object		

p8723[0...4]	CBC transmit PDO 4 / Transmit PDO 4		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208, 9210
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex
Description:	Sets the communication parameters for CANopen transmit process data object 4 (TPDO 4).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type [2] = Inhibit time (in 100 µs) [3] = Reserved [4] = Event timer (in ms)		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Notice:	For inhibit time and even timer, the following apply: A value that is not a multiple integer of CANopen (4 ms) is rounded-off.		
Note:	Corresponds to the CANopen object 1803 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1 ... F0, FE and FF can be set. PDO: Process Data Object		

p8724[0...4]	CBC transmit PDO 5 / Transmit PDO 5		
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex
Description:	Sets the communication parameters for CANopen transmit process data object 5 (TPDO 5).		
Index:	[0] = PDO COB-ID [1] = PDO transmission type [2] = Inhibit time (in 100 µs) [3] = Reserved [4] = Event timer (in ms)		
Dependency:	A valid COB-ID can only be set for the available (existing) channel. Refer to: p8740, p8741		
Notice:	For inhibit time and even timer, the following apply: A value that is not a multiple integer of CANopen (4 ms) is rounded-off.		
Note:	Corresponds to the CANopen object 1804 hex + 40 hex * x (x: Drive number 0 ... 7). Transmission types 0, 1 ... F0, FE and FF can be set. PDO: Process Data Object		

p8725[0...4] CBC transmit PDO 6 / Transmit PDO 6

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208
	P-Group: Communications	Max	Unit selection: -
	Min 0000 hex	C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex

Description: Sets the communication parameters for CANopen transmit process data object 6 (TPDO 6).

Index:
 [0] = PDO COB-ID
 [1] = PDO transmission type
 [2] = Inhibit time (in 100 µs)
 [3] = Reserved
 [4] = Event timer (in ms)

Dependency: A valid COB-ID can only be set for the available (existing) channel.
Refer to: p8740, p8741

Notice: For inhibit time and even timer, the following apply:
A value that is not a multiple integer of CANopen (4 ms) is rounded-off.

Note: Corresponds to the CANopen object 1805 hex + 40 hex * x (x: Drive number 0 ... 7).
Transmission types 0, 1 ... F0, FE and FF can be set.
PDO: Process Data Object

p8726[0...4] CBC transmit PDO 7 / Transmit PDO 7

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208
	P-Group: Communications	Max	Unit selection: -
	Min 0000 hex	C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex

Description: Sets the communication parameters for CANopen transmit process data object 7 (TPDO 7).

Index:
 [0] = PDO COB-ID
 [1] = PDO transmission type
 [2] = Inhibit time (in 100 µs)
 [3] = Reserved
 [4] = Event timer (in ms)

Dependency: A valid COB-ID can only be set for the available (existing) channel.
Refer to: p8740, p8741

Notice: For inhibit time and even timer, the following apply:
A value that is not a multiple integer of CANopen (4 ms) is rounded-off.

Note: Corresponds to the CANopen object 1806 hex + 40 hex * x (x: Drive number 0 ... 7).
Transmission types 0, 1 ... F0, FE and FF can be set.
PDO: Process Data Object

p8727[0...4] CBC transmit PDO 8 / Transmit PDO 8

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max C000 06DF hex	Factory setting [0] C000 06DF hex [1] 00FE hex [2] 0000 hex [3] 0000 hex [4] 0000 hex

Description: Sets the communication parameters for CANopen transmit process data object 8 (TPDO 8).

Index:
 [0] = PDO COB-ID
 [1] = PDO transmission type
 [2] = Inhibit time (in 100 µs)
 [3] = Reserved
 [4] = Event timer (in ms)

Dependency: A valid COB-ID can only be set for the available (existing) channel.
Refer to: p8740, p8741

Notice: For inhibit time and even timer, the following apply:
A value that is not a multiple integer of CANopen (4 ms) is rounded-off.

Note: Corresponds to the CANopen object 1807 hex + 40 hex * x (x: Drive number 0 ... 7).
Transmission types 0, 1 ... F0, FE and FF can be set.
PDO: Process Data Object

p8730[0...3] CBC send mapping for TPDO 1 / Mapping TPDO 1

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208, 9210
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex

Description: Sets the mapping parameters for CANopen transmit process data object 1 (TPDO 1).

Index:
 [0] = Mapped object 1
 [1] = Mapped object 2
 [2] = Mapped object 3
 [3] = Mapped object 4

Note: Corresponds to the CANopen object 1A00 hex + 40 hex * x (x: Drive number 0 ... 7).

p8731[0...3] CBC send mapping for TPDO 2 / Mapping TPDO 2

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208, 9210
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex

Description: Sets the mapping parameters for CANopen transmit process data object 2 (TPDO 2).

Index:
 [0] = Mapped object 1
 [1] = Mapped object 2
 [2] = Mapped object 3
 [3] = Mapped object 4

Note: Corresponds to the CANopen object 1A01 hex + 40 hex * x (x: Drive number 0 ... 7).

p8732[0...3] CBC send mapping for TPDO 3 / Mapping TPDO 3

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208, 9210
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen transmit process data object 3 (TPDO 3).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1A02 hex + 40 hex * x (x: Drive number 0 ... 7).		

p8733[0...3] CBC send mapping for TPDO 4 / Mapping TPDO 4

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208, 9210
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen transmit process data object 4 (TPDO 4).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1A03 hex + 40 hex * x (x: Drive number 0 ... 7).		

p8734[0...3] CBC send mapping for TPDO 5 / Mapping TPDO 5

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen transmit process data object 5 (TPDO 5).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1A04 hex + 40 hex * x (x: Drive number 0 ... 7).		

p8735[0...3] CBC send mapping for TPDO 6 / Mapping TPDO 6

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: 9208
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen transmit process data object 6 (TPDO 6).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1A05 hex + 40 hex * x (x: Drive number 0 ... 7).		

p8736[0...3] CBC send mapping for TPDO 7 / Mapping TPDO 7

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen transmit process data object 7 (TPDO 7).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1A06 hex + 40 hex * x (x: Drive number 0 ... 7).		

p8737[0...3] CBC send mapping for TPDO 8 / Mapping TPDO 8

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: 9208
	P-Group: Communications		Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the mapping parameters for CANopen transmit process data object 8 (TPDO 8).		
Index:	[0] = Mapped object 1 [1] = Mapped object 2 [2] = Mapped object 3 [3] = Mapped object 4		
Note:	Corresponds to the CANopen object 1A07 hex + 40 hex * x (x: Drive number 0 ... 7).		

p8740[0...23] CBC channel assignment / Chann assign.

CU_S (CAN)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min 0	Max 8	Factory setting 0
Description:	Sets the number of channels for receive PDOs and Transmit PDOs. To define the number of channels of a drive, there are 3 indices (3 * n indices, n = 8). Index 0: Number of channels for receive PDOs (1st drive) Index 1: Number of channels for transmit PDOs (1st drive) Index 2: Reserved Correspondingly, indices 3 to 5 are valid for the 2nd drive, etc.		
Index:	[0] = Number of channels for receive PDOs (drive 1) [1] = Number of channels for transmit PDOs (drive 1) [2] = Reserved [3] = Number of channels for receive PDOs (drive 2) [4] = Number of channels for transmit PDOs (drive 2) [5] = Reserved [6] = Number of channels for receive PDOs (drive 3) [7] = Number of channels for transmit PDOs (drive 3) [8] = Reserved [9] = Number of channels for receive PDOs (drive 4) [10] = Number of channels for transmit PDOs (drive 4) [11] = Reserved [12] = Number of channels for receive PDOs (drive 5) [13] = Number of channels for transmit PDOs (drive 5) [14] = Reserved		

[15] = Number of channels for receive PDOs (drive 6)
 [16] = Number of channels for transmit PDOs (drive 6)
 [17] = Reserved
 [18] = Number of channels for receive PDOs (drive 7)
 [19] = Number of channels for transmit PDOs (drive 7)
 [20] = Reserved
 [21] = Number of channels for receive PDOs (drive 8)
 [22] = Number of channels for transmit PDOs (drive 8)
 [23] = Reserved

Dependency: Refer to: p8741
Note: Channel assignment not yet in effect. To acknowledge set p8741 = 1.

p8741 CBC PDO configuration acknowledgement / PDO config ackn

CU_S (CAN)	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min	Max	Factory setting
	0	1	0

Description: Acknowledges the channel distribution selection made (p8740) and the setting of the predefined connection sets (p8744).

Values:
 0: not active
 1: Acknowledge configuration

Dependency: Refer to: p8740

r8742 CBC number of free RPDO channels / Qty free RPDO

CU_S (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Communications		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the RPDO channels that are still available.

Dependency: Refer to: p8741

Note: The display is updated after acknowledging the configuration (p8741 = 1).
 RPDO: Receive Process Data Object

r8743[0...7] CBC assignment, drive ID / Drive ID

CU_S (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the drive ID associated with each drive.

Index:
 [0] = Drive ID for 1st drive
 [1] = Drive ID for 2nd drive
 [2] = Drive ID for 3rd drive
 [3] = Drive ID for 4th drive
 [4] = Drive ID for 5th drive
 [5] = Drive ID for 6th drive
 [6] = Drive ID for 7th drive
 [7] = Drive ID for 8th drive

p8744 CBC PDO mapping configuration / PDO Mapping conf.

SERVO (CAN), VEC-TOR (CAN)	Can be changed: C2, T	Dynamic index: -	Access level: 2
	Data type: Integer16		Function diagram: 9204, 9206, 9208, 9210
	P-Group: -	Units group: -	Unit selection: -
	Min 1	Max 2	Factory setting 2
Description:	Selector switch for the PDO mapping. Sets the mapping for download or in the online mode after acknowledging with p8741.		
Values:	1: Predefined Connection Set 2: Free PDO Mapping		

r8750[0...15] CBC mapped 16-bit receive objects / RPDO 16 mapped

SERVO (CAN), VEC-TOR (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -

Description: Displays 16-bit receive CANopen objects mapped to process data buffer.
Example:
The control word is mapped in p8720[0] and p8721[0]; this means that r8750[0] indicates that it is located at the first position (p8850[0]) in the process data buffer.

Index:	[0] = PZD 1
	[1] = PZD 2
	[2] = PZD 3
	[3] = PZD 4
	[4] = PZD 5
	[5] = PZD 6
	[6] = PZD 7
	[7] = PZD 8
	[8] = PZD 9
	[9] = PZD 10
	[10] = PZD 11
	[11] = PZD 12
	[12] = PZD 13
	[13] = PZD 14
	[14] = PZD 15
	[15] = PZD 16

r8751[0...15] CBC mapped 16-bit transmit objects / TPDO 16 mapped

SERVO (CAN), VEC-TOR (CAN)	Can be changed: - Data type: Unsigned16 P-Group: Communications Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: - Unit selection: - Factory setting -
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Description: Displays mapped 16-bit transmit CANopen objects in the process data buffer.

Index:

- [0] = PZD 1
- [1] = PZD 2
- [2] = PZD 3
- [3] = PZD 4
- [4] = PZD 5
- [5] = PZD 6
- [6] = PZD 7
- [7] = PZD 8
- [8] = PZD 9
- [9] = PZD 10
- [10] = PZD 11
- [11] = PZD 12
- [12] = PZD 13
- [13] = PZD 14
- [14] = PZD 15
- [15] = PZD 16

Dependency: Refer to: r8750

r8760[0...14] CBC mapped 32-bit receive objects / RPDO 32 mapped

SERVO (CAN), VEC-TOR (CAN)	Can be changed: - Data type: Unsigned16 P-Group: Communications Min -	Dynamic index: - Units group: - Max -	Access level: 3 Function diagram: - Unit selection: - Factory setting -
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Description: Displays 32-bit receive CANopen objects mapped to process data buffer.

Index:

- [0] = PZD 1 + 2
- [1] = PZD 2 + 3
- [2] = PZD 3 + 4
- [3] = PZD 4 + 5
- [4] = PZD 5 + 6
- [5] = PZD 6 + 7
- [6] = PZD 7 + 8
- [7] = PZD 8 + 9
- [8] = PZD 9 + 10
- [9] = PZD 10 + 11
- [10] = PZD 11 + 12
- [11] = PZD 12 + 13
- [12] = PZD 13 + 14
- [13] = PZD 14 + 15
- [14] = PZD 15 + 16

r8761[0...14] CBC mapped 32-bit transmit objects / TPDO 32 mapped

SERVO (CAN), VEC-TOR (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Communications		Unit selection: -
	Min	Max	Factory setting

- - -

Description: Displays mapped 32-bit transmit CANopen objects in the process data buffer.

Index:

- [0] = PZD 1 + 2
- [1] = PZD 2 + 3
- [2] = PZD 3 + 4
- [3] = PZD 4 + 5
- [4] = PZD 5 + 6
- [5] = PZD 6 + 7
- [6] = PZD 7 + 8
- [7] = PZD 8 + 9
- [8] = PZD 9 + 10
- [9] = PZD 10 + 11
- [10] = PZD 11 + 12
- [11] = PZD 12 + 13
- [12] = PZD 13 + 14
- [13] = PZD 14 + 15
- [14] = PZD 15 + 16

r8784 CO: CBC status word / Status word

SERVO (CAN), VEC-TOR (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: 8010
	P-Group: Communications		Unit selection: -
	Min	Max	Factory setting

- - 0000 bin

Description: Displays the CANopen status word.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Ready to power up	Yes	No	-
	01	Ready	Yes	No	-
	02	Operation enabled	Yes	No	-
	03	Fault present	Yes	No	-
	04	No coasting active	Yes	No	-
	05	No fast stop active	Yes	No	-
	06	Power-on inhibit active	Yes	No	-
	07	Alarm present	Yes	No	-
	08	Can be freely interconnected (BI: p8785)	High	Low	-
	09	Control requested	Yes	No	-
	10	Target reached	Yes	No	-
	11	Torq limit reached	Yes	No	-
	12	Velocity equal to zero	Yes	No	-
	14	Can be freely interconnected (BI: p8786)	High	Low	-
	15	Can be freely interconnected (BI: p8787)	High	Low	-

Note: Corresponds to the CANopen object 6041 hex + 800 hex * x (x: Drive number 0 ... 7).

Re bit 10:

When the ramp-function generator is activated, the interconnection from CI: p2151 = r1119 can be changed, so that to evaluate bit 10, the setpoint can be retrieved (taken) from in front of the ramp-function generator.

Re bit 10, 12:

When braking, the two bits must indicate the same state. This is the reason that the following parameters must be set the same:

p2161 (speed threshold value 3, for r2199.0) = p2163 (speed threshold value 4, for r2197.7)

p2150 (hysteresis speed 3, for r2199.0) = p2164 (hysteresis speed 4, for r2197.7)

p8785	BI: CBC status word bit 8 / Status word bit 8			
SERVO (CAN), VEC-TOR (CAN)	Can be changed: T	Dynamic index: -	Access level: 3	
	Data type: Unsigned32	Units group: -	Function diagram: -	
	P-Group: Communications		Unit selection: -	
	Min	Max	Factory setting	
	-	-	0	
Description:	Binector input for CANopen status word bit 8.			
Dependency:	Refer to: r8784			
p8786	BI: CBC status word bit 14 / Status word bit 14			
SERVO (CAN), VEC-TOR (CAN)	Can be changed: T	Dynamic index: -	Access level: 3	
	Data type: Unsigned32	Units group: -	Function diagram: -	
	P-Group: Communications		Unit selection: -	
	Min	Max	Factory setting	
	-	-	0	
Description:	Binector input for CANopen status word bit 14.			
Dependency:	Refer to: r8784			
p8787	BI: CBC status word bit 15 / Status word bit 15			
SERVO (CAN), VEC-TOR (CAN)	Can be changed: T	Dynamic index: -	Access level: 3	
	Data type: Unsigned32	Units group: -	Function diagram: -	
	P-Group: Communications		Unit selection: -	
	Min	Max	Factory setting	
	-	-	0	
Description:	Binector input for CANopen status word bit 15.			
Dependency:	Refer to: r8784			
p8790	CBC control word - auto interconnection / STW_interconn.auto			
SERVO (CAN), VEC-TOR (CAN)	Can be changed: C1(3), T	Dynamic index: -	Access level: 3	
	Data type: Integer16	Units group: -	Function diagram: -	
	P-Group: Communications		Unit selection: -	
	Min	Max	Factory setting	
	0	1	0	
Description:	Sets the automatic BICO interconnection of the CANopen control word.			
Values:	0: No interconn 1: Interconnection			
Dependency:	Refer to: r8750, r8795, r8850			
Note:	The following BICO interconnections are automatically established if the CANopen control word is mapped at one of the locations x = 0 ... 3 in the receive process data buffer. BI: p0840.0 = r889x.0 BI: p0844.0 = r889x.1 BI: p0848.0 = r889x.2 BI: p0852.0 = r889x.3 BI: p2103.0 = r889x.7			
	The write access is rejected if a CANopen control word is not mapped at one of these locations. This means that the STARTER project download is interrupted.			

r8795 CBC control word / Control word

SERVO (CAN), VEC-TOR (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min -	Max -	Factory setting 0000 bin

Description: Access to the CANopen control word using SDO transfer.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	Do not activate coast down	Yes	No	-
	02	Do not activate a fast stop	Yes	No	-
	03	Enable operation	Yes	No	-
	07	Acknowledge fault	Yes	No	-
	11	Freely interconn	High	Low	-
	12	Freely interconn	High	Low	-
	13	Freely interconn	High	Low	-
	14	Freely interconn	High	Low	-
	15	Freely interconn	High	Low	-

Dependency: Refer to: p8790

Note: Corresponds to the CANopen object 6040 hex + 800 hex * x (x: Drive number 0 ... 7).

r8796 CBC target velocity / Target velocity

SERVO (CAN), VEC-TOR (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Integer32	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min -	Max -	Factory setting -

Description: Access to the CANopen object target velocity using the SDO transfer.
The value is displayed in increments/second as standard.

Note: Corresponds to the CANopen object 60FF hex + 800 hex * x (x: Drive number 0 ... 7).
The displayed value is calculated as follows:
 $r8796 = n_set \text{ [RPM]} / 60 \text{ s} * p0408 * 2^{p0418} * p8798[1] / p8798[0]$

r8797 CBC target torque / Target torque

SERVO (CAN), VEC-TOR (CAN)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min -	Max -	Factory setting -

Description: Access to the CANopen object target torque using SDO transfer.
The value is displayed as per mille (1/1000) as standard.

Note: Corresponds to the CANopen object 6071 hex + 800 hex * x (x: Drive number 0 ... 7).
The displayed value is calculated as follows:
 $r8797 \text{ [per mille]} = M_set \text{ [Nm]} / p0333 \text{ [Nm]} * 1000$

p8798[0...1]	CBC speed conversion factor / n_conv_factor			
SERVO (CAN), VECTOR (CAN)	Can be changed: T		Dynamic index: -	Access level: 3
	Data type: Unsigned32		Units group: -	Function diagram: -
	P-Group: -			Unit selection: -
	Min 1	Max 4294967295		Factory setting 1
Description:	The factor converts the required velocity units into the internal velocity units (U/s). With the factor setting, for CANopen, the velocity units are increments/second. The parameter corresponds to the CANopen object 6094 hex. The internal velocity is calculated as follows: $n_set_internal = object\ 6094.1 / object\ 6094.2 * 1 / (p0408 * 2^{p0418}) * n_set_bus$			
Index:	[0] = Counter [1] = Denominator			
p8840	COMM BOARD monitoring time / CB t_monitoring			
CU_S (CB, CBE)	Can be changed: U, T		Dynamic index: -	Access level: 3
	Data type: Floating Point		Units group: -	Function diagram: -
	P-Group: Communications			Unit selection: -
	Min 0 [ms]	Max 65535000 [ms]		Factory setting 20 [ms]
p8841[0...39]	COMM BOARD send configuration data / CB S_config_data			
CU_S (CB, CBE)	Can be changed: U, T		Dynamic index: -	Access level: 3
	Data type: Unsigned16		Units group: -	Function diagram: -
	P-Group: Communications			Unit selection: -
	Min 0	Max 65535		Factory setting 0
p8842	COMM BOARD start configuration / CB config start			
CU_S (CB, CBE)	Can be changed: U, T		Dynamic index: -	Access level: 3
	Data type: Unsigned16		Units group: -	Function diagram: -
	P-Group: Communications			Unit selection: -
	Min 0	Max 1		Factory setting 0
r8849[0...139]	COMM BOARD receive configuration data / CB E_config_data			
CU_S (CB, CBE)	Can be changed: -		Dynamic index: -	Access level: 3
	Data type: Unsigned16		Units group: -	Function diagram: -
	P-Group: Communications			Unit selection: -
	Min -	Max -		Factory setting -

r8850[0...15]	CO: COMM BOARD PZD receive word / CB PZD recv word		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Connector output for interconnecting the PZD (setpoints) received from the COMM BOARD in the word format.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16		
Dependency:	Refer to: r8860, r8890, r8891, r8892, r8893		
Note:	PZD1 to PZD4 are displayed bit-serially in r8890 to r8893.		

p8851[0...15]	CI: COMM BOARD PZD send word / CB PZD send word		
SERVO, VECTOR	Can be changed: U, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 9208
	P-Group: Communications	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	0
Description:	Selects PZD (actual values) to be sent to COMM BOARD in the word format.		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16		
Dependency:	Refer to: p8861		

r8853[0...15] COMM BOARD PZD send diagnostics / CB diag PZD send					
SERVO, VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 9208, 9210	
	P-Group: Communications	Units group: -		Unit selection: -	
	Min -	Max -		Factory setting 0000 bin	
Description:	Displays PZD (actual values) sent to COMM BOARD.				
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4 [4] = PZD 5 [5] = PZD 6 [6] = PZD 7 [7] = PZD 8 [8] = PZD 9 [9] = PZD 10 [10] = PZD 11 [11] = PZD 12 [12] = PZD 13 [13] = PZD 14 [14] = PZD 15 [15] = PZD 16				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: p8851, p8861				

r8854	COMM BOARD state / CB state		
CU_S (CB, CBE)	Can be changed: -		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min 0	Max 255	Factory setting 0
Description:	Status display for COMM BOARD.		
Values:	0: No initialization 1: Fatal Error 2: Initialization 3: Send configuration 4: Receive configuration 5: Non-cyclic communication 6: Cyclic communications but no setpoints (stop/no clock cycle) 255: Cyclic communication		
r8858[0...39]	COMM BOARD read diagnostics channel / CB diagn. read		
CU_S (CB, CBE)	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
r8859[0...7]	COMM BOARD identification Data / CB Ident_data		
CU_S (CB, CBE)	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
r8860[0...14]	CO: COMM BOARD PZD receive double word / CB PZD recv DW		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Integer32	Dynamic index: -	Function diagram: 9204, 9206
	P-Group: Communications	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Connector output for interconnecting the PZD (setpoints) received from the COMM BOARD with double word format		
Index:	[0] = PZD 1 + 2 [1] = PZD 2 + 3 [2] = PZD 3 + 4 [3] = PZD 4 + 5 [4] = PZD 5 + 6 [5] = PZD 6 + 7 [6] = PZD 7 + 8 [7] = PZD 8 + 9 [8] = PZD 9 + 10 [9] = PZD 10 + 11 [10] = PZD 11 + 12 [11] = PZD 12 + 13 [12] = PZD 13 + 14 [13] = PZD 14 + 15 [14] = PZD 15 + 16		
Dependency:	Refer to: r8850		

p8861[0...14] CI: COMM BOARD PZD send doubleword / CB PZD send DW

SERVO, VECTOR	Can be changed: U, T	Access level: 3
	Data type: Unsigned32	Function diagram: 9208, 9210
	Dynamic index: -	Unit selection: -
	P-Group: Communications	Unit selection: -
	Units group: -	Factory setting
	Min	0
	-	
	Max	
	-	

Description: Selects PZD (actual values) to be sent to COMM BOARD in the double word format.

Index:

- [0] = PZD 1 + 2
- [1] = PZD 2 + 3
- [2] = PZD 3 + 4
- [3] = PZD 4 + 5
- [4] = PZD 5 + 6
- [5] = PZD 6 + 7
- [6] = PZD 7 + 8
- [7] = PZD 8 + 9
- [8] = PZD 9 + 10
- [9] = PZD 10 + 11
- [10] = PZD 11 + 12
- [11] = PZD 12 + 13
- [12] = PZD 13 + 14
- [13] = PZD 14 + 15
- [14] = PZD 15 + 16

Dependency: Refer to: p8851

r8890 BO: COMM BOARD PZD1 receive bit-serial / CB PZD1 recv bitw

SERVO, VECTOR	Can be changed: -	Access level: 3
	Data type: Unsigned16	Function diagram: 9204, 9206
	Dynamic index: -	Unit selection: -
	P-Group: Communications	Unit selection: -
	Units group: -	Factory setting
	Min	0000 bin
	-	
	Max	
	-	

Description: Binector output for bit-serial interconnection of a PZD1 (normally control word 1) word received from the COMM BOARD.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-

Dependency: Refer to: r8850

r8891		BO: COMM BOARD PZD2 receive bit-serial / CB PZD2 recv bitw			
SERVO, VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 9204, 9206	
	P-Group: Communications	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Binector output for bit-serial interconnection of a PZD2 word received from the COMM BOARD.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: r8850				

r8892		BO: COMM BOARD PZD3 receive bit-serial / CB PZD3 recv bitw			
SERVO, VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 9204, 9206	
	P-Group: Communications	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Binector output for bit-serial interconnection of a PZD3 word received from the COMM BOARD..				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: r8850				

r8893		BO: COMM BOARD PZD4 receive bit-serial / CB PZD4 recv bitw			
SERVO, VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned16	Dynamic index: -		Function diagram: 9204, 9206	
	P-Group: Communications	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Binector output for bit-serial interconnection of a PZD4 (normally control word 2) word received from the COMM BOARD.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Bit 0	On	Off	-
	01	Bit 1	On	Off	-
	02	Bit 2	On	Off	-
	03	Bit 3	On	Off	-
	04	Bit 4	On	Off	-
	05	Bit 5	On	Off	-
	06	Bit 6	On	Off	-
	07	Bit 7	On	Off	-
	08	Bit 8	On	Off	-
	09	Bit 9	On	Off	-
	10	Bit 10	On	Off	-
	11	Bit 11	On	Off	-
	12	Bit 12	On	Off	-
	13	Bit 13	On	Off	-
	14	Bit 14	On	Off	-
	15	Bit 15	On	Off	-
Dependency:	Refer to: r8850				

p9300		SI motion monitoring clock cycle (Motor Module) / SI Mtn clock MM		
SERVO, VECTOR	Can be changed: U, T			Access level: 4
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	500.00 [µs]	25000.00 [µs]		12000.00 [µs]
Description:	Sets the monitoring clock cycle for safe motion monitoring.			
Dependency:	Refer to: p0115, p9500 Refer to: F01652			
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.			
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.			
Note:	The monitoring clock cycle must be a multiple of the position controller clock cycle.			

p9301		SI motion enable safety functions (Motor Module) / SI Mtn enable MM			
SERVO, VECTOR	Can be changed: U, T			Access level: 4	
	Data type: Unsigned32	Dynamic index: -		Function diagram: -	
	P-Group: Safety Integrated	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Sets the enable signals for the safe motion monitoring.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00				-
	03	Enable actual value synchronization	Enable	Inhibit	-
	06				-
Dependency:	Refer to: p9501 Refer to: F01682, F01683				

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.
Notice: This parameter is overwritten by the copy function of the drive-based safety functions.
Note: A change only becomes effective after a POWER ON.
 SOS: Safe operating stop
 SLS: Safely-reduced speed

p9302 SI motion axis type (Motor Module) / SI Mtn AxisType MM

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Integer16 **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0 1 0

Description: Sets the axis type (linear axis or rotary axis/spindle).

Values:
 0: Linear axis
 1: Rot axis/spindle

Dependency: Refer to: p9502

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.

Notice: This parameter is overwritten by the copy function of the drive-based safety functions.

Note: A change only becomes effective after a POWER ON.

p9316 SI motion enc. configuration, safety functions (Motor Module) / SI Mtn enc cfg MM

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Sets the configuration for the encoder and position actual value.

The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Encoder, rotating/linear	Linear	Rotating:	-
	01	Position actual value, sign change	Yes	No	-

Dependency: Refer to: p0404, p0410, p9516

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.

Note: A change only becomes effective after a POWER ON.

p9317 SI motion linear scale, grid division (Motor Module) / SI Mtn grid MM

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Floating Point **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0.00 [nm] 250000000.00 [nm] 10000.00 [nm]

Description: Sets the grid division for a linear encoder.

The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.

Dependency: Refer to: p0407, p9316

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.

Note: A change only becomes effective after a POWER ON.

p9318	SI motion encoder pulses per revolution (Motor Module) / SI Mtn p/rev MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0	Max 100000	Factory setting 2048
Description:	Sets the number of encoder pulses per revolution for rotary encoders. The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.		
Dependency:	Refer to: p0408, p9316		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Note:	A change only becomes effective after a POWER ON.		
p9319	SI motion fine resolution G1_XIST1 (Motor Module) / SI Mtn fine resolu		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 2	Max 18	Factory setting 11
Description:	Sets the fine resolution for G1_XIST1 in bits. For safe functions that are not enabled (p9301 = 0), the following applies: p9319 is automatically set the same as p0418 at run-up. For safety functions that are enabled (p9301 > 0), the following applies: p9319 is checked to see that it matches p0418. The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.		
Dependency:	Refer to: p0418 Refer to: F01670, F01671		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Note:	A change only becomes effective after a POWER ON. G1_XIST1: Position actual value of the encoder according to PROFIdrive		
p9320	SI motion spindle pitch (Motor Module) / SI Mtn sp_pitch MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.10 [mm]	Max 8388.00 [mm]	Factory setting 10.00 [mm]
Description:	Sets the gear ratio between the encoder and load in mm/rev for a linear axis with rotary encoder. The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.		
Dependency:	Refer to: p9520		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Note:	A change only becomes effective after a POWER ON.		

p9321[0...7] SI motion gearbox encoder/load denominator (Motor Module) / SI Mtn gearDenomMM			
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 1	Max 2147000000	Factory setting 1
Description:	Sets the denominator for the gearbox between the encoder and load. The actual gearbox stage is selected via safety-relevant inputs (SGE). The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.		
Index:	[0] = Gearbox 1 [1] = Gearbox 2 [2] = Gearbox 3 [3] = Gearbox 4 [4] = Gearbox 5 [5] = Gearbox 6 [6] = Gearbox 7 [7] = Gearbox 8		
Dependency:	Refer to: p9322		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Note:	A change only becomes effective after a POWER ON.		
p9322[0...7] SI motion gearbox encoder/load numerator / SI Mtn gear num MM			
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 1	Max 2147000000	Factory setting 1
Description:	Sets the numerator for the gearbox between the encoder and load. The actual gearbox stage is selected via safety-relevant inputs (SGE). The encoder that is used for the safe motion monitoring functions on the Motor Module must be parameterized in this parameter.		
Index:	[0] = Gearbox 1 [1] = Gearbox 2 [2] = Gearbox 3 [3] = Gearbox 4 [4] = Gearbox 5 [5] = Gearbox 6 [6] = Gearbox 7 [7] = Gearbox 8		
Dependency:	Refer to: p9321		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Note:	A change only becomes effective after a POWER ON.		
p9326 SI motion encoder assignment (Motor Module) / SI Mtn encoder MM			
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 1	Max 3	Factory setting 1
Description:	Sets the number of the encoder that the Motor Module uses for safe motion monitoring functions.		
Dependency:	For the safe motion monitoring functions, the redundant safety position actual value sensing must be activated in the appropriate encoder data set (p0430.19 = 1). Refer to: p0187, p0188, p0189, p0430, p9526		

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.
Notice: This parameter is overwritten by the copy function of the drive-based safety functions.
Note: If a 1 is parameterized (the Motor Module uses an encoder for closed-loop speed control), then a single-encoder system is being used.
 A change only becomes effective after a POWER ON.

p9328[0...11] SI Motion Sensor Module Node Identifier (Motor Module) / SI Mtn SM NodId MM

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Unsigned8 **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0000 hex 00FF hex 0000 hex

Description: Node Identifier of the Sensor Module that is used by the Motor Module for the motion monitoring functions.

Dependency: Refer to: r9881

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.

Notice: This parameter is overwritten by the copy function of the drive-based safety functions.

p9330 SI motion standstill tolerance (Motor Module) / SI Mtn SOS Tol MM

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Floating Point **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0.00 [mm] 100.00 [mm] 1.00 [mm]

Description: Sets the tolerance in mm or degrees for the function "safe operating stop" (SBH/SOS).

Dependency: Refer to: p9530

Refer to: C01707

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.

Notice: This parameter is overwritten by the copy function of the drive-based safety functions.

Note: A change only becomes effective after a POWER ON.

p9330 SI motion standstill tolerance (Motor Module) / SI Mtn SOS Tol MM

SERVO (Safety rot) **Can be changed:** U, T **Access level:** 4
Data type: Floating Point **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0.00 [°] 100.00 [°] 1.00 [°]

Description: Sets the tolerance in mm or degrees for the function "safe operating stop" (SBH/SOS).

Dependency: Refer to: p9530

Refer to: C01707

Caution: The parameter has not been released in firmware version 2.4 and may not be changed.

Notice: This parameter is overwritten by the copy function of the drive-based safety functions.

Note: A change only becomes effective after a POWER ON.

p9331[0...3]	SI motion SG limit values / SI Mtn SG lim MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 1000000.00 [mm/min]	Factory setting 2000.00 [mm/min]
Description:	Sets the limit values for the function "safely reduced speed" (SLS).		
Index:	[0] = Limit value SG1 [1] = Limit value SG2 [2] = Limit value SG3 [3] = Limit value SG4		
Dependency:	Refer to: p9363, p9531 Refer to: C01714		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
p9331[0...3]	SI motion SG limit values / SI Mtn SG lim MM		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 1000000.00 [1/min]	Factory setting 2000.00 [1/min]
Description:	Sets the limit values for the function "safely reduced speed" (SLS).		
Index:	[0] = Limit value SG1 [1] = Limit value SG2 [2] = Limit value SG3 [3] = Limit value SG4		
Dependency:	Refer to: p9363, p9531 Refer to: C01714		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
p9342	SI motion act val comparison tol (crosswise) (Motor Module) / SI Mtn act tol MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0010 [mm]	Max 360.0000 [mm]	Factory setting 0.1000 [mm]
Description:	Sets the tolerance for the crosswise data comparison of the actual position between the two monitoring channels.		
Dependency:	Refer to: p9542 Refer to: C01711		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9342	SI motion act val comparison tol (crosswise) (Motor Module) / SI Mtn act tol MM		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0010 [°]	Max 360.0000 [°]	Factory setting 0.1000 [°]
Description:	Sets the tolerance for the crosswise data comparison of the actual position between the two monitoring channels.		
Dependency:	Refer to: p9542 Refer to: C01711		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
p9346	SI motion velocity limit n_x (Motor Module) / SI Mtn lim n_x MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 6000.00 [mm/min]	Factory setting 20.00 [mm/min]
Description:	Sets the velocity limit n_x to detect standstill (zero speed). When this limit value is fallen below, SGA "n < n_x" is set.		
Dependency:	Refer to: p9546		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON. SGA: Safety-related output		
p9346	SI motion velocity limit n_x (Motor Module) / SI Mtn lim n_x MM		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 6000.00 [1/min]	Factory setting 20.00 [1/min]
Description:	Sets the velocity limit n_x to detect standstill (zero speed). When this limit value is fallen below, SGA "n < n_x" is set.		
Dependency:	Refer to: p9546		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON. SGA: Safety-related output		

p9348	SI motion SBR actual velocity tolerance (Motor Module) / SI Mtn SBR Tol MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 120000.00 [mm/min]	Factory setting 300.00 [mm/min]
Description:	Sets the velocity tolerance for the "Safe Braking Ramp" (SBR).		
Dependency:	Refer to: p9548 Refer to: C01706		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON. SBR: Safe braking ramp		
p9348	SI motion SBR actual velocity tolerance (Motor Module) / SI Mtn SBR Tol MM		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 120000.00 [1/min]	Factory setting 300.00 [1/min]
Description:	Sets the velocity tolerance for the "Safe Braking Ramp" (SBR).		
Dependency:	Refer to: p9548 Refer to: C01706		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON. SBR: Safe braking ramp		
p9349	SI motion slip velocity tolerance (Motor Module) / SI Mtn slip MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 6000.00 [mm/min]	Factory setting 6.00 [mm/min]
Description:	Sets the velocity tolerance that is used for a two encoder system in crosswise comparison between the Control Unit and the Motor Module.		
Dependency:	Refer to: p9301, p9342, p9549		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	If the "actual value synchronization" is not enabled (p9301.3 = 0), then the value parameterized in p9342 is used as tolerance in the crosswise data comparison. A change only becomes effective after a POWER ON.		

p9349	SI motion slip velocity tolerance (Motor Module) / SI Mtn slip MM		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 6000.00 [1/min]	Factory setting 6.00 [1/min]
Description:	Sets the velocity tolerance that is used for a two encoder system in crosswise comparison between the Control Unit and the Motor Module.		
Dependency:	Refer to: p9301, p9342, p9549		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	If the "actual value synchronization" is not enabled (p9301.3 = 0), then the value parameterized in p9342 is used as tolerance in the crosswise data comparison. A change only becomes effective after a POWER ON.		
p9351	SI motion SG changeover delay time (Motor Module) / SI Mtn SG t_del MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 60000000.00 [µs]	Factory setting 100000.00 [µs]
Description:	Sets the delay time for the SG changeover for the function "safely reduced speed" (SLS). When transitioning from a higher to a lower safely-reduced velocity/speed stage or to the safe operating stop (SOS), within this delay time, the "old" velocity stage remains active. Even if SLS or SOS is activated from non safety-related operation, then this delay is still applied.		
Dependency:	Refer to: p9551		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
p9352	SI motion transition time STOP C to SBH (Motor Module) / SI Mtn t C->SBH MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 10000000.00 [µs]	Factory setting 100000.00 [µs]
Description:	Sets the transition time from STOP C to "safe operating stop" (SBH).		
Dependency:	Refer to: p9552		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9353 SI motion transition time STOP D to SBH (Motor Module) / SI Mtn t D->SBH MM

SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 60000000.00 [µs]	Factory setting 100000.00 [µs]
Description:	Sets the transition time from STOP D to "safe operating stop" (SBH).		
Dependency:	Refer to: p9553		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9356 SI motion pulse cancellation delay time (Motor Module) / SI Mtn IL t_del MM

SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 10000000.00 [µs]	Factory setting 100000.00 [µs]
Description:	Sets the delay time for the safe pulse cancellation after STOP B / SS1.		
Dependency:	Refer to: p9360, p9556 Refer to: C01701		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9357 SI motion pulse cancellation test time (Motor Module) / SI Mtn IL tTest MM

SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 10000000.00 [µs]	Factory setting 100000.00 [µs]
Description:	Sets the time after which the pulses must have been cancelled when initiating the test stop.		
Dependency:	Refer to: p9557 Refer to: C01798		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9358 SI motion acceptance test mode time limit (Motor Module) / SI Mtn t accept MM

SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 5000000.00 [µs]	Max 100000000.00 [µs]	Factory setting 40000000.00 [µs]
Description:	Sets the maximum time for the acceptance test mode. If the acceptance test mode takes longer than the selected time limit, then the mode is automatically terminated.		
Dependency:	Refer to: p9558, Refer to: C01799		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9360	SI motion pulse cancellation shutdown speed (Motor Module) / SI Mtn IL n_shd MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 6000.00 [mm/min]	Factory setting 0.00 [mm/min]
Description:	Sets the velocity, under which the axis is considered to be "stationary" and for a STOP B, the pulses are cancelled (by changing to STOP A).		
Dependency:	Refer to: p9356, p9560		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
p9360	SI motion pulse cancellation shutdown speed (Motor Module) / SI Mtn IL n_shd MM		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 6000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the velocity, under which the axis is considered to be "stationary" and for a STOP B, the pulses are cancelled (by changing to STOP A).		
Dependency:	Refer to: p9356, p9560		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
p9363[0...3]	SI motion stop response SLS (Motor Module) / SI Mtn Stop SLS MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0	Max 13	Factory setting 2
Description:	Sets the stop response for the function "safely reduced speed" (SLS). This setting applies to the individual SG limit values.		
Values:	0: STOP A 1: STOP B 2: STOP C 3: STOP D 10: STOP A with delayed pulse cancellation when the bus fails 11: STOP B with delayed pulse cancellation when the bus fails 12: STOP C with delayed pulse cancellation when the bus fails 13: STOP D with delayed pulse cancellation when the bus fails		
Index:	[0] = Limit value SG1 [1] = Limit value SG2 [2] = Limit value SG3 [3] = Limit value SG4		
Dependency:	Refer to: p9331, p9380, p9563		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		

p9370	SI motion acceptance test mode (Motor Module) / SI Mtn acc mode MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max 00AC hex	Factory setting 0000 hex
Description:	Setting to select and de-select the acceptance test mode.		
Values:	0: [00 hex] De-select the acceptance test mode 172: [AC hex] Select the acceptance test mode		
Dependency:	Refer to: p9358, r9371, Refer to: C01799		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
r9371	SI motion acceptance test status (Motor Module) / SI Mtn acc stat MM		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max 00AC hex	Factory setting 0000 hex
Description:	Displays the status of the acceptance test mode.		
Values:	0: [00 hex] Acc_mode inactive 12: [0C hex] Acc_mode not possible due to POWER ON fault 13: [0D hex] Acc_mode not possible due to incorrect ID in p9370 15: [0F hex] Acc_mode not possible due to expired Acc_timer 172: [AC hex] Acc_mode active		
Dependency:	Refer to: p9358, p9370 Refer to: C01799		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
p9380	SI motion pulse cancellation delay bus failure (Motor Module) / SI Mtn t to IL MM		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 800000.00 [µs]	Factory setting 0.00 [µs]
Description:	Sets the delay time after which the pulses are safely cancelled after a bus failure.		
Dependency:	Refer to: p9363		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
Notice:	This parameter is overwritten by the copy function of the drive-based safety functions.		
Note:	A change only becomes effective after a POWER ON.		
r9398[0...1]	SI motion actual checksum SI parameters (Motor Module) / SI Mtn act CRC MM		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the checksum for the checked Safety Integrated parameters of the motion monitoring function (actual checksum) on the Motor Module.		
Index:	[0] = Check sum over SI parameters for motion monitoring [1] = Check sum over SI parameters for actual values		
Dependency:	Refer to: p9399		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		

p9399[0...1] SI motion reference checksum SI parameters (Motor Module) / SI Mtn ref CRC MM			
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the checksum for the checked Safety Integrated parameters of the motion monitoring function (actual checksum) on the Motor Module.		
Index:	[0] = Check sum over SI parameters for motion monitoring [1] = Check sum over SI parameters for actual values		
Dependency:	Refer to: r9398		
Caution:	The parameter has not been released in firmware version 2.4 and may not be changed.		
r9406[0...19] PS file parameter number, parameter not transferred / PS par n. transf			
All objects	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the parameters that were not able to be transferred when reading the parameter back-up files (PS files) from the CompactFlash card. r9406[0] = 0 --> All of the parameter values were able to be transferred error-free. r9406[0...x] > 0 --> Displays the parameter number whose value was not able to be completely transferred or for an indexed parameter, for at least 1 index, was not able to be transferred. The first index that is not transferred is displayed in r9407.		
Dependency:	Refer to: r9407, r9408		
Note:	All indices from r9406 to r9408 designate the same parameter. The parameter number is in r9406[x], the parameter index is in r9407[x], and the associated fault code is in r94088[x].		
r9407[0...19] PS file parameter index, parameter not transferred / PS paridx n.transf			
All objects	Can be changed: -		Access level: 1
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the first index of the parameter that was not able to be transferred when reading the parameter back-up files (PS files) from the CompactFlash card. If, from an indexed parameter, at least one index was not able to be transferred, then the parameter number is displayed in r9406[n] and the first index that was not transferred is displayed in r9407[n]. r9406[0] = 0 --> All of the parameter values were able to be transferred error-free. r9406[n] > 0 --> Displays r9407[n] the first index of the parameter number r9406[n] that was not transferred.		
Dependency:	Refer to: r9406, r9408		
Note:	All indices from r9406 to r9408 designate the same parameter. The parameter number is in r9406[x], the parameter index is in r9407[x], and the associated fault code is in r94088[x].		

r9408[0...19]	PS file fault code parameter not transferred / PS fault code		
All objects	Can be changed: -	Dynamic index: -	Access level: 1
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	Factory setting	
	-	-	-
Description:	Only for internal Siemens service.		
Note:	All indices from r9406 to r9408 designate the same parameter. The parameter number is in r9406[x], the parameter index is in r9407[x], and the associated fault code is in r94088[x].		
r9409	Number of parameters to be saved / Qty par to save		
All objects	Can be changed: -	Dynamic index: -	Access level: 4
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	Factory setting	
	-	-	-
Description:	Displays the number of modified parameters and those that have still not be saved for this drive object.		
Dependency:	Refer to: p0971, p0977		
Note:	The modified parameters that still need to be saved are internally listed in r9410 ... r9419.		
r9481	Number of BICO interconnections / BICO count		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16	Units group: -	Function diagram: -
	P-Group: Commands	Max	Unit selection: -
	Min	Factory setting	
	-	-	-
Description:	Displays the number of BICO interconnections (signal drains) to other drive objects. The selected BICO interconnections should be entered into r9482[0...59] and r9483[0...59].		
Dependency:	Refer to: r9482, r9483		
r9482[0...59]	BICO interconnections, BI/CI parameters / BICO BI/CI par		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32	Units group: -	Function diagram: -
	P-Group: Commands	Max	Unit selection: -
	Min	Factory setting	
	-	-	-
Description:	Displays the signal drains (Binector/Connector Inputs, BI/CI parameters) to other drive objects. The number of BICO interconnections to other drive objects is displayed in r9481.		
Dependency:	Refer to: r9481, r9483		
Note:	The list is sorted according to signal sources and is structured as follows: r9842[0]: Interconnection 1 (signal drain, BICO coded), r9843[0]: Interconnection 1 (signal source, BICO coded) r9842[1]: Interconnection 2 (signal drain, BICO coded), r9843[1]: Interconnection 2 (signal source, BICO coded) ...		

r9483[0...59]	BICO interconnections, BO/CO parameters / BICO BO/CO par		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: - Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the signal sources (Binector/Connector Outputs, BO/CO parameters) to other drive objects. The number of BICO interconnections to other drive objects is displayed in r9481.		
Dependency:	Refer to: r9481, r9482		
Note:	The list is sorted according to signal sources and is structured as follows: r9842[0]: Interconnection 1 (signal drain, BICO coded), r9843[0]: Interconnection 1 (signal source, BICO coded) r9842[1]: Interconnection 2 (signal drain, BICO coded), r9843[1]: Interconnection 2 (signal source, BICO coded) ...		
p9484	BICO interconnections, search signal source / BICO S_src srch		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: T Data type: Unsigned32	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 4294967295	Factory setting 0
Description:	Sets the signal source (BO/CO parameter, BICO coded) to search in the signal drains. The question is answered: How often is a connection made to a signal source in the drive object and from which index are these interconnections saved (r9482[0...59], r9483[0...59])?		
Dependency:	Refer to: r9481, r9482, r9483, r9485, r9486		
r9485	BICO interconnections, signal source search count / BICO S_src srchQty		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: - Data type: Unsigned16	Dynamic index: -	Access level: 3 Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the number of BICO interconnections to the signal drain being searched for. The signal source to be searched is set in p9484 (BICO-coded). The search result is contained in r9482[0...59] and r9483[0...59] and is specified by the count (r9485) and the first index (r9486).		
Dependency:	Refer to: r9481, r9482, r9483, p9484, r9486		

r9486	BICO interconnections, signal source search first index / BICO S_src srchldx		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the first index of the signal source being searched for. The signal source to be searched is set in p9484 (BICO-coded). The search result is contained in r9482[0...59] and r9483[0...59] and is specified by the count (r9485) and the first index (r9486).		
Dependency:	Refer to: r9481, r9482, r9483, p9484, r9485		
r9490	Number of BICO interconnections to other drives / Qty BICO to drive		
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of signal sources from this drive to other drives/drive objects (Binector Output/Connector Output, BO/CO).		
Dependency:	Refer to: r9491, r9492, p9493		
r9491[0...9]	BI/CI of BICO interconnections to other drives / BI/CI to drive		
All objects	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the signal receiver list (Binector Input/Connector Input, BI/CI) for the first interconnections between this drive and other drives/drive objects.		
Dependency:	Refer to: r9490, r9492, p9493		
Notice:	A drive cannot be deleted if this list is not empty! Otherwise, another drive would continue to attempt to read a signal from a drive that no longer existed.		
Note:	All indices of r9491 to p9493 designate the same interconnection. r9491[x] contains the signal receiver and r9492[x] the matching signal source; p9493[x] can be set to modify the interconnection.		

r9492[0...9]	BO/CO of BICO interconnections to other drives / BO/CO to drive		
All objects	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the signal source list (Binector Output/Connector Output, BO/CO) for the first interconnections between this drive and other drives/drive objects.		
Dependency:	Refer to: r9490, r9491, p9493		
Notice:	A drive cannot be deleted if this list is not empty! Otherwise, another drive would continue to attempt to read a signal from a drive that no longer existed.		
Note:	All indices of r9491 to p9493 designate the same interconnection. r9491[x] contains the signal receiver and r9492[x] the matching signal source; p9493[x] can be set to modify the interconnection.		
p9493[0...9]	Reset BICO interconnections to other drives / Reset BICO to drv		
All objects	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	15	15
Description:	Setting to reset the BICO interconnections to other drives. Each interconnection can be individually reset.		
Values:	0: Set connection to 0 1: Set connection to 1 (100 %) 2: Set connection to factory setting 15: Finished		
Dependency:	Refer to: r9490, r9491, r9492		
Note:	All indices of r9491 to p9493 designate the same interconnection. r9491[x] contains the signal receiver and r9492[x] the matching signal source; p9493[x] can be set to modify the interconnection.		
p9495	BICO behavior to de-activated drive objects / Behav to deact obj		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: T		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0	2	0
Description:	Setting for the behavior for BICO interconnections to other non-operational/de-activated drive objects. If this drive object has BICO interconnections to other non-operational or de-activated drive objects as drain, then using these parameters, all of the associated BI/CI parameters of this drive object can be set to the re-set value and marked, or only marked.		
Values:	0: Do not do anything 1: Mark connection 2: Set the connection to default and mark		
Dependency:	Refer to: p9496, p9497, r9498, r9499 Refer to: A01318, F01507		
Note:	The BI/CI parameters involved are listed in r9498[0...29] (drain). The associated BO/CO parameters are listed in r9499[0...29] (source). However, r9498 and r9499 are only then filled if p9495 is not equal to 0, otherwise they remain empty.		

p9496	Restore BICO to the drive objects that are now activated / Rest BICO act obj		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Integer16		Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 2	Factory setting 0
Description:	If this drive object has BICO interconnections to other drive objects that are either not operational or have been de-activated, then using this parameter, all of the BI/CI parameters involved with this drive object can be re-established.		
Values:	0: Do not do anything 1: Restore the connections from the list 2: Delete the connection from the list		
Dependency:	Refer to: p9495, p9497, r9498, r9499 Refer to: A01318, F01507		
Note:	The BI/CI parameters involved are listed in r9498[0...29] (drain). The associated BO/CO parameters are listed in r9499[0...29] (source). After setting p9496 to 1 or 2, r9498 and r9499 are reset, r9497 is set to 0 and p9496 itself is set to 0.		
p9497	BICO number of interconnections to de-activated drive objects / Qty to deact obj		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: T	Dynamic index: -	Access level: 3
	Data type: Unsigned16		Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Displays the number of signal drains of this drive object to other drives/drive objects that are no longer operational/de-activated (Binector Input/Connector Input, BI/CI).		
Dependency:	Refer to: p9495, p9496, r9498, r9499 Refer to: A01318, F01507		
Note:	The parameter is only used for display purposes and cannot be written into.		
r9498[0...29]	BICO BI/CI parameters to de-activated drive objects / BI/CI to deact obj		
A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned32		Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	List of the BI/CI parameters that represent a connection to non-operational/de-activated drive objects.		
Dependency:	Refer to: p9495, p9496, p9497, r9499 Refer to: A01318, F01507		
Note:	All indices from r9498 to r9499 designate the same BICO interconnection. This signal drain is in r9498[x] and the associated signal source in r9499[x].		

r9499[0...29] BICO BO/CO parameters to de-activated drive objects / BO/CO to deact obj

A_INF, B_INF, CU_LINK, CU_S, SERVO, TB30, TM15, TM15DI_DO, TM17, TM31, TM41, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Commands	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0

Description: List of the BO/CO parameters that represent a connection to non-operational/de-activated drive objects.

Dependency: Refer to: p9495, p9496, p9497, r9498
Refer to: A01318, F01507

Note: All indices from r9498 to r9499 designate the same BICO interconnection.
This signal drain is in r9498[x] and the associated signal source in r9499[x].

p9500 SI motion monitoring clock cycle / SI Mtn clock

SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.50 [ms]	Max 25.00 [ms]	Factory setting 12.00 [ms]

Description: Sets the monitoring clock cycle for safe motion monitoring.

Dependency: Refer to: p0115
Refer to: F01652

Note: The monitoring clock cycle must be a multiple of the position controller clock cycle.

p9501 SI motion enable safety-relevant functions / SI Mtn enable

SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0000 bin

Description: Sets the enable signals for the safe motion monitoring.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable SBH/SG	Enable	Inhibit	-
	01	Enable SE	Enable	Inhibit	-
	03	Enable actual value synchronization	Enable	Inhibit	-
	04	Enable external ESR activation	Enable	Inhibit	-
	05	Enable override SG	Enable	Inhibit	-
	06	Enable external STOPS	Enable	Inhibit	-
	07	Enable cam synchronization	Enable	Inhibit	-
	08	Enable SN1+	Enable	Inhibit	-
	09	Enable SN1 -	Enable	Inhibit	-
	10	Enable SN2 +	Enable	Inhibit	-
	11	Enable SN2 -	Enable	Inhibit	-
	12	Enable SN3 +	Enable	Inhibit	-
	13	Enable SN3 -	Enable	Inhibit	-
	14	Enable SN4 +	Enable	Inhibit	-
	15	Enable SN4 -	Enable	Inhibit	-

Dependency: Refer to: F01682, F01683

Note: A change only becomes effective after a POWER ON.
 ESR: Extended Stopping and Retraction
 SBH: Safe operating stop
 SE: Safe software limit switch
 SG: Safely-reduced speed
 SN: Safe software cam

p9502 SI motion axis type / SI Mtn axis type

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Integer16 **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0 1 0

Description: Sets the axis type (linear axis or rotary axis/spindle).

Values:
 0: Linear axis
 1: Rot axis/spindle

Note: A change only becomes effective after a POWER ON.

p9505 SI motion SN modulo value / SI Mtn Sn modulo

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Floating Point **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0 [°] 737280 [°] 0 [°]

Description: Sets the modulo range of the safe position actual value in degrees for the function "safe software cam" (SN) for rotary axes.

Dependency: Refer to: p9536, p9537

Note: A change only becomes effective after a POWER ON.
 SN: Safe software cam

p9516 SI motion motor encoder configuration, safety-relevant functions / SI Mtn enc config

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Unsigned16 **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 - - 0000 bin

Description: Sets the configuration for the motor encoder and position actual value.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Motor encoder, rotating/linear	Linear	Rotating:	-
	01	Position actual value, sign change	Yes	No	-

Note: A change only becomes effective after a POWER ON.

p9517 SI motion linear scale, grid division / SI Mtn grid

SERVO, VECTOR **Can be changed:** U, T **Access level:** 4
Data type: Floating Point **Dynamic index:** - **Function diagram:** -
P-Group: Safety Integrated **Units group:** - **Unit selection:** -
Min **Max** **Factory setting**
 0.00 [nm] 250000000.00 [nm] 10000.00 [nm]

Description: Sets the grid division for a linear motor encoder.

Dependency: Refer to: p9516

Note: A change only becomes effective after a POWER ON.

p9518	SI motion encoder pulses per revolution / SI Mtn pulses/rev		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0	Max 100000	Factory setting 2048
Description:	Sets the number of encoder pulses per revolution for rotary motor encoders.		
Dependency:	Refer to: p9516		
Note:	A change only becomes effective after a POWER ON.		

p9519	SI motion fine resolution G1_XIST1 / SI Mtn fine resolu		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 2	Max 18	Factory setting 11
Description:	Sets the fine resolution for G1_XIST1 in bits. For safe functions that are not enabled (p9501 = 0), the following applies: p9519 is automatically set the same as p0418 at run-up. For safety functions that are enabled (p9501 > 0), the following applies: p9519 is checked to see that it matches p0418.		
Dependency:	Refer to: p0418, Refer to: F01670, F01671		
Note:	A change only becomes effective after a POWER ON. G1_XIST1: Position actual value of the motor encoder according to PROFIdrive		

p9520	SI motion spindle pitch / SI Mtn Sp_pitch		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.10 [mm]	Max 8388.00 [mm]	Factory setting 10.00 [mm]
Description:	Sets the gear ratio between the encoder and load in mm/rev for a linear axis with rotary encoder.		
Note:	A change only becomes effective after a POWER ON.		

p9521[0...7]	SI motion gearbox encoder/load denominator / SI Mtn gear denom		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 1	Max 2147000000	Factory setting 1
Description:	Sets the denominator for the gearbox between the encoder and load. The actual gearbox stage is selected via safety-relevant inputs (SGE).		
Index:	[0] = Gearbox 1 [1] = Gearbox 2 [2] = Gearbox 3 [3] = Gearbox 4 [4] = Gearbox 5 [5] = Gearbox 6 [6] = Gearbox 7 [7] = Gearbox 8		
Dependency:	Refer to: p9522		
Note:	A change only becomes effective after a POWER ON.		

p9522[0...7]	SI motion gearbox encoder/load numerator / SI Mtn gear numer		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 1	Max 2147000000	Factory setting 1
Description:	Sets the numerator for the gearbox between the encoder and load. The actual gearbox stage is selected via safety-relevant inputs (SGE).		
Index:	[0] = Gearbox 1 [1] = Gearbox 2 [2] = Gearbox 3 [3] = Gearbox 4 [4] = Gearbox 5 [5] = Gearbox 6 [6] = Gearbox 7 [7] = Gearbox 8		
Dependency:	Refer to: p9521		
Note:	A change only becomes effective after a POWER ON.		
p9526	SI motion encoder assignment 2nd channel / SI Mtn enc 2ndChan		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 1	Max 3	Factory setting 1
Description:	Sets the number of the encoder that the 2nd channel (control, Motor Module) uses for safe motion monitoring functions.		
Dependency:	For the safe motion monitoring functions, the redundant safety position actual value sensing must be activated in the appropriate encoder data set (p0430.19 = 1). Refer to: p0187, p0188, p0189, p0430		
Note:	If a 1 is parameterized (the 2nd channel of the motion monitoring functions uses encoders for closed-loop speed control), then a single-encoder system is being used. A change only becomes effective after a POWER ON.		
p9530	SI motion standstill tolerance / SI Mtn standst_tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm]	Max 100.00 [mm]	Factory setting 1.00 [mm]
Description:	Sets the tolerance for the function "safe operating stop" (SBH).		
Dependency:	Refer to: C01707		
Note:	A change only becomes effective after a POWER ON.		

p9530	SI motion standstill tolerance / SI Mtn standst_tol		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [°]	Max 100.00 [°]	Factory setting 1.00 [°]
Description:	Sets the tolerance for the function "safe operating stop" (SBH).		
Dependency:	Refer to: C01707		
Note:	A change only becomes effective after a POWER ON.		

p9531[0...3]	SI motion SG limit values / SI Mtn SG lim val		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 1000000.00 [mm/min]	Factory setting 2000.00 [mm/min]
Description:	Sets the limit values for the function "safely reduced speed" (SG).		
Index:	[0] = Limit value SG1 [1] = Limit value SG2 [2] = Limit value SG3 [3] = Limit value SG4		
Dependency:	Refer to: p9532, p9561, p9563 Refer to: C01714		
Note:	A change only becomes effective after a POWER ON.		

p9531[0...3]	SI motion SG limit values / SI Mtn SG lim val		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 1000000.00 [1/min]	Factory setting 2000.00 [1/min]
Description:	Sets the limit values for the function "safely reduced speed" (SG).		
Index:	[0] = Limit value SG1 [1] = Limit value SG2 [2] = Limit value SG3 [3] = Limit value SG4		
Dependency:	Refer to: p9532, p9561, p9563 Refer to: C01714		
Note:	A change only becomes effective after a POWER ON.		

p9532[0...15]	SI motion SG override factor / SI Mtn SG override		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.000 [%]	Max 100.000 [%]	Factory setting 100.000 [%]
Description:	Sets the override factor for the limit value for SG2 and SG4 for the function "safely reduced speed" (SG).		
Index:	[0] = SG override factor 0 [1] = SG override factor 1 [2] = SG override factor 2 [3] = SG override factor 3		

[4] = SG override factor 4
 [5] = SG override factor 5
 [6] = SG override factor 6
 [7] = SG override factor 7
 [8] = SG override factor 8
 [9] = SG override factor 9
 [10] = SG override factor 10
 [11] = SG override factor 11
 [12] = SG override factor 12
 [13] = SG override factor 13
 [14] = SG override factor 14
 [15] = SG override factor 15

Dependency: Refer to: p9501, p9531

Note: The actual override factor for SG2 and SG4 is selected using the safety-relevant inputs (SGE).
 A change only becomes effective after a POWER ON.

p9534[0...1] SI motion SE upper limit values / SI Mtn SE up_lim

SERVO, VECTOR

Can be changed: U, T

Data type: Floating Point

P-Group: Safety Integrated

Dynamic index: -

Units group: -

Access level: 4

Function diagram: -

Unit selection: -

Min
-2147000.00 [mm]

Max
2147000.00 [mm]

Factory setting
100000.00 [mm]

Description: Sets the upper limit value for the function "safe software limit switch" (SE).

Index:
[0] = Limit value SE1
[1] = Limit value SE 2

Dependency: Refer to: p9501, p9535, p9562

Note: For the setting of the SE limit values, the following applies: p9534 > p9535
 A change only becomes effective after a POWER ON.

p9534[0...1] SI motion SE upper limit values / SI Mtn SE up_lim

SERVO (Safety rot)

Can be changed: U, T

Data type: Floating Point

P-Group: Safety Integrated

Dynamic index: -

Units group: -

Access level: 4

Function diagram: -

Unit selection: -

Min
-2147000.00 [°]

Max
2147000.00 [°]

Factory setting
100000.00 [°]

Description: Sets the upper limit value for the function "safe software limit switch" (SE).

Index:
[0] = Limit value SE1
[1] = Limit value SE 2

Dependency: Refer to: p9501, p9535, p9562

Note: For the setting of the SE limit values, the following applies: p9534 > p9535
 A change only becomes effective after a POWER ON.

p9535[0...1] SI motion SE lower limit values / SI Mtn SE low_lim

SERVO, VECTOR

Can be changed: U, T

Data type: Floating Point

P-Group: Safety Integrated

Dynamic index: -

Units group: -

Access level: 4

Function diagram: -

Unit selection: -

Min
-2147000.00 [mm]

Max
2147000.00 [mm]

Factory setting
-100000.00 [mm]

Description: Sets the lower limit value for the function "safe software limit switch" (SE).

Index:
[0] = Limit value SE1
[1] = Limit value SE 2

Dependency: Refer to: p9501, p9534, p9562

Note: For the setting of the SE limit values, the following applies: p9534 > p9535
 A change only becomes effective after a POWER ON.

p9535[0...1]	SI motion SE lower limit values / SI Mtn SE low_lim		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -2147000.00 [°]	Max 2147000.00 [°]	Factory setting -100000.00 [°]
Description:	Sets the lower limit value for the function "safe software limit switch" (SE).		
Index:	[0] = Limit value SE1 [1] = Limit value SE 2		
Dependency:	Refer to: p9501, p9534, p9562		
Note:	For the setting of the SE limit values, the following applies: p9534 > p9535 A change only becomes effective after a POWER ON.		

p9536[0...29]	SI motion SN plus cam position / SI Mtn SN+		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -2147000.00 [mm]	Max 2147000.00 [mm]	Factory setting 10.00 [mm]
Description:	Sets the plus cam position for the function "safe software cam" (SN).		
Index:	[0] = Cam position SN1 [1] = Cam position SN2 [2] = Cam position SN3 [3] = Cam position SN4 [4] = Cam position SN5 [5] = Cam position SN6 [6] = Cam position SN7 [7] = Cam position SN8 [8] = Cam position SN9 [9] = Cam position SN10 [10] = Cam position SN11 [11] = Cam position SN12 [12] = Cam position SN13 [13] = Cam position SN14 [14] = Cam position SN15 [15] = Cam position SN16 [16] = Cam position SN17 [17] = Cam position SN18 [18] = Cam position SN19 [19] = Cam position SN20 [20] = Cam position SN21 [21] = Cam position SN22 [22] = Cam position SN23 [23] = Cam position SN24 [24] = Cam position SN25 [25] = Cam position SN26 [26] = Cam position SN27 [27] = Cam position SN28 [28] = Cam position SN29 [29] = Cam position SN30		
Dependency:	Refer to: p9501, p9537		
Note:	A change only becomes effective after a POWER ON.		

p9536[0...29]	SI motion SN plus cam position / SI Mtn SN+		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -2147000.00 [°]	Max 2147000.00 [°]	Factory setting 10.00 [°]
Description:	Sets the plus cam position for the function "safe software cam" (SN).		
Index:	[0] = Cam position SN1 [1] = Cam position SN2 [2] = Cam position SN3 [3] = Cam position SN4 [4] = Cam position SN5 [5] = Cam position SN6 [6] = Cam position SN7 [7] = Cam position SN8 [8] = Cam position SN9 [9] = Cam position SN10 [10] = Cam position SN11 [11] = Cam position SN12 [12] = Cam position SN13 [13] = Cam position SN14 [14] = Cam position SN15 [15] = Cam position SN16 [16] = Cam position SN17 [17] = Cam position SN18 [18] = Cam position SN19 [19] = Cam position SN20 [20] = Cam position SN21 [21] = Cam position SN22 [22] = Cam position SN23 [23] = Cam position SN24 [24] = Cam position SN25 [25] = Cam position SN26 [26] = Cam position SN27 [27] = Cam position SN28 [28] = Cam position SN29 [29] = Cam position SN30		
Dependency:	Refer to: p9501, p9537		
Note:	A change only becomes effective after a POWER ON.		

p9537[0...29]	SI motion SN minus cam position / SI Mtn SN-		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -2147000.00 [mm]	Max 2147000.00 [mm]	Factory setting -10.00 [mm]
Description:	Sets the minus cam position for the function "safe software cam" (SN).		
Index:	[0] = Cam position SN1 [1] = Cam position SN2 [2] = Cam position SN3 [3] = Cam position SN4 [4] = Cam position SN5 [5] = Cam position SN6 [6] = Cam position SN7 [7] = Cam position SN8 [8] = Cam position SN9 [9] = Cam position SN10 [10] = Cam position SN11		

[11] = Cam position SN12
 [12] = Cam position SN13
 [13] = Cam position SN14
 [14] = Cam position SN15
 [15] = Cam position SN16
 [16] = Cam position SN17
 [17] = Cam position SN18
 [18] = Cam position SN19
 [19] = Cam position SN20
 [20] = Cam position SN21
 [21] = Cam position SN22
 [22] = Cam position SN23
 [23] = Cam position SN24
 [24] = Cam position SN25
 [25] = Cam position SN26
 [26] = Cam position SN27
 [27] = Cam position SN28
 [28] = Cam position SN29
 [29] = Cam position SN30

Dependency: Refer to: p9501, p9536

Note: A change only becomes effective after a POWER ON.

p9537[0...29] SI motion SN minus cam position / SI Mtn SN-

SERVO (Safety rot)

Can be changed: U, T

Data type: Floating Point

P-Group: Safety Integrated

Min

-2147000.00 [°]

Dynamic index: -

Units group: -

Max

2147000.00 [°]

Access level: 4

Function diagram: -

Unit selection: -

Factory setting

-10.00 [°]

Description: Sets the minus cam position for the function "safe software cam" (SN).

Index:

[0] = Cam position SN1
 [1] = Cam position SN2
 [2] = Cam position SN3
 [3] = Cam position SN4
 [4] = Cam position SN5
 [5] = Cam position SN6
 [6] = Cam position SN7
 [7] = Cam position SN8
 [8] = Cam position SN9
 [9] = Cam position SN10
 [10] = Cam position SN11
 [11] = Cam position SN12
 [12] = Cam position SN13
 [13] = Cam position SN14
 [14] = Cam position SN15
 [15] = Cam position SN16
 [16] = Cam position SN17
 [17] = Cam position SN18
 [18] = Cam position SN19
 [19] = Cam position SN20
 [20] = Cam position SN21
 [21] = Cam position SN22
 [22] = Cam position SN23
 [23] = Cam position SN24
 [24] = Cam position SN25
 [25] = Cam position SN26
 [26] = Cam position SN27
 [27] = Cam position SN28
 [28] = Cam position SN29
 [29] = Cam position SN30

Dependency: Refer to: p9501, p9536

Note: A change only becomes effective after a POWER ON.

p9540	SI motion SN tolerance / SI Mtn SN tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0010 [mm]	Max 10.0000 [mm]	Factory setting 0.1000 [mm]
Description:	Sets the tolerance for the function "safe software cam" (SN). Within this tolerance, both monitoring channels may signal different signal states of the same safe software cam.		
Note:	A change only becomes effective after a POWER ON.		
p9540	SI motion SN tolerance / SI Mtn SN tol		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0010 [°]	Max 10.0000 [°]	Factory setting 0.1000 [°]
Description:	Sets the tolerance for the function "safe software cam" (SN). Within this tolerance, both monitoring channels may signal different signal states of the same safe software cam.		
Note:	A change only becomes effective after a POWER ON.		
p9542	SI motion actual value comparison tolerance (crosswise) / SI Mtn act val tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0010 [mm]	Max 360.0000 [mm]	Factory setting 0.1000 [mm]
Description:	Sets the tolerance for the crosswise data comparison of the actual position between the two monitoring channels.		
Dependency:	Refer to: C01711		
Note:	A change only becomes effective after a POWER ON.		
p9542	SI motion actual value comparison tolerance (crosswise) / SI Mtn act val tol		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0010 [°]	Max 360.0000 [°]	Factory setting 0.1000 [°]
Description:	Sets the tolerance for the crosswise data comparison of the actual position between the two monitoring channels.		
Dependency:	Refer to: C01711		
Note:	A change only becomes effective after a POWER ON.		
p9544	SI motion actual value comparison tolerance (referencing) / SI Mtn ref tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0000 [mm]	Max 36.0000 [mm]	Factory setting 0.0100 [mm]
Description:	Sets the tolerance to check the actual values after referencing (incremental encoder) or when powering-up (absolute encoder).		
Dependency:	Refer to: C01711		
Note:	A change only becomes effective after a POWER ON.		

p9544	SI motion actual value comparison tolerance (referencing) / SI Mtn ref tol		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.0000 [°]	Max 36.0000 [°]	Factory setting 0.0100 [°]
Description:	Sets the tolerance to check the actual values after referencing (incremental encoder) or when powering-up (absolute encoder).		
Dependency:	Refer to: C01711		
Note:	A change only becomes effective after a POWER ON.		
p9546	SI motion velocity limit n_x / SI Mtn lim val n_x		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 6000.00 [mm/min]	Factory setting 20.00 [mm/min]
Description:	Sets the velocity limit n_x to detect standstill (zero speed). When this limit value is fallen below, SGA "n < n_x" is set.		
Note:	A change only becomes effective after a POWER ON. SGA: Safety-related output		
p9546	SI motion velocity limit n_x / SI Mtn lim val n_x		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 6000.00 [1/min]	Factory setting 20.00 [1/min]
Description:	Sets the velocity limit n_x to detect standstill (zero speed). When this limit value is fallen below, SGA "n < n_x" is set.		
Note:	A change only becomes effective after a POWER ON. SGA: Safety-related output		
p9548	SI motion SBR actual speed tolerance / SI Mtn SBR tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 120000.00 [mm/min]	Factory setting 300.00 [mm/min]
Description:	Sets the velocity tolerance for the "Safe Braking Ramp" (SBR).		
Dependency:	Refer to: C01706		
Note:	A change only becomes effective after a POWER ON. SBR: Safe braking ramp		

p9548	SI motion SBR actual speed tolerance / SI Mtn SBR tol		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 120000.00 [1/min]	Factory setting 300.00 [1/min]
Description:	Sets the velocity tolerance for the "Safe Braking Ramp" (SBR).		
Dependency:	Refer to: C01706		
Note:	A change only becomes effective after a POWER ON. SBR: Safe braking ramp		
p9549	SI motion slip speed tolerance / SI Mtn slip tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 6000.00 [mm/min]	Factory setting 6.00 [mm/min]
Description:	Sets the velocity tolerance that is used for a two encoder system in crosswise comparison between the drive and the control.		
Dependency:	Refer to: p9501, p9542		
Note:	If the "actual value synchronization" is not enabled (p9501.3 = 0), then the value parameterized in p9542 is used as tolerance in the crosswise data comparison. A change only becomes effective after a POWER ON.		
p9549	SI motion slip speed tolerance / SI Mtn slip tol		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 6000.00 [1/min]	Factory setting 6.00 [1/min]
Description:	Sets the velocity tolerance that is used for a two encoder system in crosswise comparison between the drive and the control.		
Dependency:	Refer to: p9501, p9542		
Note:	If the "actual value synchronization" is not enabled (p9501.3 = 0), then the value parameterized in p9542 is used as tolerance in the crosswise data comparison. A change only becomes effective after a POWER ON.		
p9550	SI motion SGE changeover tolerance time / SI Mtn SGE tol		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 500.00 [ms]
Description:	Sets the tolerance time for the changeover of the safety-related inputs (SGE).		
Note:	A change only becomes effective after a POWER ON.		

p9551	SI motion SG changeover delay time / SI Mtn SG t_del		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 60000.00 [ms]	Factory setting 100.00 [ms]
Description:	Sets the delay time for the SG changeover for the function "safely reduced speed" (SG). When transitioning from a higher to a lower safely-reduced velocity/speed stage or to the safe operating stop, within this delay time, the "old" velocity stage remains active.		
Note:	A change only becomes effective after a POWER ON.		
p9552	SI motion transition time STOP C to SBH / SI Mtn time C->SBH		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 100.00 [ms]
Description:	Sets the transition time from STOP C to "safe operating stop" (SBH).		
Note:	A change only becomes effective after a POWER ON.		
p9553	SI motion transition time STOP D to SBH / SI Mtn time D->SBH		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 60000.00 [ms]	Factory setting 100.00 [ms]
Description:	Sets the transition time from STOP D to "safe operating stop" (SBH).		
Note:	A change only becomes effective after a POWER ON.		
p9554	SI motion transition time STOP E to SBH / SI Mtn time E->SBH		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 60000.00 [ms]	Factory setting 100.00 [ms]
Description:	Sets the transition time from STOP E to "safe operating stop" (SBH).		
Note:	A change only becomes effective after a POWER ON.		
p9555	SI motion transition time STOP F to STOP B / SI Mtn time F->B		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 60000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the transition time from STOP F to STOP B.		
Dependency:	Refer to: C01711		
Note:	A change only becomes effective after a POWER ON.		

p9556	SI motion pulse cancellation delay time / SI Mtn IL t_del		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 100.00 [ms]
Description:	Sets the delay time for the safe pulse cancellation after STOP B.		
Dependency:	Refer to: p9560 Refer to: C01701		
Note:	A change only becomes effective after a POWER ON.		
p9557	SI motion pulse cancelation test time / SI Mtn IL t_test		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 10000.00 [ms]	Factory setting 100.00 [ms]
Description:	Sets the time after which the pulses must have been cancelled when initiating the test stop.		
Dependency:	Refer to: C01798		
Note:	A change only becomes effective after a POWER ON.		
p9558	SI motion acceptance test mode, time limit / SI Mtn t_accept		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 5000.00 [ms]	Max 100000.00 [ms]	Factory setting 40000.00 [ms]
Description:	Sets the maximum time for the acceptance test mode. If the acceptance test mode takes longer than the selected time limit, then the mode is automatically terminated.		
Dependency:	Refer to: C01799		
Note:	A change only becomes effective after a POWER ON.		
p9560	SI motion pulse cancellation shutdown speed / SI Mtn IL n_shutd		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [mm/min]	Max 6000.00 [mm/min]	Factory setting 0.00 [mm/min]
Description:	Sets the velocity, under which the axis is considered to be "stationary" and for a STOP B, the pulses are cancelled (by changing to STOP A).		
Dependency:	Refer to: p9556		
Note:	A change only becomes effective after a POWER ON.		

p9560	SI motion pulse cancellation shutdown speed / SI Mtn IL n_shutd		
SERVO (Safety rot)	Can be changed: U, T		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [1/min]	Max 6000.00 [1/min]	Factory setting 0.00 [1/min]
Description:	Sets the velocity, under which the axis is considered to be "stationary" and for a STOP B, the pulses are cancelled (by changing to STOP A).		
Dependency:	Refer to: p9556		
Note:	A change only becomes effective after a POWER ON.		
p9561	SI motion SG stop response / SI Mtn SG stop res		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0	Max 14	Factory setting 5
Description:	Sets the stop response for the function "safely reduced speed" (SG). This setting applies for all SG limit values. An input value of less than 5 signifies personnel protection, from 10 and upwards, machine protection.		
Values:	<ul style="list-style-type: none"> 0: STOP A 1: STOP B 2: STOP C 3: STOP D 4: STOP E 5: Sets the stop response via p9563 (SG-specific) 10: STOP A with delayed pulse cancellation when the bus fails 11: STOP B with delayed pulse cancellation when the bus fails 12: STOP C with delayed pulse cancellation when the bus fails 13: STOP D with delayed pulse cancellation when the bus fails 14: STOP E with delayed pulse cancellation when the bus fails 		
Dependency:	Refer to: p9531, p9563, p9580		
Note:	A change only becomes effective after a POWER ON.		
p9562	SI motion SE stop response / SI Mtn SE stop res		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 2	Max 4	Factory setting 2
Description:	Sets the stop response for the function "safe software limit switch" (SE).		
Values:	<ul style="list-style-type: none"> 2: STOP C 3: STOP D 4: STOP E 		
Dependency:	Refer to: p9534, p9535		
Note:	A change only becomes effective after a POWER ON.		

p9563[0...3]	SI motion SG-specific stop response / SI Mtn SGspec stop		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0	Max 14	Factory setting 2
Description:	Sets the stop response for the function "safely reduced speed" (SG, SG-specific). This setting applies to the individual SG limit values.		
Values:	0: STOP A 1: STOP B 2: STOP C 3: STOP D 4: STOP E 10: STOP A with delayed pulse cancellation when the bus fails 11: STOP B with delayed pulse cancellation when the bus fails 12: STOP C with delayed pulse cancellation when the bus fails 13: STOP D with delayed pulse cancellation when the bus fails 14: STOP E with delayed pulse cancellation when the bus fails		
Index:	[0] = Limit value SG1 [1] = Limit value SG2 [2] = Limit value SG3 [3] = Limit value SG4		
Dependency:	Refer to: p9531, p9561, p9580		
Note:	A change only becomes effective after a POWER ON.		

p9570	SI motion acceptance test mode / SI Mtn Acc_mode		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max 00AC hex	Factory setting 0000 hex
Description:	Setting to select and de-select the acceptance test mode.		
Values:	0: [00 hex] De-select the acceptance test mode 172: [AC hex] Select the acceptance test mode		
Dependency:	Refer to: p9558, r9571 Refer to: C01799		

r9571	SI motion acceptance test status / SI Mtn acc_status		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max 00AC hex	Factory setting 00AC hex
Description:	Displays the status of the acceptance test mode.		
Values:	0: [00 hex] Acc_mode inactive 12: [0C hex] Acc_mode not possible due to POWER ON fault 13: [0D hex] Acc_mode not possible due to incorrect ID in p9570 15: [0F hex] Acc_mode not possible due to expired Acc_timer 172: [AC hex] Acc_mode active		
Dependency:	Refer to: p9558, p9570 Refer to: C01799		

p9580	SI motion pulse cancellation delay time after bus failure / SI Mtn t to IL			
SERVO, VECTOR	Can be changed: U, T			Access level: 4
	Data type: Floating Point	Dynamic index: -		Function diagram: -
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min 0.00 [ms]	Max 800.00 [ms]		Factory setting 0.00 [ms]
Description:	Sets the delay time after which the pulses are safely cancelled after a bus failure.			
Dependency:	Refer to: p9561, p9563			
Note:	A change only becomes effective after a POWER ON.			
r9590[0...2]	SI motion version, safe motion monitoring functions / SI Mtn version			
SERVO, VECTOR	Can be changed: -			Access level: 4
	Data type: Unsigned16	Dynamic index: -		Function diagram: -
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min -	Max -		Factory setting -
Description:	Displays the Safety Integrated version for the safe monitoring functions.			
Index:	[0] = Safety Version (major release) [1] = Safety Version (minor release) [2] = Safety Version (baselevel or patch)			
Dependency:	Refer to: r9770, r9870, r9890			
Note:	Example: r9590[0] = 2, r9590[1] = 3, r9590[2] = 1 --> SI motion version V02.03.01			
p9601	SI enable, functions integrated in the drive (Control Unit) / SI enable fct CU			
SERVO, VECTOR	Can be changed: C2			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: -
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min -	Max -		Factory setting 0000 bin
Description:	Sets the enable signals for safety functions on the Control Unit that are integrated in the drive.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Enable SH via terminal (Control Unit)	Enable	Inhibit
	02	Motion monitoring functions integr. in the drive (Control Unit)	Enable	Inhibit
	03	Enable PROFIsafe (Control Unit)	Enable	Inhibit
Dependency:	Refer to: p9801			
Note:	CU: Control Unit SH: Safe standstill SI: Safety Integrated SMM: Safe Motion Monitoring			
p9602	SI enable Safe Brake Control (Control Unit) / SI enable SBC CU			
SERVO, VECTOR	Can be changed: C2			Access level: 3
	Data type: Integer16	Dynamic index: -		Function diagram: 2814
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min 0	Max 1		Factory setting 0
Description:	Sets the enable signal for the function "Safe Brake Control" (SBC) on the Control Unit.			
Values:	0: Inhibit SBC 1: Enable SBC			

Dependency: Refer to: p9802

Note: The "Safe Brake Control" function is not activated until at least one safety monitoring function has been enabled (i.e. p9501 not equal to 0 and/or p9601 not equal to 0).
 The parameterization "no motor holding brake available" and "Safe Brake Control" enabled (p1215 = 0, p9602 = p9802 = 1) is not practical if there is no motor holding brake.
 The parameterization "motor holding brake the same as sequence control, connection via BICO" and "Safe Brake Control" enabled (p1215 = 3, p9602 = 1, p9802 = 1) is not practical.
 It is not permissible to parameterize "motor holding brake without feedback signals" and also enable "safe brake control" (p1278 = 1, p9602 = 1, p9802 = 1).
 CU: Control Unit
 SBC: Safe Brake Control
 SI: Safety Integrated

p9610	SI PROFIsafe address (Control Unit) / SI PROFIsafe CU		
SERVO, VECTOR	Can be changed: C2		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFE hex	Factory setting 0000 hex
Description:	Sets the PROFIsafe address of the Control Unit.		
Dependency:	Refer to: p9810		
p9620	BI: SI signal source for SH/SBC/SS1 (Control Unit) / SI sel SH/SS1 CU		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2810
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the functions "Safe standstill" (SH), "Safe Brake Control" (SBC) and "Safe Stop 1" (SS1) on the Control Unit.		
Dependency:	Refer to: p9601		
Note:	The following signal sources are permitted: - fixed zero (standard setting). - digital inputs DI 0 to DI 7 on the Control Unit 320 (CU320). - digital inputs DI 0 to DI 3 on the Controller Extensions (CX32, NX10, NX15). - digital inputs DI 0 to DI 3 on the Control Unit 310 (CU310). It is not permitted to establish an interconnection to a digital input in the simulation mode.		
p9650	SI SGE changeover tolerance time (Control Unit) / SI SGE_chg tol CU		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 2810
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 2000.00 [ms]	Factory setting 500.00 [ms]
Description:	Sets the tolerance time to change over the safety-related inputs (SGE) on the Control Unit. An SGE changeover is not simultaneously effective due to the different runtimes in the two monitoring channels. After an SGE changeover, dynamic data is not subject to a crosswise data comparison during this tolerance time.		
Dependency:	Refer to: p9850		
Note:	For a crosswise data comparison between p9650 and p9850, a difference of one Safety monitoring clock cycle is tolerated. The parameterized time is internally rounded-off to an integer multiple of the monitoring clock cycle. SGE: Safety-related input (e.g. SH terminals)		

p9652	SI Safe Stop delay time (Control Unit) / SI Stop 1 t_del CU		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [s]	Max 300.00 [s]	Factory setting 0.00 [s]
Description:	Sets the delay time of the pulse cancellation for the function "Safe Stop 1" (SS1) on the Control Unit to brake along the OFF3 down ramp (p1135).		
Dependency:	Refer to: p1135, p9852		
Note:	For a crosswise data comparison between p9652 and p9852, a difference of one Safety monitoring clock cycle is tolerated. The parameterized time is internally rounded-off to an integer multiple of the monitoring clock cycle. SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)		
p9658	SI transition time STOP F to STOP A (Control Unit) / SI STOP F->A CU		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 30000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the transition period from STOP F to STOP A on the Control Unit.		
Dependency:	Refer to: r9795, p9858 Refer to: F01611		
Note:	For a crosswise data comparison between p9658 and p9858, a difference of one Safety monitoring clock cycle is tolerated. The parameterized time is internally rounded-off to an integer multiple of the monitoring clock cycle. STOP F: Defect in a monitoring channel (error in the crosswise data comparison) STOP A: Pulse cancellation via the safety shutdown path		
p9659	SI forced checking procedure timer / SI FrcdCkProcTimer		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 2810
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [h]	Max 9000.00 [h]	Factory setting 8.00 [h]
Description:	Sets the time to carry-out the dynamic update and testing the safety shutdown paths (forced checking procedure). Within the parameterized time, safe standstill must have been de-selected at least once. The monitoring time is reset each time that SH is de-selected.		
Dependency:	Refer to: A01699		
p9700	SI Motion, start copy function / SI Mtn copy		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 hex	Max 0057 hex	Factory setting 0000 hex
Description:	Starts the copy function of the drive-based motion monitoring function parameters from the Control Unit to the Motor Module with the value 57 (hex) After the write access operations have been completed, the parameter is again reset to 0.		
Values:	0: [00 hex] Copy function ended 87: [00 hex] Start copy function		

p9701	SI Motion data acknowledge / SI Mtn dat ackn		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 hex	Max 00AC hex	Factory setting 0000 hex
Description:	Accepts the reference checksums of all drive-based monitoring parameters from the associated actual checksums when writing the value AC (hex). After the write access operations have been completed, the parameter is again reset to 0.		
Values:	0: [00 hex] Data unchanged 172: [AC hex] Data change, acknowledge		
Dependency:	Refer to: r9398, p9399, r9728, p9729, r9798, p9799, r9898, p9899		

r9710[0...1]	SI motion diagnostics result list 1 / SI Mtn res_list 1				
SERVO, VECTOR	Can be changed: -		Access level: 4		
	Data type: Unsigned32	Dynamic index: -	Function diagram: -		
	P-Group: -	Units group: -	Unit selection: -		
	Min -	Max -	Factory setting 0000 bin		
Description:	Displays result list 1, that for the crosswise data comparison with the control, led to the fault.				
Index:	[0] = Result list, control [1] = Result list, drive				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Actual value > upper limit, SBH	Yes	No	-
	01	Actual value > lower limit, SBH	Yes	No	-
	02	Actual value > upper limit, SE1	Yes	No	-
	03	Actual value > lower limit, SE1	Yes	No	-
	04	Actual value > upper limit, SE2	Yes	No	-
	05	Actual value > lower limit, SE2	Yes	No	-
	06	Actual value > upper limit, SG1	Yes	No	-
	07	Actual value > lower limit, SG1	Yes	No	-
	08	Actual value > upper limit, SG2	Yes	No	-
	09	Actual value > lower limit, SG2	Yes	No	-
	10	Actual value > upper limit, SG3	Yes	No	-
	11	Actual value > lower limit, SG3	Yes	No	-
	12	Actual value > upper limit, SG4	Yes	No	-
	13	Actual value > lower limit, SG4	Yes	No	-
	16	Actual value > upper limit, SBR	Yes	No	-
	17	Actual value > lower limit, SBR	Yes	No	-
Dependency:	Refer to: C01711				

r9711[0...1] SI motion diagnostics result list 2 / SI Mtn res_list 2

SERVO, VECTOR	Can be changed: -	Access level: 4
	Data type: Unsigned32	Dynamic index: -
	P-Group: -	Function diagram: -
	Min	Units group: -
	-	Unit selection: -
	Max	Factory setting
	-	0000 bin

Description: Displays result list 2, that for the crosswise data comparison with the control, led to the fault.

Index:
[0] = Result list, control
[1] = Result list, drive

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Actual value > upper limit, SN1+	Yes	No	-
	01	Actual value > lower limit, SN1+	Yes	No	-
	02	Actual value > upper limit, SN1-	Yes	No	-
	03	Actual value > lower limit, SN1-	Yes	No	-
	04	Actual value > upper limit, SN2+	Yes	No	-
	05	Actual value > lower limit, SN2+	Yes	No	-
	06	Actual value > upper limit, SN2-	Yes	No	-
	07	Actual value > lower limit, SN2-	Yes	No	-
	08	Actual value > upper limit, SN3+	Yes	No	-
	09	Actual value > lower limit, SN3+	Yes	No	-
	10	Actual value > upper limit, SN3-	Yes	No	-
	11	Actual value > lower limit, SN3-	Yes	No	-
	12	Actual value > upper limit, SN4+	Yes	No	-
	13	Actual value > lower limit, SN4+	Yes	No	-
	14	Actual value > upper limit, SN4-	Yes	No	-
	15	Actual value > lower limit, SN4-	Yes	No	-
	16	Actual value > upper limit, n_x+	Yes	No	-
	17	Actual value > lower limit, n_x+	Yes	No	-
	18	Actual value > upper limit, n_x-	Yes	No	-
	19	Actual value > lower limit, n_x-	Yes	No	-
	20	Actual value > upper limit, modulo	Yes	No	-
	21	Actual value > lower limit, modulo	Yes	No	-

Dependency: Refer to: C01711

r9718 CO/BO: SI motion control signals 1 / SI Mtn ctrl_sig 1

SERVO, VECTOR	Can be changed: -	Access level: 4
	Data type: Unsigned32	Dynamic index: -
	P-Group: Safety Integrated	Function diagram: -
	Min	Units group: -
	-	Unit selection: -
	Max	Factory setting
	-	0000 bin

Description: Control signal 1 for safety-relevant motion monitoring functions.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	23	Set offset for TfS to the actual torque	Set	Reset	-

Note: TfS: Traverse to fixed stop

r9719 CO/BO: SI motion control signals 2 / SI Mtn ctrl_sig 2

SERVO, VECTOR

Can be changed: -**Data type:** Unsigned32**P-Group:** Safety Integrated**Min**

-

Dynamic index: -**Units group:** -**Max**

-

Access level: 4**Function diagram:** -**Unit selection:** -**Factory setting**

0000 bin

Description:

Control signal 2 for safety-relevant motion monitoring functions.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Control signal de-select SBH/SG	Yes	No	-
01	Control signal de-select SBH	Yes	No	-
03	Control signal select SG bit 0	set	not set	-
04	Control signal select SG bit 1	set	not set	-
08	Control signal gearbox selection, bit 0	set	not set	-
09	Control signal gearbox selection, bit 1	set	not set	-
10	Control signal gearbox selection, bit 2	set	not set	-
12	Control signal, select SE	2	1	-
13	Control signal, close brake from control	Yes	No	-
15	Control signal, select test stop	Yes	No	-
16	Control signal SGE valid	Yes	No	-
18	Control signal de-select ext. Stop A	Yes	No	-
19	Control signal de-select ext. Stop C	Yes	No	-
20	Control signal de-select ext. Stop D	Yes	No	-
21	Control signal de-select ext. Stop E	Yes	No	-
28	Control signal select SG override, bit 0	set	not set	-
29	Control signal select SG override, bit 1	set	not set	-
30	Control signal SG override, bit 2	set	not set	-
31	Control signal select SG override, bit 3	set	not set	-

r9721 SI motion status signals / SI Mtn stat_sig

SERVO, VECTOR

Can be changed: -**Data type:** Unsigned32**P-Group:** Safety Integrated**Min**

-

Dynamic index: -**Units group:** -**Max**

-

Access level: 4**Function diagram:** -**Unit selection:** -**Factory setting**

0000 bin

Description:

Status signal for safety-relevant motion monitoring functions.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Status signal SBH or SG active	Yes	No	-
01	Status signal SBH active	Yes	No	-
02	Status signal, pulses	cleared	enabled	-
03	Status signal active SG stage, bit 0	set	not set	-
04	Status signal active SG stage, bit 1	set	not set	-
05	Status signal velocity below limit value nx	Yes	No	-
06	Status signals valid	Yes	No	-
07	Status signal safely referenced	Yes	No	-
12	Status signal Stop A or B active	Yes	No	-
13	Status signal Stop C active	Yes	No	-
14	Status signal Stop D active	Yes	No	-
15	Status signal Stop E active	Yes	No	-

r9725	SI motion, diagnostics STOP F / SI Mtn Diag STOP F		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the message value that resulted in the STOP F on the drive. Value = 0 means: The controlled signaled a STOP F. Value = 1 ... 999 means: Number of the incorrect crosswise compared data between the drive and control. Value >= 1000 means: Additional diagnostic values of the drive.		
Dependency:	Refer to: C01711		
Note:	The significance of the individual values is described in message 27001 of the higher-level control.		
p9726	SI motion, user agreement selection/de-selection / SI Mtn UserAgr sel		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0000 hex	00AC hex	0000 hex
Description:	Setting to select and de-select the user agreement.		
Values:	0: [00 hex] De-select user agreement 172: [AC hex] Select user agreement		
Dependency:	Refer to: r9727		
r9727	SI motion user agreement, inside the drive / SI Mtn UserAgr int		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the internal state of the user agreement. Value = 0: User agreement is not set. Value = AC hex: User agreement is set.		
Dependency:	Refer to: p9726		
r9728[0...1]	SI motion actual checksum, SI parameters / SI Mtn act CRC		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the checksum over the checked Safety Integrated parameters of the motion monitoring functions (actual checksum).		
Index:	[0] = Check sum over SI parameters for motion monitoring [1] = Check sum over SI parameters for actual values		
Dependency:	Refer to: p9729 Refer to: F01680		

p9729[0...1]	SI motion reference checksum, SI parameters / SI Mtn ref CRC		
SERVO, VECTOR	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the checksum using the checksum-tested Safety Integrated parameters for motion monitoring functions (reference checksum).		
Index:	[0] = Check sum over SI parameters for motion monitoring [1] = Check sum over SI parameters for actual values		
Dependency:	Refer to: r9728, Refer to: F01680		
r9744	SI message buffer changes, counter / SI msg_buffer chng		
SERVO	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the changes of the safety message buffer. This counter is incremented every time that the safety message buffer changes.		
Recommendation:	This is used to check whether the safety message buffer has been read-out consistently.		
Dependency:	Refer to: r9747, r9748, r9749, p9752, r9753, r9754, r9755, r9756, p9759		
r9747[0...63]	SI message code / SI msg_code		
SERVO	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the numbers of safety messages that have occurred.		
Dependency:	Refer to: r9744, r9748, r9749, p9752, r9753, r9754, r9755, r9756, p9759		
Note:	The messages type "safety message" (Cxxxxx) are entered in the message fault buffer.		
r9748[0...63]	SI message time received in milliseconds / SI t_msg rcv ms		
SERVO	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the relative system runtime in milliseconds when the safety message occurred.		
Dependency:	Refer to: r9744, r9747, r9749, p9752, r9753, r9754, r9755, r9756, p9759		
r9749[0...63]	SI message value / SI msg_value		
SERVO	Can be changed: -		Access level: 4
	Data type: Integer32	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the additional information about the safety message that occurred (as integer number).		
Dependency:	Refer to: r9744, r9747, r9748, p9752, r9753, r9754, r9755, r9756, p9759		

p9752	SI message cases, counter / SI msg_cases count		
SERVO	Can be changed: U, T		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 65535	Factory setting 0
Description:	Number of safety messages that have occurred since the last reset.		
Dependency:	The safety message buffer is cleared by resetting the parameter to 0. Refer to: r9744, r9747, r9748, r9749, r9753, r9754, r9755, r9756, p9759		
Note:	The parameter is reset to 0 at POWER ON.		

r9753[0...63]	SI message value for float values / SI msg_val float		
SERVO	Can be changed: -		Access level: 4
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays additional information about the safety message that has occurred for float values.		
Dependency:	Refer to: r9744, r9747, r9748, r9749, p9752, r9754, r9755, r9756, p9759		

r9754[0...63]	SI message time received in days / SI t_msg rcv days		
SERVO	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the relative system runtime in days when the safety message occurred.		
Dependency:	Refer to: r9744, r9747, r9748, r9749, p9752, r9753, r9755, r9756, p9759		

r9755[0...63]	SI message time removed in milliseconds / SI t_msg rem ms		
SERVO	Can be changed: -		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the relative system runtime in milliseconds when the safety message was removed.		
Dependency:	Refer to: r9744, r9747, r9748, r9749, p9752, r9753, r9754, r9756, p9759		

r9756[0...63]	SI message time removed in days / SI t_msg rem days		
SERVO	Can be changed: -		Access level: 4
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the relative system runtime in days when the safety message was removed.		
Dependency:	Refer to: r9744, r9747, r9748, r9749, p9752, r9753, r9754, r9755, p9759		

p9759	SI, acknowledge messages, drive object / SI msg ackn DO		
SERVO	Can be changed: U, T		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Messages	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	Acknowledges all safety messages present for a drive object.		
Dependency:	Refer to: r9744, r9747, r9748, r9749, p9752, r9753, r9754, r9755, r9756		
Note:	Parameter should be set from 0 to 1 to acknowledge. After acknowledgement, the parameter is automatically reset to 0.		
p9761	SI password input / SI password input		
SERVO, VECTOR	Can be changed: C1, T		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Enters the Safety Integrated password.		
Dependency:	Refer to: F01659		
Note:	It is not permissible to change Safety Integrated parameter settings until the Safety Integrated password has been entered.		
p9762	SI password new / SI password new		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Enters a new Safety Integrated password.		
Dependency:	A change made to the Safety Integrated password must be acknowledged in the following parameter: Refer to: p9763		
p9763	SI password acknowledgment / SI ackn password		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Acknowledges the new Safety Integrated password.		
Dependency:	Refer to: p9762		
Note:	The new password entered into p9762 must be re-entered in order to acknowledge. p9762 = p9763 = 0 is automatically set after the new Safety Integrated password has been successfully acknowledged.		

r9770[0...2]		SI vers. safety fcts that run indep. in the drive (Control Unit) / SI version Drv CU		
SERVO, VECTOR	Can be changed: -			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: 2802
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the Safety Integrated version for the safety functions that run independently in the drive on the Control Unit.			
Index:	[0] = Safety Version (major release) [1] = Safety Version (minor release) [2] = Safety Version (baselevel or patch)			
Dependency:	Refer to: r9870, r9890			
Note:	Example: r9770[0] = 2, r9770[1] = 3, r9770[2] = 1 --> Safety-Version V02.03.01			

r9771		SI common functions (Control Unit) / SI common fct CU			
SERVO, VECTOR	Can be changed: -			Access level: 3	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2804	
	P-Group: Safety Integrated	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the safety integrated monitoring functions supported on the Control Unit and Motor Module. The Control Unit determines this display.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	SH supported via terminal	Yes	No	2804
	01	SBC supported	Yes	No	2804
	02	SI Motion supported	Yes	No	2804
	03	SS1 supported	Yes	No	2804
	04	PROFIsafe supported	Yes	No	-
	05	Drive-based motion monitoring functions supported	Yes	No	-
Dependency:	Refer to: r9871				
Note:	CU: Control Unit SBC: Safe Brake Control SH: Safe standstill SI: Safety Integrated SS1: Safe Stop 1				

r9772		CO/BO: SI status (Control Unit) / SI stat CU			
SERVO, VECTOR	Can be changed: -			Access level: 2	
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2804	
	P-Group: Safety Integrated	Units group: -		Unit selection: -	
	Min	Max		Factory setting	
	-	-		0000 bin	
Description:	Displays the Safety Integrated status on the Control Unit.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	SH selected on Control Unit	Yes	No	2810
	01	SH active on the Control Unit	Yes	No	2810
	02	SS1 active on Control Unit	Yes	No	-
	04	SBC requested	Yes	No	2814
	09	STOP A cannot be acknowledged, active	Yes	No	2802
	10	STOP A active	Yes	No	2802
	15	STOP F active	Yes	No	2802
Dependency:	Refer to: r9872				

r9773		CO/BO: SI status (Control Unit + Motor Module) / SI stat CU+MM		
SERVO, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2804
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the Safety Integrated status on the drive (Control Unit + Motor Module).			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	SH in the drive selected	Yes	No
	01	SH in the drive active	Yes	No
	02	SS1 in drive active	Yes	No
	04	SBC requested	Yes	No
	31	Shutdown paths must be tested	Yes	No
				FP
				2804
				2804
				2804
				2804
				2810
Note:	This status is formed from the AND operation of the relevant status of the two monitoring channels.			
r9774		CO/BO: SI status (safe standstill group) / SI stat group SH		
SERVO, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2804
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the status for Safety Integrated of the group to which this drive belongs. These signals are an AND logic operation of the individual status signals of the drives included in this group.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	SH selected in group	Yes	No
	01	SH active in group	Yes	No
	02	SS1 in group active	Yes	No
	04	SBC in group requested	Yes	No
	31	Shutdown paths of the group must be tested	Yes	No
				FP
				2804
				2804
				-
				2804
				2804
Dependency:	Refer to: p9620, r9773			
Note:	A group is formed by appropriately grouping the terminals for "safe standstill". The status of a group of n drives is, for drives 1 to n - 1 displayed with a delay of one monitoring clock cycle; this is a system-related effect.			
r9780		SI monitoring clock cycle (Control Unit) / SI monitor_click CU		
SERVO, VECTOR	Can be changed: -			Access level: 3
	Data type: Floating Point	Dynamic index: -		Function diagram: 2802
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	- [ms]	- [ms]		- [ms]
Description:	Displays the clock cycle time for the safety functions on the Control Unit.			
Dependency:	Refer to: r9880			

r9794[0...19]	SI crosswise comparison list (Control Unit) / SI KDV_list CU		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of the data that are being presently compared crosswise on the Control Unit. Example: r9794[0] = 1 (monitoring clock cycle) r9794[1] = 2 (enable safety-related functions) r9794[2] = 3 (SGE changeover, tolerance time) r9794[3] = 4 (transition time, STOP F to STOP A) ... The list of crosswise compared data is obtained dependent on the particular application.		
Dependency:	Refer to: r9894		
Note:	The complete list of numbers for crosswise data comparison is listed in Fault F01611.		
r9795	SI diagnostics STOP F (Control Unit) / SI diag STOP F CU		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of the cross-checked data which has caused STOP F on the Control Unit.		
Dependency:	Refer to: r9895 Refer to: F01611		
Note:	The complete list of numbers for crosswise data comparison is listed in Fault F01611.		
r9798	SI actual checksum SI parameters (Control Unit) / SI act_checksum CU		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the checksum over the checked Safety Integrated parameters on the Control Unit (actual checksum).		
Dependency:	Refer to: p9799, r9898		
p9799	SI reference checksum SI parameters (Control Unit) / SI set_checksum CU		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex
Description:	Sets the checksum for the checked Safety Integrated parameters on the Control Unit (reference checksum).		
Dependency:	Refer to: r9798, p9899		

p9801		SI enable, functions integrated in the drive (Motor Module) / SI enable fct MM			
SERVO, VECTOR	Can be changed: C2		Dynamic index: -	Access level: 3	
	Data type: Unsigned16		Units group: -	Function diagram: -	
	P-Group: Safety Integrated			Unit selection: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Sets the enable signals for safety functions on the Motor Module that are integrated in the drive.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable SH via terminal (Motor Module)	Enable	Inhibit	2810
	02	Motion monitoring functions integr. in the drive (Motor Module)	Enable	Inhibit	-
	03	Enable PROFIsafe (Motor Module)	Enable	Inhibit	-
Dependency:	Refer to: p9601				
Note:	MM: Motor Module SH: Safe standstill SI: Safety Integrated				
p9802		SI enable Safe Brake Control (Motor Module) / SI enable SBC MM			
SERVO, VECTOR	Can be changed: C2		Dynamic index: -	Access level: 3	
	Data type: Integer32		Units group: -	Function diagram: 2814	
	P-Group: Safety Integrated			Unit selection: -	
	Min		Max	Factory setting	
	0		1	0	
Description:	Sets the enable signal for the "Safe Brake Control" function (SBC) on the Motor Module. 0: Inhibit SBC 1: Enable SBC				
Dependency:	Refer to: p9602				
Note:	The "Safe Brake Control" function is not activated until at least one safety monitoring function has been enabled (i.e. p9501 not equal to 0 and/or p9801 not equal to 0). The parameterization "no motor holding brake available" and "Safe Brake Control" enabled (p1215 = 0, p9602 = p9802 = 1) is not practical if there is no motor holding brake. The parameterization "motor holding brake the same as sequence control, connection via BICO" and "Safe Brake Control" enabled (p1215 = 3, p9602 = 1, p9802 = 1) is not practical. It is not permissible to parameterize "motor holding brake without feedback signals" and also enable "safe brake control" (p1278 = 1, p9602 = 1, p9802 = 1). MM: Motor Module SBC: Safe Brake Control SI: Safety Integrated				
p9810		SI PROFIsafe address (Motor Module) / SI PROFIsafe MM			
SERVO, VECTOR	Can be changed: C2		Dynamic index: -	Access level: 3	
	Data type: Unsigned16		Units group: -	Function diagram: -	
	P-Group: Safety Integrated			Unit selection: -	
	Min		Max	Factory setting	
	0000 hex		FFFE hex	0000 hex	
Description:	Sets the PROFIsafe address of the Motor Module.				

p9850	SI SGE changeover tolerance time (Motor Module) / SI SGE_chg tol MM		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 2810
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 2000000.00 [µs]	Factory setting 500000.00 [µs]
Description:	Sets the tolerance time to change over the safety-related inputs (SGE) on the Motor Module. An SGE changeover is not simultaneously effective due to the different runtimes in the two monitoring channels. After an SGE changeover, dynamic data is not subject to a crosswise data comparison during this tolerance time.		
Dependency:	Refer to: p9650		
Note:	For a crosswise data comparison between p9650 and p9850, a difference of one Safety monitoring clock cycle is tolerated. The parameterized time is internally rounded-off to an integer multiple of the monitoring clock cycle. SGE: Safety-related input (e.g. SH terminals)		
p9852	SI Safe Stop 1 delay time (Motor Module) / SI Stop 1 t_del MM		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [ms]	Max 300000.00 [ms]	Factory setting 0.00 [ms]
Description:	Sets the delay time of the pulse cancellation for the function "Safe Stop 1" (SS1) on the Motor Module to brake along the OFF3 down ramp (p1135).		
Dependency:	Refer to: p1135, p9652		
Note:	For a crosswise data comparison between p9652 and p9852, a difference of one Safety monitoring clock cycle is tolerated. The parameterized time is internally rounded-off to an integer multiple of the monitoring clock cycle. SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)		
p9858	SI transition time STOP F to STOP A (Control Unit) / SI STOP F->A MM		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0.00 [µs]	Max 30000000.00 [µs]	Factory setting 0.00 [µs]
Description:	Sets the transition period from STOP F to STOP A on the Motor Module.		
Dependency:	Refer to: p9658, r9895 Refer to: F30611		
Note:	For a crosswise data comparison between p9658 and p9858, a difference of one Safety monitoring clock cycle is tolerated. The parameterized time is internally rounded-off to an integer multiple of the monitoring clock cycle. STOP F: Defect in a monitoring channel (error in the crosswise data comparison) STOP A: Pulse cancellation via the safety shutdown path		

r9870[0...2]		SI version (Motor Module) / SI version MM		
SERVO, VECTOR	Can be changed: -			Access level: 3
	Data type: Unsigned16	Dynamic index: -		Function diagram: 2802
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		-
Description:	Displays the Safety Integrated version on the Motor Module.			
Index:	[0] = Safety Version (major release) [1] = Safety Version (minor release) [2] = Safety Version (baselevel or patch)			
Dependency:	Refer to: r9770, r9890			
Note:	Example: r9870[0] = 2, r9870[1] = 3, r9870[2] = 1 --> Safety-Version V02.03.01			
r9871		SI common functions (Motor Module / SI general fct MM		
SERVO, VECTOR	Can be changed: -			Access level: 3
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2804
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the safety integrated monitoring functions supported on the Control Unit and Motor Module. The Motor Module determines this display.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	SH supported via terminal	Yes	No
	01	SBC supported	Yes	No
	02	SI Motion supported	Yes	No
	03	SS1 supported	Yes	No
	04	PROFIsafe supported	Yes	No
	05	Drive-based motion monitoring functions supported	Yes	No
				FP
				2804
				2804
				2804
				2804
				-
				-
Dependency:	Refer to: r9771			
Note:	MM: Motor Module SBC: Safe Brake Control SH: Safe standstill SI: Safety Integrated SS1: Safe Stop 1			
r9872		CO/BO: SI status list (Motor Module) / SI status MM		
SERVO, VECTOR	Can be changed: -			Access level: 2
	Data type: Unsigned32	Dynamic index: -		Function diagram: 2804
	P-Group: Safety Integrated	Units group: -		Unit selection: -
	Min	Max		Factory setting
	-	-		0000 bin
Description:	Displays the Safety Integrated status on the Motor Module.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	SH on selected on Motor Module	Yes	No
	01	SH on Motor Module active	Yes	No
	02	SS1 on Motor Module active	Yes	No
	04	SBC requested	Yes	No
	09	STOP A cannot be acknowledged, active	Yes	No
	10	STOP A active	Yes	No
	15	STOP F active	Yes	No
				FP
				2810
				2810
				2804
				2814
				2802
				2802
				2802
Dependency:	Refer to: r9772			

r9880	SI monitoring clock cycle (Motor Module) / SI_monitor_clk MM		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Floating Point	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min - [ms]	Max - [ms]	Factory setting - [ms]
Description:	Displays the cycle time for the safety functions on the Motor Module.		
Dependency:	Refer to: r9780		
r9881[0...11]	SI Motion Sensor Module Node Identifier 2nd Channel / SI_Mtn_SM node Id		
SERVO, VECTOR	Can be changed: -		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the Node Identifier of the Sensor Module that the 2nd channel uses for the motion monitoring functions.		
r9890[0...2]	SI version (Sensor Module) / SI version SM		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the Safety Integrated version on the Sensor Module.		
Index:	[0] = Safety Version (major release) [1] = Safety Version (minor release) [2] = Safety Version (baselevel or patch)		
Dependency:	Refer to: r9770, r9870		
Note:	Example: r9890[0] = 2, r9890[1] = 3, r9890[2] = 1 --> Safety-Version V02.03.01		
r9894[0...19]	SI crosswise comparison list (Motor Module) / SI_KDV_list MM		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the number of the data that are being presently compared crosswise on the Motor Module. Example: r9894[0] = 1 (monitoring clock cycle) r9894[1] = 2 (enable safety-related functions) r9894[2] = 3 (SGE changeover, tolerance time) r9894[3] = 4 (transition time, STOP F to STOP A) ... The list of crosswise compared data is obtained dependent on the particular application.		
Dependency:	Refer to: r9794		
Note:	The complete list of numbers for crosswise data comparison is listed in Fault F30611.		

r9895	SI diagnostics STOP F (Motor Module) / SI diag STOP F MM		
SERVO, VECTOR	Can be changed: -		Access level: 2
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2802
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the number of the cross-checked data which has caused STOP F on the Motor Module.		
Dependency:	Refer to: r9795 Refer to: F30611		
Note:	The complete list of numbers for crosswise data comparison is listed in Fault F30611.		
r9898	SI actual checksum SI parameters (Motor Module) / SI act_checksum MM		
SERVO, VECTOR	Can be changed: -		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min -	Max -	Factory setting -
Description:	Displays the checksum for the checked Safety Integrated parameters on the Motor Module (actual checksum).		
Dependency:	Refer to: r9798, p9899		
p9899	SI reference checksum SI parameters (Motor Module) / SI set_checksum MM		
SERVO, VECTOR	Can be changed: C2		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: 2800
	P-Group: Safety Integrated	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Sets the checksum for the checked Safety Integrated parameters on the Motor Module (reference checksum).		
Dependency:	Refer to: p9799, r9898		

p9904 Topology comparison, acknowledge differences / Topo_compare ackn			
CU_S	Can be changed: C1(1)		Access level: 3
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	<p>If, when comparing the actual topology and target topology, only error has occurred, that can be acknowledged, then using this parameter, a new comparison can be started - acknowledging the error in the target topology.</p> <p>Differences that can be acknowledged:</p> <ul style="list-style-type: none"> - topology comparison, component shifted - topology comparison, serial number of a component has been detected to be different (byte 3 = 1) - topology comparison shows one component that is connected differently <p>The following parameter values are available:</p> <p>p9904 = 1 --> the procedure is started.</p> <p>p9904 = 0 after starting --> the procedure has been successfully completed.</p> <p>p9904 = 1 after starting --> the procedure has not been successfully completed.</p> <p>The possible causes for an unsuccessful procedure are located in bytes 4, 3, 2.</p> <p>Byte 2: Number of structural differences.</p> <p>Byte 3: Number of differences that can be acknowledged (p9904).</p> <p>Byte 4: Number of differences. These differences can be resolved as follows:</p> <ul style="list-style-type: none"> - sets the topology comparison (p9906 or p9907/p9908). - change over the actual topology. <p>The appropriate action should be selected corresponding to the message that is displayed/output.</p>		
Note:	In order to permanently accept the acknowledgement of the fault that can be resolved, then it must be saved in a non-volatile fashion (p0977).		
p9905 Device specialization / Device specializ.			
CU_S	Can be changed: C1(1)		Access level: 3
	Data type: Unsigned16	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 0
Description:	<p>With p9905 = 1, the serial numbers and the hardware versions of all of the components are transferred from the actual topology into the target topology and a new comparison is started..</p> <p>For the device specialization, the components of the target topology may only differ from those of the actual topology by the serial numbers.</p>		
Note:	<p>p9905 is automatically set to 0 at the end of the operation.</p> <p>In order to permanently accept the data, it is necessary to save in a non-volatile fashion (p0977).</p>		

p9906	Topology comparison, comparison stage of all components / Topo_cmpr tot comp		
CU_S	Can be changed: C1(1)		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 0
Description:	Sets the type of comparison between the actual topology and target topology. The comparison is started by setting the required value.		
Values:	0: High: Compares the complete electronic rating plate 1: Average: Compares the component type and the Order number 2: Low: Compares the component type 3: Minimum: Compares the component class 99: Topology has different comparison stages		
Note:	The electronic rating plate comprises the following data: - component type (e.g. "SMC20") - Order No. (e.g. "6SL3055-0AA0-5BA0") - manufacturer (e.g. SIEMENS) - hardware version (e.g. "A") - Serial No. (e.g. "T-P30050495") When comparing the topology, the following data is compared in the target and actual topologies: p9906 = 0: Component type, Order No., Hardware version, Manufacturer, Serial No. p9906 = 1: Component type, Order No. p9906 = 2: Component type p9906 = 3: Component class (e.g. Sensor Module or Motor Module)		
p9907	Topology comparison, comparison stage of the component number / Topo_cmpr comp_no		
CU_S	Can be changed: C1(1)		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 199	Factory setting 0
Description:	Enters the number of the component where the setting of how the actual topology should be compared to the target topology should be changed.		
Dependency:	Refer to: p9908		

p9908	Topology comparison, comparison stage of a component / Topo_cmpr 1 comp		
CU_S	Can be changed: C1(1)		Access level: 3
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 99	Factory setting 0
Description:	Sets the type of comparison of a component in the target topology with the actual topology. The comparison is started by setting the required value.		
Values:	0: High: Compares the complete electronic rating plate 1: Average: Compares the component type and the Order number 2: Low: Compares the component type 3: Minimum: Compares the component class 99: Topology has different comparison stages		
Dependency:	Refer to: p9907		
Note:	The electronic rating plate comprises the following data: - component type (e.g. "SMC20") - Order No. (e.g. "6SL3055-0AA0-5BA0") - manufacturer (e.g. SIEMENS) - hardware version (e.g. "A") - Serial No. (e.g. "T-P30050495") When comparing the topology, the following data is compared in the target and actual topologies: p9908 = 0: Component type, Order No., Hardware version, Manufacturer, Serial No. p9908 = 1: Component type, Order No. p9908 = 2: Component type p9908 = 3: Component class (e.g. Sensor Module or Motor Module)		
p9909	Topology comparison, component replacement / Topo_cmpr replace		
CU_S	Can be changed: C1(1)		Access level: 3
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 1	Factory setting 1
Description:	For p9909 = 1, the serial number and the hardware version of the new replaced component is automatically transferred from the actual topology into the target topology and then saved in a non-volatile fashion. For the components that have been replaced, the electronic type plate must match as far as the following data is concerned: - component type (e.g. "SMC20") - Order No. (e.g. "6SL3055-0AA0-5BA0") For p9909 = 0, serial numbers and hardware versions are not automatically transferred. In this case, the transfer must be made using p9904.		
Dependency:	Refer to: p9904, p9905		
Note:	The modified target topology is automatically saved in a non-volatile fashion when the drive object runs-up (e.g. after a POWER ON). Special case for Control Unit and option slot modules: When replacing these components, independent of p9909, the serial number and hardware version are automatically transferred and saved in a non-volatile fashion.		

p9910	Transfer additional components into the target topology / Transfer comp		
CU_S	Can be changed: C1(1)		Access level: 1
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0	Max 5	Factory setting 0
Description:	Transfer additional inserted DRIVE-CLiQ components into the target topology and add the appropriate drive objects to the project.		
Values:	0: No selection 1: Drive object type SERVO 2: Drive object type VECTOR 3: SINAMICS GM (DFEMV & VECTORMV) 4: SINAMICS SM (AFEMV & VECTORMV) 5: SINAMICS GL (VECTORGL)		
p9915	DRIVE-CLiQ data transfer error, shutdown threshold, master / DLQ fault master		
CU_S	Can be changed: C1(1)		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0000 hex	Max 0007 07FF hex	Factory setting 0007 02FF hex
Description:	Only for internal Siemens service.		
p9916	DRIVE-CLiQ data transfer error, shutdown threshold, slave / DLQ fault slave		
CU_S	Can be changed: C1(1)		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: Topology	Units group: -	Unit selection: -
	Min 0000 hex	Max 0007 07FF hex	Factory setting 0007 02FF hex
Description:	Only for internal Siemens service.		
p9920[0...19]	Licensing, enter license key / Enter license key		
CU_S	Can be changed: U, T		Access level: 2
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 255	Factory setting 0
Description:	Enters the license key for this drive unit. Example of the license key: EACZ-QBCA = 69 65 67 90 45 81 66 67 65 dec (ASCII characters) Index 0 = license key character 1 (e.g. 69 dec) Index 1 = license key character 2 (e.g. 65 dec) ... Index 19 = license key character 20 (e.g. 0 dec)		
Dependency:	Refer to: r7843, p9921 Refer to: A13000, A13001		
Notice:	An ASCII table can be found, for example, in the following reference: SINAMICS S120 Commissioning Manual		

Note: When changing p9920[x] to the value 0, all of the following indices are also set to 0.
 After entering the license key, the license key must be activated (p9921).
 If the licensing is not adequate, then the following alarm is displayed together with LED:
 - A13000 --> licensing not sufficient
 - LED READY --> flashes green/red with 0.5 Hz

p9921 Licensing, activate license key / Act. license key

CU_S	Can be changed: U, T	Dynamic index: -	Access level: 2
	Data type: Integer16	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min	Max	Factory setting
	0	1	0

Description: Activates the entered license key.
 The following is executed when activating the license key.
 - the checksum of the entered license key is checked.
 - the entered license key is saved in the a non-volatile fashion on the CompactFlash card.
 - re-enter the license key.

Values:
 0: not active
 1: Activate start license key

Dependency:
 Refer to: p9920
 Refer to: A13000, A13001

Note: Before activation, the license key entered using parameter p9920 is checked. If this check identifies an error, activation is rejected. In this case, writing a 1 to p9921 is rejected.
 When the license key has been activated, p9921 is automatically set to 0.

r9925[0...99] CompactFlash card file error / CF file error

CU_S	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the directory and the name of the file that was identified as illegal with respect to the state when supplied from the factory when checking the CompactFlash card.

Dependency:
 Refer to: r9926
 Refer to: A01016

Note: The directory and name of the file is displayed in the ASCII code.

r9926 CompactFlash card check status / CF check status

CU_S	Can be changed: -	Dynamic index: -	Access level: 2
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: -		Unit selection: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the status when checking the CompactFlash card after powering-up.
 0: CompactFlash Card still not checked.
 1: Check running.
 2: Check successfully completed.
 3: Check indicates an error.

Dependency:
 Refer to: r9925
 Refer to: A01016

p9930[0...8]	System logbook activation / SYSLOG activation		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 255	Factory setting 0
Description:	Only for service purposes.		
Index:	[0] = System logbook stage (0: Not active) [1] = COM2/COM1 (0: COM2, 1: COM1) [2] = Activate file write (0: Not active) [3] = Display time stamp (0: Not displayed) [4] = Display system logbook stage (0: Not displayed) [5] = Display drive object number (0: Not displayed) [6] = Display software module name (0: Not displayed) [7] = Output buffer size (stages, each 1 kB) [8] = System logbook file size (stages, each 10 kB)		
Notice:	Before powering-down the Control Unit, ensure that the system logbook is switched-out (p9930[0] = 0).		
p9931[0...99]	System logbook module selection / SYSLOG mod select.		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned32	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0000 hex	Max FFFF FFFF hex	Factory setting 0000 hex
Description:	Only for service purposes.		
p9932	Save system logbook EEPROM / SYSLOG EEPROM save		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Unsigned8	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 255	Factory setting 0
Description:	Only for service purposes.		
p9950	Runtime measurement, control / Runtime_meas ctrl		
CU_S	Can be changed: U, T		Access level: 4
	Data type: Integer16	Dynamic index: -	Function diagram: -
	P-Group: -	Units group: -	Unit selection: -
	Min 0	Max 3	Factory setting 0
Description:	Setting to control the runtime measurement.		
Values:	0: Stop runtime measurement 1: Start runtime meas (internal) 2: Clear trace buffer (internal) 3: Activate calculation of remaining computing time		
Dependency:	Refer to: r9976		

r9976[0...7]	System load / System load		
CU_S	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Floating Point	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	Factory setting	
	- [%]	- [%]	- [%]
Description:	<p>Displays the system load.</p> <p>The system load measurement is automatically started after run-up.</p> <p>The individual values (computation load and cyclic load) are measured over short time slices and from the measurements, the maximum, the minimum and the average value are formed and displayed in the appropriate indices. Further, the degree of memory utilization of the data and program memory is displayed.</p>		
Index:	<p>[0] = comp. time load (min)</p> <p>[1] = Computation time load (averaged)</p> <p>[2] = Computation time load (max)</p> <p>[3] = Computation time load cyclic (min)</p> <p>[4] = Computation time load cyclic (avg)</p> <p>[5] = Computation time load cyclic (max)</p> <p>[6] = Data memory locked</p> <p>[7] = Program memory locked</p>		
Dependency:	<p>Refer to: p9950</p> <p>Refer to: A01053</p>		
r11000[0...239]	PROFINET Name of Station / PN Name of Station		
CU_S (CBE)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	Factory setting	
	-	-	-
Description:	<p>Displays PROFINET Name of Station.</p>		
r11001[0...3]	PROFINET IP of Station / PN IP of Station		
CU_S (CBE)	Can be changed: -	Dynamic index: -	Access level: 3
	Data type: Unsigned8	Units group: -	Function diagram: -
	P-Group: -	Max	Unit selection: -
	Min	Factory setting	
	-	-	-
Description:	<p>Displays PROFINET IP of Station.</p>		

1.3 Parameters for data sets

1.3.1 Parameters for command data sets (CDS)

Note:

References: /IH1/ SINAMICS S120 Installation and Start-Up Manual
"Data sets" section

The following list contains the command-data-set-dependent parameters.

Product: SINAMICS S, Version: 2402300, Label: ., Language: eng

p0700[0...n]	Macro Binector Input (BI) / Macro BI
p0820[0...n]	BI: Drive data set selection DDS bit 0 / DDS select., bit 0
p0821[0...n]	BI: Drive data set selection DDS bit 1 / DDS select., bit 1
p0822[0...n]	BI: Drive data set selection DDS bit 2 / DDS select., bit 2
p0823[0...n]	BI: Drive data set selection DDS bit 3 / DDS select., bit 3
p0824[0...n]	BI: Drive data set selection DDS bit 4 / DDS select., bit 4
p0828[0...n]	BI: Motor changeover, feedback signal / Mot_chng fdbk sig
p0840[0...n]	BI: ON/OFF1 / ON/OFF1
p0844[0...n]	BI: 1. OFF2 / 1. OFF2
p0845[0...n]	BI: 2. OFF2 / 2. OFF2
p0848[0...n]	BI: 1. OFF3 / 1. OFF3
p0849[0...n]	BI: 2. OFF3 / 2. OFF3
p0852[0...n]	BI: Enable operation / Enable operation
p0854[0...n]	BI: Master ctrl by PLC / Master ctrl by PLC
p0855[0...n]	BI: Unconditionally release holding brake / Uncond open brake
p0856[0...n]	BI: Enable speed controller / Enable n_ctrl
p0858[0...n]	BI: Unconditionally close holding brake / Uncond close brake
p0858[0...n]	BI: Unconditionally close holding brake / Uncond close brake
p1000[0...n]	Macro Connector Inputs (CI) for speed setpoints / Macro CI n_set
p1000[0...n]	Macro Connector Inputs (CI) for velocity setpoints / Macro CI v_set
p1020[0...n]	BI: Fixed speed setpoint selection Bit 0 / n_set_fixed Bit 0
p1020[0...n]	BI: Fixed velocity setpoint selection Bit 0 / v_set_fixed Bit 0
p1021[0...n]	BI: Fixed speed setpoint selection Bit 1 / n_set_fixed Bit 1
p1021[0...n]	BI: Fixed velocity setpoint selection Bit 1 / v_set_fixed Bit 1
p1022[0...n]	BI: Fixed speed setpoint selection Bit 2 / n_set_fixed Bit 2
p1022[0...n]	BI: Fixed velocity setpoint selection Bit 2 / v_set_fixed Bit 2
p1023[0...n]	BI: Fixed speed setpoint selection Bit 3 / n_set_fixed Bit 3
p1023[0...n]	BI: Fixed velocity setpoint selection Bit 3 / v_set_fixed Bit 3
p1035[0...n]	BI: Motorized potentiometer, setpoint, raise / Mop raise
p1036[0...n]	BI: Motorized potentiometer, lower setpoint / Mop lower
p1039[0...n]	BI: Motorized potentiometer, inversion / Mop inversion
p1041[0...n]	BI: Motorized potentiometer, manual/automatic / Mop manual/auto
p1042[0...n]	CI: Motorized potentiometer, automatic setpoint / Mop auto setpoint
p1043[0...n]	BI: Motorized potentiometer, accept setpoint / Mop accept set val
p1044[0...n]	CI: Motorized potentiometer, setting value / Mop setting value
p1055[0...n]	BI: Jog bit 0 / Jog bit 0
p1056[0...n]	BI: Jog bit 1 / Jog bit 1
p1070[0...n]	CI: Main setpoint / Main setpoint

p1071[0...n]	CI: Main setpoint scaling / Main setpt scal
p1075[0...n]	CI: Suppl setpoint / Suppl setpoint
p1076[0...n]	CI: Supplementary setpoint scaling / Suppl setpt scal
p1085[0...n]	CI: Speed limit in positive direction of rotation / n_limit pos
p1085[0...n]	CI: Velocity limit, positive direction / v_limit pos
p1088[0...n]	CI: Speed limit negative direction of rotation / n_limit neg
p1088[0...n]	CI: Velocity limit, negative direction / n_limit neg
p1110[0...n]	BI: Inhibit negative direction / Inhib neg dir rot
p1111[0...n]	BI: Inhibit positive direction / Inhib pos dir rot
p1113[0...n]	BI: Direction reversal / Direction reversal
p1122[0...n]	BI: Bypass ramp-function generator / Bypass RFG
p1140[0...n]	BI: Enables the ramp-function generator / Enable RFG
p1141[0...n]	BI: Start ramp-function generator / Start RFG
p1142[0...n]	BI: Enable speed setpoint / Enable n_set
p1142[0...n]	BI: Enable velocity setpoint / Enable v_set
p1143[0...n]	BI: Ramp-function generator, accept setting value / Accept RFG set val
p1144[0...n]	CI: Ramp-function generator setting value / RFG setting value
p1155[0...n]	CI: Speed controller speed setpoint 1 / n_ctrl n_set 1
p1155[0...n]	CI: Velocity controller, velocity setpoint 1 / v_ctrl n_set 1
p1160[0...n]	CI: Speed controller speed setpoint 2 / n_ctrl n_set 2
p1160[0...n]	CI: Velocity controller, velocity setpoint 2 / v_ctrl n_set 2
p1230[0...n]	BI: Activating armature short-circuit / ASC act
p1235[0...n]	BI: External armature short-circuit, contactor feedback signal / ASC ext feedback
p1330[0...n]	CI: V/Hz control independent voltage setpoint / Uf U_set independ.
p1356[0...n]	CI: U/f control, angular setpoint / Uf ang setpoint
p1430[0...n]	CI: Speed precontrol / n_prectrl
p1430[0...n]	CI: Velocity precontrol / v_prectrl
p1437[0...n]	CI: Speed controller, reference model I component input / n_ctrRefMod I_comp
p1455[0...n]	CI: Speed controller P gain adaptation signal / n_ctrl Adpt_sig Kp
p1455[0...n]	CI: Velocity controller, P gain adaptation signal / v_ctrl Adpt_sig Kp
p1466[0...n]	CI: Speed controller P-gain scaling / n_ctrl Kp Scal
p1466[0...n]	CI: Velocity controller P gain scaling / v_ctrl Kp scal
p1476[0...n]	BI: Speed controller hold integrator / n_ctrl integ stop
p1476[0...n]	BI: Velocity controller, hold integrator / v_ctrl integ stop
p1477[0...n]	BI: Speed controller set integrator value / n_ctrl integ set
p1477[0...n]	BI: Set velocity controller integrator value / v_ctrl integ set
p1478[0...n]	CI: Speed controller integrator setting value / n_ctr integ_setVal
p1478[0...n]	CI: Velocity controller, integrator value / v_ctr integ_setVal
p1479[0...n]	CI: Speed controller integrator setting value scaling / n_ctrl I_val scal
p1492[0...n]	BI: Droop feedback enable / Enables droop
p1495[0...n]	CI: Acceleration pre-control, speed change each 1 s / a_prectrl dn/1s
p1500[0...n]	Macro Connector Inputs (CI) for torque setpoints / Macro CI M_set
p1500[0...n]	Macro Connector Inputs (CI) for force setpoints / Macro CI F_set
p1501[0...n]	BI: Change over between closed-loop speed/torque control / Changeov n/M_ctrl
p1501[0...n]	BI: Changeover velocity/force control / Changeov n/F_ctrl
p1503[0...n]	CI: Torque setpoint / M_set
p1511[0...n]	CI: Supplementary torque 1 / M_suppl 1
p1511[0...n]	CI: Supplementary force 1 / F_suppl 1
p1512[0...n]	CI: Supplementary torque 1 scaling / M_suppl 1 scal
p1512[0...n]	CI: Supplementary force 1 scaling / F_suppl 1 scal
p1513[0...n]	CI: Supplementary torque 2 / M_suppl 2
p1513[0...n]	CI: Supplementary force 2 / F_suppl 2
p1522[0...n]	CI: Torque limit, upper/motoring / M_max upper/mot

p1523[0...n]	Cl: Torque limit, lower/regenerative / M_max lower/regen
p1528[0...n]	Cl: Torque limit, upper/motoring, scaling / M_max up/mot scal
p1528[0...n]	Cl: Force limit upper/motoring scaling / F_max up/mot scal
p1528[0...n]	Cl: Torque limit upper scaling / M_max upper scal
p1529[0...n]	Cl: Torque limit, lower/regenerating scaling / M_max low/gen scal
p1529[0...n]	Cl: Force limit, lower/regenerative scaling / F_max low/gen scal
p1529[0...n]	Cl: Torque limit lower scaling / M_max lower scal
p1540[0...n]	Cl: Torque limit, speed controller upper scaling / M_max n-ctr upScal
p1541[0...n]	Cl: Torque limit. speed controller lower scaling / M_max nctr lowScal
p1542[0...n]	Cl: Travel to a fixed endstop, torque reduction / TfS M_red
p1545[0...n]	Bl: Activates travel to a fixed endstop / TfS activation
p1550[0...n]	Bl: Transfer actual torque as torque offset / Accept act. torque
p1551[0...n]	Bl: Torque limit, variable/fixed signal source / M_lim var/fixS_src
p1552[0...n]	Cl: Torque limit, upper scaling without offset / M_max up offs scal
p1554[0...n]	Cl: Torque limit, lower scaling without offset / M_max low offsScal
p1555[0...n]	Cl: Power limit / P_max
p1569[0...n]	Cl: Supplementary torque 3 / M_suppl 3
p1640[0...n]	Cl: Excitation current actual value / Excit curr act val
p2103[0...n]	Bl: 1. Acknowledge faults / 1. Acknowledge
p2104[0...n]	Bl: 2. Acknowledge faults / 2. Acknowledge
p2105[0...n]	Bl: 3. Acknowledge faults / 3. Acknowledge
p2106[0...n]	Bl: External fault 1 / External fault 1
p2107[0...n]	Bl: External fault 2 / External fault 2
p2108[0...n]	Bl: External fault 3 / External fault 3
p2112[0...n]	Bl: External alarm 1 / External alarm 1
p2116[0...n]	Bl: External alarm 2 / External alarm 2
p2117[0...n]	Bl: External alarm 3 / External alarm 3
p2148[0...n]	Bl: Ramp-function generator active / HLG active
p2151[0...n]	Cl: Speed setpoint for messages/signals / n_set for msg
p2151[0...n]	Cl: Speed setpoint for messages/signals / n_set for msg
p2154[0...n]	Cl: Speed setpoint 2 / n_set 2
p2200[0...n]	Bl: Technology controller enable / Tec_ctr enable
p2220[0...n]	Bl: Technology controller fixed value selection bit 0 / Tec_ctr sel bit 0
p2221[0...n]	Bl: Technology controller fixed value selection bit 1 / Tec_ctr sel bit 1
p2222[0...n]	Bl: Technology controller fixed value selection bit 2 / Tec_ctr sel bit 2
p2223[0...n]	Bl: Technology controller fixed value selection bit 3 / Tec_ctr sel bit 3
p2235[0...n]	Bl: Technology controller motorized potentiometer, raise setpoint / Tec_ctr mop raise
p2236[0...n]	Bl: Technology controller motorized potentiometer, lower setpoint / Tec_ctr mop lower
p2253[0...n]	Cl: Technology controller setpoint 1 / Tec_ctr setpoint 1
p2254[0...n]	Cl: Technology controller setpoint 2 / Tec_ctr setpoint 2
p2264[0...n]	Cl: Technology controller actual value / Tec_ctr act val
p2289[0...n]	Cl: Technology controller pre-control signal / Tec_ctr prectrl
p2296[0...n]	Cl: Technology controller output scaling / Tec_ctr outp scal
p2297[0...n]	Cl: Technology controller maximum limiting / Tec_ctr max_limit
p2298[0...n]	Cl: Technology controller minimum limiting / Tec_ctr min_lim
p3111[0...n]	Bl: External fault 3, enable / Ext fault 3 enab
p3112[0...n]	Bl: External fault 3 enable negated / Ext flt 3 enab neg
p3784[0...n]	Bl: Sync line-drive external increase voltage / Sync ext U incr
p3785[0...n]	Bl: Sync line-drive external decrease voltage / Sync ext U decr
p3802[0...n]	Bl: Sync line-drive enable / Sync enable

1.3.2 Parameters for drive data sets (DDS)

Note:

References: /IH1/ SINAMICS S120 Installation and Start-Up Manual
"Data sets" section

The following list contains the drive-data-set-dependent parameters.

Product: SINAMICS S, Version: 2402300, Label: ., Language: eng

p0186[0...n]	Motor Data Sets (MDS) number / MDS number
p0187[0...n]	Encoder 1 encoder data set number / Enc 1 EDS number
p0188[0...n]	Encoder 2 encoder data set number / Enc 2 EDS number
p0189[0...n]	Encoder 3 encoder data set number / Enc 3 EDS number
p0340[0...n]	Automatic calculation of motor/control parameters / Calc auto par
p0578[0...n]	Calculate parameters that are dependent on the technology/units / Calc techn par
p0640[0...n]	Current limit / Current limit
p1001[0...n]	CO: Fixed speed setpoint 1 / n_set_fixed 1
p1001[0...n]	CO: Fixed velocity setpoint 1 / n_set_fixed 1
p1002[0...n]	CO: Fixed speed setpoint 2 / n_set_fixed 2
p1002[0...n]	CO: Fixed velocity setpoint 2 / n_set_fixed 2
p1003[0...n]	CO: Fixed speed setpoint 3 / n_set_fixed 3
p1003[0...n]	CO: Fixed velocity setpoint 3 / n_set_fixed 3
p1004[0...n]	CO: Fixed speed setpoint 4 / n_set_fixed 4
p1004[0...n]	CO: Fixed velocity setpoint 4 / n_set_fixed 4
p1005[0...n]	CO: Fixed speed setpoint 5 / n_set_fixed 5
p1005[0...n]	CO: Fixed velocity setpoint 5 / n_set_fixed 5
p1006[0...n]	CO: Fixed speed setpoint 6 / n_set_fixed 6
p1006[0...n]	CO: Fixed velocity setpoint 6 / n_set_fixed 6
p1007[0...n]	CO: Fixed speed setpoint 7 / n_set_fixed 7
p1007[0...n]	CO: Fixed velocity setpoint 7 / n_set_fixed 7
p1008[0...n]	CO: Fixed speed setpoint 8 / n_set_fixed 8
p1008[0...n]	CO: Fixed velocity setpoint 8 / n_set_fixed 8
p1009[0...n]	CO: Fixed speed setpoint 9 / n_set_fixed 9
p1009[0...n]	CO: Fixed velocity setpoint 9 / n_set_fixed 9
p1010[0...n]	CO: Fixed speed setpoint 10 / n_set_fixed 10
p1010[0...n]	CO: Fixed velocity setpoint 10 / n_set_fixed 10
p1011[0...n]	CO: Fixed speed setpoint 11 / n_set_fixed 11
p1011[0...n]	CO: Fixed velocity setpoint 11 / n_set_fixed 11
p1012[0...n]	CO: Fixed speed setpoint 12 / n_set_fixed 12
p1012[0...n]	CO: Fixed velocity setpoint 12 / n_set_fixed 12
p1013[0...n]	CO: Fixed speed setpoint 13 / n_set_fixed 13
p1013[0...n]	CO: Fixed velocity setpoint 13 / n_set_fixed 13
p1014[0...n]	CO: Fixed speed setpoint 14 / n_set_fixed 14
p1014[0...n]	CO: Fixed velocity setpoint 14 / n_set_fixed 14
p1015[0...n]	CO: Fixed speed setpoint 15 / n_set_fixed 15
p1015[0...n]	CO: Fixed velocity setpoint 15 / n_set_fixed 15
p1030[0...n]	Motorized potentiometer, configuration / Mop configuration
p1037[0...n]	Motorized potentiometer, maximum speed / Mop n_max
p1037[0...n]	Motorized potentiometer, maximum velocity / Mop n_max
p1038[0...n]	Motorized potentiometer, minimum speed / Mop n_min
p1038[0...n]	Motorized potentiometer, minimum velocity / Mop n_min

p1040[0...n]	Motorized potentiometer, starting value / Mop start value
p1040[0...n]	Motorized potentiometer, starting value / Mop start value
p1047[0...n]	Motorized potentiometer, ramp-up time / Mop ramp-up time
p1048[0...n]	Motorized potentiometer, ramp-down time / Mop ramp-down time
p1058[0...n]	Jog 1 speed setpoint / Jog 1 n_set
p1058[0...n]	Jog 1 velocity setpoint / Jog 1 n_set
p1059[0...n]	Jog 2 speed setpoint / Jog 2 n_set
p1059[0...n]	Jog 2 velocity setpoint / Jog 2 n_set
p1063[0...n]	Speed limit, setpoint channel / n_limit setp.
p1063[0...n]	Velocity limit, setpoint channel / v_limit setp.
p1080[0...n]	Minimum speed / Minimum speed
p1080[0...n]	Minimum velocity / Minimum speed
p1082[0...n]	Maximum speed / Maximum speed
p1082[0...n]	Maximum velocity / Maximum speed
p1082[0...n]	Maximum speed / Maximum speed
p1083[0...n]	CO: Speed limit in positive direction of rotation / n_limit pos
p1083[0...n]	CO: Velocity limit, positive direction / v_limit pos
p1086[0...n]	CO: Speed limit negative direction of rotation / n_limit neg
p1086[0...n]	CO: Velocity limit, negative direction / v_limit neg
p1091[0...n]	Skip speed 1 / Skip speed 1
p1091[0...n]	Skip velocity 1 / Skip speed 1
p1092[0...n]	Skip speed 2 / Skip speed 2
p1092[0...n]	Skip velocity 2 / Skip speed 2
p1093[0...n]	Skip speed 3 / Skip speed 3
p1093[0...n]	Skip velocity 3 / Skip speed 3
p1094[0...n]	Skip speed 4 / Skip speed 4
p1094[0...n]	Skip velocity 4 / Skip speed 4
p1101[0...n]	Skip speed bandwidth / Skip_n bandwidth
p1101[0...n]	Skip velocity bandwidth / Skip_n bandwidth
p1120[0...n]	Ramp-function generator ramp-up time / RFG ramp-up time
p1120[0...n]	Ramp-function generator ramp-up time / RFG ramp-up time
p1121[0...n]	Ramp-function generator ramp-down time / RFG ramp-down time
p1121[0...n]	Ramp-function generator ramp-down time / RFG ramp-down time
p1130[0...n]	Ramp-function generator initial rounding-off time / RFG t_start_round
p1131[0...n]	Ramp-function generator final rounding-off time / RFG t_end_delay
p1134[0...n]	Ramp-function generator rounding-off type / RFG round-off type
p1135[0...n]	OFF3 ramp-down time / RFG OFF3 t_ramp-dn
p1135[0...n]	OFF3 ramp-down time / RFG OFF3 t_ramp-dn
p1136[0...n]	OFF3 initial rounding-off time / RFG OFF3 t_strt_rnd
p1137[0...n]	OFF3 final rounding-off time / RFG OFF3 t_end_del
p1145[0...n]	Ramp-function generator tracking intensity. / RFG track intens
p1148[0...n]	Ramp-function gen., tolerance for ramp-up and ramp-down active / RFG tol HL/RL act
p1148[0...n]	Ramp-function gen., tolerance for ramp-up and ramp-down active / RFG tol HL/RL act
p1151[0...n]	Ramp-function generator configuration / RFG config
p1189[0...n]	Speed setpoint configuration / n_ctrl config
p1189[0...n]	Velocity setpoint configuration / v_ctrl config
p1192[0...n]	DSC enc selection / DSC enc selection
p1193[0...n]	DSC encoder adaptation factor / DSC encodAdaptFact
p1200[0...n]	FlyRest oper mode / FlyRest oper mode
p1202[0...n]	FlyRest srch curr / FlyRest srch curr
p1203[0...n]	Flying restart search rate factor / FlyRst v_Srch Fact
p1240[0...n]	Vdc controller configuration / Vdc_ctrl config
p1243[0...n]	Vdc_max controller dynamic factor / Vdc_max dyn_factor

p1245[0...n]	Vdc_min controller switch-in level (kinetic buffering) / Vdc_min on_level
p1247[0...n]	Vdc_min controller dynamic factor (kinetic buffering) / Vdc_min dyn_factor
p1250[0...n]	Vdc controller proportional gain / Vdc_ctrl Kp
p1251[0...n]	Vdc controller integral time / Vdc_ctrl Tn
p1252[0...n]	Vdc controller rate time / Vdc_ctrl t_rate
p1255[0...n]	Vdc_min controller time threshold / Vdc_min t_thresh
p1256[0...n]	Vdc_min controller response (kinetic buffering) / Vdc_min response
p1257[0...n]	Vdc_min controller speed threshold / Vdc_min n_thresh
p1262[0...n]	Bypass deadtime / Bypass t_dead
p1280[0...n]	Vdc controller configuration (U/f) / Vdc_ctrl config
p1283[0...n]	Vdc_max controller dynamic factor (U/f) / Vdc_max dyn_factor
p1285[0...n]	Vdc_min controller switch-in level (kinetic buffering) (U/f) / Vdc_min on_level
p1287[0...n]	Vdc_min controller dynamic factor (kinetic buffering) (U/f) / Vdc_min dyn_factor
p1290[0...n]	Vdc controller proportional gain (U/f) / Vdc_ctrl Kp
p1291[0...n]	Vdc controller integral time (U/f) / Vdc_ctrl Tn
p1292[0...n]	Vdc controller rate time (U/f) / Vdc_ctrl t_rate
p1293[0...n]	Vdc controller output limit (U/f) / Vdc_ctrl outp_lim
p1295[0...n]	Vdc_min controller time threshold (U/f) / Vdc_min t_thresh
p1296[0...n]	Vdc_min controller response (kinetic buffering) (U/f) / Vdc_min response
p1297[0...n]	Vdc_min controller speed threshold (U/f) / Vdc_min n_thresh
p1300[0...n]	Open-loop/closed-loop control operating mode / Control mode
p1300[0...n]	Open-loop/closed-loop control operating mode / Control mode
p1310[0...n]	Voltage boost permanent / U_boost perm
p1311[0...n]	Voltage boost at acceleration / U_boost accelerate
p1317[0...n]	U/f control diagnostics activation / Uf diagn act
p1318[0...n]	U/f control ramp-up/ramp-down time / Uf t_rmp-up_rmp-dn
p1319[0...n]	U/f control voltage at zero frequency / Uf U at f=0 Hz
p1320[0...n]	U/f control programmable characteristic frequency 1 / Uf char f1
p1321[0...n]	U/f control programmable characteristic voltage 1 / Uf char U1
p1322[0...n]	U/f control programmable characteristic frequency 2 / Uf char f2
p1323[0...n]	U/f control programmable characteristic voltage 2 / Uf char U2
p1324[0...n]	U/f control programmable characteristic frequency 3 / Uf char f3
p1325[0...n]	U/f control programmable characteristic voltage 3 / Uf char U3
p1326[0...n]	U/f control programmable characteristic frequency 4 / Uf char f4
p1327[0...n]	U/f control programmable characteristic voltage 4 / Uf char U4
p1335[0...n]	Slip compensation, scaling / Slip comp scal
p1336[0...n]	Slip compensation limit value / Slip comp lim val
p1338[0...n]	U/f mode resonance damping gain / Uf Res_damp gain
p1339[0...n]	U/f mode resonance damping filter time constant / Uf Res_damp T
p1340[0...n]	I_max frequency controller proportional gain / I_max_ctrl Kp
p1341[0...n]	I_max frequency controller integral time / I_max_ctrl Tn
p1345[0...n]	I_max voltage controller proportional gain / I_max_U_ctrl Kp
p1346[0...n]	I_max voltage controller integral time / I_max_U_ctrl Tn
p1349[0...n]	U/f mode resonance damping maximum frequency / Uf res_damp F_max
p1350[0...n]	Soft starting / Soft starting
p1358[0...n]	Angular difference, symmetrizing, actual angle / Sym act angle
p1400[0...n]	Speed control configuration / n_ctrl config
p1400[0...n]	Velocity control, configuration / v_ctrl config
p1400[0...n]	Speed control configuration / n_ctrl config
p1401[0...n]	Flux control configuration / F_ctrl config
p1402[0...n]	Closed-loop current control and motor model configuration / I_ctrl config
p1402[0...n]	Closed-loop current control and motor model configuration / I_ctrl config
p1404[0...n]	Sensorless operation changeover speed / Sensorl op n_chgov

p1404[0...n]	Sensorless operation changeover velocity / Sensorl op v_chgov
p1412[0...n]	Speed setpoint filter, deadtime / n_set deadtime
p1414[0...n]	Speed setpoint filter activation / n_set_filt active
p1414[0...n]	Velocity setpoint filter activation / v_set_filt active
p1414[0...n]	Speed setpoint filter activation / n_set_filt active
p1415[0...n]	Speed setpoint filter 1 type / n_set_filt 1 typ
p1415[0...n]	Velocity setpoint filter 1 type / n_set_filt 1 typ
p1416[0...n]	Speed setpoint filter 1 time constant / n_set_filt 1 T
p1416[0...n]	Velocity setpoint filter 1 time constant / v_set_filt 1 T
p1417[0...n]	Speed setpoint filter 1 denominator natural frequency / n_set_filt 1 fn_d
p1417[0...n]	Velocity setpoint filter 1 denominator natural frequency / v_set_filt 1 fn_d
p1417[0...n]	Speed setpoint filter 1 denominator natural frequency / n_set_filt 1 fn_d
p1418[0...n]	Speed setpoint filter 1 denominator damping / n_set_filt 1 D_d
p1418[0...n]	Velocity setpoint filter 1 denominator damping / v_set_filt 1 D_d
p1418[0...n]	Speed setpoint filter 1 denominator damping / n_set_filt 1 D_d
p1419[0...n]	Speed setpoint filter 1 numerator natural frequency / n_set_filt 1 fn_n
p1419[0...n]	Velocity setpoint filter 1 numerator natural frequency / v_set_filt 1 fn_n
p1420[0...n]	Speed setpoint filter 1 numerator damping / n_set_filt 1 D_n
p1420[0...n]	Velocity setpoint filter 1 numerator damping / v_set_filt 1 D_n
p1421[0...n]	Speed setpoint filter 2 type / n_set_filt 2 typ
p1421[0...n]	Velocity setpoint filter 2 type / n_set_filt 2 typ
p1422[0...n]	Speed setpoint filter 2 time constant / n_set_filt 2 T
p1422[0...n]	Velocity setpoint filter 2 time constant / v_set_filt 2 T
p1423[0...n]	Speed setpoint filter 2 denominator natural frequency / n_set_filt 2 fn_d
p1423[0...n]	Velocity setpoint filter 2 denominator natural frequency / v_set_filt 2 fn_d
p1424[0...n]	Speed setpoint filter 2 denominator damping / n_set_filt 2 D_d
p1424[0...n]	Velocity setpoint filter 2 denominator damping / v_set_filt 2 D_d
p1425[0...n]	Speed setpoint filter 2 numerator natural frequency / n_set_filt 2 fn_n
p1425[0...n]	Velocity setpoint filter 2 numerator natural frequency / v_set_filt 2 fn_n
p1426[0...n]	Speed setpoint filter 2 numerator damping / n_set_filt 2 D_n
p1426[0...n]	Velocity setpoint filter 2 numerator damping / v_set_filt 2 D_n
p1428[0...n]	Speed precontrol symmetrizing deadtime / n_prectrSym t_dead
p1428[0...n]	Velocity precontrol symmetrizing deadtime / n_prectrSym t_dead
p1429[0...n]	Speed precontrol symmetrizing time constant / n_prectr sym T
p1429[0...n]	Velocity precontrol symmetrizing time constant / n_prectr sym T
p1433[0...n]	Speed controller reference model natural frequency / n_ctrl RefMod fn
p1433[0...n]	Velocity controller reference model natural frequency / v_ctrl RefMod fn
p1434[0...n]	Speed controller reference model damping / n_ctrl RefMod D
p1434[0...n]	Velocity controller reference model damping / v_ctrl RefMod D
p1435[0...n]	Speed controller reference model deadtime / n_ctrRefMod t_dead
p1435[0...n]	Velocity controller reference model deadtime / v_ctrRefMod t_dead
p1441[0...n]	Actual speed smoothing time / n_act T_smooth
p1441[0...n]	Actual velocity, smoothing time / v_act T_smooth
p1441[0...n]	Actual speed smoothing time / n_act T_smooth
p1442[0...n]	Speed controller speed actual value smoothing time / n_ctr n_act T_smth
p1452[0...n]	Speed controller speed actual value smoothing time (SLVC) / n_C n_act T_s SLVC
p1456[0...n]	Speed controller P gain adaptation lower starting point / n_ctrl AdaptKpLow.
p1456[0...n]	Velocity controller P gain adaptation, lower starting point / n_ctrl AdaptKpLow.
p1456[0...n]	Speed controller P gain adaptation lower starting point / n_ctrl AdaptKpLow.
p1457[0...n]	Speed controller P gain adaptation upper starting point / n_ctrl AdaptKp up.
p1457[0...n]	Velocity controller P gain adaptation upper starting point / v_ctrl AdaptKp up.
p1457[0...n]	Speed controller P gain adaptation upper starting point / n_ctrl AdaptKp up.
p1458[0...n]	Adaptation factor, lower / Adapt_factor lower

p1458[0...n]	Adaptation factor, lower / Adapt_factor lower
p1459[0...n]	Adaptation factor, upper / Adapt_factor upper
p1459[0...n]	Adaptation factor, upper / Adapt_factor upper
p1460[0...n]	Speed controller P gain adaptation speed, lower / n_ctrl Kp n lower
p1460[0...n]	Velocity controller, P gain adaptation velocity, lower / v_ctrl Kp n lower
p1460[0...n]	Speed controller P gain adaptation speed, lower / n_ctrl Kp n lower
p1461[0...n]	Speed controller Kp adaptation speed, upper scaling / n_ctrl Kp n upper
p1461[0...n]	Velocity controller, P gain adaptation velocity, upper / v_ctrl Kp n upper
p1461[0...n]	Speed controller Kp adaptation speed, upper scaling / n_ctrl Kp n upper
p1462[0...n]	Speed controller integral time adaptation speed, lower / n_ctrl Tn n lower
p1462[0...n]	Velocity contr., integral act. time adaptation velocity, lower / v_ctrl Tn n lower
p1463[0...n]	Speed controller Tn adaptation speed, upper scaling / n_ctrl Tn n upper
p1463[0...n]	Velocity contr., integral act. time adaptation velocity, upper / v_ctrl Tn n upper
p1463[0...n]	Speed controller Tn adaptation speed, upper scaling / n_ctrl Tn n upper
p1464[0...n]	Speed controller adaptation speed, lower / n_ctrl n lower
p1464[0...n]	Velocity controller adaptation velocity, lower / v_ctrl n lower
p1464[0...n]	Speed controller adaptation speed, lower / n_ctrl n lower
p1465[0...n]	Speed controller adaptation speed, upper / n_ctrl n upper
p1465[0...n]	Velocity controller adaptation velocity, upper / v_ctrl n upper
p1465[0...n]	Speed controller adaptation speed, upper / n_ctrl n upper
p1470[0...n]	Speed controller sensorless operation P-gain / n_ctrl SLVC Kp
p1470[0...n]	Velocity controller sensorless operation P-gain / v_ctrl SLVC Kp
p1470[0...n]	Speed controller sensorless operation P-gain / n_ctrl SLVC Kp
p1472[0...n]	Speed controller sensorless operation integral time / n_ctrl SLVC Tn
p1472[0...n]	Velocity controller sensorless operation integral time / v_ctrl SLVC Tn
p1488[0...n]	Droop input source / Droop input,source
p1489[0...n]	Droop feedback scaling / Droop scaling
p1494[0...n]	Speed controller integrator feedback time constant / n_ctr integ_fdbk T
p1494[0...n]	Velocity controller integrator feedback time constant / v_ctr integ_fdbk T
p1496[0...n]	Acceleration pre-control scaling / a_before scaling
p1498[0...n]	Load moment of inertia / Load mom of inert
p1498[0...n]	Load mass / Load mass
p1499[0...n]	Accelerating for torque control, scaling / a for M_ctrl scal
p1514[0...n]	Supplementary torque 2 scaling / M_suppl 2 scal
p1517[0...n]	Accelerating torque smoothing time constant / M_accel T_smooth
p1517[0...n]	Acceleration force smoothing time constant / F_accel T_smooth
p1520[0...n]	CO: Torque limit, upper/motoring / M_max upper/mot
p1520[0...n]	CO: Force limit upper/motoring / F_max upper/mot
p1521[0...n]	CO: Torque limit, lower/regenerative / M_max lower/regen
p1521[0...n]	CO: Force limit, lower/regenerative / F_max lower/regen
p1524[0...n]	CO: Torque limit, upper/motoring, scaling / M_max up/mot scal
p1524[0...n]	CO: Force limit upper/motoring scaling / F_max up/mot scal
p1525[0...n]	CO: Torque limit, lower/regenerating scaling / M_max low/gen scal
p1525[0...n]	CO: Force limit, lower/regenerative scaling / F_max low/gen scal
p1530[0...n]	Power limit, motoring / P_max mot
p1531[0...n]	Power limit, regenerating / P_max gen
p1532[0...n]	CO: Torque limit, offset / M_max offset
p1532[0...n]	CO: Force offset, force limit / F_max offset
p1556[0...n]	Power limit scaling / P_max_scale
p1570[0...n]	CO: Flux setpoint / Flux setpoint
p1572[0...n]	Supplementary flux setpoint / Suppl flux setp
p1574[0...n]	Voltage reserve dynamic / U_reserve dyn
p1576[0...n]	Flux boost, adaptation speed, lower / Flux boost n lower

p1577[0...n]	Flux boost adaptation speed, upper / Flux boost n upper
p1580[0...n]	Efficiency optimization / Efficiency opt.
p1582[0...n]	Flux setpoint smoothing time / Flux setp T_smth
p1584[0...n]	Field weakening operation, flux setpoint smoothing time / Field weak T_smth
p1585[0...n]	Flux actual value, smoothing time / Flux actVal T_smth
p1590[0...n]	Flux controller P gain / Flux controller Kp
p1590[0...n]	Flux controller P gain / Flux controller Kp
p1592[0...n]	Flux controller integral.action time / Flux controller Tn
p1592[0...n]	Flux controller integral.action time / Flux controller Tn
p1594[0...n]	Field-weakening controller, P gain / Field_ctrl Kp
p1596[0...n]	Field weakening controller integral-action time / Field_ctrl Tn
p1599[0...n]	Flux controller, excitation current difference / Flux ctr I_excDiff
p1600[0...n]	P flux controller, P gain / P flux ctrl Kp
p1609[0...n]	Current setpoint for I/f operation / I_set I/f oper
p1610[0...n]	Torque setpoint static (SLVC) / M_set static
p1611[0...n]	Supplementary accelerating torque (SLVC) / M_suppl_accel
p1612[0...n]	Current setpoint, open-loop control, sensorless / I_setCtrSensorless
p1616[0...n]	Current setpoint smoothing time / I_set T_smooth
p1619[0...n]	Setpoint/actual value tracking threshold / SetAct track thrsh
p1620[0...n]	Stator current, minimum / I_stator min
p1621[0...n]	Changeover speed, inner $\cos \phi = 1 / n_chngov \cos \phi = 1$
p1622[0...n]	Field-generating current setpoint smoothing time constant / Id_setp T_smth
p1625[0...n]	Excitation current setpoint calibration / I_exc_setp cal
p1628[0...n]	Current model controller, dynamic factor / I_mod_ctr dyn_fact
p1629[0...n]	Current model controller P gain / I_mod_ctrl Kp
p1630[0...n]	Current model controller integral time / I_ctrl Tn
p1642[0...n]	Minimum excitation current / Min I_exc
p1643[0...n]	Gain factor, minimum excitation current closed-loop control / Min I_exc Kp
p1653[0...n]	Current setpoint torque-generating minimum smoothing time / Isq_s T_smth_min
p1654[0...n]	Curr. setpoint torque-gen. smoothing time field weakening range / Isq_s T_smth FW
p1656[0...n]	Activates current setpoint filter / I_set_filt active
p1656[0...n]	Activates current setpoint filter / I_set_filt active
p1657[0...n]	Current setpoint filter 1 type / I_set_filt 1 Typ
p1658[0...n]	Current setpoint filter 1 denominator natural frequency / I_set_filt 1 fn_n
p1659[0...n]	Current setpoint filter 1 denominator damping / I_set_filt 1 D_n
p1660[0...n]	Current setpoint filter 1 numerator natural frequency / I_set_filt 1 fn_z
p1661[0...n]	Current setpoint filter 1 numerator damping / I_set_filt 1 D_z
p1662[0...n]	Current setpoint filter 2 type / I_set_filt 2 Typ
p1663[0...n]	Current setpoint filter 2 denominator natural frequency / I_set_filt 2 fn_n
p1664[0...n]	Current setpoint filter 2 denominator damping / I_set_filt 2 D_n
p1665[0...n]	Current setpoint filter 2 numerator natural frequency / I_set_filt 2 fn_z
p1666[0...n]	Current setpoint filter 2 numerator damping / I_set_filt 2 D_z
p1667[0...n]	Current setpoint filter 3 type / I_set_filt 3 Typ
p1668[0...n]	Current setpoint filter 3 denominator natural frequency / I_set_filt 3 fn_n
p1669[0...n]	Current setpoint filter 3 denominator damping / I_set_filt 3 D_n
p1670[0...n]	Current setpoint filter 3 numerator natural frequency / I_set_filt 3 fn_z
p1671[0...n]	Current setpoint filter 3 numerator damping / I_set_filt 3 D_z
p1672[0...n]	Current setpoint filter 4 type / I_set_filt 4 Typ
p1673[0...n]	Current setpoint filter 4 denominator natural frequency / I_set_filt 4 fn_n
p1674[0...n]	Current setpoint filter 4 denominator damping / I_set_filt 4 D_n
p1675[0...n]	Current setpoint filter 4 numerator natural frequency / I_set_filt 4 fn_n
p1676[0...n]	Current setpoint filter 4 numerator damping / I_set_filt 4 D_z
p1701[0...n]	Current controller reference model deadtime / I_ctrRefMod t_dead

p1702[0...n]	Isd current controller pre-control scaling / Isd_ctr_prectrScal
p1703[0...n]	Isq current controller pre-control scaling / Isq_ctr_prectrScal
p1704[0...n]	EMF scaling of the Isq current controller pre-control / EMF scal Isq_ctrl
p1705[0...n]	Flux setpoint/actual value tracking threshold / Flux track thresh
p1715[0...n]	Current controller P gain / I_ctrl Kp
p1715[0...n]	Current controller P gain / I_ctrl Kp
p1717[0...n]	Current controller integral-action time / I_ctrl Tn
p1726[0...n]	Quadrature arm decoupling, scaling / Transv_decpl scal
p1727[0...n]	Quadrature arm decoupling at voltage limit, scaling / TrnsvDecplVmaxScal
p1740[0...n]	Gain resonance damping for sensorless closed loop control / Gain res_damp
p1744[0...n]	Motor model speed threshold stall detection / MotMod n_thr stall
p1745[0...n]	Motor model error threshold stall detection / MotMod ThreshStall
p1750[0...n]	Motor model configuration / MotMod config
p1752[0...n]	Motor model changeover speed operation with encoder / MotMod n_chgov enc
p1752[0...n]	Motor model with encoder changeover velocity / MotMod v_chgov enc
p1754[0...n]	Flux angle difference smoothing time / Angle diff T_smth
p1755[0...n]	Motor model changeover speed sensorless operation / MotMod n_chgSnsorl
p1755[0...n]	Motor model changeover velocity sensorless operation / MotMod v_chgSnsorl
p1755[0...n]	Motor model changeover speed sensorless operation / MotMod n_chgSnsorl
p1757[0...n]	Motor model w/o enc. op./cl.-loop controlled stab. controller Kp / MotMod w/o enc Kp
p1758[0...n]	Motor model changeover delay time, closed/open-loop control / MotMod t_cl_op
p1759[0...n]	Motor model changeover delay time open/closed loop control / MotMod t_op_cl
p1760[0...n]	Motor model with encoder speed adaptation Kp / MotMod wE n_ada Kp
p1761[0...n]	Motor model with encoder speed adaptation Tn / MotMod wE n_ada Tn
p1764[0...n]	Motor model without encoder speed adaptation Kp / MotMod woE n_adaKp
p1767[0...n]	Motor model without encoder speed adaptation Tn / MotMod woE n_adaTn
p1774[0...n]	Motor model, offset voltage compensation alpha / MotMod offs comp A
p1775[0...n]	Motor model, offset voltage compensation beta / MotMod offs comp B
p1780[0...n]	Motor model adaptation configuration / MotMod adapt conf
p1780[0...n]	Motor/converter model adaptation configuration / MotMod adapt conf
p1780[0...n]	Motor model adaptation configuration / MotMod adapt conf
p1781[0...n]	Motor model ASM Rs adaptation integral time / MotMod Rs Tn
p1783[0...n]	Motor model ASM Rs adaptation Kp / MotMod Rs Kp
p1785[0...n]	Motor model ASM Lh adaptation Kp / MotMod Lh Kp
p1786[0...n]	Motor model ASM Lh adaptation integral time / MotMod Lh Tn
p1795[0...n]	Motor model PEM kT adaptation smoothing time / MotMod kT T_smth
p1795[0...n]	Motor model PEM kT adaptation integral time / MotMod kT Tn
p1800[0...n]	Pulse frequency / Pulse frequency
p1800[0...n]	Pulse frequency / Pulse frequency
p1802[0...n]	Modulator mode / Modulator mode
p1803[0...n]	Maximum modulation depth / Modulat depth max
p1804[0...n]	Filter time constant smoothed modulation index / T_filt mod_idxSmth
p1806[0...n]	Filter time constant Vdc correction / T_filt Vdc_corr
p1820[0...n]	Output phase direction of rotation / Phase revers. outp
p1821[0...n]	Direction reversal / Direction reversal
p1840[0...n]	Actual value correction, configuration / ActVal_corr config
p1845[0...n]	Actual value correction evaluation factor Lsig / ActV_corr FactLsig
p1846[0...n]	Actual value correction damping factor / ActV_corr D_factor
p1952[0...n]	Voltage emulation error, final value / U_error final val
p1953[0...n]	Voltage emulation error current offset / U_error I_offset
p1959[0...n]	Rotating measurement configuration / Rot meas config
p2140[0...n]	Hysteresis speed 2 / n_hysteresis 2
p2140[0...n]	Hysteresis velocity 2 / v_hysteresis 2

p2141[0...n]	Speed threshold 1 / n_thresh val 1
p2141[0...n]	Velocity threshold value 1 / v_thresh val 1
p2142[0...n]	Hysteresis speed 1 / n_hysteresis 1
p2142[0...n]	Hysteresis velocity 1 / v_hysteresis 1
p2149[0...n]	Monitoring, configuration / Monit config
p2149[0...n]	Monitoring, configuration / Monit config
p2150[0...n]	Hysteresis speed 3 / n_hysteresis 3
p2150[0...n]	Hysteresis velocity 3 / v_hysteresis 3
p2153[0...n]	Speed actual value filter time constant / n_act_filt T
p2155[0...n]	Speed threshold 2 / n_thresh val 2
p2155[0...n]	Velocity threshold value 2 / v_thresh val 2
p2156[0...n]	On delay, comparison value reached / t_on cmpr val rchd
p2161[0...n]	Speed threshold 3 / n_thresh val 3
p2161[0...n]	Velocity threshold value 3 / v_thresh val 3
p2162[0...n]	Hysteresis speed n_act > n_max / Hyst n_act>n_max
p2162[0...n]	Hysteresis velocity v_act > v_max / Hyst v_act>v_max
p2163[0...n]	Speed threshold 4 / n_thresh val 4
p2163[0...n]	Velocity threshold value 4 / v_thresh val 4
p2164[0...n]	Hysteresis speed 4 / n_hysteresis 4
p2164[0...n]	Hysteresis velocity 4 / v_hysteresis 4
p2166[0...n]	Off delay n_act = n_set / t_del_off n_i=n_so
p2167[0...n]	Switch-on delay n_act = n_set / t_on n_act=n_set
p2174[0...n]	Torque threshold value 1 / M_thresh val 1
p2174[0...n]	Force threshold value 1 / F_thresh val 1
p2175[0...n]	Motor locked speed threshold / Mot lock n_thresh
p2175[0...n]	Motor locked, velocity threshold / Mot lock v_thresh
p2177[0...n]	Motor locked delay time / Mot lock t_del
p2178[0...n]	Motor stalled delay time / Mot stall t_del
p2181[0...n]	Load monitoring, response / Load monit. resp.
p2182[0...n]	Load monitoring, speed threshold value 1 / n_thresh 1
p2182[0...n]	Load monitoring, velocity threshold 1 / n_thresh 1
p2183[0...n]	Load monitoring, speed threshold value 2 / n_thresh 2
p2183[0...n]	Load monitoring, velocity threshold 2 / n_thresh 2
p2184[0...n]	Load monitoring, speed threshold value 3 / n_thresh 3
p2184[0...n]	Load monitoring, velocity threshold 3 / n_thresh 3
p2185[0...n]	Load monitoring torque threshold 1, upper / M_thresh 1 upper
p2185[0...n]	Load monitoring force threshold 1, upper / M_thresh 1 upper
p2186[0...n]	Load monitoring torque threshold 1, lower / M_thresh 1 lower
p2186[0...n]	Load monitoring force threshold 1, lower / M_thresh 1 lower
p2187[0...n]	Load monitoring torque threshold 2, upper / M_thresh 2 upper
p2187[0...n]	Load monitoring force threshold 2, upper / M_thresh 2 upper
p2188[0...n]	Load monitoring torque threshold 2, lower / M_thresh 2 lower
p2188[0...n]	Load monitoring force threshold 2, lower / M_thresh 2 lower
p2189[0...n]	Load monitoring torque threshold 3, upper / M_thresh 3 upper
p2189[0...n]	Load monitoring force threshold 3, upper / M_thresh 3 upper
p2190[0...n]	Load monitoring torque threshold 3, lower / M_thresh 3 lower
p2190[0...n]	Load monitoring force threshold 3, lower / M_thresh 3 lower
p2192[0...n]	Load monitoring, delay time / Load monit t_del
p2194[0...n]	Torque threshold value 2 / M_thresh val 2
p2195[0...n]	Torque utilization switch-off delay / M_util t_off
p2201[0...n]	CO: Technology controller, fixed value 1 / Tec_ctr fix val 1
p2202[0...n]	CO: Technology controller, fixed value 2 / Tec_ctr fix val 2
p2203[0...n]	CO: Technology controller, fixed value 3 / Tec_ctr fix val 3

p2204[0...n]	CO: Technology controller, fixed value 4 / Tec_ctr fix val 4
p2205[0...n]	CO: Technology controller, fixed value 5 / Tec_ctr fix val 5
p2206[0...n]	CO: Technology controller, fixed value 6 / Tec_ctr fix val 6
p2207[0...n]	CO: Technology controller, fixed value 7 / Tec_ctr fix val 7
p2208[0...n]	CO: Technology controller, fixed value 8 / Tec_ctr fix val 8
p2209[0...n]	CO: Technology controller, fixed value 9 / Tec_ctr fix val 9
p2210[0...n]	CO: Technology controller, fixed value 10 / Tec_ctr fix val 10
p2211[0...n]	CO: Technology controller, fixed value 11 / Tec_ctr fix val 11
p2212[0...n]	CO: Technology controller, fixed value 12 / Tec_ctr fix val 12
p2213[0...n]	CO: Technology controller, fixed value 13 / Tec_ctr fix val 13
p2214[0...n]	CO: Technology controller, fixed value 14 / Tec_ctr fix val 14
p2215[0...n]	CO: Technology controller, fixed value 15 / Tec_ctr fix val 15
p2230[0...n]	Technology controller motorized potentiometer configuration / Tec_ctr mop config
p2237[0...n]	Technology controller motorized potentiometer maximum value / Tec_ctr mop max
p2238[0...n]	Technology controller motorized potentiometer minimum value / Tec_ctr mop min
p2240[0...n]	Technology controller motorized potentiometer starting value / Tec_ctr mop start
p2247[0...n]	Technology controller motorized potentiometer ramp-up time / Tec_ctr mop t_r-up
p2248[0...n]	Technology controller motorized potentiometer ramp-down time / Tec_ctrMop t_rdown
p2502[0...n]	LR encoder assignment / Encoder assignment
p2503[0...n]	LR length unit LU per 10 mm / LU per 10 mm
p2504[0...n]	LR motor/load motor revolutions / Mot/load motor rev
p2505[0...n]	LR motor/load motor revolutions / Mot/load motor rev
p2506[0...n]	LR length unit LU per load revolution / LU per load rev
p2533[0...n]	LR position setpoint filter, time constant / s_set_filt T
p2534[0...n]	LR speed precontrol factor / n_prectrl fact
p2535[0...n]	LR speed precontrol symmetrizing filter deadtime / n_ffCtr flt t_dead
p2536[0...n]	LR speed precontrol, symmetrizing filter PT1 / n_prectrl flt PT1
p2538[0...n]	LR proportional gain / Kp
p2539[0...n]	LR integral time / Tn
p2546[0...n]	LR dynamic following error monitoring tolerance / s_delta_monit tol
p2900[0...n]	CO: Fixed value 1 [%] / Fixed value 1 [%]
p2901[0...n]	CO: Fixed value 2 [%] / Fixed value 2 [%]
p2930[0...n]	CO: Fixed value M [Nm] / Fixed value M [Nm]
p2930[0...n]	CO: Fixed value F [N] / Fixed value F [N]
p3201[0...n]	Excitation current outside the tolerance threshold value / I_exc n.Tol thresh
p3202[0...n]	Excitation current outside the tolerance hysteresis / I_exc n.Tol hyst
p3203[0...n]	Excitation current outside the tolerance delay time / I_exc n.Tol t_del
p3204[0...n]	Flux outside the tolerance threshold value / Flux n. tol thresh
p3205[0...n]	Flux outside the tolerance hysteresis / Flux n. tol hyst
p3206[0...n]	Flux outside tolerance delay time / Flux n. tol t_del
p3207[0...n]	Zero current signal, threshold value / I_0_sig thresh
p3208[0...n]	Zero current signal, hysteresis / I_0_sig hyst
p3209[0...n]	Zero current signal, delay time / I_0_sig t_del
p3704[0...n]	APC filter activation / APC filter activ.
p3705[0...n]	APC filter type / APC filter type
p3706[0...n]	APC sub-sampling, filter 2.x / APC sub-samp. 2.x
p3707[0...n]	APC sub-sampling, filter 3.x / APC sub-samp. 3.x
p3711[0...n]	APC filter 1.1 denominator natural frequency / APC Filt 1.1 fn_d
p3712[0...n]	APC filter 1.1 denominator damping / APC Filt 1.1 D_d
p3713[0...n]	APC filter 1.1 numerator natural frequency / APC Filt 1.1 fn_n
p3714[0...n]	APC filter 1.1 numerator damping / APC Filt 1.1 D_n
p3721[0...n]	APC filter 2.1 denominator natural frequency / APC Filt 2.1 fn_d
p3722[0...n]	APC filter 2.1 denominator damping / APC Filt 2.1 D_d

p3723[0...n]	APC filter 2.1 numerator natural frequency / APC Filt 2.1 fn_n
p3724[0...n]	APC filter 2.1 numerator damping / APC Filt 2.1 D_n
p3726[0...n]	APC filter 2.2 denominator natural frequency / APC Filt 2.2 fn_d
p3727[0...n]	APC filter 2.2 denominator damping / APC Filt 2.2 D_d
p3728[0...n]	APC filter 2.2 numerator natural frequency / APC Filt 2.2 fn_n
p3729[0...n]	APC filter 2.2 numerator damping / APC Filt 2.2 D_n
p3731[0...n]	APC filter 3.1 denominator natural frequency / APC Filt 2.1 fn_d
p3732[0...n]	APC filter 3.1 denominator damping / APC Filt 3.1 D_d
p3733[0...n]	APC filter 3.1 numerator natural frequency / APC Filt 2.1 fn_n
p3734[0...n]	APC filter 3.1 numerator damping / APC Filt 3.1 D_n
p3736[0...n]	APC filter 3.2 denominator natural frequency / APC Filt 3.2 fn_d
p3737[0...n]	APC filter 3.2 denominator damping / APC Filt 3.2 D_d
p3738[0...n]	APC filter 3.2 numerator natural frequency / APC Filt 3.2 fn_n
p3739[0...n]	APC filter 3.2 numerator damping / APC Filt 3.2 D_n
p3760[0...n]	APC load speed controller 1 P gain / APC n_load ctr1 Kp
p3760[0...n]	APC load velocity controller 1 P gain / APC v_load ctr1 Kp
p3761[0...n]	APC load speed controller 1 rate time / APC n_load ctr1 Tv
p3761[0...n]	APC load velocity controller 1 rate time / APC v_load ctr1 Tv
p3765[0...n]	APC load speed controller 2 P gain / APC n_load ctr2 Kp
p3765[0...n]	APC load velocity controller 2 P gain / APC v_load ctr2 Kp
p3766[0...n]	APC load speed controller 2 rate time / APC n_load ctr2 Tv
p3766[0...n]	APC load velocity controller 2 rate time / APC v_load ctr2 Tv
p3800[0...n]	Sync line-drive activation / Sync activ.
p3801[0...n]	Sync line-drive, drive object number / Sync DO_No.
p3806[0...n]	Sync line-drive frequency difference threshold value / Sync f_diff thresh
p3809[0...n]	Sync line-drive phase setpoint / Sync phase setp
p3811[0...n]	Sync line-drive frequency limiting / Sync f_lim
p3813[0...n]	Sync line-drive phase synchronism threshold value / Sync Ph_sync thrsh
p3815[0...n]	Sync line-drive voltage difference threshold value / Sync U_diff thresh
p3820[0...n]	Friction characteristic, value n0 / Friction n0
p3820[0...n]	Friction characteristic, value v0 / Friction v0
p3821[0...n]	Friction characteristic, value n1 / Friction n1
p3821[0...n]	Friction characteristic, value v1 / Friction v1
p3822[0...n]	Friction characteristic, value n2 / Friction n2
p3822[0...n]	Friction characteristic, value v2 / Friction v2
p3823[0...n]	Friction characteristic, value n3 / Friction n3
p3823[0...n]	Friction characteristic, value v3 / Friction v3
p3824[0...n]	Friction characteristic, value n4 / Friction n4
p3824[0...n]	Friction characteristic, value v4 / Friction v4
p3825[0...n]	Friction characteristic, value n5 / Friction n5
p3825[0...n]	Friction characteristic, value v5 / Friction v5
p3826[0...n]	Friction characteristic, value n6 / Friction n6
p3826[0...n]	Friction characteristic, value v6 / Friction v6
p3827[0...n]	Friction characteristic, value n7 / Friction n7
p3827[0...n]	Friction characteristic, value v7 / Friction v7
p3828[0...n]	Friction characteristic, value n8 / Friction n8
p3828[0...n]	Friction characteristic, value v8 / Friction v8
p3829[0...n]	Friction characteristic, value n9 / Friction n9
p3829[0...n]	Friction characteristic, value v9 / Friction v9
p3830[0...n]	Friction characteristic, value M0 / Friction M0
p3830[0...n]	Friction characteristic, value F0 / Friction F0
p3831[0...n]	Friction characteristic, value M1 / Friction M1
p3831[0...n]	Friction characteristic, value F1 / Friction F1

p3832[0...n]	Friction characteristic, value M2 / Friction M2
p3832[0...n]	Friction characteristic, value F2 / Friction F2
p3833[0...n]	Friction characteristic, value M3 / Friction M3
p3833[0...n]	Friction characteristic, value F3 / Friction F3
p3834[0...n]	Friction characteristic, value M4 / Friction M4
p3834[0...n]	Friction characteristic, value F4 / Friction F4
p3835[0...n]	Friction characteristic, value M5 / Friction M5
p3835[0...n]	Friction characteristic, value F5 / Friction F5
p3836[0...n]	Friction characteristic, value M6 / Friction M6
p3836[0...n]	Friction characteristic, value F6 / Friction F6
p3837[0...n]	Friction characteristic, value M7 / Friction M7
p3837[0...n]	Friction characteristic, value F7 / Friction F7
p3838[0...n]	Friction characteristic, value M8 / Friction M8
p3838[0...n]	Friction characteristic, value F8 / Friction F8
p3839[0...n]	Friction characteristic, value M9 / Friction M9
p3839[0...n]	Friction characteristic, value F9 / Friction F9
p3846[0...n]	Friction characteristic plot ramp-up/ramp-down time / Fric plot t_RFG
p3847[0...n]	Friction characteristic plot warm-up time / Frict plot t_warm
r3925[0...n]	Identification final display / Ident final_disp
r3927[0...n]	Motor data identification control word / MotID STW
r3928[0...n]	Rotating measurement configuration / Rot meas config
p7035[0...n]	Par_circuit circulating current control, operating mode / Circ_I mode
p7036[0...n]	Par_circuit circulating current control, proportional gain / Circ_I Kp
p7037[0...n]	Par_circuit circulating current control, integral time / Circ_I TN
p7038[0...n]	Par_circuit circulating current control, limit / Circ_I limit

1.3.3 Parameters for encoder data sets (EDS)

Note:

References: /IH1/ SINAMICS S120 Installation and Start-Up Manual
"Data sets" section

The following list contains the encoder-data-set-dependent parameters.

Product: SINAMICS S, Version: 2402300, Label: ., Language: eng

p0141[0...n]	Encoder interface (Sensor Module) component number / Enc_interf comp_no
p0142[0...n]	Encoder component number / Encoder comp_no
p0144[0...n]	Sensor Module detection via LED / SM detection LED
p0145[0...n]	Activate/de-activate encoder interface / Enc_intf act/deact
r0146[0...n]	Encoder interface active/inactive / Enc_intf act/inact
r0147[0...n]	Sensor Module EPROM data version / SM EEPROM version
r0148[0...n]	Sensor Module firmware version / SM FW_version
p0400[0...n]	Enc type selection / Enc type selection
p0401[0...n]	Encoder type, OEM selection / Enc type OEM sel
p0402[0...n]	Gearbox type selection / Gearbox type
p0404[0...n]	Encoder configuration effective / Enc_config eff
p0405[0...n]	Square-wave encoder track A/B / Sq-wave enc A/B
p0407[0...n]	Linear encoder grid division / Enc grid div
p0408[0...n]	Rotary encoder pulse No. / Rot enc pulse No.
p0410[0...n]	Encoder inversion actual value / Enc inv act value
p0411[0...n]	Measuring gearbox, configuration / Config
p0413[0...n]	Measuring gearbox, position tracking tolerance window / Pos track window
p0418[0...n]	Fine resolution Gx_XIST1 (in bits) / Enc fine Gx_XIST1
p0419[0...n]	Fine resolution absolute value Gx_XIST2 (in bits) / Enc fine Gx_XIST2
p0420[0...n]	Encoder connection / Encoder connection
p0421[0...n]	Absolute encoder rotary multi-turn resolution / Enc abs multiturn
p0422[0...n]	Absolute encoder linear measuring step resolution / Enc abs meas step
p0423[0...n]	Absolute encoder rotary single-turn resolution / Enc abs singleturn
p0424[0...n]	Encoder, linear zero mark distance / Enc lin ZM_dist
p0425[0...n]	Encoder, rotary zero mark distance / Enc rot dist ZM
p0427[0...n]	Encoder SSI baud rate / Enc SSI baud rate
p0428[0...n]	Encoder SSI monoflop time / Enc SSI t_monoflop
p0429[0...n]	Encoder SSI configuration / Enc SSI config
p0430[0...n]	Sensor Module configuration / SM config
p0431[0...n]	Angular commutation offset / Ang_com offset
p0432[0...n]	Gearbox factor, encoder revolutions / Grbx_fact enc_rev
p0433[0...n]	Gearbox factor, motor/load revolutions / Grbx_fact mot_rev
p0434[0...n]	Encoder SSI error bit / Enc SSI error bit
p0435[0...n]	Encoder SSI alarm bit / Enc SSI alarm bit
p0436[0...n]	Encoder SSI parity bit / Enc SSI parity bit
p0440[0...n]	Copy encoder serial number / Copy enc ser_no
p0441[0...n]	Encoder commissioning serial number part 1 / Enc comm ser_no 1
p0442[0...n]	Encoder commissioning serial number part 2 / Enc comm ser_no 2
p0443[0...n]	Encoder commissioning serial number part 3 / Enc comm ser_no 3
p0444[0...n]	Encoder commissioning serial number part 4 / Enc comm ser_no 4
p0445[0...n]	Encoder commissioning serial number part 5 / Enc comm ser_no 5
p0446[0...n]	Encoder SSI number of bits before the absolute value / Enc SSI bit before

p0447[0...n]	Encoder SSI number of bits absolute value / Enc SSI bit val
p0448[0...n]	Encoder SSI number of bits after the absolute value / Enc SSI bit after
p0449[0...n]	Encoder SSI number of bits, filler bits / Enc SSI fill bits
p2507[0...n]	LR absolute encoder adjustment status / Abs_enc_adj stat
p2525[0...n]	CO: LR encoder adjustment, offset / Enc_adj offset
p4600[0...n]	SME motor temperature sensor 1 sensor type / MotTemp_sens typ 1
p4601[0...n]	SME motor temperature sensor 2 sensor type / MotTemp_sens typ 2
p4602[0...n]	SME motor temperature sensor 3 sensor type / MotTemp_sens typ 3
p4603[0...n]	SME motor temperature sensor 4 sensor type / MotTemp_sens typ 4

1.3.4 Parameters for motor data sets (MDS)

Note:

References: /IH1/ SINAMICS S120 Installation and Start-Up Manual
"Data sets" section

The following list contains the motor-data-set-dependent parameters.

Product: SINAMICS S, Version: 2402300, Label: ., Language: eng

p0131[0...n]	Motor component number / Mot comp_no
p0300[0...n]	Mot type selection / Mot type selection
p0300[0...n]	Mot type selection / Mot type selection
p0301[0...n]	Motor code number selection / Mot code No. sel
p0301[0...n]	Motor code number selection / Mot code No. sel
r0302[0...n]	Motor code number of motor with DRIVE-CLiQ / Motor code Mot DLQ
p0304[0...n]	Rated motor voltage / Mot U_rated
p0305[0...n]	Rated motor current / Mot I_rated
p0306[0...n]	Number of motors connected in parallel / Motor qty
p0307[0...n]	Rated motor power / Mot P_rated
p0307[0...n]	Rated motor power / Mot P_rated
p0308[0...n]	Rated motor power factor / Mot cos_phi_rated
p0309[0...n]	Rated motor efficiency / Mot eta_rated
p0310[0...n]	Rated motor frequency / Mot f_rated
p0311[0...n]	Rated motor speed / Mot n_rated
p0311[0...n]	Rated motor velocity / Mot v_rated
p0312[0...n]	Rated motor torque / Mot M_rated
p0312[0...n]	Rated motor force / Mot F_rated
r0313[0...n]	Motor pole pair number, actual (or calculated) / Mot PolePairNo act
r0313[0...n]	Motor pole pair number, actual (or calculated) / Mot PolePairNo act
p0314[0...n]	Motor pole pair number / Mot pole pair No.
p0315[0...n]	Motor pole pair width / MotPolePair width
p0316[0...n]	Motor torque constant / Mot kT
p0316[0...n]	Motor force constant / Mot kT
p0316[0...n]	Motor torque constant / Mot kT
p0317[0...n]	Motor voltage constant / Mot kE
p0317[0...n]	Motor voltage constant / Mot kE
p0318[0...n]	Motor stall current / Mot I_standstill
p0319[0...n]	Motor stall torque / Mot M_standstill
p0319[0...n]	Motor stall force / Mot F_standstill
p0320[0...n]	Motor rated magnetization current/short-circuit current / Mot I_mag_rated
p0322[0...n]	Maximum motor speed / Mot n_max
p0322[0...n]	Motor maximum velocity / Mot v_max
p0323[0...n]	Maximum motor current / Mot I_max
p0325[0...n]	Motor pole position identification current, 1st phase / Mot PolID I 1st ph
p0326[0...n]	Motor stall torque correction factor / Mot M_stallCorrFac
p0327[0...n]	Optimum motor load angle / Mot phi_load opt
p0328[0...n]	Motor reluctance torque constant / Mot kT_reluctance
p0329[0...n]	Motor pole position identification current / Mot PolID current
r0330[0...n]	Rated motor slip / Mot slip_rated
r0331[0...n]	Motor magnetizing current/short-circuit current actual / Mot I_mag_ratedAct
r0332[0...n]	Rated motor power factor / Mot cos_phi_rated

r0333[0...n]	Rated motor torque / Mot M _{rated}
r0333[0...n]	Rated motor force / Mot F _{rated}
r0334[0...n]	Motor-torque constant, actual / Mot kT act
r0334[0...n]	Motor force constant, actual / Mot kT act
p0335[0...n]	Motor cooling type / Motor cooling type
r0336[0...n]	Rated motor frequency actual / Mot f _{rated} act
r0337[0...n]	Rated motor EMF / Mot EMF _{rated}
r0337[0...n]	Rated motor EMF / Mot EMF _{rated}
p0338[0...n]	Motor limit current / Mot I _{limit}
r0339[0...n]	Rated motor voltage / Mot U _{rated}
p0341[0...n]	Motor moment of inertia / Mot M _{mom} of inert
p0341[0...n]	Motor weight / Mot weight
p0342[0...n]	Ratio between the total and motor moment of inertia / Mot MomInert Ratio
p0344[0...n]	Motor weight / Motor weight
r0345[0...n]	Nominal motor starting time / Mot t _{start} _{rated}
p0346[0...n]	Motor excitation build-up time / Mot t _{excitation}
p0347[0...n]	Motor de-excitation time / Mot t _{de-excitat.}
p0348[0...n]	Speed at the start of field weakening V _{dc} = 600 V / Mot n _{field} weaken
p0348[0...n]	Velocity at the start of field weakening V _{dc} = 600 V / Mot v _{field} weaken
p0350[0...n]	Motor stator resistance, cold / Mot R _{stator} cold
p0352[0...n]	Cable resistance / Mot R _{cable} cold
p0353[0...n]	Motor series inductance / Mot L _{series}
p0354[0...n]	Motor rotor resistance cold / damping resistance d axis / Mot R _r cold / RDd
p0355[0...n]	Motor damping resistance, q axis / Mot R _{damping} _q
p0356[0...n]	Motor stator leakage inductance / Mot L _{stator} leak.
p0356[0...n]	Motor stator leakage inductance / Mot L _{stator} leak.
p0357[0...n]	Motor stator inductance, d axis / Mot L _{stator} _d
p0358[0...n]	Motor rotor leakage inductance / damping inductance, d axis / Mot L _r leak / LDd
p0359[0...n]	Motor damping inductance, q axis / Mot L _{damping} _q
p0360[0...n]	Motor magnetizing inductance/magn. inductance, d axis saturated / Mot L _h /L _h d sat
p0361[0...n]	Motor magnetizing inductance, q axis, saturated / Mot L _h q _{sat}
p0362[0...n]	Saturation characteristic flux 1 / Mot saturat.flux 1
p0363[0...n]	Saturation characteristic flux 2 / Mot saturat.flux 2
p0364[0...n]	Saturation characteristic flux 3 / Mot saturat.flux 3
p0365[0...n]	Saturation characteristic flux 4 / Mot saturat.flux 4
p0366[0...n]	Saturation characteristic I _{mag} 1 / Mot sat. I _{mag} 1
p0367[0...n]	Saturation characteristic I _{mag} 2 / Mot sat. I _{mag} 2
p0368[0...n]	Saturation characteristic I _{mag} 3 / Mot sat. I _{mag} 3
p0369[0...n]	Saturation characteristic I _{mag} 4 / Mot sat. I _{mag} 4
r0370[0...n]	Motor stator resistance, cold / Mot R _{stator} cold
r0372[0...n]	Cable resistance / Mot R _{cable}
r0373[0...n]	Motor rated stator resistance / Mot R _{stator} rated
r0374[0...n]	Motor rotor resistance cold / damping resistance d axis / Mot R _r cold / RDd
r0375[0...n]	Motor damping resistance, q axis / Mot R _{damping} _q
r0376[0...n]	Rated motor rotor resistance / Mot R _{rotor} rated
r0377[0...n]	Motor leakage inductance, total / Mot L _{leak} total
r0378[0...n]	Motor stator inductance, d axis / Mot L _{stator} _d
r0380[0...n]	Motor damping inductance, d axis / Mot L _{damping} _d
r0381[0...n]	Motor damping inductance, q axis / Mot L _{damping} _q
r0382[0...n]	Motor magnetizing inductance transformed / L _h d axis saturated / Mot L _h t. / L _h d _s
r0383[0...n]	Motor magnetizing inductance q axis, saturated / Mot L _h q _{sat}
r0384[0...n]	Motor rotor time constant / damping time constant d axis / Mot T _{rot} / T _{DD}
r0385[0...n]	Motor damping time constant, q axis / Mot T _{Dq}

r0386[0...n]	Motor stator leakage time constant / Mot T_stator leak
r0387[0...n]	Motor stator leakage time constant, q axis / Mot T_Sleak / T_Sq
p0389[0...n]	Motor no-load excitation current / Mot I_exc_no-load
p0390[0...n]	Motor rated excitation current / Mot I_exc_rated
p0391[0...n]	Current controller adaptation, lower starting point / I_adapt pt. lower
p0392[0...n]	Current controller adaptation, upper starting point / I_adapt pt. upper
p0393[0...n]	Current controller adaptation, P gain, scaling upper / I_adapt Kp upper
r0395[0...n]	Stator resistance, actual / R_stator active
r0396[0...n]	Rotor resistance, actual / R_rotor active
p0600[0...n]	Motor temperature sensor for monitoring / Mot temp_sensor
p0600[0...n]	Motor temperature sensor for monitoring / Mot temp_sensor
p0601[0...n]	Motor temperature sensor type / Mot temp_sensortyp
p0604[0...n]	Motor overtemperature alarm threshold / Mot TempAlrmThresh
p0604[0...n]	Motor overtemperature alarm threshold / Mot TempAlrmThresh
p0605[0...n]	Motor overtemperature fault threshold / MotTempFaultThresh
p0606[0...n]	Motor overtemperature timer / Mot TempTimeStage
p0606[0...n]	Motor overtemperature timer / Mot TempTimeStage
p0607[0...n]	Temperature sensor fault timer / Sensor fault time
p0610[0...n]	Response to motor overtemperature condition / Mot temp response
p0620[0...n]	Thermal adaptation, stator and rotor resistance / Mot therm_adapt R
p0620[0...n]	Thermal adaptation, stator and rotor resistance / Mot therm_adapt R
p0621[0...n]	Temperature identification after restart / Temp_ident restart
p0622[0...n]	Motor excitation time for temp_ident after powering-up again / t_excit temp_id
p0625[0...n]	Motor ambient temperature / Mot T_ambient
p0626[0...n]	Motor overtemperature, stator core / Mot T_over core
p0627[0...n]	Motor overtemperature, stator winding / Mot T_over stator
p0628[0...n]	Rotor winding overtemperature / Mot T_over rotor
r0630[0...n]	Motor temperature model ambient temperature / MotTMod T_amb.
r0631[0...n]	Motor temperature model, stator core temperature / MotTMod T_iron
r0632[0...n]	Motor temperature model, stator winding temperature / MotTMod T_copper
r0633[0...n]	Motor temperature model, rotor temperature / MotTMod T_rotor
p0643[0...n]	Overvoltage protection for synchronous motors / Overvolt_protect
p0650[0...n]	Actual motor operating hours / Mot t_oper act
p0651[0...n]	Motor operating hours maintenance interval / Mot t_op maint
p0652[0...n]	Motor stator resistance, scaling / Mot R_stator scal
p0653[0...n]	Motor stator leakage inductance, scaling / Mot L_S_leak scal
p0655[0...n]	Motor magnetizing inductance, d axis, saturated scaling / Mot Lhd_sat scal
p0656[0...n]	Motor magnetizing inductance, q axis, saturated scaling / Mot Lhq_sat scal
p0657[0...n]	Motor damping inductance, d axis scaling / Mot L_damp_d scal
p0658[0...n]	Motor damping inductance, q axis scaling / Mot L_damp_q scal
p0659[0...n]	Motor damping resistance, d axis scaling / Mot R_damp_d scal
p0660[0...n]	Motor damping resistance, q axis scaling / Mot R_damp_q scal
p0826[0...n]	Motor changeover, motor number / Mot_chng mot No.
p0827[0...n]	Motor changeover status word bit number / Mot_chg ZSW bitNo.
p1231[0...n]	Configuration, armature short-circuit / ASC config
p1236[0...n]	Ext. armature short-cct., contactor feedback signal monit. time / ASC ext t_monit
p1237[0...n]	External armature short-circuit, waiting time when opening / ASC ext t_wait
p1909[0...n]	Motor data identification control word / MotID STW
p1909[0...n]	Motor data identification control word / MotID STW
p1909[0...n]	Motor data identification control word / MotID STW
p1958[0...n]	Motor data identification ramp-up/ramp-down time / MotID t_up_down
p1959[0...n]	Rotating measurement configuration / Rot meas config
p1980[0...n]	Pole position identification technique / PolID technique

p1980[0...n]	Pole position identification technique / PolID technique
p1981[0...n]	Pole position identification maximum distance / PolID distance max
p1982[0...n]	Pole position identification selection / PolID selection
p1982[0...n]	Pole position identification selection / PolID selection
p1991[0...n]	Motor changeover, angular commutation correction / Ang_com corr
p1993[0...n]	Pole position identification current, motion-based / PolID I mot_bas
p1994[0...n]	Pole position identification rise time, motion-based / PolID T mot_bas
p1995[0...n]	Pole position identification gain, motion-based / PolID kp mot_bas
p1995[0...n]	Pole position identification gain, motion-based / PolID kp mot_bas
p1996[0...n]	Pole position identification, integral time, motion-based / PolID Tn mot_bas
p1997[0...n]	Pole position identification, smoothing time, motion-based / PolID t_sm mot_bas
p1999[0...n]	Ang. commutation offset calibr. and pole position ID - scaling / ComOffsCalib scal

1.3.5 Parameters for Power unit Data Sets (PDS)

Note:

References: /IH1/ SINAMICS S120 Installation and Start-Up Manual
"Data sets" section

The following list contains the parameters that are dependent on the Power unit Data Sets.

Product: SINAMICS S, Version: 2402300, Label: ., Language: eng

p0121[0...n]	Power unit component number / LT comp_no
p0124[0...n]	Power unit detection via LED / LT detection LED
p0125[0...n]	Activate/de-activate power unit components / LT_comp act/de-act
r0126[0...n]	Power unit components active/inactive / LT comp act/inact
r0127[0...n]	Power unit version EPROM data / LT EPROM version
r0128[0...n]	Power unit firmware version / LT FW_version
r0200[0...n]	Power unit, actual code number / LT code no. actual
p0201[0...n]	Power unit code number / LT code number
r0203[0...n]	Actual power unit type / LT actual type
r0204[0...n]	Power unit hardware properties / LT HW property
p0251[0...n]	Operating hours counter, power unit fan / LT fan t_oper
p0895[0...n]	BI: Activate/de-activate power unit components / LT_comp act/de-act
p3469[0...n]	Latch delay time correction, zero crossover detection / t_latch corr PLL
p3902[0...n]	Power unit EEPROM Vdc calibration / LT EEPROM Vdc_cal
p7001[0...n]	Par_circuit enable power units / Enable LT
r7002[0...n]	Par_circuit status power units / Status LT
r7020[0...n]	CO: Par_circuit deviation current in phase U / Phase U curr dev
r7021[0...n]	CO: Par_circuit deviation current in phase V / Phase V curr dev
r7022[0...n]	CO: Par_circuit deviation current in phase W / Phase W curr dev
r7030[0...n]	CO: Par_circuit DC link voltage deviation / Vdc deviation
p7040[0...n]	Par_circuit correction, valve lockout time phase U / Comp t_lockout U
p7042[0...n]	Par_circuit correction, valve lockout time phase V / Comp t_lockout V
p7044[0...n]	Par_circuit correction, valve lockout time phase W / Comp t_lockout W
r7050[0...n]	Par_circuit circulating current phase U / Circ_I_phase U
r7051[0...n]	Par_circuit circulating current phase V / Circ_I_phase V
r7052[0...n]	Par_circuit circulating current phase W / Circ_I_phase W
r7200[0...n]	Par_circuit power unit overload I2T / LT overload I2T
r7201[0...n]	Par_circuit power unit temperatures max. inverter / LT temp max inv
r7202[0...n]	Par_circuit power unit temperatures max. depletion layer / LT TempMaxDepLayer
r7203[0...n]	Par_circuit power unit temperatures max. rectifier / LT temp max rect
r7204[0...n]	Par_circuit power unit temperatures air intake / LT temp air intake
r7205[0...n]	Par_circuit power unit temperatures electronics / LT temp electr
r7206[0...n]	Par_circuit power unit temperatures inverter 1 / LT temp inv 1
r7207[0...n]	Par_circuit power unit temperatures inverter 2 / LT temp inv 2
r7208[0...n]	Par_circuit power unit temperatures inverter 3 / LT temp inv 3
r7209[0...n]	Par_circuit power unit temperatures inverter 4 / LT temp inv 4
r7210[0...n]	Par_circuit power unit temperatures inverter 5 / LT temp inv 5
r7211[0...n]	Par_circuit power unit temperatures inverter 6 / LT temp inv 6
r7212[0...n]	Par_circuit power unit temperatures inverter 1 / LT temp rect 1
r7213[0...n]	Par_circuit power unit temperatures inverter 2 / LT temp rect 2
r7214[0...n]	Par_circuit power unit temperatures depletion layer 1 / LT temp DepLayer 1
r7215[0...n]	Par_circuit power unit temperatures depletion layer 2 / LT temp DepLayer 2

r7216[0...n]	Par_circuit power unit temperatures depletion layer 3 / LT temp DepLayer 3
r7217[0...n]	Par_circuit power unit temperatures depletion layer 4 / LT temp DepLayer 4
r7218[0...n]	Par_circuit power unit temperatures depletion layer 5 / LT temp DepLayer 5
r7219[0...n]	Par_circuit power unit temperatures depletion layer 6 / LT temp DepLayer 6
r7220[0...n]	Infeed par_circuit absolute current value, motoring permissible / INF I_abs mot perm
r7220[0...n]	CO: Par_circuit drive output current, maximum / Drv I_output max
r7221[0...n]	Infeed par_circuit absolute current regenerating, permissible / INF I_absRegenPerm
r7222[0...n]	CO: Par_circuit absolute current actual value / I_act abs.val.
r7223[0...n]	CO: Par_circuit phase current, actual value phase U / I_phase U act val
r7224[0...n]	CO: Par_circuit phase current, actual value phase V / I_phase V act val
r7225[0...n]	CO: Par_circuit phase current, actual value phase W / I_phase W act val
r7226[0...n]	CO: Par_circuit phase current actual value, phase U offset / I_phase U offset
r7227[0...n]	CO: Par_circuit phase current, actual value, phase V offset / I_phase V offset
r7228[0...n]	CO: Par_circuit phase current, actual value, phase W offset / I_phase W offset
r7229[0...n]	CO: Par_circuit phase current actual value sum U, V, W / I_phase sum UVW
r7230[0...n]	CO: Par_circuit DC link voltage actual value / Vdc_act
r7231[0...n]	CO: Par_circuit phase voltage, actual value phase U / U_phase U act val
r7232[0...n]	CO: Par_circuit phase voltage, actual value phase V / U_phase V act val
r7233[0...n]	CO: Par_circuit phase voltage, actual value phase W / U_phase W act val

Function diagrams

2

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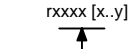
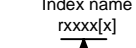
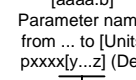
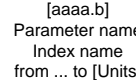
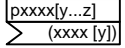
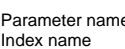
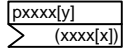
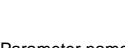
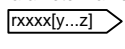

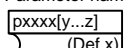
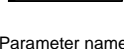
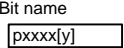
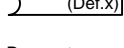
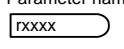

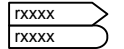
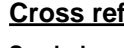
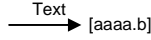
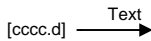






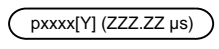
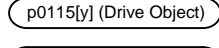
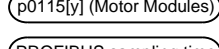
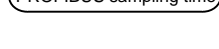
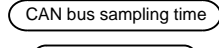
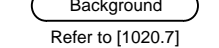
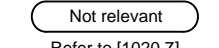
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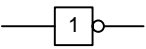
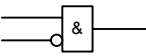
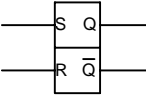
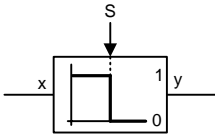
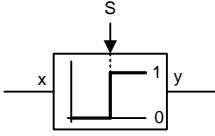
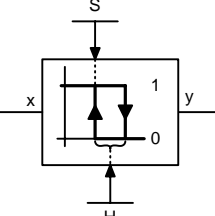
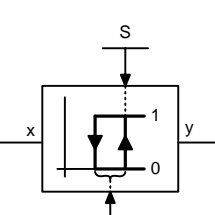
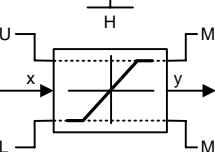
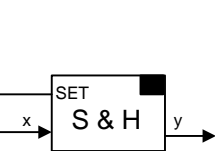

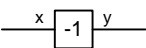
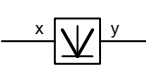
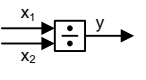
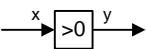
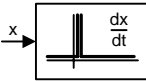
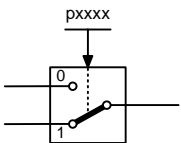
2.2 Explanations for the function diagrams

Function diagrams

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Figure 2-1 1020 – Explanation of the symbols (part 1)

<p>Parameter</p> <p>Symbol Meaning</p> <p>Parameter name [Units] Monitoring parameter (parameter may appear multiple times).  Parameter name [Units] Monitoring parameter with index (parameter may appear multiple times).  [aaaa.b] Parameter name from ... to [Units] pxxx[y...z] (Def) Setting parameter (if the parameter appears a multiple number of times, then diagram references are specified).  [aaaa.b] Parameter name from ... to [Units] pxxx[y] (Def) Setting parameter with index (if the parameter appears a multiple number of times, then diagram references are specified). </p>	<p>Connectors</p> <p>Symbol Meaning</p> <p>Parameter name   Parameter name Index name   Parameter name [Units] Connector output CO with [dimension units] and index range [y...z] (the parameter may appear multiple times).  Parameter name [Units] Connector output CO [dimension units] and with index [y] (the parameter may appear multiple times). </p>	<p>Binectors</p> <p>Symbol Meaning</p> <p>Parameter name   Parameter name Bit name   Parameter name Binector output BO (the parameter may appear multiple times).  Parameter name Binector output BO with bit yy (the parameter may appear multiple times). </p>	<p>Connectors/binectors</p> <p>Symbol Meaning</p> <p>Parameter name   Cross references between diagrams</p> <p>Symbol Meaning</p> <p>Signal path   To "function diagram name" [aaaa.b] = for binectors. Important: No cross-reference to the main diagrams or that go to or from overview diagrams.</p> <p>Cross references for control bits</p> <p>Symbol Meaning</p> <p> [aaaa.b] pxxx= Original parameter of signal aaaa = Signal comes from the source diagram aaaa b = Signal comes from signal path b</p>				
<p>Data sets</p> <p>Symbol Meaning</p> <p>pxxx[C]  Parameter belongs to the Command Data Set (CDS). pxxx[D]  Parameter belongs to the Drive Data Set (DDS). pxxx[E]  Parameter belongs to the Encoder Data Set (EDS). pxxx[M]  Parameter belongs to the Motor Data Set (MDS). pxxx[P]  Parameter belongs to the Power unit Data Set (PDS).</p>	<p>Information on parameters, binectors, connectors</p> <p>Symbol Meaning</p> <p>Parameter name Parameter name (max. 18 characters)</p> <p>[Units] [dimension units]</p> <p>rxxx[y] or rxxx[y...z] } "r" = monitoring parameter. These parameters are read-only rxxx.yy[y] } "xxxx" stands for a four-digit parameter number rxxx.yy } "[y]" specifies the valid index, "[y...z]" specifies the applicable index range "yy" specifies the bit number (e.g. 0...15).</p> <p>pxxx[y] or pxxx[y...z] } "p" = setting parameter. These parameters can be changed. pxxx.yy[y] } "xxxx" stands for a four-digit parameter number, pxxx.yy } "[y]" specifies the applicable index, "[y...z]" specifies the applicable index range pxxx.yy } ".yy" specifies the bit number (e.g. 0...15).</p> <p>from ... to Value range</p> <p>(xxx[y]) Parameter number (xxxx) and Index number [y].</p> <p>(Def) Factory setting.</p> <p>(Def.w) Factory setting with bit number as prefix.</p> <p>[aaaa.b] Diagram references for setting parameters that occur a multiple number of times. [Function diagram number, signal path]</p>	<p>Sampling times</p> <p>Symbol Meaning</p> <p> Setting parameter with factory setting to select the time slice.  Time slice depending on the pre-setting p0112 of the drive object.  Time slide depending on the rated pulse frequency of the motor module.  a) If clock-cycle synchronous, then bus cycle time alias DP cycle (Tdp). b) Otherwise 4000.00 μs.  Time slice 4000.00 μs.  Refer to [1020.7] There is no fixed sampling time for this function. The processing is made in the background. The cycle time depends on the computational load of the control unit.  Refer to [1020.7] A static state is displayed here. The sampling time data is not relevant.</p>					
1	2	3	4	5	6	7	8
DO: All objects					fp_1020_01_eng.vsd	Function diagram	
General - explanation of the symbols (part 1)					20.09.05 V02.04.00	SINAMICS S	

<p>Pre-assigned binectors and connectors Fixed percentage values</p> <p>-10 000.00...10 000.00 % p2900[D] (0.00) → Fixed value 1 [%] p2900[D]</p> <p>-10 000.00...10 000.00 % p2901[D] (0.00) → Fixed value 2 [%] p2901[D]</p>	<p>Symbols for logic functions</p> <p> Logical inversion</p> <p> AND element with logical inversion of an input signal</p> <p> R/S flip-flop S = setting input R = reset input Q = non-inverted output Q̄ = inverted output</p>	<p>Symbols for computational and closed-loop control functions</p> <p> Threshold value switch 1 / 0 Outputs at y a logical "1" if x < S.</p> <p> Threshold value switch 0 / 1 Outputs at y a logical "1" if x > S.</p> <p> Threshold value 1 / 0 with hysteresis Outputs a logical "1" at y if x < S. If x >= S + H then y returns to 0.</p> <p> Threshold value 0 / 1 with hysteresis Outputs a logical "1" at y if x > S. If x >= S + H then y returns to 0.</p> <p> Limiter x is limited to the upper limit LU and the lower limit LL and output at y. The digital signals MLU and MLL have the value "1", if the upper or lower limit is active.</p> <p> Sample & Hold element Sample and hold element. y = x if SET = 1 (this is not retentively saved at POWER OFF)</p>
<p>Pre-assigned binectors and connectors Fixed speed values</p> <p>-210 000.000...210 000.000 RPM pxxx[D] (0.000) → Fixed value 1 [n] pxxx[D]</p> <p>-210 000.000...210 000.000 RPM pxx21[D] (0.000) → Fixed value 2 [n] pxxx[D]</p>	<p>Symbol for monitoring</p> <p> Monitoring Axxxx or Fxxxx Located at the lower right in the sheet.</p>	
<p>Pre-assigned binectors and connectors Fixed torque values</p> <p>-100 000.00...100 000.00 Nm p2930[D] (0.00) → Fixed value M [Nm] p2930[D]</p>	<p>Symbols for computational and closed-loop control functions</p> <p> Sign reversal y = -x</p> <p> Absolute value generator y = x </p> <p> Divider $y = \frac{x_1}{x_2}$</p> <p> Comparator Output y = a logical "1", if the analog signal x > 0, i.e. is positive.</p> <p> Differentiator $y = \frac{dx}{dt}$</p>	
<p>Switch symbol</p> <p> Simple changeover switch The switch position is shown acc. to the factory setting. (In this case, switch position 1 in the state when supplied.)</p>		

1	2	3	4	5	6	7	8
DO: All objects					fp_1021_01_eng.vsd	Function diagram	
General - explanation of the symbols (part 2)					02.09.05 V02.04.00	SINAMICS S	
							- 1021 -

Figure 2-2 1021 – Explanation of the symbols (part 2)

Figure 2-3 1024 – Explanation of the symbols (part 3)

Switch-on delay

The digital signal x must have the value "1" without any interruption during time T before output y changes to "1".

Switch-out delay

The digital signal x must have the value "0" without interruption during time T before output y changes to "1".

Delay (switch-in and switch-out)

The digital signal x must have the value "1" without interruption during time T1 or must have the value "0" during time T2 before output y changes its signal state.

PT1 element

Delay element, first Order.
pxxxx = time constant

PT2 lowpass

Natural frequency, denominator: $\frac{fn_n}{pxxxx}$
Damping, denominator: $\frac{D_n}{pxxxx}$

Transfer function

$$H(s) = \frac{1}{\left(\frac{s}{2\pi fn_n}\right)^2 + \frac{2 \cdot D_n}{2\pi fn_n} \cdot s + 1}$$

2nd Order filter (bandstop/general filter)

Natural frequency, numerator: $\frac{fn_z}{pxxxx}$
Damping, numerator: $\frac{D_z}{pxxxx}$
Natural frequency, denominator: $\frac{fn_n}{pxxxx}$
Damping, denominator: $\frac{D_n}{pxxxx}$

Used as bandstop filter

- center frequency fs: $fn_z = fs$
 $fn_n = fs$
- bandwidth f_B: $D_z = 0$
 $D_n = \frac{f_B}{2 \cdot fs}$

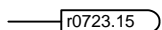
Transfer function when used as general filter

$$H(s) = \frac{\left(\frac{s}{2\pi fn_z}\right)^2 + \frac{2 \cdot D_z}{2\pi fn_z} \cdot s + 1}{\left(\frac{s}{2\pi fn_n}\right)^2 + \frac{2 \cdot D_n}{2\pi fn_n} \cdot s + 1}$$

1	2	3	4	5	6	7	8
DO: All objects					fp_1024_01_eng.vsd	Function diagram	
General - explanation of the symbols (part 3)					30.03.05 V02.04.00	SINAMICS S	

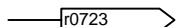
Handling BICO technology

Binector:



Binectors are binary signals that can be freely interconnected (BO = Binector Output). They represent a bit of a "BO:" display parameter (e.g. bit 15 from r0723).

Connector:



Connectors are "analog signals" that can be freely interconnected (e.g. percentage quantities, speeds or torques). Connectors are simultaneously "CO:" Display parameters (CO = Connector Output).

Parameterization:

At the signal destination (target), the required binector or connector is selected using the appropriate parameter:

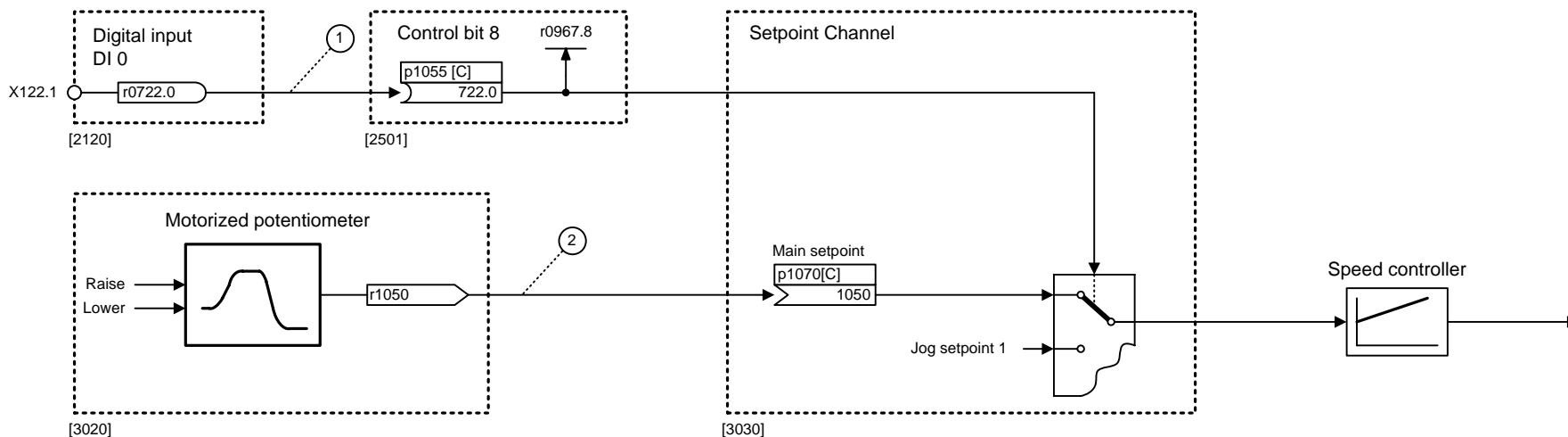
"BI:" parameter for binectors (BI = Binector Input)

or

"CI:" parameter for connectors (CI = Connector Input)

Example:

The main setpoint for the speed controller (CI: p1070) should be received from the output of the motorized potentiometer (CO: r1050) and the command "jog" (BI: p1055) from digital input DI 0 (BO: r0722.0, terminal X122.1) on the CU320.



Parameterizing steps:

- ① p1055[0] = 722.0 Terminal X122.1 acts as "Jog bit 0".
- ② p1070[0] = 1050 The output of the motorized potentiometer acts as main setpoint for the speed controller.

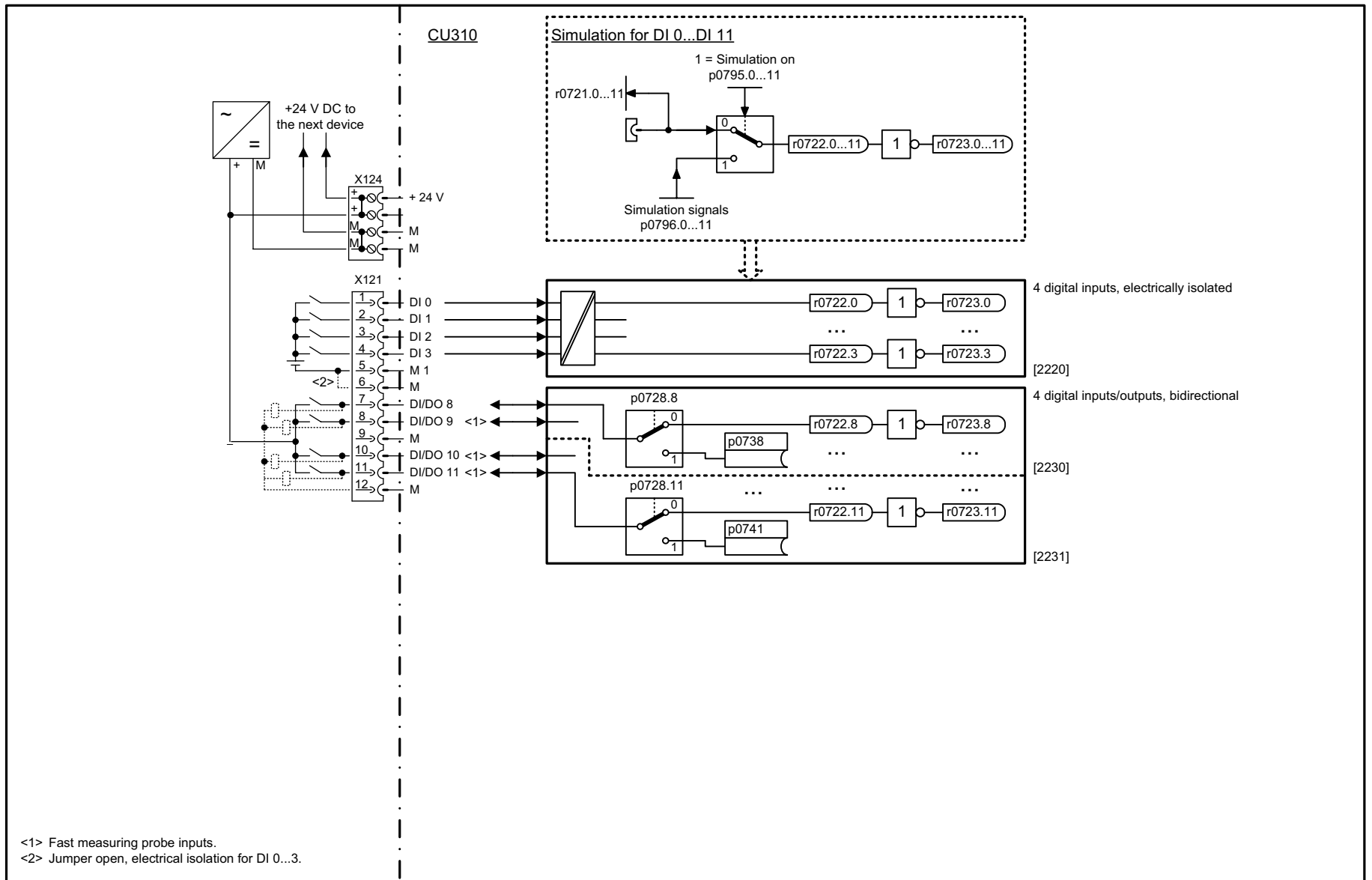
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DO: All objects					fp_1025_01_eng.vsd	Function diagram	
General - Handling BICO technology					14.12.05 V02.04.00	SINAMICS S	
							- 1025 -

Figure 2-4 1025 – Handling BICO technology

2.3 Overview

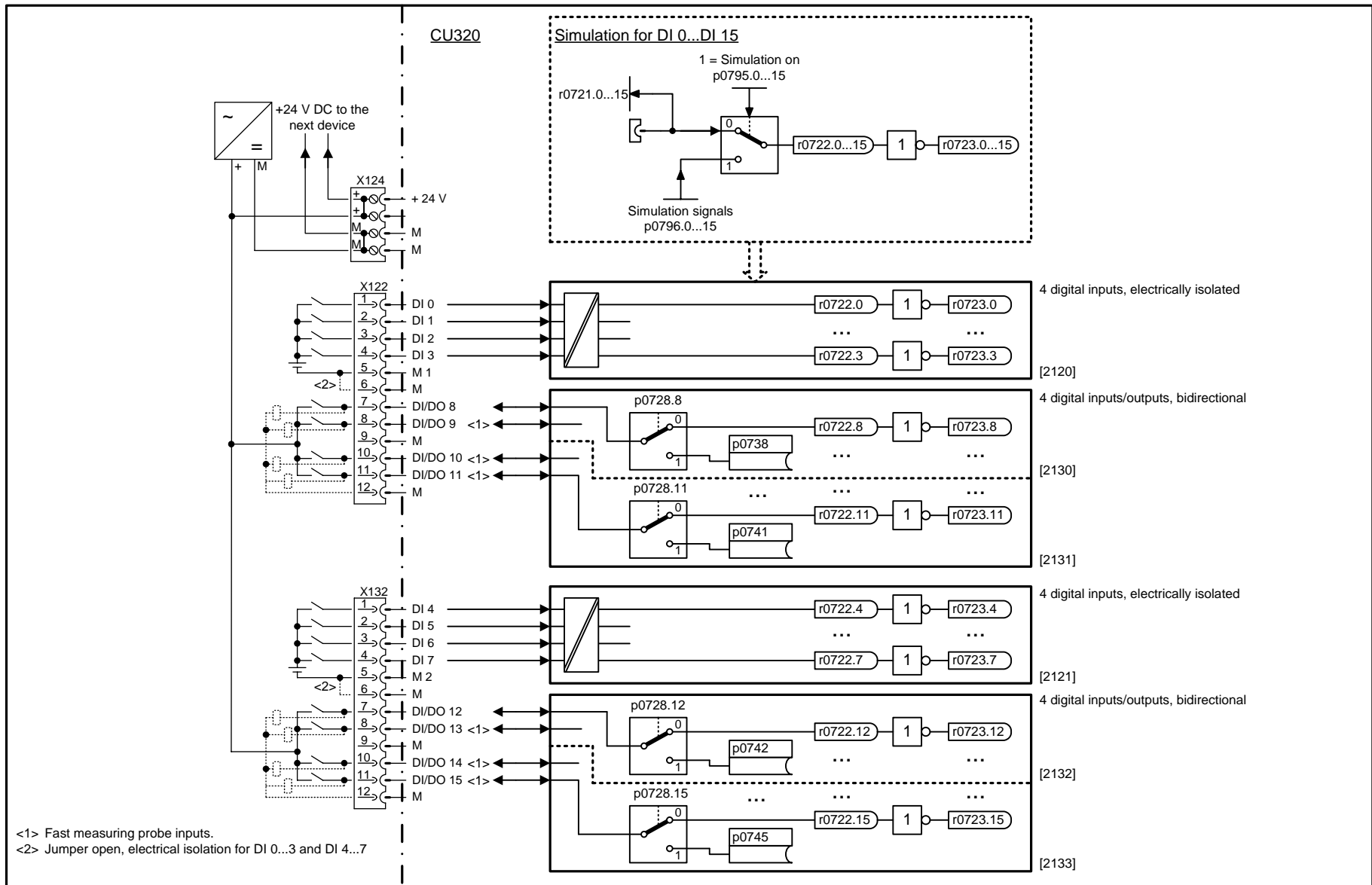
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1	2	3	4	5	6	7	8
DO: CU310					fp_1508_01_eng.vsd	Function diagram	
Overviews – CU310 input/output terminals					23.03.06 V02.04.00	SINAMICS S	

Figure 2-5 1508 – CU310 input/output terminals



1	2	3	4	5	6	7	8
DO: CU_S					fp_1510_01_eng.vsd	Function diagram	
Overviews - CU320 inputs/output terminals					14.12.05 V02.04.00	SINAMICS S	

Figure 2-6 1510 – CU320 input/output terminals

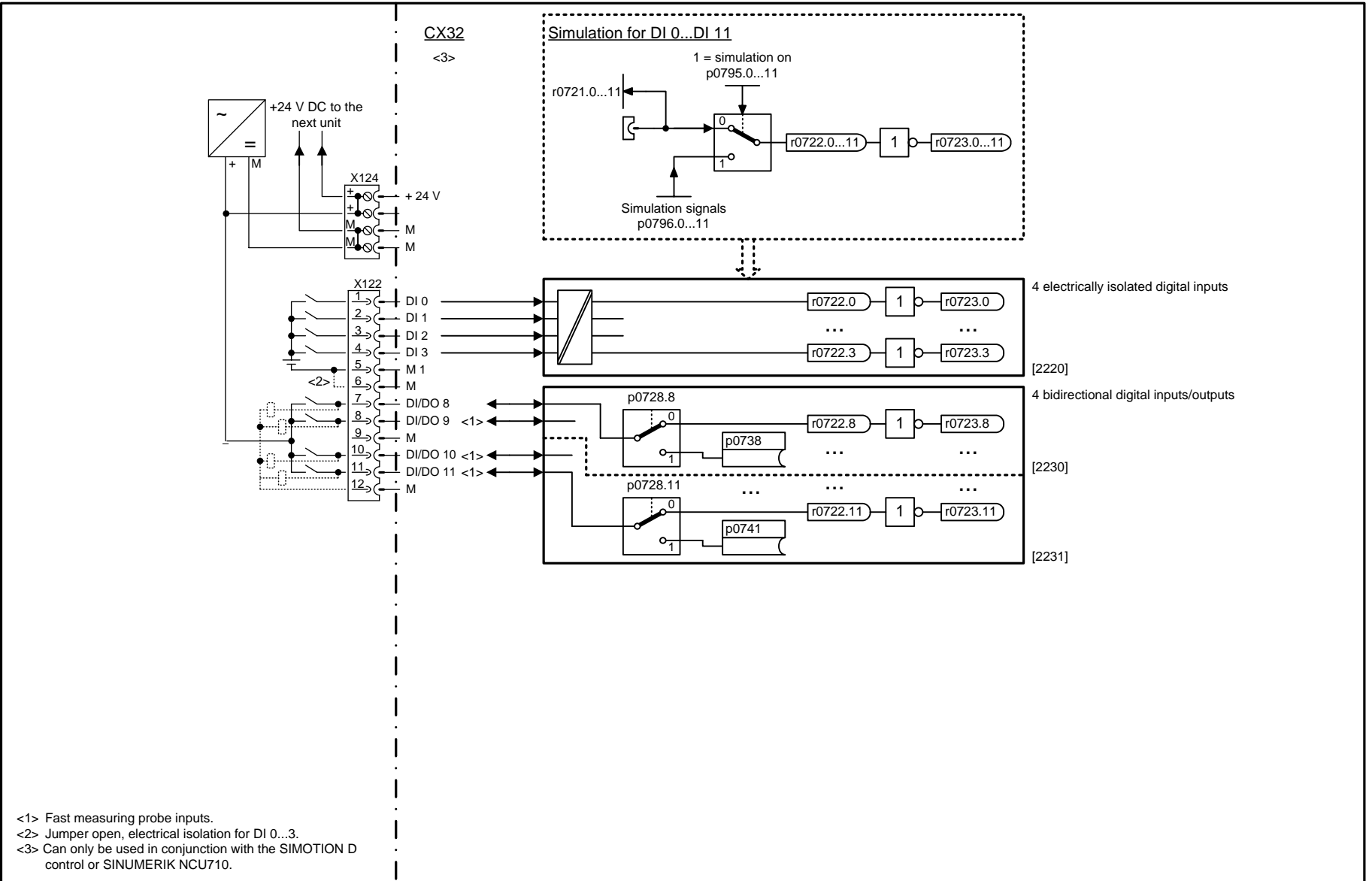
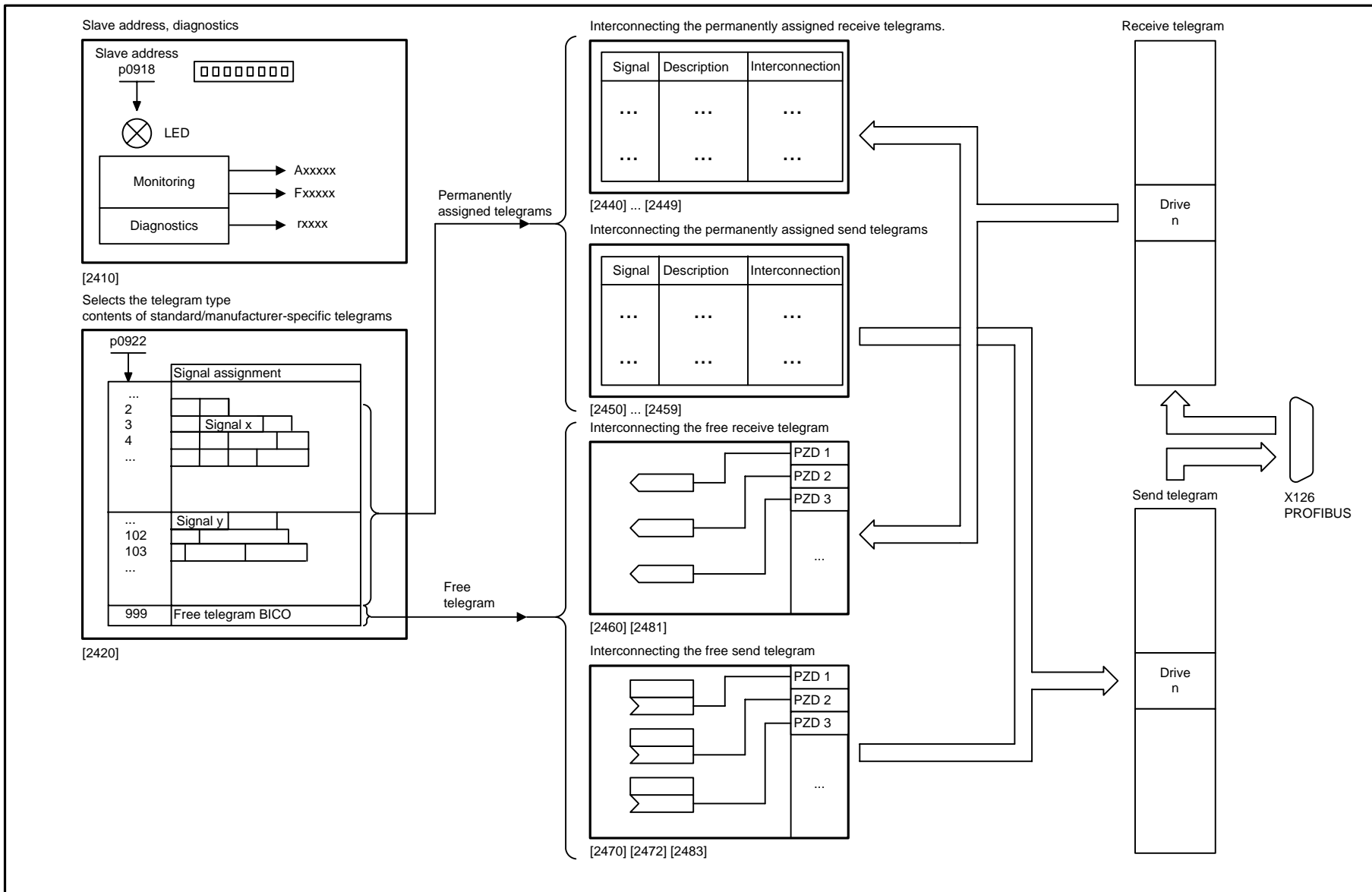


Figure 2-7 1512 – CX32 input/output terminals

2-922

1	2	3	4	5	6	7	8
DO: CX32					fp_1512_01_eng.vsd	Function diagram	
Overviews - CX32 inputs/output terminals					09.06.05 V02.04.00	SINAMICS S	
							- 1512 -

Figure 2-8 1520 – PROFIBUS



1	2	3	4	5	6	7	8
DO: All objects					fp_1520_01_eng.vsd	Function diagram	
Overviews - PROFIBUS					12.01.06 V02.04.00	SINAMICS S	
							- 1520 -

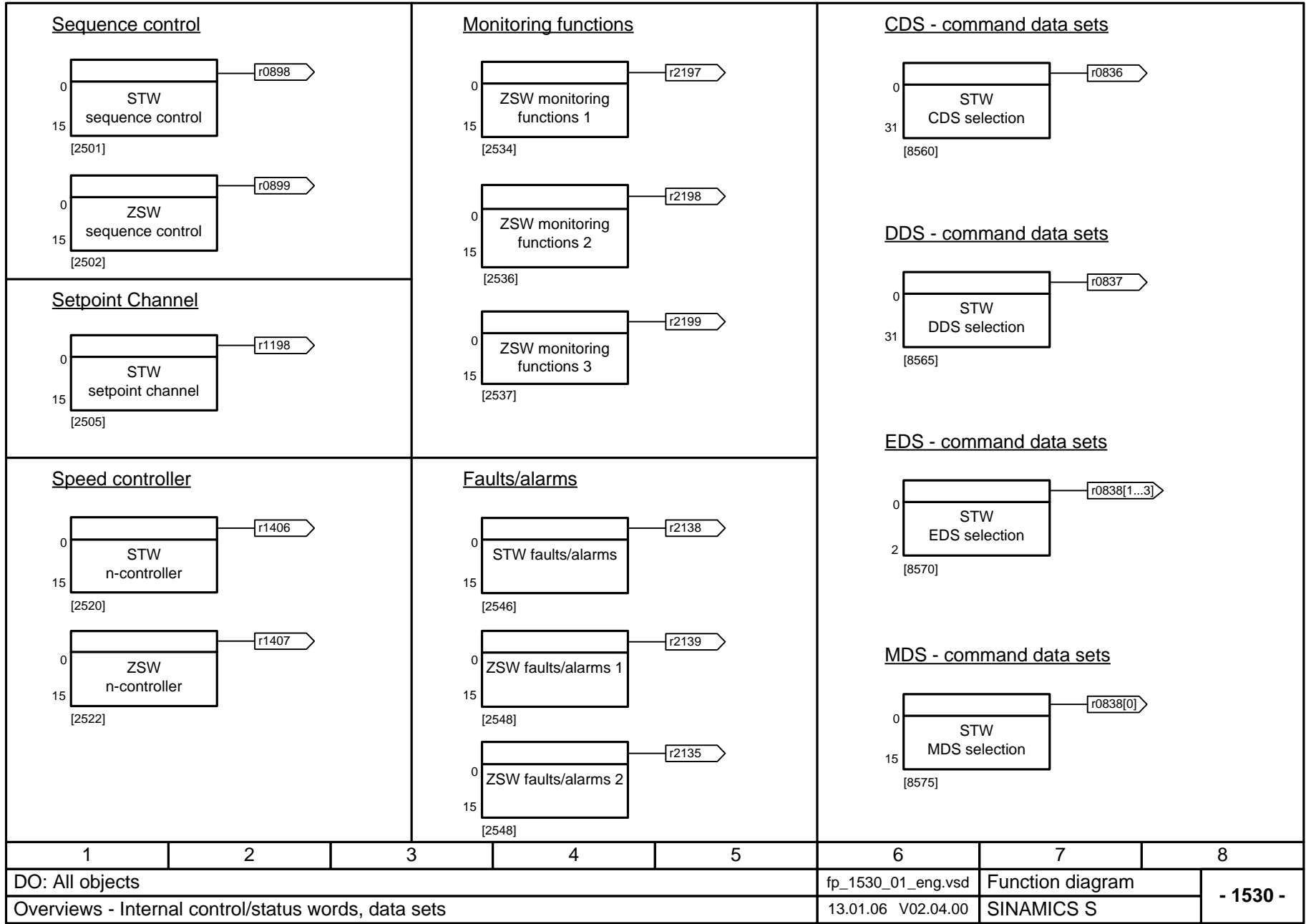
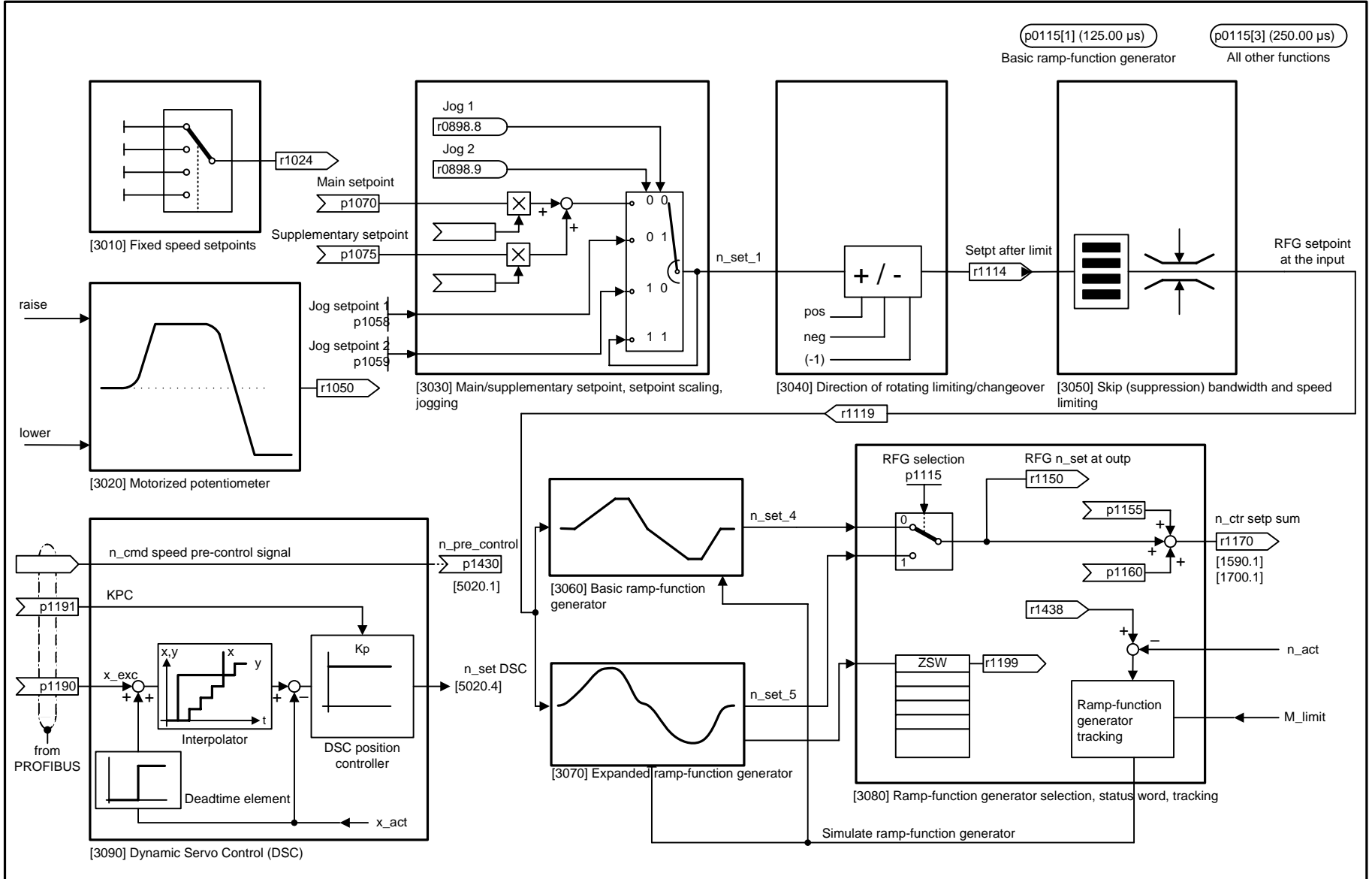
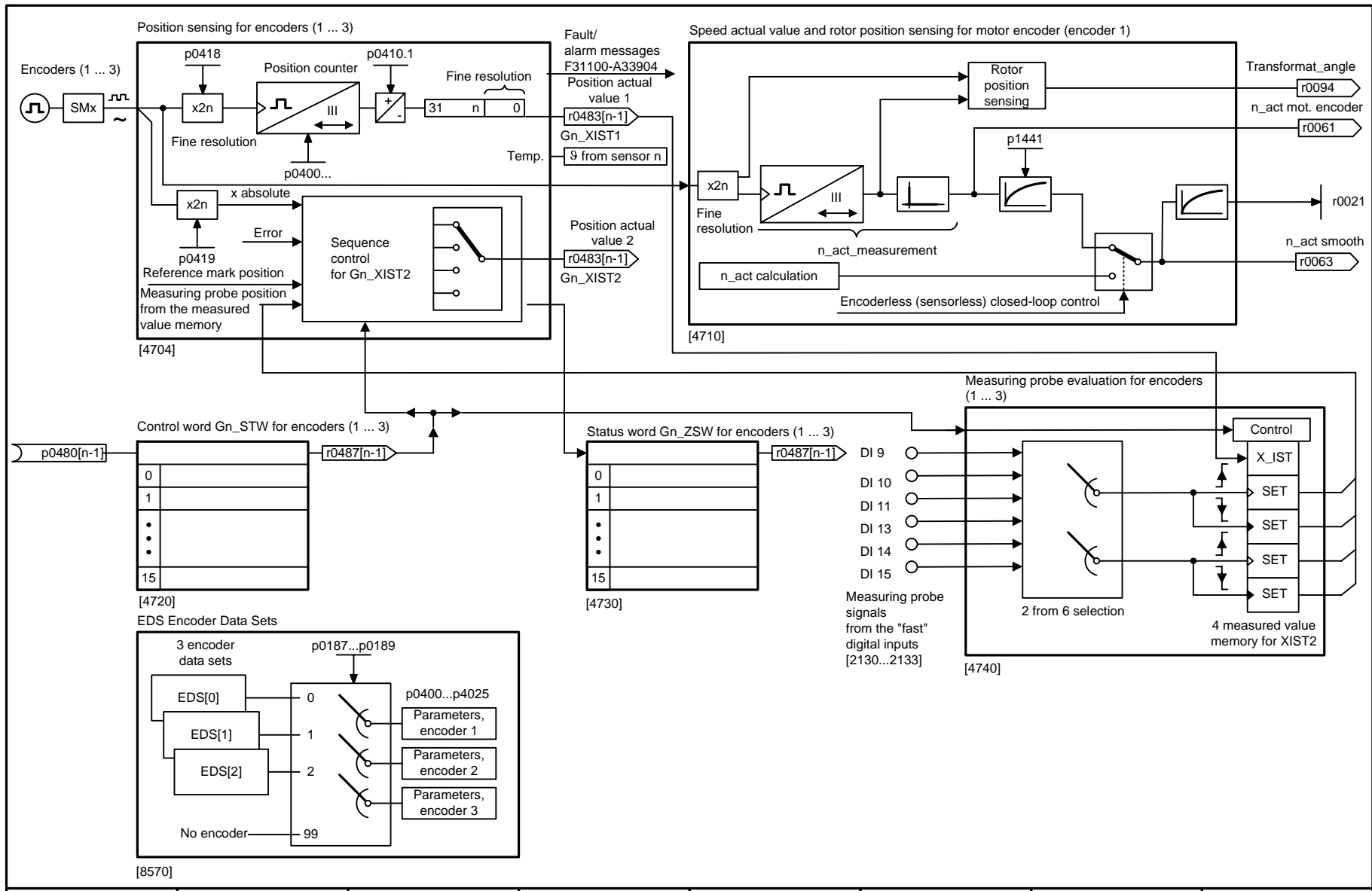


Figure 2-9 1530 – Internal control/status words, data sets

Figure 2-10 1550 – Setpoint channel



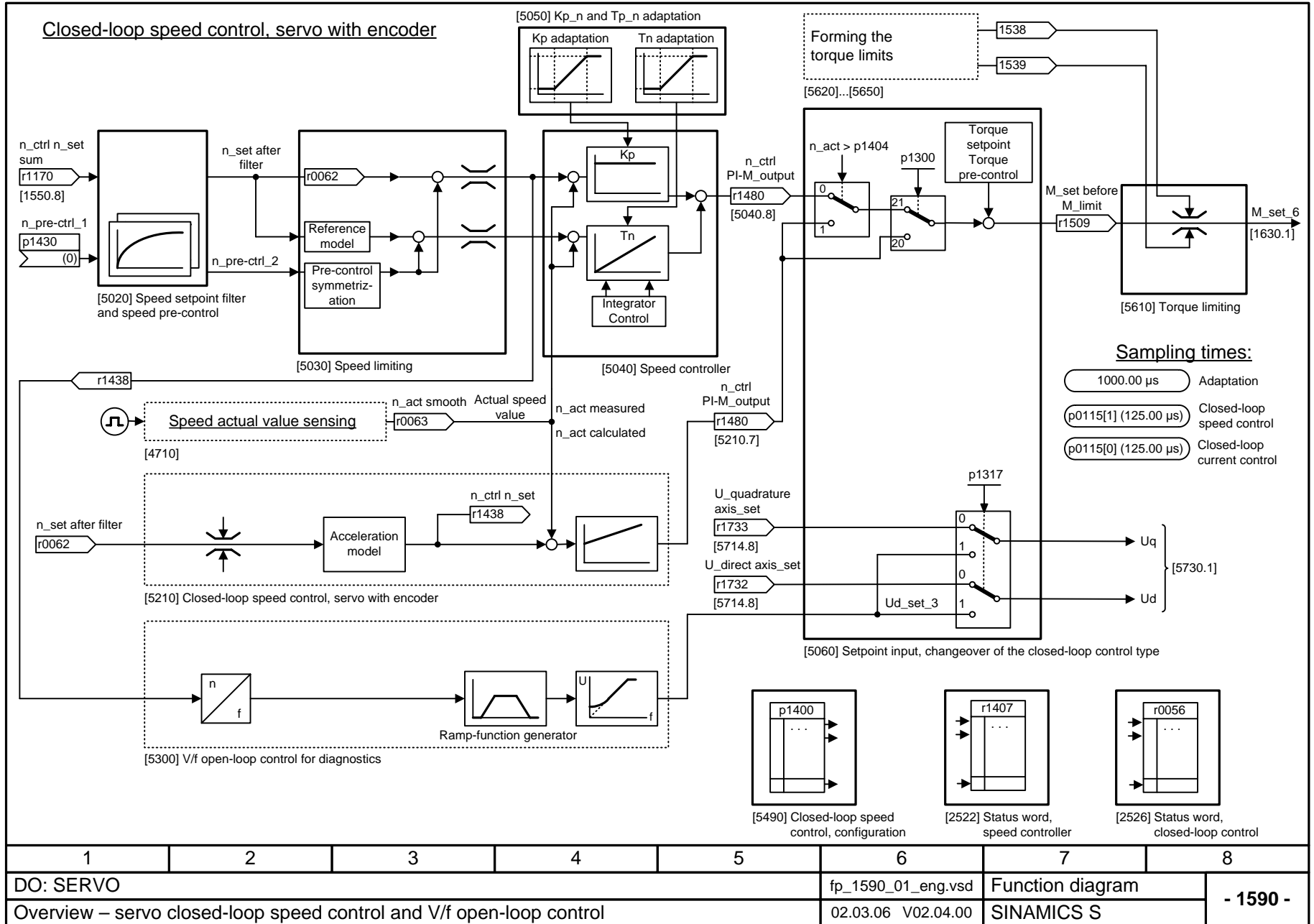
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_1550_01_eng.vsd	Function diagram	
Overviews - setpoint channel					14.04.05 V02.04.00	SINAMICS S	
							- 1550 -



1	2	3	4	5	6	7	8
DO: SERVO					fp_1580_01_eng.vsd	Function diagram	
Overviews - servo encoder evaluations (position, speed, temperature)					18.03.05 V02.04.00	SINAMICS S	
							- 1580 -

Figure 2-11 1580 – Servo encoder evaluations (position, speed, temperature)

Figure 2-12 1590 – Servo closed-loop speed control and V/f open-loop control



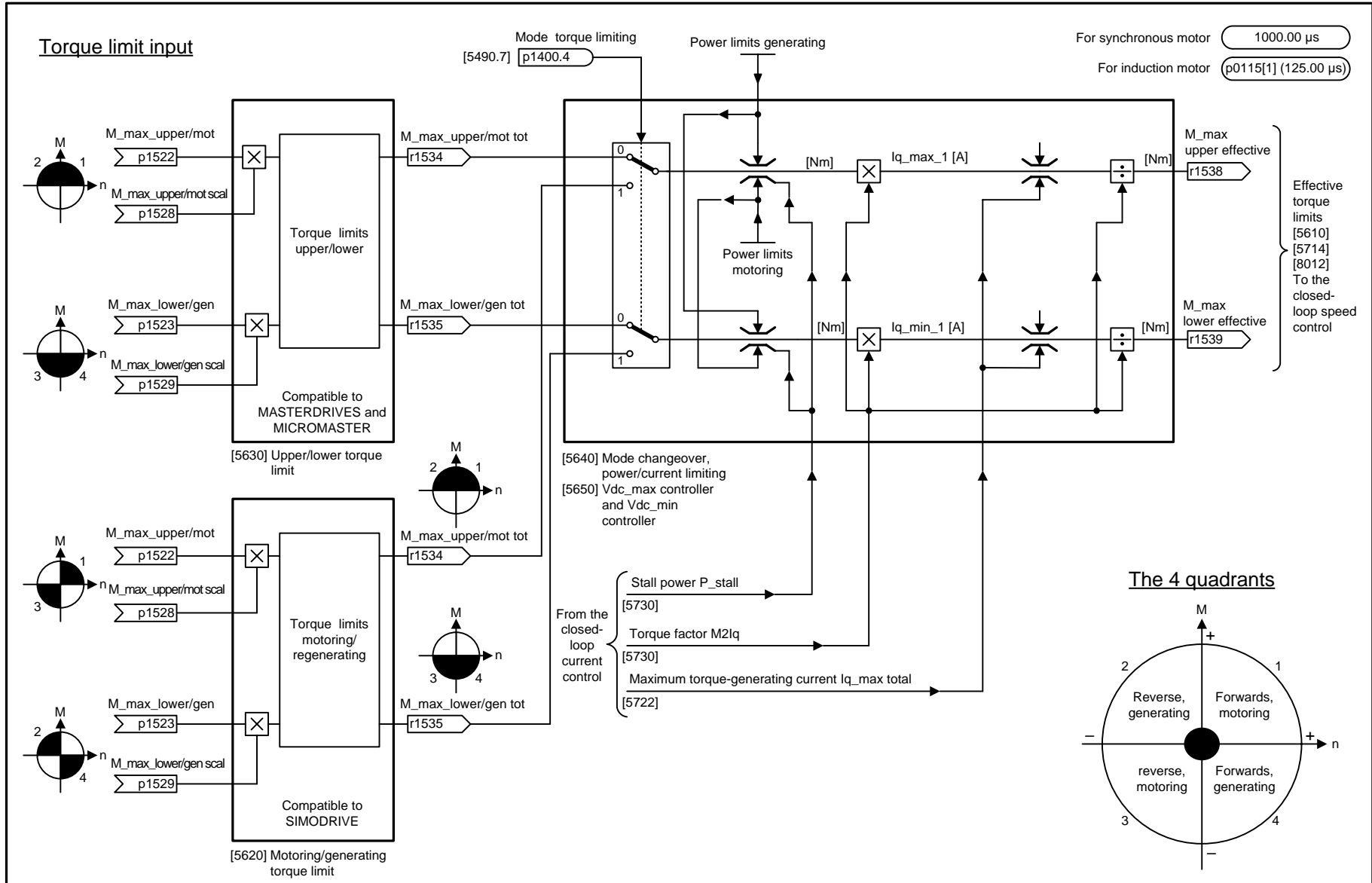
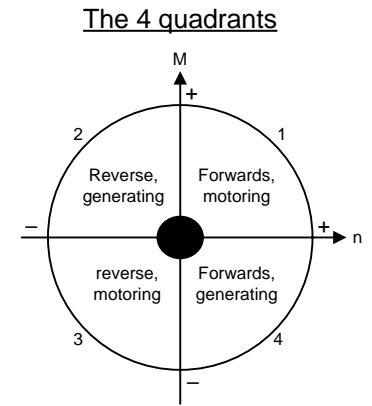


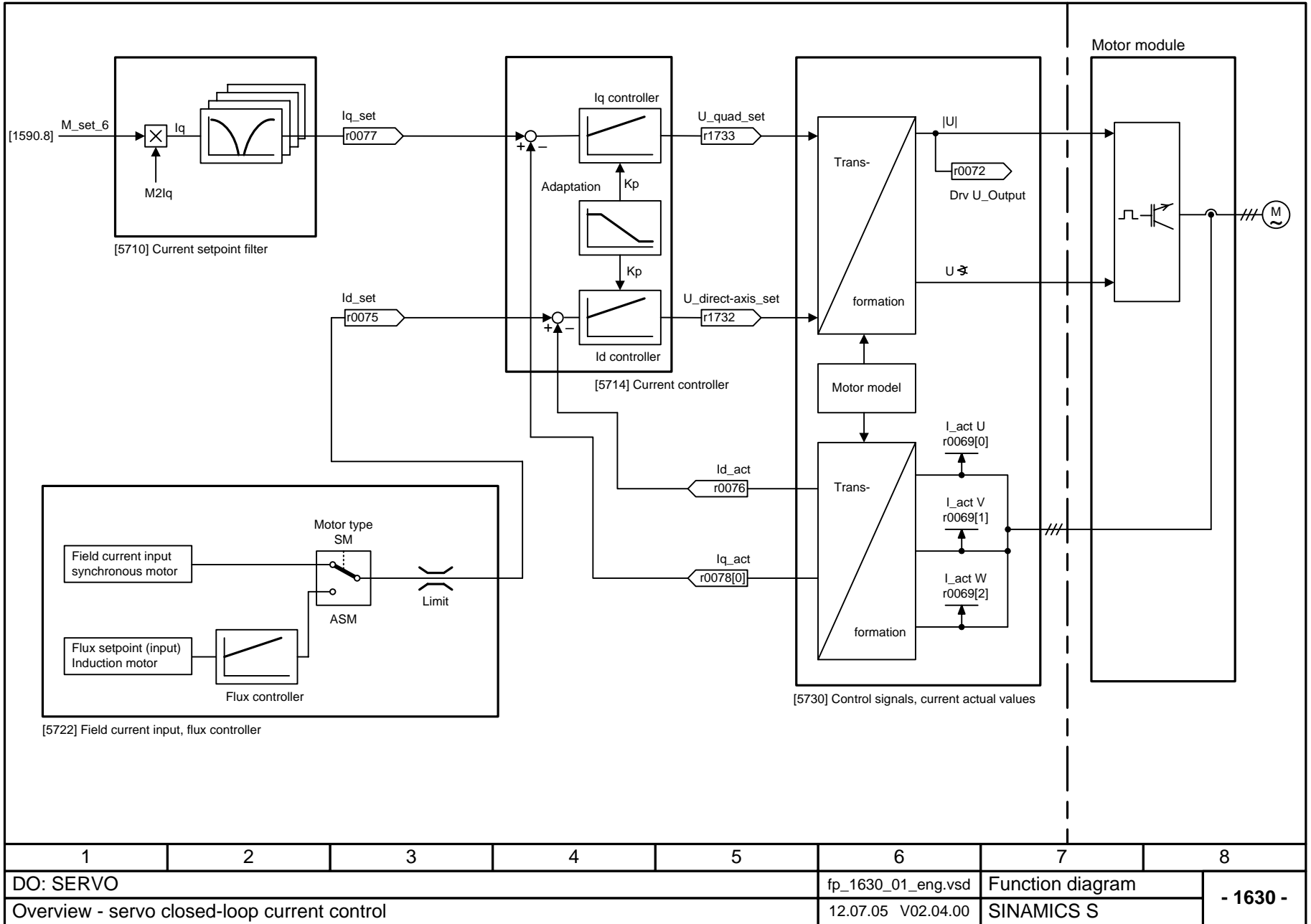
Figure 2-13 1610 – Servo generation of the torque limits

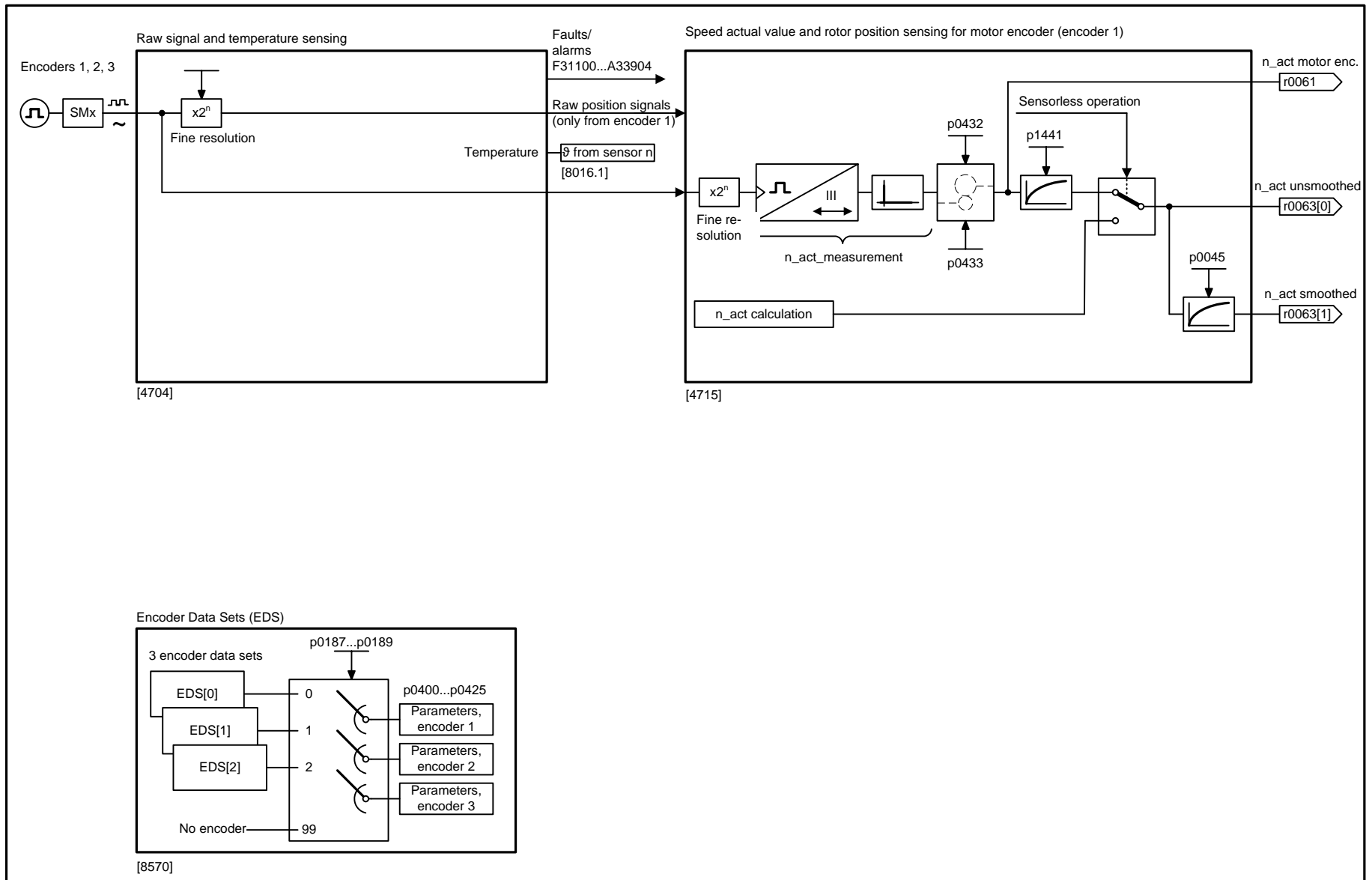
For synchronous motor 1000.00 μs
For induction motor p0115[1] (125.00 μs)



1	2	3	4	5	6	7	8
DO: SERVO					fp_1610_01_eng.vsd	Function diagram	
Overview - servo forming the torque limits					22.07.05 V02.04.00	SINAMICS S	
							- 1610 -

Figure 2-14 1630 – Servo current control

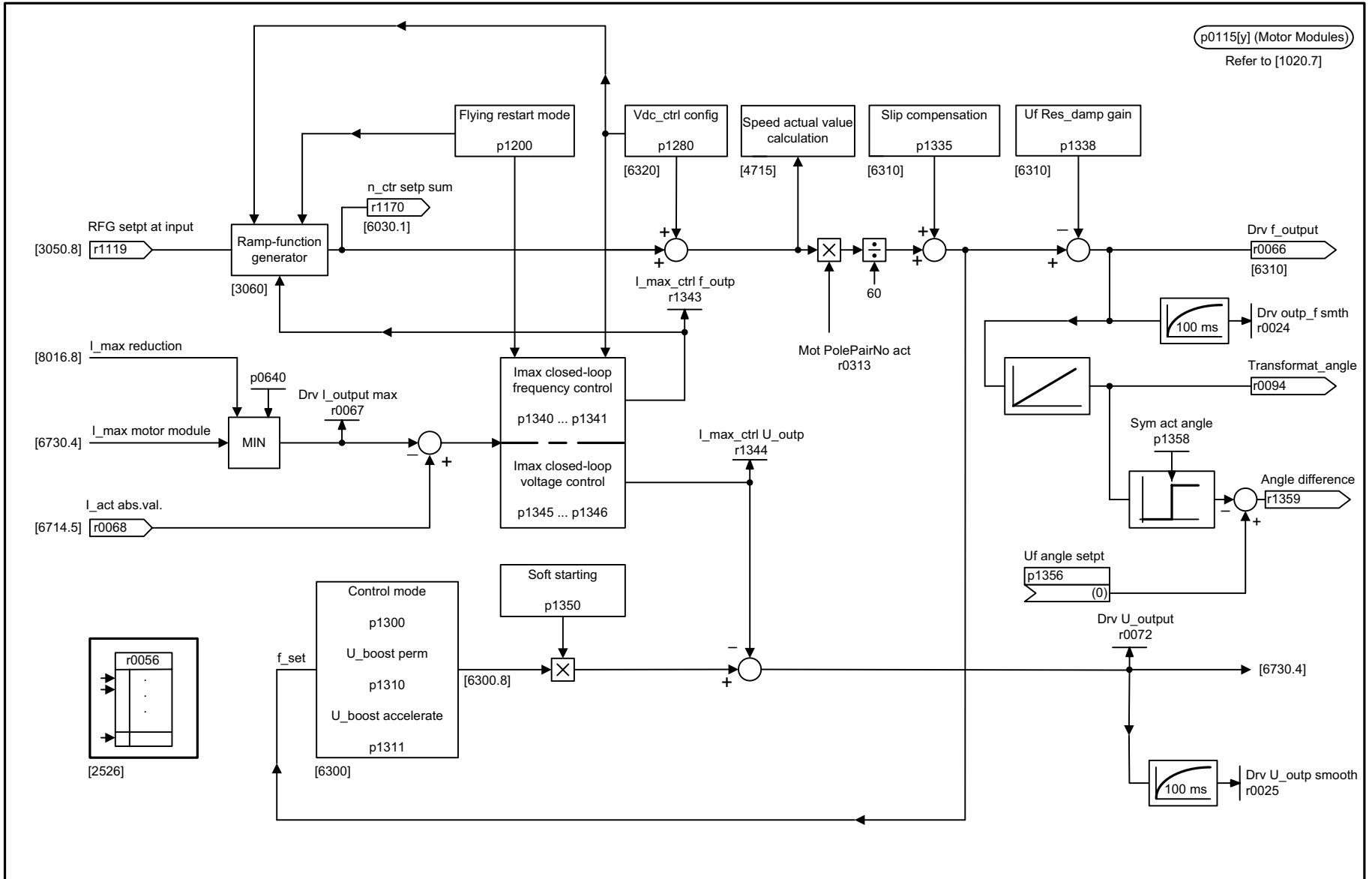




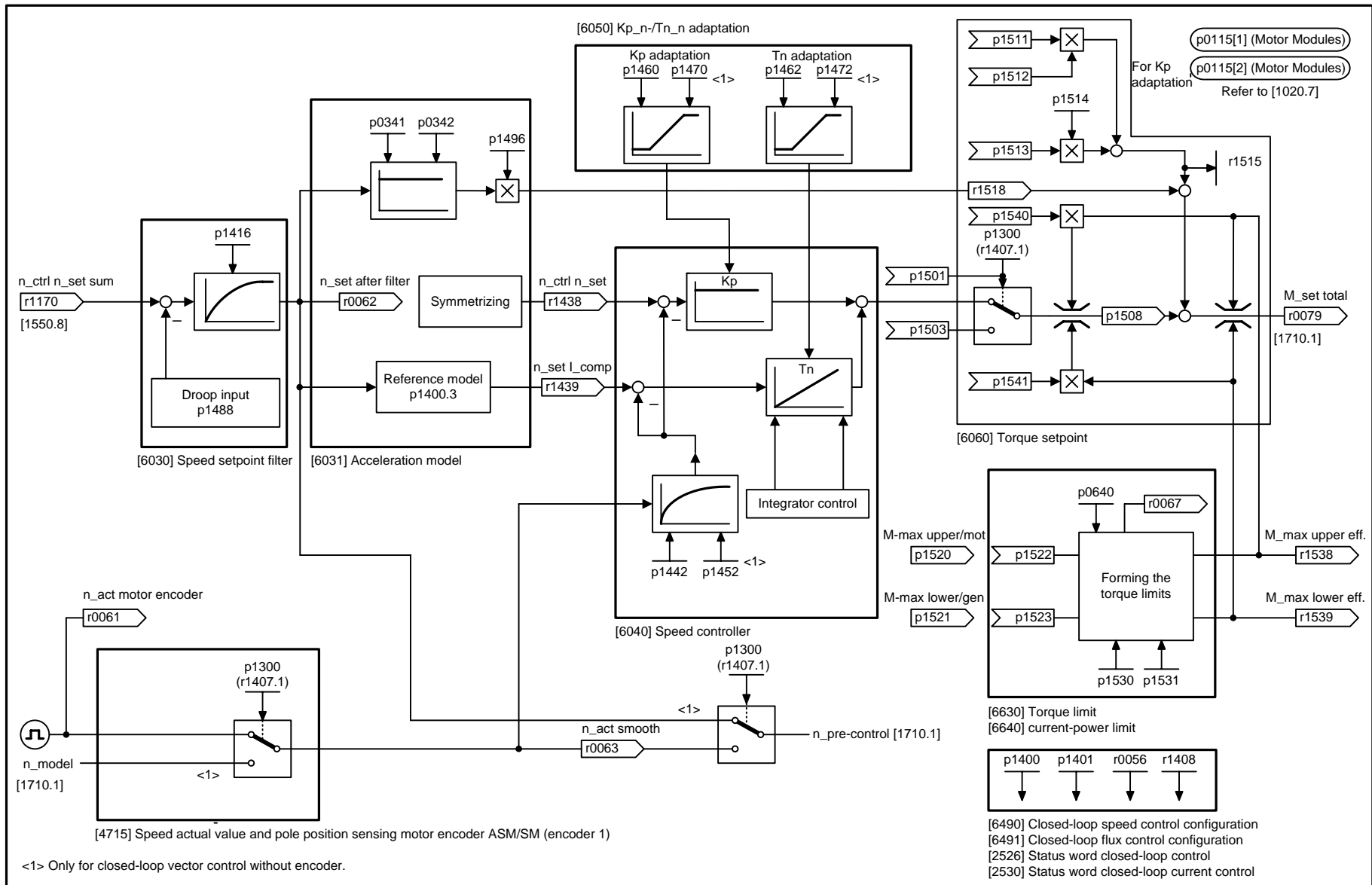
1	2	3	4	5	6	7	8
DO: VECTOR					fp_1680_01_eng.vsd	Function diagram	
Overviews - vector encoder evaluation functions (position, speed, temperature)					16.03.06 V02.04.00	SINAMICS S	
							- 1680 -

Figure 2-15 1680 – Vector encoder evaluation functions (position, speed, temperature)

Figure 2-16 1690 – Vector V/f control



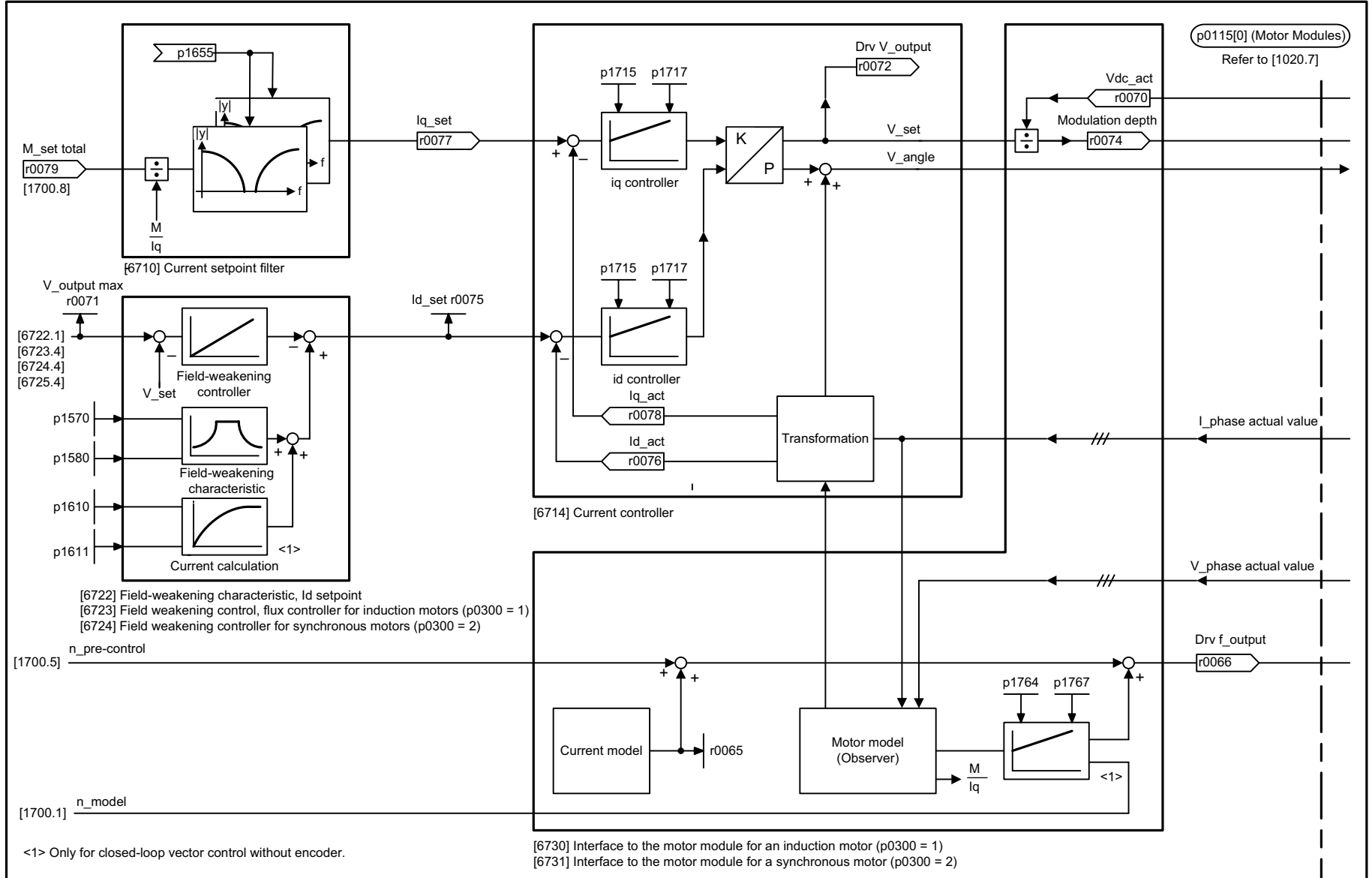
1	2	3	4	5	6	7	8
DO: VECTOR					fp_1690_01_eng.vsd	Function diagram	
Overviews - vector U/f open-loop control					23.03.06 V02.04.00	SINAMICS S	
							- 1690 -



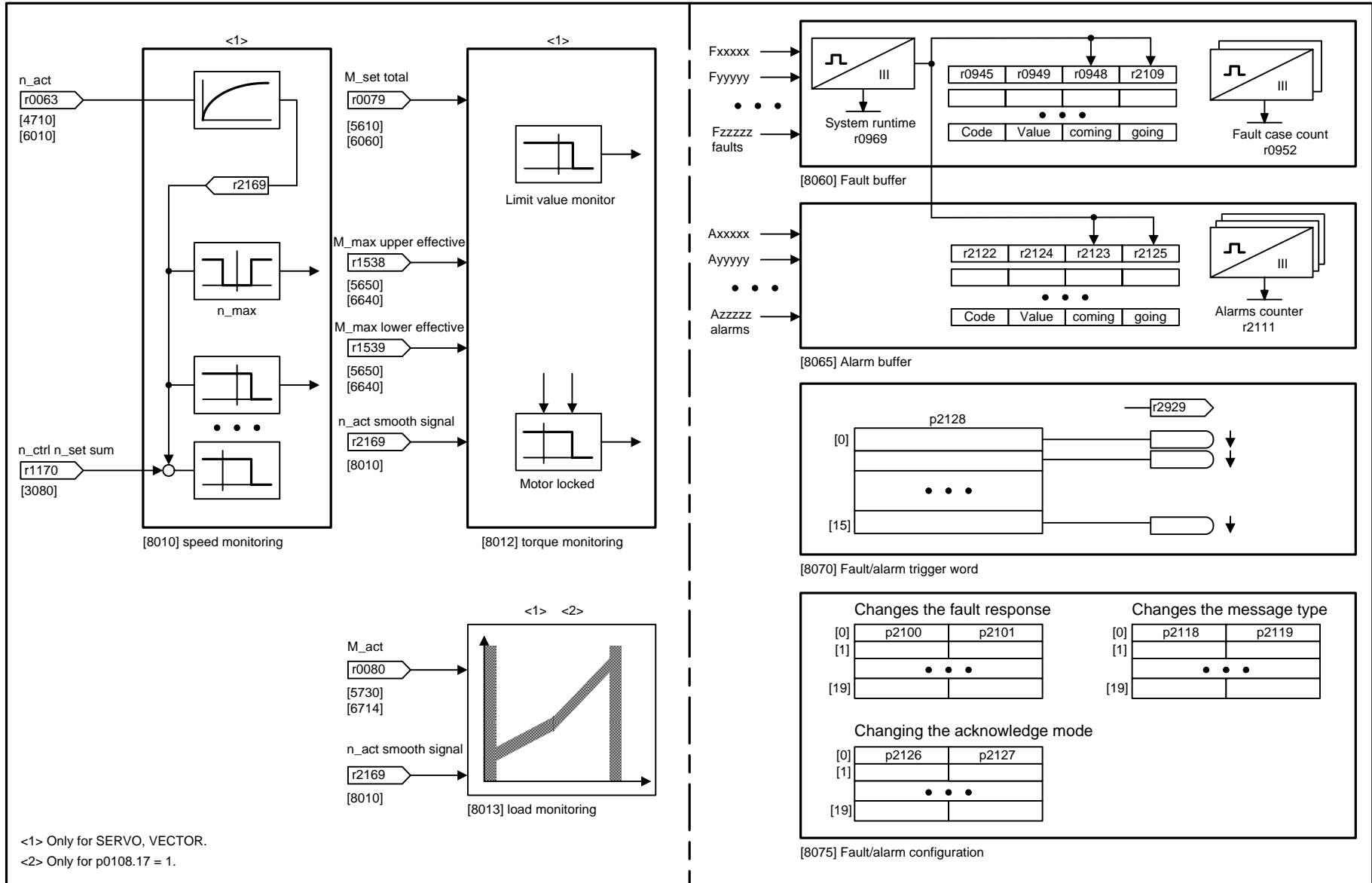
1	2	3	4	5	6	7	8
DO: VECTOR					fp_1700_01_eng.vsd	Function diagram	
Overview - vector closed-loop speed control and formation of the torque limits					16.03.06 V02.04.00	SINAMICS S	
							- 1700 -

Figure 2-17 1700 – Vector closed-loop speed control and formation of the torque limits

Figure 2-18 1710 – Vector closed-loop current control



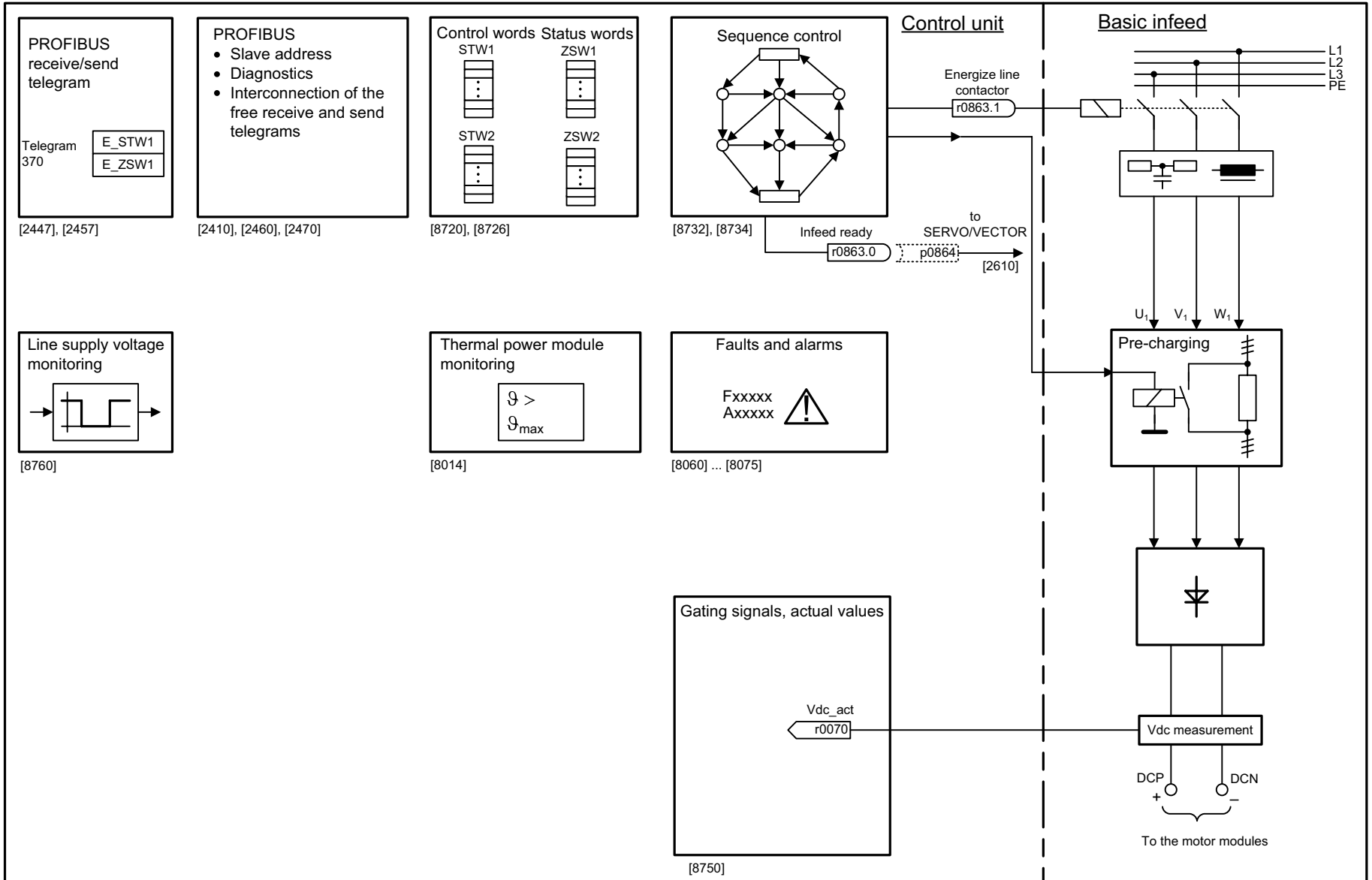
1	2	3	4	5	6	7	8
DO: VECTOR					fp_1710_01_eng.vsd	Function diagram	
Overviews - vector closed-loop current control					23.03.06 V02.04.00	SINAMICS S	
							- 1710 -



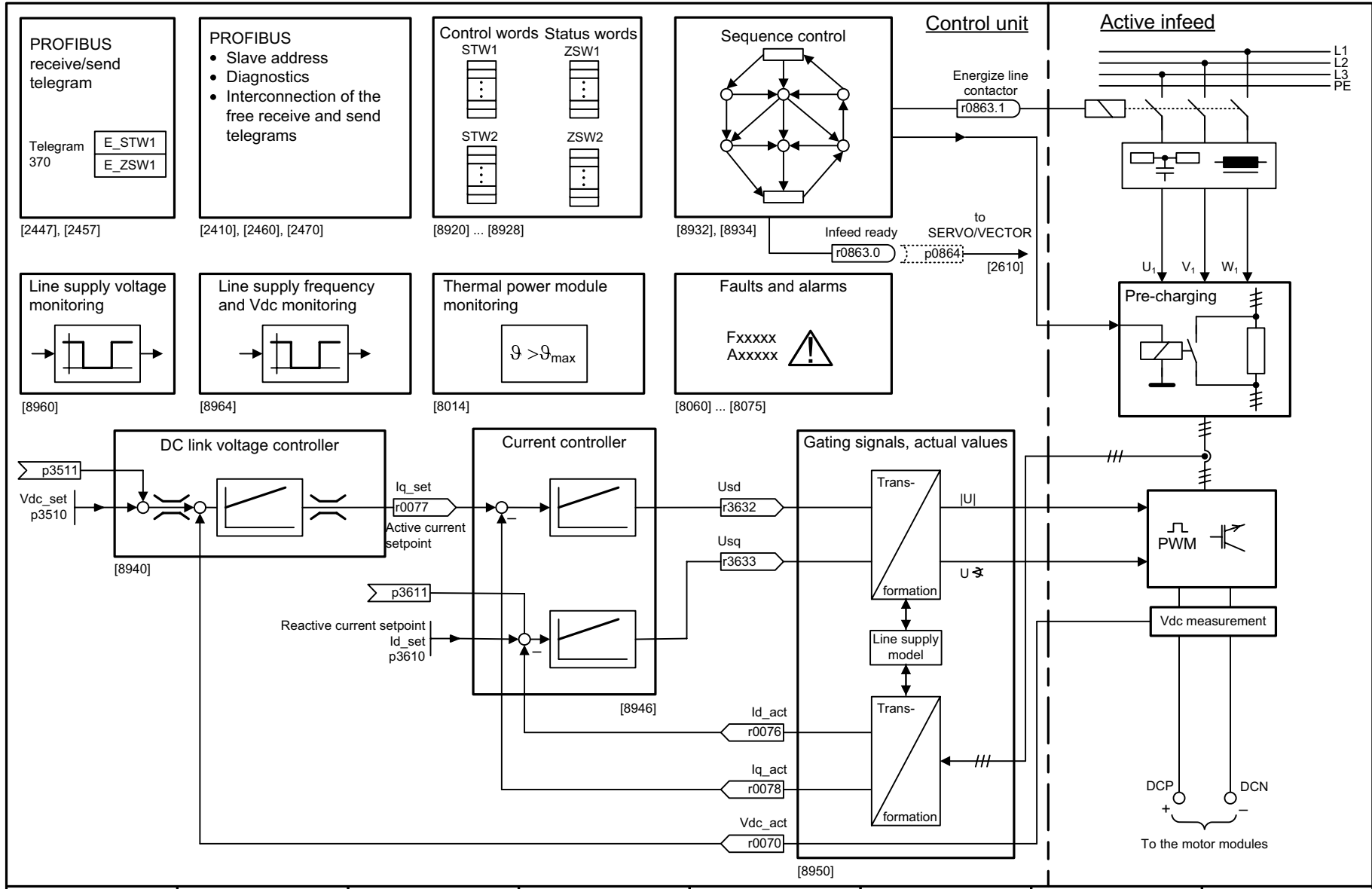
<1> Only for SERVO, VECTOR.
 <2> Only for p0108.17 = 1.

1	2	3	4	5	6	7	8
DO: Alle Objekte					fp_1750_01_eng.vsd	Function diagram	
Overview - Monitoring functions, faults, alarms					04.08.05 V02.04.00	SINAMICS S	
							- 1750 -

Figure 2-20 1773 – Basic Infeed



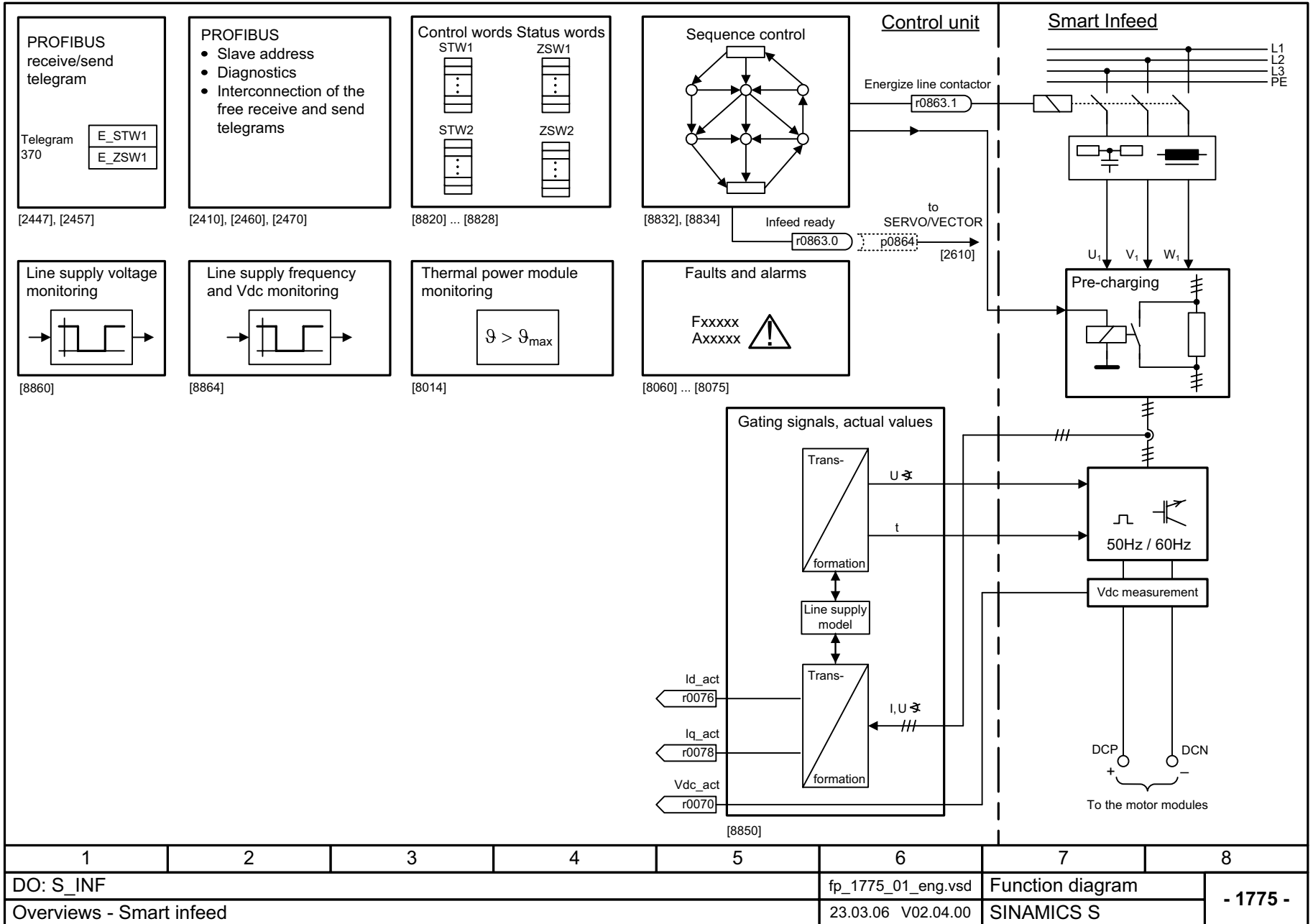
1	2	3	4	5	6	7	8
DO: B_INF					fp_1773_01_eng.vsd	Function diagram	
Overviews - Basic infeed					23.03.06 V02.04.00	SINAMICS S	
							- 1773 -



1	2	3	4	5	6	7	8
DO: A_INF					fp_1774_01_eng.vsd	Function diagram	
Overviews - active infeed					23.03.06 V02.04.00	SINAMICS S	
							- 1774 -

Figure 2-21 1774 – Active Infeed

Figure 2-22 1775 – Smart Infeed



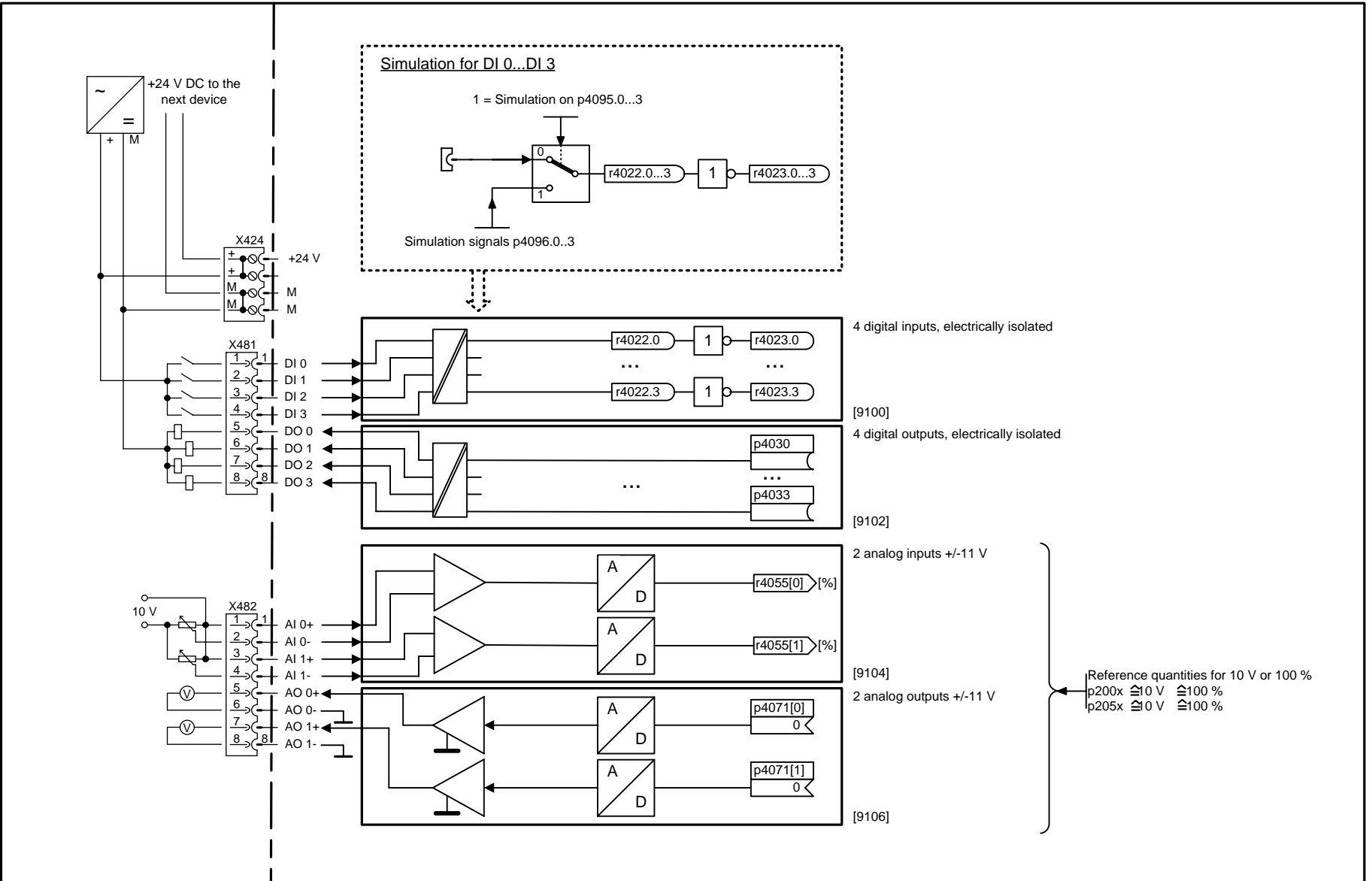
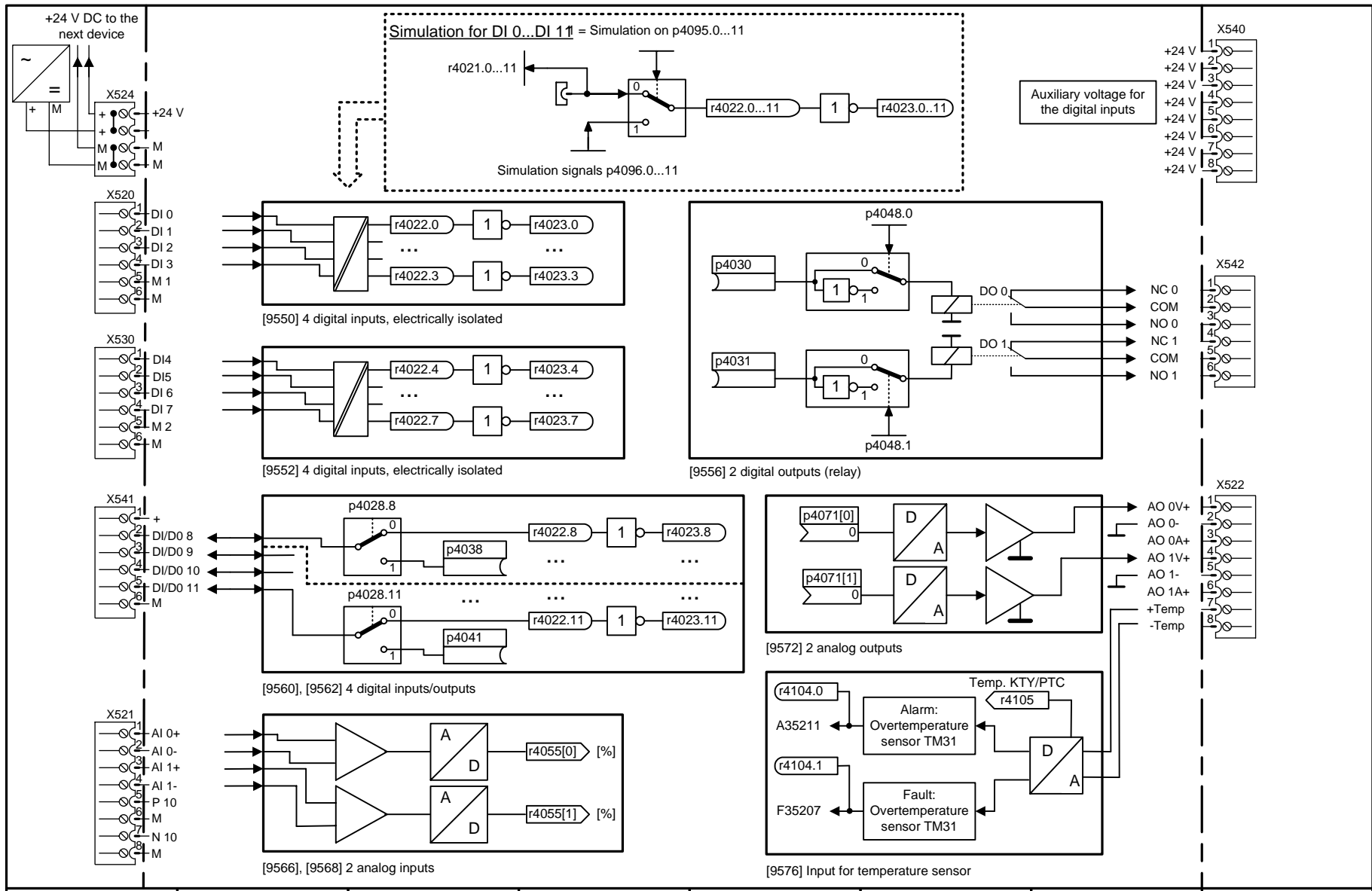


Figure 2-23 1790 – Terminal Board 30 (TB30)

1	2	3	4	5	6	7	8
DO: TB30					fp_1790_01_eng.vsd	Function diagram	
Overview - terminal board 30 (TB30)					15.12.03 V02.04.00	SINAMICS S	
							- 1790 -



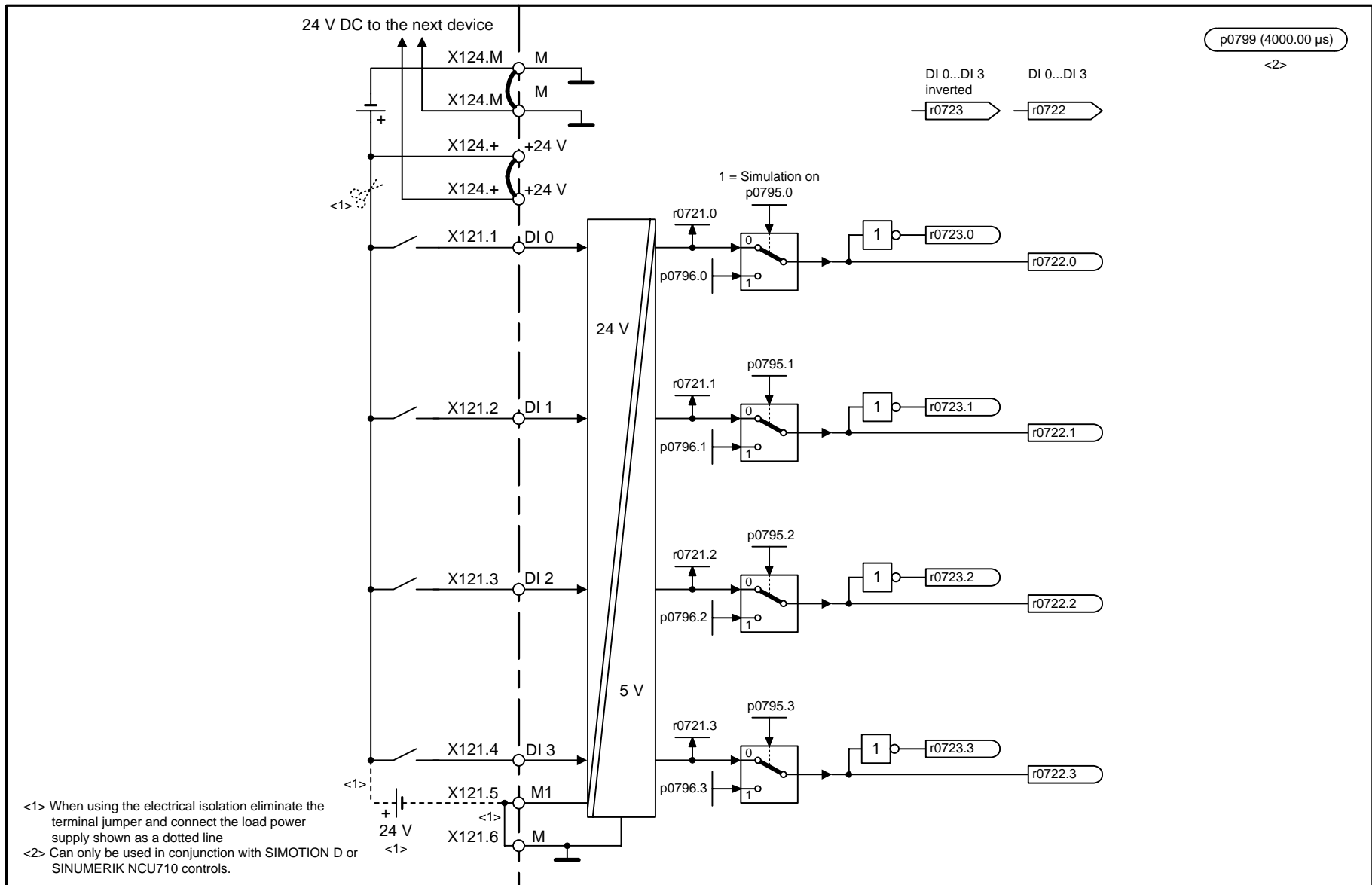
1	2	3	4	5	6	7	8
DO: TM31					fp_1840_01_eng.vsd	Function diagram	
Overviews - terminal module 31 (TM31)					12.03.04 V02.04.00	SINAMICS S	
							- 1840 -

Figure 2-24 1840 – Terminal Module 31 (TM31)

2.4 CU310 input/output terminals

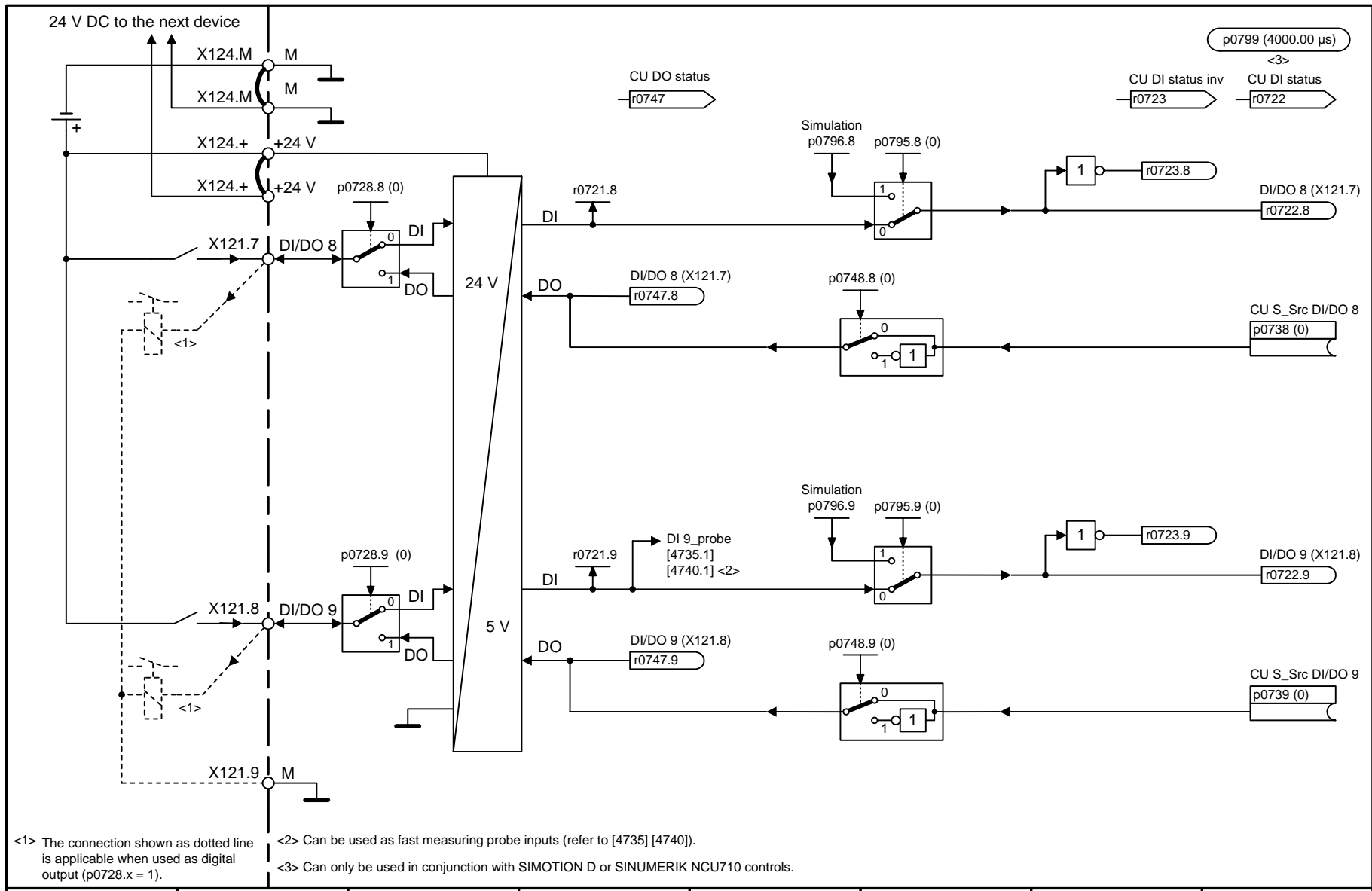
Function diagrams

2020 – Digital inputs, electrically isolated (DI 0 ... DI 3)	2-941
2030 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)	2-942
2131 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)	2-948



1	2	3	4	5	6	7	8
DO: CU310					fp_2020_01_eng.vsd	Function diagram	
CU310 input/output terminals - digital inputs are electrically isolated (DI 0 ... DI 3)					25.11.04 V02.04.00	SINAMICS S	

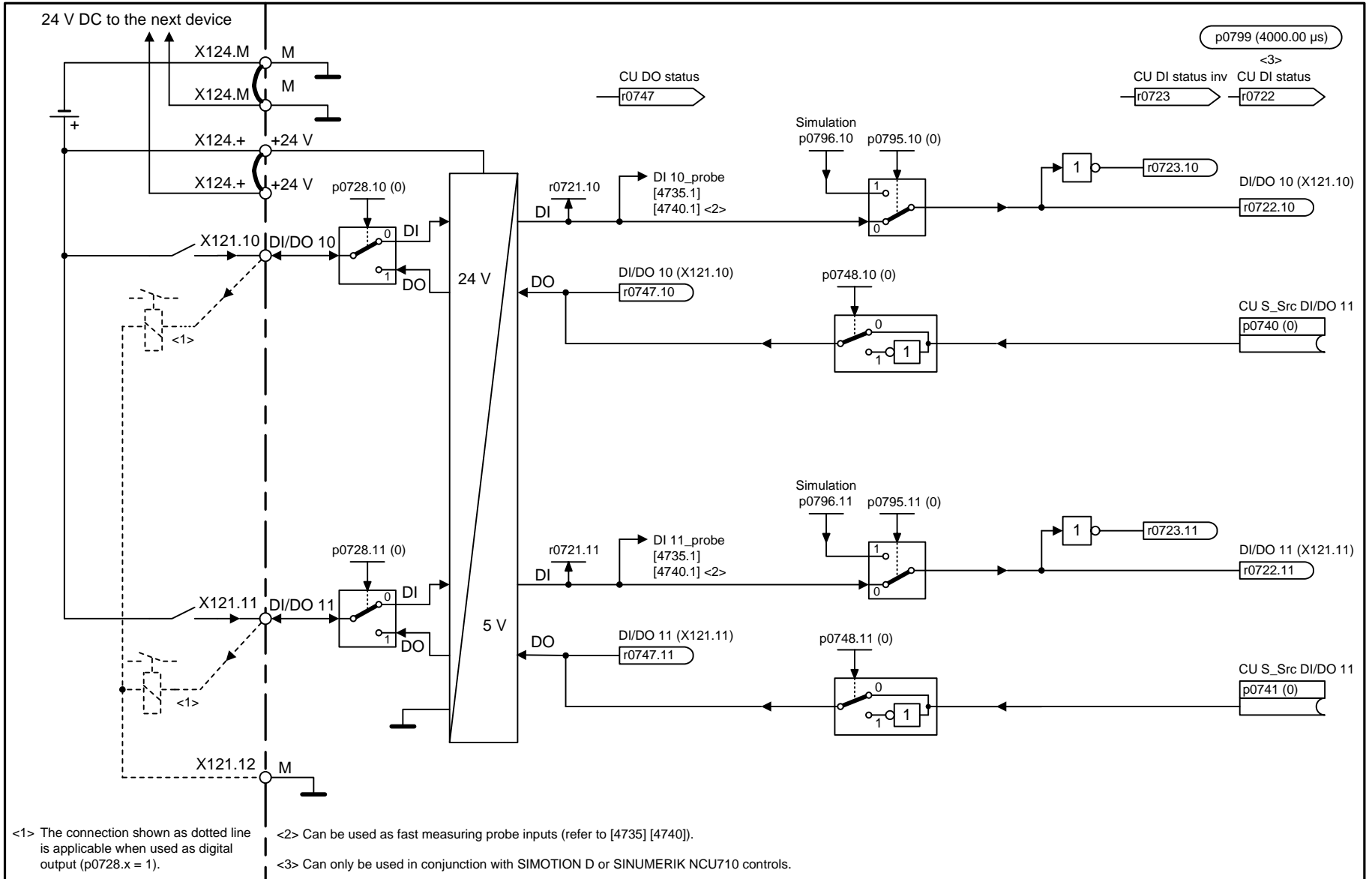
Figure 2-25 2020 – Digital inputs, electrically isolated (DI 0 ... DI 3)



1	2	3	4	5	6	7	8
DO: CU310					fp_2030_01_eng.vsd	Function diagram	
CU310 input/output terminals - digital inputs/outputs bidirectional (DI/DO 8 ... DI/DO 9)					25.11.04 V02.04.00	SINAMICS S	
							- 2030 -

Figure 2-26 2030 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)

Figure 2-27 2031 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)

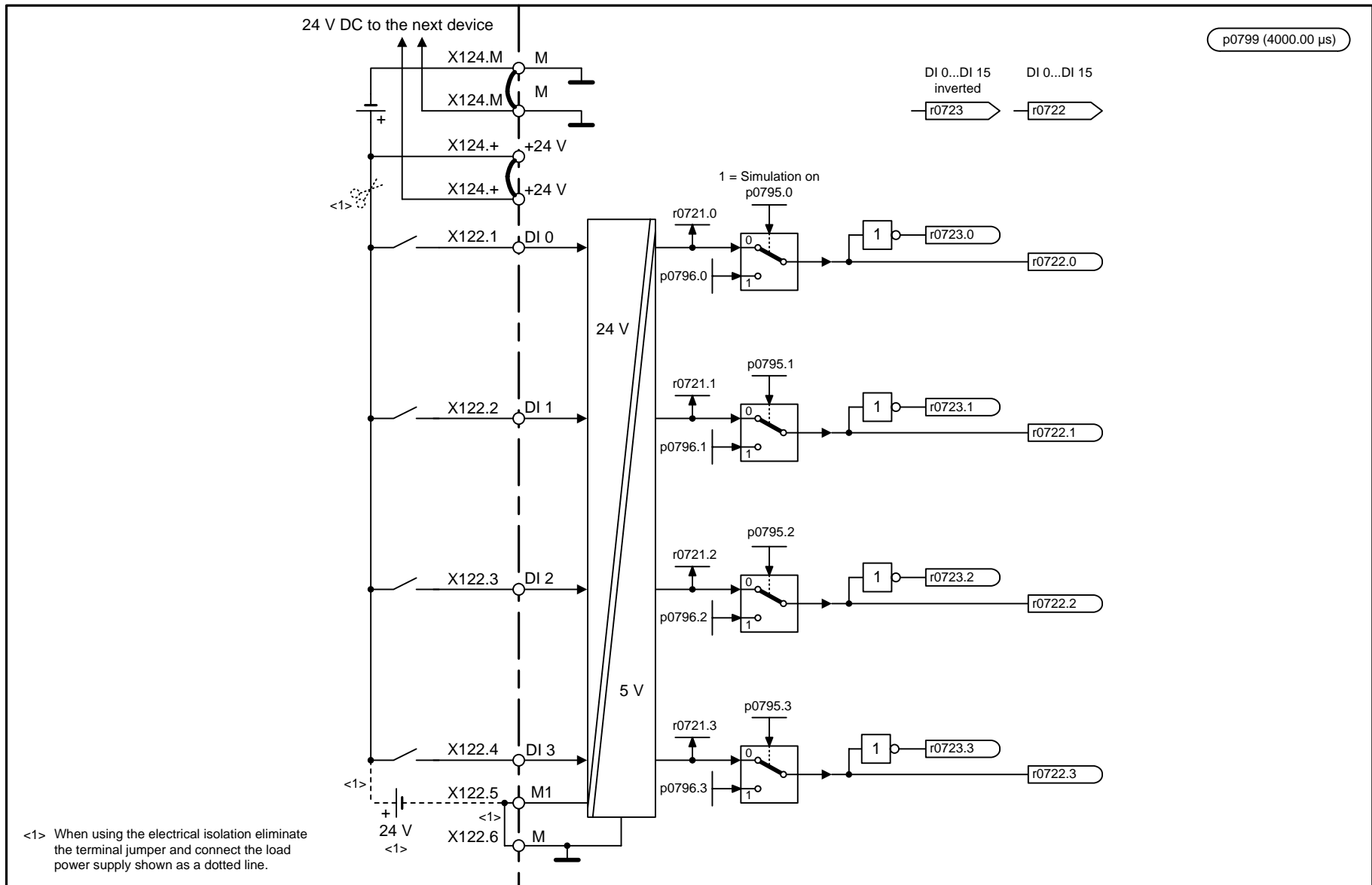


1	2	3	4	5	6	7	8
DO: CU310					fp_2031_01_eng.vsd	Function diagram	
CU310 input/output terminals - digital inputs/outputs bidirectional (DI/DO 10 ... DI/DO 11)					25.11.04 V02.04.00	SINAMICS S	
							- 2031 -

2.5 CU320 input/output terminals

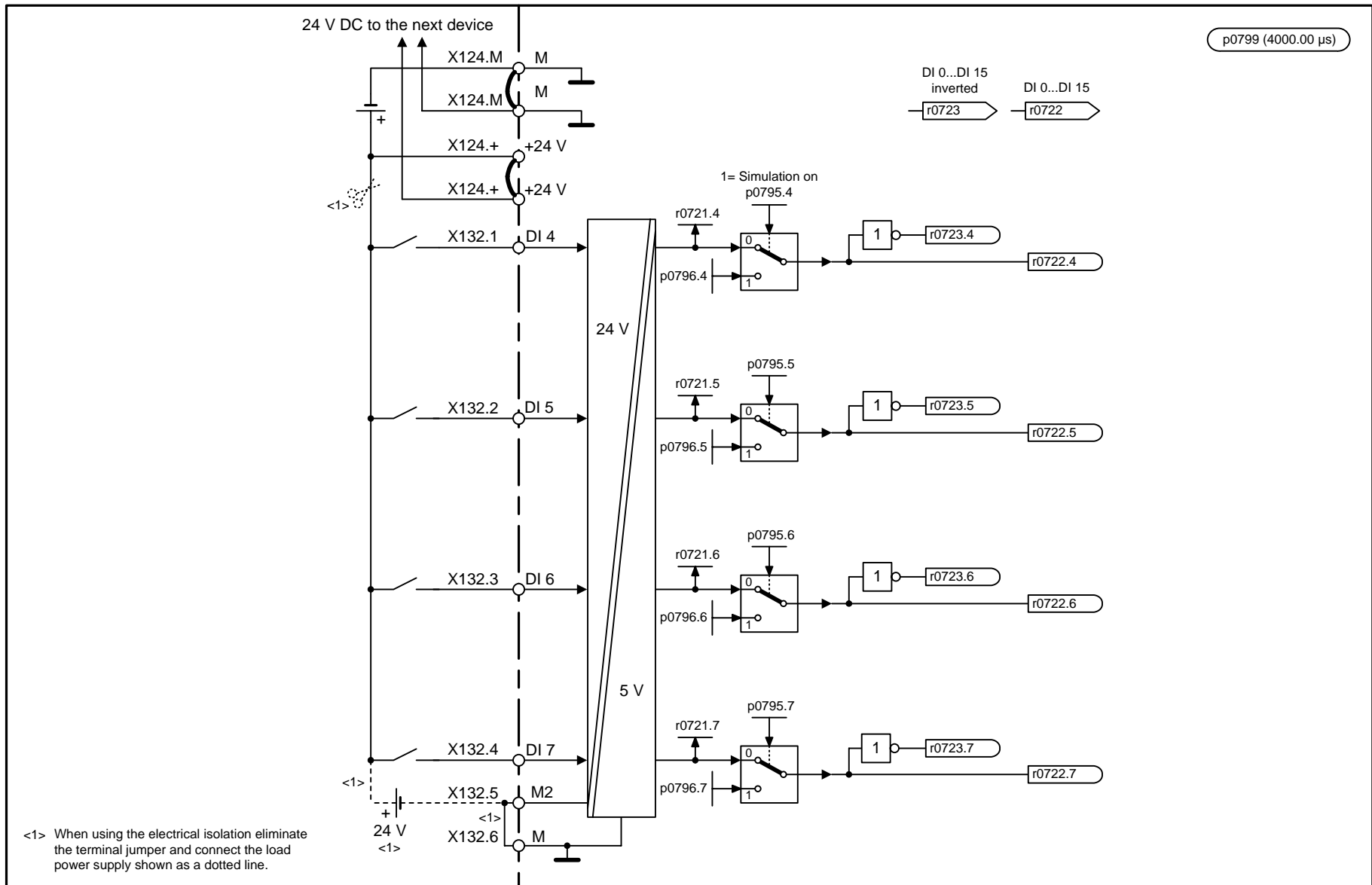
Function diagrams

2120 – Digital inputs, electrically isolated (DI 0 ... DI 3)	2-945
2121 – Digital inputs, electrically isolated (DI 4 ... DI 7)	2-946
2130 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)	2-947
2131 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)	2-948
2132 – Digital inputs/outputs, bidirectional (DI/DO 12 ... DI/DO 13)	2-949
2133 – Digital inputs/outputs, bidirectional (DI/DO 14 ... DI/DO 15)	2-950



1	2	3	4	5	6	7	8
DO: CU_S					fp_2120_01_eng.vsd	Function diagram	
CU320 input/output terminals - digital inputs are electrically isolated (DI 0 ... DI 3)					14.12.05 V02.04.00	SINAMICS S	
							- 2120 -

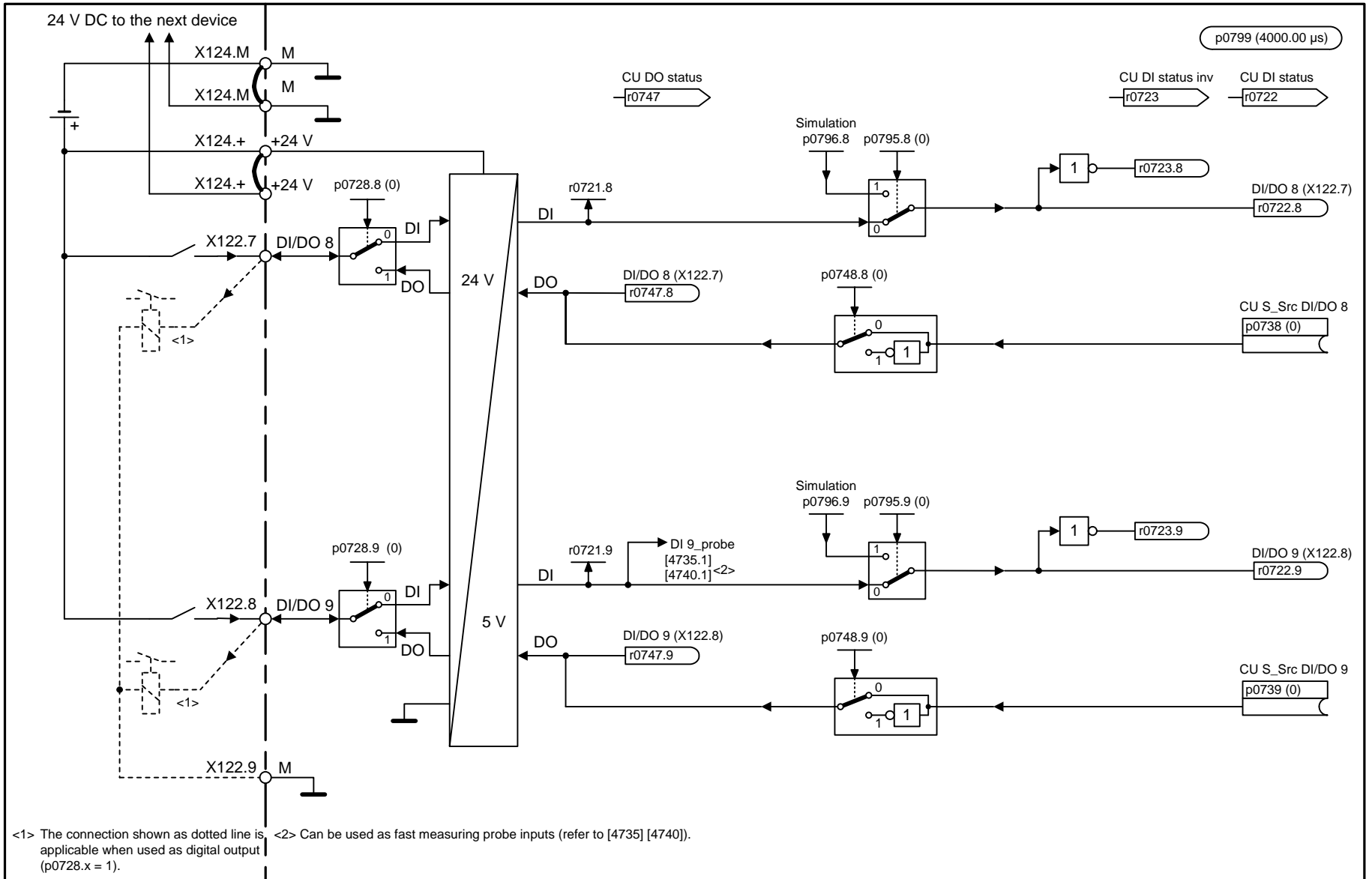
Figure 2-28 2120 – Digital inputs, electrically isolated (DI 0 ... DI 3)



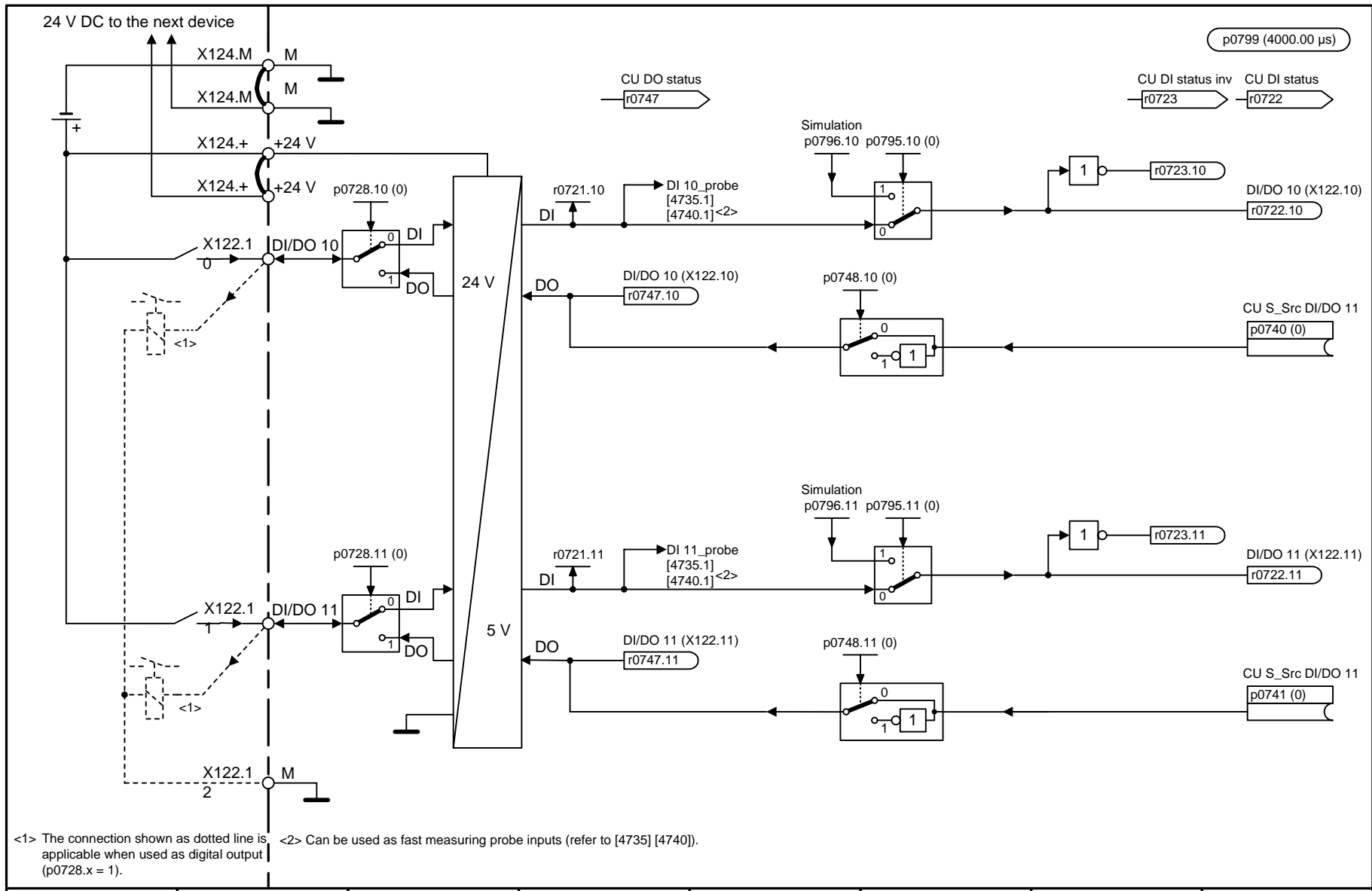
1	2	3	4	5	6	7	8
DO: CU_S					fp_2121_01_eng.vsd	Function diagram	
CU320 input/output terminals - digital inputs are electrically isolated (DI 4 ... DI 7)					14.12.05 V02.04.00	SINAMICS S	
							- 2121 -

Figure 2-29 2121 – Digital inputs, electrically isolated (DI 4 ... DI 7)

Figure 2-30 2130 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)



1	2	3	4	5	6	7	8
DO: CU_S					fp_2130_01_eng.vsd	Function diagram	
CU320 input/output terminals - digital inputs/outputs bidirectional (DI/DO 8 ... DI/DO 9)					31.03.05 V02.04.00	SINAMICS S	
							- 2130 -

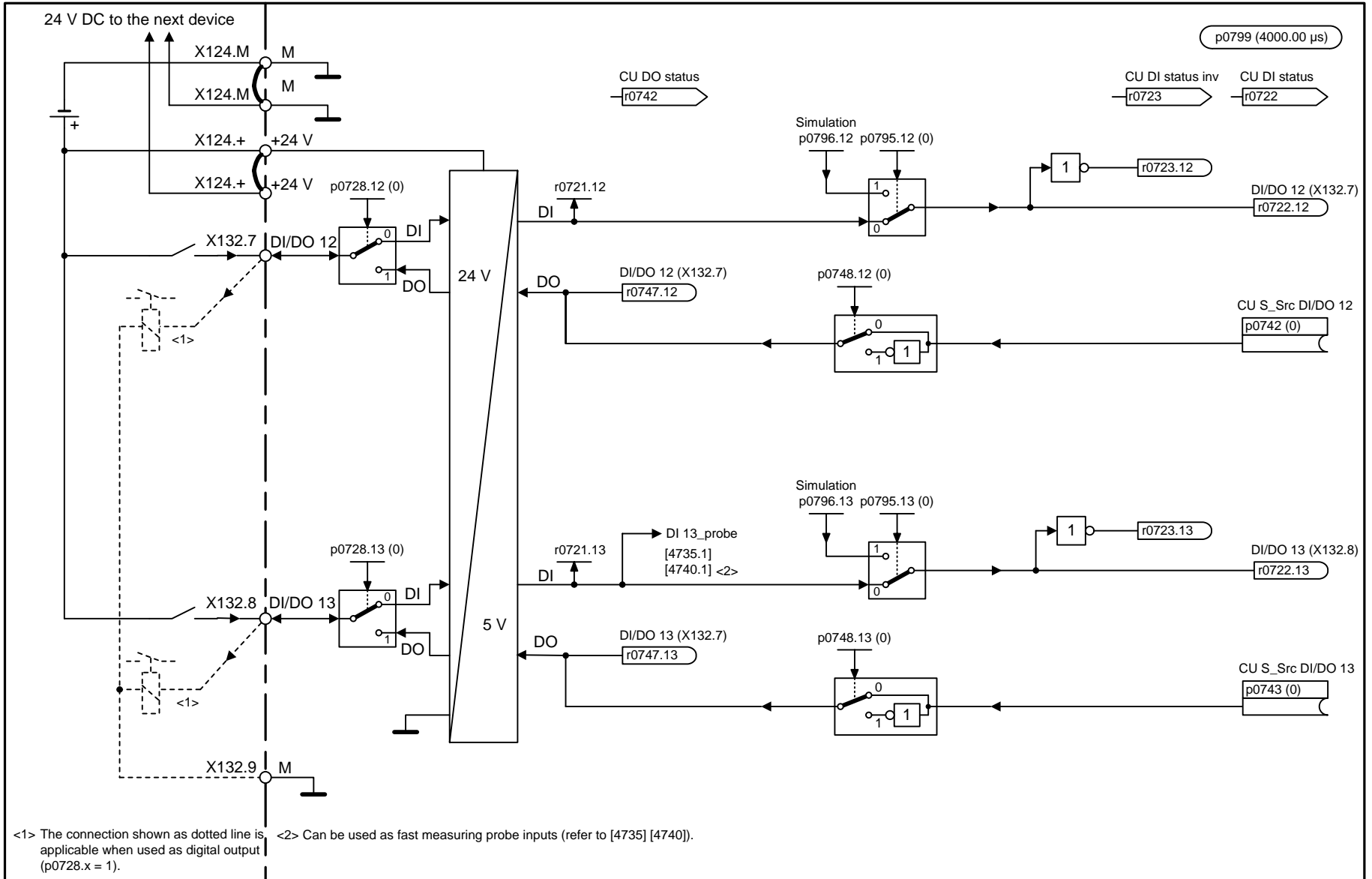


<1> The connection shown as dotted line is applicable when used as digital output (p0728.x = 1).
<2> Can be used as fast measuring probe inputs (refer to [4735] [4740]).

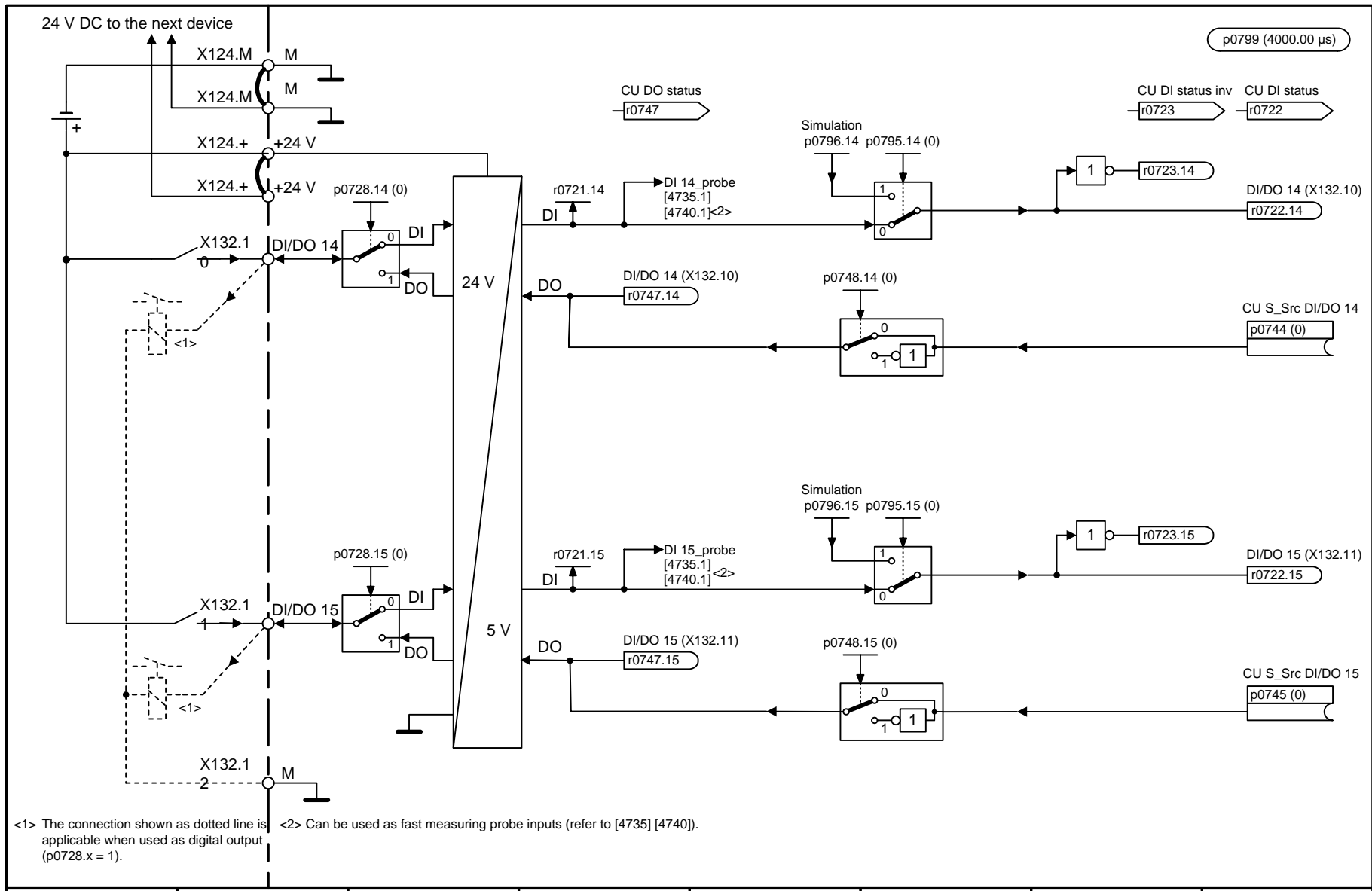
1	2	3	4	5	6	7	8
DO: CU_S					fp_2131_01_eng.vsd	Function diagram	
CU320 input/output terminals - digital inputs/outputs bidirectional (DI/DO 10 ... DI/DO 11)					31.03.05 V02.04.00	SINAMICS S	
							- 2131 -

Figure 2-31 2131 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)

Figure 2-32 2132 – Digital inputs/outputs, bidirectional (DI/DO 12 ... DI/DO 13)



1	2	3	4	5	6	7	8
DO: CU_S					fp_2132_01_eng.vsd	Function diagram	
CU320 input/output terminals - digital inputs/outputs bidirectional (DI/DO 12 ... DI/DO 13)					31.03.05 V02.04.00	SINAMICS S	
							- 2132 -



<1> The connection shown as dotted line is applicable when used as digital output (p0728.x = 1).
 <2> Can be used as fast measuring probe inputs (refer to [4735] [4740]).

1	2	3	4	5	6	7	8
DO: CU_S					fp_2133_01_eng.vsd	Function diagram	
CU320 input/output terminals - digital inputs/outputs bidirectional (DI/DO 14 ... DI/DO 15)					31.03.05 V02.04.00	SINAMICS S	
- 2133 -							

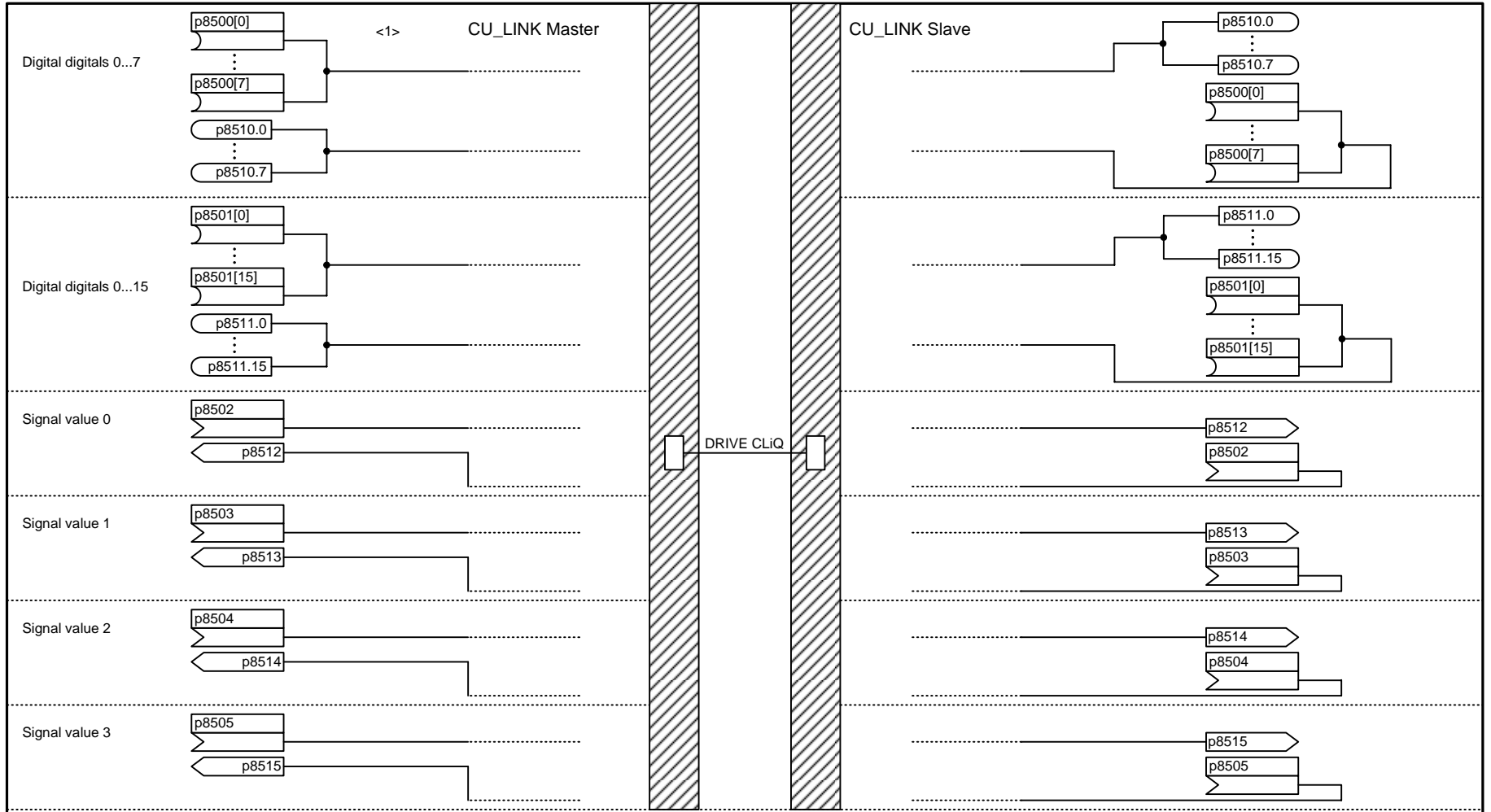
Figure 2-33 2133 – Digital inputs/outputs, bidirectional (DI/DO 14 ... DI/DO 15)

2.6 CU_LINK

Function diagrams

2211 – Data transfer

2-952



<1> The drive object CU_LINK only exists for automation systems with integrated SINAMICS functionality (e.g. SIMOTION D, SINUMERIK NCU) and the corresponding expansion components (e.g. CX32, NX10). The CU_LINK master functionality is available on the automation system, the CU_LINK slave functionality is available on the expansion components.

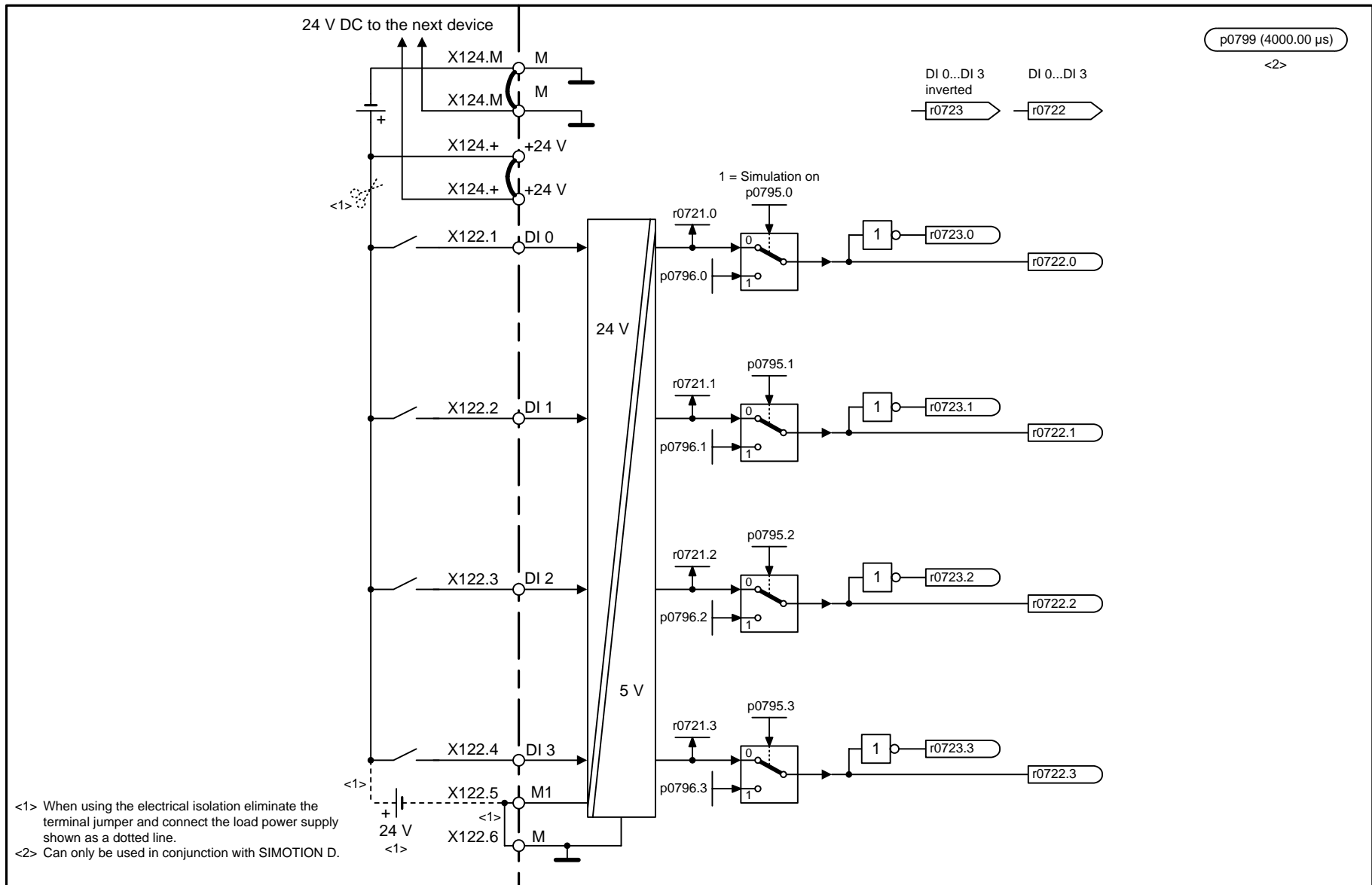
Figure 2-34 2211 – Data transfer

1	2	3	4	5	6	7	8
DO: CU_LINK					fp_2211_01_eng.vsd	Function diagram	
CU_LINK - data transfer					14.02.06 V02.04.00	SINAMICS S	
							- 2211 -

2.7 CX32 input/output terminals

Function diagrams

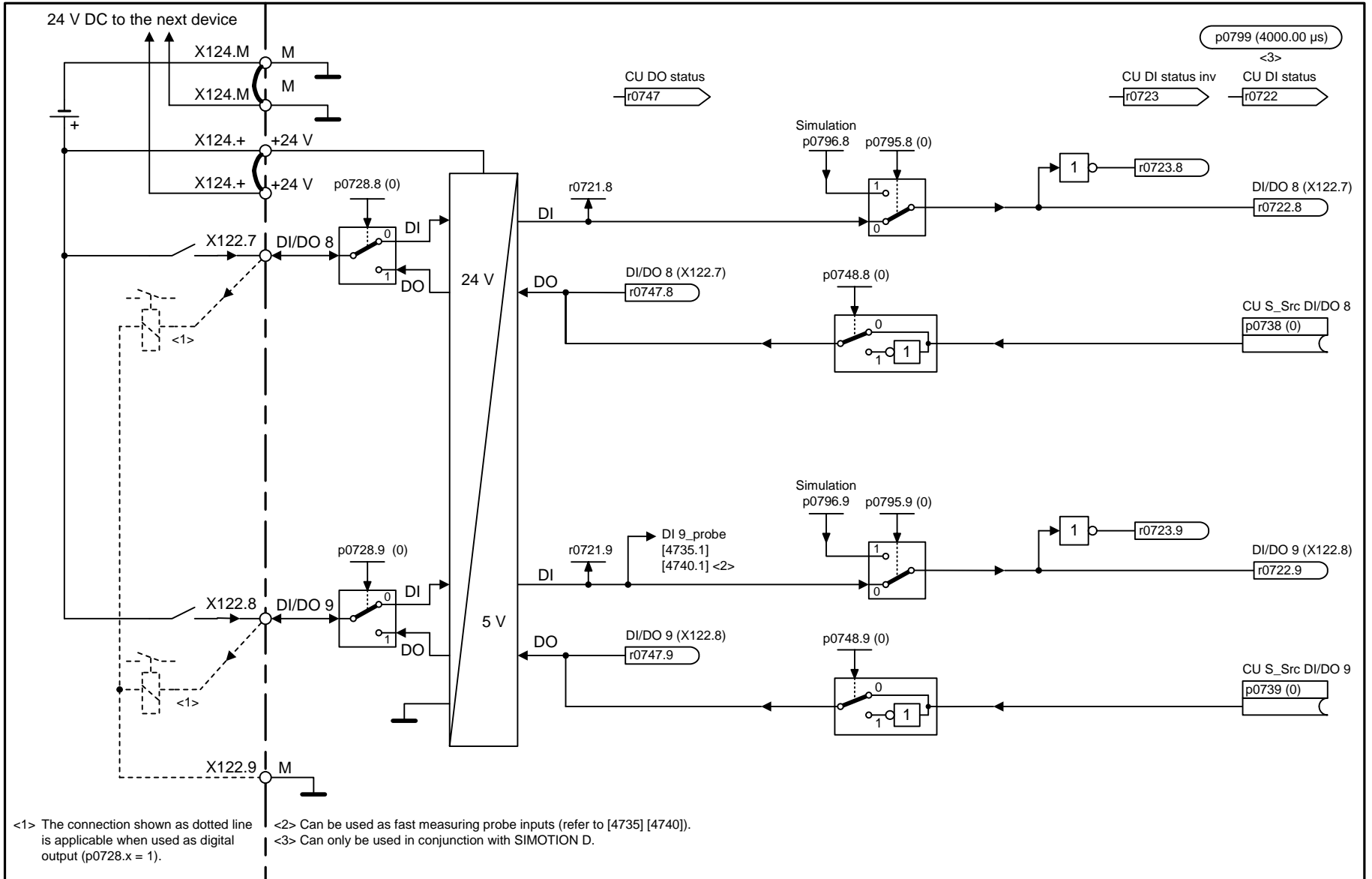
2220 – Digital inputs, electrically isolated (DI 0 ... DI 3)	2-954
2230 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)	2-955
2231 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)	2-956



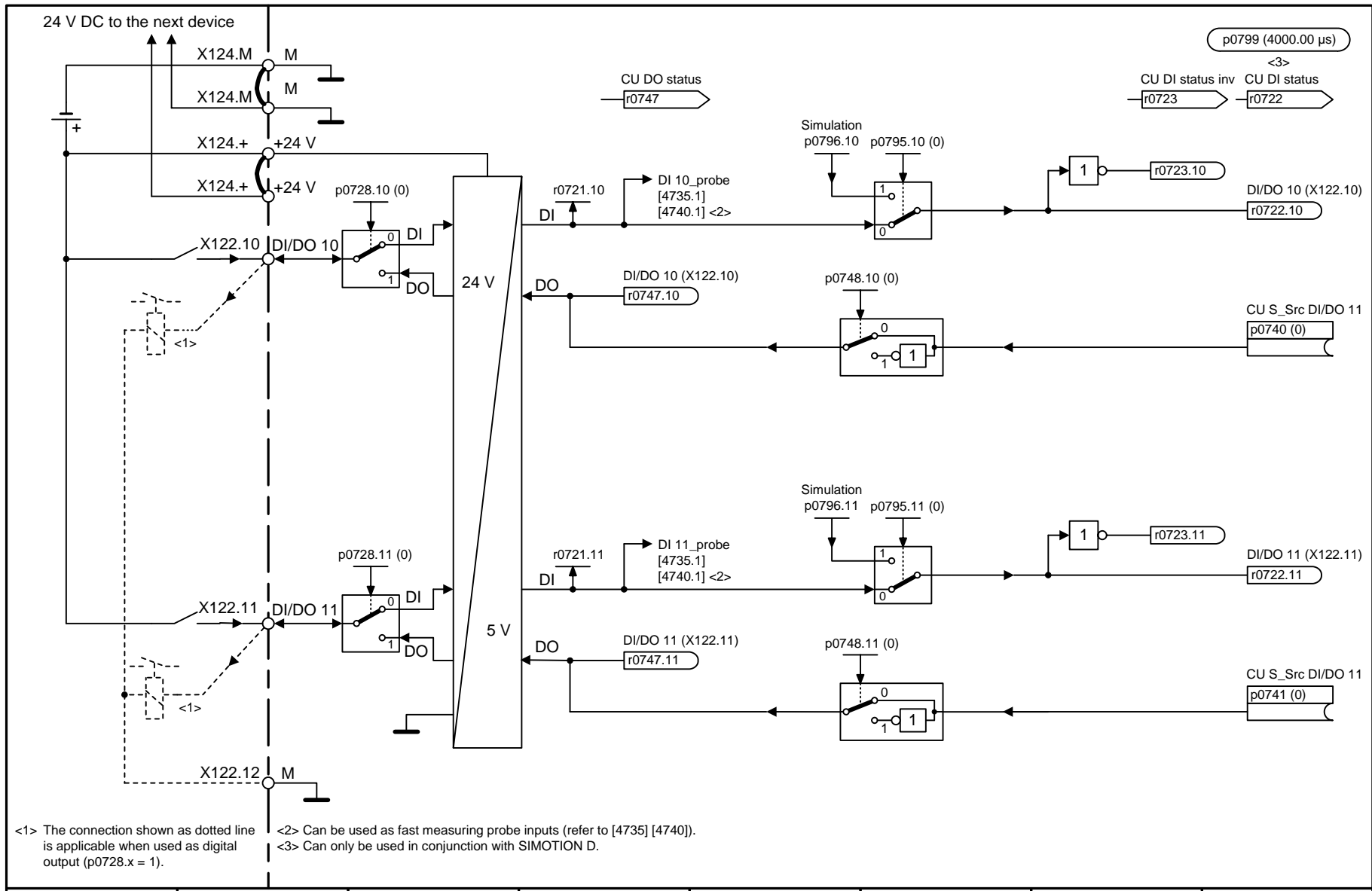
1	2	3	4	5	6	7	8
DO: CX32					fp_2220_01_eng.vsd	Function diagram	
CX32 input/output terminals – digital inputs are electrically isolated (DI 0 ... DI 3)					14.02.06 V02.04.00	SINAMICS S	
							- 2220 -

Figure 2-35 2220 – Digital inputs, electrically isolated (DI 0 ... DI 3)

Figure 2-36 2230 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)



1	2	3	4	5	6	7	8
DO: CX32					fp_2230_01_eng.vsd	Function diagram	
CX32 input/output terminals - digital inputs/outputs bidirectional (DI/DO 8 ... DI/DO 9)					14.02.06 V02.04.00	SINAMICS S	
							- 2230 -



<1> The connection shown as dotted line is applicable when used as digital output (p0728.x = 1).
 <2> Can be used as fast measuring probe inputs (refer to [4735] [4740]).
 <3> Can only be used in conjunction with SIMOTION D.

1	2	3	4	5	6	7	8
DO: CX32					fp_2231_01_eng.vsd	Function diagram	
CX32 input/output terminals - digital inputs/outputs bidirectional (DI/DO 10 ... DI/DO 11)					14.02.06 V02.04.00	SINAMICS S	
- 2231 -							

Figure 2-37 2231 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)

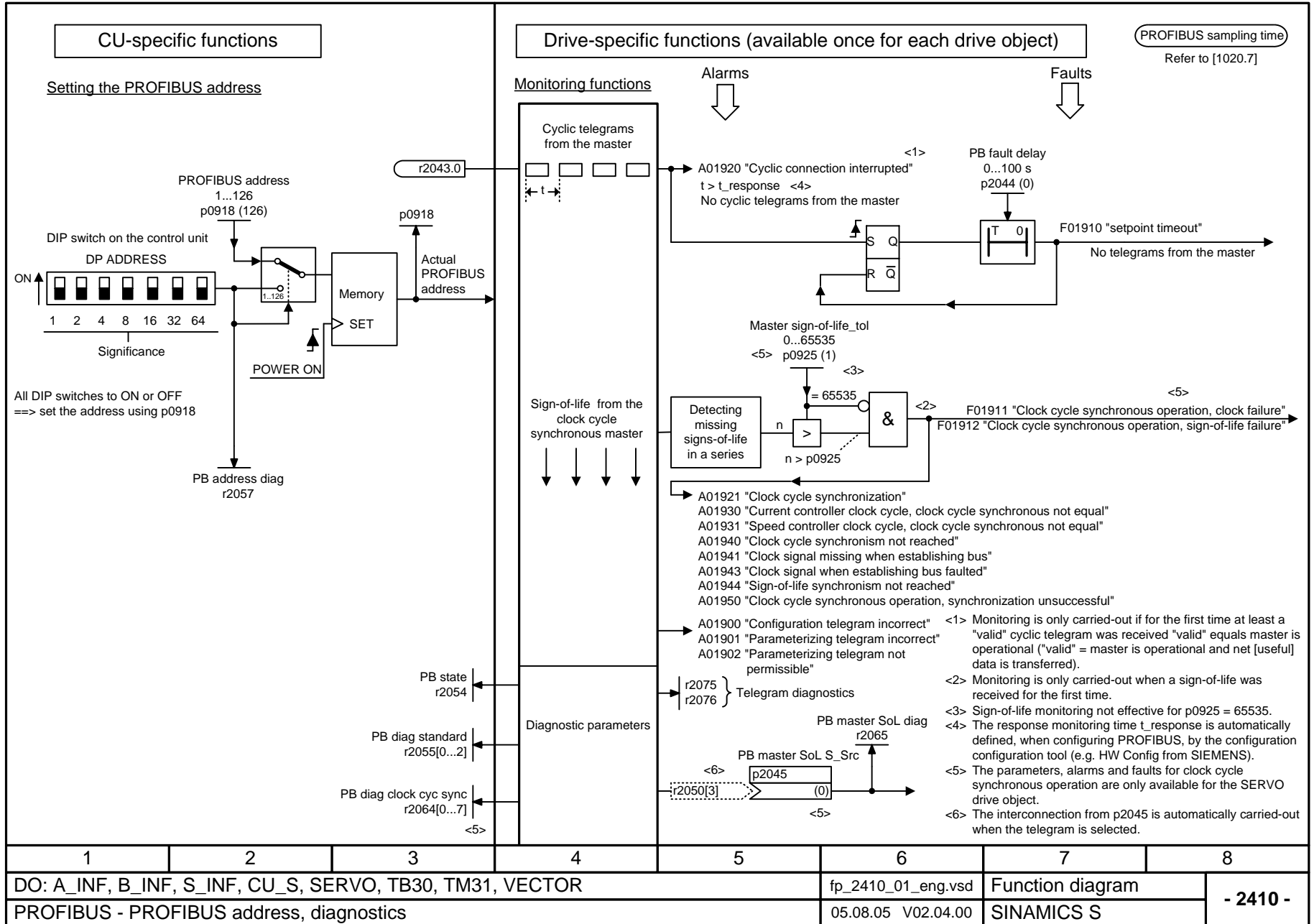
2.8 PROFIBUS

Function diagrams

2410 – PROFIBUS address, diagnostics	2-959
2420 – Telegrams and process data	2-960
2440 – PZD receive signals interconnection	2-961
2441 – STW1 control word interconnection (p2038 = 2)	2-962
2442 – STW1 control word interconnection (p2038 = 0)	2-963
2443 – STW1 control word interconnection (p2038 = 1)	2-964
2444 – STW2 control word interconnection (p2038 = 0)	2-965
2445 – STW2 control word interconnection (p2038 = 1)	2-966
2447 – E_STW1 control word infeed interconnection	2-967
2448 – CU_STW control word Control Unit interconnection	2-968
2449 – A_DIGITAL interconnection	2-969
2450 – PZD send signals interconnection	2-970
2451 – ZSW1 status word interconnection (p2038 = 2)	2-971
2452 – ZSW1 status word interconnection (p2038 = 0)	2-972
2453 – ZSW1 status word interconnection (p2038 = 1)	2-973
2454 – ZSW2 status word interconnection (p2038 = 0)	2-974
2455 – ZSW2 status word interconnection (p2038 = 1)	2-975
2456 – MELDW status word interconnection	2-976
2457 – E_ZSW1 status word infeed interconnection	2-977
2458 – CU_ZSW status word Control Unit interconnection	2-978
2459 – E_DIGITAL interconnection	2-979
2460 – Receive telegram, free interconnection via BICO (p0922 = 999)	2-980
2470 – Send telegram, free interconnection via BICO (p0922 = 999)	2-981
2472 – Status words, free interconnection	2-982
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2476 – SATZANW pos block select interconnection (r0108.4 = 1)	2-984
2477 – PosSTW pos control word interconnection (r0108.4 = 1)	2-985

2479 – ZSW1 status word 1 interconnection (r0108.4 = 1)	2-986
2481 – Receive telegram, free interconnection via BICO (p0922 = 999)	2-987
2483 – Send telegram, free interconnection via BICO (p0922 = 999)	2-988

Figure 2-38 2410 – PROFIBUS address, diagnostics



1	2	3	4	5	6	7	8
DO: A_INF, B_INF, S_INF, CU_S, SERVO, TB30, TM31, VECTOR					fp_2410_01_eng.vsd	Function diagram	
PROFIBUS - PROFIBUS address, diagnostics					05.08.05 V02.04.00	SINAMICS S	
							- 2410 -

Figure 2-39 2420 – Telegrams and process data

Telegram selection <1> p0922 (999) <2>		PROFIBUS sampling time Refer to [1020.7]																								
Interconnection is made according to	Telegram	Appl. class	Function in the drive	PZD 01	PZD 02	PZD 03	PZD 04	PZD 05	PZD 06	PZD 07	PZD 08	PZD 09	PZD 10	PZD 11	PZD 12	PZD 13	PZD 14	PZD 15	PZD 16	PZD 17	PZD 18	PZD 19				
Standard telegrams	[2440] [2450] auto- matic- ally	1	1	Speed control, 2 words	STW1 ZSW1	NSOLL_A NIST_A	← Receive telegram from PROFIBUS → Send telegram to PROFIBUS																			
		2	1	Speed control, 4 words	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	= Position encoder signal																		
		3	1, 4	Speed control, 1 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	G1_STW G1_ZSW	G1_XIST1	G1_XIST2																
		4	1, 4	Speed control, 2 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	G1_STW G1_ZSW	G2_STW G1_XIST1	G1_XIST2	G2_ZSW	G2_XIST1	G2_XIST2													
		5	4 DSC	DSC, 1 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	G1_STW G1_ZSW	XERR	G1_XIST1	KPC	G1_XIST2														
		6	4 DSC	DSC, 2 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	G1_STW G1_ZSW	G2_STW G1_XIST1	XERR	G1_XIST2	KPC	G2_ZSW	G2_XIST1	G2_XIST2											
		7	3	Basic positioner	STW1 ZSW1	SATZANW AKTSATZ																				
Manufacturer-specific telegrams	[2440] [2450] auto- matic- ally	20	1	Closed-loop control, VIK-NAMUR	STW1 ZSW1	NSOLL_A NIST_A_GLATT	IAIST_GLATT	MIST_GLATT	PIST_GLATT	<4>																
		102	1, 4	Speed control with torque reduction, 1 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	MOMRED	G1_STW G1_ZSW	G1_XIST1	G1_XIST2															
		103	1, 4	Speed control with torque reduction, 2 position encoders	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	MOMRED	G1_STW G1_ZSW	G2_STW	G1_XIST1	G1_XIST2	G2_ZSW	G2_XIST1	G2_XIST2											
		105	4 DSC	DSC with torque reduction, 1 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	MOMRED	G1_STW G1_ZSW	XERR	G1_XIST1	KPC	G1_XIST2													
		106	4 DSC	DSC with torque reduction, 2 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	MOMRED	G1_STW G1_ZSW	G2_STW	XERR	G1_XIST1	KPC	G1_XIST2	G2_ZSW	G2_XIST1	G2_XIST2									
		110	3	Basic positioner	STW1 ZSW1	SATZANW AKTSATZ	PosSTW PosZSW	STW2 ZSW2	Over	MDIPos	XistP	MDIVel	MDIAcc	MDIDec	MDIMode											
		116	4 DSC	DSC with torque reduction, 2 position encoder	STW1 ZSW1	NSOLL_B NIST_B	STW2 ZSW2	MOMRED	G1_STW G1_ZSW	G2_STW	XERR	G1_XIST1	KPC	G1_XIST2	G2_ZSW	G2_XIST1	G2_XIST2	AACT_GL	MSET_GL	FACT_GL	ITACT_GL	GL = SMOOTH				
		352	1	Closed-loop speed control, PCS7	STW1 ZSW1	NSOLL_A NIST_A_GLATT	<5>	<5>	<5>	<5>																
		370	-	Infeed, 1 word	E_STW1 E_ZSW1																					
		390	-	CU (DO1), digital inputs/outputs	CU_STW CU_ZSW	A_DIGITAL E_DIGITAL																				
391	-	CU (DO1), digital inputs/outputs and measuring probe	CU_STW CU_ZSW	A_DIGITAL E_DIGITAL	MT_STW MT_ZSW	MT1_ZS_F	MT1_ZS_S	MT2_ZS_F	MT2_ZS_S																	
Free telegram	[2460] [2470]	999	-	Free interconnection via BICO	STW1<3> ZSW1<3>	Receive telegram length can be freely selected via the central PROFIBUS configuring in the master																				
							Send telegram length can be freely selected via the central PROFIBUS configuring in the master																			

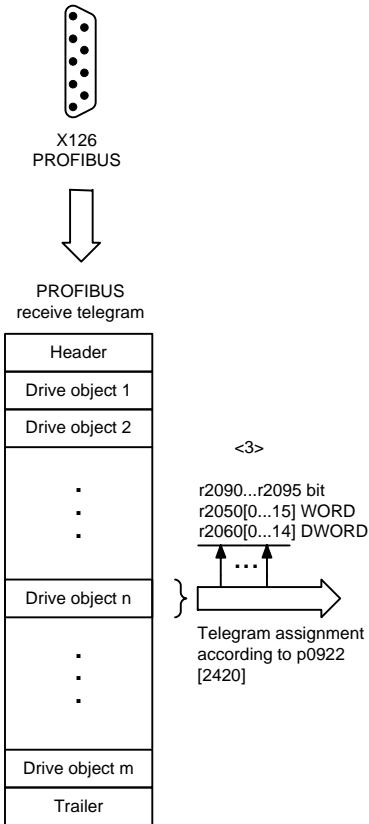
<1> Depending on the drive object, only specific telegrams can be used.
 <2> When p0922 = 999 is changed to another value, the telegram is automatically assigned according to [2420].
 If p0922 is not equal to 999 and is changed to p0922 = 999, the "old" telegram assignment is kept according to [2420]!
 <3> In order to be in compliance with the PROFIdrive profile, PZD1 must be used as control word 1 (STW1) or status word 1 (ZSW1).
 p2037 should be set to 2 if STW1, with PZD1, is not transferred according to the PROFIdrive profile.
 <4> Freely interconnectable (pre-setting: MELD_NAMUR).
 <5> Can be freely connected.

1	2	3	4	5	6	7	8
DO: A_INF, B_INF, CU_S, S_INF, SERVO, VECTOR					fp_2420_01_eng.vsd	Function diagram	
PROFIBUS - telegrams and process data					27.03.06 V02.04.00	SINAMICS S	
							- 2420 -

PROFIBUS sampling time

Refer to [1020.7]

Figure 2-40 2440 – PZD receive signals interconnection



Signal receivers for PZD receive signals		<1>		<2>		
Signal	Meaning	PROFdrive Signal No.	Interconnection parameter	Function diagram	Data type	Normalization
STW1	Control word 1 for telegram 1 ... 106, 110, 116	1	(bit serial)	[2442][2443] [2475]	U16	-
STW2	Control word 2 for telegram 2 ... 6, 8 ... 19, 21 ... 106, 110, 116	3	(bit serial)	[2444] [2445]	U16	-
NSOLL_A	Speed setpoint A (16-bit)	5	p1070	[3030.2]	I16	4000 hex $\hat{=}$ p2000
NSOLL_B	Speed setpoint B (32-bit)	7	p1155 p1430 (DSC)	[3080.4] [3090.8]	I32	4000 0000 hex $\hat{=}$ p2000
G1_STW	Encoder 1 control word	9	p0480[0]	[4720]	U16	
G2_STW	Encoder 2 control word	13	p0480[1]	[4720]	U16	
G3_STW	Encoder 3 control word	17	p0480[2]	[4720]	U16	
A_DIGITAL	Digital outputs	22	(bit serial)	[2449]	U16	
XERR	Position deviation	25	p1190	[3090.5]	I32	
KPC	Position controller gain factor	26	p1191	[3090.5]	I32	
MOMRED	Torque reduction	101	p1542	[5610.2]	I16	4000 hex $\hat{=}$ p2003
MT_STW	Measuring probe control word	130	p0682	-	U16	
SATZANW	Pos block selection	201	(bit serial)	[2476]	U16	
PosSTW	Pos control word	203	(bit serial)	[2477]	U16	
Over	Pos velocity override	205	p2646	[3630]	I16	4000 hex $\hat{=}$ 100%
MDIPos	Pos MDI position	221	p2642	[3618]	I32	1 hex $\hat{=}$ 1 LU
MDIVel	Pos MDI velocity	223	p2643	[3618]	I32	1 hex $\hat{=}$ 1000 LU/min
MDIAcc	Pos MDI acceleration override	225	p2644	[3618]	I16	4000 hex $\hat{=}$ 100%
MDIDec	Pos MDI deceleration override	227	p2645	[3618]	I16	4000 hex $\hat{=}$ 100%
MDIMode	Pos MDI mode	229	p2654	[3620]	U16	
E_STW1	INFEED control word	320	(bit serial)	[2447]	U16	
CU_STW	Control Unit control word	500	(bit serial)	[2448]	U16	

- <1> When selecting a standard telegram or a manufacturer-specific telegram using p0922, these interconnection parameters of the command data set CDS are automatically set to 0.
- <2> Data type according to to the PROFdrive profile: I16 = Integer16, I32 = Integer32, U16 = Unsigned16, U32 = Unsigned32.
- <3> Display parameters for receive data according to [2460].

1	2	3	4	5	6	7	8
DO: A_INF, B_INF, S_INF, SERVO, VECTOR					fp_2440_01_eng.vsd	Function diagram	
PROFIBUS – PZD receive signals interconnection					16.03.06 V02.04.00	SINAMICS S	
							- 2440 -

Function diagrams
PROFIBUS

PROFIBUS sampling time
Refer to [1020.7]

Signal targets for STW1 (Interface Mode PROFIdrive VIK-NAMUR, p2038 = 2) <1>

Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
STW1.0	1 = ON (pulses can be enabled) 0 = OFF1 (braking with ramp-function generator, then pulse cancellation & ready-to-power-up)	p0840[0] = r2090.0	[2501.3]	[2610]	-
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse cancellation and power-on inhibit)	p0844[0] = r2090.1	[2501.3]	[2610]	-
STW1.2	1 = No OFF3 (enable possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse cancellation and power-on inhibit)	p0848[0] = r2090.2	[2501.3]	[2610]	-
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (cancel pulses)	p0852[0] = r2090.3	[2501.3]	[2610]	-
STW1.4	1 = Operating condition (the ramp-function generator can be enabled) 0 = Inhibit ramp-function generator (set the ramp-function generator output to zero)	p1140[0] = r2090.4	[2501.3]	[3060] [3070] [3080]	-
STW1.5	1 = Enable the ramp-function generator 0 = Stop the ramp-function generator (freeze the ramp-function generator output)	p1141[0] = r2090.5	[2501.3]	[3060] [3070]	-
STW1.6	1 = Enable setpoint 0 = Inhibit setpoint (set the ramp-function generator input to zero)	p1142[0] = r2090.6	[2501.3]	[3060] [3070] [3080]	-
STW1.7	1 = Acknowledge faults	p2103[0] = r2090.7	[2546.1]	[8060]	-
STW1.8	Reserved	-	-	-	-
STW1.9	Reserved	-	-	-	-
STW1.10	1 = Control via PLC <2>	p0854[0] = r2090.10	[2501.3]	[2501]	-
STW1.11	1 = Dir of rot reversal	p1113[0] = r2090.11	[2505.3]	[3040]	-
STW1.12	Reserved	-	-	-	-
STW1.13	Reserved	-	-	-	-
STW1.14	Reserved	-	-	-	-
STW1.15	1 = CDS selection	p0810[0] = 2090.15	-	[8565]	-

<1> Used in telegram 20.

<2> Bit 10 must be set in the first PZD word of the telegram received from PROFIBUS in order that the drive accepts the process data.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2441_01_eng.vsd	Function diagram	
PROFIBUS - STW1 control word interconnection (p2038 = 2)					10.03.05 V02.04.00	SINAMICS S	
							- 2441 -

Figure 2-41 2441 – STW1 control word interconnection (p2038 = 2)

Figure 2-42 2442 – STW1 control word interconnection (p2038 = 0)

Signal targets for STW1 (Interface Mode SINAMICS/MICROMASTER, p2038 = 0)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted	
STW1.0	= ON (pulses can be enabled) 0 = OFF1 (braking with ramp-function generator, then pulse cancellation and ready-to-power-up)	p0840[0] = r2090.0	[2501.3]	[2610]	-	
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse cancellation and power-on inhibit)	p0844[0] = r2090.1	[2501.3]	[2610]	-	
STW1.2	1 = No OFF3 (enable possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse cancellation and power-on inhibit)	p0848[0] = r2090.2	[2501.3]	[2610]	-	
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (cancel pulses)	p0852[0] = r2090.3	[2501.3]	[2610]	-	
STW1.4	1 = Operating condition (the ramp-function generator can be enabled) 0 = inhibit ramp-function generator (set the ramp-function generator output to zero)	p1140[0] = r2090.4	[2501.3]	[3060] [3070] [3080]	-	
STW1.5	1 = Enable the ramp-function generator 0 = stop the ramp-function generator (freeze the ramp-function generator output)	p1141[0] = r2090.5	[2501.3]	[3060] [3070]	-	
STW1.6	1 = Enable setpoint 0 = inhibit setpoint (set the ramp-function generator input to zero)	p1142[0] = r2090.6	[2501.3]	[3060] [3070] [3080]	-	
STW1.7	= Acknowledge faults	p2103[0] = r2090.7	[2546.1]	[8060]	-	
STW1.8	Reserved	-	-	-	-	
STW1.9	Reserved	-	-	-	-	
STW1.10	1 = Control via PLC <2>	p0854[0] = r2090.10	[2501.3]	[2501]	-	
STW1.11	1 = Dir of rot reversal <3>	p1113[0] = r2090.11	[2505.3]	[3040]	-	
STW1.12	Reserved	-	-	-	-	
STW1.13	1 = Motorized potentiometer, setpoint, raise <3>	p1035[0] = r2090.13	[2505.3]	[3020]	-	
STW1.14	1 = Motorized potentiometer, setpoint, lower <3>	p1036[0] = r2090.14	[2505.3]	[3020]	-	
STW1.15	Reserved	-	-	-	-	

PROFIBUS sampling time
Refer to [1020.7]

<1> Used in telegram 1, 2, 3, 4, 5, 6, 7, 110, 352.

<2> Bit 10 must be set in the first PZD word of the telegram received from PROFIBUS in order that the drive accepts the process data.

<3> Only for "expanded setpoint channel" and "expanded ramp-function generator"

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2442_01_eng.vsd	Function diagram	
PROFIBUS - STW1 control word interconnection (p2038 = 0)					23.03.06 V02.04.00	SINAMICS S	
							- 2442 -

PROFIBUS sampling time
Refer to [1020.7]

Signal targets for STW1 (Interface Mode SIMODRIVE 611 universal, p2038 = 1) <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
STW1.0	= ON (pulses can be enabled) 0 = OFF1 (braking with ramp-function generator, then pulse cancellation, ready-to-power-up)	p0840[0] = r2090.0	[2501.3]	[2610]	-
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse cancellation and power-on inhibit)	p0844[0] = r2090.1	[2501.3]	[2610]	-
STW1.2	1 = No OFF3 (enable possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse cancellation and power-on inhibit)	p0848[0] = r2090.2	[2501.3]	[2610]	-
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (cancel pulses)	p0852[0] = r2090.3	[2501.3]	[2610]	-
STW1.4	1 = Operating condition (the ramp-function generator can be enabled) 0 = Inhibit ramp-function generator (set the ramp-function generator output to zero)	p1140[0] = r2090.4	[2501.3]	[3060] [3070] [3080]	-
STW1.5	1 = Enable the ramp-function generator 0 = Stop the ramp-function generator (freeze the ramp-function generator output)	p1141[0] = r2090.5	[2501.3]	[3060] [3070]	-
STW1.6	1 = Enable setpoint 0 = Inhibit setpoint (set the ramp-function generator input to zero)	p1142[0] = r2090.6	[2501.3]	[3060] [3070] [3080]	-
STW1.7	= Acknowledge faults	p2103[0] = r2090.7	[2546.1]	[8060]	-
STW1.8	Reserved	-	-	-	-
STW1.9	Reserved	-	-	-	-
STW1.10	1 = Control via PLC <2>	p0854[0] = r2090.10	[2501.3]	[2501]	-
STW1.11	1 = Ramp-function generator active	p2148[0] = r2090.11	-	[8010]	-
STW1.12	1 = Unconditionally open the holding brake	p0855[0] = r2090.12	[2501.3]	[2701]	-
STW1.13	Reserved	-	-	-	-
STW1.14	1 = Closed-loop torque control active 0 = Closed-loop speed control active	p1501[0] = r2090.14	[2520.3]	[5060] [6060]	-
STW1.15	Reserved	-	-	-	-

<1> Used in telegram 1, 2, 3, 4, 5, 6, 102, 103, 105, 106, 116, 352.

<2> Bit 10 must be set in the first PZD word of the telegram received from PROFIBUS in order that the drive accepts the process data.

1	2	3	4	5	6	7	8
DO: SERVO					fp_2443_01_eng.vsd	Function diagram	
PROFIBUS - STW1 control word interconnection (p2038 = 1)					23.03.06 V02.04.00	SINAMICS S	
							- 2443 -

Figure 2-43 2443 – STW1 control word interconnection (p2038 = 1)

Figure 2-44 2444 – STW2 control word interconnection (p2038 = 0)

Signal targets for STW2 (Interface Mode SINAMICS/MICROMASTER, p2038 = 0) <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
STW2.0	Drive data set selection DDS, bit 0	p0820[0] = r2093.0	-	[8565]	-
STW2.1	Drive data set selection DDS, bit 1	p0821[0] = r2093.1	-	[8565]	-
STW2.2	Drive data set selection DDS, bit 2	p0822[0] = r2093.2	-	[8565]	-
STW2.3	Drive data set selection DDS, bit 3	p0823[0] = r2093.3	-	[8565]	-
STW2.4	Drive data set selection DDS, bit 4	p0824[0] = r2093.4	-	[8565]	-
STW2.5	Reserved	-	-	-	-
STW2.6	Reserved	-	-	-	-
STW2.7	1 = Parking axis	p0897 = r2093.7	-	-	-
STW2.8	1 = Traverse to fixed endstop	p1545[0] = r2093.8	[2520.2]	[8012]	-
STW2.9	Reserved	-	-	-	-
STW2.10	Reserved	-	-	-	-
STW2.11	1 = Motor changeover, feedback Signal	p0828 = r2093.11	-	-	-
STW2.12	Master sign-of-life, bit 0	p2045 = r2050[3]	-	[2410]	-
STW2.13	Master sign-of-life, bit 1	p2045 = r2050[3]	-	[2410]	-
STW2.14	Master sign-of-life, bit 2	p2045 = r2050[3]	-	[2410]	-
STW2.15	Master sign-of-life, bit 3	p2045 = r2050[3]	-	[2410]	-


PROFIBUS sampling time
Refer to [1020.7]

<1> Used in telegram 2, 3, 4, 5, 6, 110.

1	2	3	4	5	6	7	8
DO: SERVO					fp_2444_01_eng.vsd	Function diagram	
PROFIBUS - STW2 control word interconnection (p2038 = 0)					23.03.06 V02.04.00	SINAMICS S	
							- 2444 -

Function diagrams
PROFIBUS

PROFIBUS sampling time
Refer to [1020.7]

Signal targets for STW2 (Interface Mode SIMODRIVE 611 universal, p2038 = 1)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted	
STW2.0	Drive data set selection DDS, bit 0	p0820[0] = r2093.0	-	[8565]	-	
STW2.1	Drive data set selection DDS, bit 1	p0821[0] = r2093.1	-	[8565]	-	
STW2.2	Drive data set selection DDS, bit 2	p0822[0] = r2093.2	-	[8565]	-	
STW2.3	Reserved	-	-	-	-	
STW2.4	1 = Bypass ramp-function generator <3>	p1122[0] = r2093.4	-	[3060] [3070]	-	
STW2.5	Reserved	-	-	-	-	
STW2.6	1 = Integrator inhibit, speed controller <2>	p1477[0] = r2093.6	-	[5040] [5210]	-	
STW2.7	1 = Parking axis selection	p0897 = r2093.7	-	-	-	
STW2.8	1 = Traverse to fixed endstop	p1545[0] = r2093.8	[2520.2]	[8012]	-	
STW2.9	Drive data set selection DDS, bit 3	p0823[0] = r2093.9	-	[8565]	-	
STW2.10	Drive data set selection DDS, bit 4	p0824[0] = r2093.10	-	[8565]	-	
STW2.11	 Motor changeover, feedback signal	p0828 = r2093.11	-	-	-	
STW2.12	Master sign-of-life, bit 0	p2045 = r2050[3]	-	[2410]	-	
STW2.13	Master sign-of-life, bit 1	p2045 = r2050[3]	-	[2410]	-	
STW2.14	Master sign-of-life, bit 2	p2045 = r2050[3]	-	[2410]	-	
STW2.15	Master sign-of-life, bit 3	p2045 = r2050[3]	-	[2410]	-	

<1> Used in telegram 2, 3, 4, 5, 6, 102, 103, 105, 106, 116.
 <2> For a 1 signal, the integral component of the speed controller is deleted/cleared and the integrator is inhibited. <3> Only when the function module "expanded setpoint channel" is activated (r0108.8 = 1).

1	2	3	4	5	6	7	8
DO: SERVO					fp_2445_01_eng.vsd	Function diagram	
PROFIBUS - STW2 control word interconnection (p2038 = 1)					23.03.06 V02.04.00	SINAMICS S	
							- 2445 -

Figure 2-45 2445 – STW2 control word interconnection (p2038 = 1)

PROFIBUS sampling time

Refer to [1020.7]

Signal targets for E_STW1									
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word			[Function diagram] signal target			Inverted
			A_INF	B_INF	S_INF	A_INF	B_INF	S_INF	
STW1.0	ON (close pre-charging/line contactor, pulses can be enabled) 0 = OFF1 (reduce Vdc along a ramp, pulse cancellation & open pre-charging/line contactor)	p0840[0] = r2090.0	[8920.3]	[8720.3]	[8820.3]	[8932]	[8732]	[8832]	-
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse cancellation and power-on inhibit)	p0844[0] = r2090.1	[8920.3]	[8720.3]	[8820.3]	[8932]	[8732]	[8832]	-
STW1.2	Reserved		-	-	-	-	-	-	-
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (cancel pulses)	<3> p0852[0] = r2090.3	[8920.3]	-	[8820.3]	[8932]	-	[8832]	-
STW1.4	Reserved	-	-	-	-	-	-	-	-
STW1.5	1 = Inhibit motoring operation	<4> p3532= r2090.5	[8920.3]	-	-	[8920]	-	-	-
STW1.6	1 = Inhibit regenerative operation	<3> p3533= r2090.6	[8920.3]	-	[8820.3]	[8920]	-	[8820]	-
STW1.7	ACK = Acknowledge faults	p2103[0] = r2090.7	[2546.3]			[8060]			-
STW1.8	Reserved	-	-	-	-	-	-	-	-
STW1.9	Reserved	-	-	-	-	-	-	-	-
STW1.10	1 = Control via PLC	<2> p0854[0] = r2090.10	[8920.3]	[8720.3]	[8820.3]	[8920]	[8720]	[8820]	-
STW1.11	Reserved	-	-	-	-	-	-	-	-
STW1.12	Reserved	-	-	-	-	-	-	-	-
STW1.13	Reserved	-	-	-	-	-	-	-	-
STW1.14	Reserved	-	-	-	-	-	-	-	-
STW1.15	Reserved	-	-	-	-	-	-	-	-

<1> Used in telegram 370.
 <2> Bit 10 must be set in the first PZD word of the telegram received from PROFIBUS in order that the drive object accepts the process data.
 <3> Only for A_INF, S_INF
 <4> Only for A_INF

1	2	3	4	5	6	7	8	
DO: A_INF, B_INF, S_INF					fp_2447_01_eng.vsd	Function diagram		- 2447 -
PROFIBUS - E_STW1 control word infeed interconnection					17.05.05 V02.04.00	SINAMICS S		

Function diagrams
PROFIBUS

Figure 2-46 2447 – E_STW1 control word infeed interconnection

PROFIBUS sampling time
Refer to [1020.7]

Signal targets for CU_STW <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
CU_STW.0	Synchronisation	p0681[0] = r2090.0	-	-	-
CU_STW.1	Reserved	-	-	-	-
CU_STW.2	Reserved	-	-	-	-
CU_STW.3	Reserved	-	-	-	-
CU_STW.4	Reserved	-	-	-	-
CU_STW.5	Reserved	-	-	-	-
CU_STW.6	Reserved	-	-	-	-
CU_STW.7	Acknowledge faults	p2103[0] = r2090.7	-	-	-
CU_STW.8	Reserved	-	-	-	-
CU_STW.9	Reserved	-	-	-	-
CU_STW.10	Reserved	-	-	-	-
CU_STW.11	Reserved	-	-	-	-
CU_STW.12	Master sign-of-life, Bit 0	p2045[0] = r2050[0]	-	-	-
CU_STW.13	Master sign-of-life, Bit 1	p2045[0] = r2050[0]	-	-	-
CU_STW.14	Master sign-of-life, Bit 2	p2045[0] = r2050[0]	-	-	-
CU_STW.15	Master sign-of-life, Bit 3	p2045[0] = r2050[0]	-	-	-

<1> Used in telegram 390 and 391.

1	2	3	4	5	6	7	8
DO: CU_S					fp_2448_01_eng.vsd	Function diagram	
PROFIBUS - CU_STW control word Control Unit interconnection					23.03.06 V02.04.00	SINAMICS S	
							- 2448 -

Figure 2-47 2448 – CU_STW control word Control Unit interconnection

Figure 2-48 2449 – A_DIGITAL interconnection

Signal targets for A_DIGITAL						<1>
Signal	Meaning		Interconnection parameters <3>	[Function diagram] internal status word	[Function diagram] signal target	Inverted
A_DIGITAL.0	Digital output 8 (DI/DO 8)	<2>	p0738[0] = r2091[0]	-	-	-
A_DIGITAL.1	Digital output 9 (DI/DO 9)	<2>	p0739[0] = r2091[1]	-	-	-
A_DIGITAL.2	Digital output 10 (DI/DO 10)	<2>	p0740[0] = r2091[2]	-	-	-
A_DIGITAL.3	Digital output 11 (DI/DO 11)	<2>	p0741[0] = r2091[3]	-	-	-
A_DIGITAL.4	Digital output 12 (DI/DO 12)	<2>	p0742[0] = r2091[4]	-	-	-
A_DIGITAL.5	Digital output 13 (DI/DO 13)	<2>	p0743[0] = r2091[5]	-	-	-
A_DIGITAL.6	Digital output 14 (DI/DO 14)	<2>	p0744[0] = r2091[6]	-	-	-
A_DIGITAL.7	Digital output 15 (DI/DO 15)	<2>	p0745[0] = r2091[7]	-	-	-
A_DIGITAL.8	Reserved		-	-	-	-
A_DIGITAL.9	Reserved		-	-	-	-
A_DIGITAL.10	Reserved		-	-	-	-
A_DIGITAL.11	Reserved		-	-	-	-
A_DIGITAL.12	Reserved		-	-	-	-
A_DIGITAL.13	Reserved		-	-	-	-
A_DIGITAL.14	Reserved		-	-	-	-
A_DIGITAL.15	Reserved		-	-	-	-

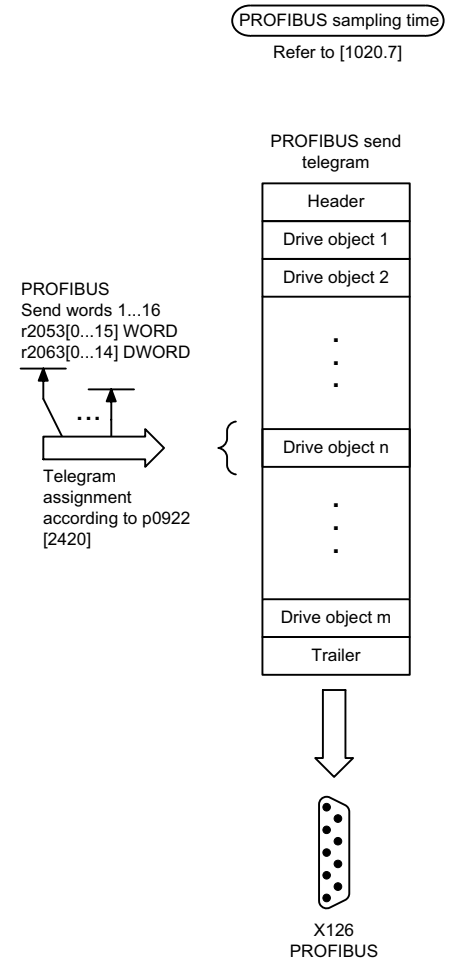
PROFIBUS sampling time
Refer to [1020.7]

<1> Used in telegram 390 and 391. <2> Can be set via p0728 as input (DI) or output (DO). <3> Pre-assignment, can be freely changed.

1	2	3	4	5	6	7	8
DO: CU_S				fp_2449_01_eng.vsd		Function diagram	
PROFIBUS - A_DIGITAL interconnection				23.03.06 V02.04.00		SINAMICS S	
							- 2449 -

Function diagrams
PROFIBUS

Signal sources for PZD send signals <1>						
Signal	Description	PROFIdrive Signal No.	Interconnection parameter	Function diagram	Data type	Normalization
ZSW1	Status word 1	2	r2089[0]	[2452][2453]	U16	-
ZSW2	Status word 2	4	r2089[1]	[2454][2455]	U16	-
NIST_A	Speed setpoint A (16 bit)	6	r0063[0]	[4715]	I16	4000 hex $\hat{=}$ p2000
NIST_B	Speed setpoint B (32 bit)	8	r0063	[4710]	I32	4000 0000 hex $\hat{=}$ p2000
G1_ZSW	Encoder 1 status word	10	r0481[0]	[4730]	U16	
G1_XIST1	Encoder 1 actual position 1	11	r0482[0]	[4704]	U32	
G1_XIST2	Encoder 1 actual position 2	12	r0483[0]	[4704]	U32	
G2_ZSW	Encoder 2 status word	14	r0481[1]	[4730]	U16	
G2_XIST1	Encoder 2 actual position 1	15	r0482[1]	[4704]	U32	
G2_XIST2	Encoder 2 actual position 2	16	r0483[1]	[4704]	U32	
G3_ZSW	Encoder 3 status word	18	r0481[2]	[4730]	U16	
G3_XIST1	Encoder 3 actual position 1	19	r0482[2]	[4704]	U32	
G3_XIST2	Encoder 3 actual position 2	20	r0483[2]	[4704]	U32	
E_DIGITAL	Digital inputs	21	r2089[2]	[2459]	U16	
IAIST_GLATT	Absolute actual current, smoothed	51	r0068[1]	[6714]	I16	4000 hex $\hat{=}$ p2002
ITACT_SMOOTH	Current actual value, torque-generating	52	r0078[1]	[5730]	I16	4000 hex $\hat{=}$ p2002
MIST_GLATT	Actual torque smoothed	53	r0080[1]	[6714]	I16	4000 hex $\hat{=}$ p2003
PIST_GLATT	Power factor, smoothed	54	r0082[1]	[6714]	I16	4000 hex $\hat{=}$ p2004
NIST_A_GLATT	Actual speed, smoothed	57	r0063[1]	[4715]	I16	4000 hex $\hat{=}$ p2000
MELD_NAMUR	VIK-NAMUR message bit bar	58	r3113	-	U16	
MELDW	Message word	102	r2089[2]	[2456]	U16	
MSET_SMOOTH	Total speed setpoint	120	r0079[1]	[5610]	I16	4000 hex $\hat{=}$ p2003
AACT_SMOOTH	Torque utilization	121	r0081	[8012]	I16	4000 hex $\hat{=}$ 100%
MT_ZSW	Measuring probe status word	131	r0688		U16	
MT1_ZS_F	Measuring probe 1 measuring time, falling edge	132	r0687[0]		U16	
MT1_ZS_S	Measuring probe 1 measuring time, rising edge	133	r0686[0]		U16	
MT2_ZS_F	Measuring probe 2 measuring time, falling edge	134	r0687[1]		U16	
MT2_ZS_S	Measuring probe 2 measuring time, rising edge	135	r0686[1]		U16	
AKTSATZ	Pos selected block	202	r2670	[3650]	U16	
PosZSW	Pos status word	204	r2683	[3645]	U16	
XistP	Pos position actual value	206	r2521	[4010]	I32	1 hex $\hat{=}$ 1 LU
FAULT_CODE	Fault code	301	r2131	[8060]	U16	
WARN_CODE	Alarm code	303	r2132	[8065]	U16	
E_ZSW1	INFEED status word (infeed)	321	r0899, r2139	[2457]	U16	
CU_ZSW	Control Unit status word	501	r2089[1]	[2458]	U16	



<1> Data type according to the PROFIdrive profile: I16 = Integer16, I32 = Integer32, U16 = Unsigned16, U32 = Unsigned32

1	2	3	4	5	6	7	8
DO: A_INF, B_INF, S_INF, SERVO, VECTOR					fp_2450_01_eng.vsd	Function diagram	
PROFIBUS – PZD send signals interconnection					23.03.06 V02.04.00	SINAMICS S	
							- 2450 -

Figure 2-49 2450 – PZD send signals interconnection

Figure 2-50 2451 – ZSW1 status word interconnection (p2038 = 2)

Signal sources for ZSW1 (Interface Mode PROFIdrive VIK-NAMUR, p2038 = 2)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] Signal source	Inverted <2>	
ZSW1.0	1 = Ready to power-up	p2080[0] = r0899.0	[2503.7]	[2610]	-	
ZSW1.1	1 = Ready to operate (DC link loaded, pulses blocked)	p2080[1] = r0899.1	[2503.7]	[2610]	-	
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	[2610]	-	
ZSW1.3	1 = Fault present	p2080[3] = r2139.3	[2548.7]	[8060]	-	
ZSW1.4	1 = No coast down active (OFF2 inactive)	p2080[4] = r0899.4	[2503.7]	[2610]	-	
ZSW1.5	1 = No fast stop active (OFF3 inactive)	p2080[5] = r0899.5	[2503.7]	[2610]	-	
ZSW1.6	1 = Power-on inhibit active	p2080[6] = r0899.6	[2503.7]	[2610]	-	
ZSW1.7	1 = Alarm present	p2080[7] = r2139.7	[2548.7]	[8065]	-	
ZSW1.8	1 = Speed setpoint - actual value deviation within tolerance t_off	p2080[8] = r2197.7	[2534.7]	[8010]	-	
ZSW1.9	1 = Control requested <3>	p2080[9] = r0899.9	[2503.7]	[2503]	-	
ZSW1.10	1 = f or n comparison value reached/exceeded	p2080[10] = r2199.1	[2536.7]	[8010]	-	
ZSW1.11	1 = I, M, or P limit not reached	p2080[11] = r0056.13	[2522.7]	[5610] [6060]		
ZSW1.12	Reserved	-	-	-	-	
ZSW1.13	1 = No motor overtemperature alarm	p2080[13] = r2135.14	[2548.7]	[8016]		
ZSW1.14	1 = Motor rotates forwards (n_act ≥ 0) 0 = Motor rotates backwards (n_act < 0)	p2080[14] = r2197.3	[2534.7]	[8010]	-	
ZSW1.15	1 = Display CDS	p2080[15] = r0836.0	-	-	-	

<1> Used in telegram 20.

<2> The status word is generated using the binector-connector converter p2088[0].

<3> The master system requests the process data.

PROFIBUS sampling time

Refer to [1020.7]

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2451_01_eng.vsd	Function diagram	
PROFIBUS - ZSW1 status word interconnection (p2038 = 2)					10.03.06 V02.04.00	SINAMICS S	
							- 2451 -

PROFIBUS sampling time
Refer to [1020.7]

Signal sources for ZSW1 (Interface Mode SINAMICS/MICROMASTER, p2038 = 0)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] signal source	Inverted <2>	
ZSW1.0	1 = Ready to power-up	p2080[0] = r0899.0	[2503.7]	[2610]	-	
ZSW1.1	1 = Ready to operate (DC link loaded, pulses blocked)	p2080[1] = r0899.1	[2503.7]	[2610]	-	
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	[2610]	-	
ZSW1.3	1 = Fault present	p2080[3] = r2139.3	[2548.7]	[8060]	-	
ZSW1.4	1 = No coast down active (OFF2 inactive)	p2080[4] = r0899.4	[2503.7]	[2610]	-	
ZSW1.5	1 = No fast stop active (OFF3 inactive)	p2080[5] = r0899.5	[2503.7]	[2610]	-	
ZSW1.6	1 = Power-on inhibit active	p2080[6] = r0899.6	[2503.7]	[2610]	-	
ZSW1.7	1 = Alarm present	p2080[7] = r2139.7	[2548.7]	[8065]	-	
ZSW1.8	1 = Speed setpoint - actual value deviation within tolerance t_off	p2080[8] = r2197.7	[2534.7]	[8010]	-	
ZSW1.9	1 = Control requested <3>	p2080[9] = r0899.9	[2503.7]	[2503]	-	
ZSW1.10	1 = f or n comparison value reached/exceeded	p2080[10] = r2199.1	[2536.7]	[8010]	-	
ZSW1.11	1 = I, M, or P limit not reached <4>	p2080[11] = r1407.7	[2522.7]	[5610] [6060]	✓	
ZSW1.12	1 = Open holding brake	p2080[12] = r0899.12	[2503.7]	[2701]	-	
ZSW1.13	1 = No motor overtemperature alarm	p2080[13] = r2135.14	[2548.7]	[8016]	✓	
ZSW1.14	1 = Motor rotates forwards (n_act ≥ 0) 0 = Motor rotates backwards (n_act < 0)	p2080[14] = r2197.3	[2534.7]	[8010]	-	
ZSW1.15	1 = No alarm, thermal overload, power unit	p2080[15] = r2135.15	[2548.7]	[8014]	✓	

<1> Used in telegram 1, 2, 3, 4, 5, 6, 7, 110, 352.
 <2> The status word is generated using the binector-connector converter p2088[0].
 <3> The master system requests the process data.
 <4> Not for Vector V/f.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2452_01_eng.vsd	Function diagram	
PROFIBUS - ZSW1 status word interconnection (p2038 = 0)					23.03.06 V02.04.00	SINAMICS S	
							- 2452 -

Figure 2-51 2452 – ZSW1 status word interconnection (p2038 = 0)

Figure 2-52 2453 – ZSW1 status word interconnection (p2038 = 1)

Signal sources for ZSW1 (Interface Mode SIMODRIVE 611 universal, p2038 = 1) <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] Signal source	Inverted
ZSW1.0	1 = Ready to power-up	p2080[0] = r0899.0	[2503.7]	[2610]	-
ZSW1.1	1 = Ready to operate (DC link loaded, pulses blocked)	p2080[1] = r0899.1	[2503.7]	[2610]	-
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	[2610]	-
ZSW1.3	1 = Fault present	p2080[3] = r2139.3	[2548.7]	[8060]	-
ZSW1.4	1 = No coast down active	p2080[4] = r0899.4	[2503.7]	[2610]	-
ZSW1.5	1 = No fast stop active	p2080[5] = r0899.5	[2503.7]	[2610]	-
ZSW1.6	1 = Power-on inhibit active	p2080[6] = r0899.6	[2503.7]	[2610]	-
ZSW1.7	1 = Alarm present	p2080[7] = r2139.7	[2548.7]	[8065]	-
ZSW1.8	1 = Speed setpoint - actual value deviation within tolerance t_off	p2080[8] = r2197.7	[2534.7]	[8010]	-
ZSW1.9	1 = Control requested <2>	p2080[9] = r0899.9	[2503.7]	[2503]	-
ZSW1.10	1 = f or n comparison value reached/exceeded	p2080[10] = r2199.1	[2536.7]	[8010]	-
ZSW1.11	Reserved	-	-	-	-
ZSW1.12	Reserved	-	-	-	-
ZSW1.13	Reserved	-	-	-	-
ZSW1.14	1 = Closed-loop torque control active	p2080[14] = r1407.2	[2522.7]	[2522]	-
ZSW1.15	Reserved	-	-	-	-

<1> Used in telegrams 1, 2, 3, 4, 5, 6, 102, 103, 105, 106, 116, 352.

<2> The master system requests the process data.

PROFIBUS sampling time

Refer to [1020.7]

1	2	3	4	5	6	7	8
DO: SERVO					fp_2453_01_eng.vsd	Function diagram	
PROFIBUS - ZSW1 status word interconnection (p2038 = 1)					20.03.06 V02.04.00	SINAMICS S	
- 2453 -							

PROFIBUS sampling time
Refer to [1020.7]

Signal sources for ZSW2 (Interface Mode SINAMICS/MICROMASTER, p2038 = 0) <1>

Signal	Meaning	Interconnection parameters	[Function diagram] internal status word	[Function diagram] signal source	Inverted
ZSW2.0	1 = Drive data set DDS effective, bit 0	p2081[0] = r0051.0	-	[8565]	-
ZSW2.1	1 = Drive data set DDS effective, bit 1	p2081[1] = r0051.1	-	[8565]	-
ZSW2.2	1 = Drive data set DDS effective, bit 2	p2081[2] = r0051.2	-	[8565]	-
ZSW2.3	1 = Drive data set DDS effective, bit 3	p2081[3] = r0051.3	-	[8565]	-
ZSW2.4	1 = Drive data set DDS effective, bit 4	p2081[4] = r0051.4	-	[8565]	-
ZSW2.5	Reserved	-	-	-	-
ZSW2.6	Reserved	-	-	-	-
ZSW2.7	1 = Parking axis active	p2081[7] = r0896.0	-	-	-
ZSW2.8	1 = Traverse to fixed endstop	p2081[8] = r1406.8	-	[2520]	-
ZSW2.9	Reserved	-	-	-	-
ZSW2.10	Reserved	-	-	-	-
ZSW2.11	1 = Data set changeover active	p2081[11] = r0835.0	-	-	-
ZSW2.12	Slave sign-of-life bit 0	Implicitly interconnected	-	-	-
ZSW2.13	Slave sign-of-life bit 1	Implicitly interconnected	-	-	-
ZSW2.14	Slave sign-of-life bit 2	Implicitly interconnected	-	-	-
ZSW2.15	Slave sign-of-life bit 3	Implicitly interconnected	-	-	-

<1> Used in telegrams 2, 3, 4, 5, 6, 7, 110.
<2> These signals are automatically interconnected for clock-cycle synchronous operation.

1	2	3	4	5	6	7	8
DO: SERVO					fp_2454_01_eng.vsd	Function diagram	
PROFIBUS - ZSW2 status word interconnection (p2038 = 0)					23.03.06 V02.04.00	SINAMICS S	
							- 2454 -

Figure 2-53 2454 – ZSW2 status word interconnection (p2038 = 0)

Figure 2-54 2455 – ZSW2 status word interconnection (p2038 = 1)

Signal sources for ZSW2 (Interface Mode SIMODRIVE 611 universal, p2038 = 1)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] Signal source	Inverted	PROFIBUS sampling time Refer to [1020.7]
ZSW2.0	1 = Drive data set DDS effective, bit 0	p2081[0] = r0051.0	-	[8565]	-	
ZSW2.1	1 = Drive data set DDS effective, bit 1	p2081[1] = r0051.1	-	[8565]	-	
ZSW2.2	1 = Drive data set DDS effective, bit 2	p2081[2] = r0051.2	-	[8565]	-	
ZSW2.3	Reserved	-	-	-	-	
ZSW2.4	1 = Ramp-function generator inactive <3>	p2081[4] = r1199.2	-	[3060] [3080]	✓	
ZSW2.5	1 = Open the holding brake	p2081[5] = r0899.12	[2503.7]	[2701]	-	
ZSW2.6	1 = Integrator inhibit, speed controller	p2081[6] = r2093.6	-	[5040] [5210]	-	
ZSW2.7	1 = Parking axis active	p2081[7] = r0896.0	-	-	-	
ZSW2.8	1 = Traverse to fixed endstop	p2081[8] = r1406.8	-	[2520]	-	
ZSW2.9	1 = Drive data set DDS effective, bit 3	p2081[9] = r0051.3	-	[8565]	-	
ZSW2.10	1 = Drive data set DDS effective, bit 4	p2081[10] = r0051.4	-	[8565]	-	
ZSW2.11	1 = Data set changeover active	p2081 [11] = r0835.0	-	-	-	
ZSW2.12	Slave sign-of-life bit 0	Implicitly interconnected	-	-	-	
ZSW2.13	Slave sign-of-life bit 1	Implicitly interconnected	-	-	-	
ZSW2.14	Slave sign-of-life bit 2	Implicitly interconnected	-	-	-	
ZSW2.15	Slave sign-of-life bit 3	Implicitly interconnected	-	-	-	

<1> Used in telegrams 2, 3, 4, 5, 6, 102, 103, 105, 106, 116.
 <2> These signals are automatically interconnected for clock-cycle synchronous operation.
 <3> Only when the function module "expanded setpoint channel" is activated (r0108.8 = 1).

1	2	3	4	5	6	7	8
DO: SERVO					fp_2455_01_eng.vsd	Function diagram	
PROFIBUS - ZSW2 status word interconnection (p2038 = 1)					23.03.06 V02.04.00	SINAMICS S	

- 2455 -

PROFIBUS sampling time
Refer to [1020.7]

Signal sources for MELDW						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] signal source	Inverted <2>	
MELDW.0	1 = Ramp-up/ramp-down completed 0 = Ramp-function generator active	p2082[0] = r2199.5	[2537.7]	[8010]	-	
MELDW.1	1 = Torque utilization [%] < torque threshold value 2 (p2194)	p2082[1] = r2199.11	[2537.7]	[8012]	-	
MELDW.2	1 = n_act < speed threshold value 3 (p2161)	p2082[2] = r2199.0	[2537.7]	[8010]	-	
MELDW.3	1 = n_act □ speed threshold value 2 (p2155)	p2082[3] = r2197.1	[2534.7]	[8010]	-	
MELDW.4	Reserved	-	-	-	-	
MELDW.5	Reserved	-	-	-	-	
MELDW.6	1 = No motor overtemperature alarm	p2082[6] = r2135.14	[2548.7]	[8016]	✓	
MELDW.7	1 = No alarm, thermal overload, power unit	p2082[7] = r2135.15	[2548.7]	[8014]	✓	
MELDW.8	1 = Speed setpoint - actual value deviation within tolerance t_on	p2082[8] = r2199.4	[2537.7]	[8010]	-	
MELDW.9	Reserved	-	-	-	-	
MELDW.10	Reserved	-	-	-	-	
MELDW.11	1 = Controller enable	p2082[11] = r0899.8	[2503.7]	[2610]	-	
MELDW.12	1 = Drive ready	p2082[12] = r0899.7	[2503.7]	[2610]	-	
MELDW.13	1 = Pulses enabled	p2082[13] = r0899.11	[2503.7]	[2610]	-	
MELDW.14	Reserved	-	-	-	-	
MELDW.15	Reserved	-	-	-	-	

<1> Used in telegrams 102, 103, 105, 106, 110, 116.
<2> The status word is generated using the binector-connector converter p2088[2].

1	2	3	4	5	6	7	8
DO: SERVO					fp_2456_01_eng.vsd	Function diagram	
PROFIBUS - MELDW status word interconnection					23.03.06 V02.04.00	SINAMICS S	
- 2456 -							

Figure 2-55 2456 – MELDW status word interconnection

PROFIBUS sampling time

Refer to [1020.7]

Signal sources for E_ZSW1

<1>

Signal	Meaning	Interconnection parameters	[Function diagram] signal source			[Function diagram] internal status word			Inverted
			A_INF	B_INF	S_INF	A_INF	B_INF	S_INF	
ZSW1.0	1 = Ready to power-up	p2080[0] = r0899.0	[8932]	[8732]	[8832]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.1	1 = Ready to operate	p2080[1] = r0899.1	[8932]	[8732]	[8832]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.2	1 = Operation enabled	p2080[2] = r0899.2	[8932]	[8732]	[8832]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.3	1 = Fault present	p2080[3] = r2139.3	[8060]			[2548.7]			-
ZSW1.4	1 = No OFF2 effective	p2080[4] = r0899.4	[8932]	[8732]	[8832]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.5	Reserved	-	-	-	-	-	-	-	-
ZSW1.6	1 = Power-on inhibit	p2080[6] = r0899.6	[8932]	[8732]	[8832]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.7	1 = Alarm present	p2080[7] = r2139.7	[8065]			[2548.7]			-
ZSW1.8	Reserved	-	-	-	-	-	-	-	-
ZSW1.9	1 = PLC requests control <2>	p2080[9] = r0899.9	[8926]	[8726]	[8826]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.10	Reserved	-	-	-	-	-	-	-	-
ZSW1.11	1 = Pre-charging completed	p2080[11] = r0899.11	[8950]	[8750]	[8850]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.12	1 = Line contactor closed	p2080[12] = r0899.12	[8934]	[8734]	[8834]	[8926.7]	[8726.7]	[8826.7]	-
ZSW1.13	Reserved	-	-	-	-	-	-	-	-
ZSW1.14	Reserved	-	-	-	-	-	-	-	-
ZSW1.15	Reserved	-	-	-	-	-	-	-	-

<1> Used in telegram 370.
 <2> Master system requests process data.

1	2	3	4	5	6	7	8	
DO: A_INF, B_INF, S_INF					fp_2457_01_eng.vsd	Function diagram		- 2457 -
PROFIBUS - E_ZSW1 status word infeed interconnection					17.05.05 V02.04.00	SINAMICS S		

Function diagrams
PROFIBUS

Figure 2-56 2457 – E_ZSW1 status word infeed interconnection

PROFIBUS sampling time
Refer to [1020.7]

Signal sources for CU_ZSW <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] signal source	Inverted
CU_ZSW.0	Reserved	-	-	-	-
CU_ZSW.1	Reserved	-	-	-	-
CU_ZSW.2	Reserved	-	-	-	-
CU_ZSW.3	Fault present	p2081[3] = r2139.3	-	-	-
CU_ZSW.4	Reserved	-	-	-	-
CU_ZSW.5	Reserved	-	-	-	-
CU_ZSW.6	Reserved	-	-	-	-
CU_ZSW.7	Alarm present	p2081[7] = r2139.7	-	-	-
CU_ZSW.8	Synchronisation (SYNC)	p2081[8] = r0899.8	-	-	-
CU_ZSW.9	Reserved	-	-	-	-
CU_ZSW.10	Reserved	-	-	-	-
CU_ZSW.11	Reserved	-	-	-	-
CU_ZSW.12	Slave-Sign-of-life Bit 0	Implicitly interconnected	-	-	-
CU_ZSW.13	Slave-Sign-of-life Bit 1	Implicitly interconnected	-	-	-
CU_ZSW.14	Slave-Sign-of-life Bit 2	Implicitly interconnected	-	-	-
CU_ZSW.15	Slave-Sign-of-life Bit 3	Implicitly interconnected	-	-	-

<1> Used in telegram 390 and 391.

1	2	3	4	5	6	7	8
DO: CU_S					fp_2458_01_eng.vsd	Function diagram	
PROFIBUS - CU_ZSW status word Control Unit interconnection					23.03.06 V02.04.00	SINAMICS S	
							- 2458 -

Figure 2-57 2458 – CU_ZSW status word Control Unit Interconnection

Figure 2-58 2459 – E_DIGITAL interconnection

Signal targets for E_DIGITAL						<1>
Signal	Meaning		Interconnection parameters <3>	[Function diagram] Internal status word	[Function diagram] signal target	Inverted
E_DIGITAL.0	Digital input 8 (DI/DO 8)	<2>	p2082[0] = r0722[8]	-	-	-
E_DIGITAL.1	Digital input 9 (DI/DO 9)	<2>	p2082[1] = r0722[9]	-	-	-
E_DIGITAL.2	Digital input 10 (DI/DO 10)	<2>	p2082[2] = r0722[10]	-	-	-
E_DIGITAL.3	Digital input 11 (DI/DO 11)	<2>	p2082[3] = r0722[11]	-	-	-
E_DIGITAL.4	Digital input 12 (DI/DO 12)	<2>	p2082[4] = r0722[12]	-	-	-
E_DIGITAL.5	Digital input 13 (DI/DO 13)	<2>	p2082[5] = r0722[13]	-	-	-
E_DIGITAL.6	Digital input 14 (DI/DO 14)	<2>	p2082[6] = r0722[14]	-	-	-
E_DIGITAL.7	Digital input 15 (DI/DO 15)	<2>	p2082[7] = r0722[15]	-	-	-
E_DIGITAL.8	Digital input 0 (DI 0)		p2082[8] = r0722[0]	-	-	-
E_DIGITAL.9	Digital input 1 (DI 1)		p2082[9] = r0722[1]	-	-	-
E_DIGITAL.10	Digital input 2 (DI 2)		p2082[10] = r0722[2]	-	-	-
E_DIGITAL.11	Digital input 3 (DI 3)		p2082[11] = r0722[3]	-	-	-
E_DIGITAL.12	Digital input 4 (DI 4)		p2082[12] = r0722[4]	-	-	-
E_DIGITAL.13	Digital input 5 (DI 5)		p2082[13] = r0722[5]	-	-	-
E_DIGITAL.14	Digital input 6 (DI 6)		p2082[14] = r0722[6]	-	-	-
E_DIGITAL.15	Digital input 7 (DI 7)		p2082[15] = r0722[7]	-	-	-

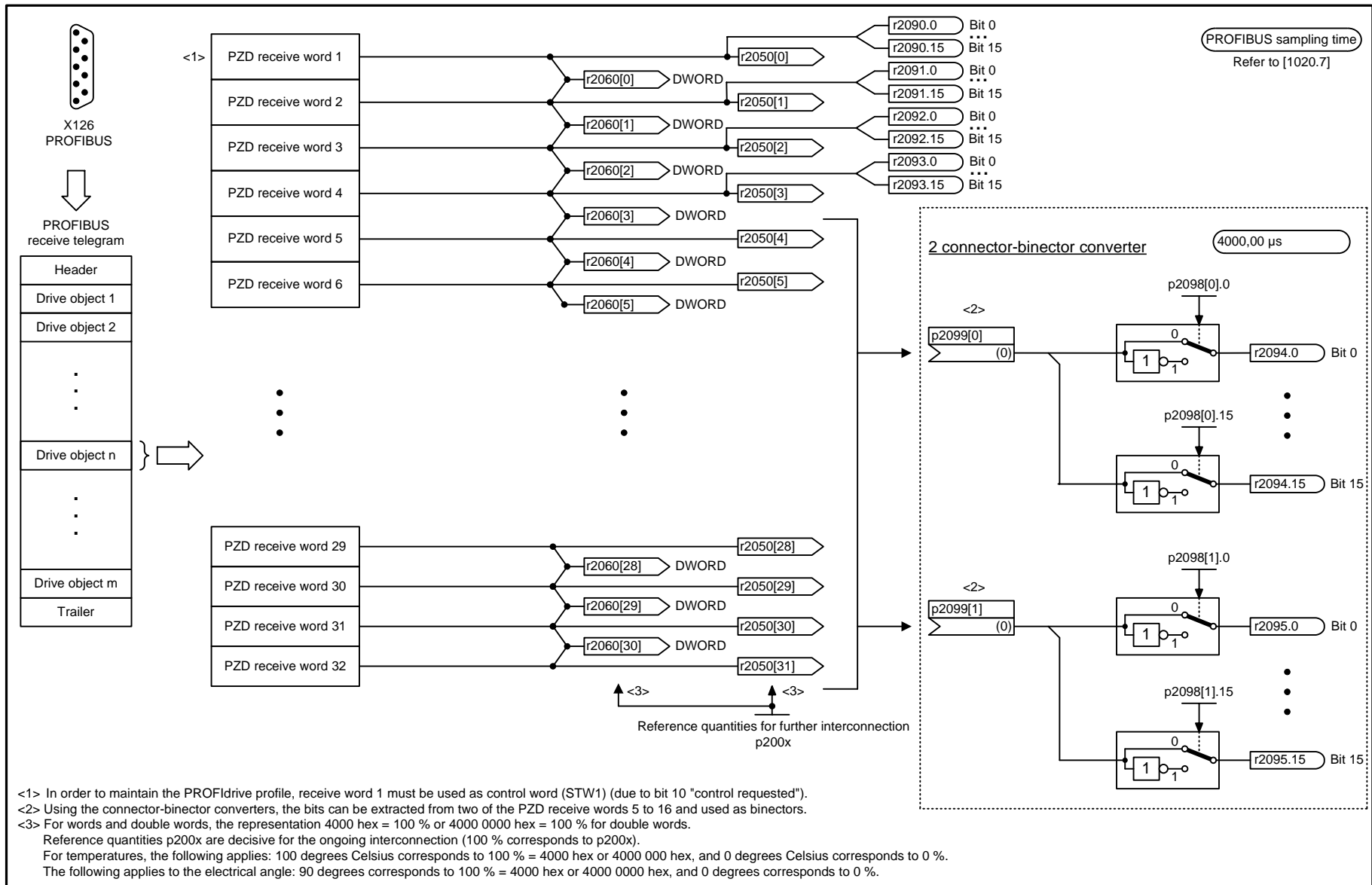
PROFIBUS sampling time
Refer to [1020.7]

<1> Used in telegram 390 and 391.

<2> Can be set via p0728 as input (DI) or output (DO).

<3> Pre-assignment, can be freely changed.

1	2	3	4	5	6	7	8
DO: CU_S					fp_2459_01_eng.vsd	Function diagram	
PROFIBUS - E_DIGITAL interconnection					23.03.06 V02.04.00	SINAMICS S	
							- 2459 -



<1> In order to maintain the PROFIdrive profile, receive word 1 must be used as control word (STW1) (due to bit 10 "control requested").
 <2> Using the connector-binector converters, the bits can be extracted from two of the PZD receive words 5 to 16 and used as binectors.
 <3> For words and double words, the representation 4000 hex = 100 % or 4000 0000 hex = 100 % for double words.
 Reference quantities p200x are decisive for the ongoing interconnection (100 % corresponds to p200x).
 For temperatures, the following applies: 100 degrees Celsius corresponds to 100 % = 4000 hex or 4000 0000 hex, and 0 degrees Celsius corresponds to 0 %.
 The following applies to the electrical angle: 90 degrees corresponds to 100 % = 4000 hex or 4000 0000 hex, and 0 degrees corresponds to 0 %.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2460_01_eng.vsd	Function diagram	
PROFIBUS - Receive telegram, free interconnection via BICO (p0922 = 999)					20.03.06 V02.04.00	SINAMICS S	
							- 2460 -

Figure 2-59 2460 – Receive telegram, free interconnection via BICO (p0922 = 999)

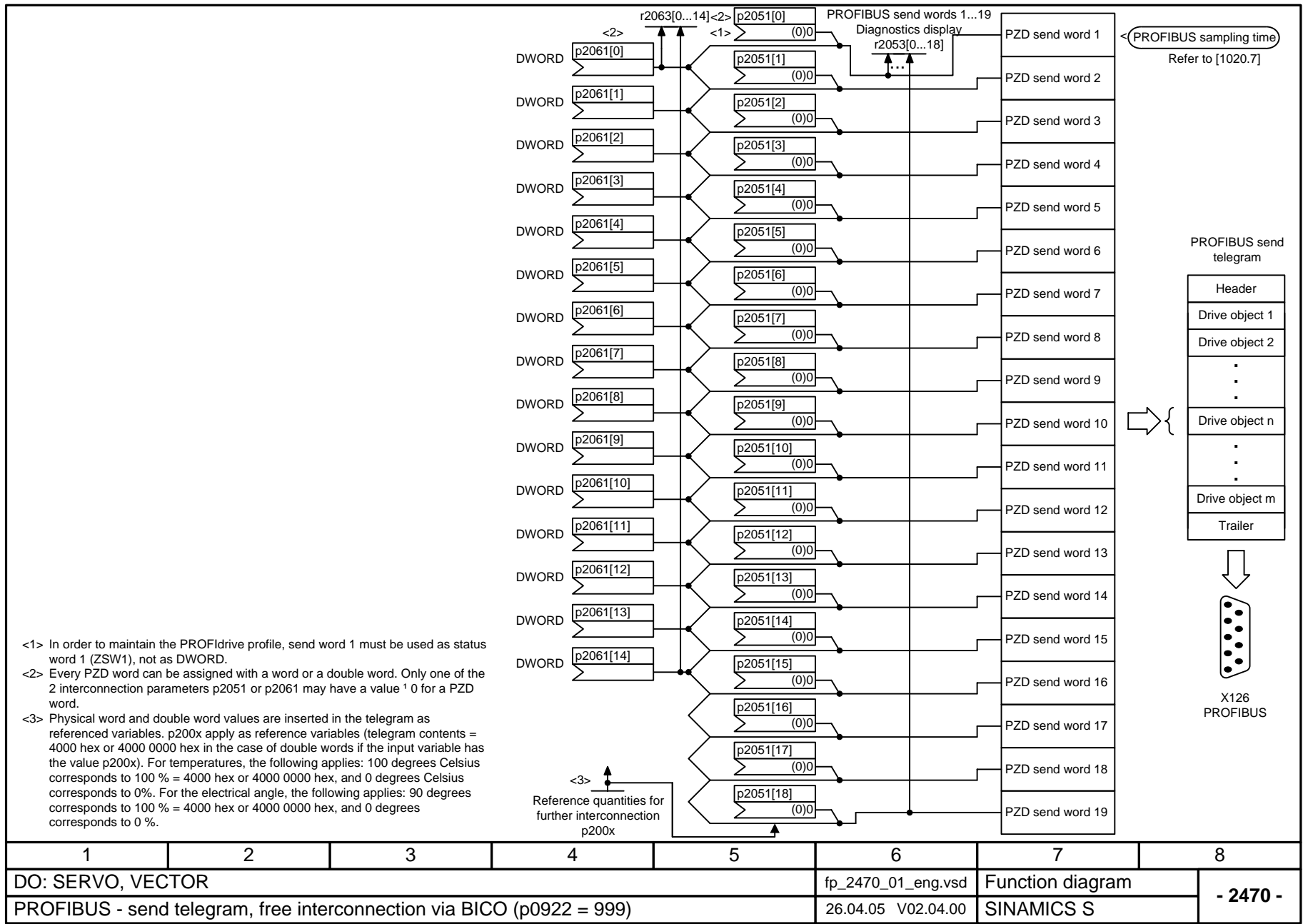
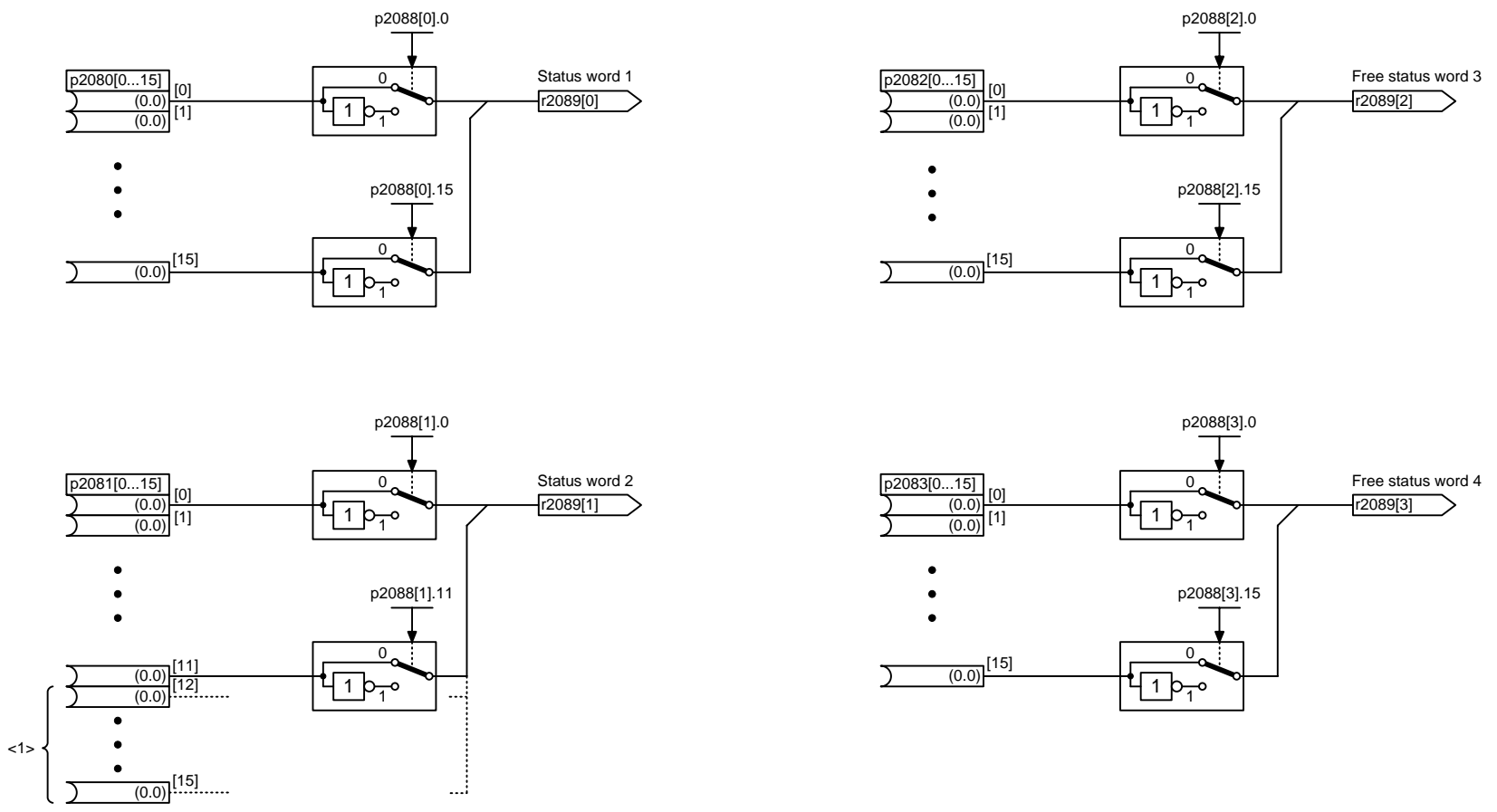


Figure 2-60 2470 – Send telegram, free interconnection via BICO (p0922 = 999)

4000.00 µs

4 binector-connector converter



<1> For clock-cycle synchronous SERVO, these signals may not be interconnected (slave sign-of-life).

1	2	3	4	5	6	7	8
DO: A_INF, CU_S, SERVO, TB30, TM31, VECTOR					fp_2472_01_eng.vsd	Function diagram	
PROFIBUS – status words free interconnection					31.03.05 V02.04.00	SINAMICS S	
							- 2472 -

Figure 2-61 2472 – Status words, free interconnection

Figure 2-62 2475 – STW1 control word 1 interconnection (r0108.4 = 1)

Signal targets for STW1 (positioning mode, r0108.4 = 1)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted	
STW1.0	= ON (pulses can be enabled) 0 = OFF1 (braking with ramp-funct. generator, then pulse cancellation and ready-to-power-up)	p0840[0] = r2090.0	[2501.3]	[2610]	-	
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse cancellation and power-on inhibit)	p0844[0] = r2090.1	[2501.3]	[2610]	-	
STW1.2	1 = No OFF3 (enable possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse cancellation and power-on inhibit)	p0848[0] = r2090.2	[2501.3]	[2610]	-	
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (cancel pulses)	p0852[0] = r2090.3	[2501.3]	[2610]	-	
STW1.4	1 = Do not reject traversing task 0 = Reject traversing task (ramp-down with the maximum deceleration)	p2641 = r2090.4	-	[3616.5] [3625]	-	
STW1.5	1 = No intermediate stop 0 = Intermediate stop	p2640 = r2090.5	-	[3616.5] [3625]	-	
STW1.6	= Activate traversing task	<3>p2631 = r2090.6 p2650 = r2090.6	-	[3620.1] [3625] [3640.1]	-	
STW1.7	= Acknowledge faults	p2103[0] = r2090.7	[2546.1]	[8060]	-	
STW1.8	1 = Jog 1 ON 0 = Jog 1 OFF	p2589 = r2090.8	-	[3610.1] [3625]	-	
STW1.9	1 = Jog 2 ON 0 = Jog 2 OFF	p2590 = r2090.9	-	[3610.1] [3625]	-	
STW1.10	1 = Control via PLC <2>	p0854[0] = r2090.10	[2501.3]	[2501]	-	
STW1.11	1 = Start homing 0 = Stop homing	p2595 = r2090.11	-	[3612.1] [3625]	-	
STW1.12	Reserved	-	-	-	-	
STW1.13	Reserved	-	-	-	-	
STW1.14	Reserved	-	-	-	-	
STW1.15	Reserved	-	-	-	-	

<1> Used in telegram 7, 110, 999.

<3> In addition, the interconnection p2649 = 0 is made

<2> Bit 10 must be set in the first PZD word of the telegram received from PROFIBUS in order that the drive accepts the process data.

PROFIBUS sampling time

Refer to [1020.7]

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2475_01_eng.vsd	Function diagram	
PROFIBUS - STW1 control word 1 interconnection (r0108.4 = 1)					24.01.06 V02.04.00	SINAMICS S	
							- 2475 -

PROFIBUS sampling time
Refer to [1020.7]

Signal targets for SATZANW (positioning mode, r0108.4 = 1) <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
SATZANW1.0	1 = Block selection, bit 0	p2625 = r2091.0	-	[3640]	-
SATZANW1.1	1 = Block selection, bit 1	p2626 = r2091.1	-	[3640]	-
SATZANW1.2	1 = Block selection, bit 2	p2627 = r2091.2	-	[3640]	-
SATZANW1.3	1 = Block selection, bit 3	p2628 = r2091.3	-	[3640]	-
SATZANW1.4	1 = Block selection, bit 4	p2629 = r2091.4	-	[3640]	-
SATZANW1.5	1 = Block selection, bit 5	p2630 = r2091.5	-	[3640]	-
SATZANW1.6	Reserved	-	-	-	-
SATZANW1.7	Reserved	-	-	-	-
SATZANW1.8	Reserved	-	-	-	-
SATZANW1.9	Reserved	-	-	-	-
SATZANW1.10	Reserved	-	-	-	-
SATZANW1.11	Reserved	-	-	-	-
SATZANW1.12	Reserved	-	-	-	-
SATZANW1.13	Reserved	-	-	-	-
SATZANW1.14	Reserved	-	-	-	-
SATZANW1.15	1 = Activate MDI 0 = De-activate MDI	p2647 = r2091.15	-	[3625] [3640]	-

<1> Used in telegram 7, 110, 999.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2476_01_eng.vsd	Function diagram	
PROFIBUS – SATZANW pos block select interconnection (r0108.4 = 1)					24.01.06 V02.04.00	SINAMICS S	
							- 2476 -

Figure 2-63 2476 – SATZANW pos block select interconnection (r0108.4 = 1)

Figure 2-64 2477 – PosSTW pos control word interconnection (r0108.4 = 1)


Signal targets for PosSTW (positioning mode, r0108.4 = 1) <1>					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
PosSTW1.0	1 = Tracking mode 0 = No tracking mode	p2655 = r2092.0	-	[3635]	-
PosSTW1.1	1 = Set home position 0 = Do not set home position	p2596 = r2092.1	-	[3612]	-
PosSTW1.2	1 = Reference cam active	p2612 = r2092.2	-	[3612]	-
PosSTW1.3	Reserved	-	-	-	-
PosSTW1.4	Reserved	-	-	-	-
PosSTW1.5	1 = Jogging, incremental active 0 = Jogging, velocity active	p2591 = r2092.5	-	[3610]	-
PosSTW1.6	Reserved	-	-	-	-
PosSTW1.7	Reserved	-	-	-	-
PosSTW1.8	Reserved	-	-	-	-
PosSTW1.9	Reserved	-	-	-	-
PosSTW1.10	Reserved	-	-	-	-
PosSTW1.11	Reserved	-	-	-	-
PosSTW1.12	Reserved	-	-	-	-
PosSTW1.13	Reserved	-	-	-	-
PosSTW1.14	Reserved	-	-	-	-
PosSTW1.15	Reserved	-	-	-	-

PROFIBUS sampling time
Refer to [1020.7]

<1> Used in telegram 110, 999.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2477_01_eng.vsd	Function diagram	
PROFIBUS – PosSTW pos control word interconnection (r0108.4 = 1)					20.01.06 V02.04.00	SINAMICS S	
							- 2477 -

PROFIBUS sampling time
Refer to [1020.7]

Signal sources for ZSW1 (positioning mode, r0108.4 = 1)						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] Internal status word	[Function diagram] signal source	Inverted <2>	
ZSW1.0	1 = Ready to power-up	p2080[0] = r0899.0	[2503.7]	[2610]	-	
ZSW1.1	1 = Ready to operate (DC link loaded, pulses blocked)	p2080[1] = r0899.1	[2503.7]	[2610]	-	
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	[2610]	-	
ZSW1.3	1 = Fault present	p2080[3] = r2139.3	[2548.7]	[8060]	-	
ZSW1.4	1 = No coast down active (OFF2 inactive)	p2080[4] = r0899.4	[2503.7]	[2610]	-	
ZSW1.5	1 = No fast stop active (OFF3 inactive)	p2080[5] = r0899.5	[2503.7]	[2610]	-	
ZSW1.6	1 = Power-on inhibit active	p2080[6] = r0899.6	[2503.7]	[2610]	-	
ZSW1.7	1 = Alarm present	p2080[7] = r2139.7	[2548.7]	[8065]	-	
ZSW1.8	1 = Following error within tolerance	p2080[8] = r2684.8	[3646.7]	[4025]	-	
ZSW1.9	1 = Control requested <3>	p2080[9] = r0899.9	[2503.7]	[2503]	-	
ZSW1.10	1 = Target position reached	p2080[10] = r2684.10	[3646.7]	[4020] [3625]	-	
ZSW1.11	1 = Home position set	p2080[11] = r2684.11	[3646.7]	[3612] [3614]		
ZSW1.12	 = Acknowledgement traversing block activated	p2080[12] = r2684.12	[3646.7]	[3616] [3620]	-	
ZSW1.13	1 = Drive at standstill	p2080[13] = r2199.0	[2537.7]	[8010] [3625]		
ZSW1.14	Reserved	-	-	-	-	
ZSW1.15	Reserved	-	-	-	-	

<1> Used in telegram 7, 110, 999.

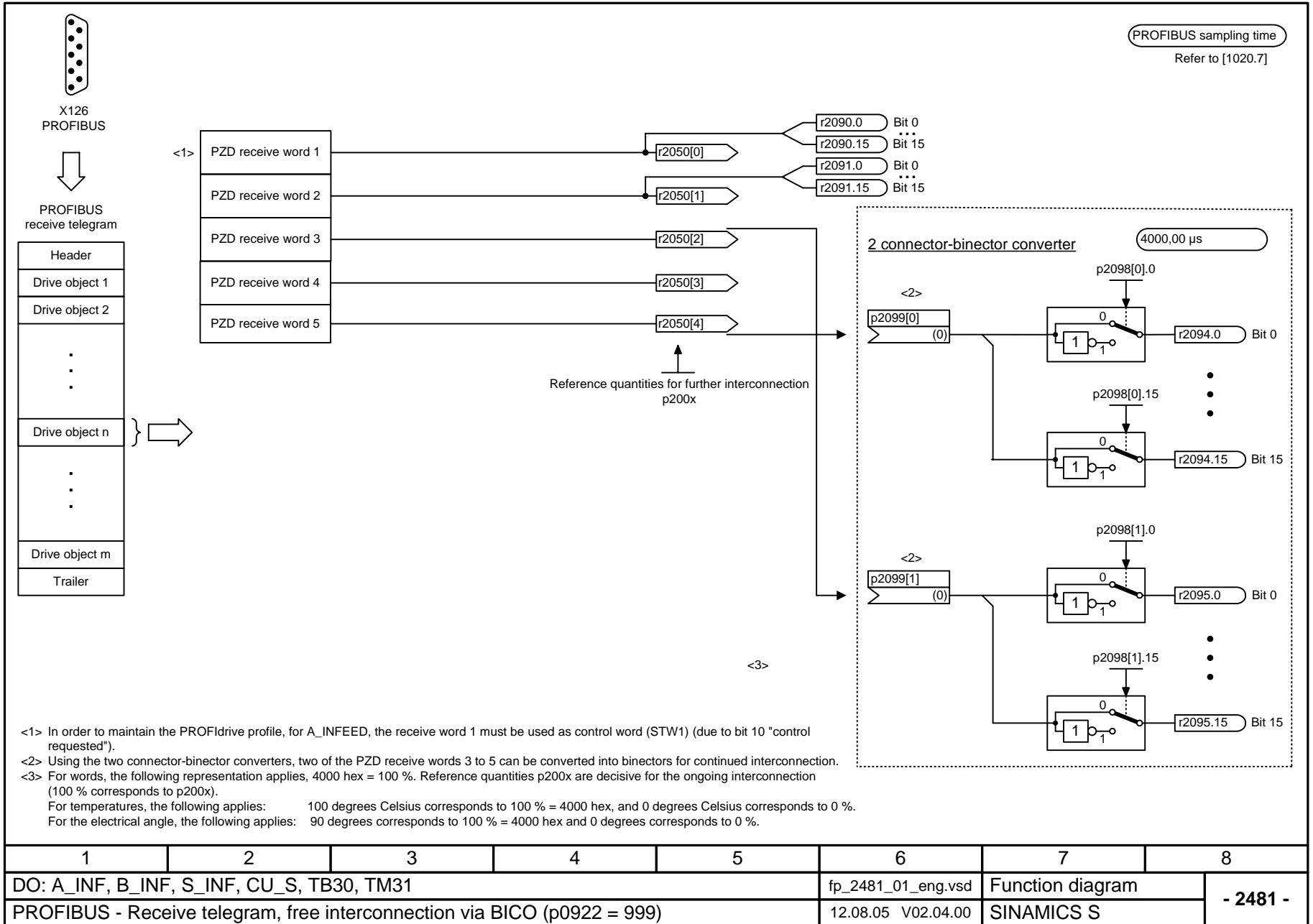
<2> The status word is generated using the binector-connector converter p2088[0].

<3> The master system requests the process data.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2479_01_eng.vsd	Function diagram	
PROFIBUS - ZSW1 status word 1 interconnection (r0108.4 = 1)					24.01.06 V02.04.00	SINAMICS S	
							- 2479 -

Figure 2-65 2479 – ZSW1 status word 1 interconnection (r0108.4 = 1)

Figure 2-66 2481 – Receive telegram, free interconnection via BICO (p0922 = 999)



PROFIBUS sampling time
 Refer to [1020.7]

4000,00 µs

2 connector-binector converter

Reference quantities for further interconnection
 p200x

<3>

<1> In order to maintain the PROFIdrive profile, for A_INFEED, the receive word 1 must be used as control word (STW1) (due to bit 10 "control requested").
 <2> Using the two connector-binector converters, two of the PZD receive words 3 to 5 can be converted into binectors for continued interconnection.
 <3> For words, the following representation applies, 4000 hex = 100 %. Reference quantities p200x are decisive for the ongoing interconnection (100 % corresponds to p200x).
 For temperatures, the following applies: 100 degrees Celsius corresponds to 100 % = 4000 hex, and 0 degrees Celsius corresponds to 0 %.
 For the electrical angle, the following applies: 90 degrees corresponds to 100 % = 4000 hex and 0 degrees corresponds to 0 %.

DO: A_INF, B_INF, S_INF, CU_S, TB30, TM31

fp_2481_01_eng.vsd

Function diagram

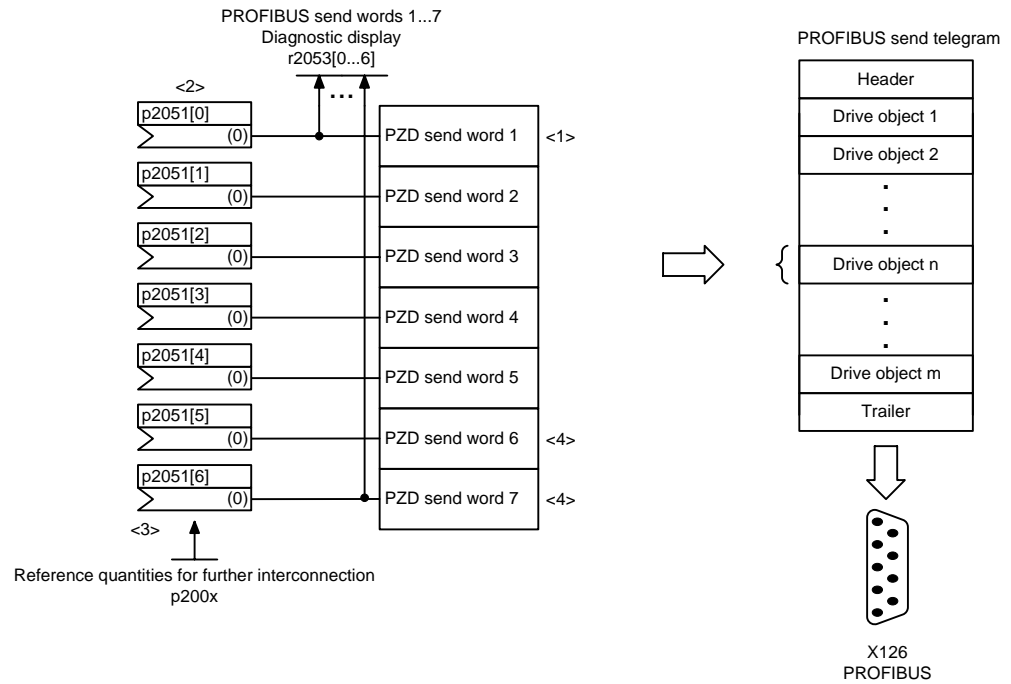
- 2481 -

PROFIBUS - Receive telegram, free interconnection via BICO (p0922 = 999)

12.08.05 V02.04.00

SINAMICS S

PROFIBUS sampling time
Refer to [1020.7]



<1> In order to maintain the PROFIdrive profile, send word 1 must be used as status word 1 (ZSW1) for A_INFEED.
 <2> Using the binector/connector converters at [2472], bits of 4 send words can be interconnected with any binectors.
 <3> Physical word quantities are inserted in the telegram as referenced quantities. In this case, p200x is decisive as reference quantity (telegram contents = 4000 hex if the input quantity has the value p200x).
 For temperatures, the following applies: 100 degrees Celsius corresponds to 100 % = 4000 hex and 0 degrees Celsius corresponds to 0 %.
 For the electrical angle, the following applies: 90 degrees corresponds to 100 % = 4000 hex and 0 degrees corresponds to 0 %.
 <4> Valid for CU_S.

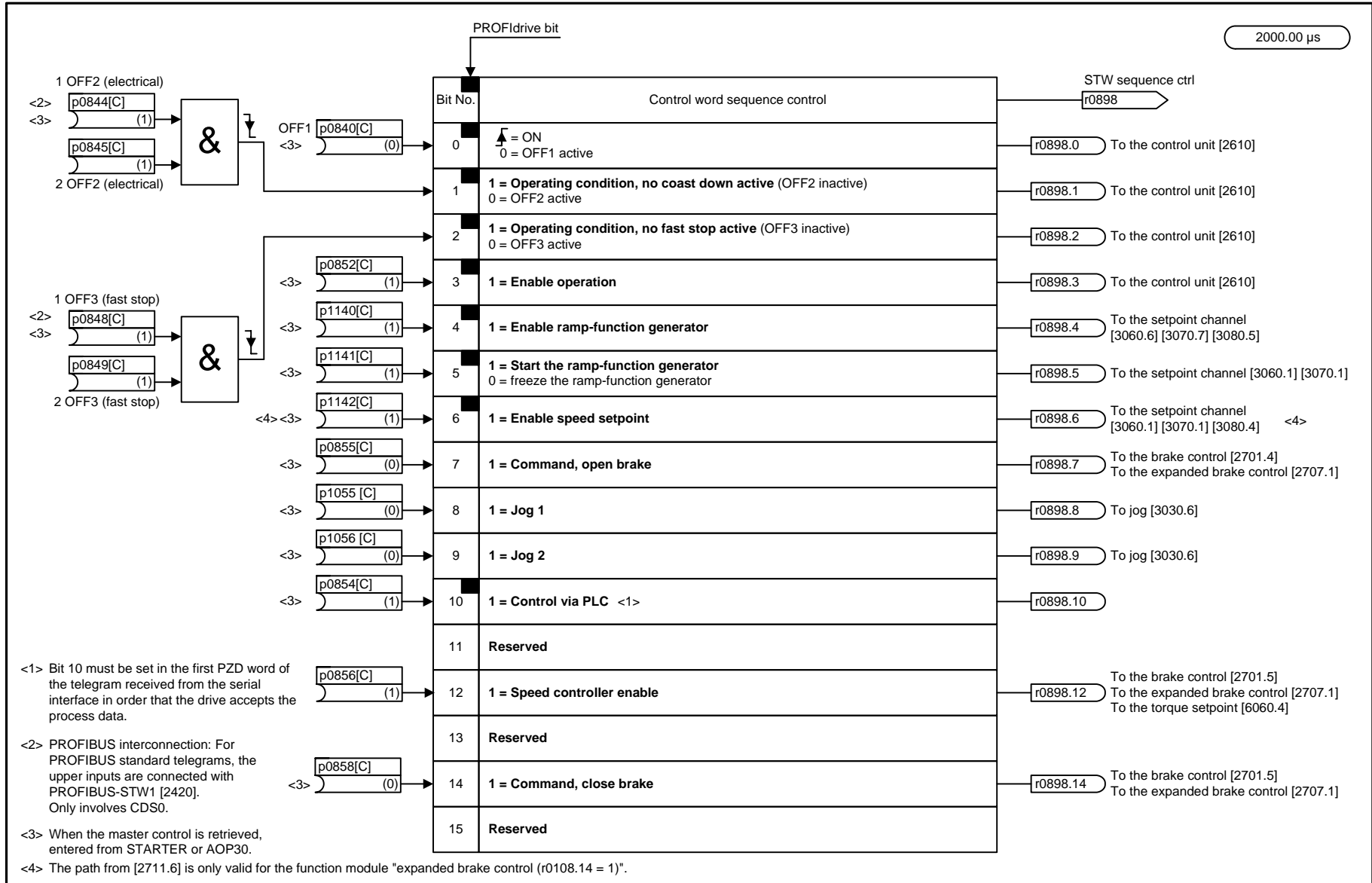
Figure 2-67 2483 – Send telegram, free interconnection via BICO (p0922 = 999)

1	2	3	4	5	6	7	8
DO: A_INF, B_INF, CU_S, S_INF, TB30, TM15DI/DO, TM31					fp_2483_01_eng.vsd	Function diagram	
PROFIBUS - send telegram, free interconnection via BICO (p0922 = 999)					12.08.05 V02.04.00	SINAMICS S	
							- 2483 -

2.9 Internal control/status words

Function diagrams

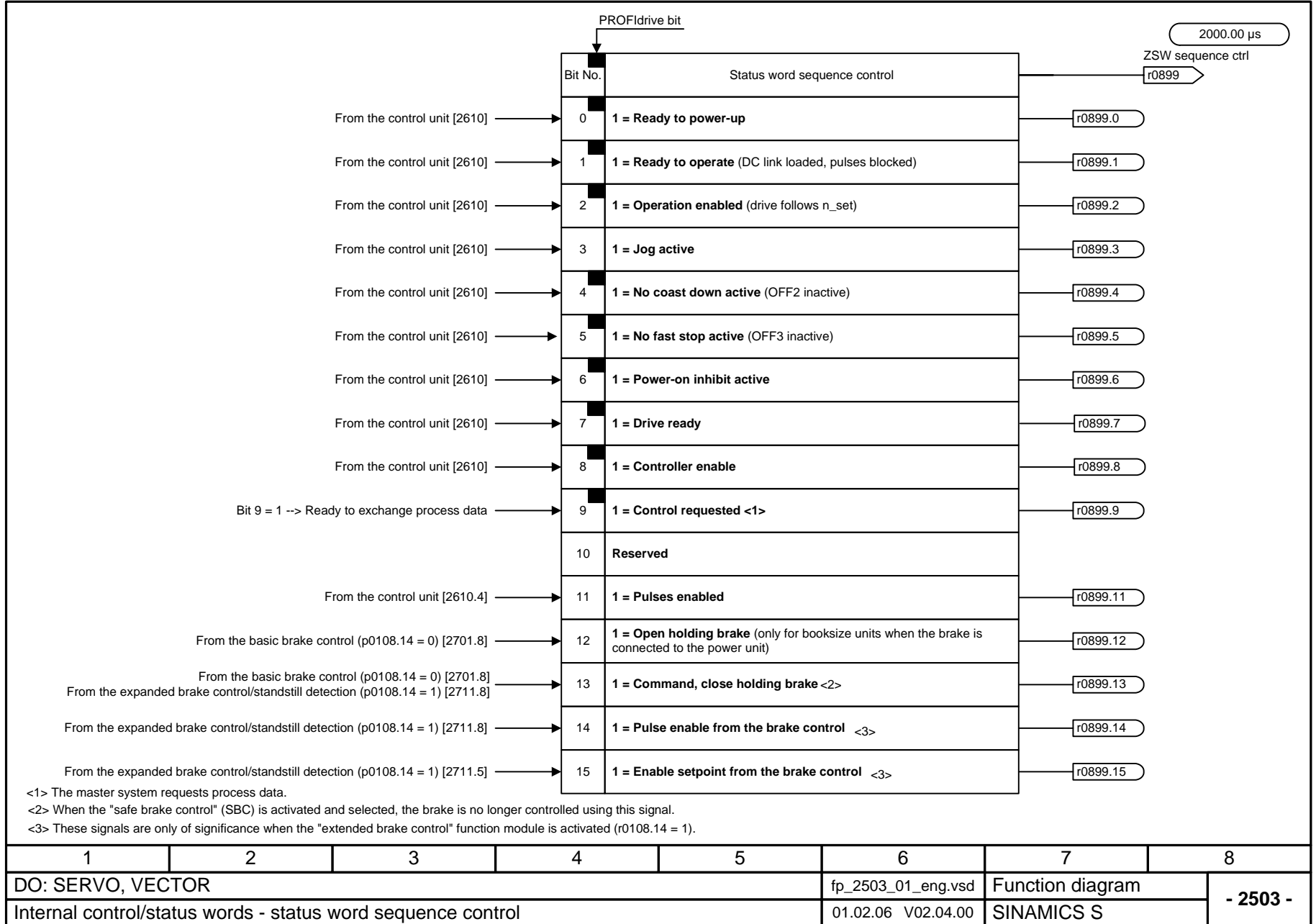
2501 – Control word sequence control	2-990
2503 – Status word sequence control	2-991
2505 – Control word setpoint channel	2-992
2520 – Control word speed controller	2-993
2522 – Status word speed controller	2-994
2526 – Status word closed-loop control	2-995
2530 – Status word closed-loop current control	2-996
2534 – Status word monitoring 1	2-997
2536 – Status word monitoring 2	2-998
2537 – Status word monitoring 3	2-999
2546 – Control word faults/alarms	2-1000
2548 – Status word, faults/warnings 1 and 2	2-1001



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2501_01_eng.vsd	Function diagram	
Internal control/status words, control word sequence control					08.12.05 V02.04.00	SINAMICS S	
							- 2501 -

Figure 2-68 2501 – Control word sequence control

Figure 2-69 2503 – Status word sequence control



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2503_01_eng.vsd	Function diagram	
Internal control/status words - status word sequence control					01.02.06 V02.04.00	SINAMICS S	
							- 2503 -

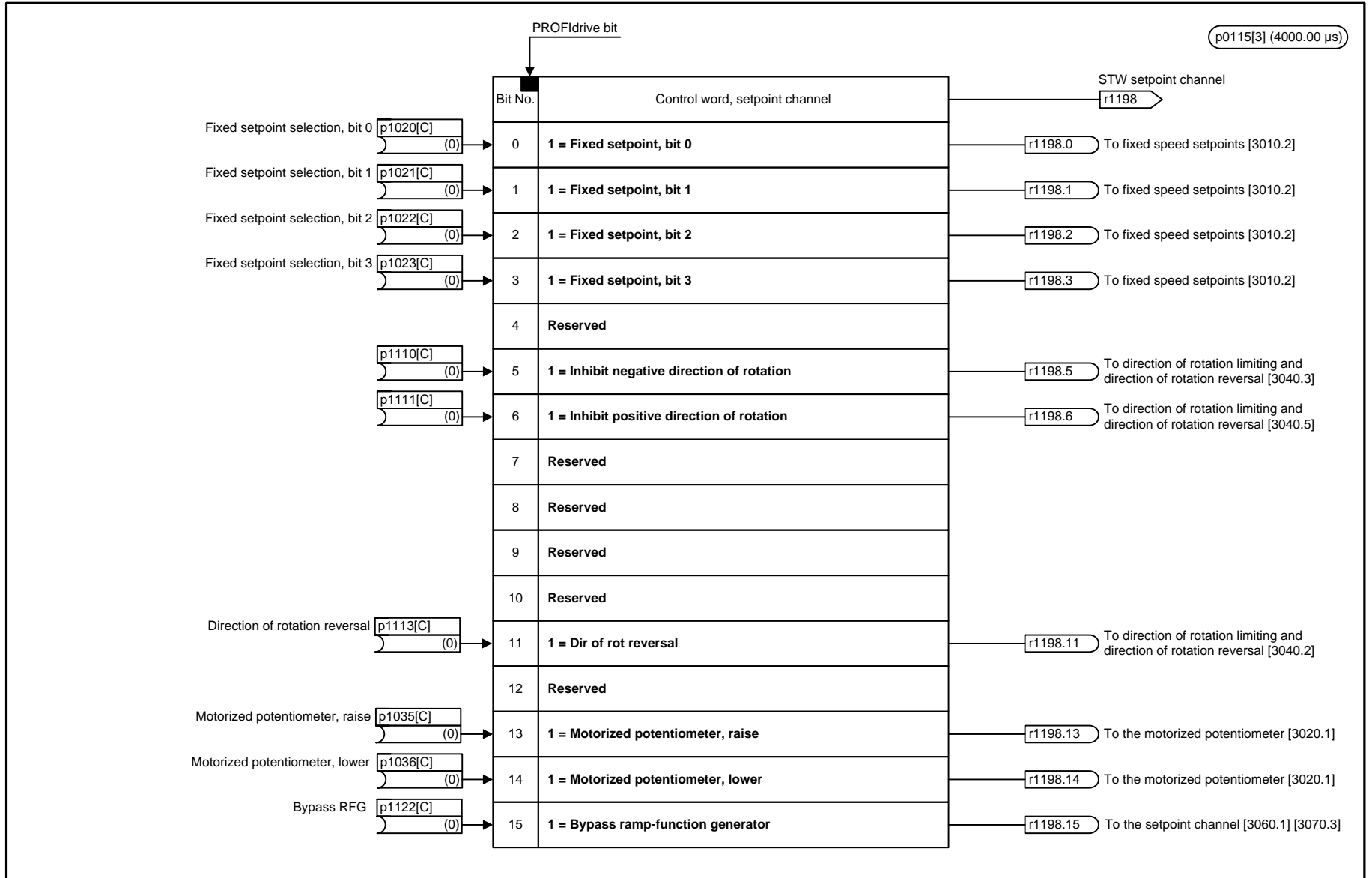
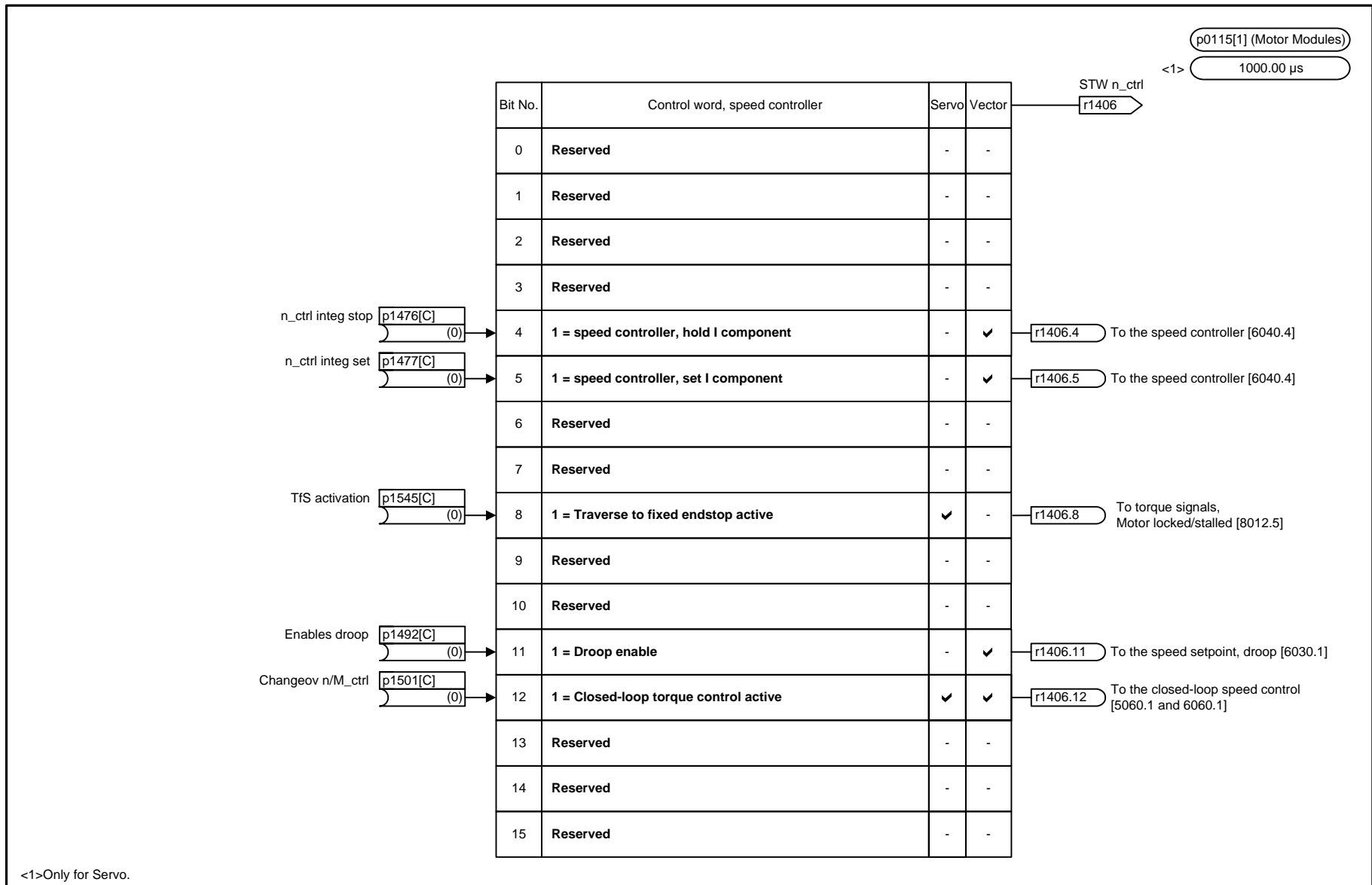


Figure 2-70 2505 – Control word setpoint channel

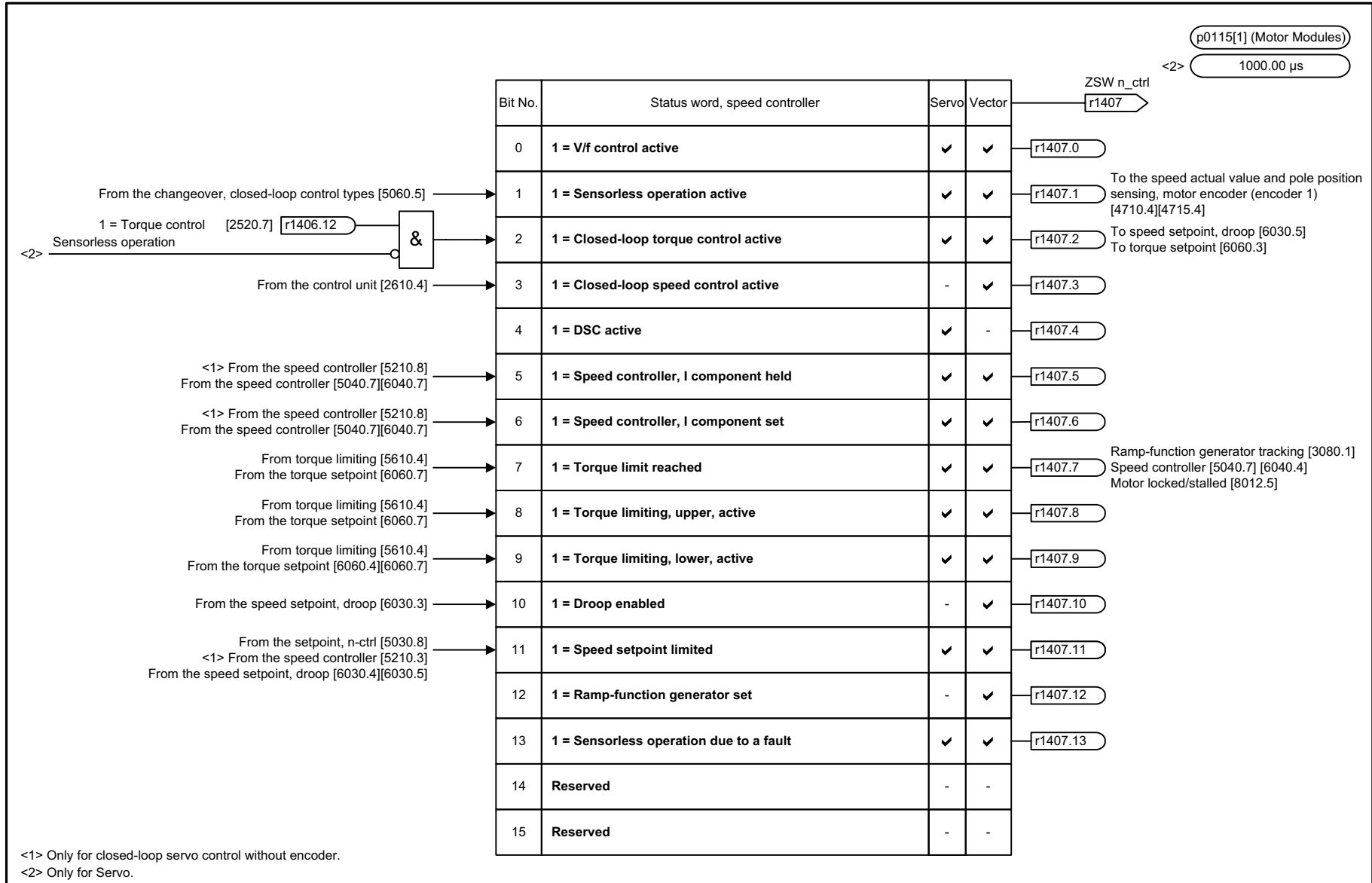
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2505_01_eng.vsd	Function diagram	
Internal control/status words - control word setpoint channel					16.03.05 V02.04.00	SINAMICS S	
- 2505 -							



<1>Only for Servo.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2520_01_eng.vsd	Function diagram	
Internal control/status words - control word speed controller					19.04.05 V02.04.00	SINAMICS S	
							- 2520 -

Figure 2-71 2520 – Control word speed controller



<1> Only for closed-loop servo control without encoder.
<2> Only for Servo.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2522_01_eng.vsd	Function diagram	
Internal control/status words - status word speed controller					23.03.06 V02.04.00	SINAMICS S	
							- 2522 -

Figure 2-72 2522 – Status word speed controller

p0115[y] (Motor Modules)
Refer to [1020.7]

Status word closed-loop control

Bit No.	Meaning	
		ZSW closed-loop control r0056
0	1 = Initialization completed <2>	r0056.0
1	1 = De-magnetization completed	r0056.1
2	1 = Pulses enabled <2>	r0056.2
3	1 = Soft starting available <1> <2>	r0056.3
[6722.6] → 4	1 = Magnetization completed	r0056.4
5	Reserved	r0056.5
6	1 = Acceleration voltage active <1> <2>	r0056.6
[6730.5][6731.5] → 7	1 = Frequency, negative <2>	r0056.7
[6722.3] → 8	1 = Field weakening active	r0056.8
[6714.8] → 9	1 = Voltage limit active <2>	r0056.9
[6310.8] → 10	1 = Slip limiting active <1> <2>	r0056.10
[6730.5][6731.5] → 11	1 = Frequency limit active <2>	r0056.11
12	1 = Current limiting controller, voltage output active <1> <2>	r0056.12
[6060.7] → 13	1 = Current/torque limiting active <1> <2>	r0056.13
[6320.8][6710.2] → 14	1 = Vdc_max controller active	r0056.14
[6320.8][6710.2] → 15	1 = Vdc_min controller active	r0056.15

<1> Only for U/f control.
<2> Not for SERVO.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2526_01_eng.vsd	Function diagram	
Internal control/status words - status word closed-loop control					02.03.06 V02.04.00	SINAMICS S	
- 2526 -							

Figure 2-73 2526 – Status word closed-loop control

Status word closed-loop current control

p0115[y] (Motor Modules)
Refer to [1020.7]

Bit No.	Meaning	
0	1 = Closed-loop current control active	ZSW closed-loop current control r1408
[6714.5] → 1	1 = Lim. I comp. Id-R active <2>	
2	Reserved	
[6714.7] → 3	1 = Limiting U active <2>	
4	1 = Limiting Ud active <1>	
5	1 = Limiting Uq active <1>	→ [5040.7]
6	1 = Pos. limit. Iq active <1>	→ [5714.5]
7	1 = Neg. limit. Iq active <1>	→ [5714.4]
8	1 = Iq setpoint limit. active <1>	→ [5714.4]
9	1 = Id setpoint limit. active <1>	→ [5722.7]
[6730.3] → 10	1 = Lim. EMF/Obs-ctrl. active <2>	
11	1 = Error EMF/Obs-N active <2>	
12	1 = Motor stalled active <2>	
13	Reserved	
14	Reserved	
15	Reserved	

<1> Only for SERVO.
<2> Only for VECTOR.

Figure 2-74 2530 – Status word closed-loop current control

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2530_01_eng.vsd	Function diagram	
Internal control/status words - status word closed-loop current control					02.03.06 V02.04.00	SINAMICS S	
- 2530 -							

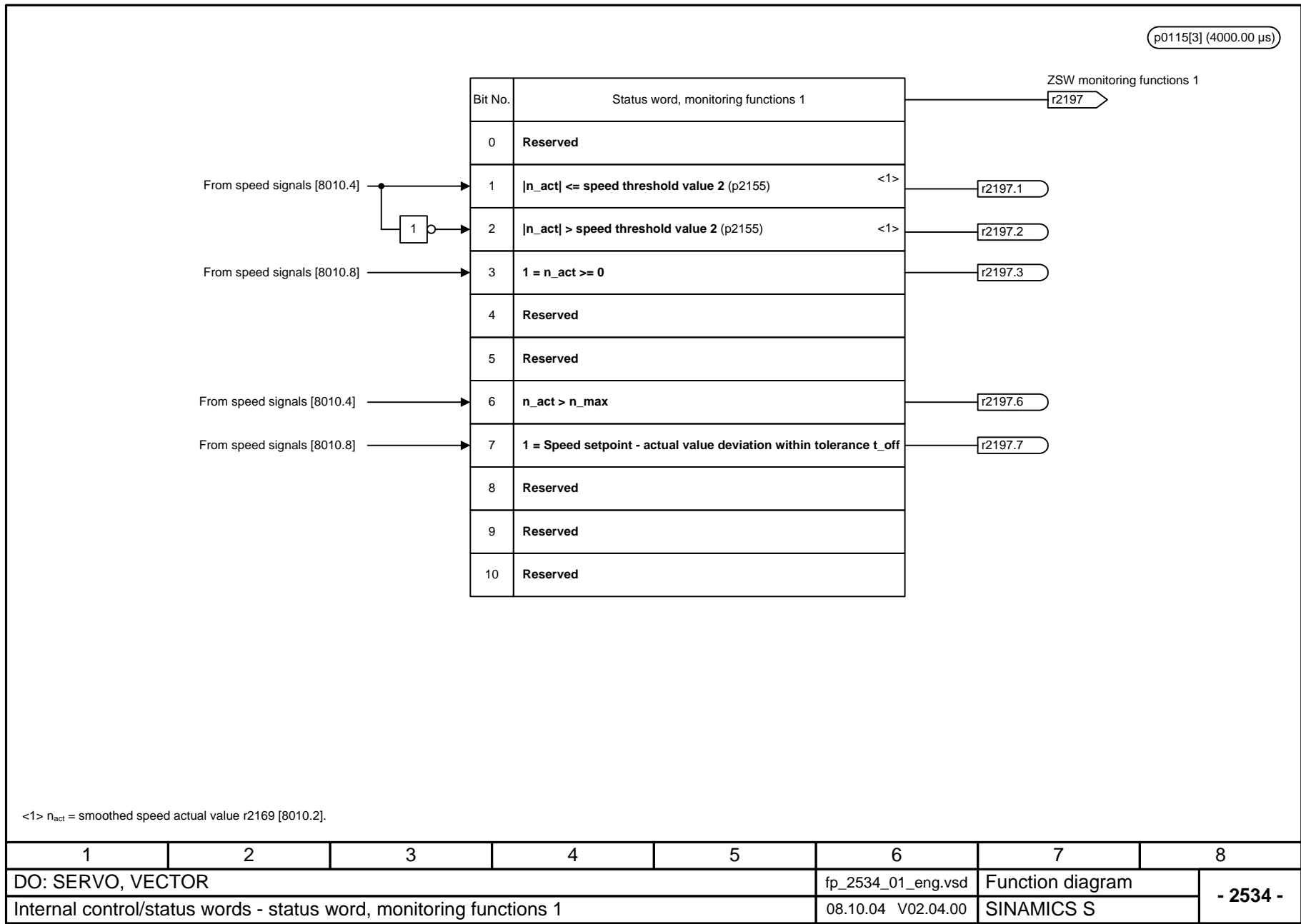


Figure 2-75 2534 – Status word monitoring 1

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2534_01_eng.vsd	Function diagram	
Internal control/status words - status word, monitoring functions 1					08.10.04 V02.04.00	SINAMICS S	
							- 2534 -

p0115[3] (4000.00 μs)

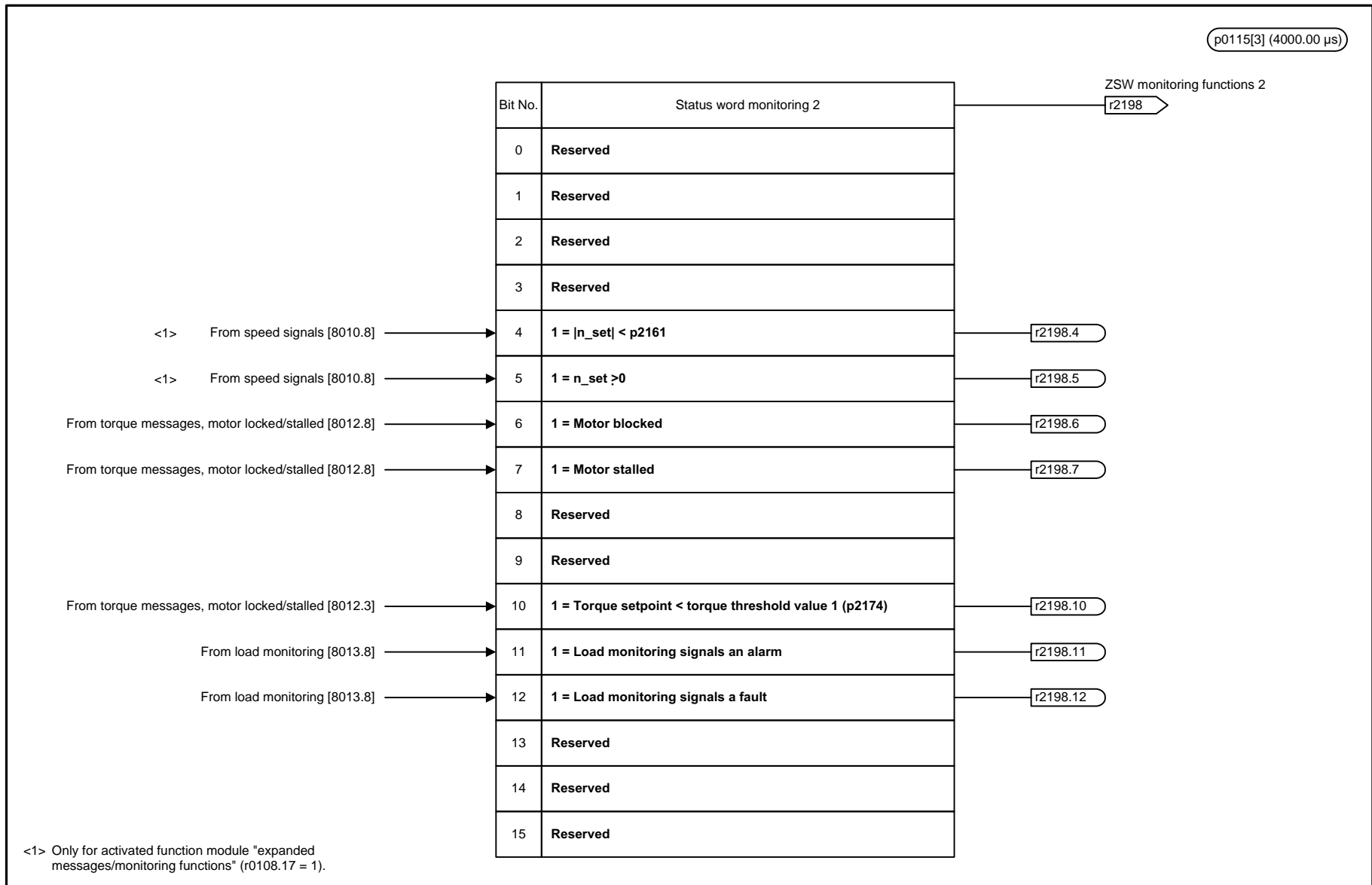
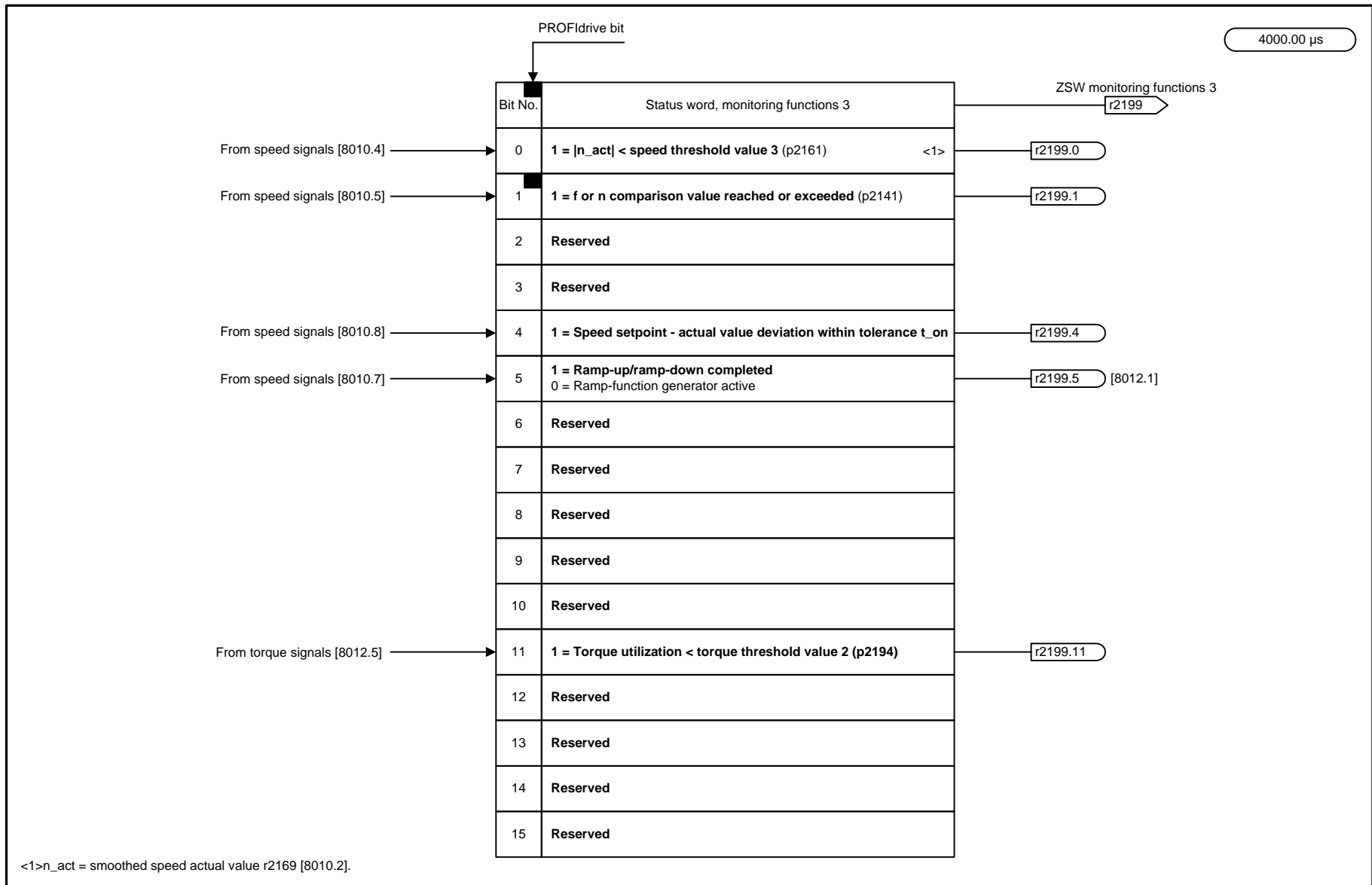


Figure 2-76 2536 – Status word monitoring 2

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2536_01_eng.vsd	Function diagram	
Internal control/status words – status word monitoring 2					23.12.04 V02.04.00	SINAMICS S	
- 2536 -							



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2537_01_eng.vsd	Function diagram	
Internal control/status words - status word, monitoring functions 3					08.10.04 V02.04.00	SINAMICS S	
							- 2537 -

Figure 2-77 2537 – Status word monitoring 3

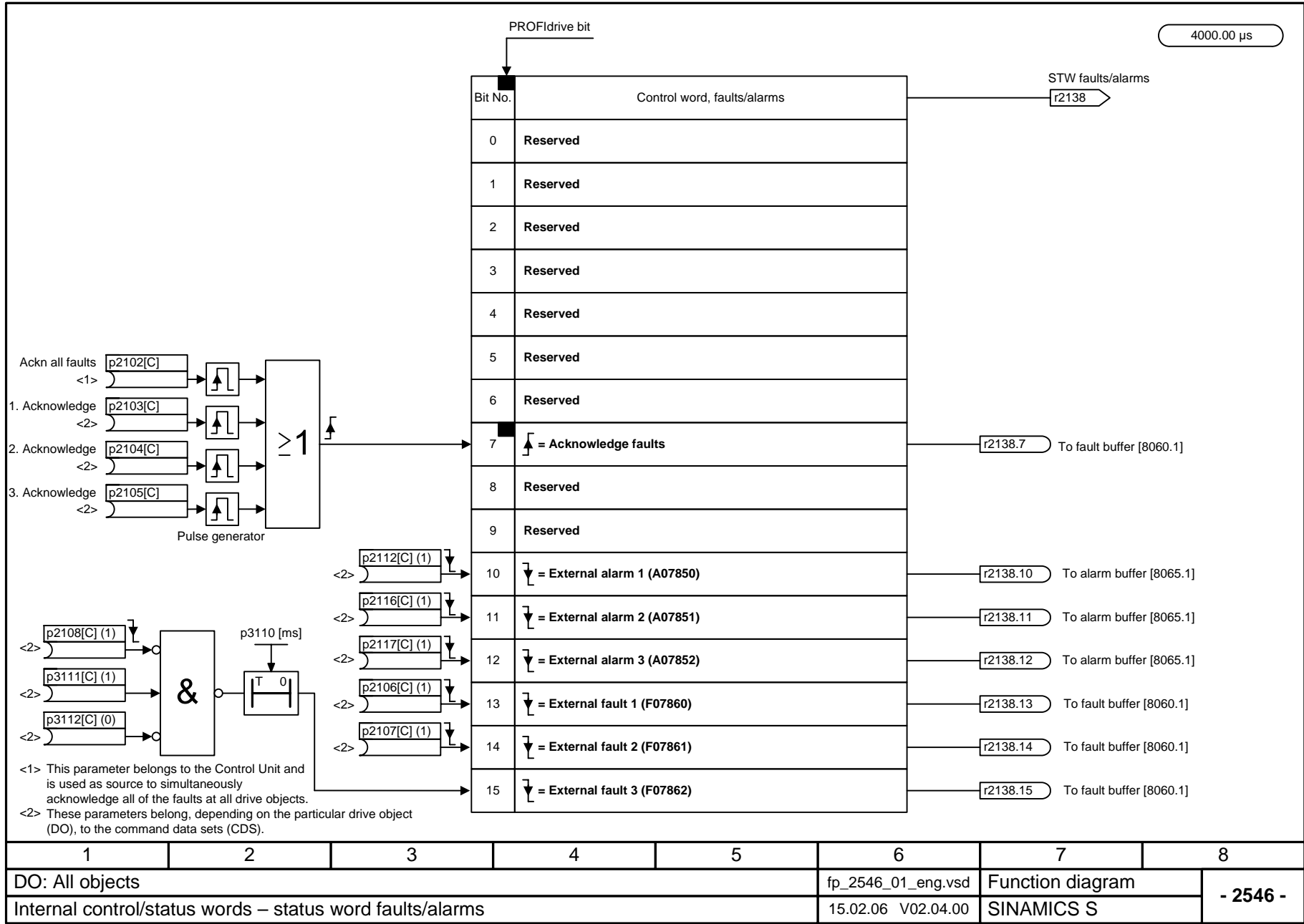
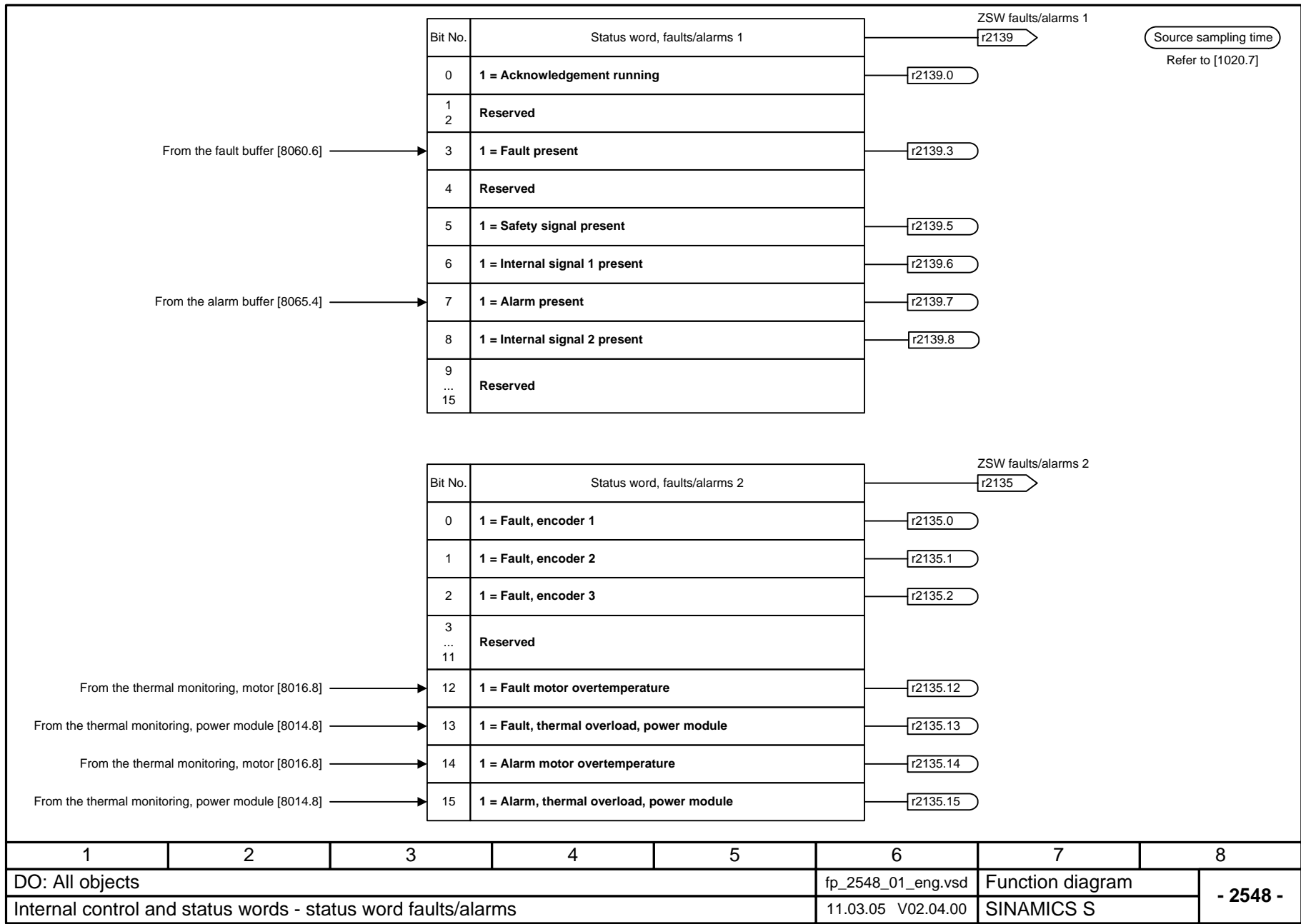


Figure 2-78 2546 – Control word faults/alarms



Source sampling time
Refer to [1020.7]

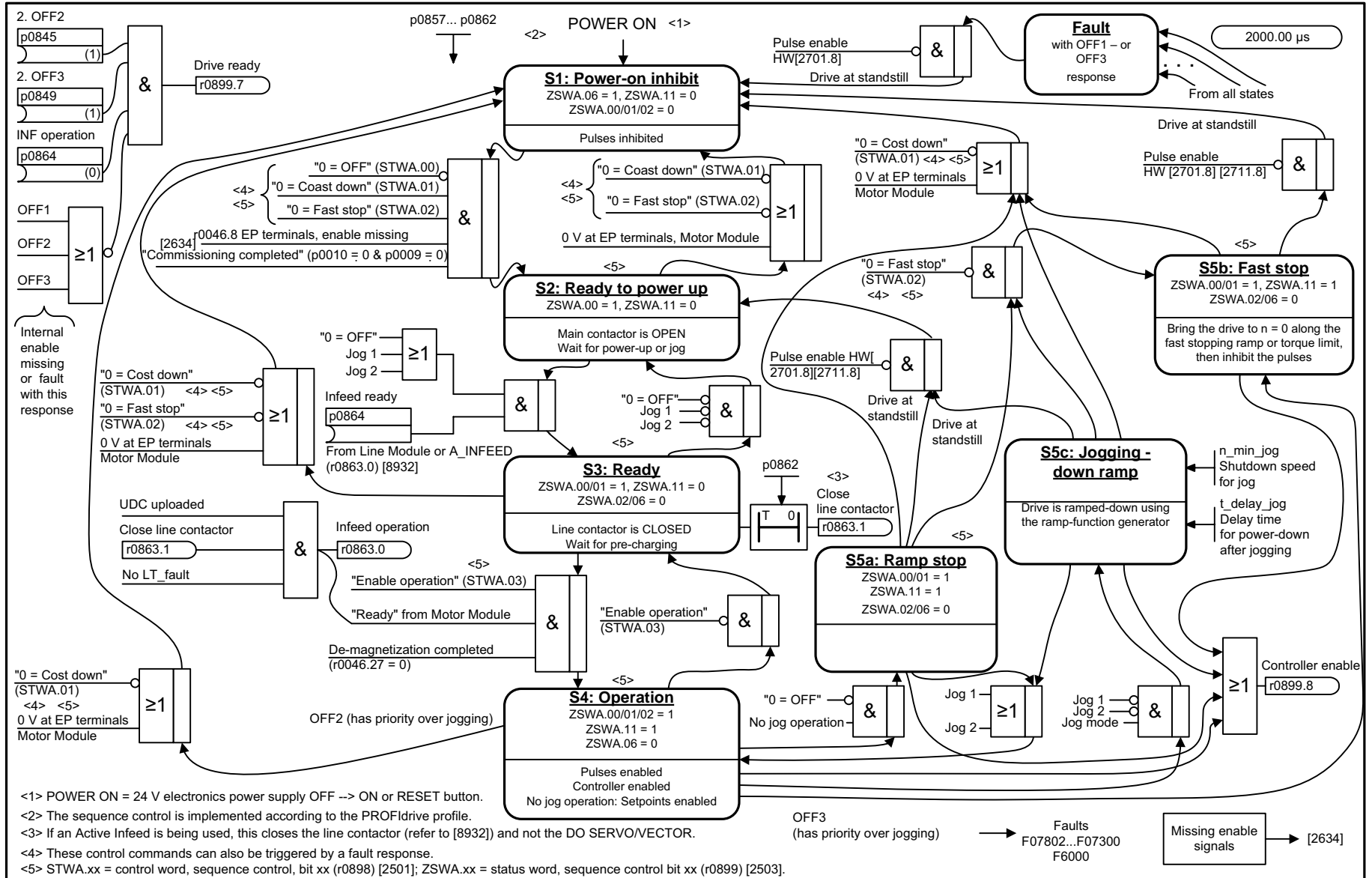
Figure 2-79 2548 – Status word, faults/warnings 1 and 2

2.10 Sequence control

Function diagrams

2610 – Control unit	2-1003
2634 – Missing enable signals, line contactor control	2-1004

Figure 2-80 2610 – Control unit



<1> POWER ON = 24 V electronics power supply OFF --> ON or RESET button.
 <2> The sequence control is implemented according to the PROFdrive profile.
 <3> If an Active Infeed is being used, this closes the line contactor (refer to [8932]) and not the DO SERVO/VECTOR.
 <4> These control commands can also be triggered by a fault response.
 <5> STWA.xx = control word, sequence control, bit xx (r0898) [2501]; ZSWA.xx = status word, sequence control bit xx (r0899) [2503].

Function diagrams
 Sequence control

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2610_01_eng.vsd	Function diagram	
Sequence control					07.02.06 V02.04.00	SINAMICS S	
							- 2610 -

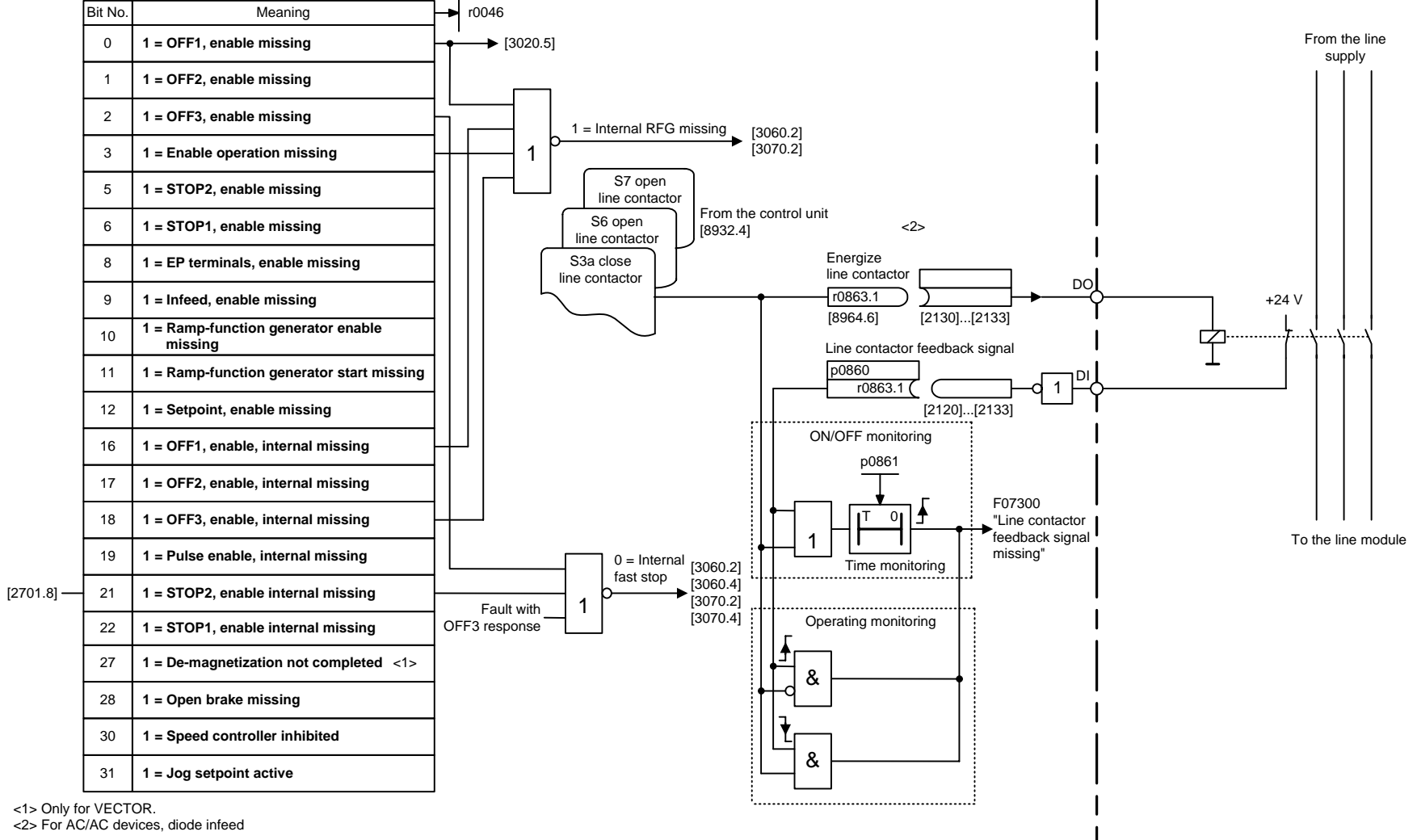
Missing enable signals

Missing enable signals that prevent the drive going into operation (this situation can be detected at the ZSW sequence control, infeed r0899.2 = 1 [8926]).

Bit No.	Meaning
0	1 = OFF1, enable missing
1	1 = OFF2, enable missing
2	1 = OFF3, enable missing
3	1 = Enable operation missing
5	1 = STOP2, enable missing
6	1 = STOP1, enable missing
8	1 = EP terminals, enable missing
9	1 = Infeed, enable missing
10	1 = Ramp-function generator enable missing
11	1 = Ramp-function generator start missing
12	1 = Setpoint, enable missing
16	1 = OFF1, enable, internal missing
17	1 = OFF2, enable, internal missing
18	1 = OFF3, enable, internal missing
19	1 = Pulse enable, internal missing
21	1 = STOP2, enable internal missing
22	1 = STOP1, enable internal missing
27	1 = De-magnetization not completed <1>
28	1 = Open brake missing
30	1 = Speed controller inhibited
31	1 = Jog setpoint active

Line contactor control

Control unit



<1> Only for VECTOR.
<2> For AC/AC devices, diode infeed

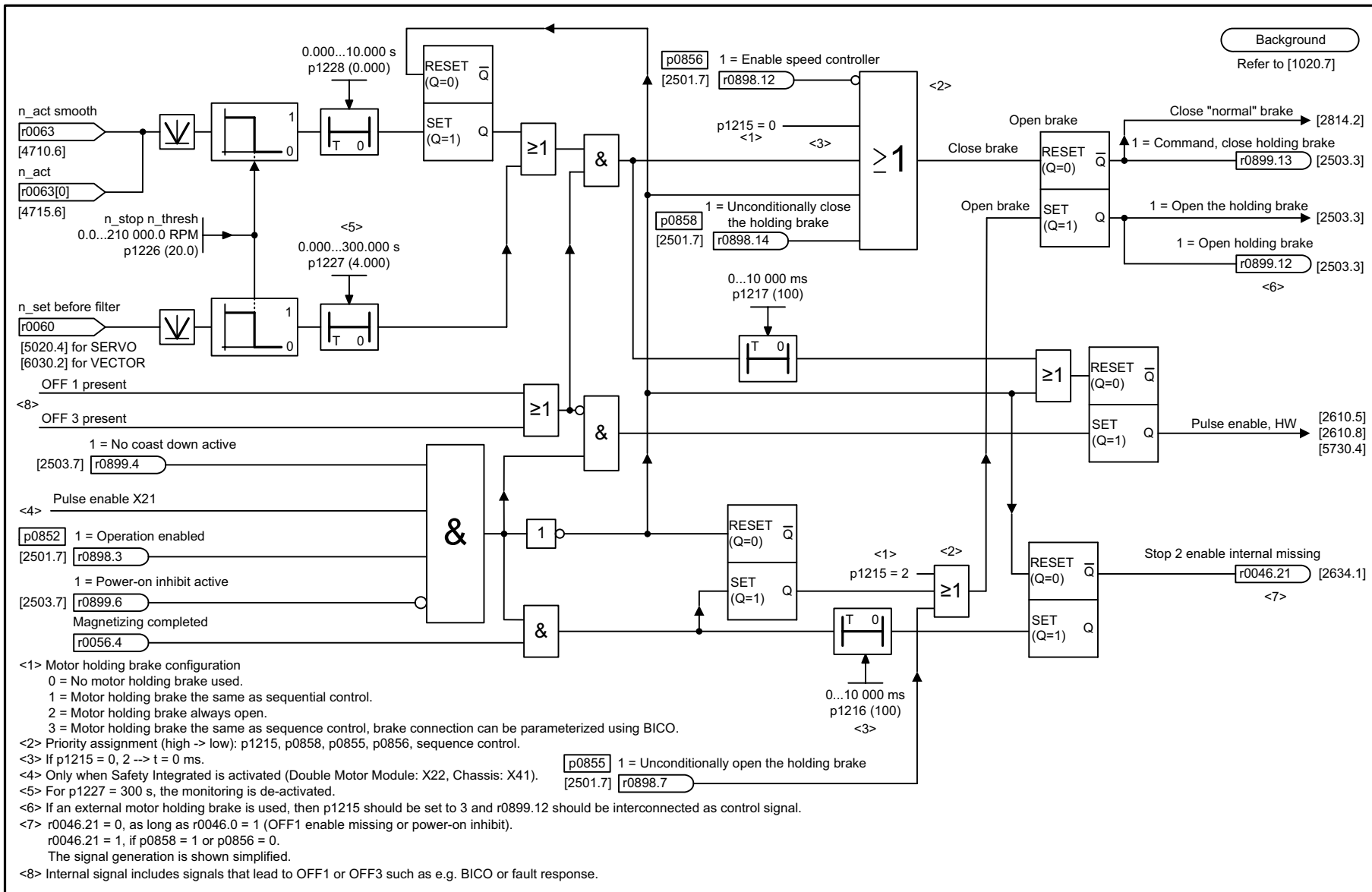
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2634_01_eng.vsd	Function diagram	
Sequence control - missing enable signals, line contactor control					14.12.05 V02.04.00	SINAMICS S	
							- 2634 -

Figure 2-81 2634 – Missing enable signals, line contactor control

2.11 Brake control

Function diagrams

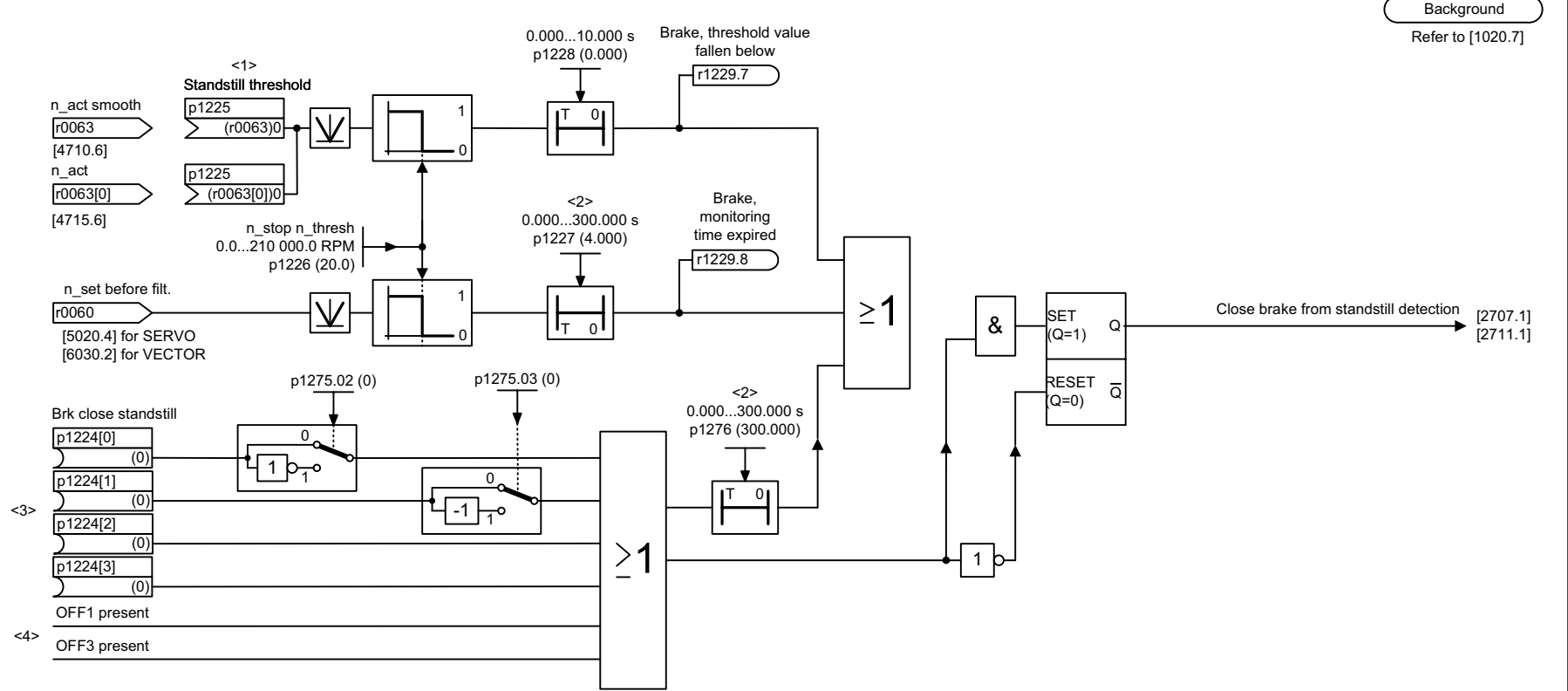
2701 – Basic brake control (r0108.14 = 0)	2-1006
2704 – Extended brake control/zero speed detection (r0108.14 = 1)	2-1007
2707 – Extended brake control/open and close brake (r0108.14 = 1)	2-1008
2711 – Extended brake control/signal outputs (r0108.14 = 1)	2-1009



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2701_01_eng.vsd	Function diagram	
Brake control - basic brake control (r0108.14 = 0)					29.03.06 V02.04.00	SINAMICS S	
							- 2701 -

Figure 2-82 2701 – Basic brake control (r0108.14 = 0)

Figure 2-83 2704 – Extended brake control/zero speed detection (r0108.14 = 1)



- <1> Shutdown threshold of the standstill detection. Here (e.g. when using a brake), another criterion to cancel the pulses can be selected other than the speed actual value. Otherwise, we recommend that the factory setting is kept.
- <2> For p1276 = 300.000 s, the timer is de-activated, i.e. the timer output is always 0. Note: When operating a motor with a brake, which may not be closed while the motor is rotating, then the monitoring time of both timers must be set to 300 s.
- <3> For operation without brake, p1224[0...3] must be = 0 (factory setting) in order to avoid undesirable interaction with the sequence control.
- <4> Internal signal contains signals that lead to OFF1 or OFF3 such as e.g. BICO or fault response.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2704_01_eng.vsd	Function diagram	
Brake control - expanded brake control/standstill detection (r0108.14 = 1)					23.03.06 V02.04.00	SINAMICS S	

Background
 Refer to [1020.7]

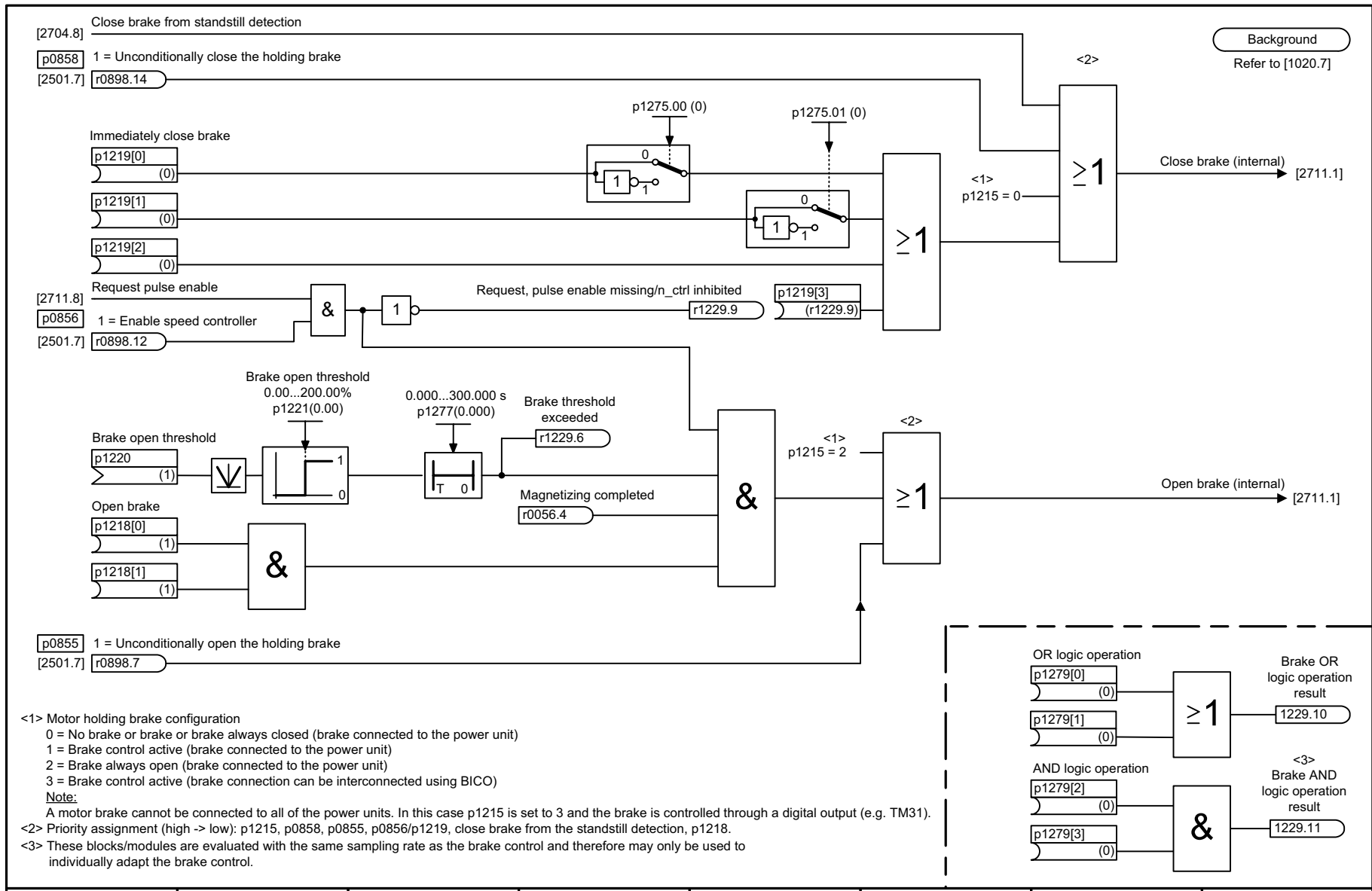
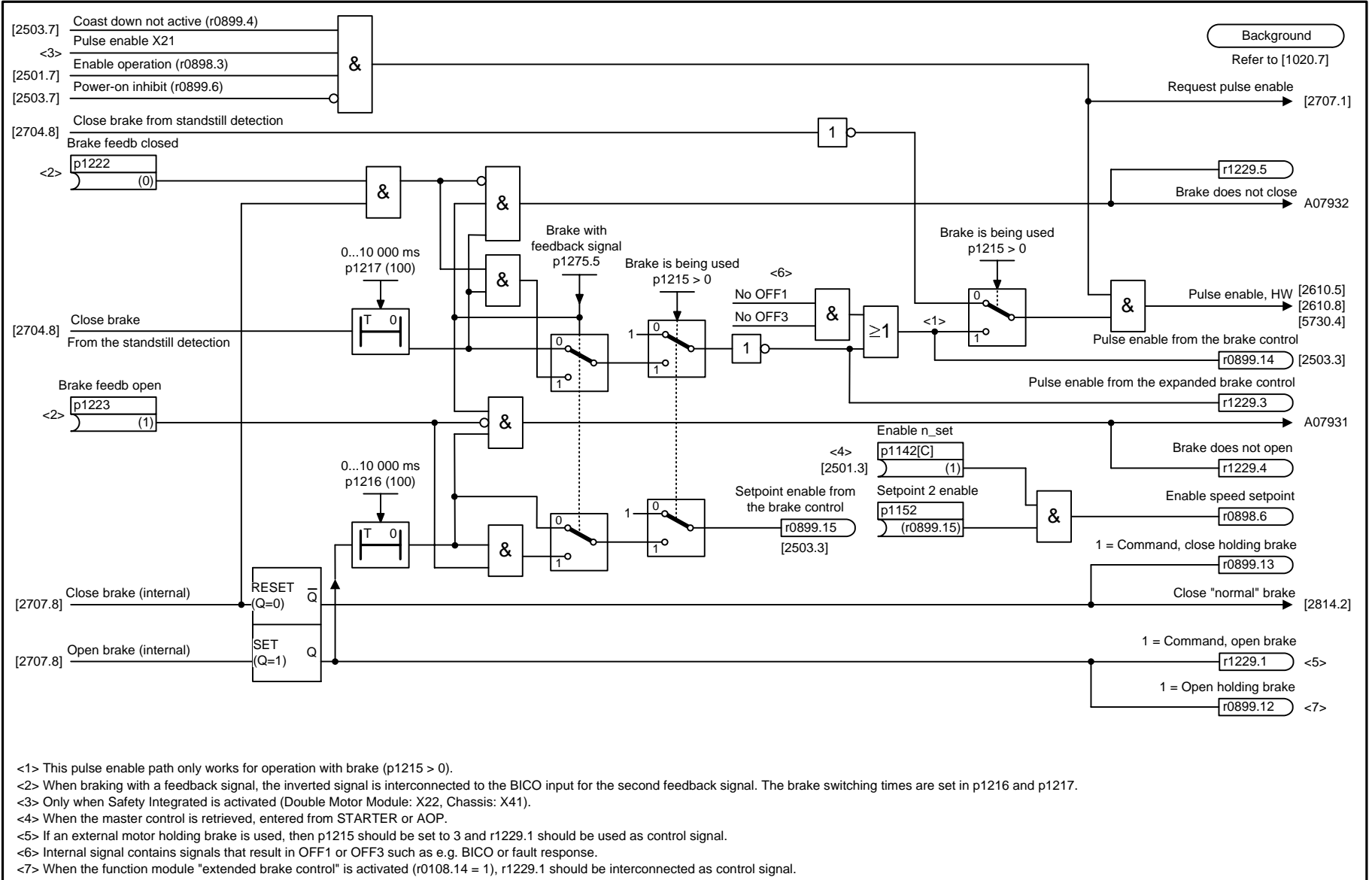


Figure 2-84 2707 – Extended brake control/open and close brake (r0108.14 = 1)

2-1008

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2707_01_eng.vsd	Function diagram	
Brake control - Extended brake control / open/close brake (r0108.14 = 1)					29.03.06 V02.04.00	SINAMICS S	
							- 2707 -

Figure 2-85 2711 – Extended brake control/signal outputs (r0108.14 = 1)



- <1> This pulse enable path only works for operation with brake (p1215 > 0).
- <2> When braking with a feedback signal, the inverted signal is interconnected to the BICO input for the second feedback signal. The brake switching times are set in p1216 and p1217.
- <3> Only when Safety Integrated is activated (Double Motor Module: X22, Chassis: X41).
- <4> When the master control is retrieved, entered from STARTER or AOP.
- <5> If an external motor holding brake is used, then p1215 should be set to 3 and r1229.1 should be used as control signal.
- <6> Internal signal contains signals that result in OFF1 or OFF3 such as e.g. BICO or fault response.
- <7> When the function module "extended brake control" is activated (r0108.14 = 1), r1229.1 should be interconnected as control signal.

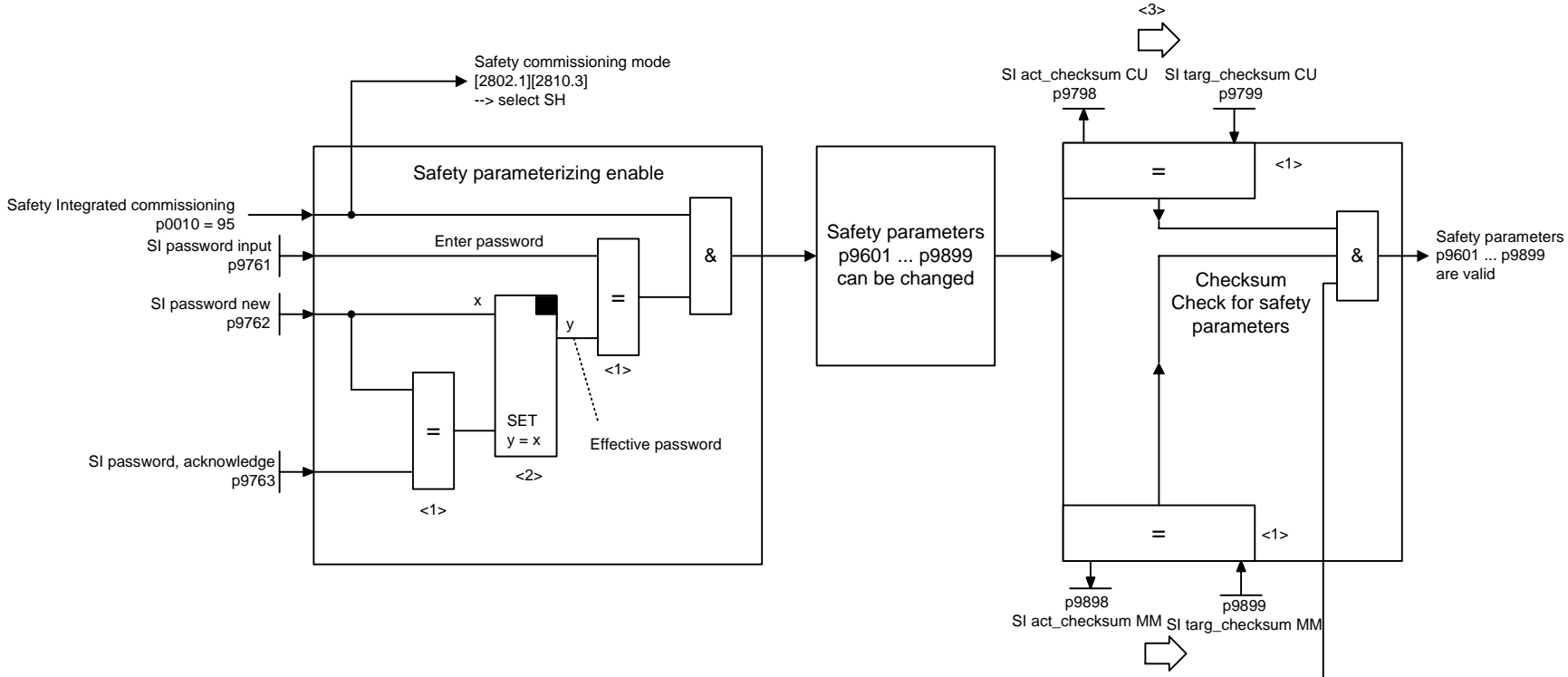
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2711_01_eng.vsd	Function diagram	
Brake control - extended brake control/signal outputs (r0108.14 = 1)					07.04.05 V02.04.00	SINAMICS S	
							- 2711 -

2.12 Safety Integrated

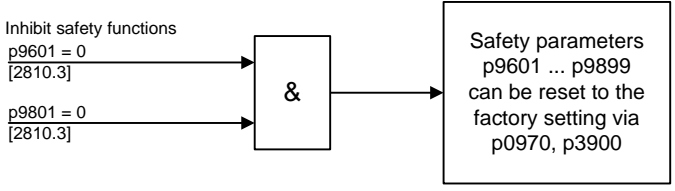
Function diagrams

2800 – Parameter manager	2-1011
2802 – Monitoring functions and faults/alarms	2-1012
2804 – Status words	2-1013
2810 – Safe standstill (SH)	2-1014
2814 – Safe brake control (SBC)	2-1015

Change safety parameter



Reset safety parameter



<1> Comparator, refer to [1021]
 <2> Analog signal memory, refer to [1021]
 <3> Target checksum must be equal to the actual checksum.

Figure 2-86 2800 – Parameter manager

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2800_01_eng.vsd	Function diagram	
Safety Integrated - parameter manager					25.01.06 V02.04.00	SINAMICS S	
- 2800 -							

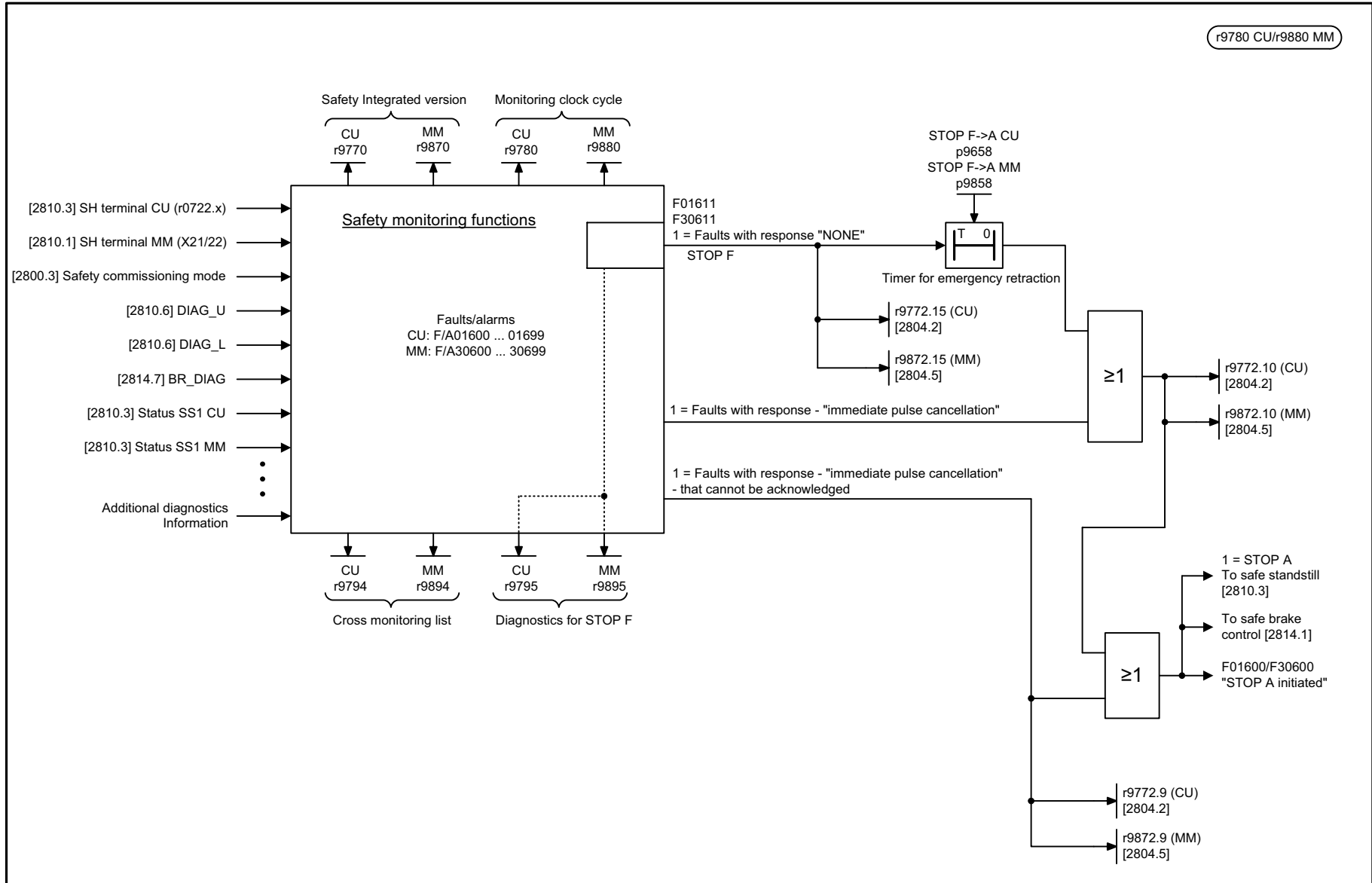


Figure 2-87 2802 – Monitoring functions and faults/alarms

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_2802_01_eng.vsd	Function diagram	
Safety Integrated – Monitoring functions and faults/alarms					14.03.06 V02.04.00	SINAMICS S	
							- 2802 -

Figure 2-88 2804 – Status words

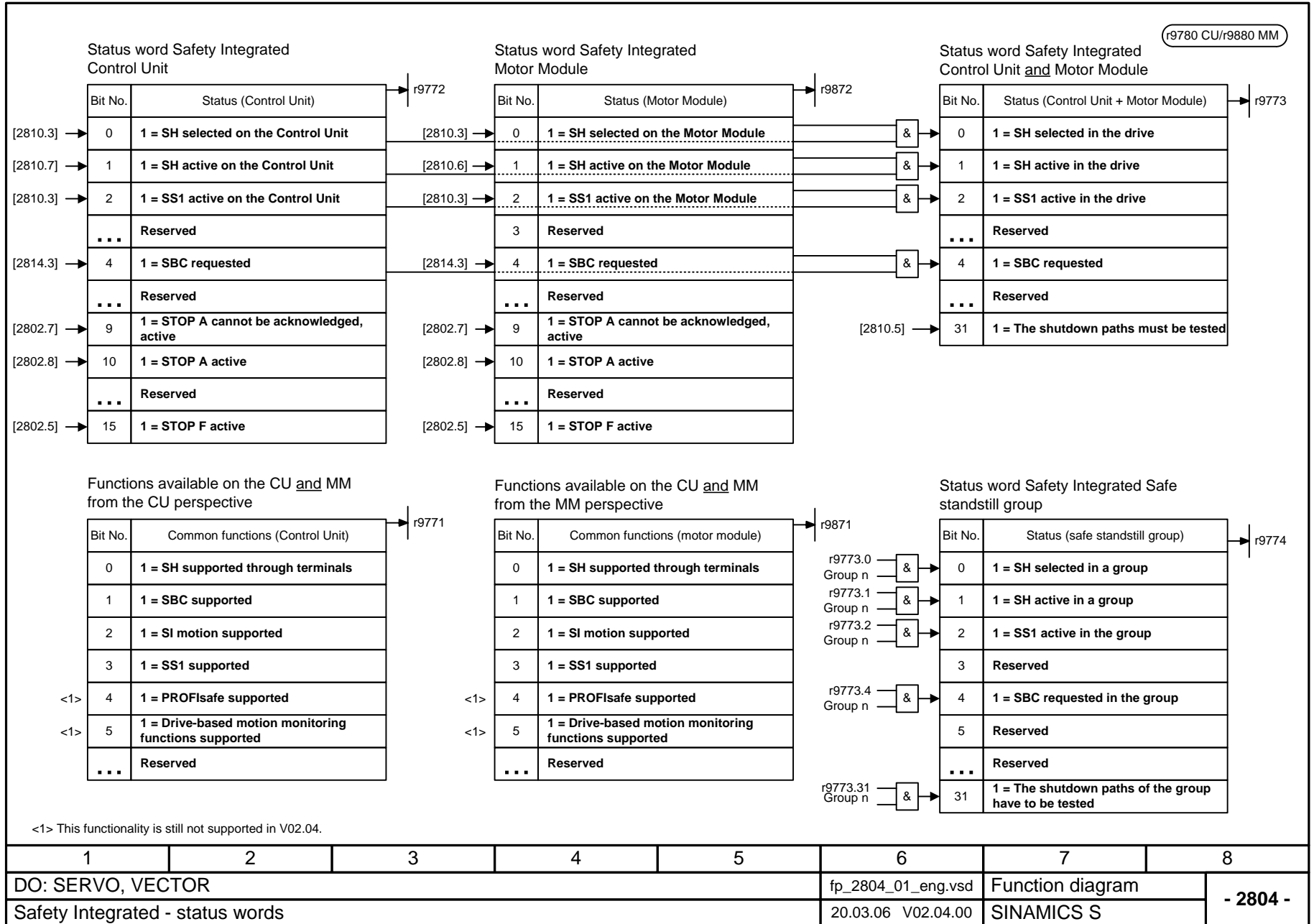


Figure 2-89 2810 – Safe standstill (SH)

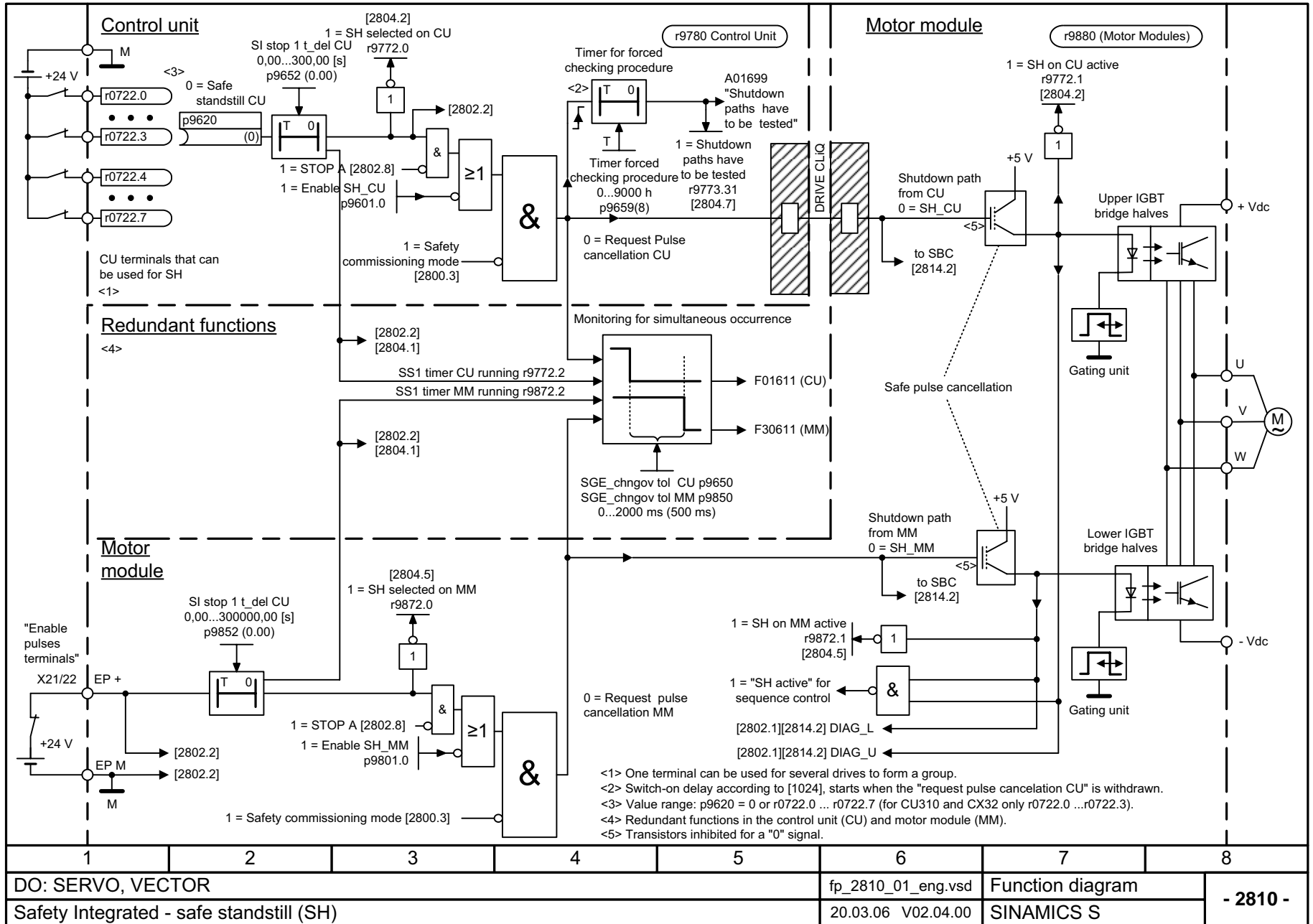
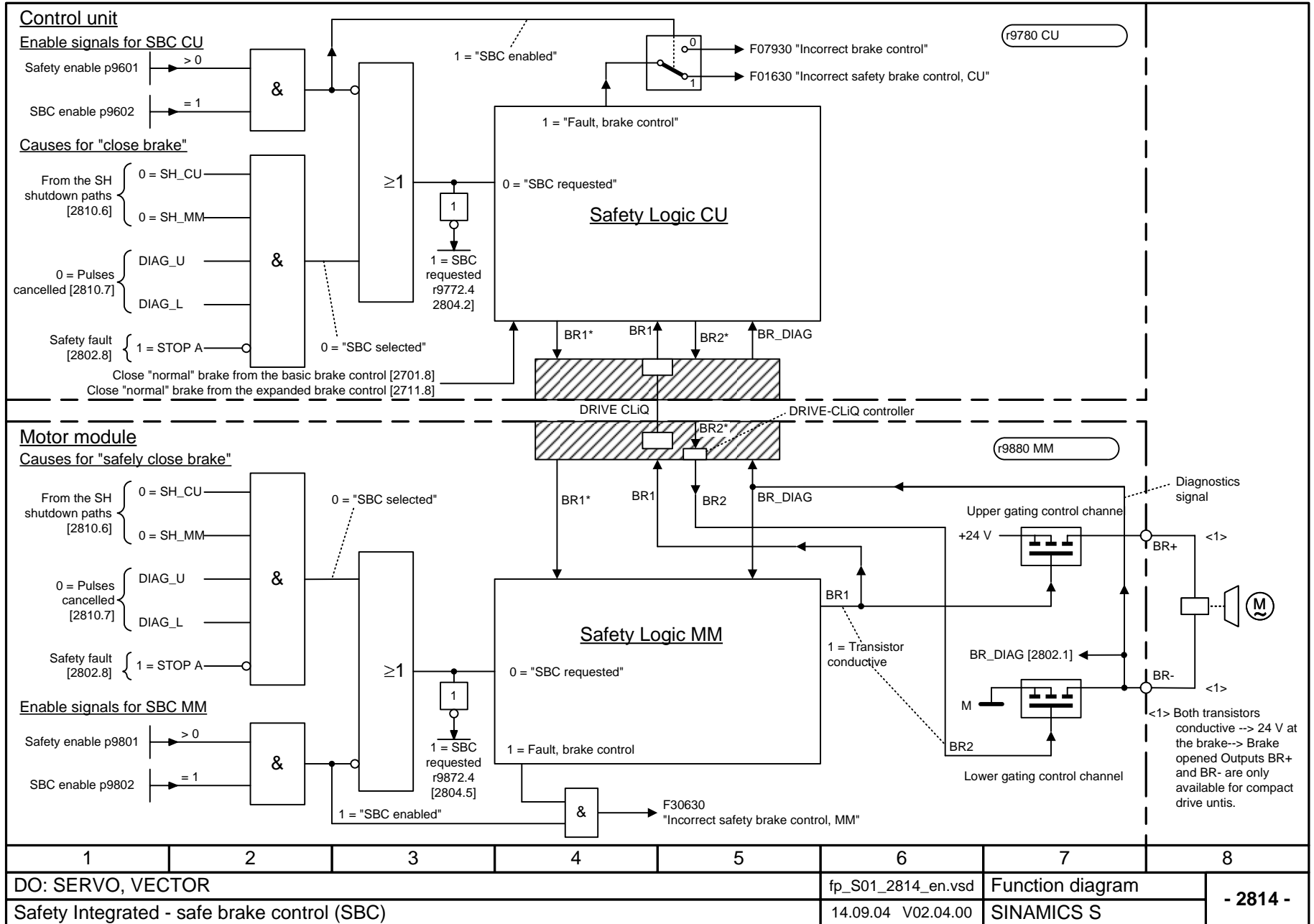


Figure 2-90 2814 – Safe brake control (SBC)

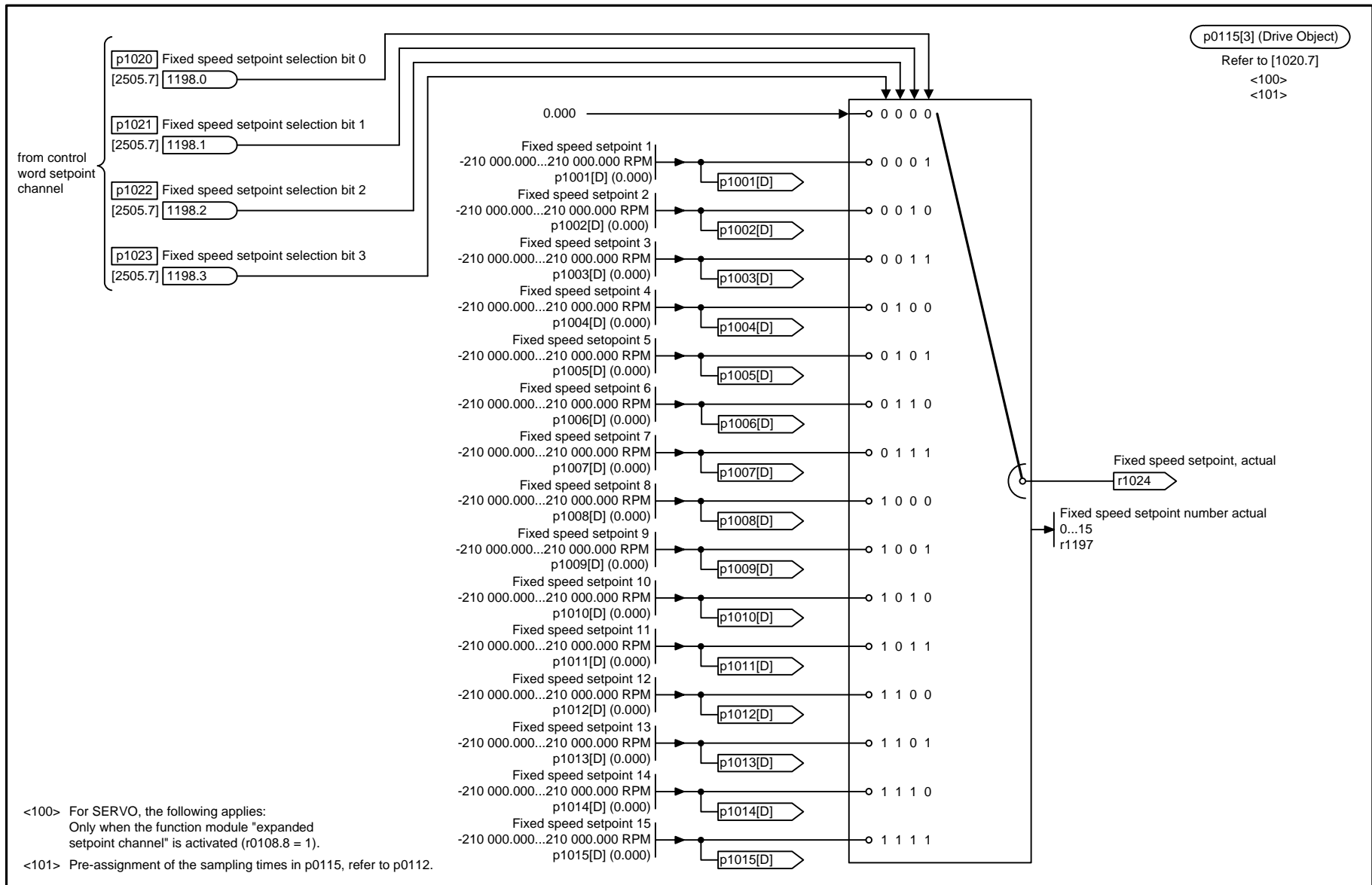


Function diagrams
Safety Integrated

2.13 Setpoint channel

Function diagrams

3010 – Fixed speed setpoints	2-1017
3020 – Motorized potentiometer	2-1018
3030 – Main/supplementary setpoint, setpoint scaling, jogging	2-1019
3040 – Direction of rotation limitation and direction of rotation reversal	2-1020
3050 – Suppression bandwidth and speed limiting	2-1021
3060 – Simple ramp-function generator	2-1022
3070 – Expanded ramp-function generator	2-1023
3080 – Ramp-function generator selection, status word, tracking	2-1024
3090 – Dynamic Servo Control (DSC)	2-1025

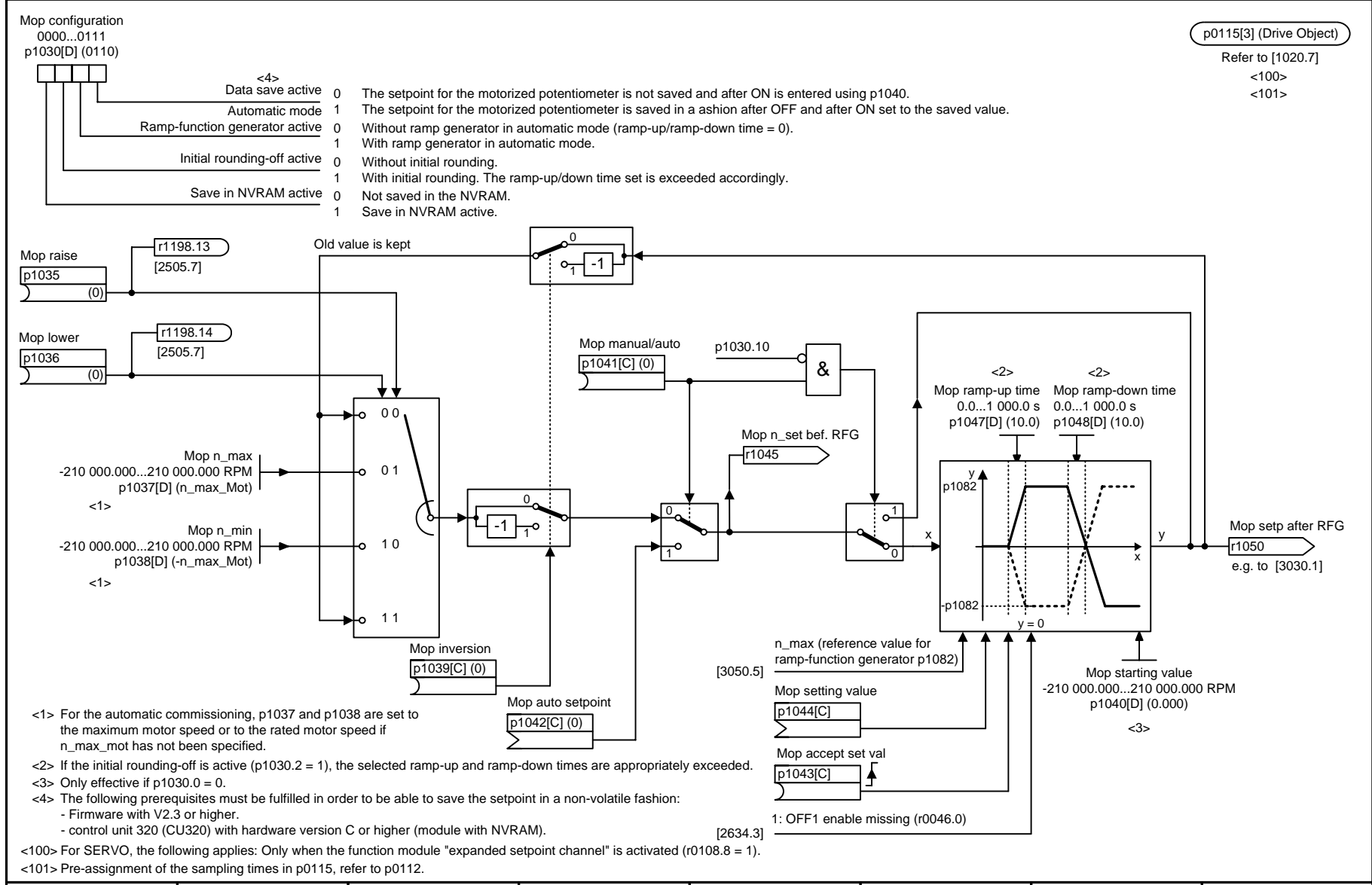


<100> For SERVO, the following applies:
Only when the function module "expanded setpoint channel" is activated (r0108.8 = 1).

<101> Pre-assignment of the sampling times in p0115, refer to p0112.

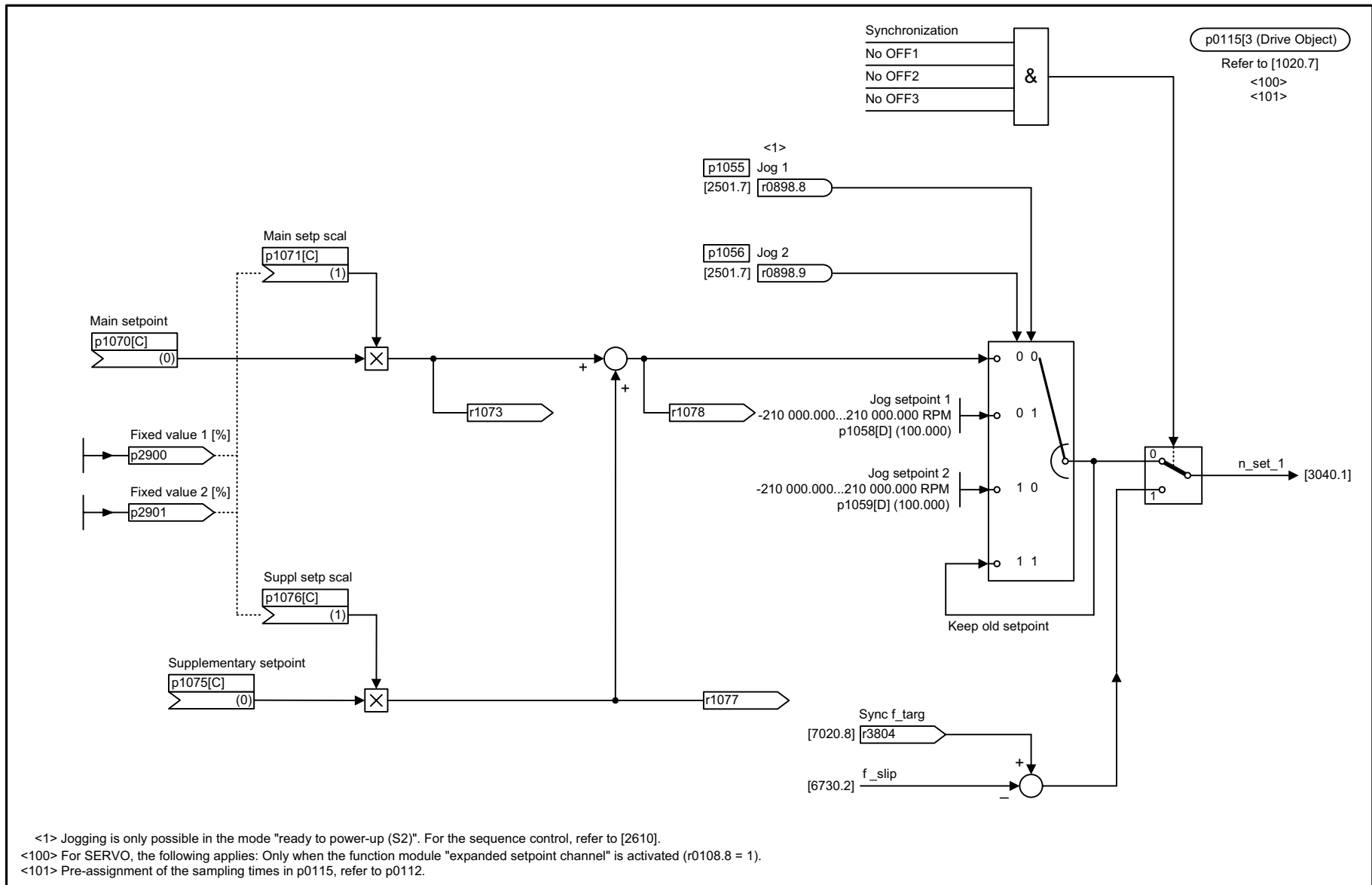
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3010_01_eng.vsd	Function diagram	
Setpoint channel - fixed speed setpoints					24.02.05 V02.04.00	SINAMICS S	
							- 3010 -

Figure 2-91 3010 – Fixed speed setpoints



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3020_01_eng.vsd	Function diagram	
Setpoint channel - motorized potentiometer					08.07.05 V02.04.00	SINAMICS S	
							- 3020 -

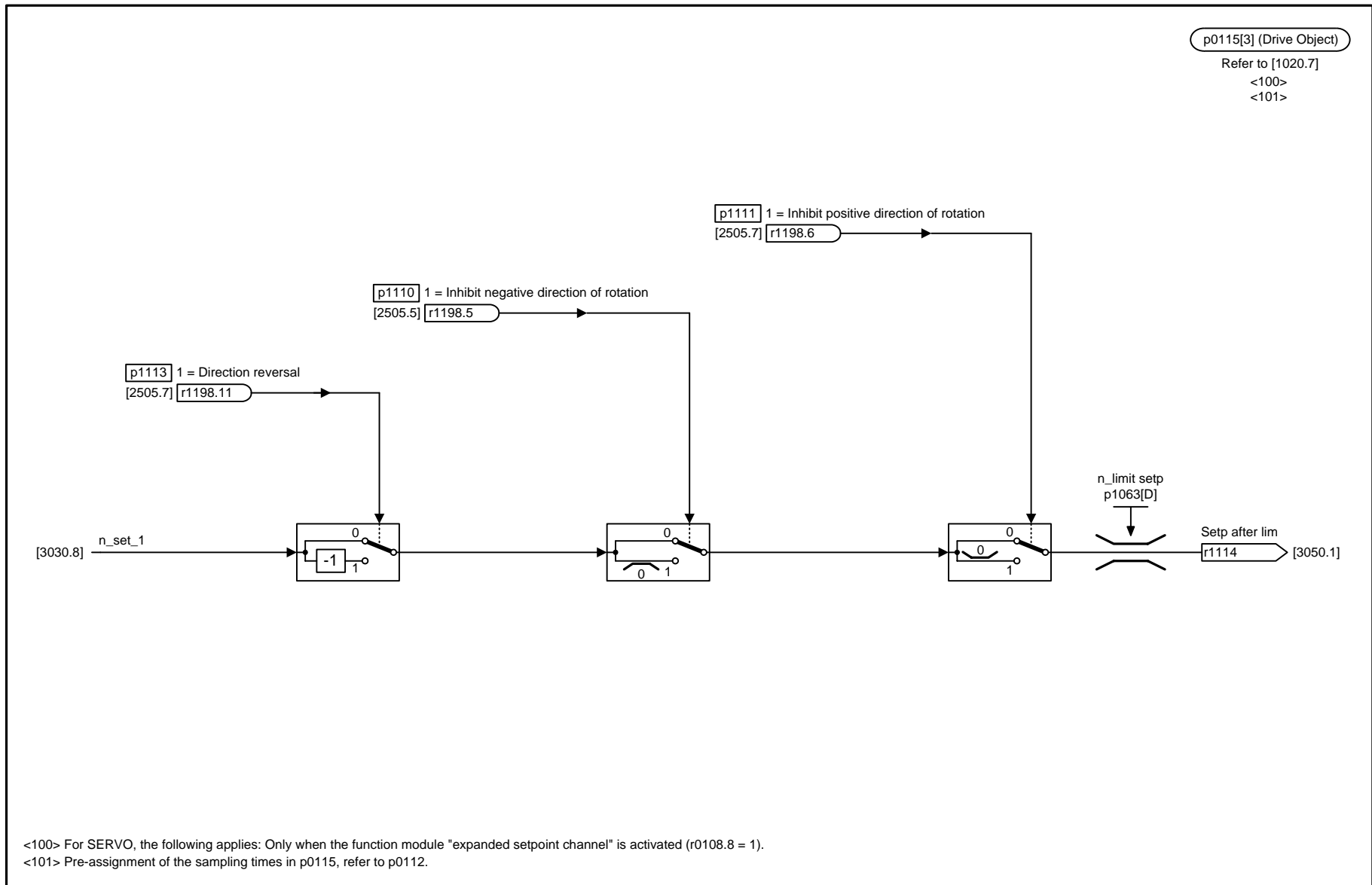
Figure 2-92 3020 – Motorized potentiometer



<1> Jogging is only possible in the mode "ready to power-up (S2)". For the sequence control, refer to [2610].
 <100> For SERVO, the following applies: Only when the function module "expanded setpoint channel" is activated (r0108.8 = 1).
 <101> Pre-assignment of the sampling times in p0115, refer to p0112.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3030_01_eng.vsd	Function diagram	
Setpoint channel - main/supplementary setpoint, setpoint scaling, jogging					23.03.06 V02.04.00	SINAMICS S	
							- 3030 -

Figure 2-93 3030 – Main/supplementary setpoint, setpoint scaling, jogging

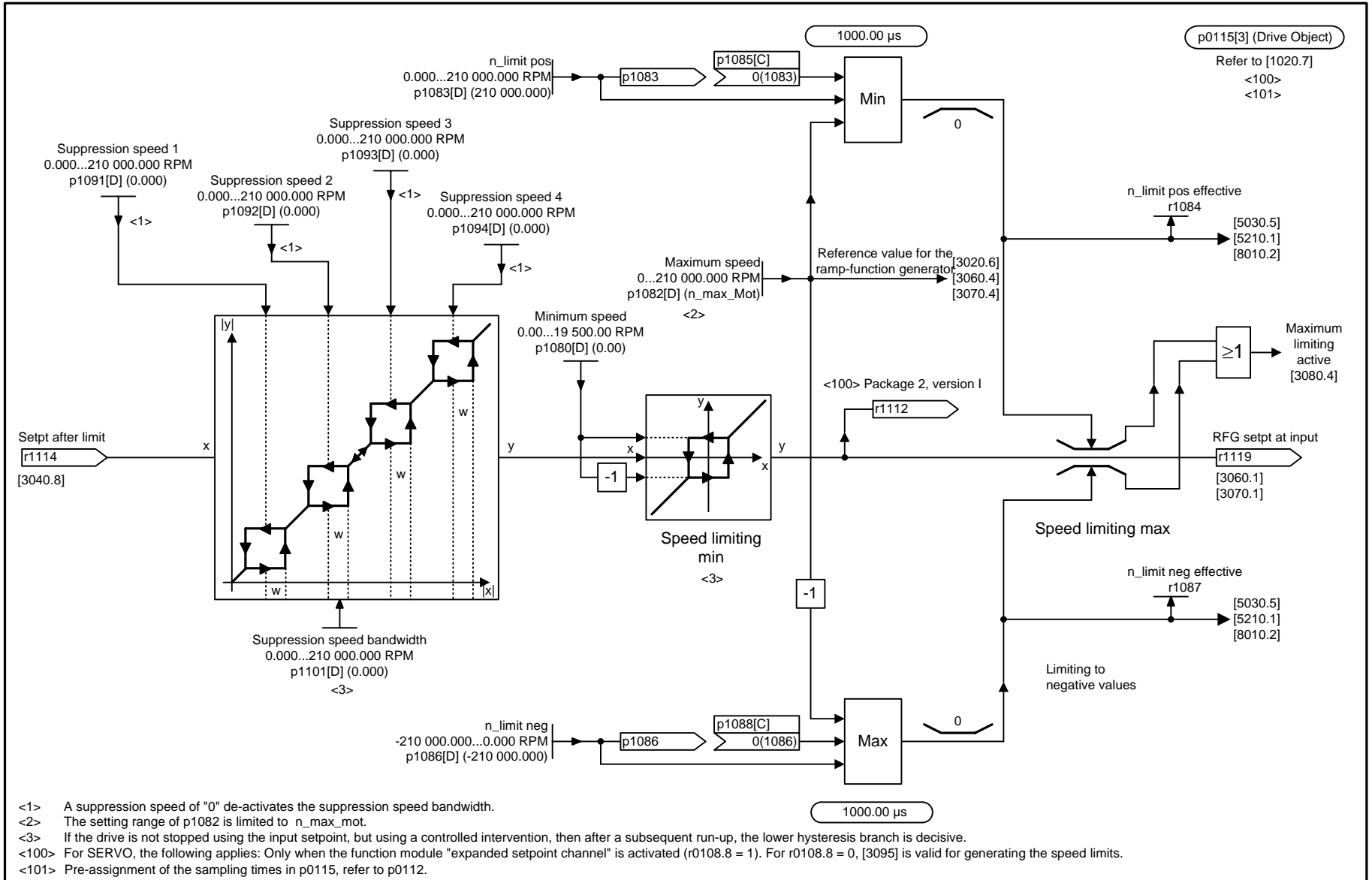


<100> For SERVO, the following applies: Only when the function module "expanded setpoint channel" is activated (r0108.8 = 1).
<101> Pre-assignment of the sampling times in p0115, refer to p0112.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3040_01_eng.vsd	Function diagram	
Setpoint channel - Direction of rotation limiting and direction of rotation reversal					24.06.05 V02.04.00	SINAMICS S	

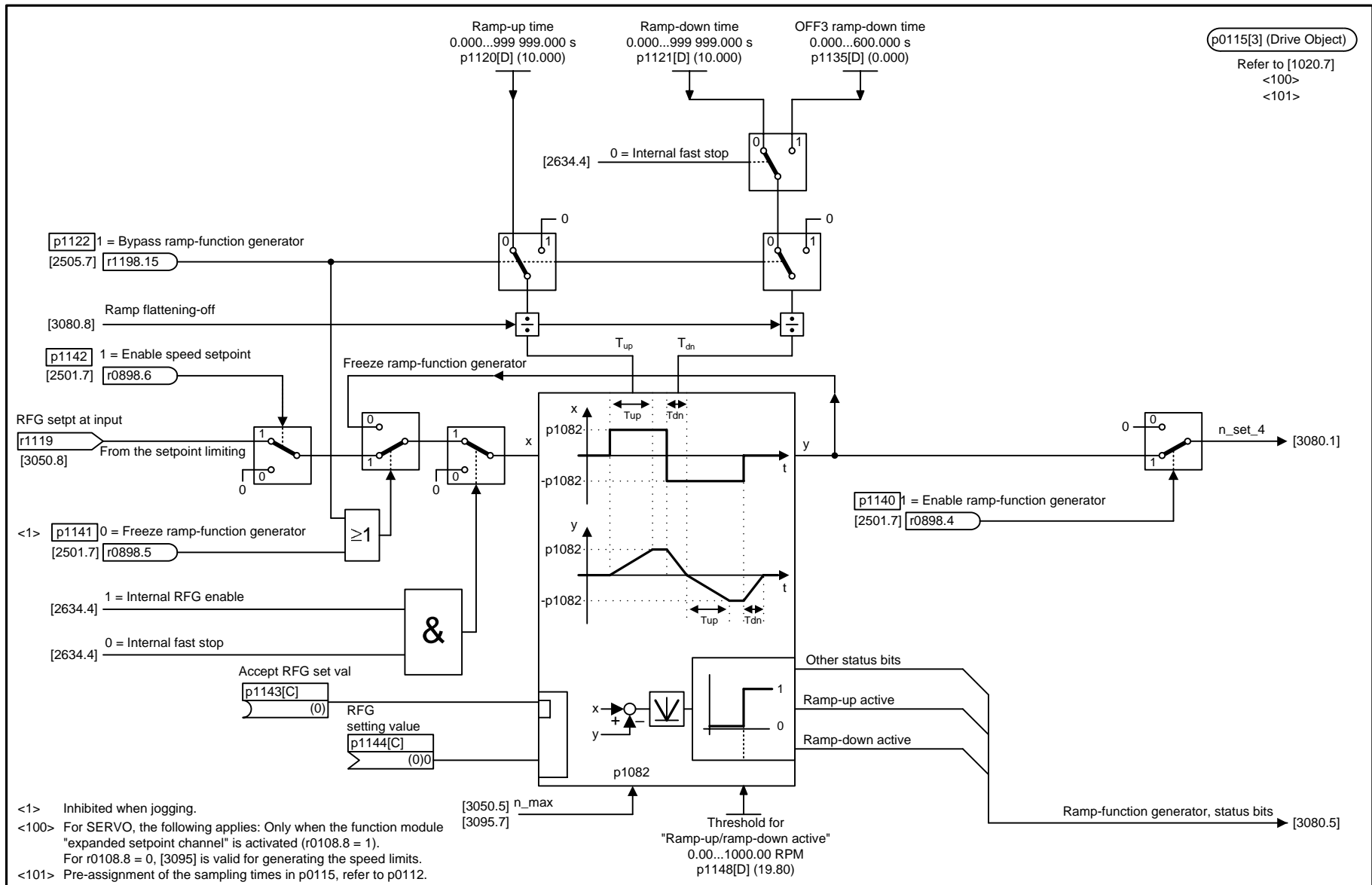
Figure 2-94 3040 – Direction of rotation limitation and direction of rotation reversal

Figure 2-95 3050 – Suppression bandwidth and speed limiting



Function diagrams
 Setpoint channel

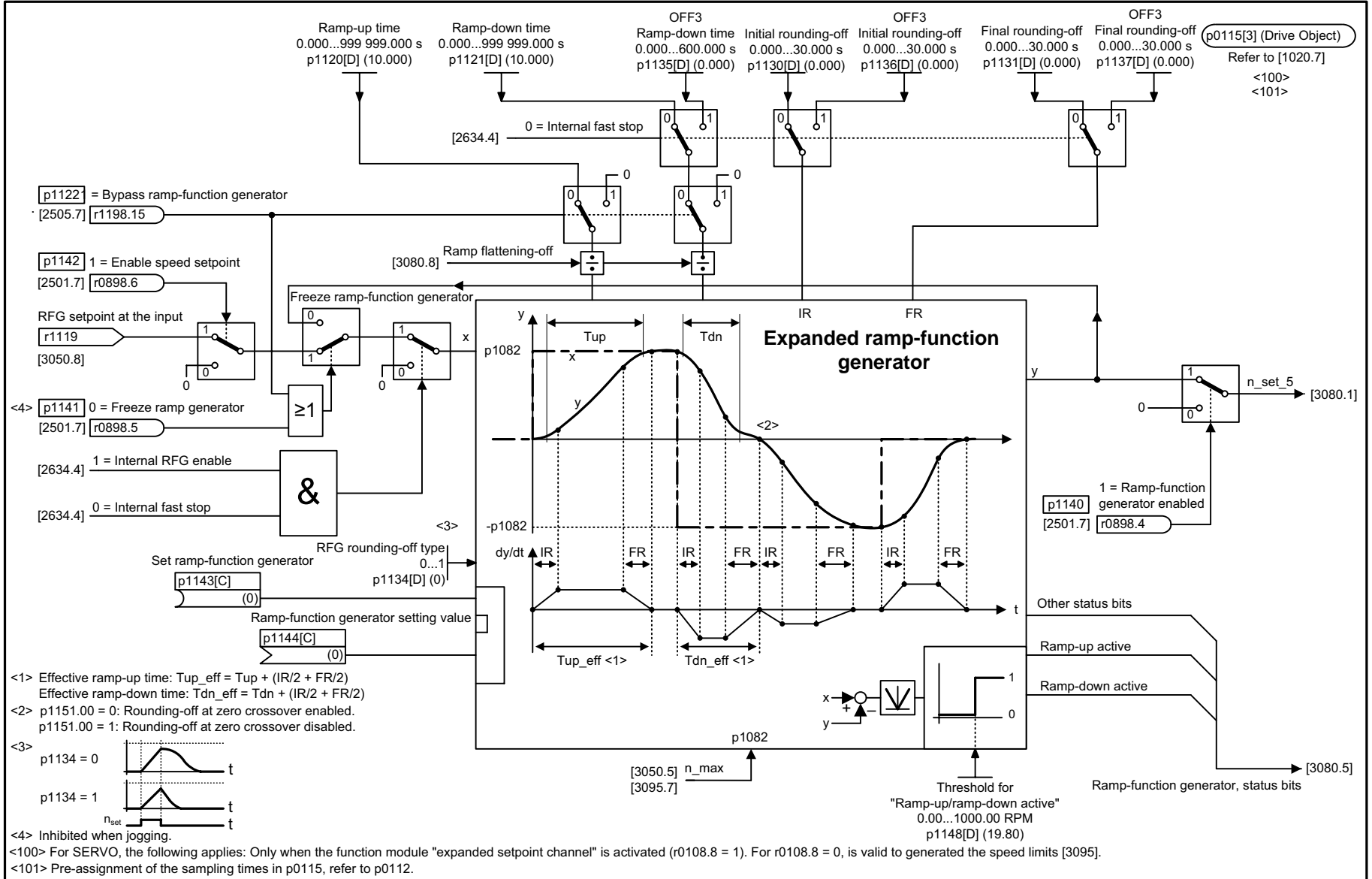
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3050_01_eng.vsd	Function diagram	
Setpoint channel - suppression bandwidth and speed limiting					08.06.05 V02.04.00	SINAMICS S	
							- 3050 -



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3060_01_eng.vsd	Function diagram	
Setpoint channel - basic ramp-function generator					28.07.05 V02.04.00	SINAMICS S	
- 3060 -							

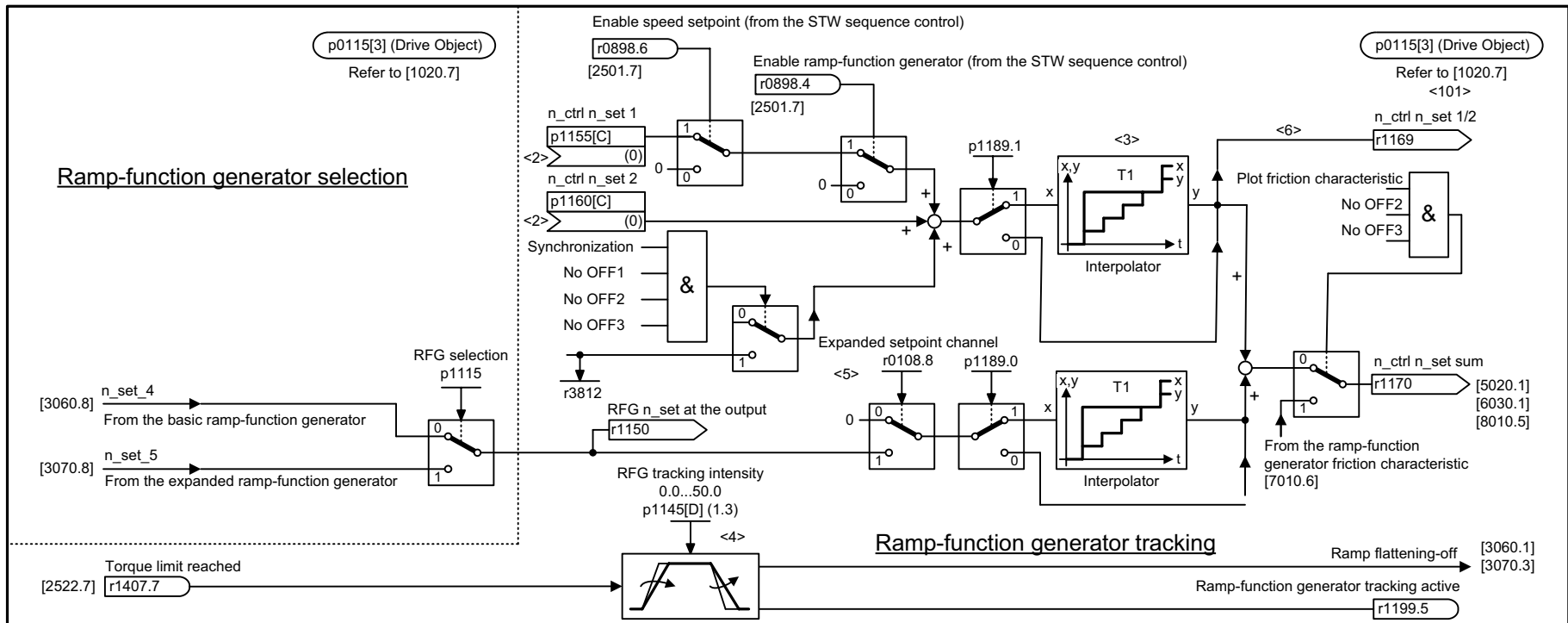
Figure 2-96 3060 – Simple ramp-function generator

Figure 2-97 3070 – Expanded ramp-function generator



Function diagrams
Setpoint channel

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3070_01_eng.vsd	Function diagram	
Setpoint channel - expanded ramp-function generator					23.02.06 V02.04.00	SINAMICS S	
							- 3070 -



- <1> For $p1145 > 0$, the ramp-function generator tracking is activated when the torque limiting responds. This means that the speed controller output only exceeds the torque limit by a deviation that can be set using $p1145$.
- <2> For OFF1/OFF3 the ramp-function generator ramp is active. The ramp-function generator is set (SERVO: to the actual value, VECTOR to the setpoint ($r1170$)) and stops the drive with the ramp-downtime ($p1121$ or $p1135$). STW1.4 (enable ramp-function generator) is effective while the drive is being stopped via the ramp-function generator. Depending on the $p1115$, the basic ramp-function generator [3060] or the extended ramp-function generator [3070] is effective. When the function module "extended setpoint channel" ($r0108.8 = 0$) is not active for OFF1/OFF3, the down ramp of the basic ramp-function generator is effective (refer to n_set_4 on [3060.8]).
- <3> The interpolator is only effective for clock-cycle synchronous PROFIBUS operation and sign-of-life received from the master (STW2.12 ... STW2.15).
- <4> Behavior of the response ramp of the torque limiting:
 $p1145 = 0.0$: No ramp-function generator tracking. The ramp-function generator ramp distances itself from the speed actual value.
 $p1145 = 1.0$: The ramp-function generator ramp remains as close as possible to the speed actual value.
 $p1145 > 1.0$: The ramp-function generator ramp is steeper than for $p1145 = 1.0$ (higher "speed following error").
- <5> For SERVO, the following applies: Only when the function module "expanded setpoint channel" is activated ($r0108.8 = 1$).
- <6> The value is only correctly displayed if the drive is enabled.
- <101> Pre-assignment of the sampling times in $p0115$, refer to $p0112$.

Ramp-function generator status word

Bit	Ramp-function generator status word
0	Ramp-up active
1	Ramp-down active
2	Ramp-function generator active
3	Ramp-function generator set
4	Ramp-function generator held
5	Ramp-function generator tracking active
6	Maximum limiting active
7	Reserved
8	Reserved
9	Reserved
10	Reserved
11	Reserved
12	Reserved
13	Reserved
14	Reserved
15	Reserved

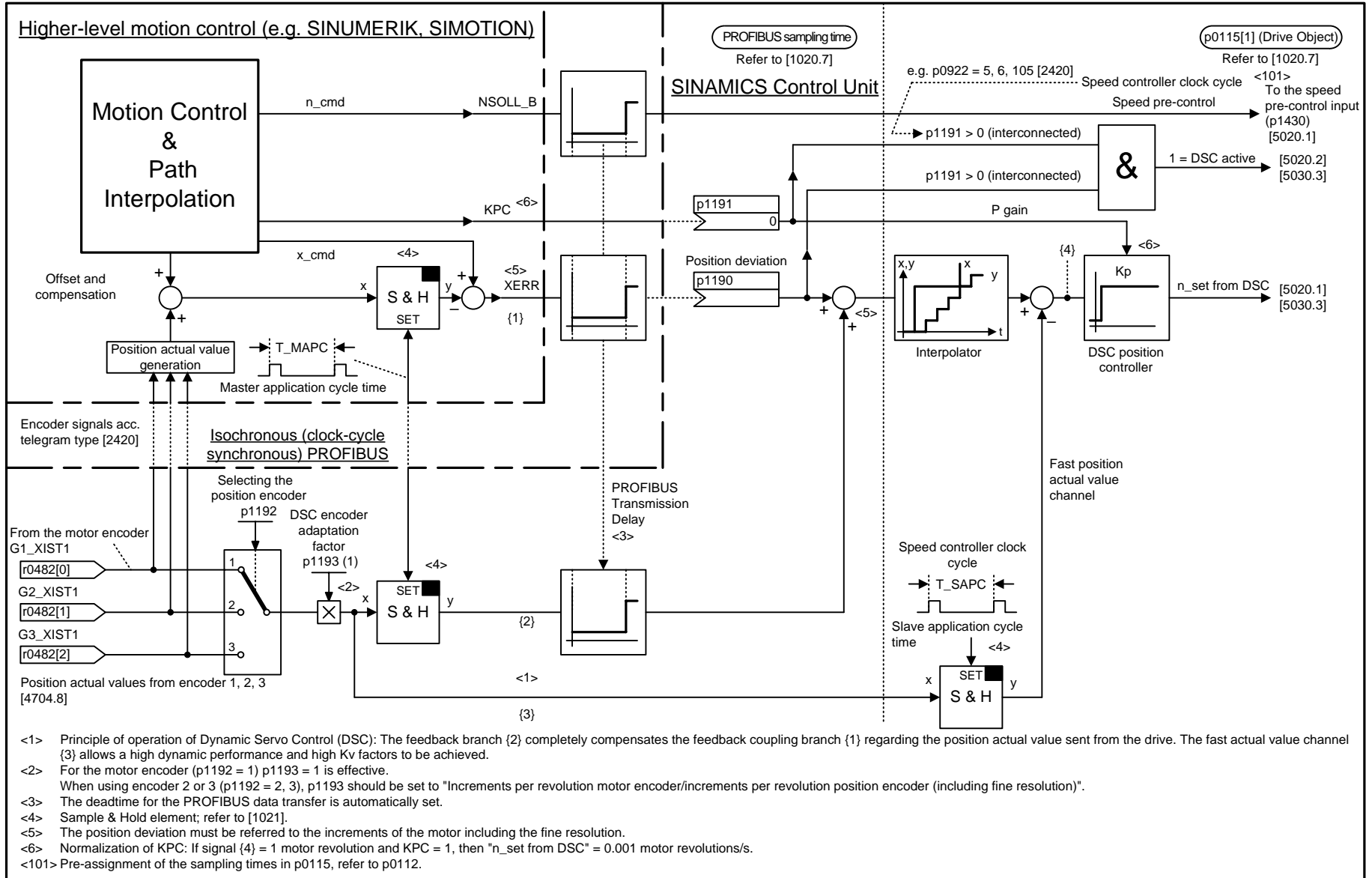
Bit 0-2 are connected to $r1199$. Bit 3-5 are connected to $r1199.2$ [8010.5]. Bit 6 is connected to $r1199.5$.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3080_01_eng.vsd	Function diagram	
Setpoint channel - ramp-function generator selection, status word, tracking					22.03.06 V02.04.00	SINAMICS S	
- 3080 -							

2-1024

Figure 2-98 3080 – Ramp-function generator selection, status word, tracking

Figure 2-99 3090 – Dynamic Servo Control (DSC)



- <1> Principle of operation of Dynamic Servo Control (DSC): The feedback branch {2} completely compensates the feedback coupling branch {1} regarding the position actual value sent from the drive. The fast actual value channel {3} allows a high dynamic performance and high Kv factors to be achieved.
- <2> For the motor encoder (p1192 = 1) p1193 = 1 is effective.
 When using encoder 2 or 3 (p1192 = 2, 3), p1193 should be set to "Increments per revolution motor encoder/increments per revolution position encoder (including fine resolution)".
- <3> The deadtime for the PROFIBUS data transfer is automatically set.
- <4> Sample & Hold element; refer to [1021].
- <5> The position deviation must be referred to the increments of the motor including the fine resolution.
- <6> Normalization of KPC: If signal {4} = 1 motor revolution and KPC = 1, then "n_set from DSC" = 0.001 motor revolutions/s.
- <101> Pre-assignment of the sampling times in p0115, refer to p0112.

1	2	3	4	5	6	7	8
DO: SERVO					fp_3090_01_eng.vsd	Function diagram	
Setpoint channel - Dynamic Servo Control (DSC)					15.10.04 V02.04.00	SINAMICS S	
							- 3090 -

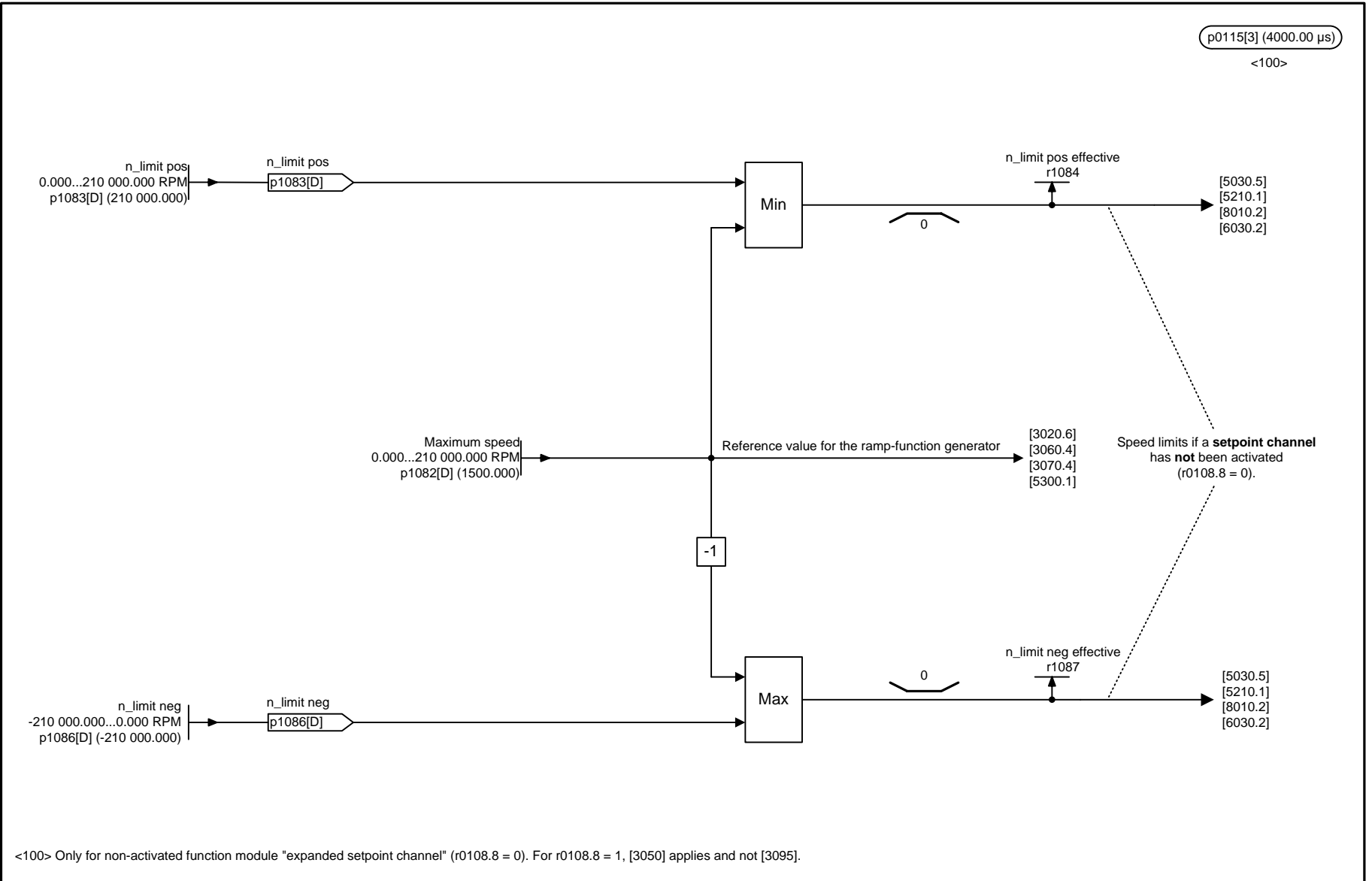
Function diagrams
Setpoint channel

2.14 Setpoint channel not activated

Function diagrams

3095 – Generation of the speed limits (r0108.8 = 0)

2-1027



1	2	3	4	5	6	7	8
DO: SERVO					fp_3095_01_eng.vsd	Function diagram	
Setpoint channel not activated - generating the speed limits (r0108.8 = 0)					24.02.05 V02.04.00	SINAMICS S	
							- 3095 -

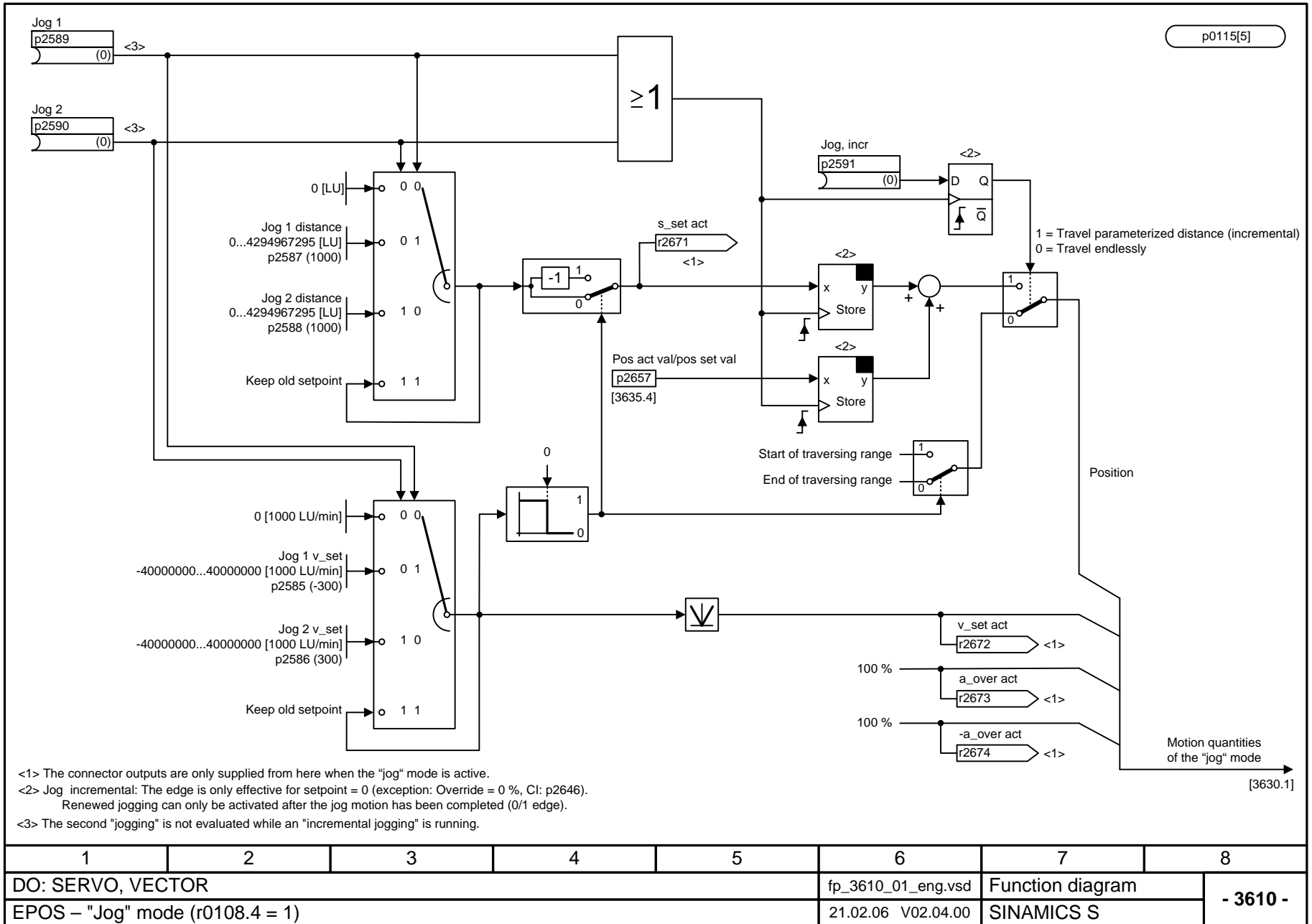
Figure 2-100 3095 – Generation of the speed limits (r0108.8 = 0)

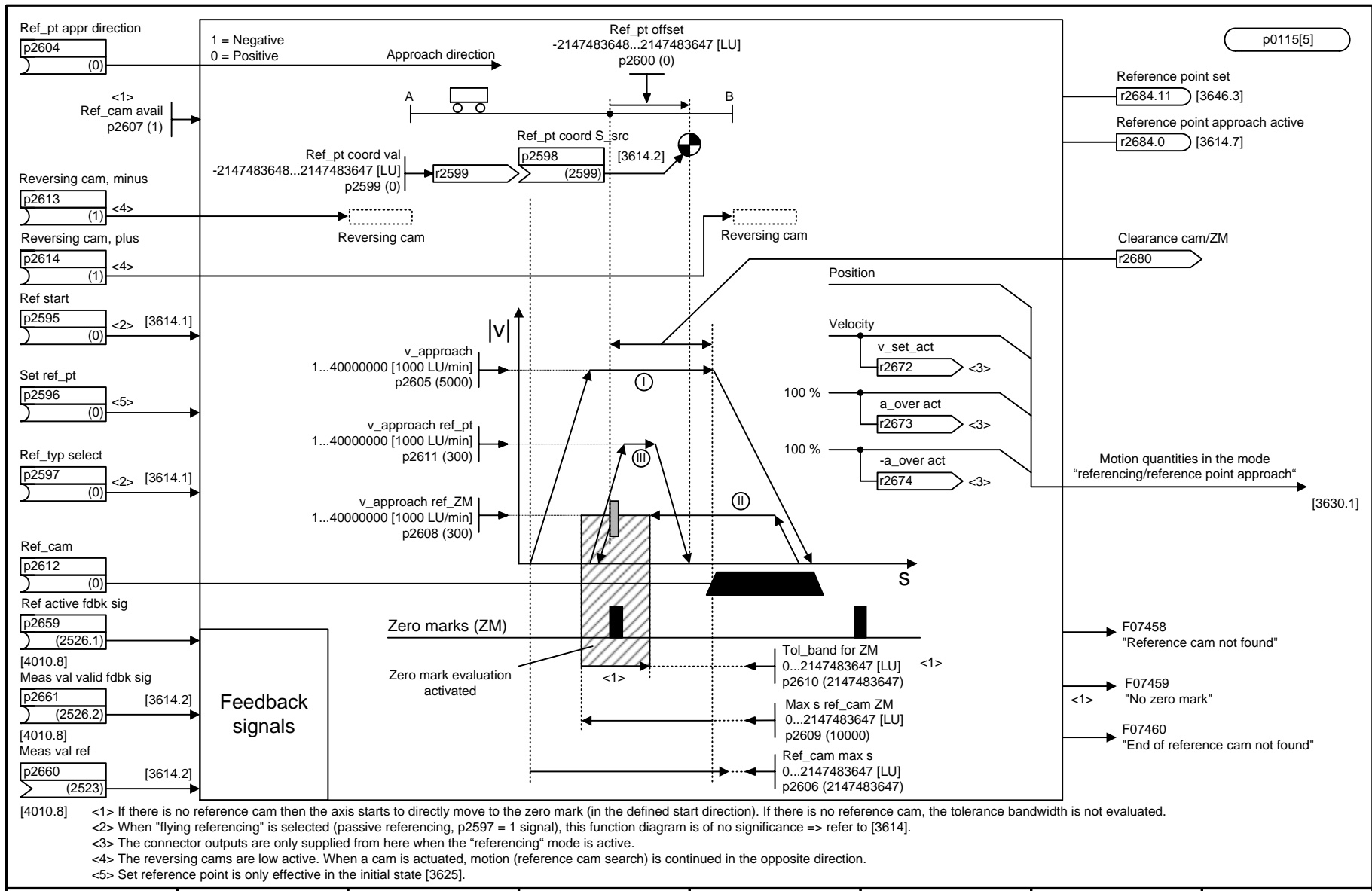
2.15 Basic positioner

Function diagrams

3610 – “Jog” mode (r0108.4 = 1)	2-1029
3612 – “Referencing/reference point approach” mode (r0108.4 = 1) (p2597 = 0 signal)	2-1030
3614 – “Flying referencing” mode (r0108.4 = 1) (p2597 = 1 signal)	2-1031
3616 – “Traversing blocks” mode (r0108.4 = 1)	2-1032
3618 – “Direct setpoint input/MDI” mode, dynamic values (r0108.4 = 1)	2-1033
3620 – Direct setpoint input mode/MDI (r0108.4 = 1)	2-1034
3625 – Mode control (r0108.4 = 1)	2-1035
3630 – Traversing range limitations (r0108.4 = 1)	2-1036
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3645 – Status word 1 (r0108.3 = 1, r0108.4 = 1)	2-1039
3646 – Status word 2 (r0108.3 = 1, r0108.4 = 1)	2-1040
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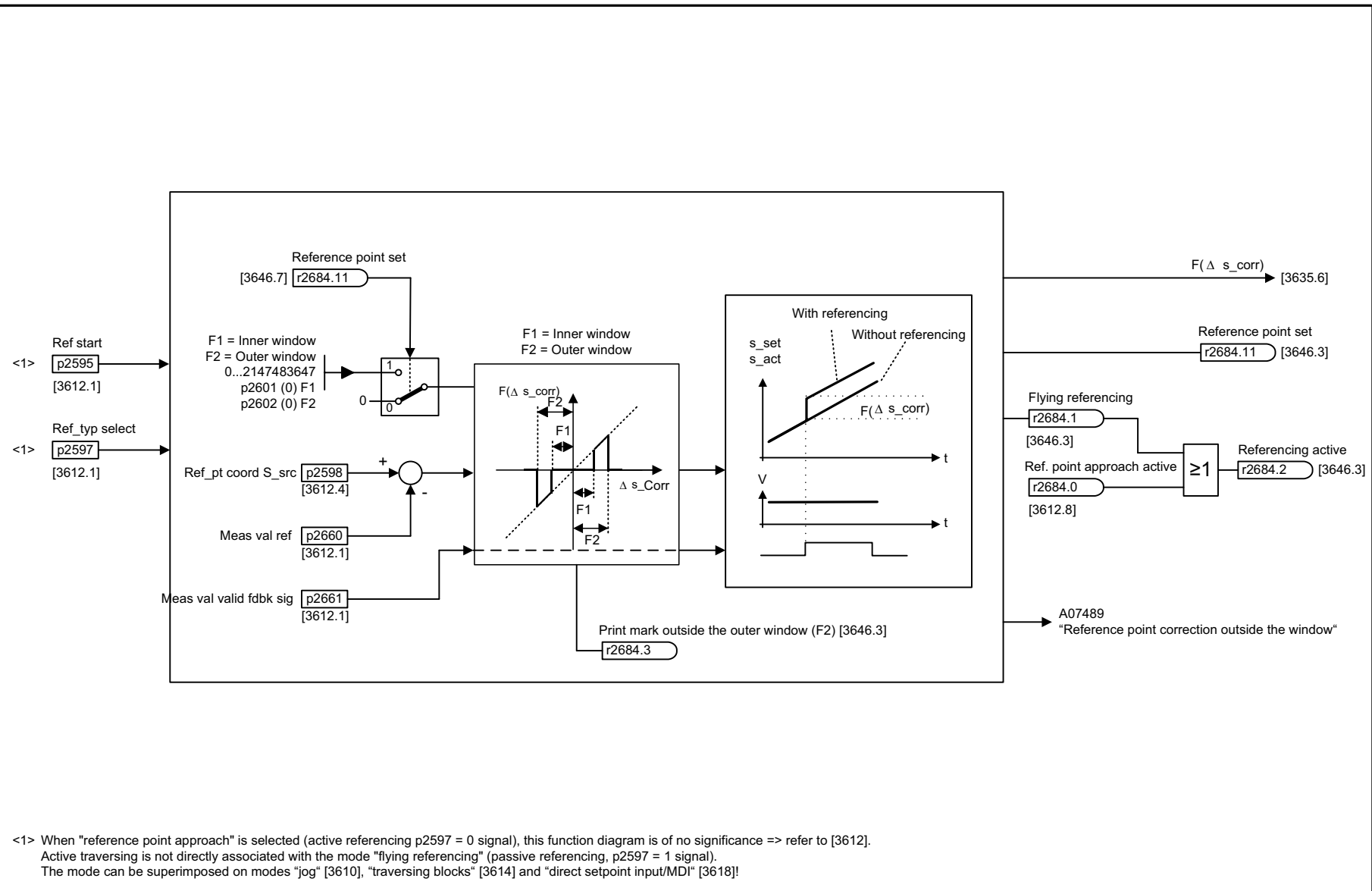
Figure 2-101 3610 – "Jog" mode (r0108.4 = 1)





1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3612_01_eng.vsd	Function diagram	
EPOS - "Referencing/reference point approach" mode (r0108.4 = 1) (p2597 = 0 signal)					08.03.06 V02.04.00	SINAMICS S	
							- 3612 -

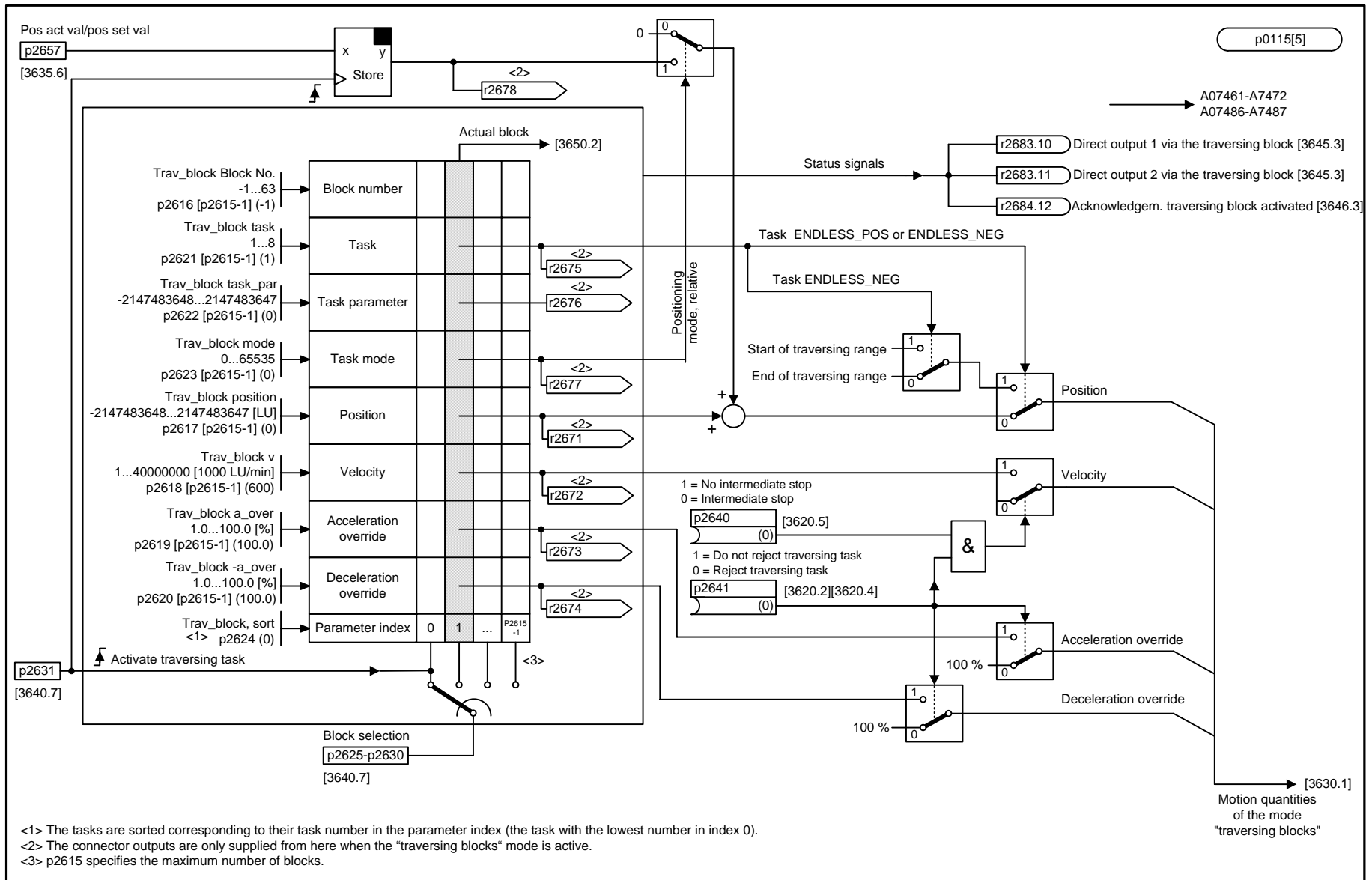
Figure 2-102 3612 – "Referencing/reference point approach" mode (r0108.4 = 1) (p2597 = 0 signal)



<1> When "reference point approach" is selected (active referencing p2597 = 0 signal), this function diagram is of no significance => refer to [3612].
Active traversing is not directly associated with the mode "flying referencing" (passive referencing, p2597 = 1 signal).
The mode can be superimposed on modes "jog" [3610], "traversing blocks" [3614] and "direct setpoint input/MDI" [3618]!

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3614_01_eng.vsd	Function diagram	
EPOS - "Flying referencing" mode (r0108.4 = 1) (p2597 = 1 signal)					09.02.06 V02.04.00	SINAMICS S	
							- 3614 -

Figure 2-103 3614 – "Flying referencing" mode (r0108.4 = 1) (p2597 = 1 signal)



<1> The tasks are sorted corresponding to their task number in the parameter index (the task with the lowest number in index 0).
 <2> The connector outputs are only supplied from here when the "traversing blocks" mode is active.
 <3> p2615 specifies the maximum number of blocks.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3616_01_eng.vsd	Function diagram	
EPOS - "Traversing blocks" mode (r0108.4 = 1)					09.02.06 V02.04.00	SINAMICS S	
							- 3616 -

Figure 2-104 3616 – "Traversing blocks" mode (r0108.4 = 1)

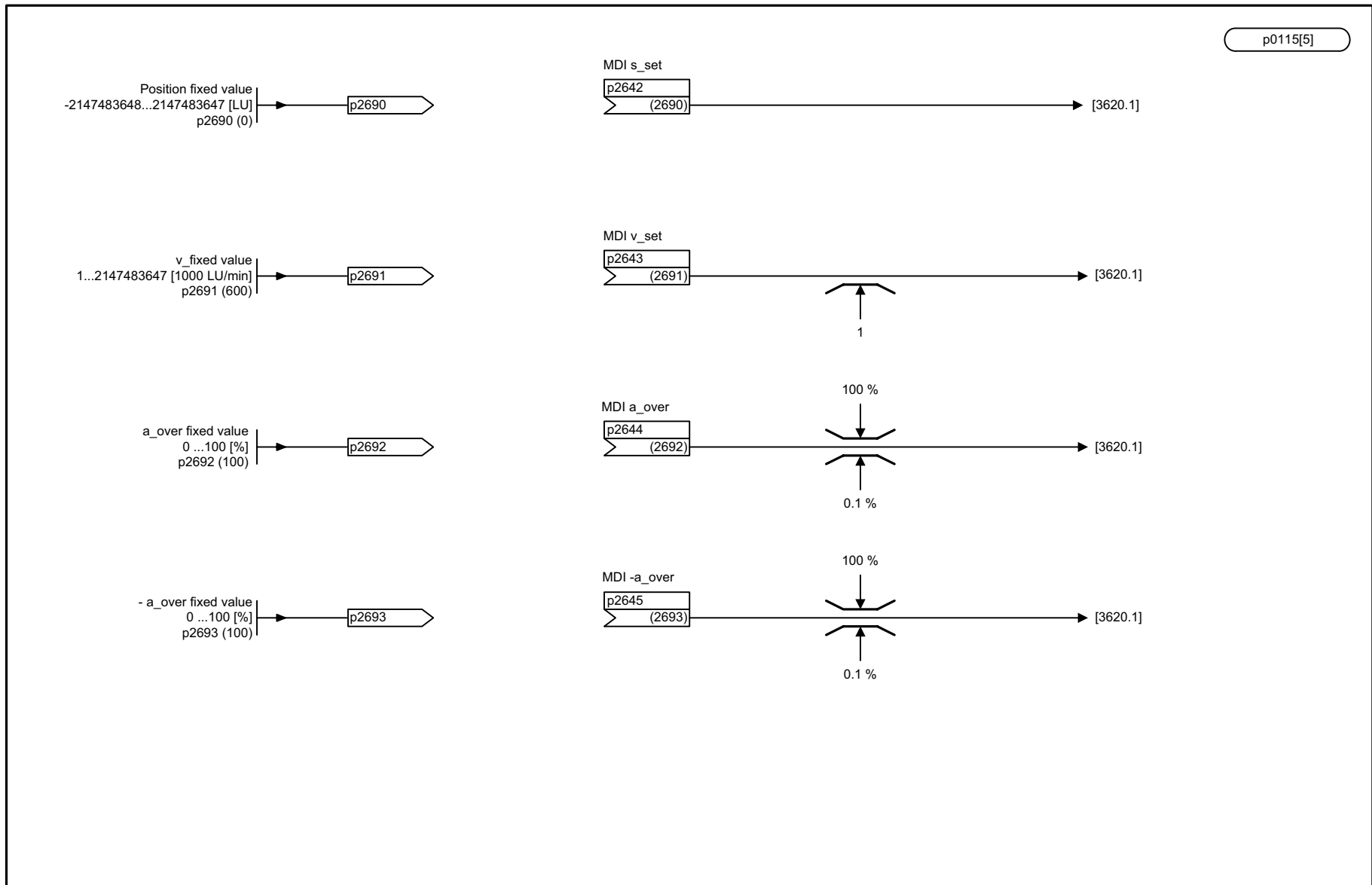
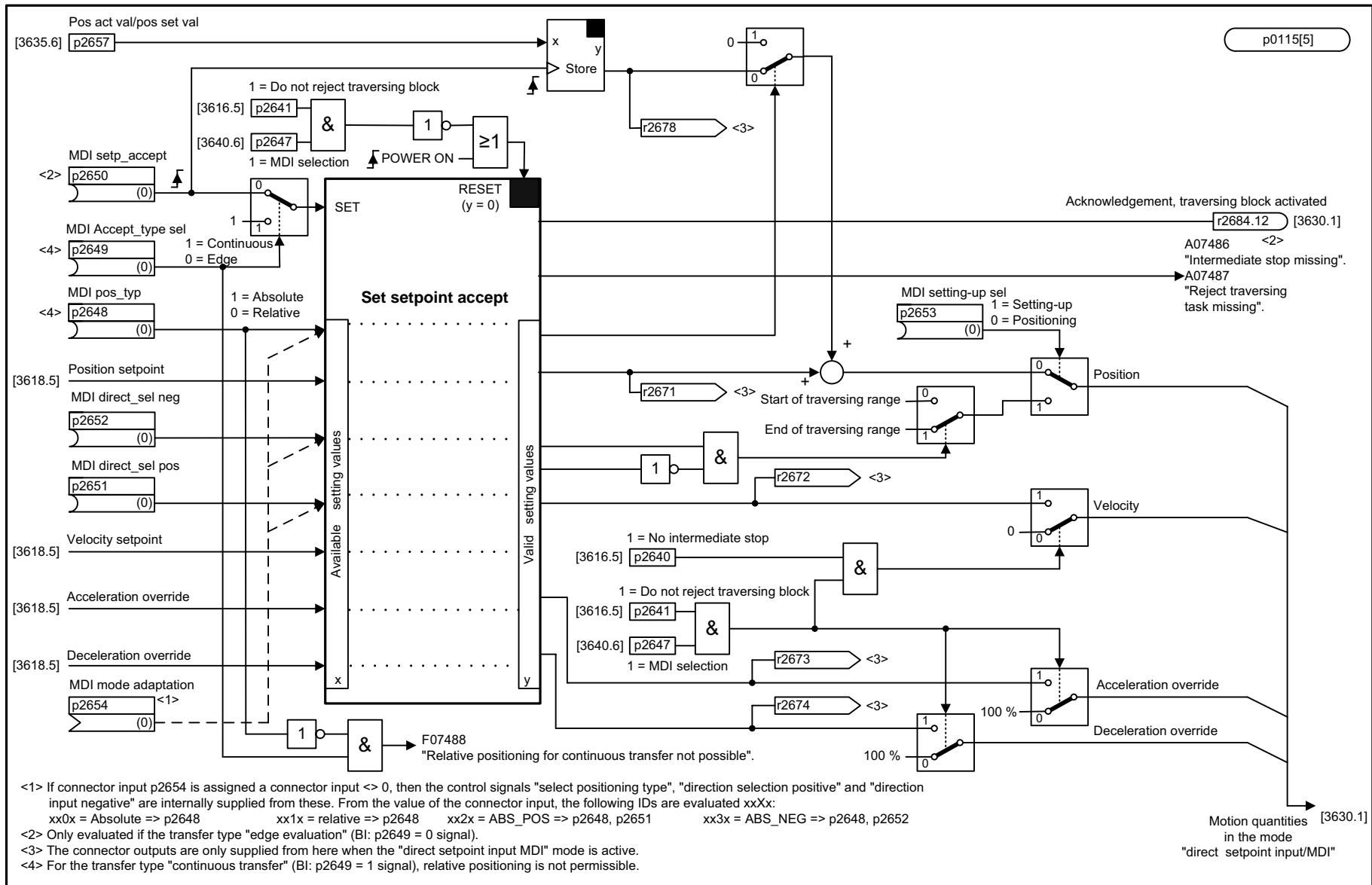


Figure 2-105 3618 – “Direct setpoint input/MDI” mode, dynamic values (r0108.4 = 1)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3618_01_eng.vsd	Function diagram	
EPOS – “Direct setpoint input MDI” mode, dynamic values (r0108.4 = 1)					24.03.06 V02.04.00	SINAMICS S	
							- 3618 -

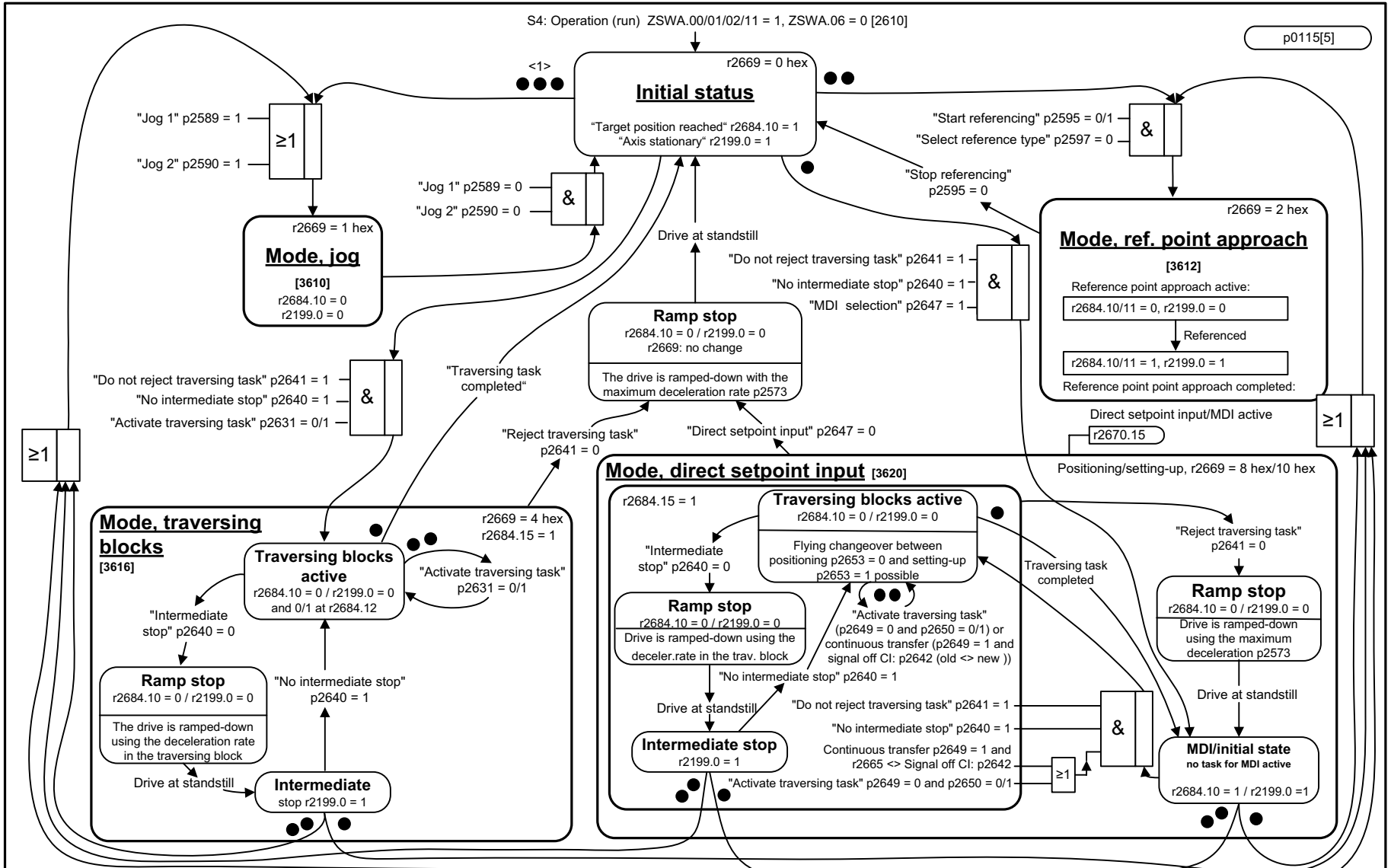


<1> If connector input p2654 is assigned a connector input <> 0, then the control signals "select positioning type", "direction selection positive" and "direction input negative" are internally supplied from these. From the value of the connector input, the following IDs are evaluated xxXx:
 xx0x = Absolute => p2648 xx1x = relative => p2648 xx2x = ABS_POS => p2648, p2651 xx3x = ABS_NEG => p2648, p2652
 <2> Only evaluated if the transfer type "edge evaluation" (BI: p2649 = 0 signal).
 <3> The connector outputs are only supplied from here when the "direct setpoint input MDI" mode is active.
 <4> For the transfer type "continuous transfer" (BI: p2649 = 1 signal), relative positioning is not permissible.

Figure 2-106 3620 – Direct setpoint input mode/MDI (r0108.4 = 1)

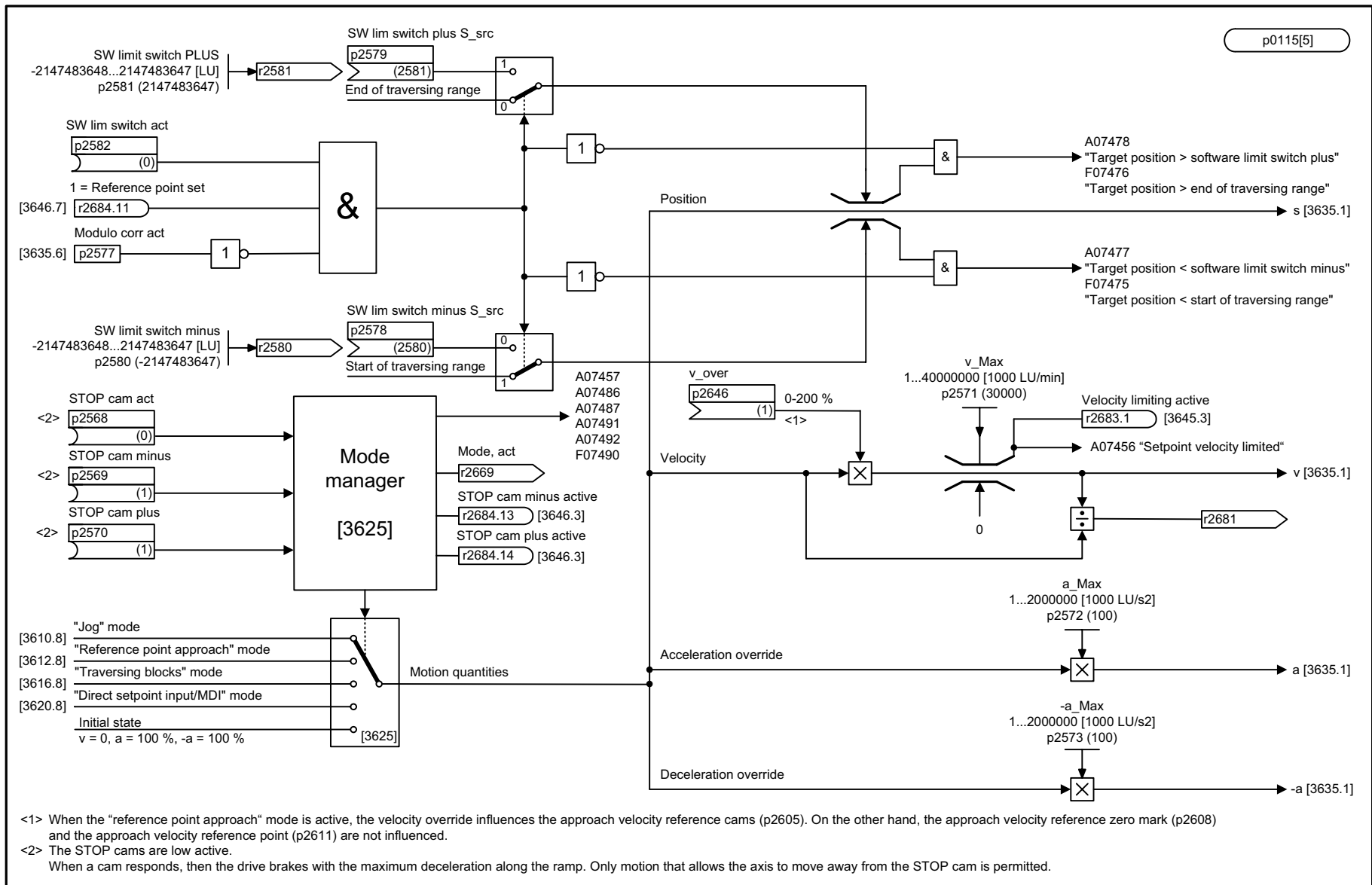
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3620_01_eng.vsd	Function diagram	
EPOS – Direct setpoint input mode/MDI (r0108.4 = 1)					06.03.06 V02.04.00	SINAMICS S	
							- 3620 -

Figure 2-107 3625 – Mode control (r0108.4 = 1)



<1> The more points that exist at a transition, the higher the priority.

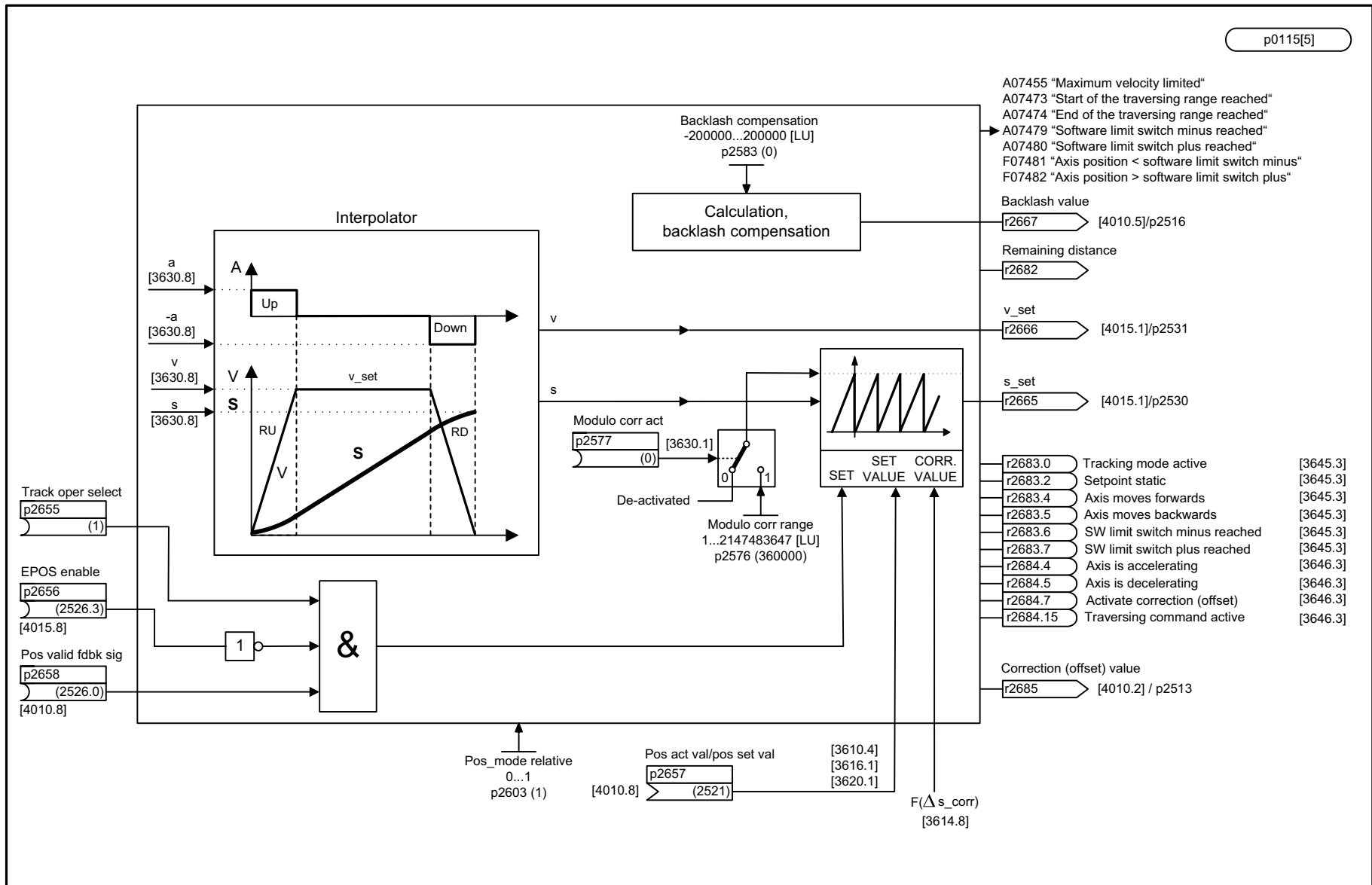
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3625_01_eng.vsd	Function diagram	
EPOS – Mode control (r0108.4 = 1)					29.03.06 V02.04.00	SINAMICS S	
							- 3625 -



<1> When the "reference point approach" mode is active, the velocity override influences the approach velocity reference cams (p2605). On the other hand, the approach velocity reference zero mark (p2608) and the approach velocity reference point (p2611) are not influenced.
 <2> The STOP cams are low active.
 When a cam responds, then the drive brakes with the maximum deceleration along the ramp. Only motion that allows the axis to move away from the STOP cam is permitted.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3630_01_eng.vsd	Function diagram	
EPOS – Traversing range limits (r0108.4 = 1)					29.03.06 V02.04.00	SINAMICS S	
							- 3630 -

Figure 2-108 3630 – Traversing range limitations (r0108.4 = 1)



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3635_01_eng.vsd	Function diagram	
EPOS – Interpolator (r0108.4 = 1)					23.03.06 V02.04.00	SINAMICS S	
							- 3635 -

Figure 2-109 3635 – Interpolator (r0108.4 = 1)

p0115[5]

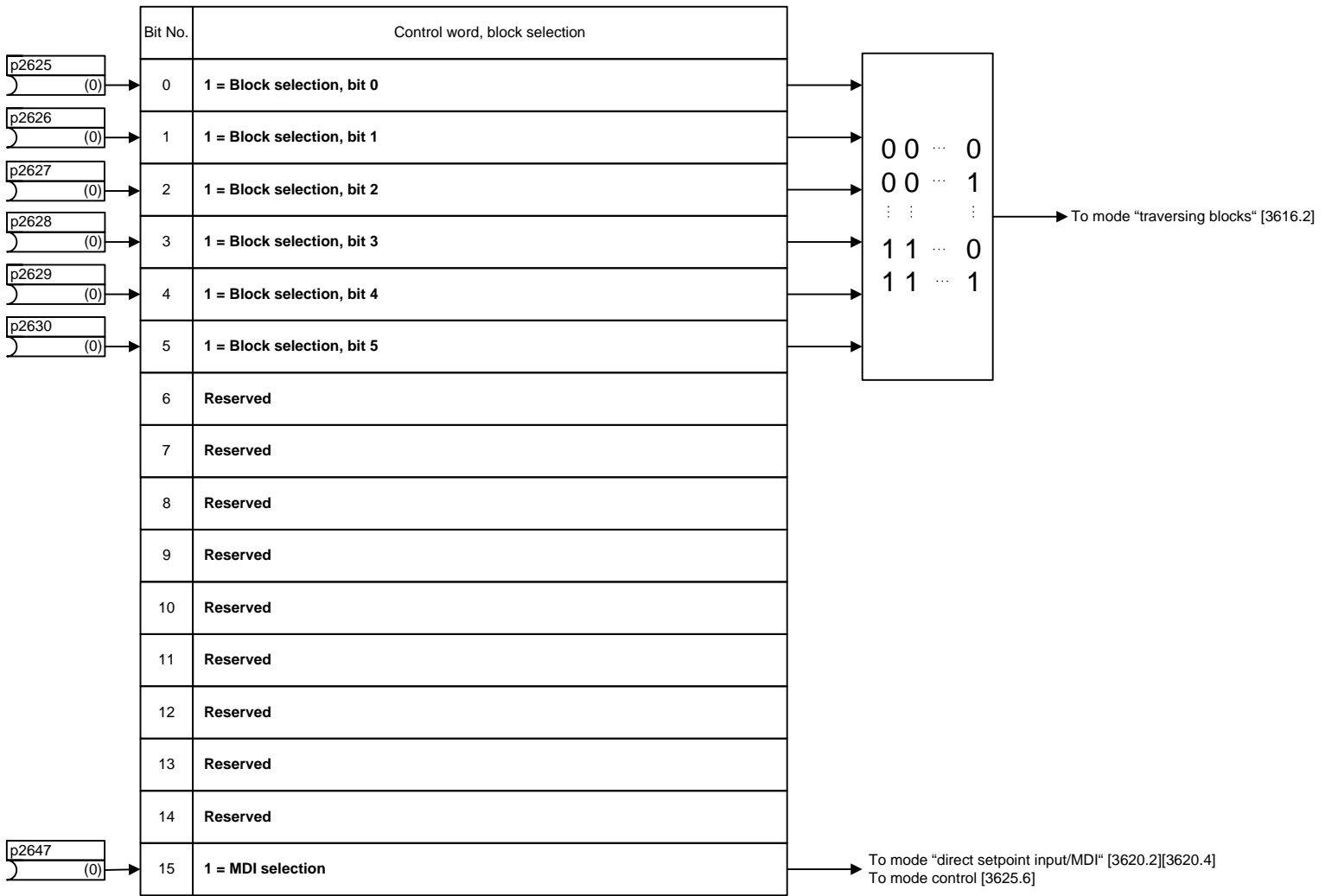
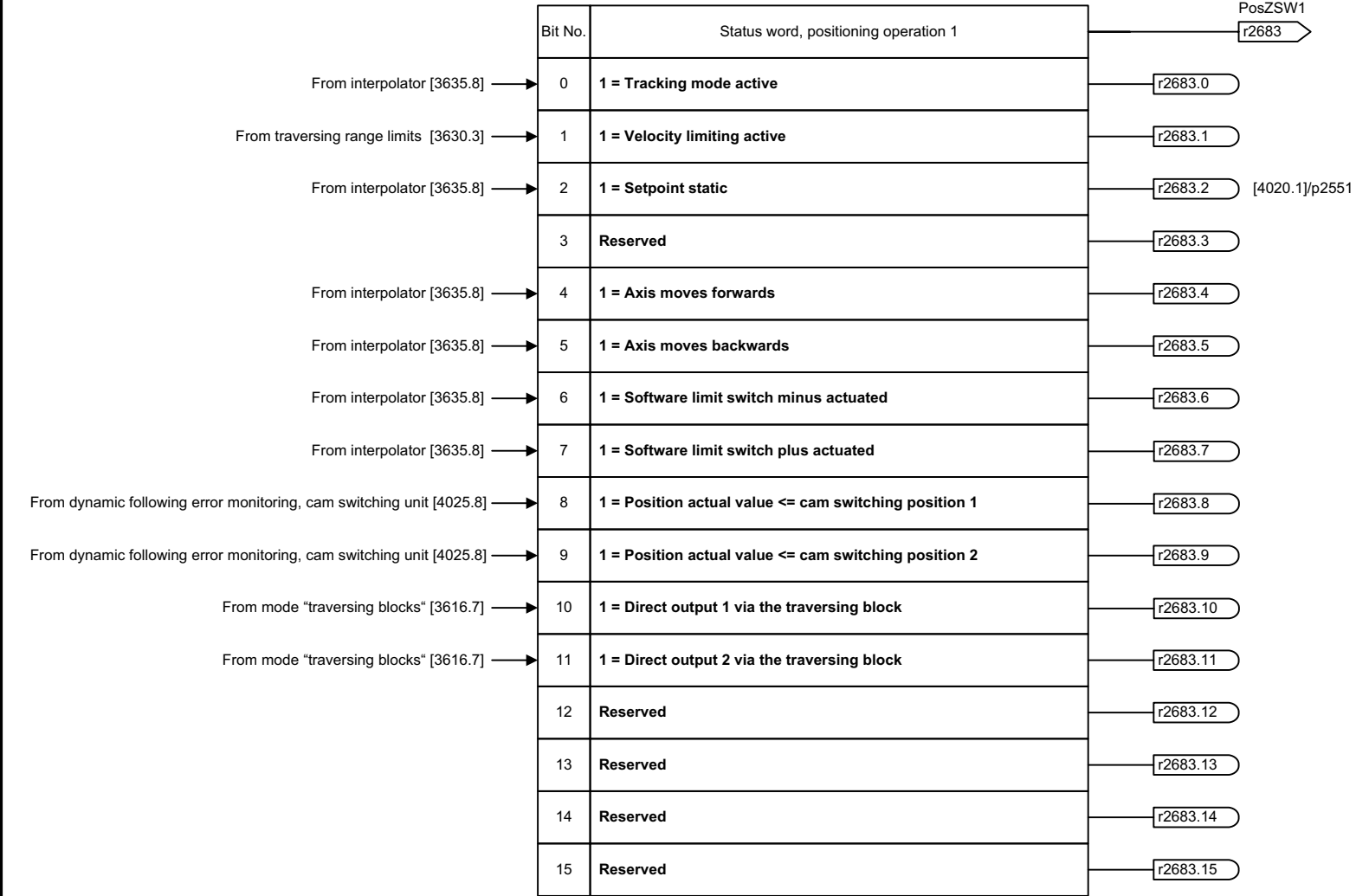


Figure 2-110 3640 – Control word block selection/MDI selection (r0108.4 = 1)

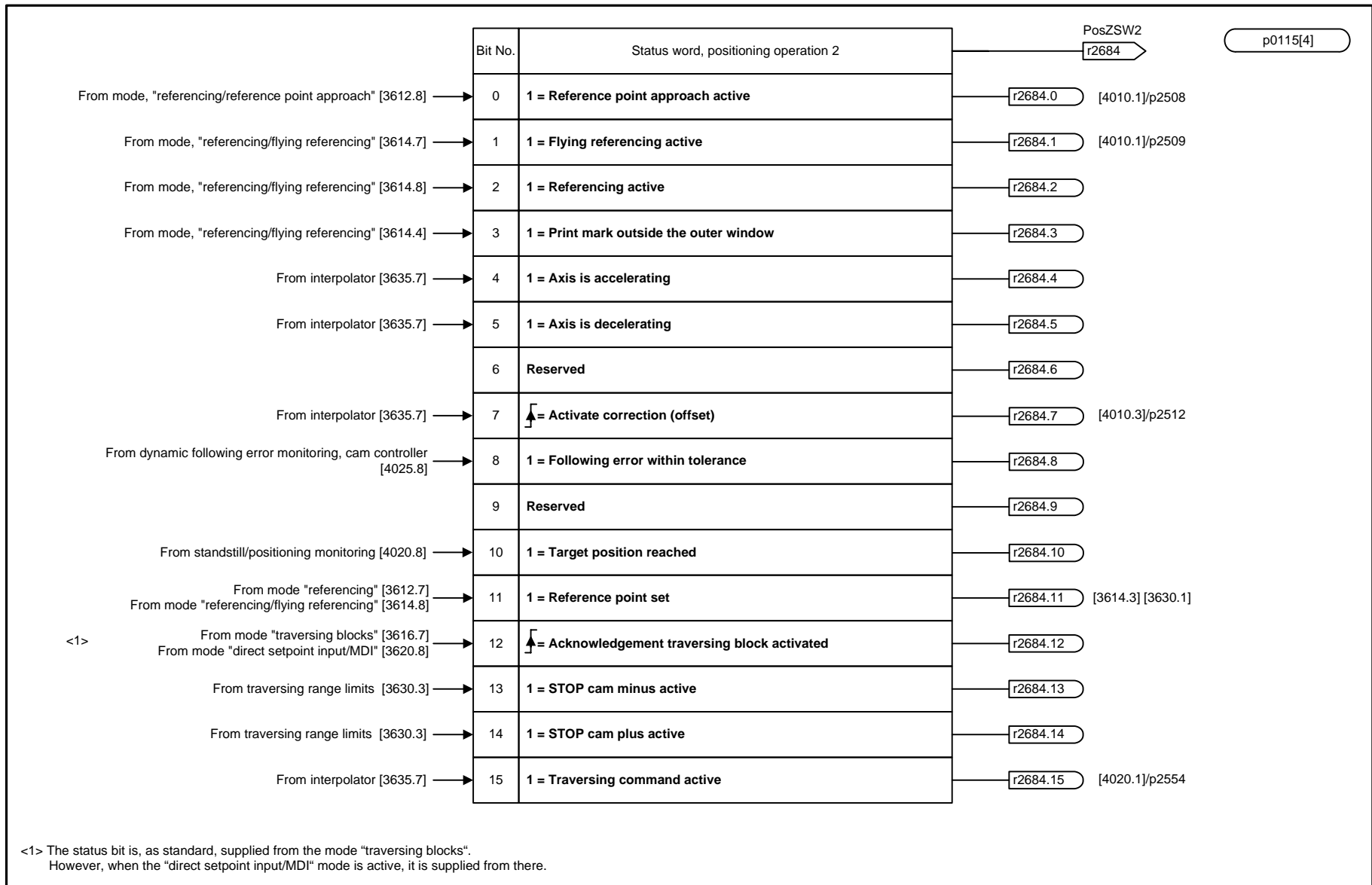
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3640_01_eng.vsd	Function diagram	
EPOS – Control word block selection/MDI selection (r0108.4 = 1)					06.03.06 V02.04.00	SINAMICS S	
- 3640 -							



PosZSW1
r2683

Figure 2-111 3645 – Status word 1 (r0108.3 = 1, r0108.4 = 1)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3645_01_eng.vsd	Function diagram	
EPOS – Status word 1 (r0108.3 = 1, r0108.4 = 1)					23.03.06 V02.04.00	SINAMICS S	



<1> The status bit is, as standard, supplied from the mode "traversing blocks".
However, when the "direct setpoint input/MDI" mode is active, it is supplied from there.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3646_01_eng.vsd	Function diagram	
EPOS – Status word 2 (r0108.3 = 1, r0108.4 = 1)					16.03.06 V02.04.00	SINAMICS S	
							- 3646 -

Figure 2-112 3646 – Status word 2 (r0108.3 = 1, r0108.4 = 1)

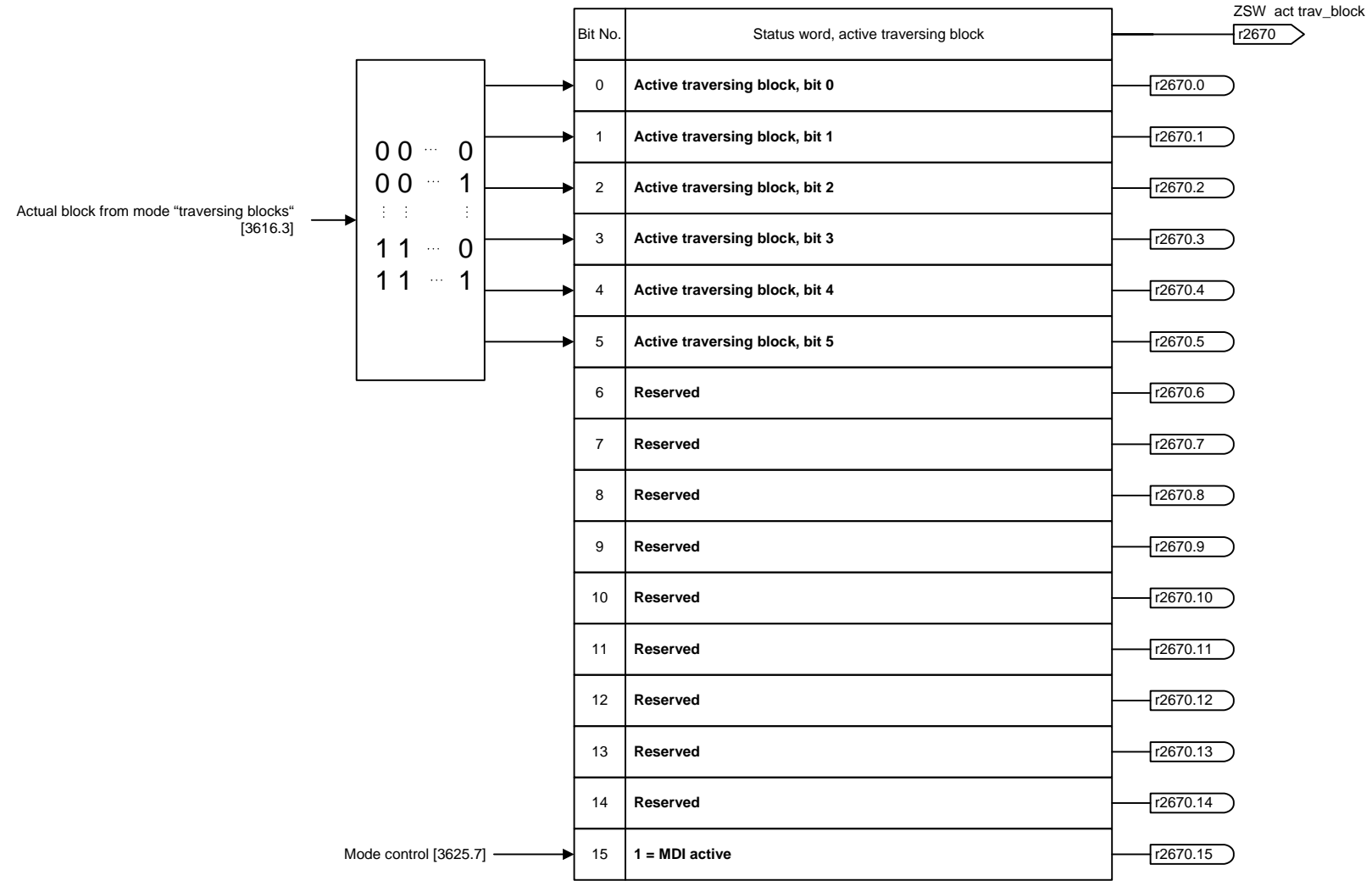


Figure 2-113 3650 – Status word, active traversing block/MDI active (r0108.4 = 1)

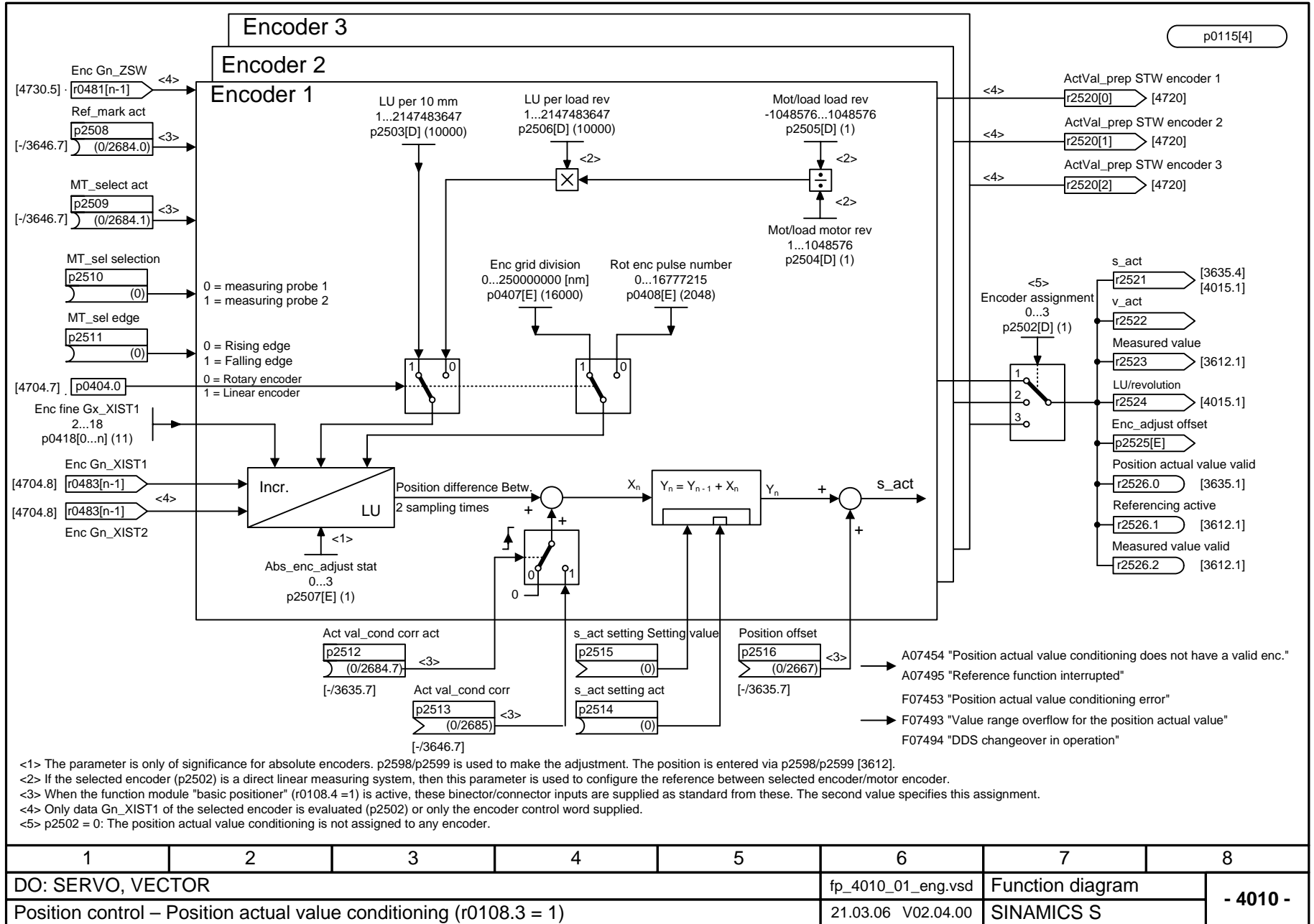
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_3650_01_eng.vsd	Function diagram	
EPOS – Status word, active traversing block/MDI active (r0108.4 = 1)					10.02.06 V02.04.00	SINAMICS S	
							- 3650 -

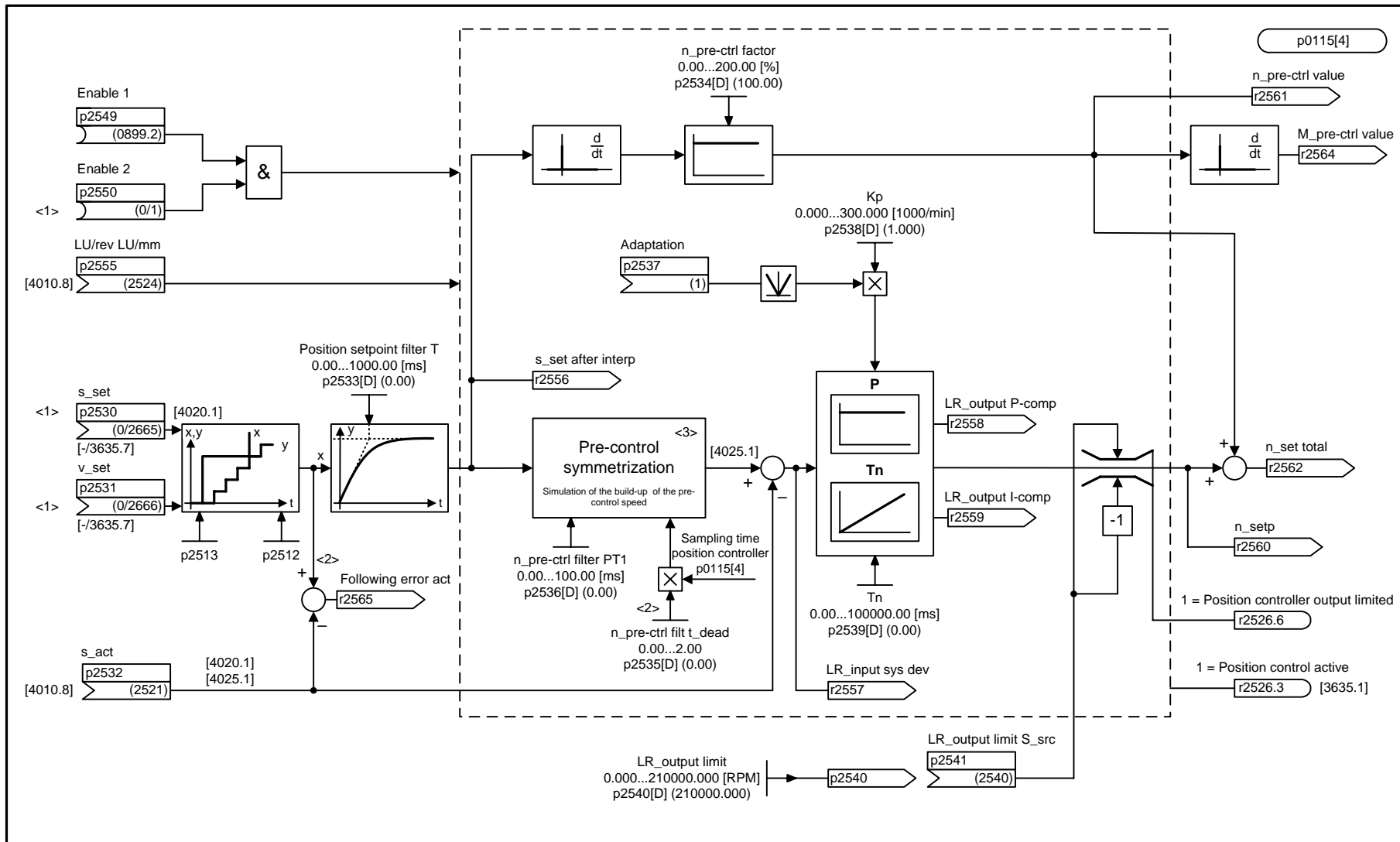
2.16 Position controller

Function diagrams

4010 – Position actual value conditioning (r0108.3 = 1)	2-1043
4015 – Position controller (r0108.3 = 1)	2-1044
4020 – Standstill/positioning monitoring (r0108.3 = 1)	2-1045
4025 – Dynamic following error monitoring, cam switching values (r0108.3 = 1)	2-1046

Figure 2-114 4010 – Position actual value conditioning (r0108.3 = 1)



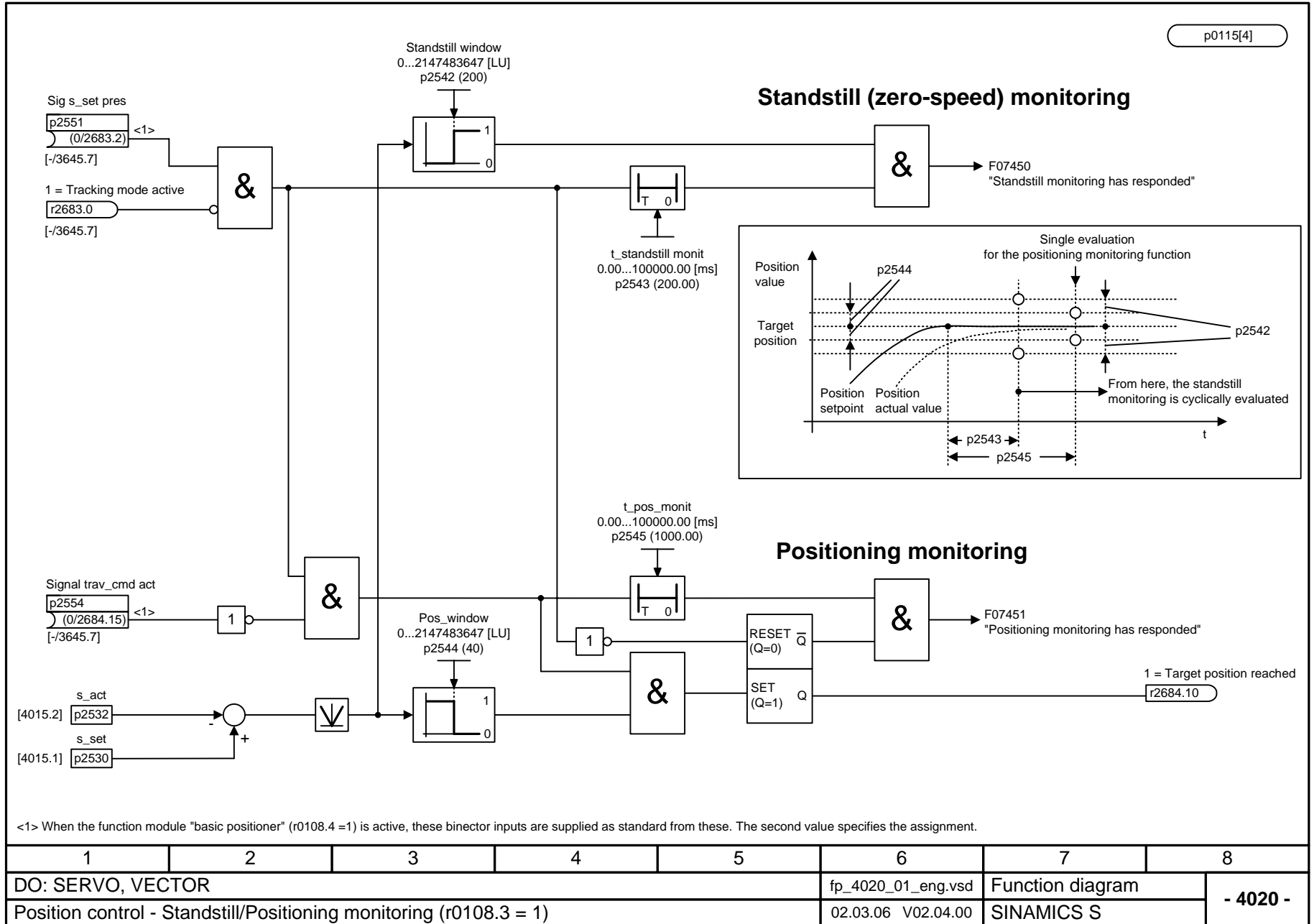


<1> When the function module "basic positioner" (r0108.4 = 1) is active, these binector/connector inputs are supplied as standard from these. The second value specifies this assignment.
 <2> For p2534 > 0 % the following applies: In addition, a deadtime of two position controller clock cycles is effective.
 <3> For p2534 = 0 % the following applies: The pre-control symmetrization is not effective.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4015_01_eng.vsd	Function diagram	
Position control – Position controller (r0108.3 = 1)					20.02.06 V02.04.00	SINAMICS S	
							- 4015 -

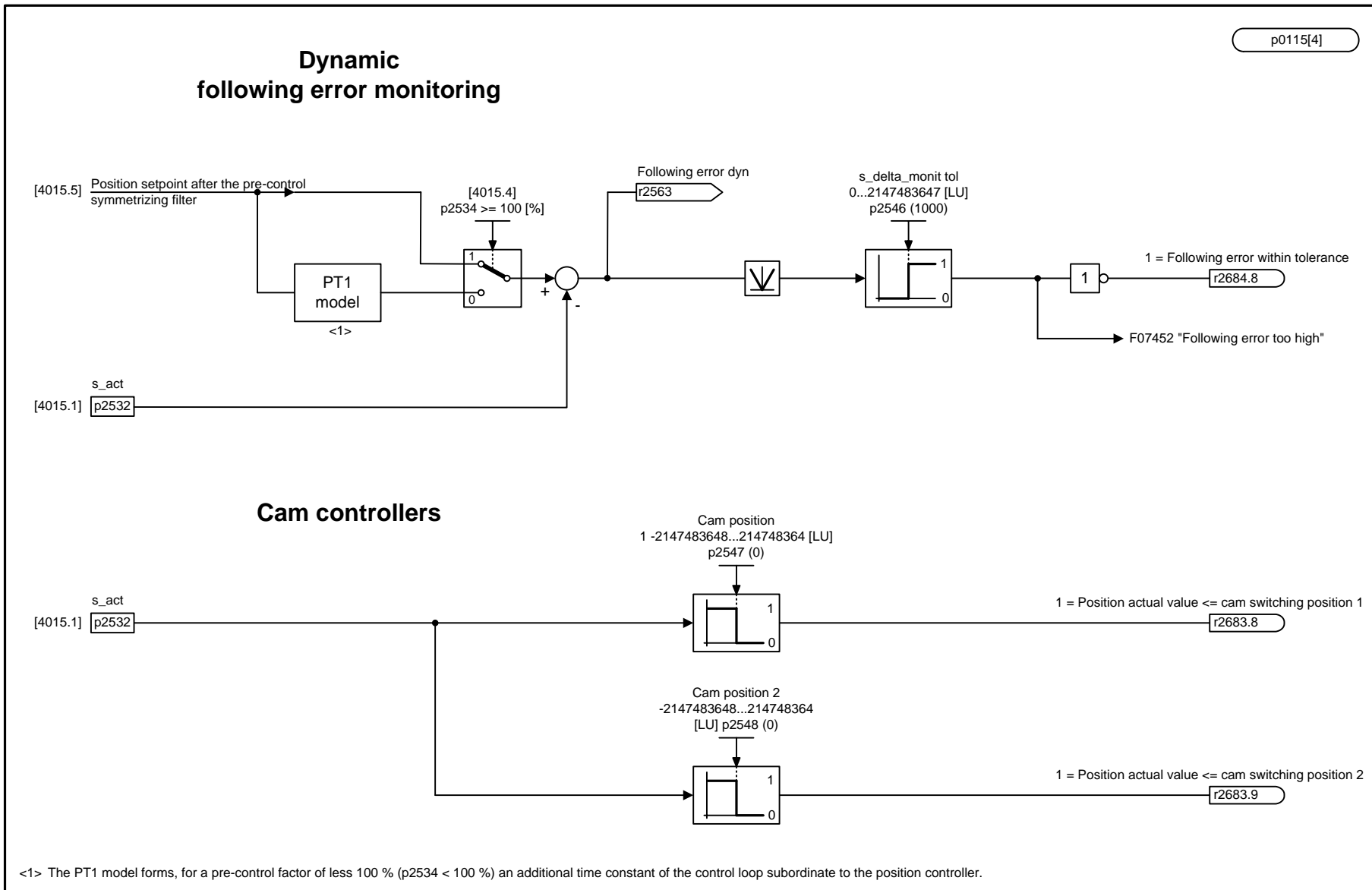
Figure 2-115 4015 – Position controller (r0108.3 = 1)

Figure 2-116 4020 – Standstill/positioning monitoring (r0108.3 = 1)



<1> When the function module "basic positioner" (r0108.4 = 1) is active, these binector inputs are supplied as standard from these. The second value specifies the assignment.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4020_01_eng.vsd	Function diagram	
Position control - Standstill/Positioning monitoring (r0108.3 = 1)					02.03.06 V02.04.00	SINAMICS S	
							- 4020 -



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4025_01_eng.vsd	Function diagram	
Position control - Dynamic following error monitoring, cam switching values (r0108.3 = 1)					20.03.06 V02.04.00	SINAMICS S	
							- 4025 -

Figure 2-117 4025 – Dynamic following error monitoring; cam switching values (r0108.3 = 1)

2.17 Encoder evaluations

Function diagrams

4704 – Position and temperature sensing, encoder 1 ... 3	2-1048
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4711 – Speed actual value sensing, encoders 2, 3 (r0108.7 = 1)	2-1050
4715 – Speed actual value and pole position sensing for motor ASM/SM (encoder 1)	2-1051
4720 – Encoder interface, receive signals, encoders 1 ... 3	2-1052
4730 – Encoder interface, send signals, encoders 1 ... 3	2-1053
4735 – Reference mark search with equivalent zero mark, encoders 1 ... 3	2-1054
4740 – Measuring input evaluation, measured value memory, encoders 1 ... 3	2-1055

Figure 2-118 4704 – Position and temperature sensing, encoder 1 ... 3

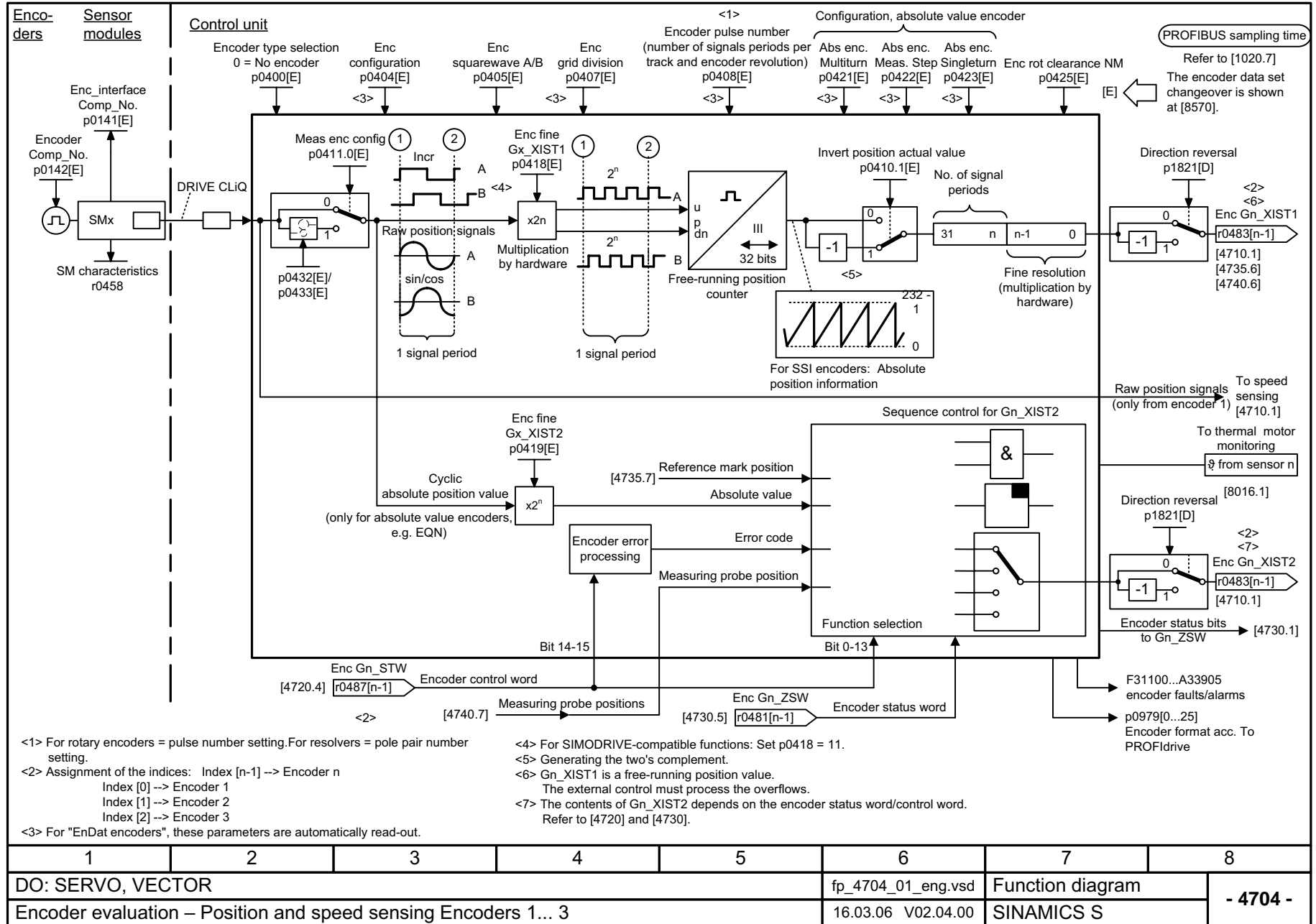
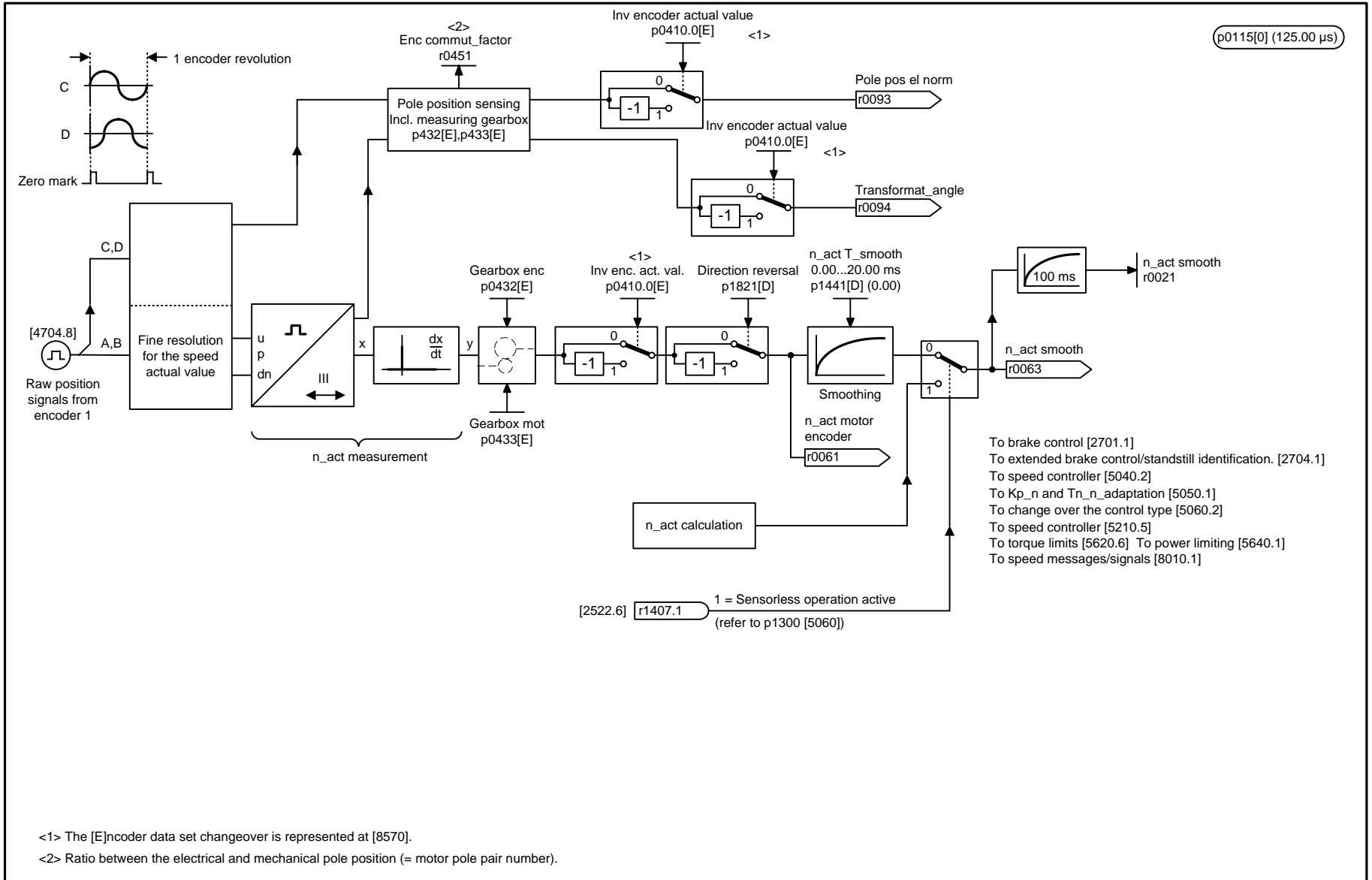
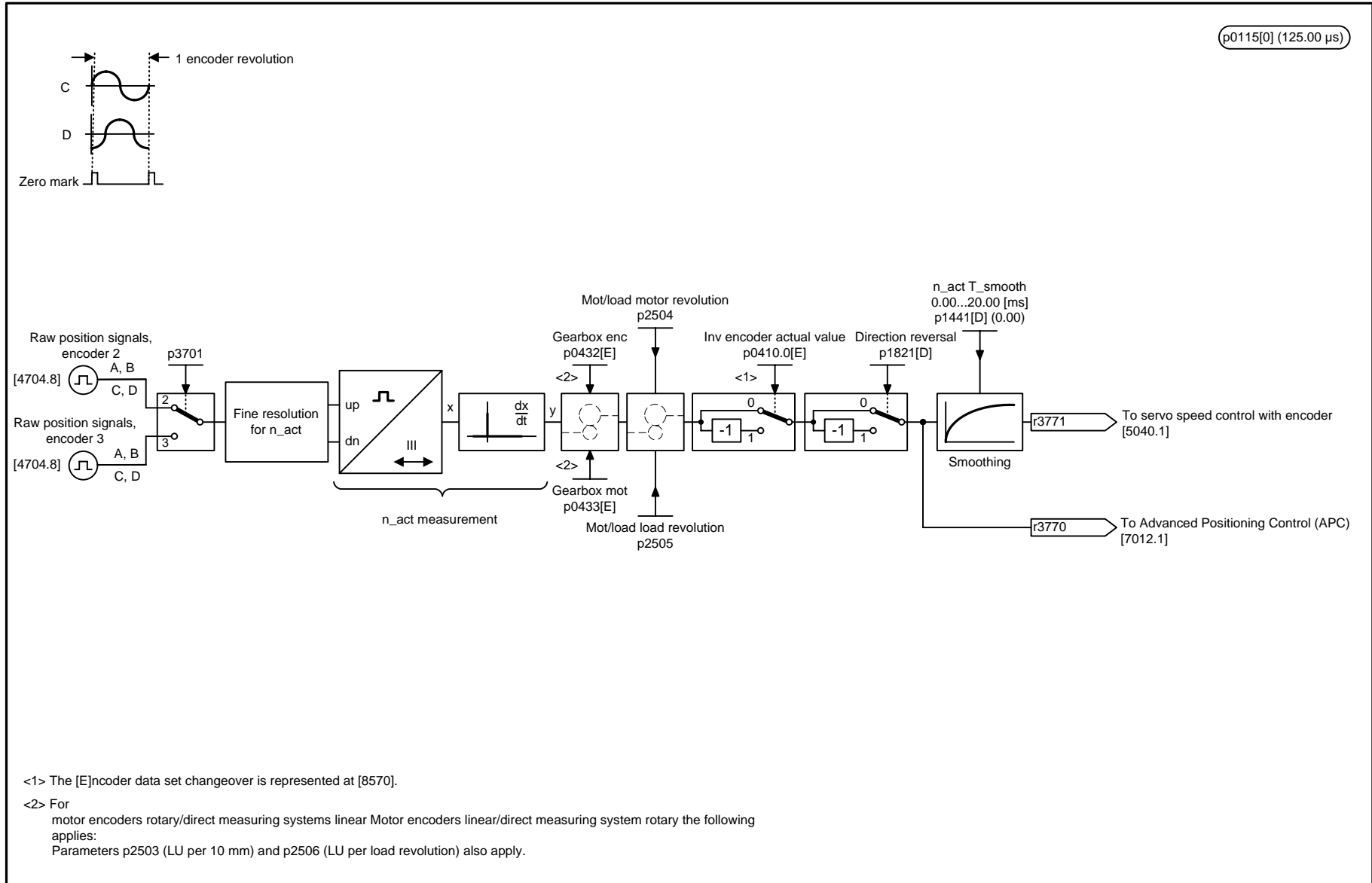


Figure 2-119 4710 – Speed actual value and pole position sensing for motor (encoder 1)



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4710_01_eng.vsd	Function diagram	
Encoder evaluation - speed act. value and pole pos. sensing for motor encoder (encoder 1)					02.03.06 V02.04.00	SINAMICS S	
							- 4710 -



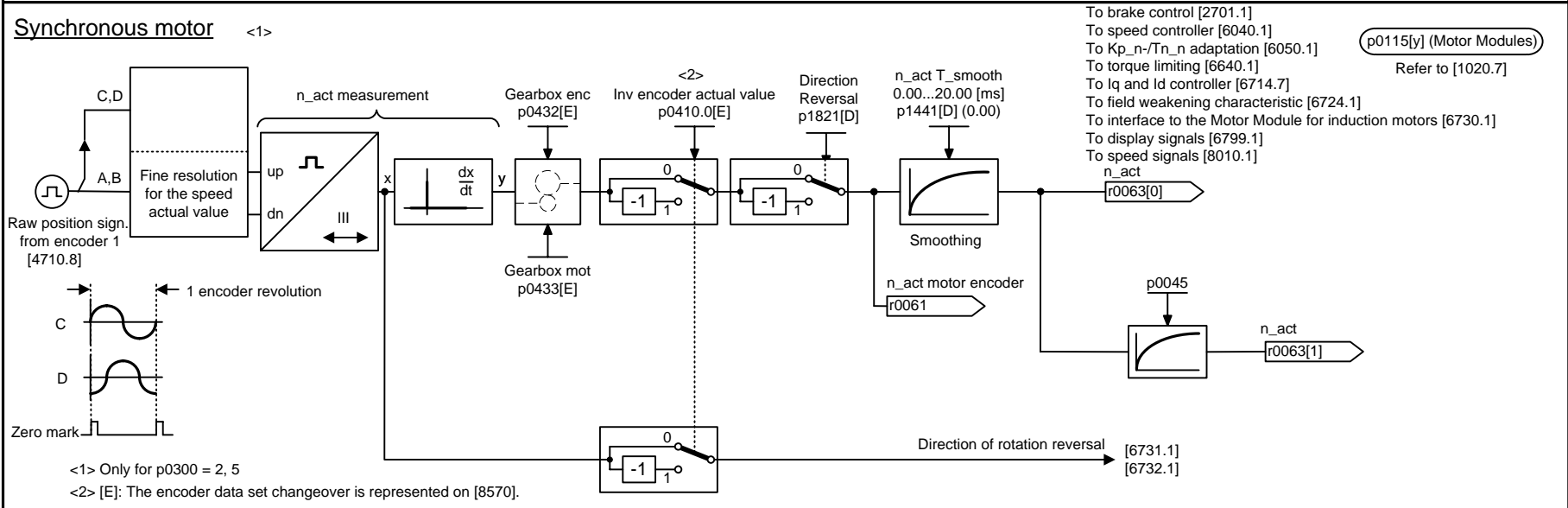
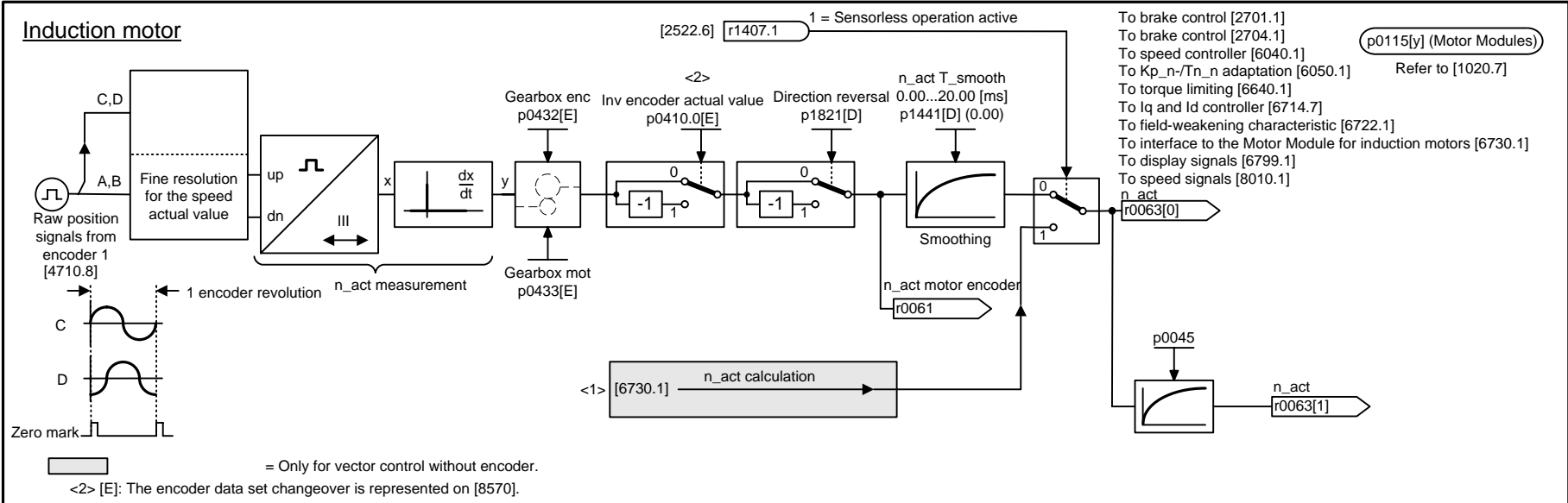
p0115[0] (125.00 μs)

<1> The [E]ncoder data set changeover is represented at [8570].
 <2> For motor encoders rotary/direct measuring systems linear Motor encoders linear/direct measuring system rotary the following applies:
 Parameters p2503 (LU per 10 mm) and p2506 (LU per load revolution) also apply.

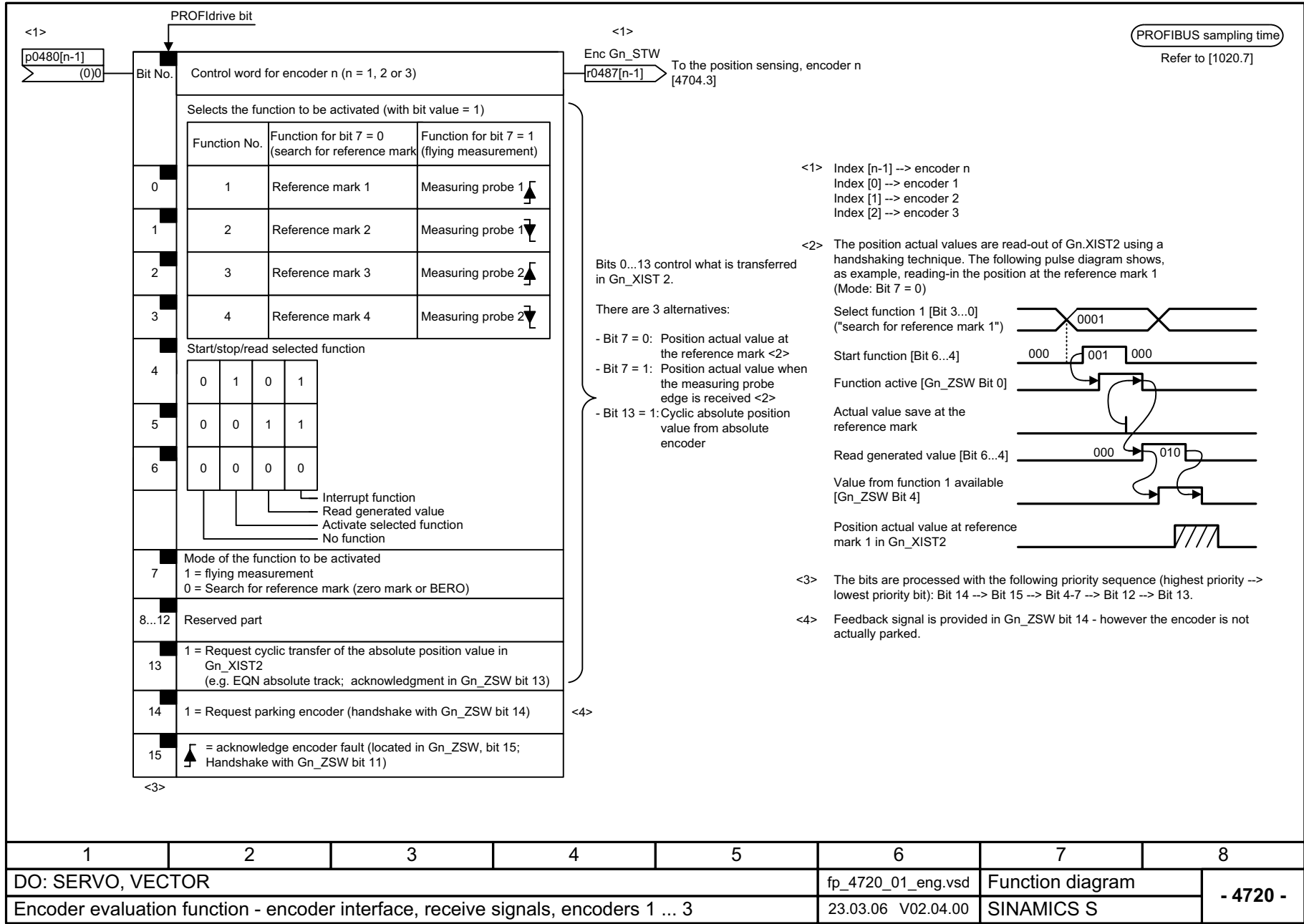
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4711_01_eng.vsd	Function diagram	
Encoder evaluation – speed actual value sensing, encoders 2, 3 (r0108.7 = 1)					13.03.06 V02.04.00	SINAMICS S	
							- 4711 -

Figure 2-120 4711 – Speed actual value sensing, encoders 2, 3 (r0108.7 = 1)

Figure 2-121 4715 – Speed actual value and pole position sensing for motor ASM/SM (encoder 1)

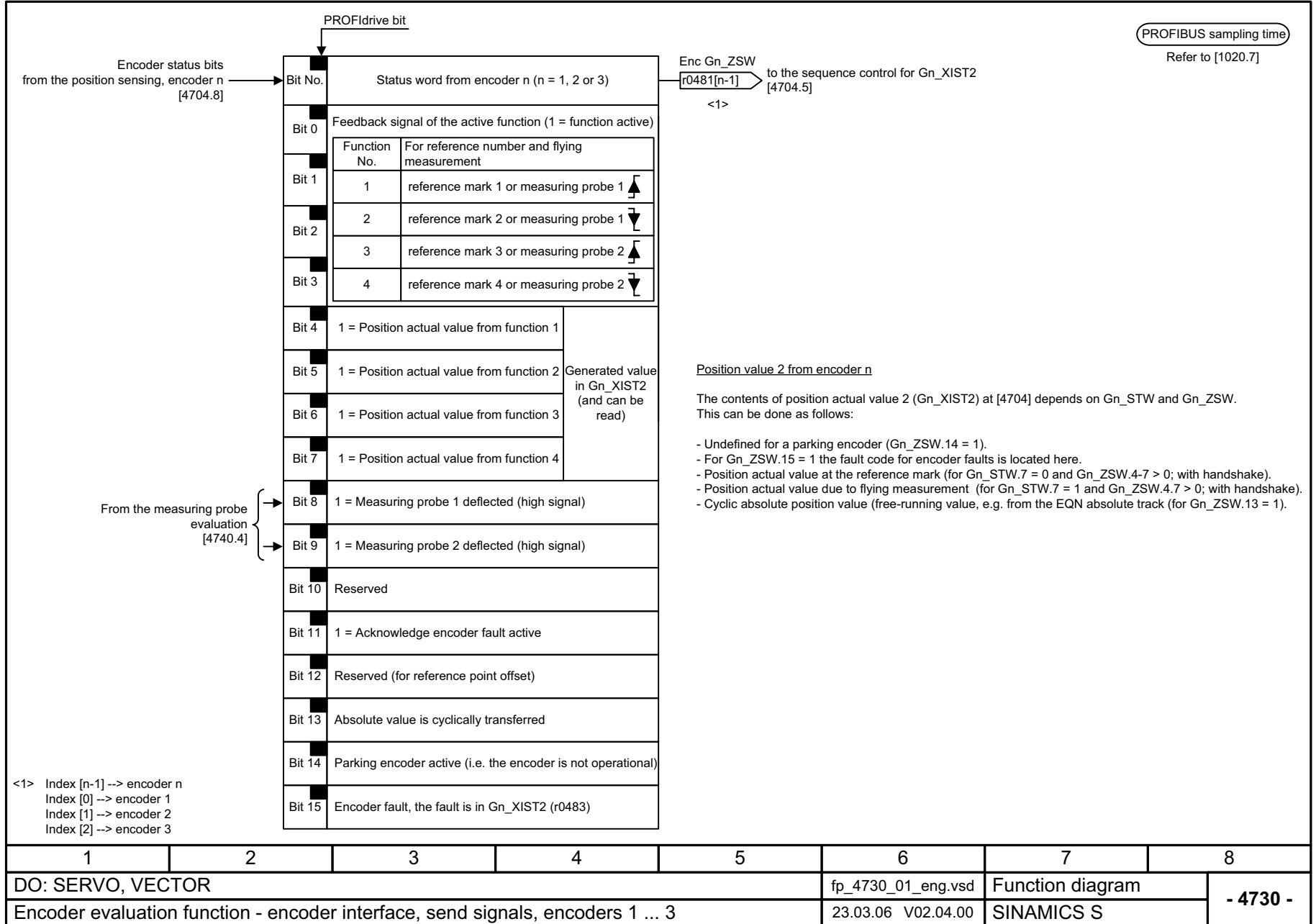


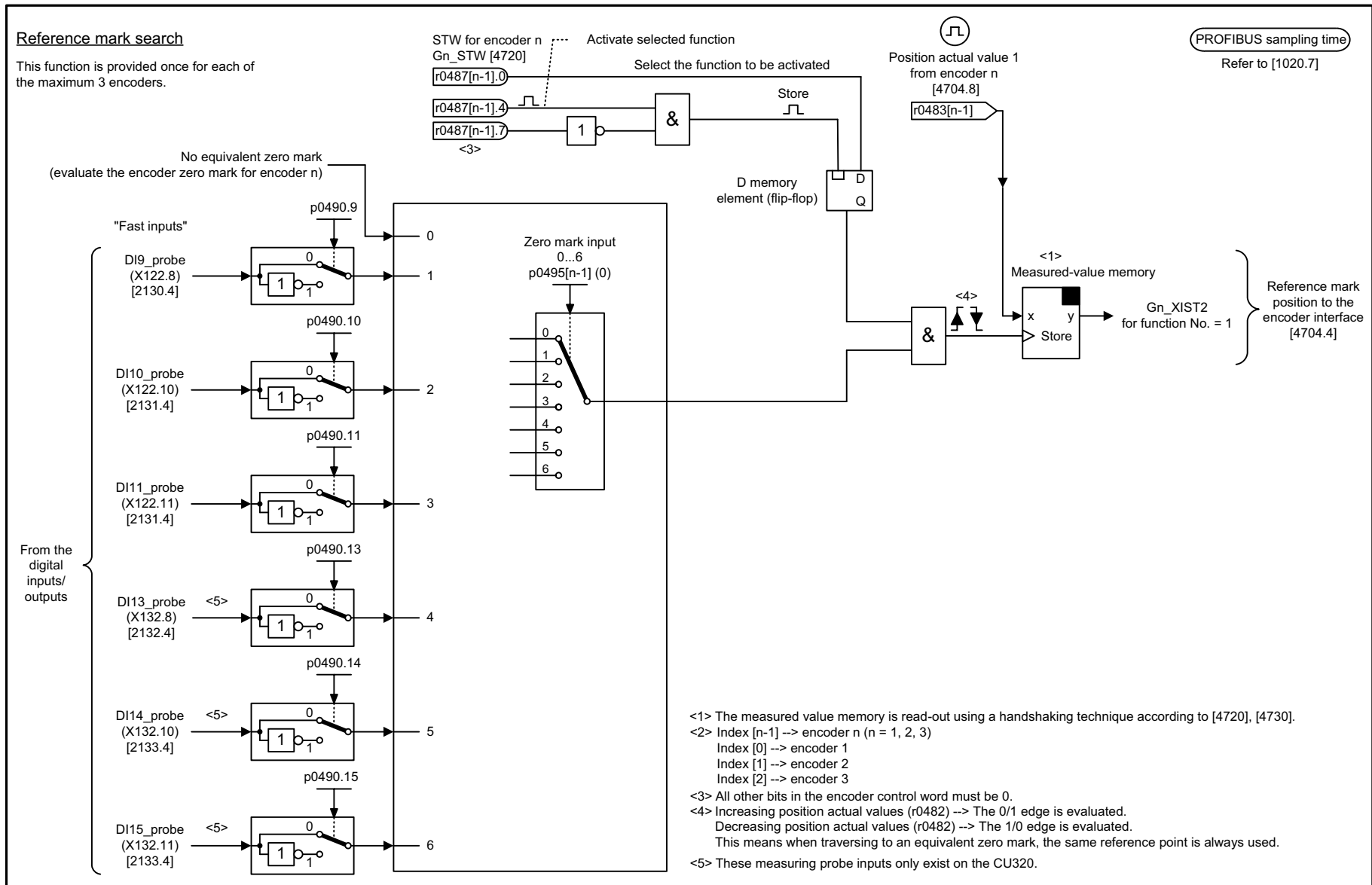
1	2	3	4	5	6	7	8
DO: VECTOR					fp_4715_01_eng.vsd	Function diagram	
Encoder evaluation - speed act. value and pole pos. sensing motor enc. ASM/SM (encoder 1)					03.03.06 V02.04.00	SINAMICS S	
							- 4715 -



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4720_01_eng.vsd	Function diagram	
Encoder evaluation function - encoder interface, receive signals, encoders 1 ... 3					23.03.06 V02.04.00	SINAMICS S	
							- 4720 -

Figure 2-123 4730 – Encoder interface, send signals, encoders 1 ... 3

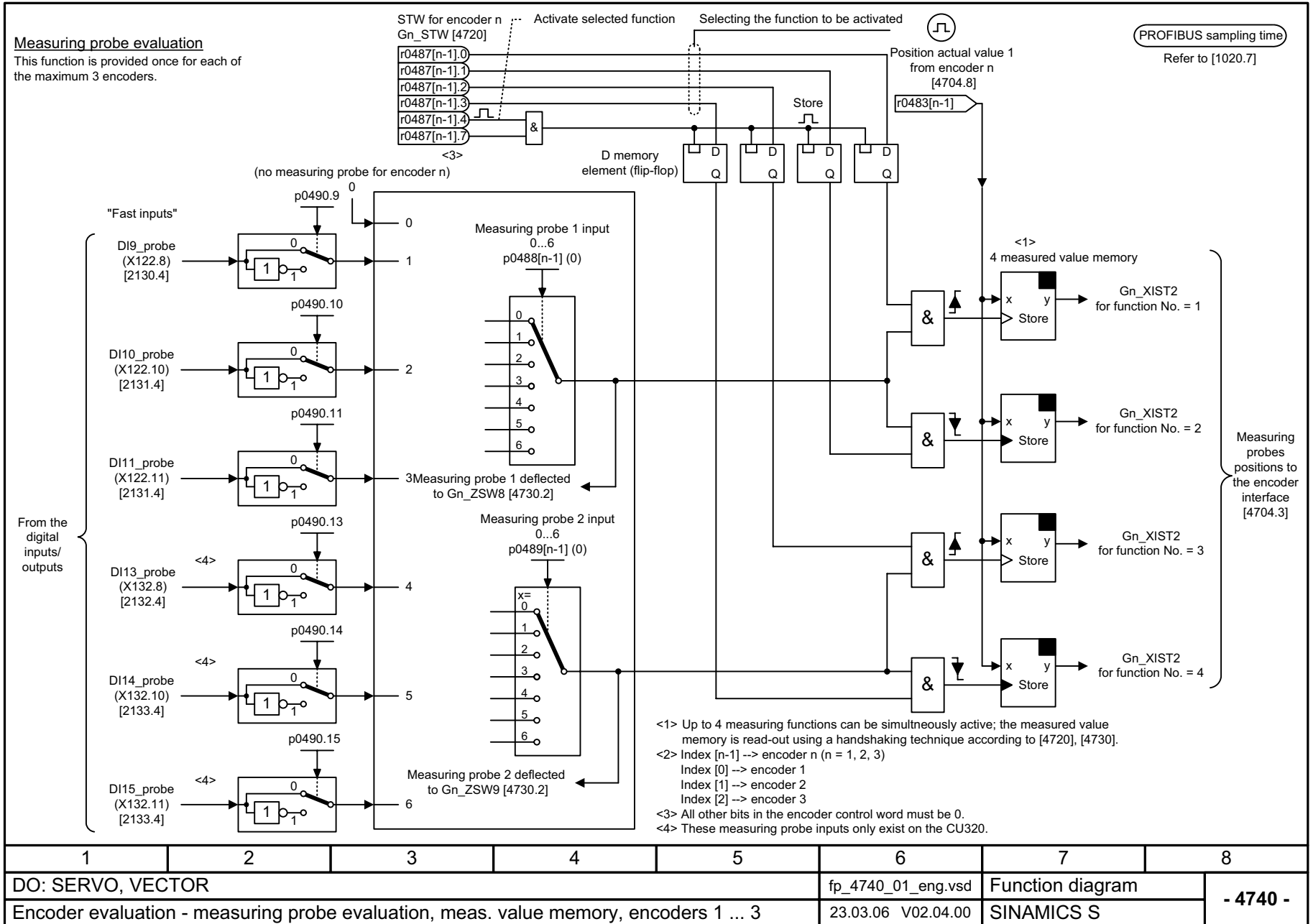




1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_4735_01_eng.vsd	Function diagram	
Encoder evaluation - reference mark search with equivalent zero mark, encoders 1 ... 3					23.03.06 V02.04.00	SINAMICS S	
							- 4735 -

Figure 2-124 4735 – Reference mark search with equivalent zero mark, encoders 1 ... 3

Figure 2-125 4740 – Measuring input evaluation, measured value memory, encoders 1 ... 3

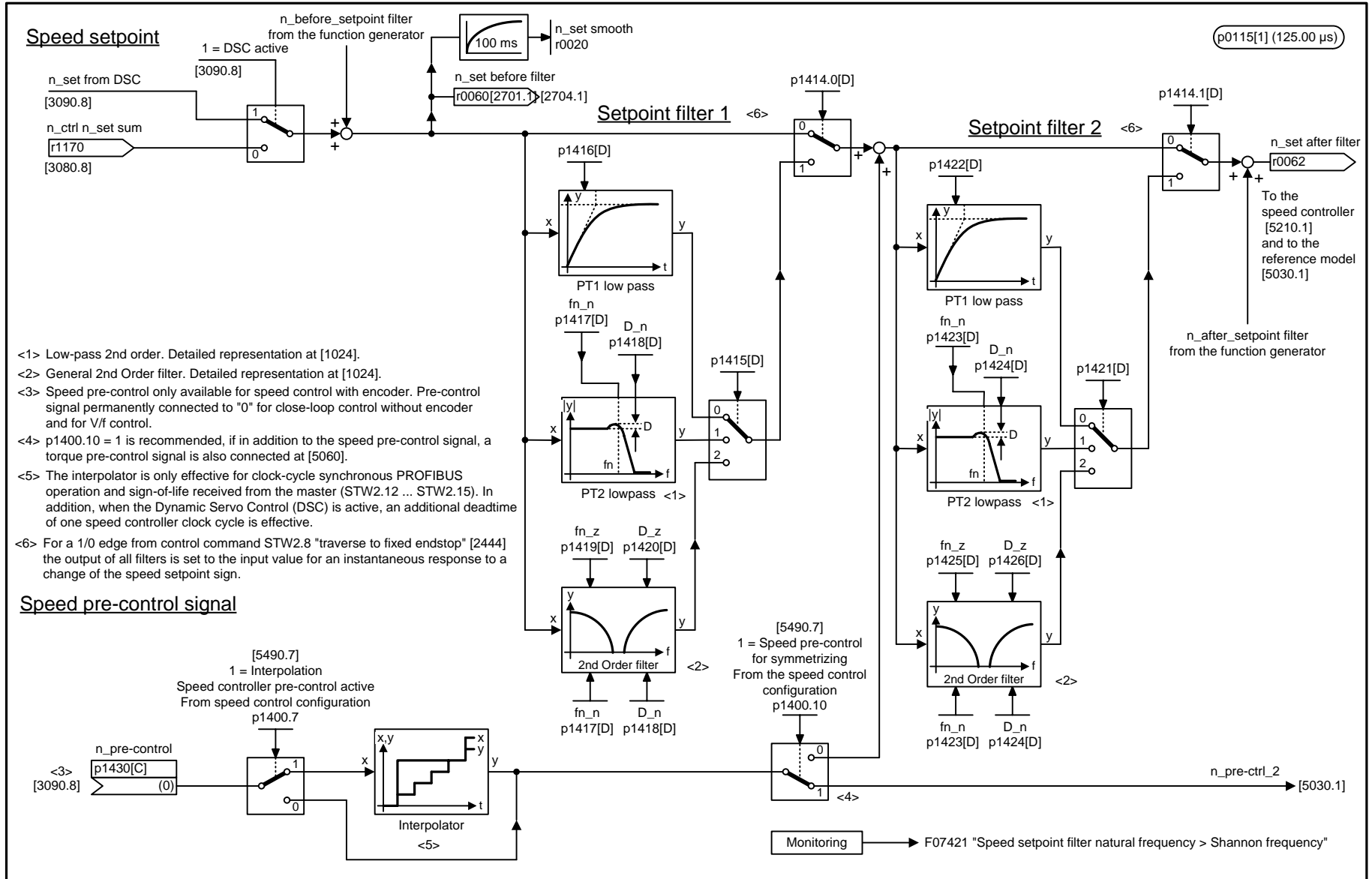


2.18 Servo control

Function diagrams

5020 – Speed setpoint filter and speed pre-control	2-1057
5030 – Reference model/pre-control symmetrization/setpoint n-controller	2-1058
5040 – Speed controller with encoder	2-1059
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5650 – Vdc_max controller and Vdc_min controller	2-1069
5710 – Current setpoint filter	2-1070
5714 – Iq and Id controller	2-1071
5722 – Field current setpoint, flux controller	2-1072
5730 – Interface to the motor module (gating/control signals, current actual values)	2-1073

Figure 2-126 5020 – Speed setpoint filter and speed pre-control



1	2	3	4	5	6	7	8
DO: SERVO					fp_5020_01_eng.vsd	Fuction diagram	
Servo speed control with encoder - speed setpoint filter and speed pre-control					07.02.06 V02.04.00	SINAMICS S	
							- 5020 -

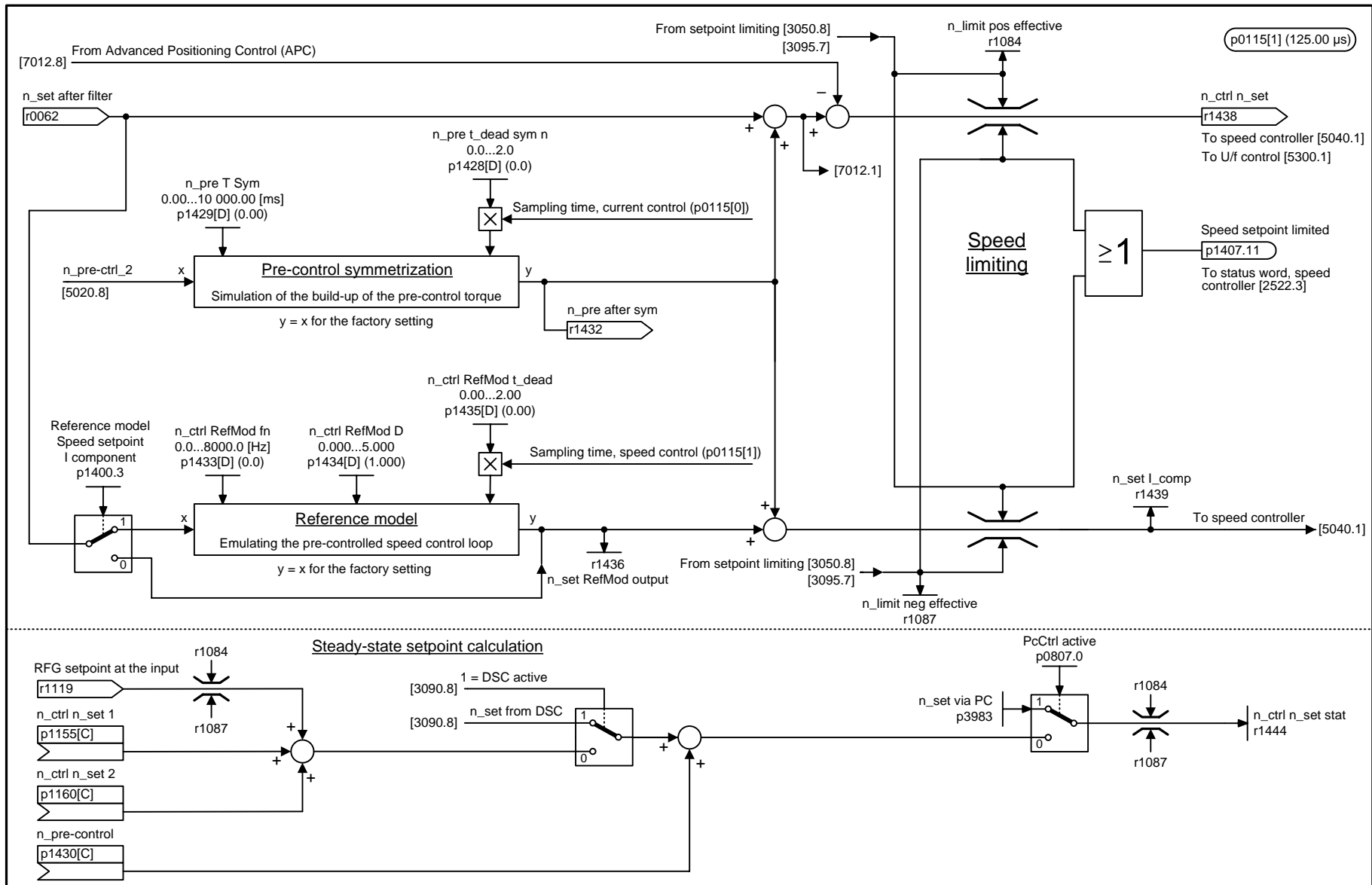
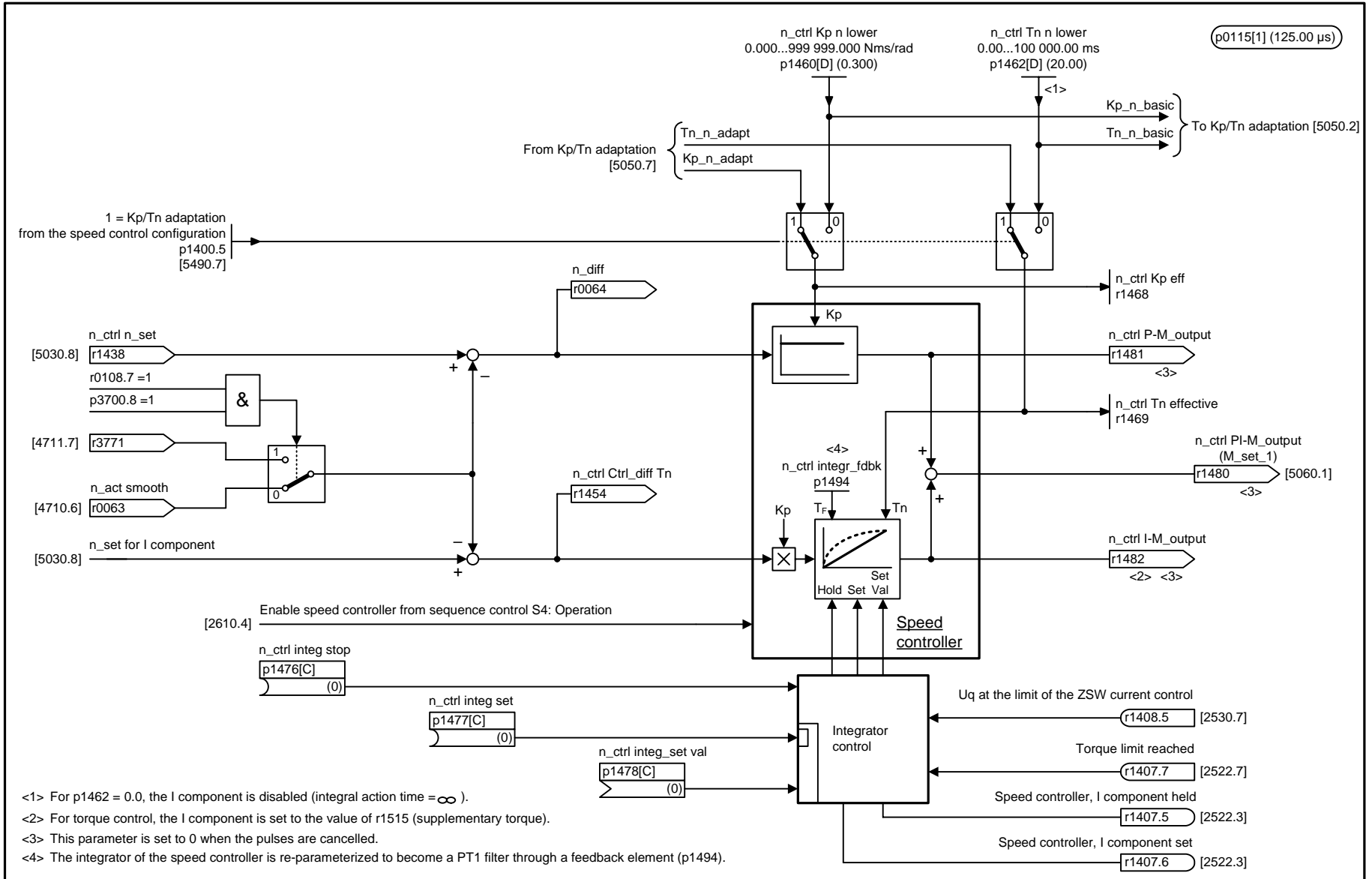


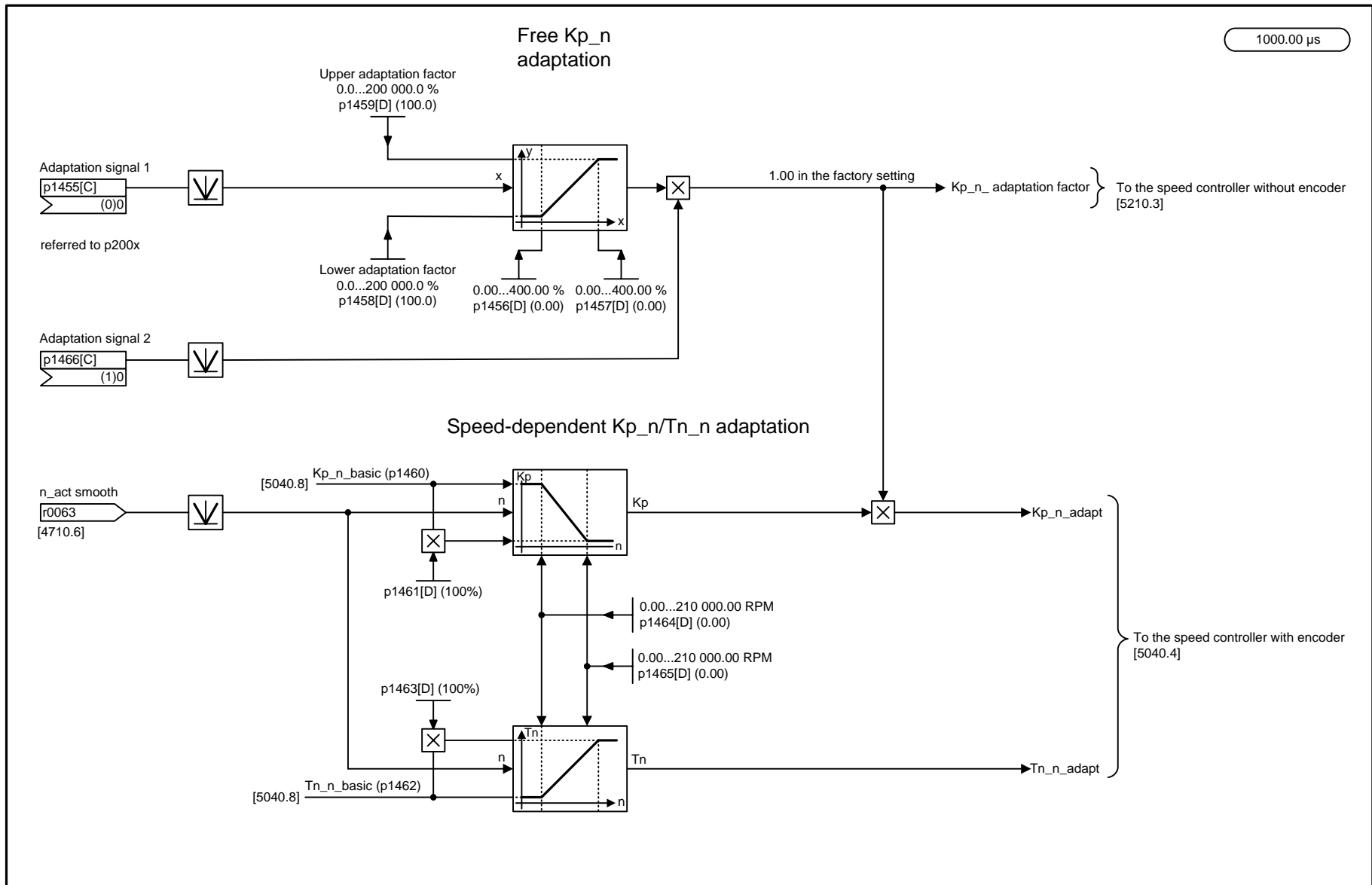
Figure 2-127 5030 – Reference model/pre-control symmetrization/setpoint n-controller

1	2	3	4	5	6	7	8
DO: SERVO					fp_5030_01_eng.vsd	Function diagram	
Servo speed control with encoder - reference model/pre-control symmetrization/setpoint n_ctrl.					13.03.06 V02.04.00	SINAMICS S	
- 5030 -							

Figure 2-128 5040 – Speed controller with encoder



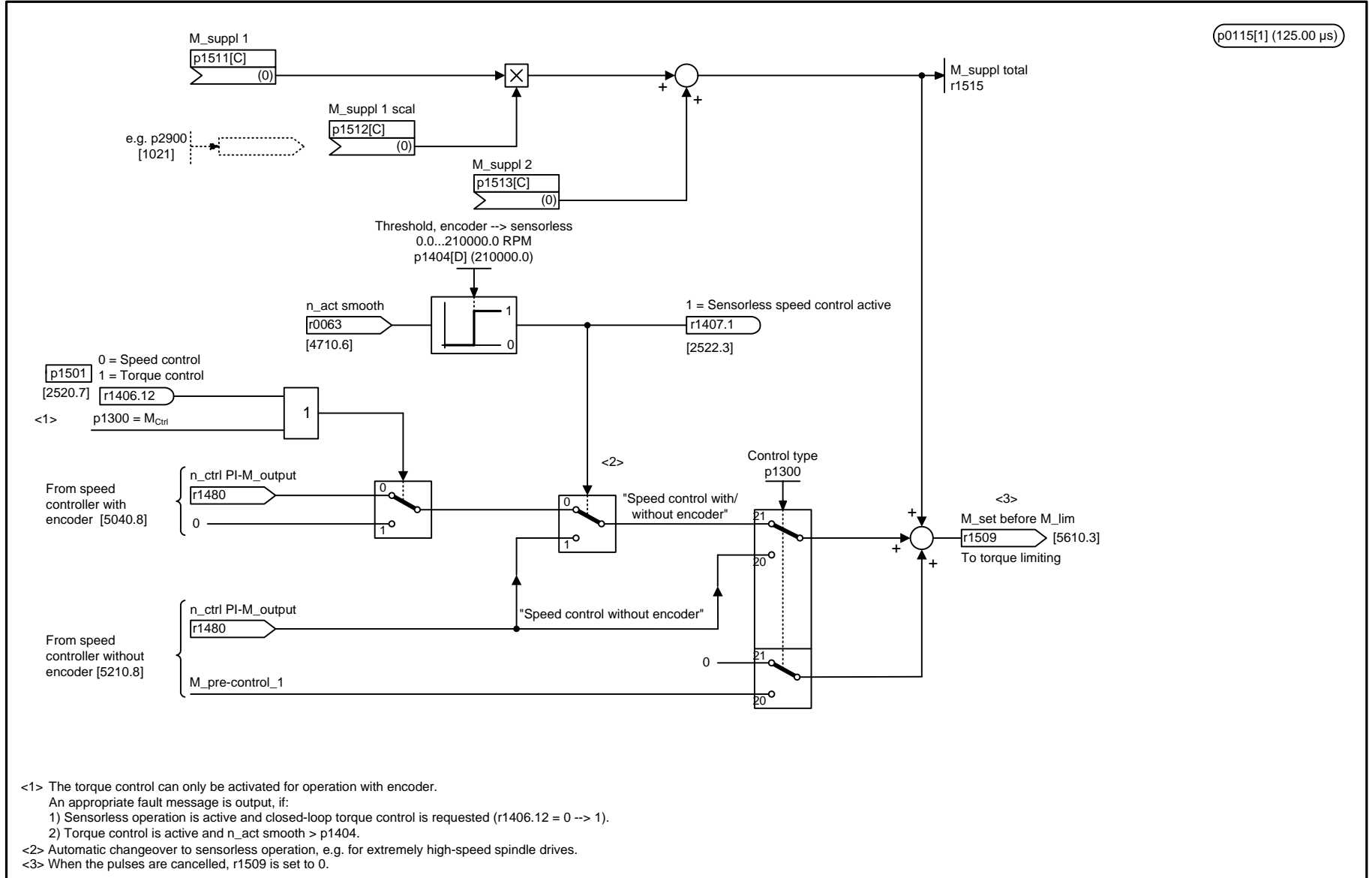
1	2	3	4	5	6	7	8
DO: SERVO					fp_5040_01_eng.vsd	Function diagram	
Servo speed control with encoder - speed controller					02.03.06 V02.04.00	SINAMICS S	
							- 5040 -



1	2	3	4	5	6	7	8
DO: SERVO					fp_5050_01_eng.vsd	Function diagram	
Servo speed control without encoder - Kp_n/Tn_n adaptation					09.11.04 V02.04.00	SINAMICS S	
							- 5050 -

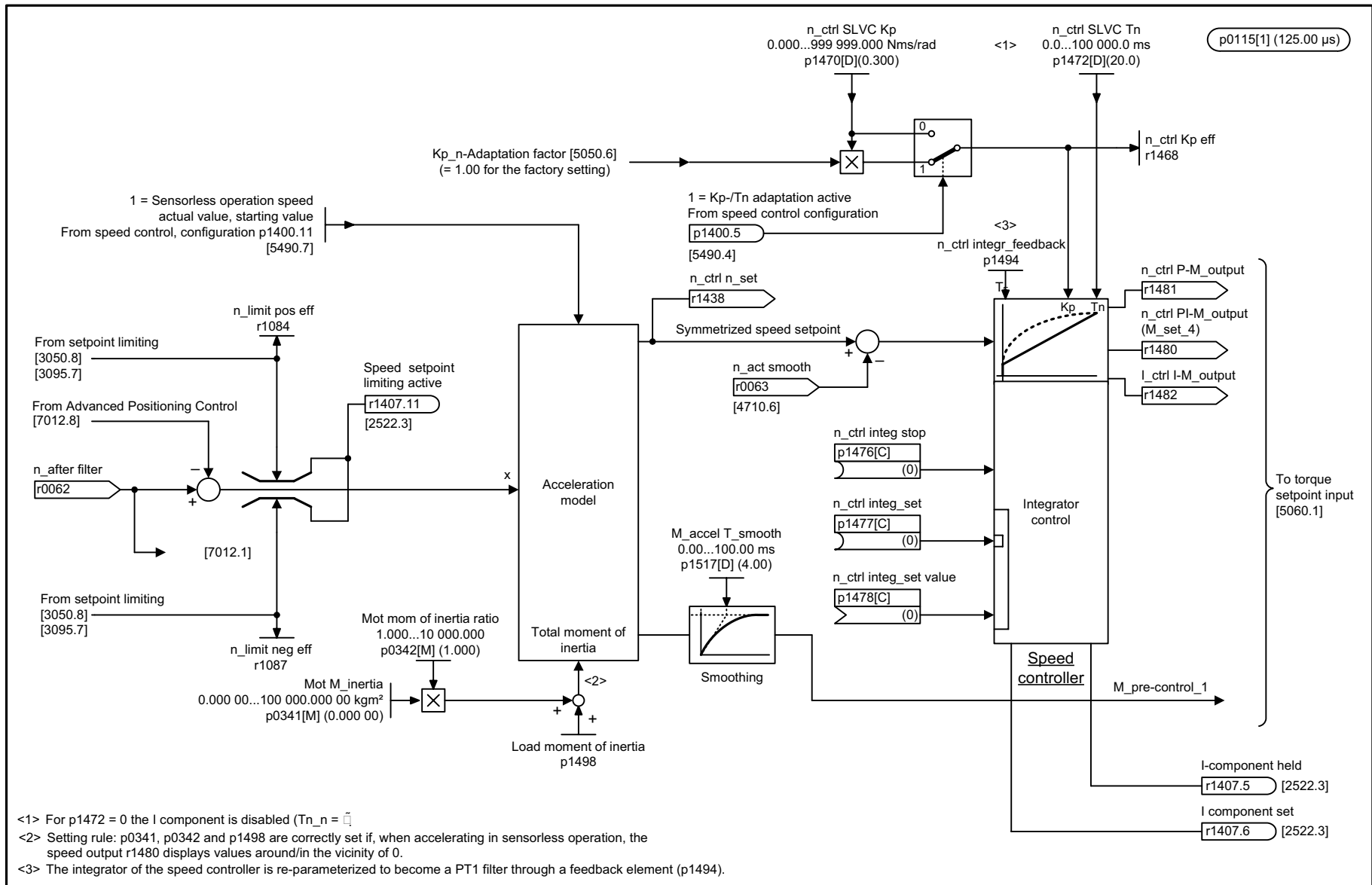
Figure 2-129 5050 – Kp_n/Tn_n adaptation

Figure 2-130 5060 – Torque setpoint, changeover control type



- <1> The torque control can only be activated for operation with encoder.
 An appropriate fault message is output, if:
 1) Sensorless operation is active and closed-loop torque control is requested (r1406.12 = 0 --> 1).
 2) Torque control is active and n_act smooth > p1404.
- <2> Automatic changeover to sensorless operation, e.g. for extremely high-speed spindle drives.
- <3> When the pulses are cancelled, r1509 is set to 0.

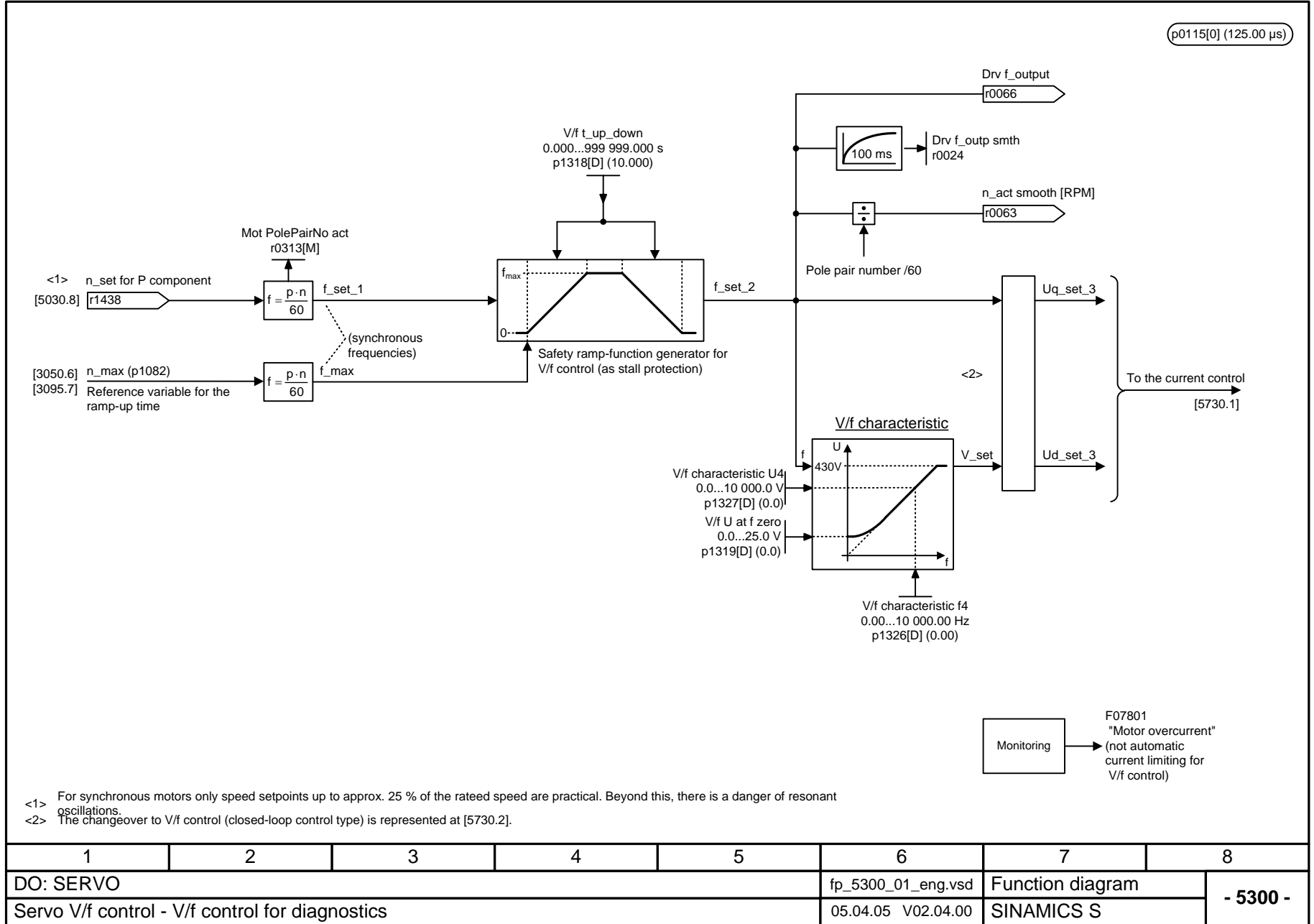
1	2	3	4	5	6	7	8
DO: SERVO					fp_5060_01_eng.vsd	Function diagram	
Servo speed control with encoder - torque setpoint, changeover control type					18.05.05 V02.04.00	SINAMICS S	
							- 5060 -



1	2	3	4	5	6	7	8
DO: SERVO					fp_5210_01_eng.vsd	Function diagram	
Servo speed control without encoder - speed controller					22.11.05 V02.04.00	SINAMICS S	
							- 5210 -

Figure 2-131 5210 – Speed controller without encoder

Figure 2-132 5300 – V/f control for diagnostics



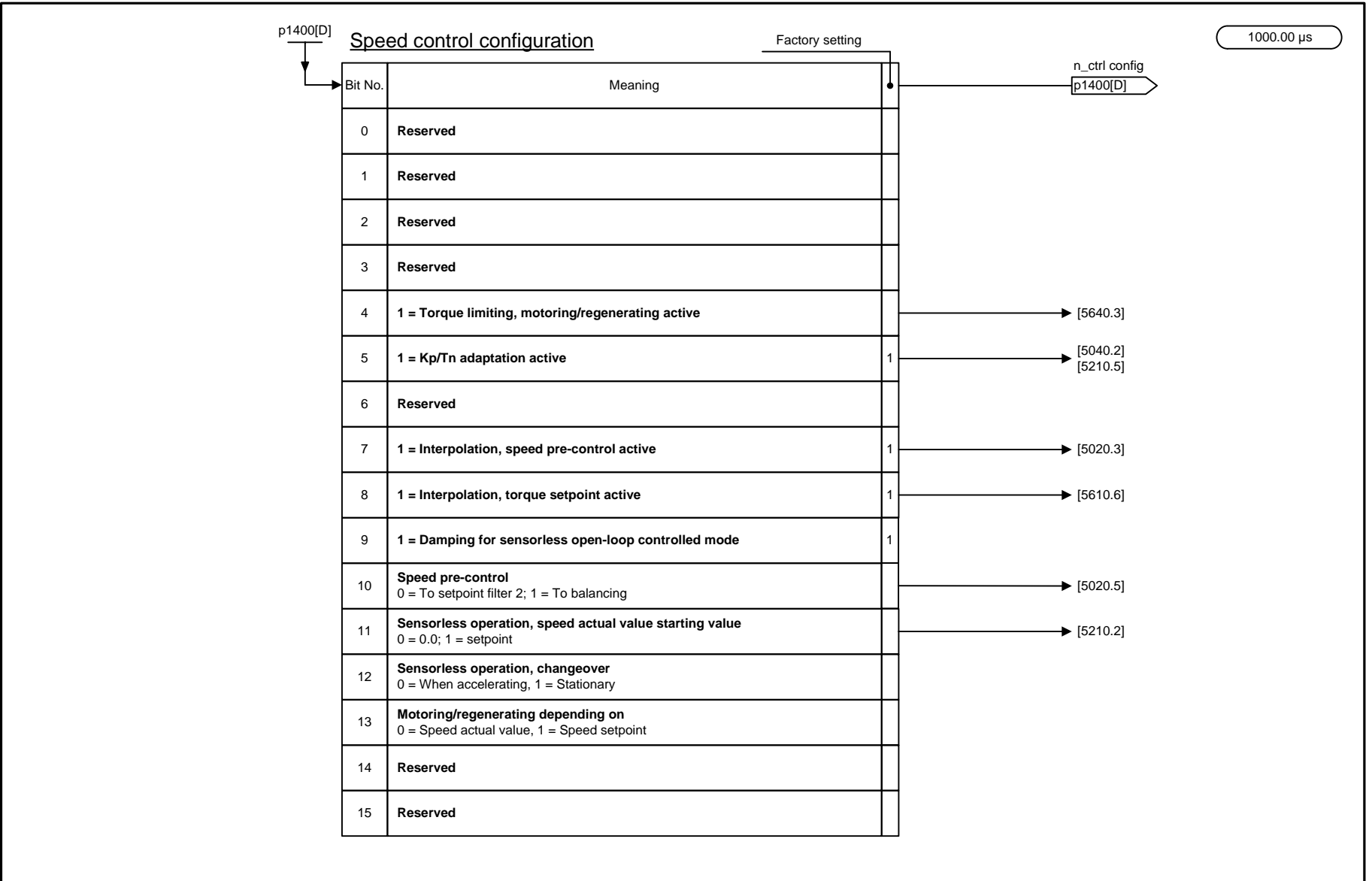
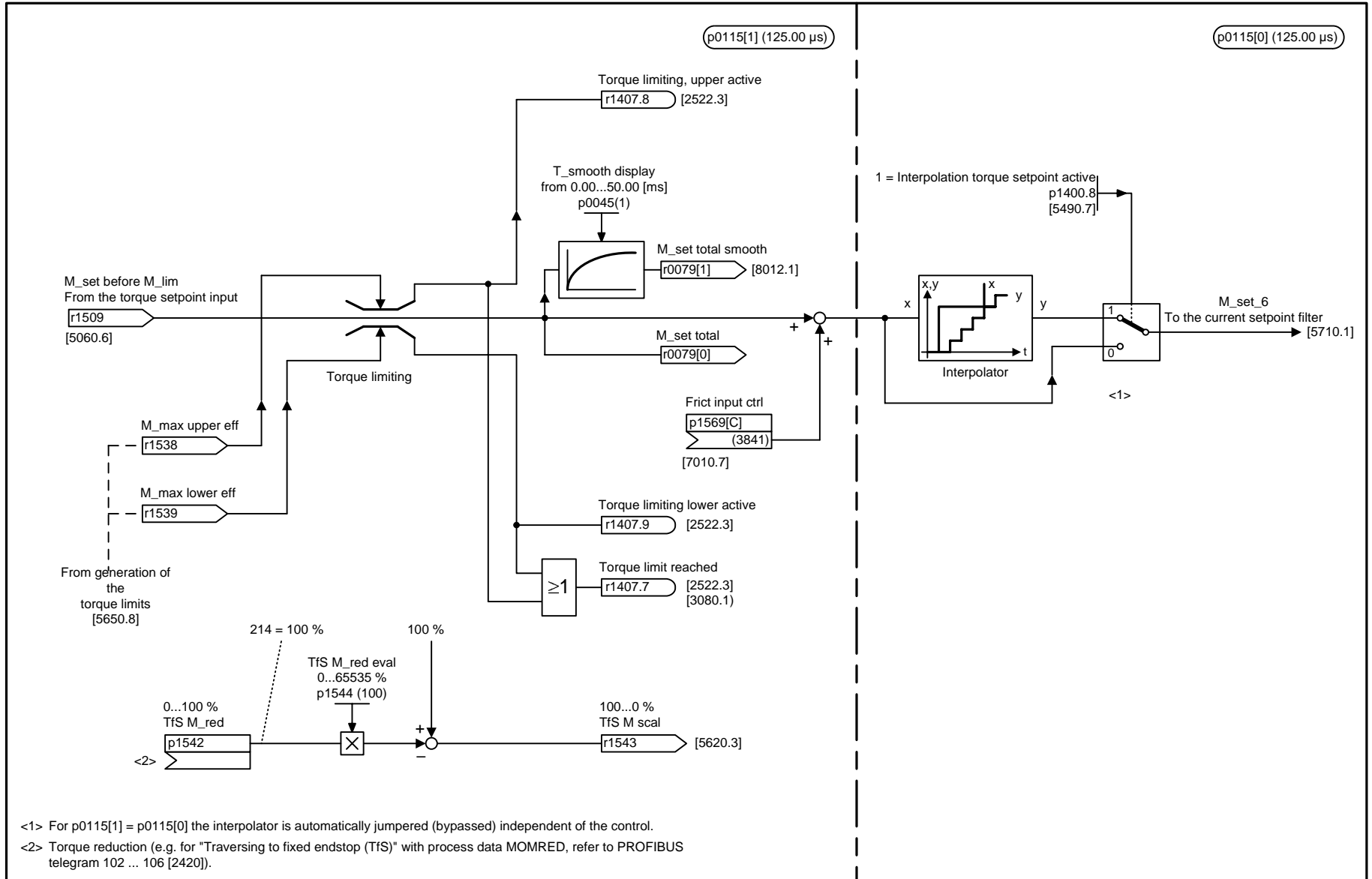


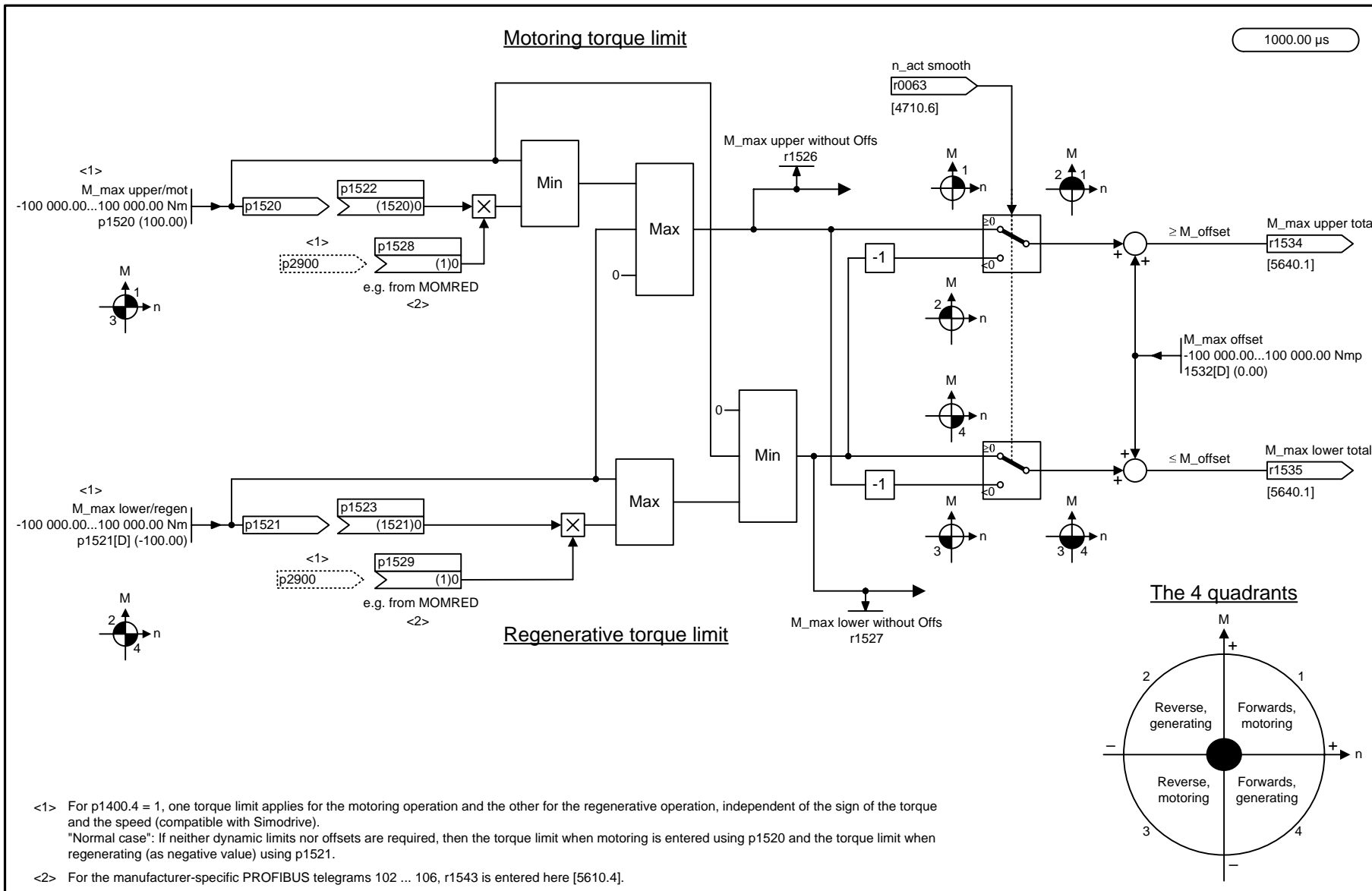
Figure 2-133 5490 – Speed control configuration

1	2	3	4	5	6	7	8
DO: SERVO					fp_5490_01_eng.vsd	Function diagram	
Servo closed-loop - open-loop status words - speed control configuration					08.03.05 V02.04.00	SINAMICS S	
- 5490 -							

Figure 2-134 5610 – Torque limiting/reduction/interpolator



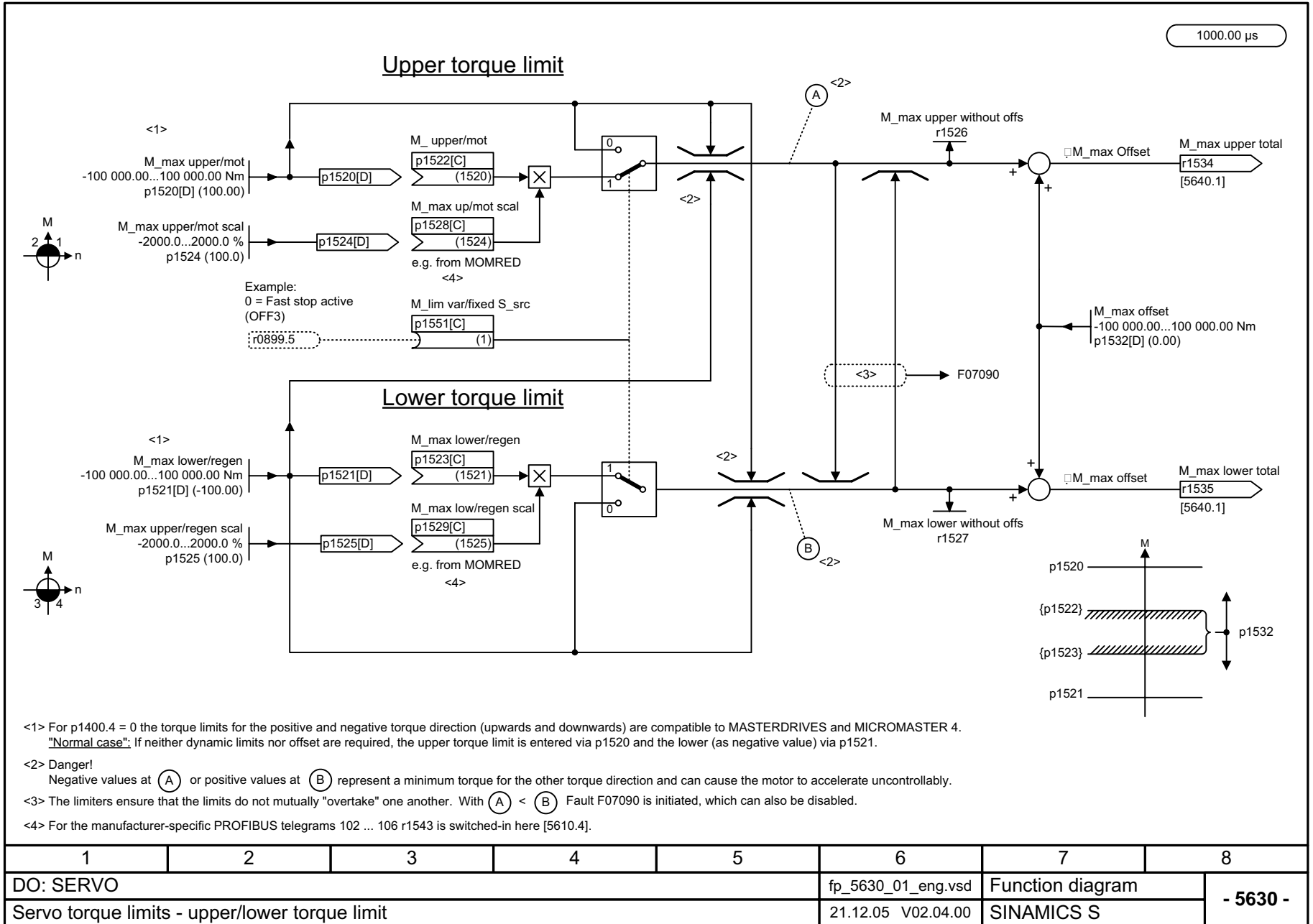
1	2	3	4	5	6	7	8
DO: SERVO					fp_5610_01_eng.vsd	Function diagram	
Servo torque limits - torque limiting/reduction/interpolator					12.07.05 V02.04.00	SINAMICS S	
							- 5610 -



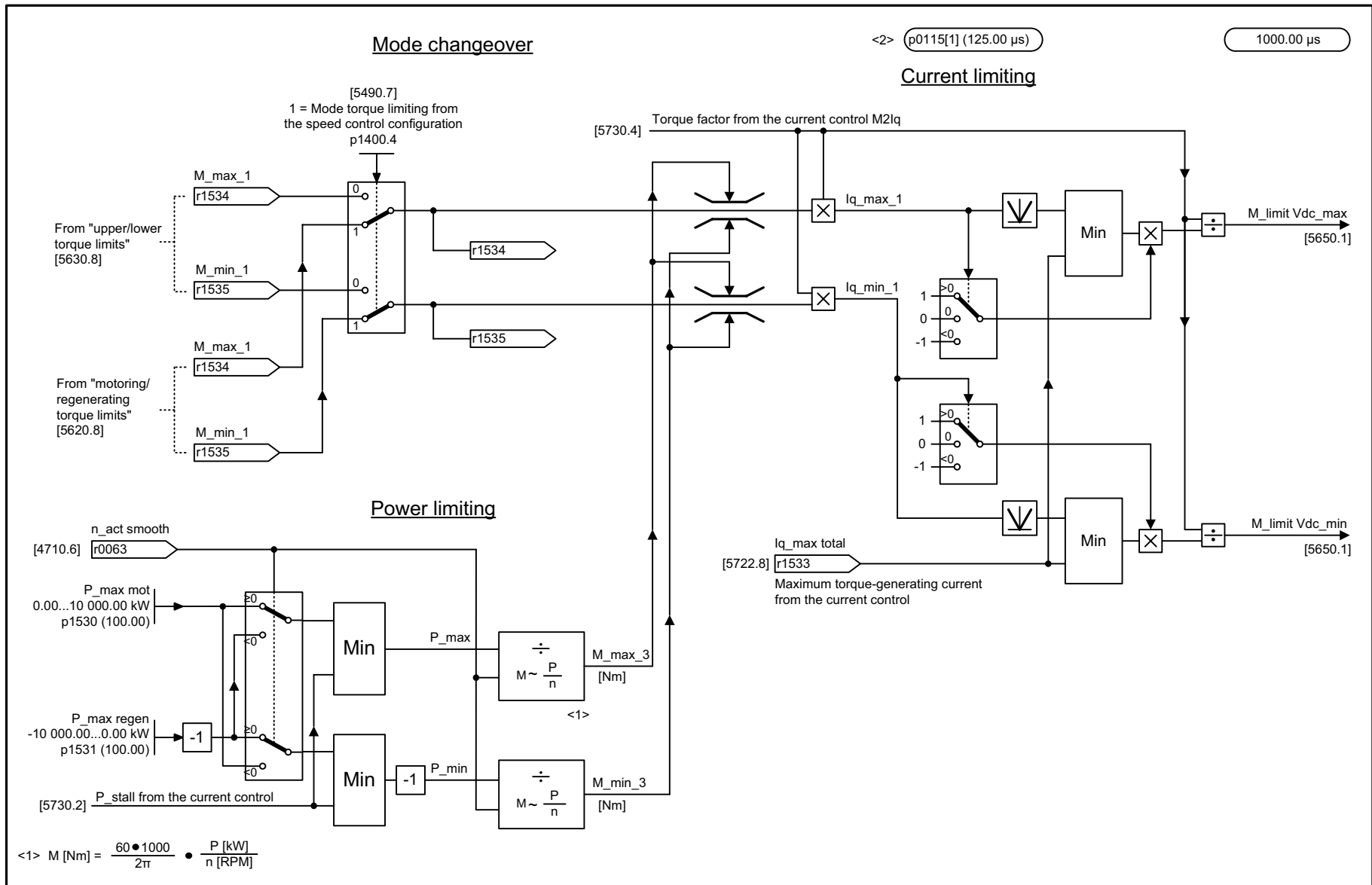
1	2	3	4	5	6	7	8
DO: SERVO					fp_5620_01_eng.vsd	Function diagram	
Servo torque limitis - motoring/regenerating torque limit					05.10.04 V02.04.00	SINAMICS S	
							- 5620 -

Figure 2-135 5620 – Motor/generator torque limit

Figure 2-136 5630 – Upper/lower torque limit



1	2	3	4	5	6	7	8
DO: SERVO					fp_5630_01_eng.vsd	Function diagram	
Servo torque limits - upper/lower torque limit					21.12.05 V02.04.00	SINAMICS S	
							- 5630 -



<1> $M [Nm] = \frac{60 \bullet 1000}{2\pi} \bullet \frac{P [kW]}{n [RPM]}$

1	2	3	4	5	6	7	8
DO: SERVO					fp_5640_01_eng.vsd	Function diagram	
Servo torque limits - mode changeover, power/current limiting					24.01.06 V02.04.00	SINAMICS S	
							- 5640 -

Figure 2-137 5640 – Mode changeover, power/current limiting

1000.00 μ s

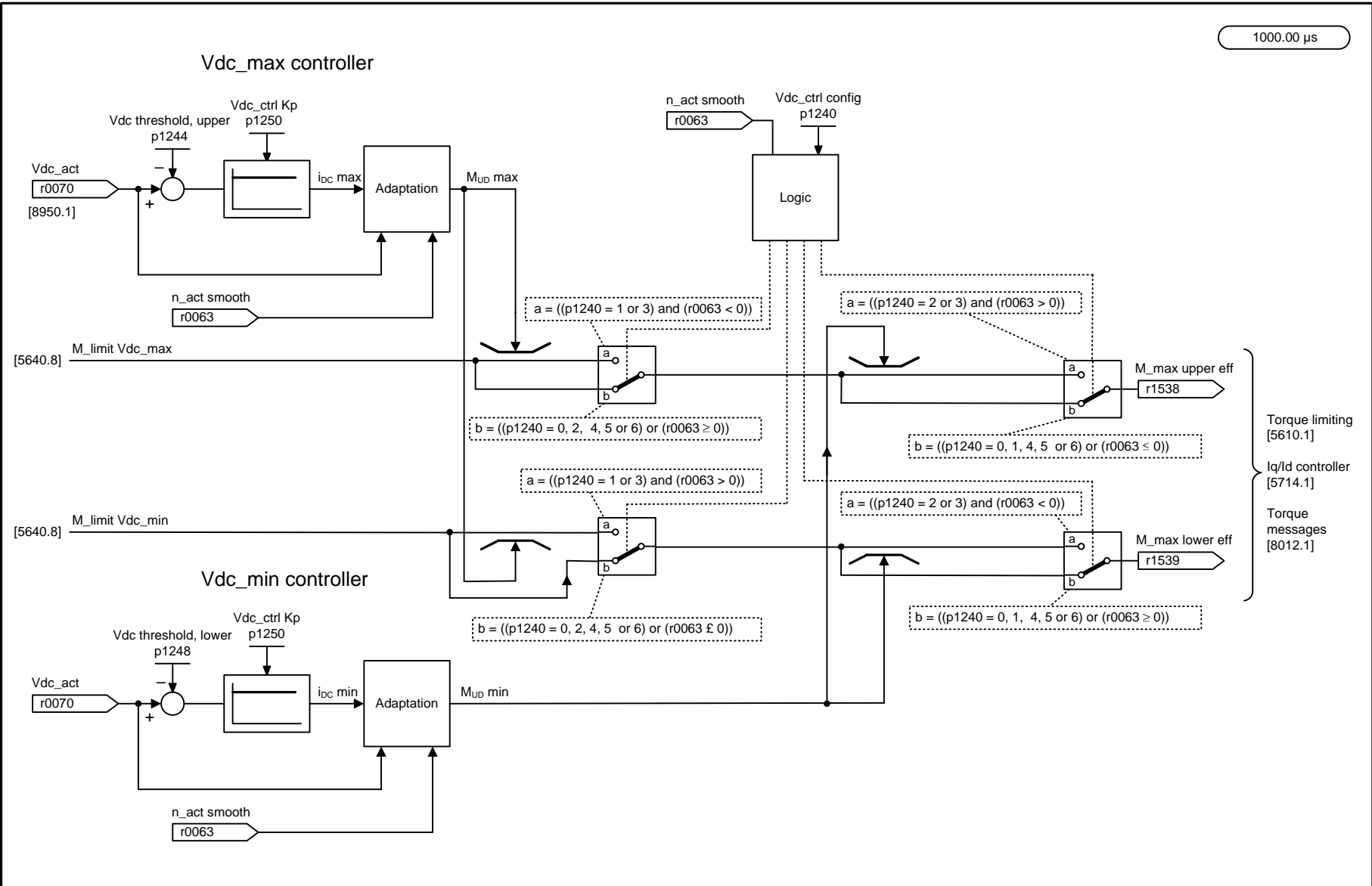
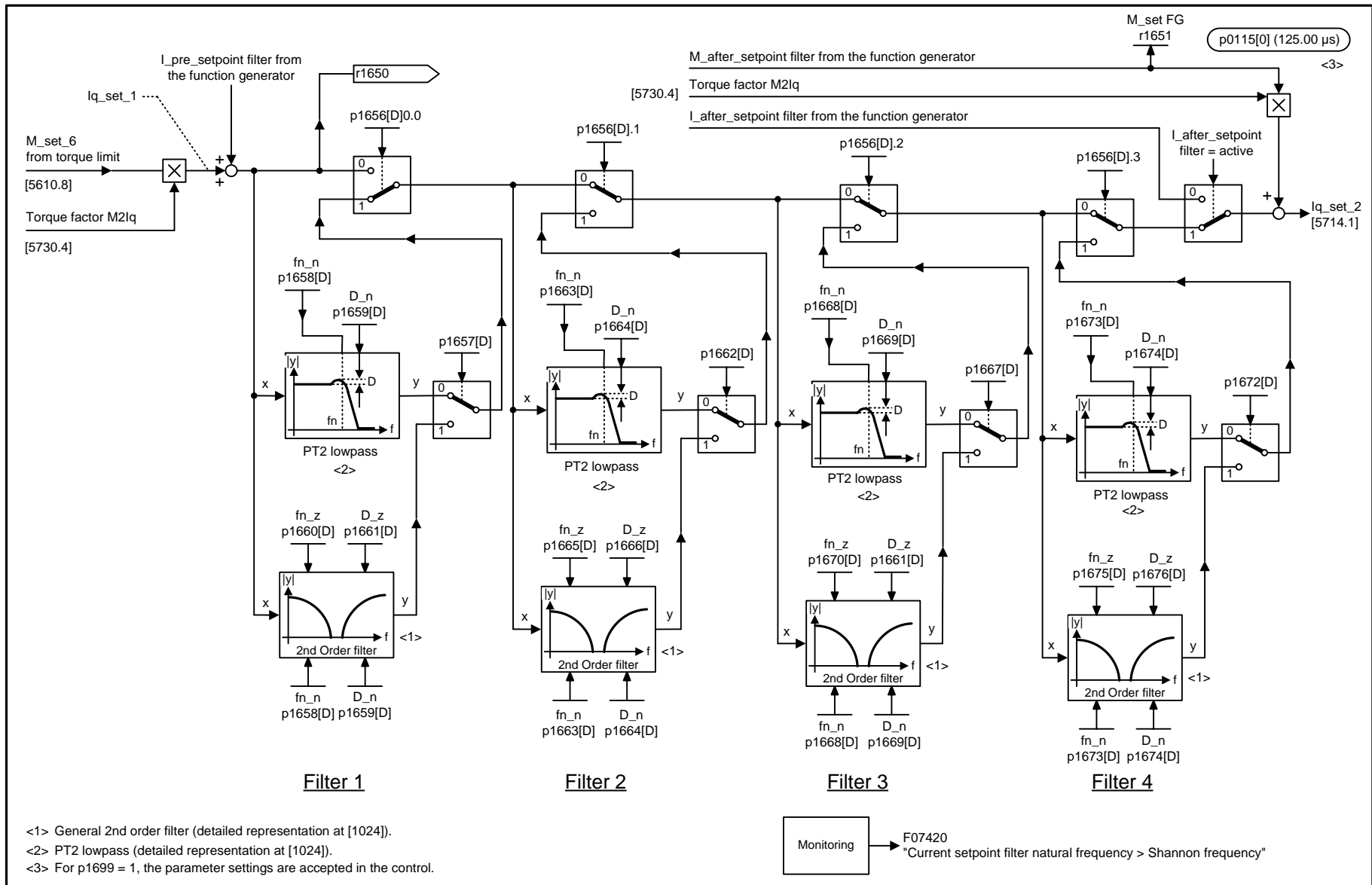


Figure 2-138 5650 – Vdc_max controller and Vdc_min controller

1	2	3	4	5	6	7	8
DO: SERVO					fp_5650_01_eng.vsd	Function diagram	
Servo torque limits - Vdc_max controller and Vdc_min controller					14.07.05 V02.04.00	SINAMICS S	
							- 5650 -



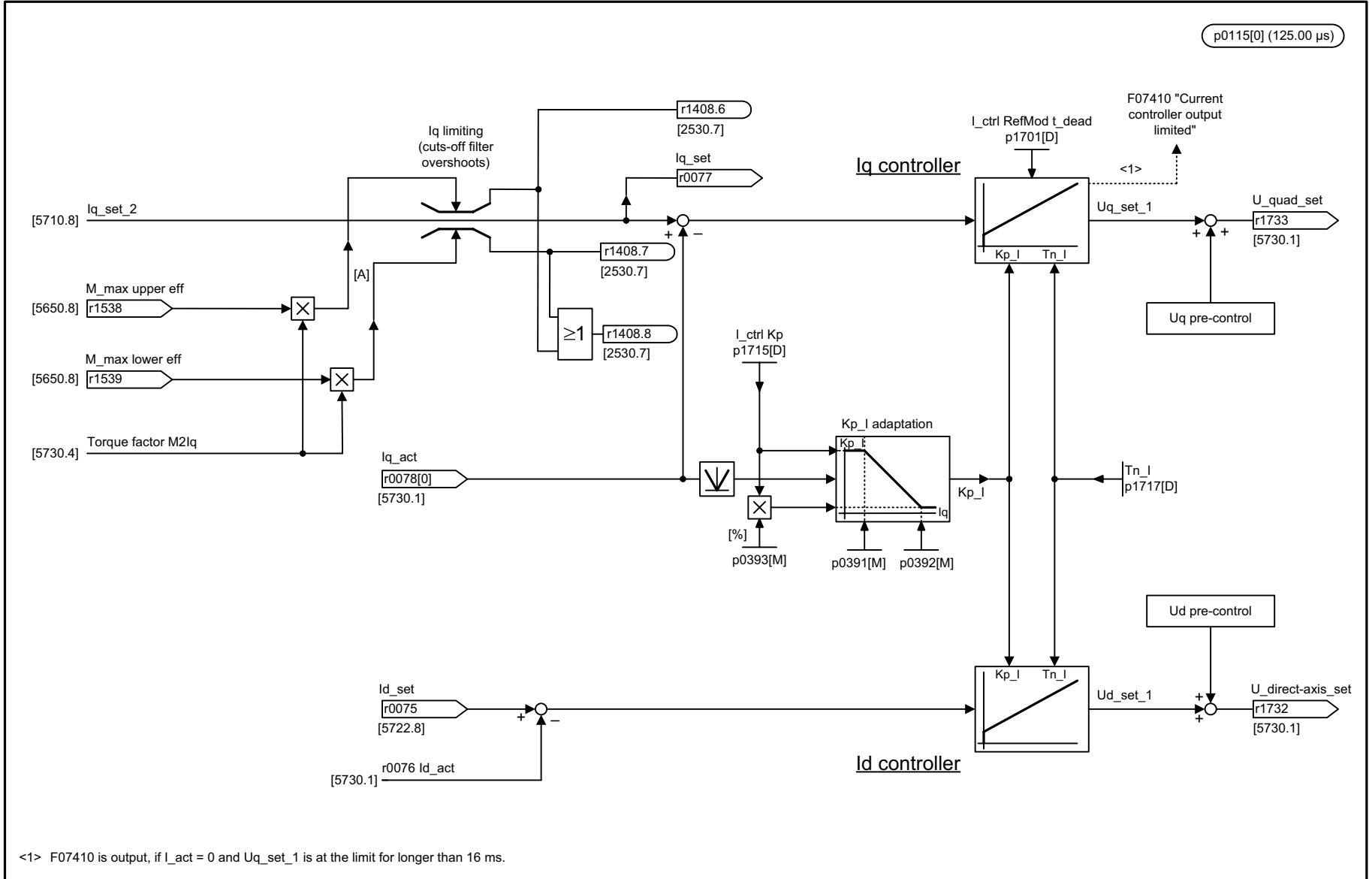
<1> General 2nd order filter (detailed representation at [1024]).
 <2> PT2 lowpass (detailed representation at [1024]).
 <3> For p1699 = 1, the parameter settings are accepted in the control.

Monitoring → F07420
 "Current setpoint filter natural frequency > Shannon frequency"

1	2	3	4	5	6	7	8
DO: SERVO					fp_5710_01_eng.vsd	Function diagram	
Servo current control - current setpoint filter					09.09.05 V02.04.00	SINAMICS S	
							- 5710 -

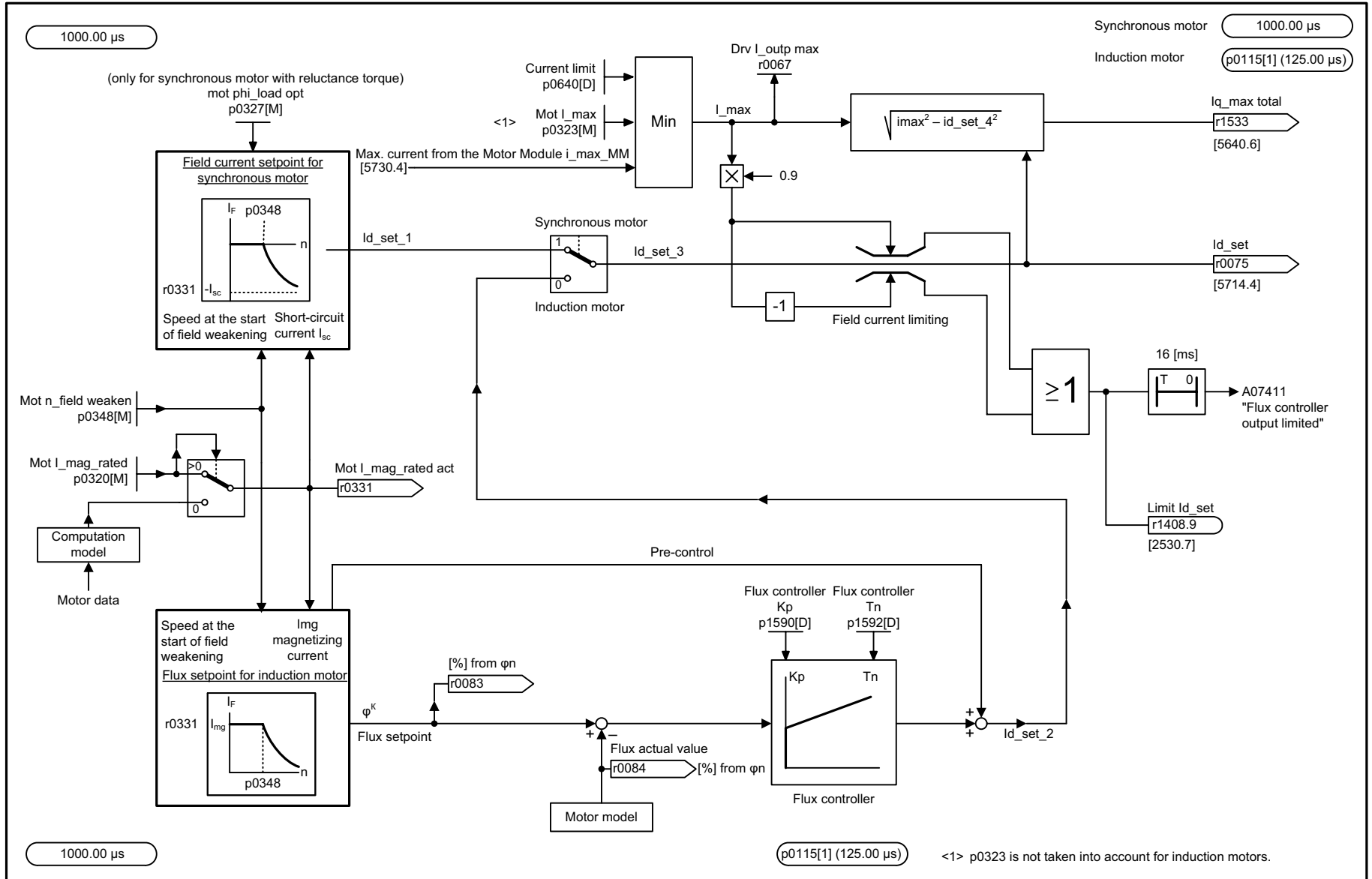
Figure 2-139 5710 – Current setpoint filter

Figure 2-140 5714 – Iq and Id controller



<1> F07410 is output, if $I_{act} = 0$ and $U_{q_set_1}$ is at the limit for longer than 16 ms.

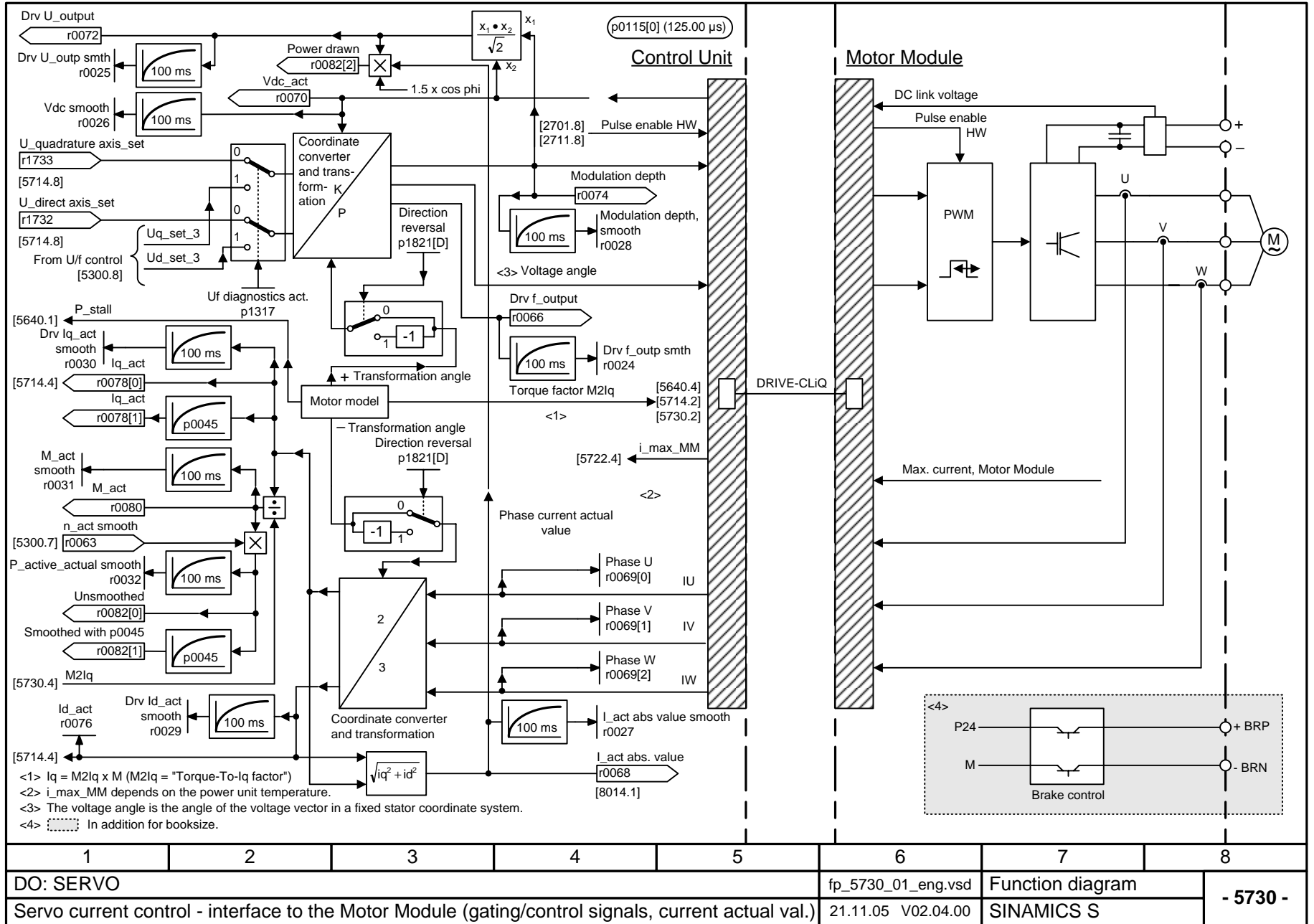
1	2	3	4	5	6	7	8
DO: SERVO					fp_5714_01_eng.vsd	Function diagram	
Servo current control - Iq and Id controller					23.03.06 V02.04.00	SINAMICS S	
							- 5714 -



1	2	3	4	5	6	7	8
DO: SERVO					fp_5722_01_eng.vsd	Function diagram	
Servo current control - field current setpoint, flux controller					23.03.06 V02.04.00	SINAMICS S	
							- 5722 -

Figure 2-141 5722 – Field current setpoint, flux controller

Figure 2-142 5730 – Interface to the motor module (gating/control signals, current actual values)



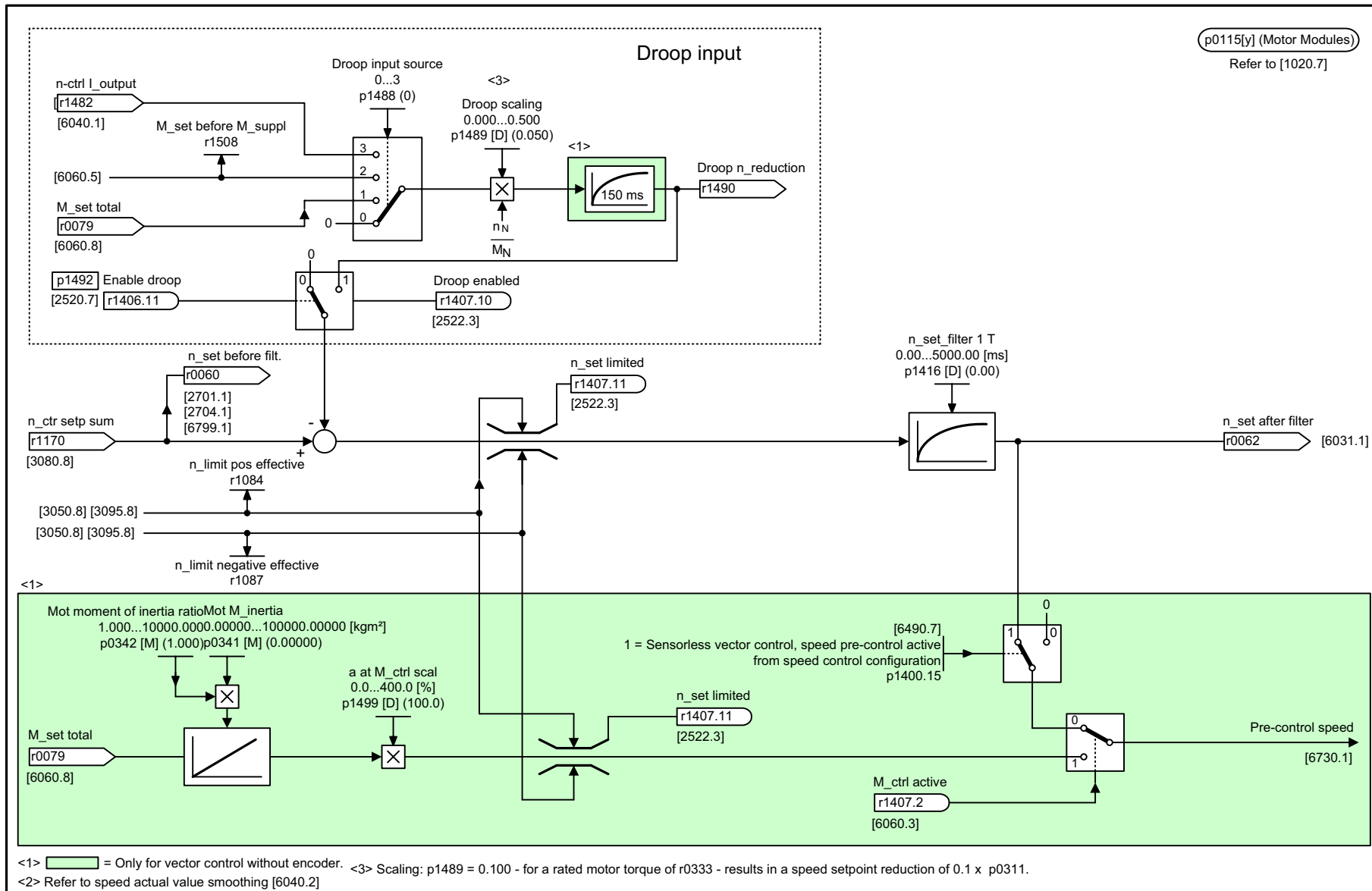
1	2	3	4	5	6	7	8
DO: SERVO					fp_5730_01_eng.vsd	Function diagram	
Servo current control - interface to the Motor Module (gating/control signals, current actual val.)					21.11.05 V02.04.00	SINAMICS S	
- 5730 -							

2.19 Vector control

Function diagrams

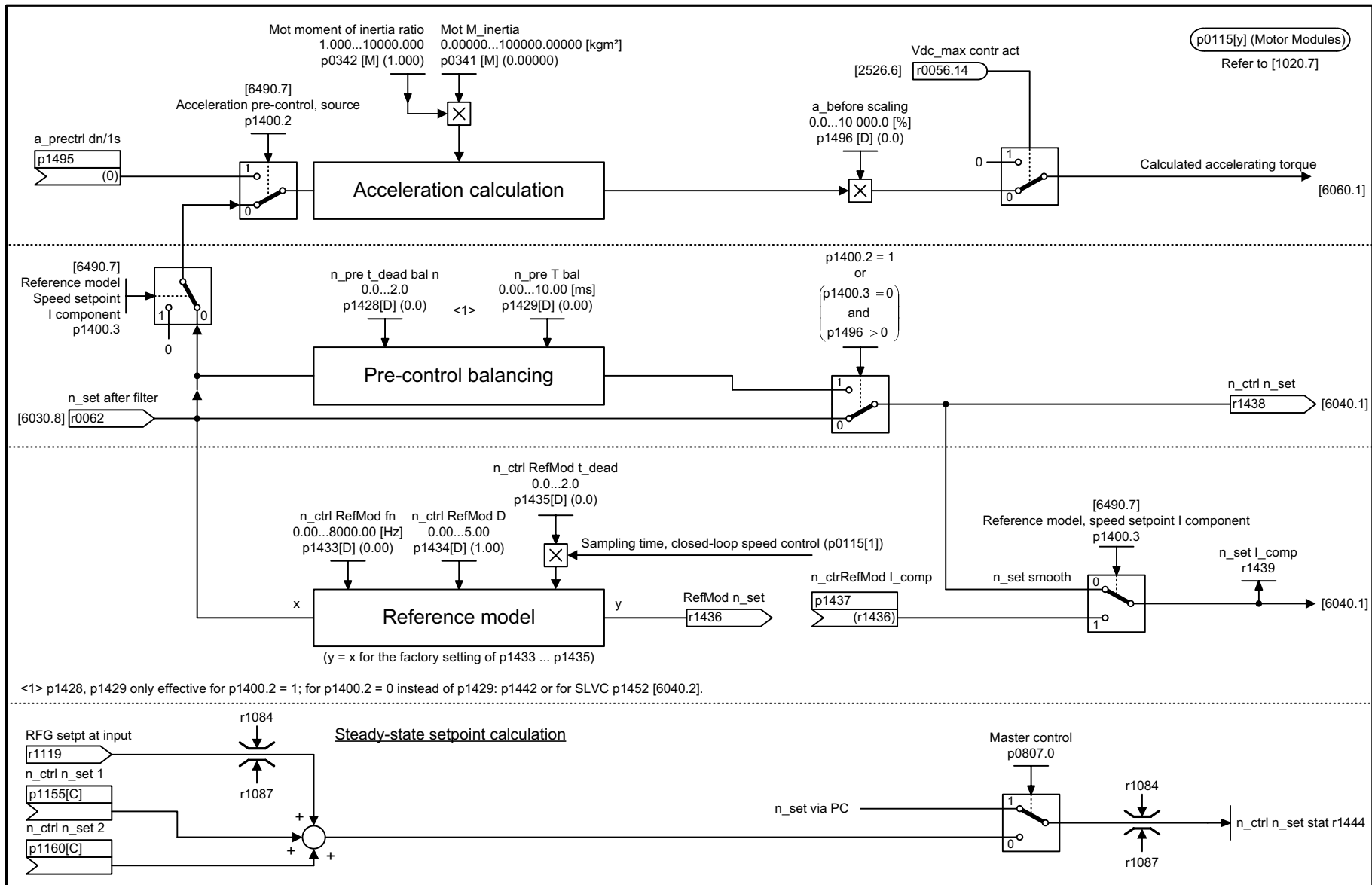
6030 – Speed setpoint, droop	2-1075
6031 – Pre-control balancing for reference/acceleration model	2-1076
6040 – Speed controller with/without encoder	2-1077
6050 – Kp_n/Tn_n adaptation	2-1078
6060 – Torque setpoint	2-1079
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6300 – V/f characteristic and voltage boost	2-1081
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6710 – Current setpoint filter	2-1089
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6721 – Id setpoint (PEM, p0300 = 2)	2-1091
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6726 – Field weakening controller, flux controller (FEM, p0300 = 5)	2-1096
6727 – Current model, excitation current monitoring, cos phi (FEM, p0300 = 5)	2-1097
6730 – Interface to the motor module (ASM, p0300 = 1)	2-1098
6731 – Interface to the motor module (PEM, p0300 = 2)	2-1099
6732 – Interface to the motor module (FEM, p0300 = 5)	2-1100
6799 – Display signals	2-1101

Figure 2-143 6030 – Speed setpoint, droop



Function diagrams
Vector control

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6030_01_eng.vsd	Function diagram	
Vector speed control with/without encoder - speed setpoint, droop					06.07.05 V02.04.00	SINAMICS S	
							- 6030 -

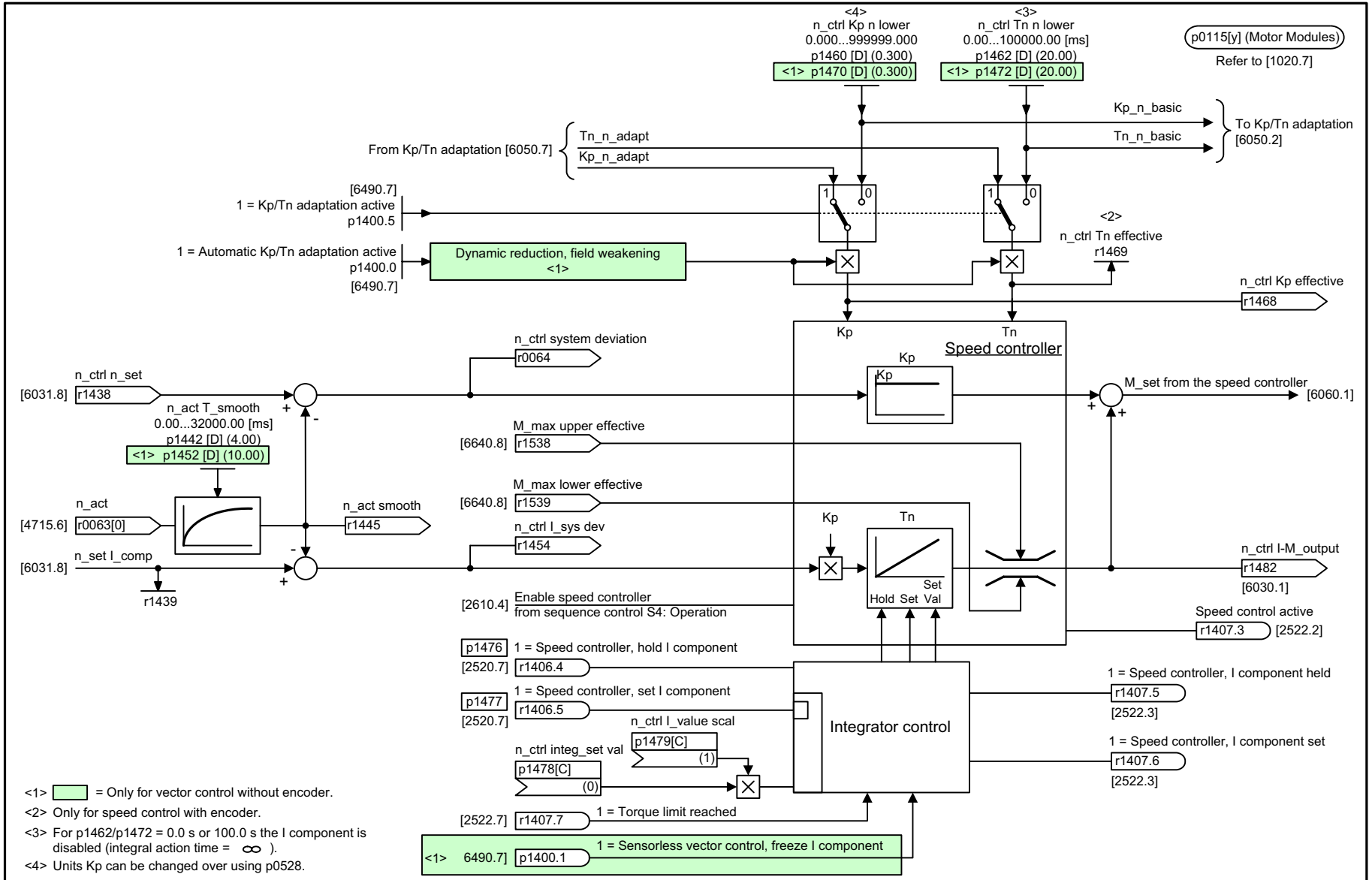


<1> p1428, p1429 only effective for p1400.2 = 1; for p1400.2 = 0 instead of p1429: p1442 or for SLVC p1452 [6040.2].

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6031_01_eng.vsd	Function diagram	
Vector closed-loop speed control with/without encoder - pre-control balancing ref./accel. model					23.03.06 V02.04.00	SINAMICS S	
- 6031 -							

Figure 2-144 6031 – Pre-control balancing for reference/acceleration model

Figure 2-145 6040 – Speed controller with/without encoder



- <1> [Green box] = Only for vector control without encoder.
- <2> Only for speed control with encoder.
- <3> For p1462/p1472 = 0.0 s or 100.0 s the I component is disabled (integral action time = ∞).
- <4> Units K_p can be changed over using p0528.

Function diagrams
 Vector control

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6040_01_eng.vsd	Function diagram	
Vector speed control with/without encoder - speed controller					23.03.06 V02.04.00	SINAMICS S	
							- 6040 -

p0115[y] (Motor Modules)
Refer to [1020.7]

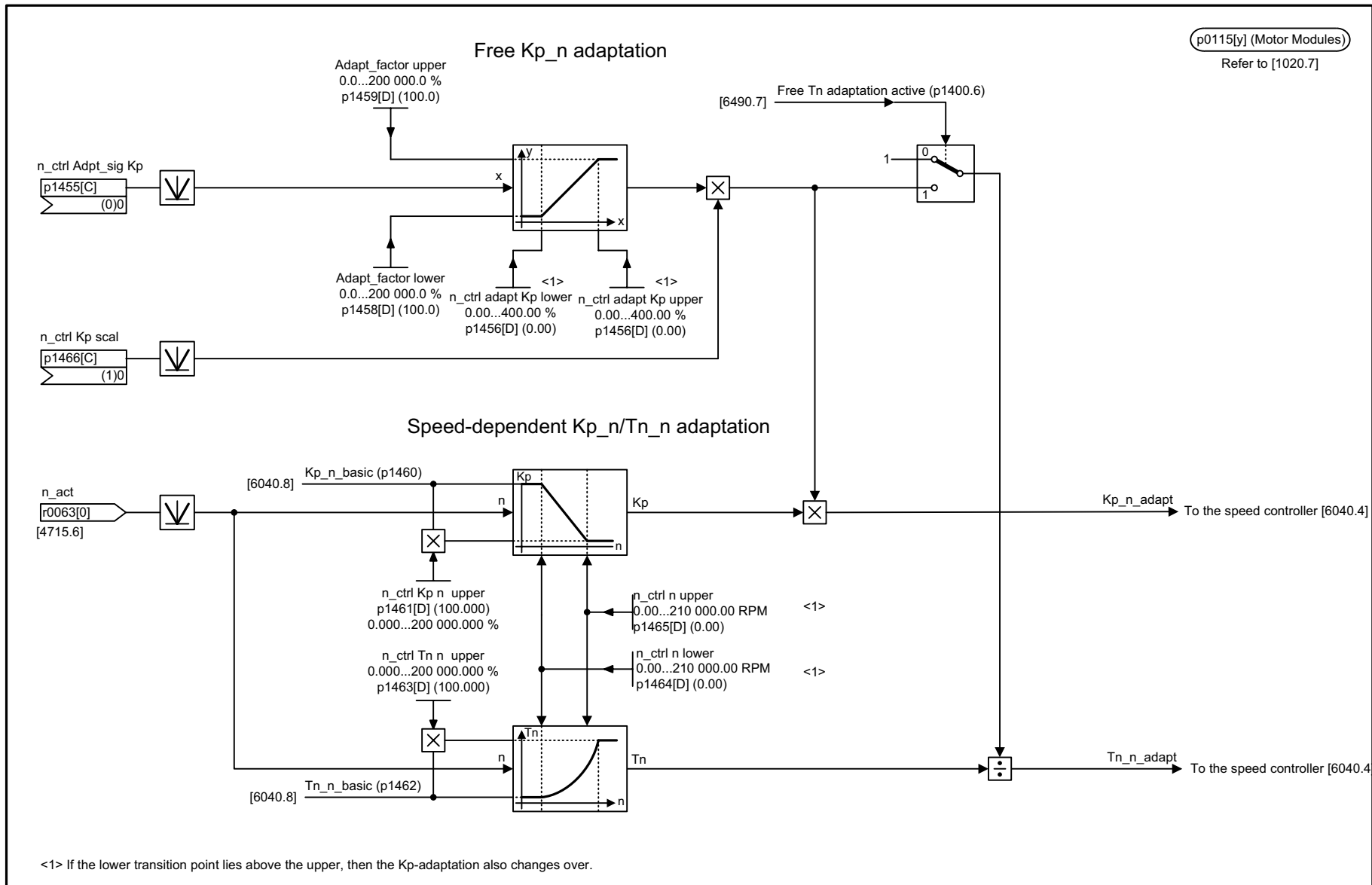
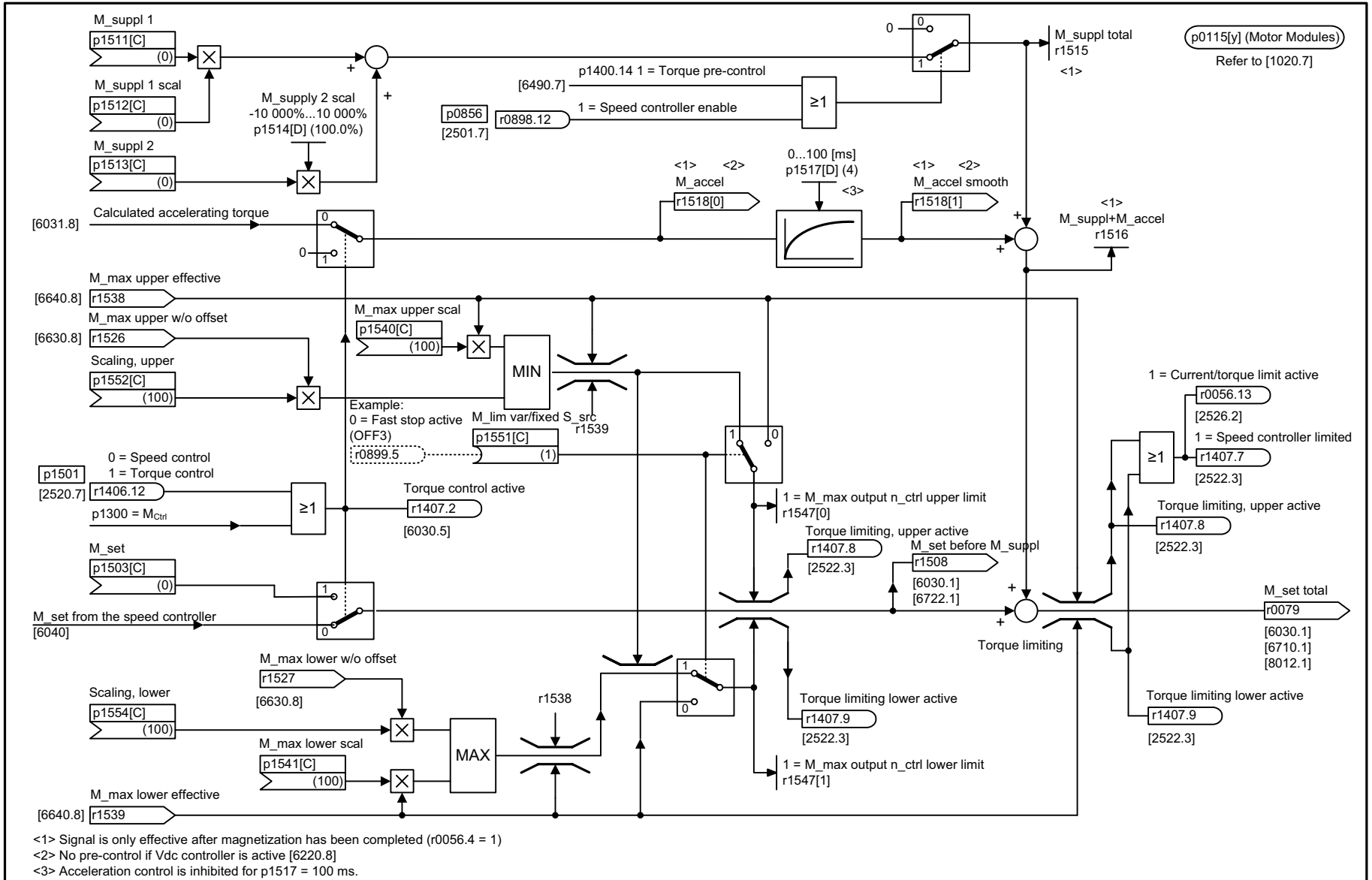


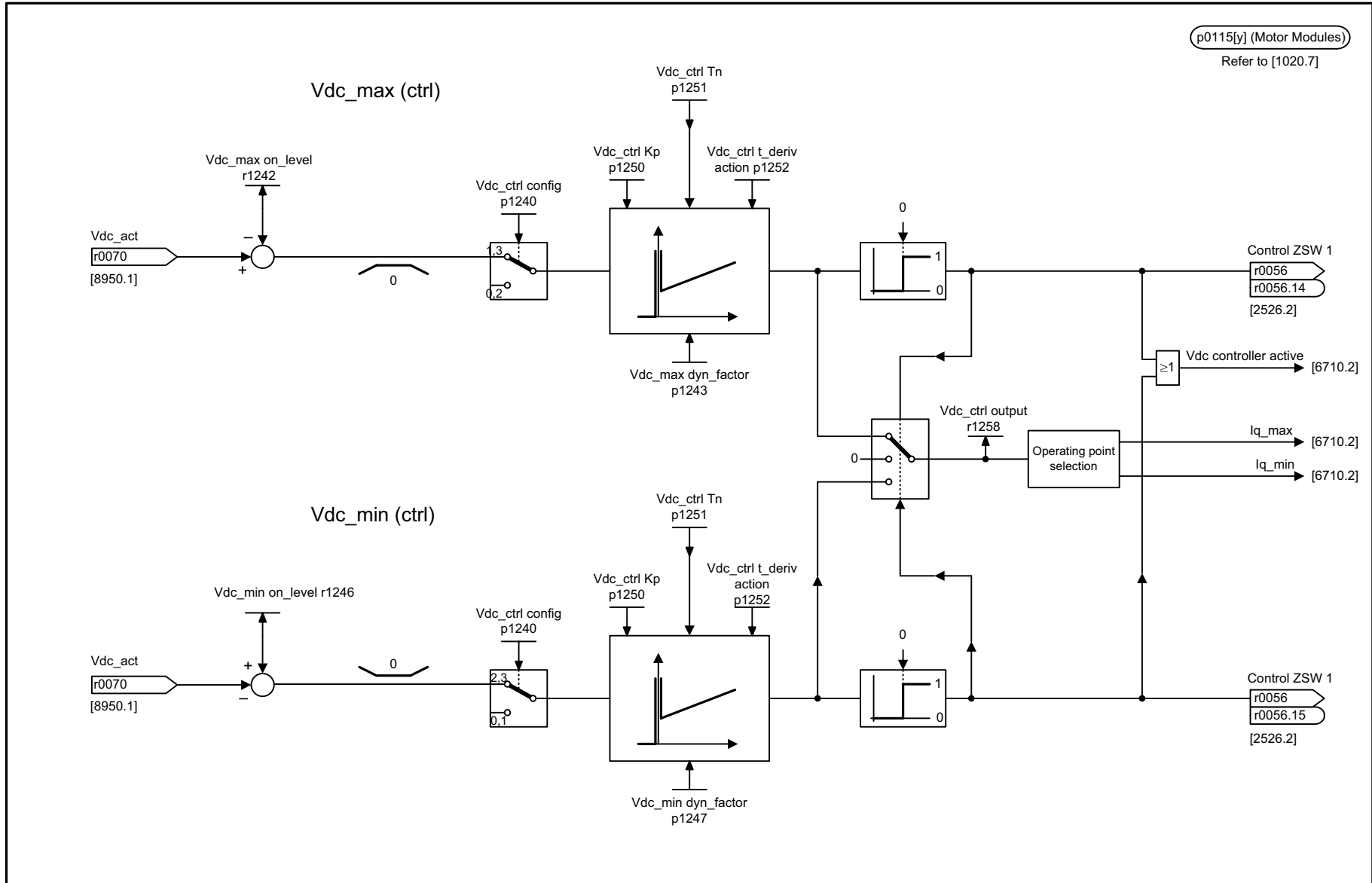
Figure 2-146 6050 – Kp_n/Tn_n adaptation

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6050_01_eng.vsd	Function diagram	
Vector, speed control with/without encoder - Kp_n/Tn_n adaptation					23.03.06 V02.04.00	SINAMICS S	
							- 6050 -

Figure 2-147 6060 – Torque setpoint



1	2	3	4	5	6	7	8
DO: VECTOR					fp_6060_01_eng.vsd	Function diagram	
Vector speed control with encoder - torque setpoint					09.03.06 V02.04.00	SINAMICS S	
							- 6060 -

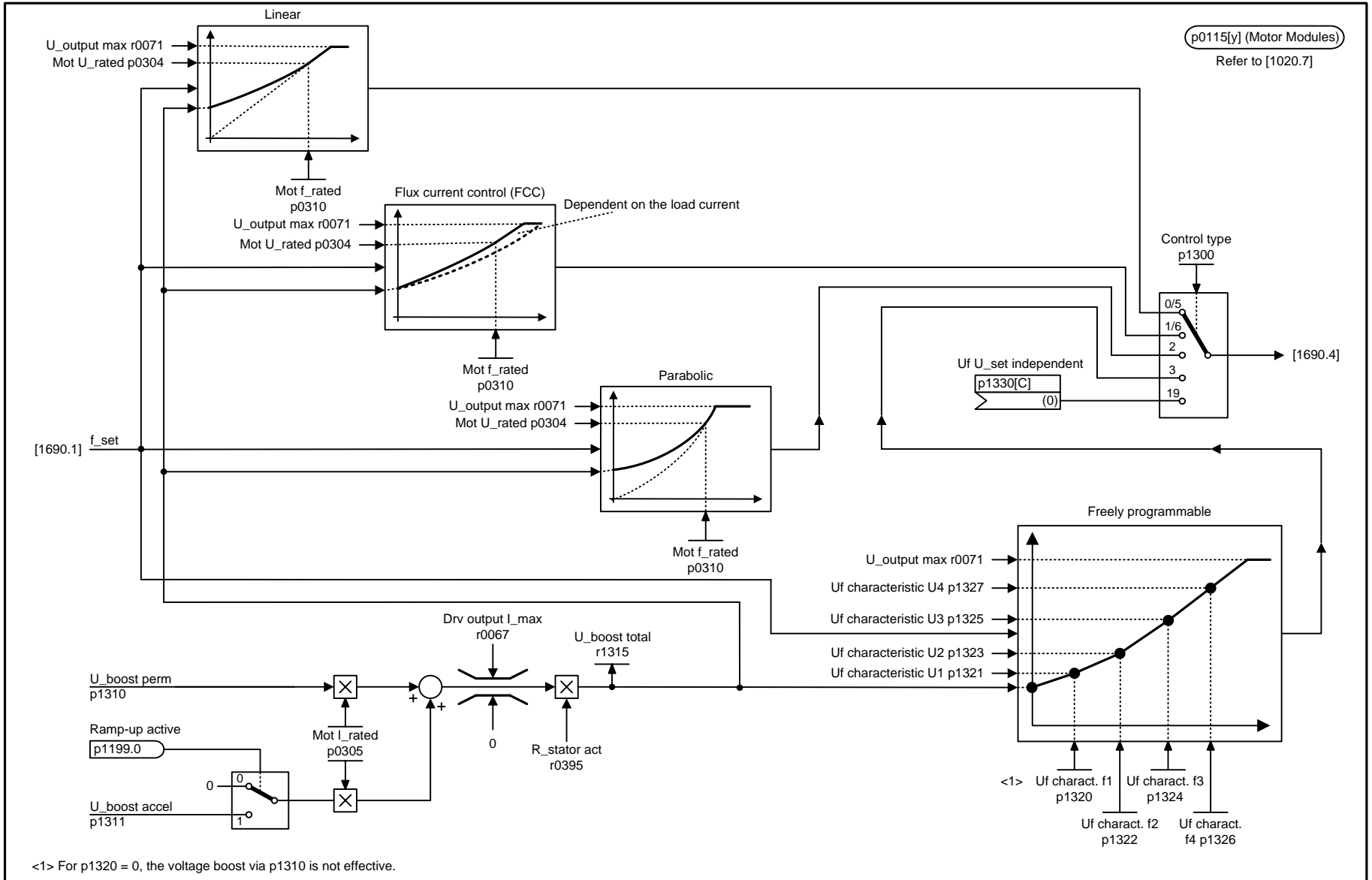


p0115[y] (Motor Modules)
Refer to [1020.7]

Figure 2-148 6220 – Vdc_max controller and Vdc_min controller

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6220_01_eng.vsd	Function diagram	
Vector control - Vdc_max controller and Vdc_min controller					23.03.06 V02.04.00	SINAMICS S	
							- 6220 -

Figure 2-149 6300 – V/f characteristic and voltage boost



Function diagrams
 Vector control

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6300_01_eng.vsd	Function diagram	
Vector U/f control - U/f characteristic and voltage boost					12.01.06 V02.04.00	SINAMICS S	
							- 6300 -

p0115[y] (Motor Modules)
Refer to [1020.7]

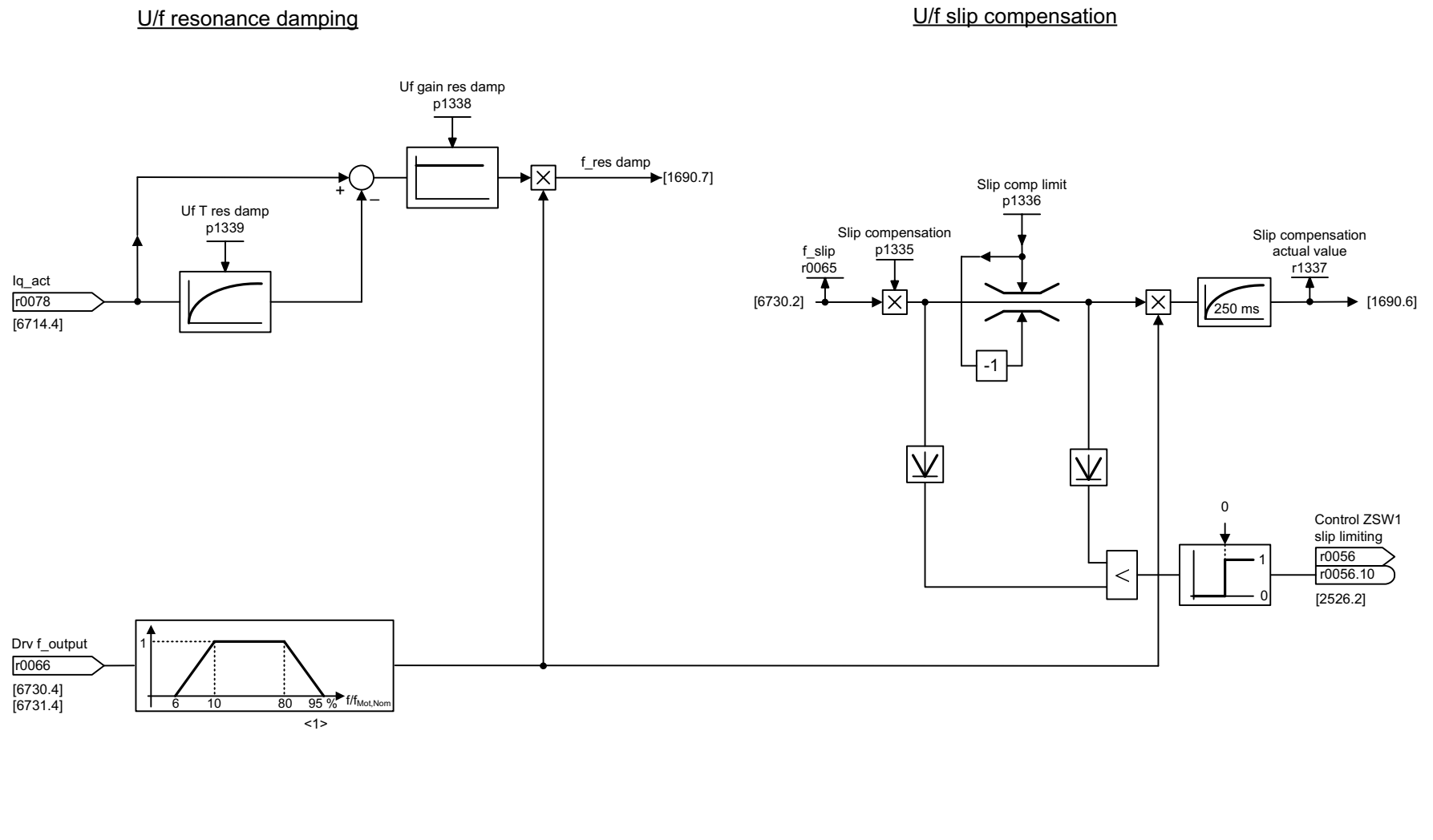
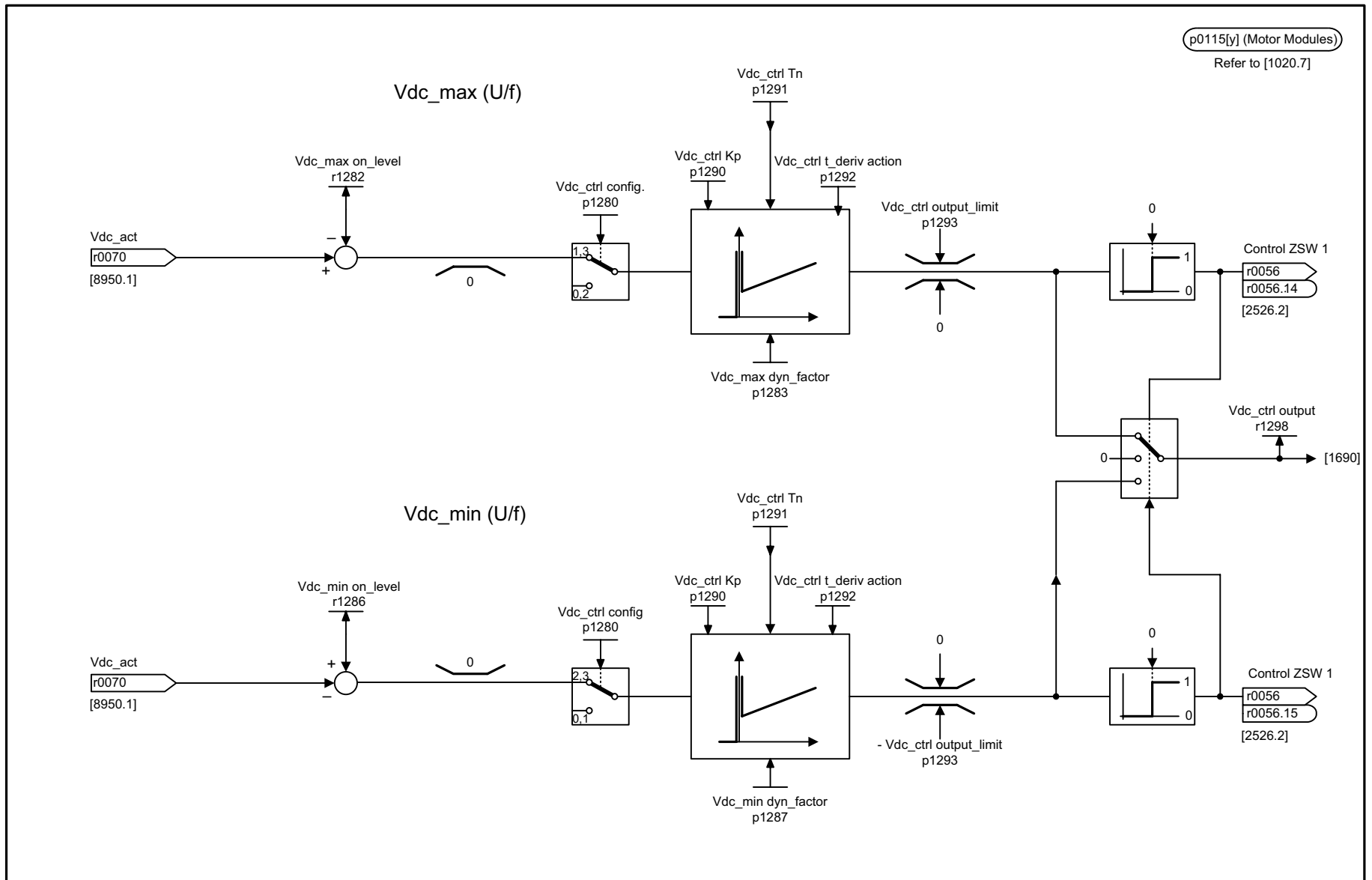


Figure 2-150 6310 – Resonance damping and slip compensation

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6310_01_eng.vsd	Function diagram	
Vector U/f control - resonance damping and slip compensation					23.03.06 V02.04.00	SINAMICS S	
							- 6310 -



p0115[y] (Motor Modules)
Refer to [1020.7]

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6320_01_eng.vsd	Function diagram	
Vector U/f control - Vdc_max controller and Vdc_min controller					23.03.06 V02.04.00	SINAMICS S	
							- 6320 -

Figure 2-151 6320 – Vdc_max controller and Vdc_min controller

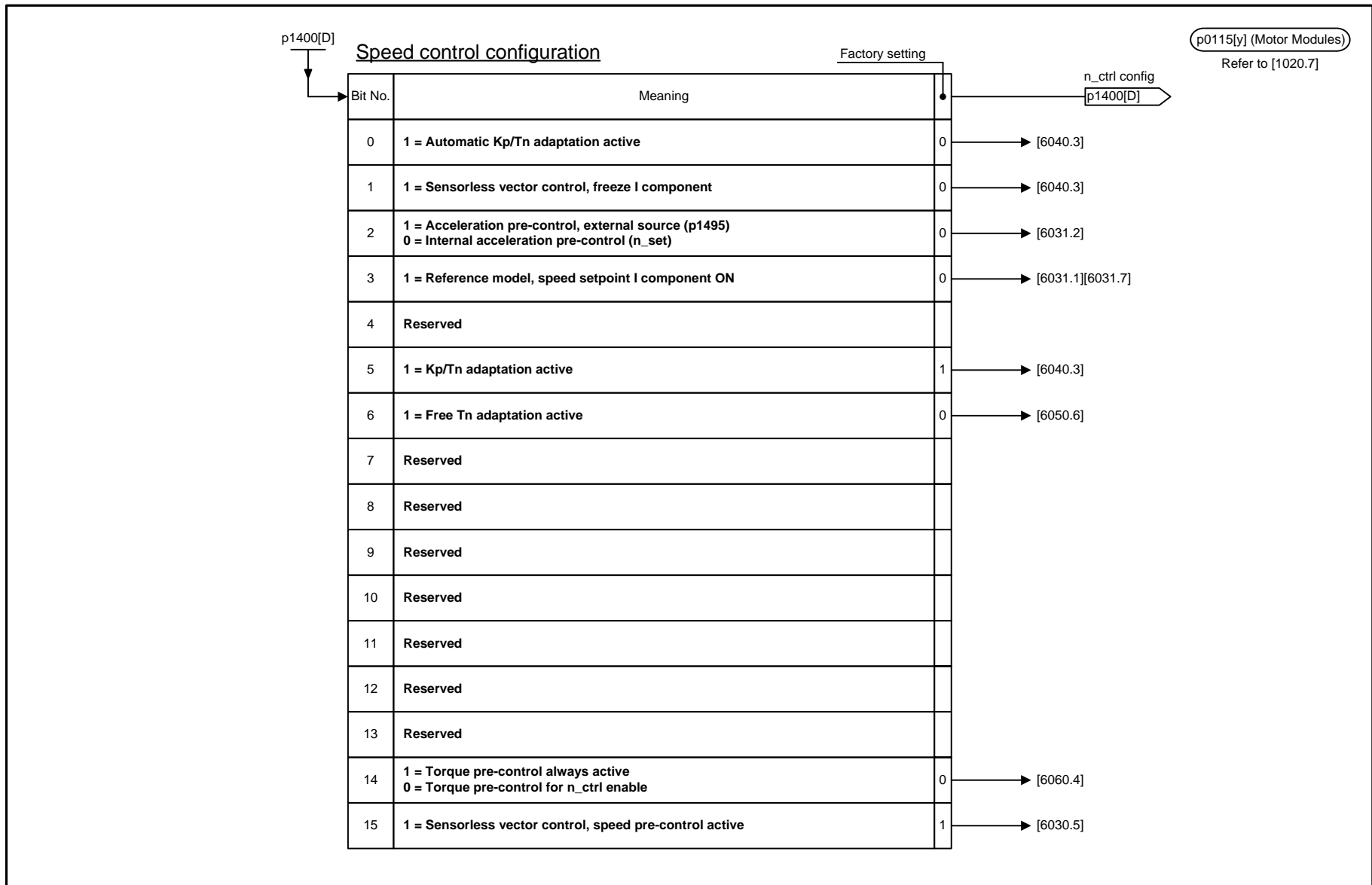


Figure 2-152 6490 – Speed control configuration

2-1084

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6490_01_eng.vsd	Function diagram	
Vector open-loop - closed-loop control status words - speed control configuration					29.07.05 V02.04.00	SINAMICS S	
							- 6490 -

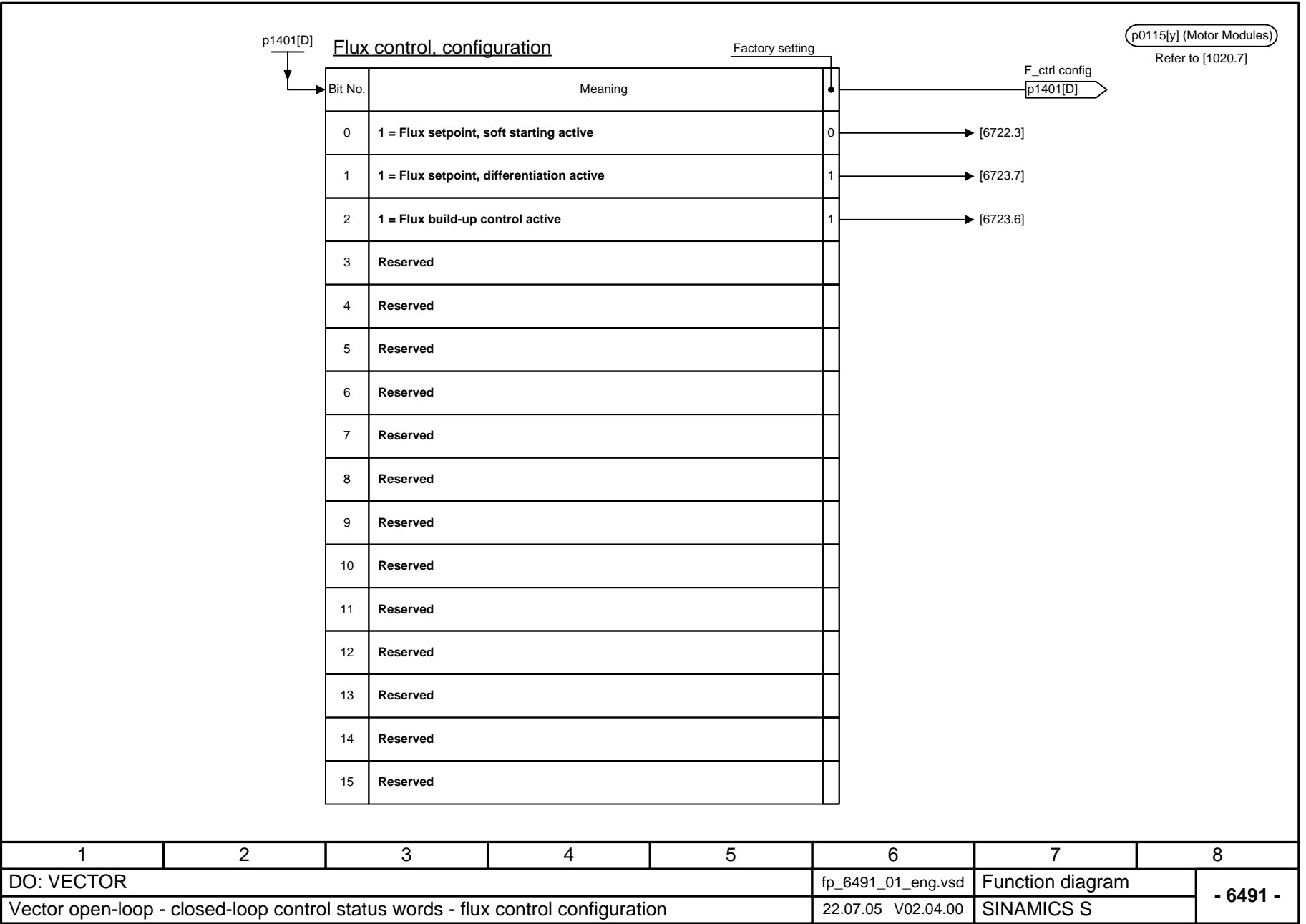


Figure 2-153 6491 – Flux control configuration

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6491_01_eng.vsd	Function diagram	
Vector open-loop - closed-loop control status words - flux control configuration					22.07.05 V02.04.00	SINAMICS S	
							- 6491 -

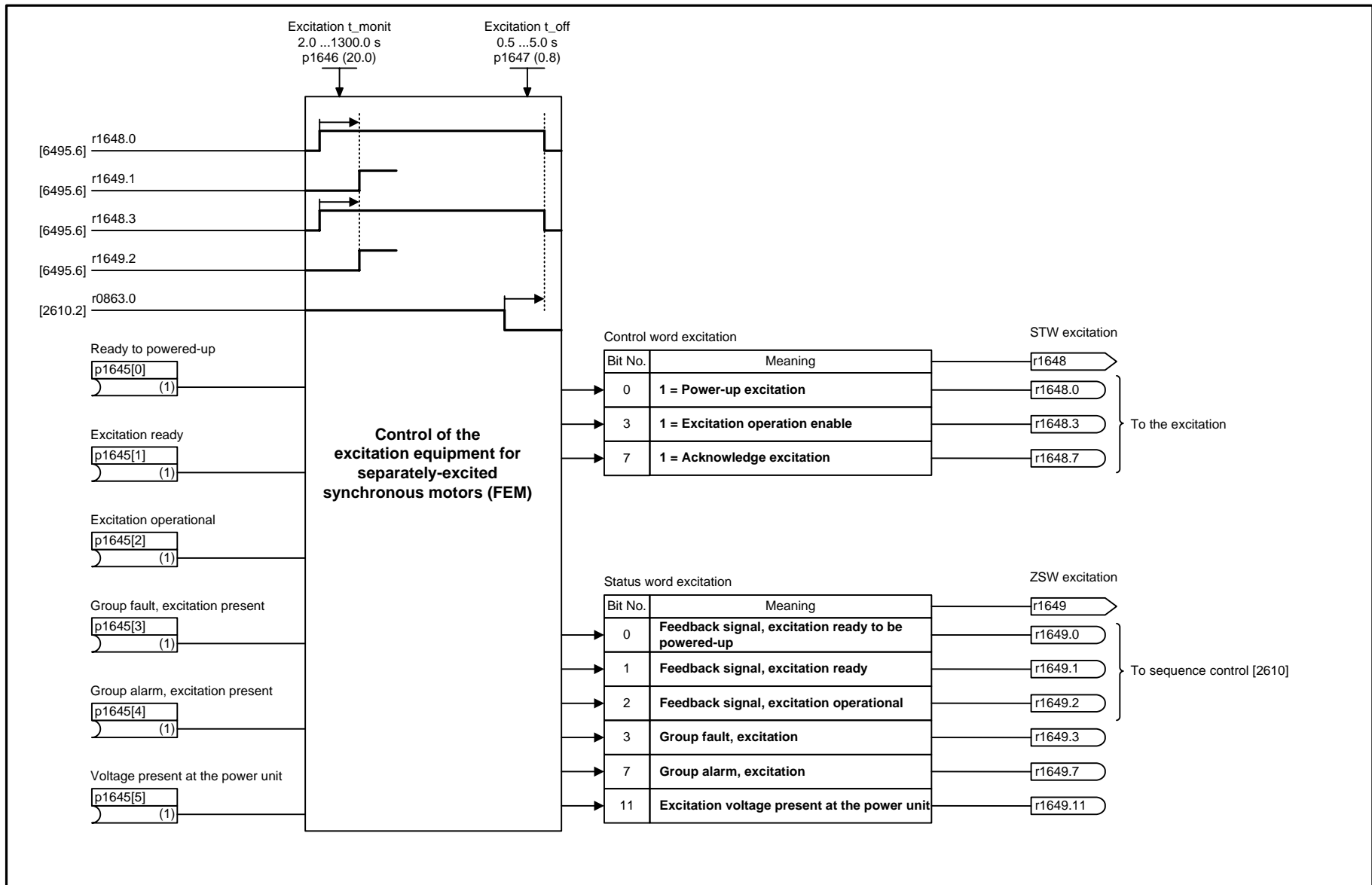
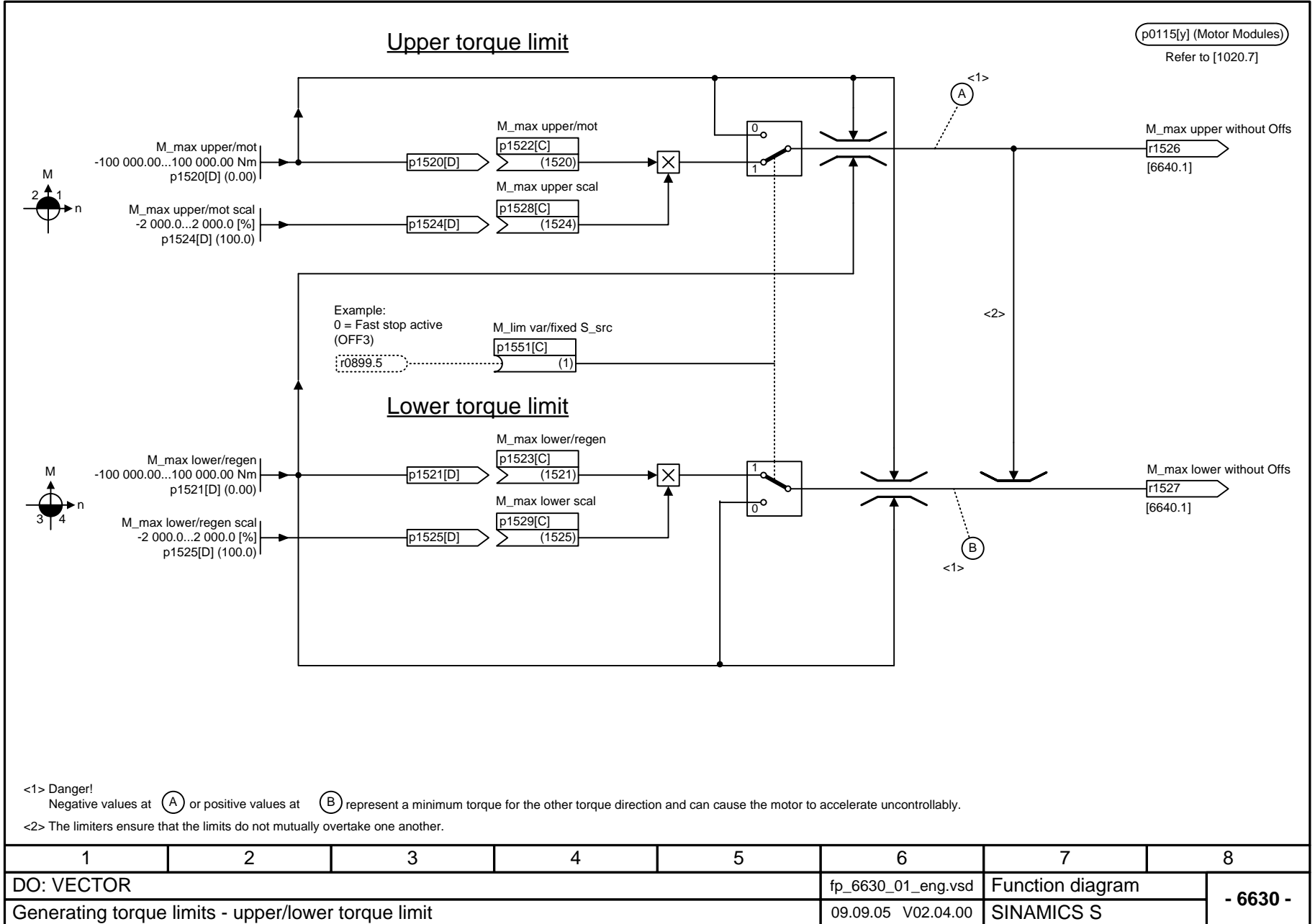


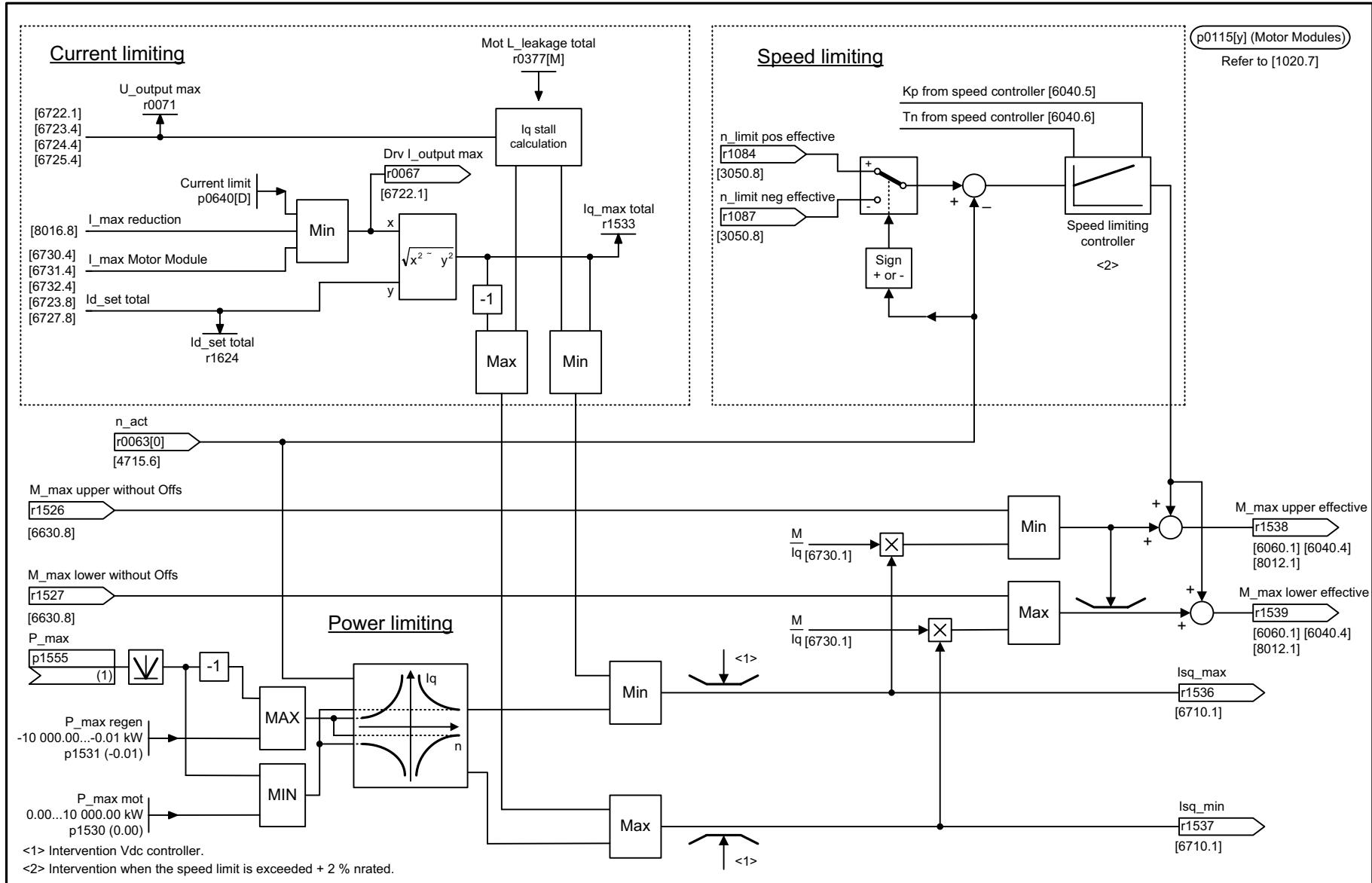
Figure 2-154 6495 – Excitation (FEM, p0300 = 5)

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6495_01_eng.vsd	Function diagram	
Vector closed-loop control/status words - excitation (FEM, p0300 = 5)					14.02.06 V02.04.00	SINAMICS S	
							- 6495 -

Figure 2-155 6630 – Upper/lower torque limit



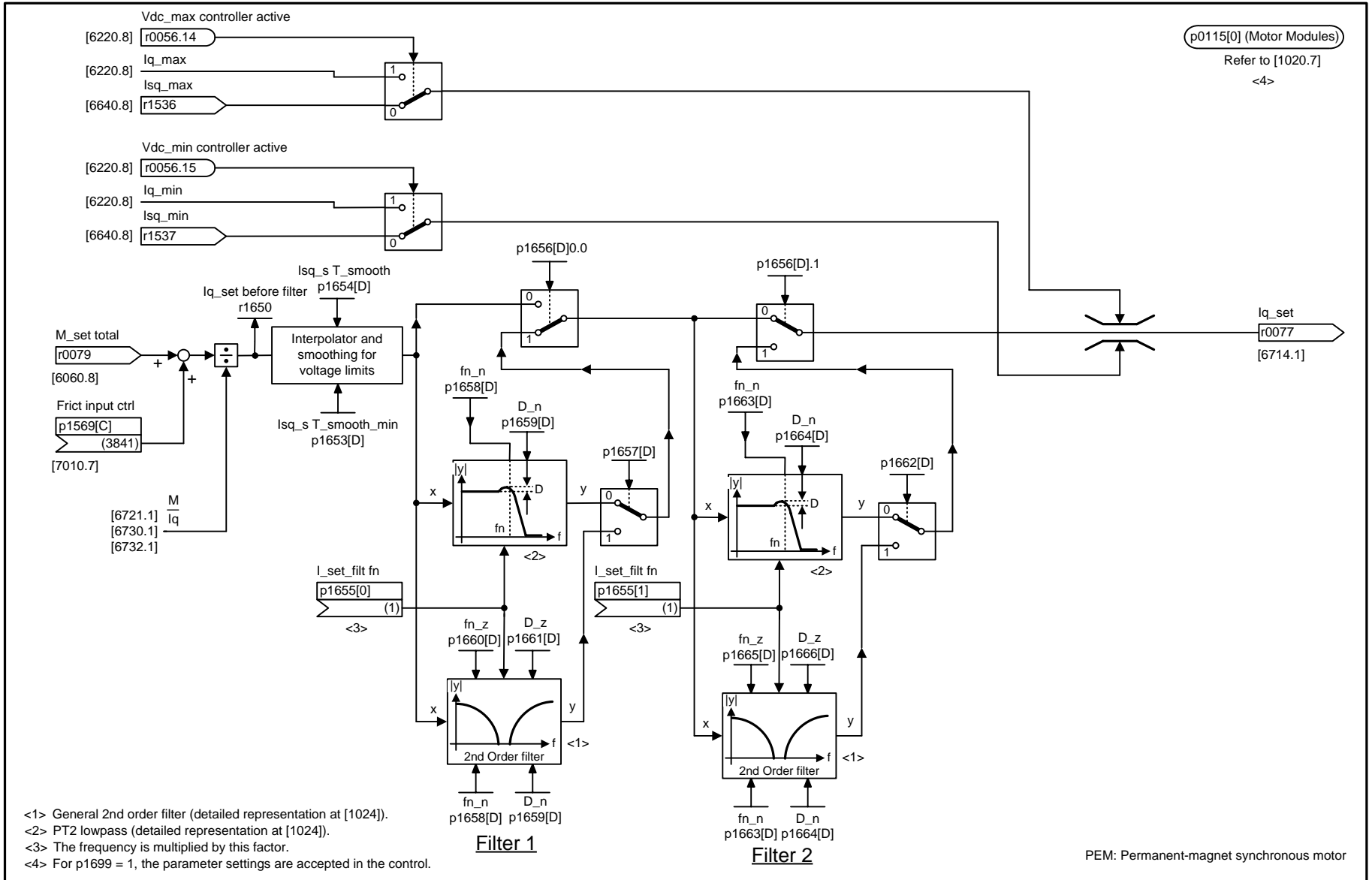
1	2	3	4	5	6	7	8
DO: VECTOR					fp_6630_01_eng.vsd	Function diagram	
Generating torque limits - upper/lower torque limit					09.09.05 V02.04.00	SINAMICS S	
							- 6630 -



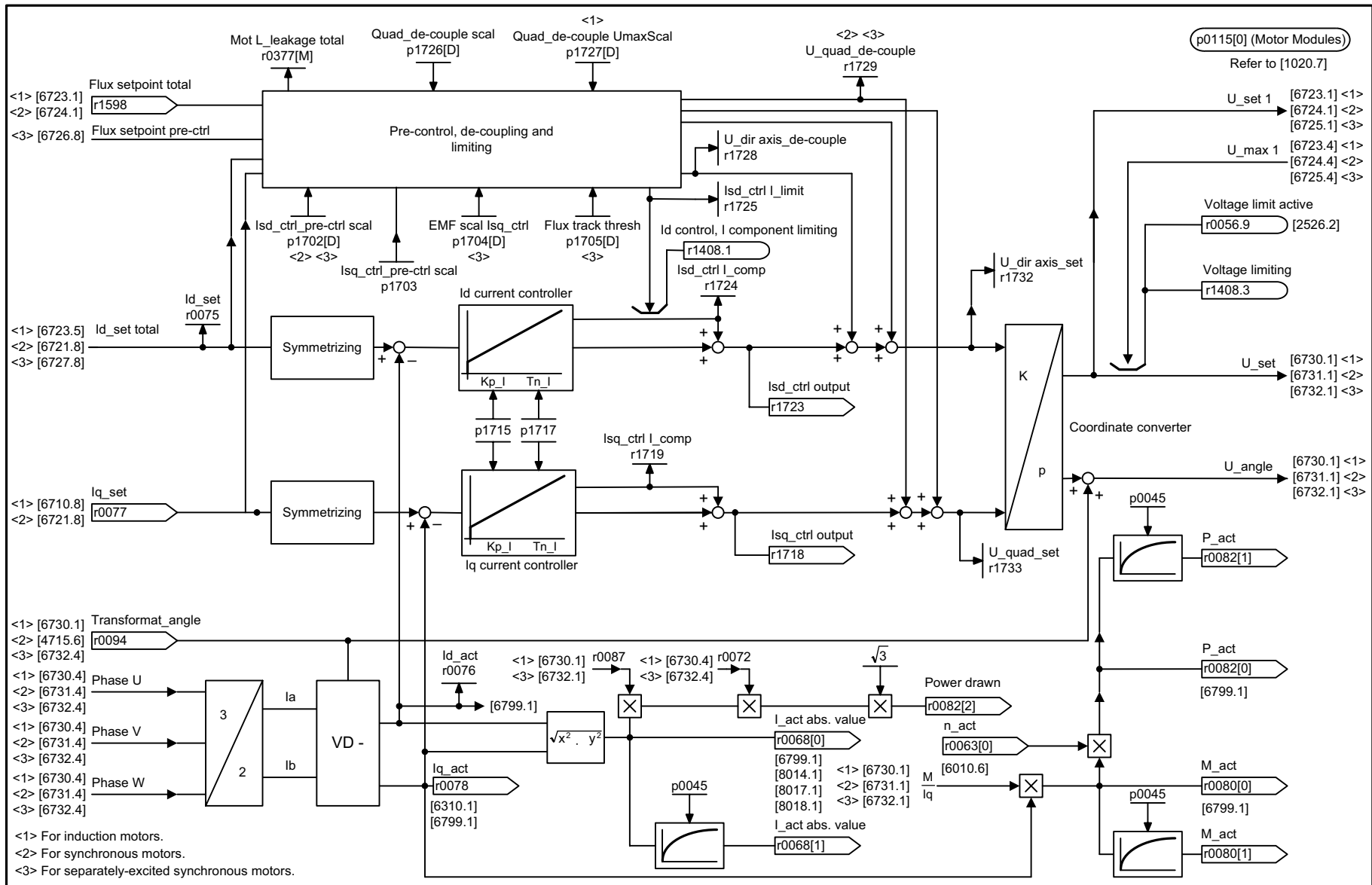
1	2	3	4	5	6	7	8
DO: VECTOR					fp_6640_01_eng.vsd	Function diagram	
Generating torque limits - current/power/torque limits					16.03.06 V02.04.00	SINAMICS S	
							- 6640 -

Figure 2-156 6640 – Current/power/torque limits

Figure 2-157 6710 – Current setpoint filter



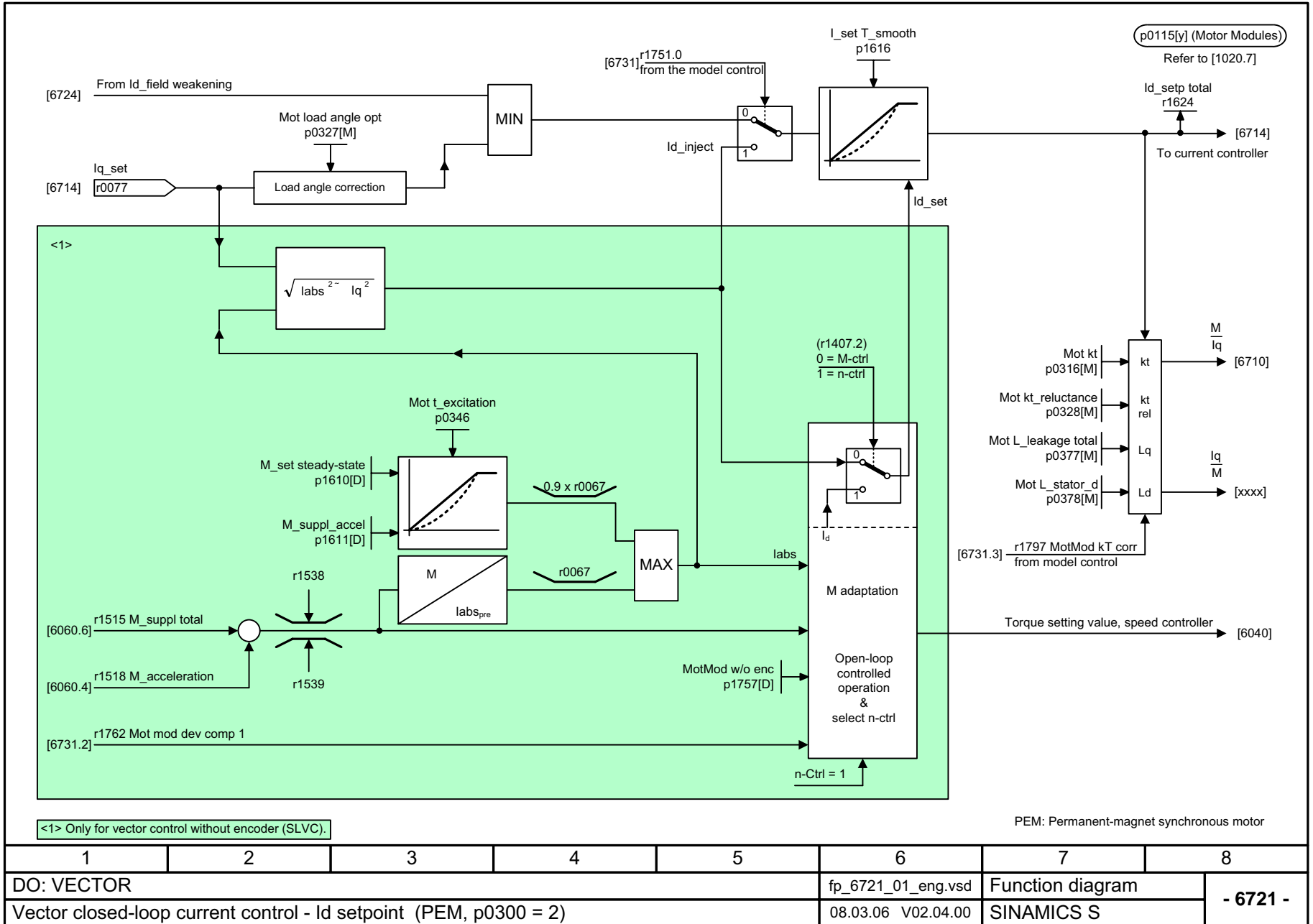
1	2	3	4	5	6	7	8
DO: VECTOR					fp_6710_01_eng.vsd	Function diagram	
Vector current control - current setpoint filter					13.03.06 V02.04.00	SINAMICS S	
							- 6710 -

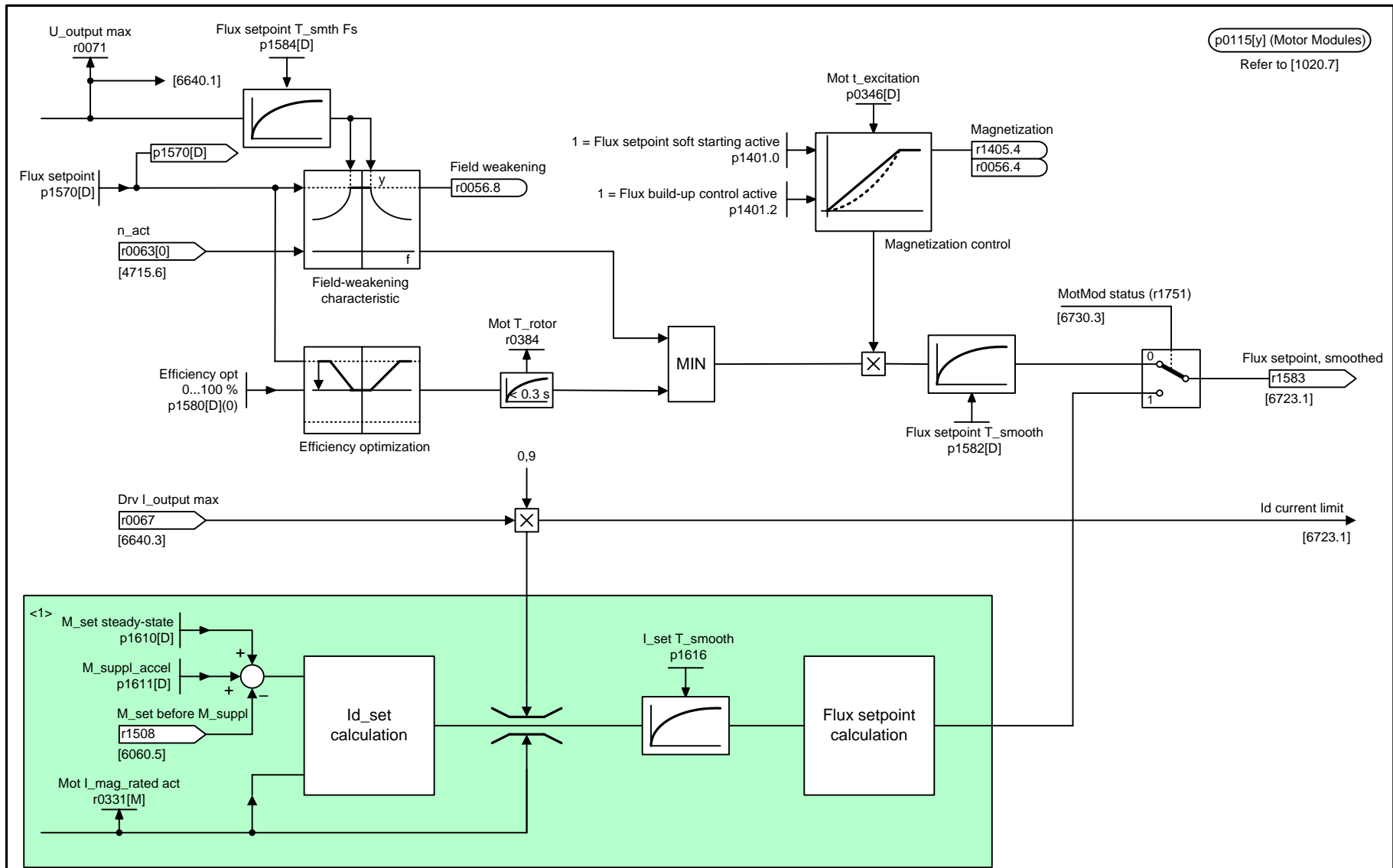


1	2	3	4	5	6	7	8
DO: VECTOR					fp_6714_01_eng.vsd	Function diagram	
Vector current control - Iq and Id controllers					16.03.06 V02.04.00	SINAMICS S	
							- 6714 -

Figure 2-158 6714 – Iq and Id controllers

Figure 2-159 6721 – Id setpoint (PEM, p0300 = 2)



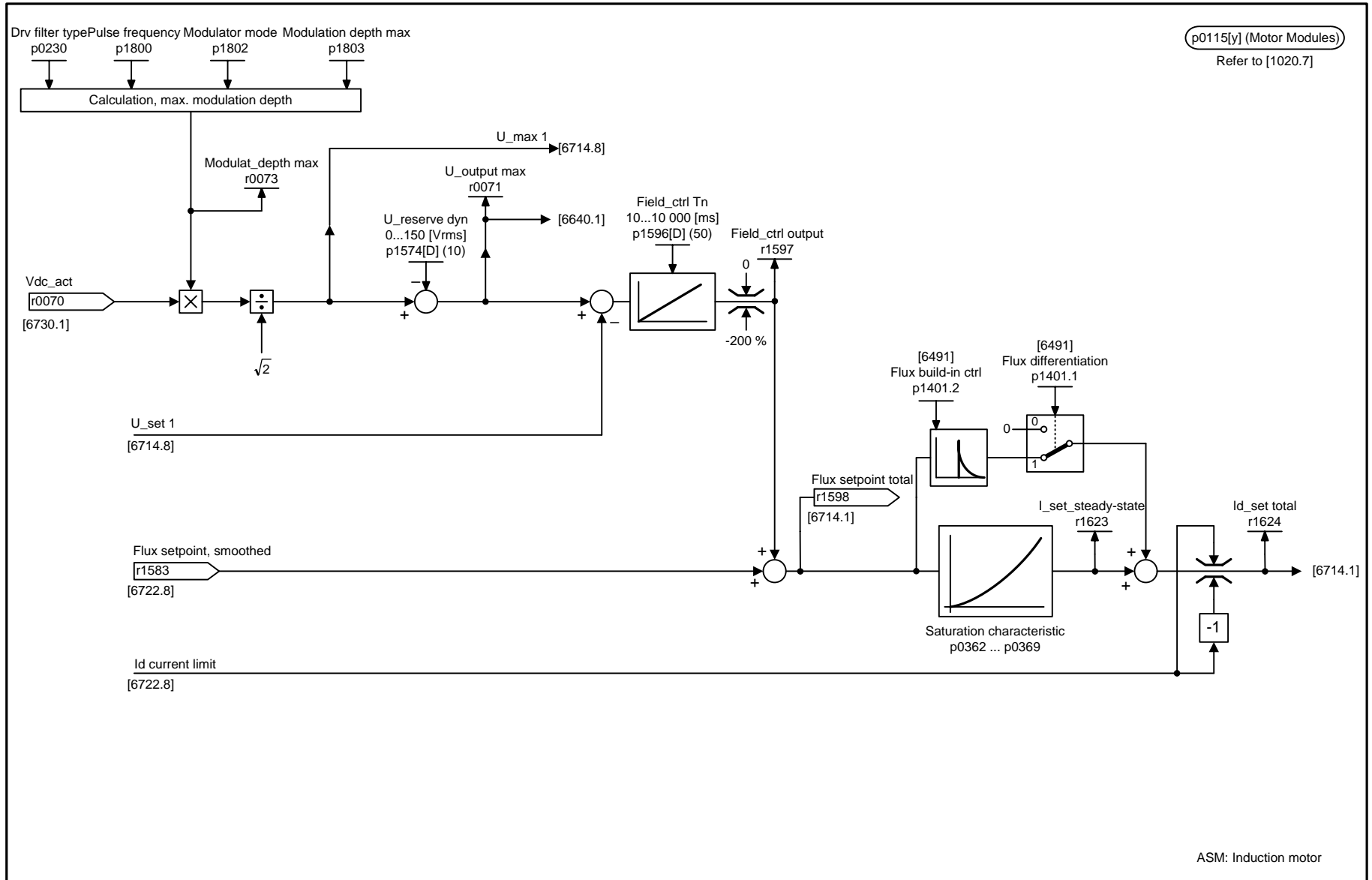


<1> Only for vector control without encoder (SLVC). ASM: Induction motor

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6722_01_eng.vsd	Function diagram	
Vector closed-loop current control - field weakening charact., Id setpoint (ASM, p0300 = 1)					16.03.06 V02.04.00	SINAMICS S	

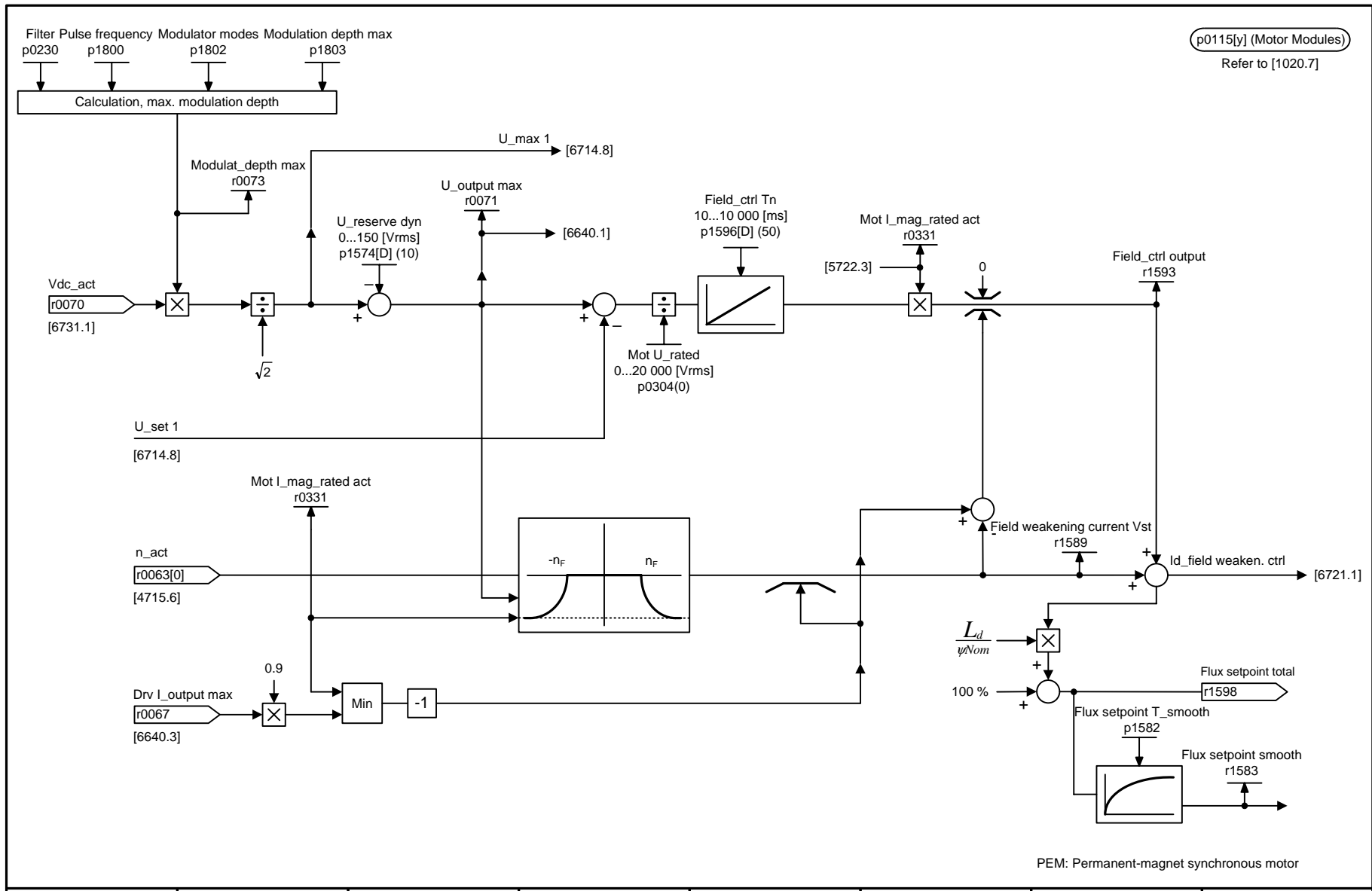
Figure 2-160 6722 – Field weakening characteristic, Id setpoint (ASM, p0300 = 1)

Figure 2-161 6723 – Field weakening characteristic, flux controller (ASM, p0300 = 1)



p0115[y] (Motor Modules)
Refer to [1020.7]

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6723_01_eng.vsd	Function diagram	
Vector closed-loop current control - field weakening charact., flux controller (ASM, p0300 = 1)					07.02.06 V02.04.00	SINAMICS S	
							- 6723 -

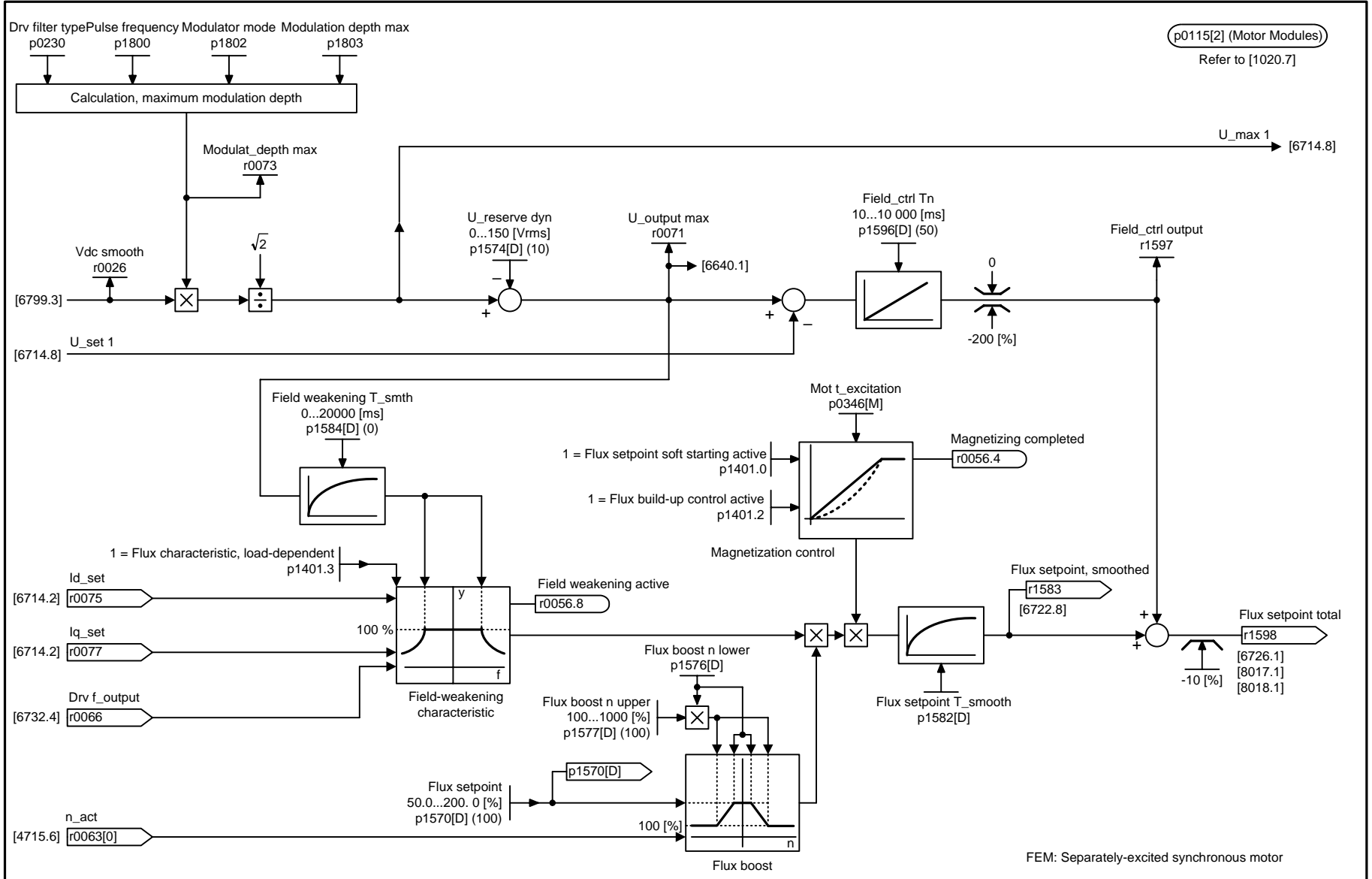


1	2	3	4	5	6	7	8
DO: VECTOR					fp_6724_01_eng.vsd	Function diagram	
Vector closed-loop current control - field weakening controller (PEM, p0300 = 2)					16.03.06 V02.04.00	SINAMICS S	
							- 6724 -

Figure 2-162 6724 – Field weakening controller (PEM, p0300 = 2)

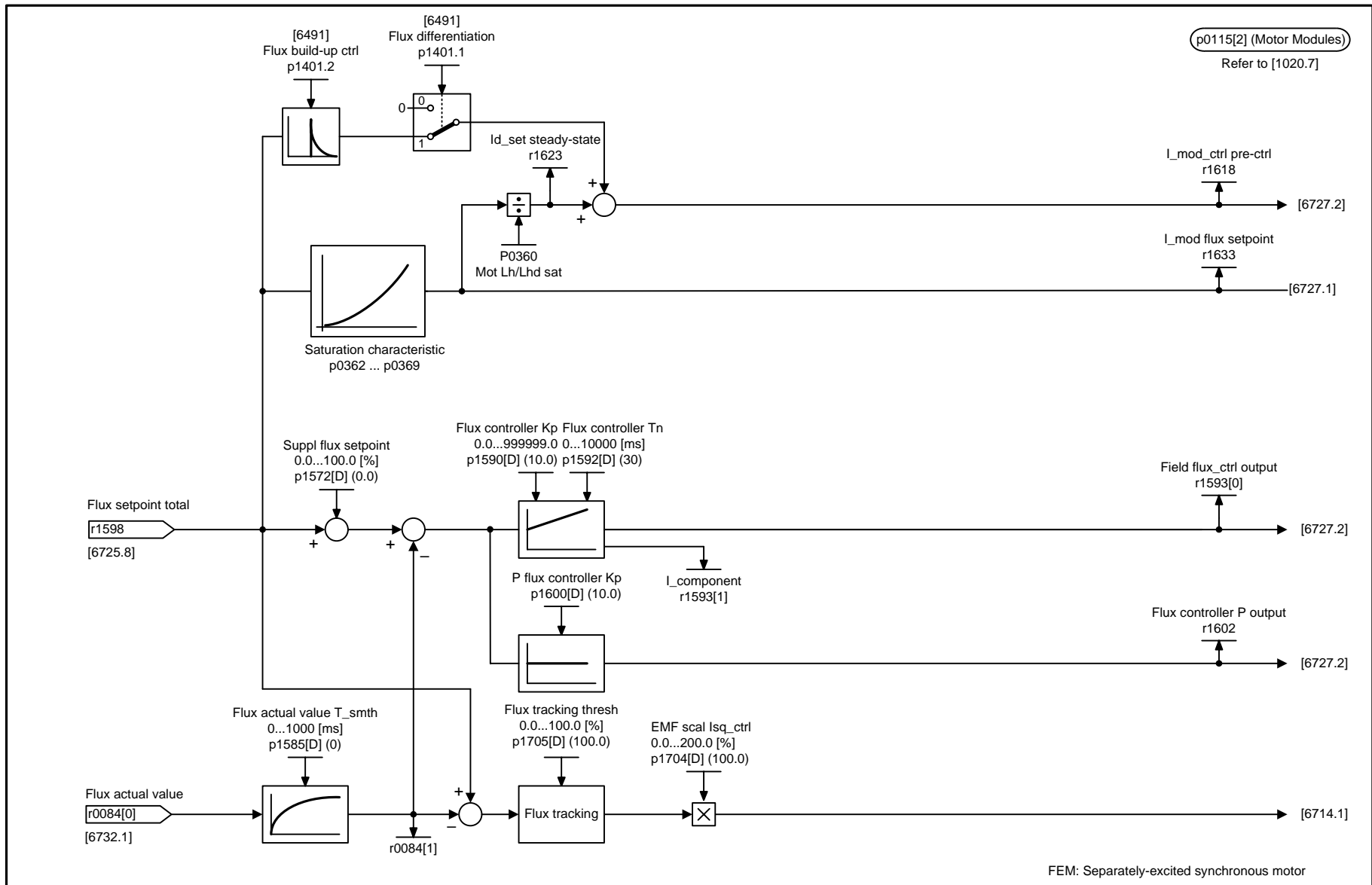
2-1094

Figure 2-163 6725 – Flux setpoint, field weakening controller (FEM, p0300 = 5)



FEM: Separately-excited synchronous motor

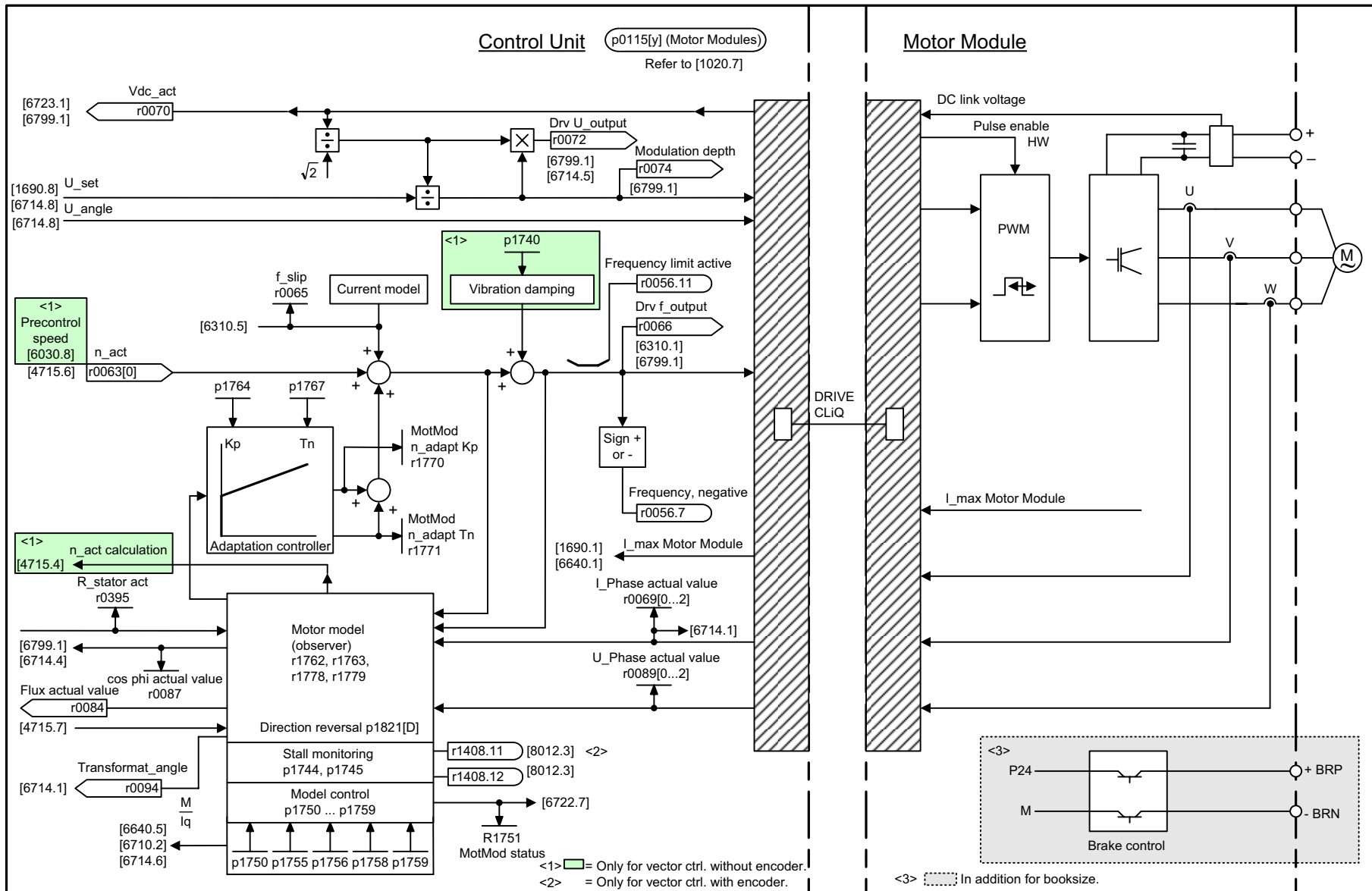
1	2	3	4	5	6	7	8
DO: VECTOR					fp_6725_01_eng.vsd	Function diagram	
Vector closed-loop current control - flux setpoint, field weakening controller (FEM, p0300 = 5)					16.03.06 V02.04.00	SINAMICS S	
							- 6725 -



FEM: Separately-excited synchronous motor

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6726_01_eng.vsd	Function diagram	
Vector closed-loop current control - field weakening controller, flux controller (FEM, p0300 = 5)					25.01.06 V02.04.00	SINAMICS S	
							- 6726 -

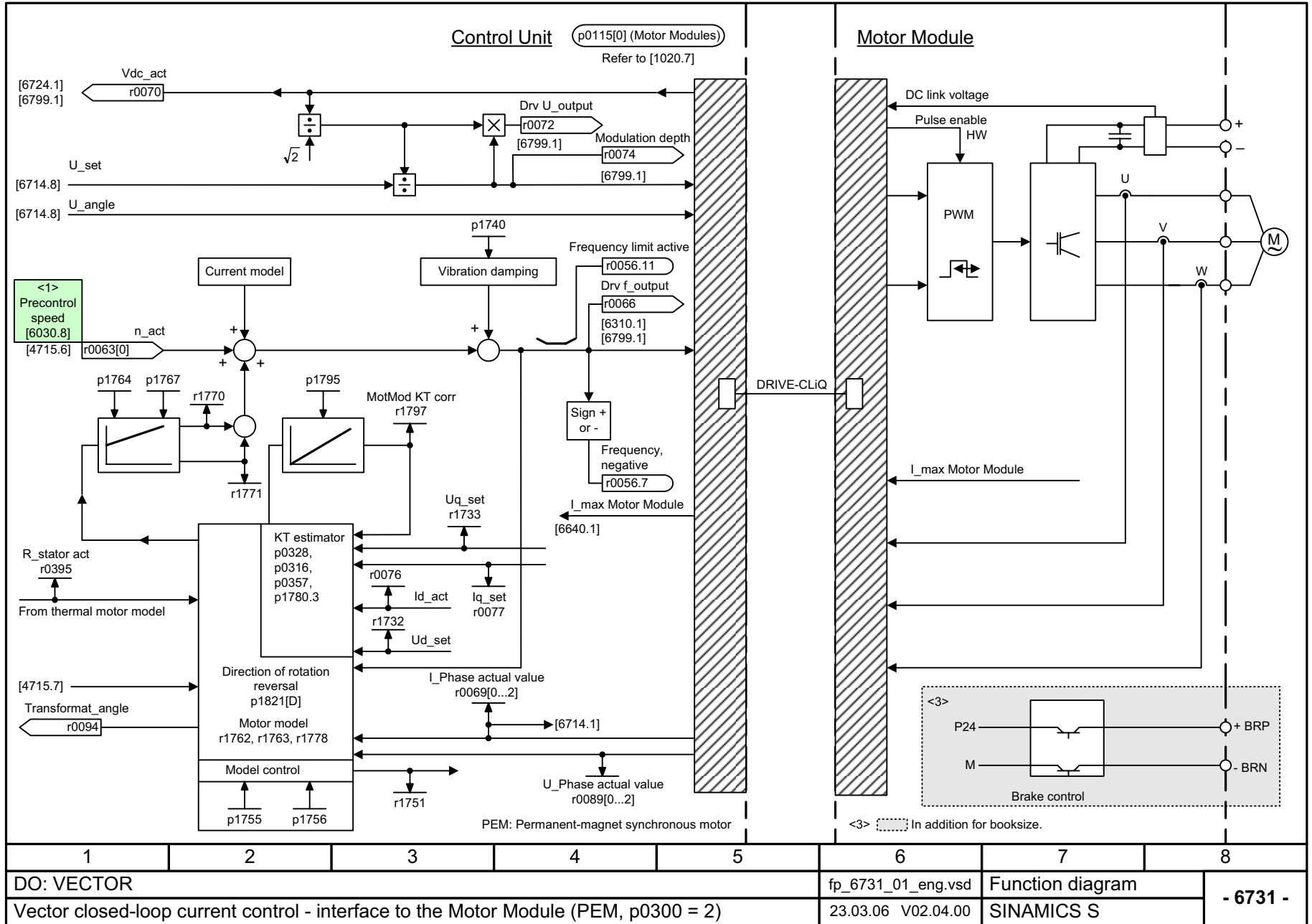
Figure 2-164 6726 – Field weakening controller, flux controller (FEM, p0300 = 5)



1	2	3	4	5	6	7	8
DO: VECTOR					fp_6730_01_eng.vsd	Function diagram	
Vector closed-loop current control - interface to the Motor Module (ASM, p0300 = 1)					23.03.06 V02.04.00	SINAMICS S	
							- 6730 -

Figure 2-166 6730 – Interface to the motor module (ASM, p0300 = 1)

Figure 2-167 6731 – Interface to the motor module (PEM, p0300 = 2)



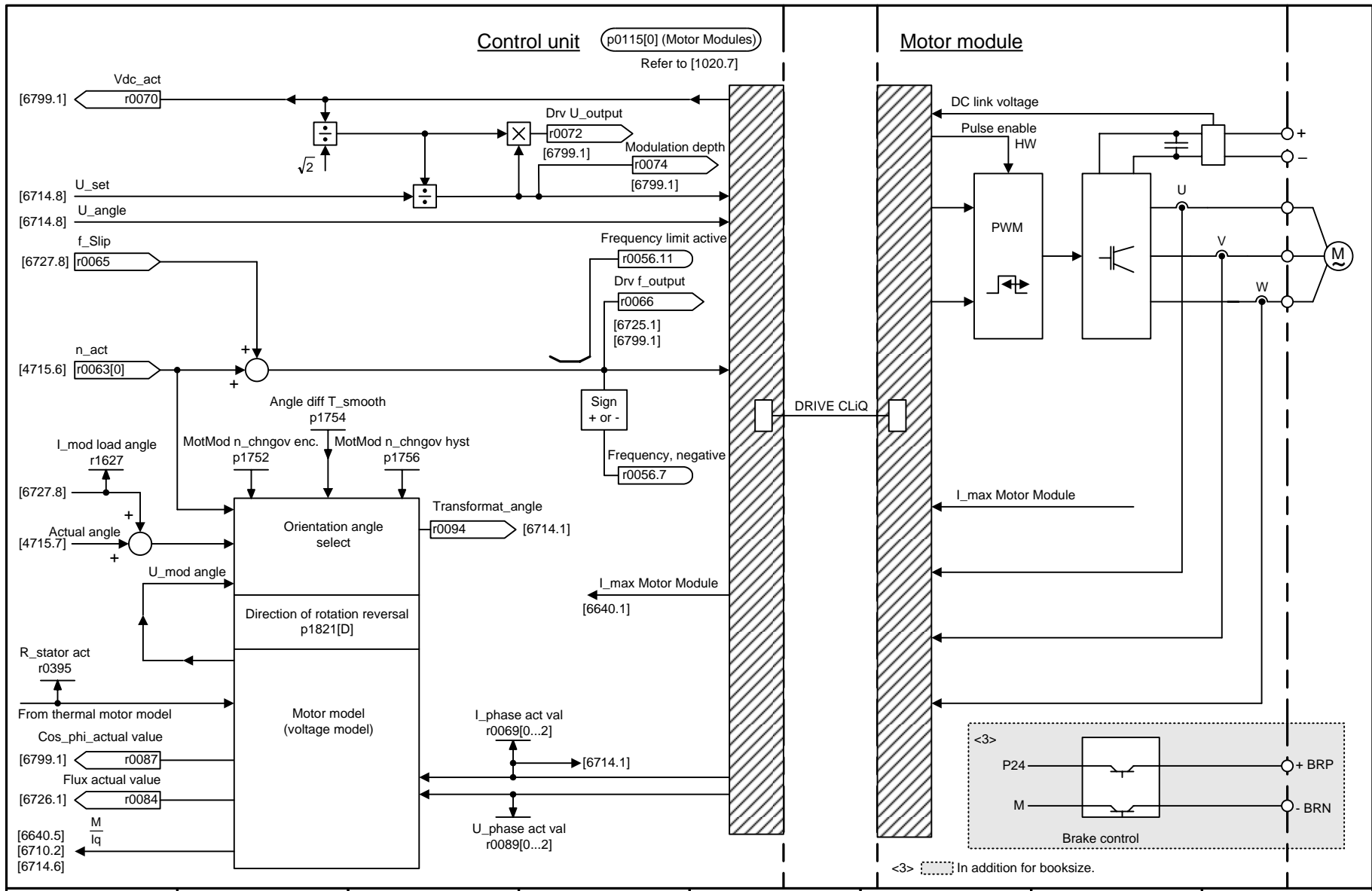


Figure 2-168 6732 – Interface to the motor module (FEM, p0300 = 5)

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6732_01_eng.vsd	Function diagram	
Vector closed-loop current control - interface to the Motor Module (FEM, p0300 = 5)					16.03.06 V02.04.00	SINAMICS S	
							- 6732 -

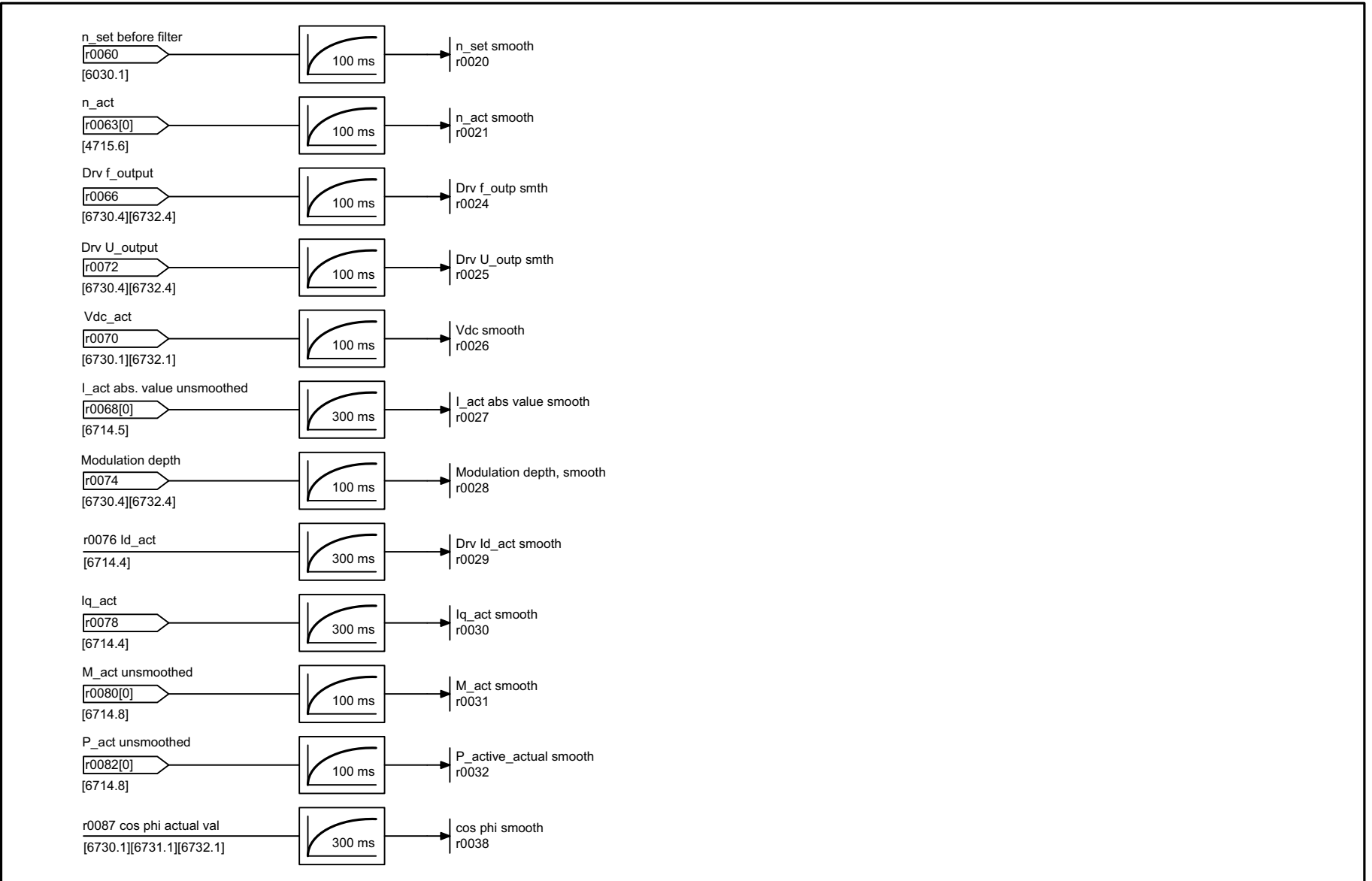


Figure 2-169 – Display signals

1	2	3	4	5	6	7	8
DO: VECTOR					fp_6799_01_eng.vsd	Function diagram	
Vector current control – display signals					23.03.06 V02.04.00	SINAMICS S	
							- 6799 -

2.20 Technology functions

Function diagrams

7008 – kT estimator	2-1103
7010 – Friction characteristic	2-1104
7012 – Advanced Positioning Control (APC, r0108.7 = 1))	2-1105
7014 – External armature short circuit (EASC, p0300 = 2xx or 4xx)	2-1106
7015 – Internal voltage protection (IVP, p0300 = 2xx or 4xx)	2-1107
7020 – Synchronization	2-1108

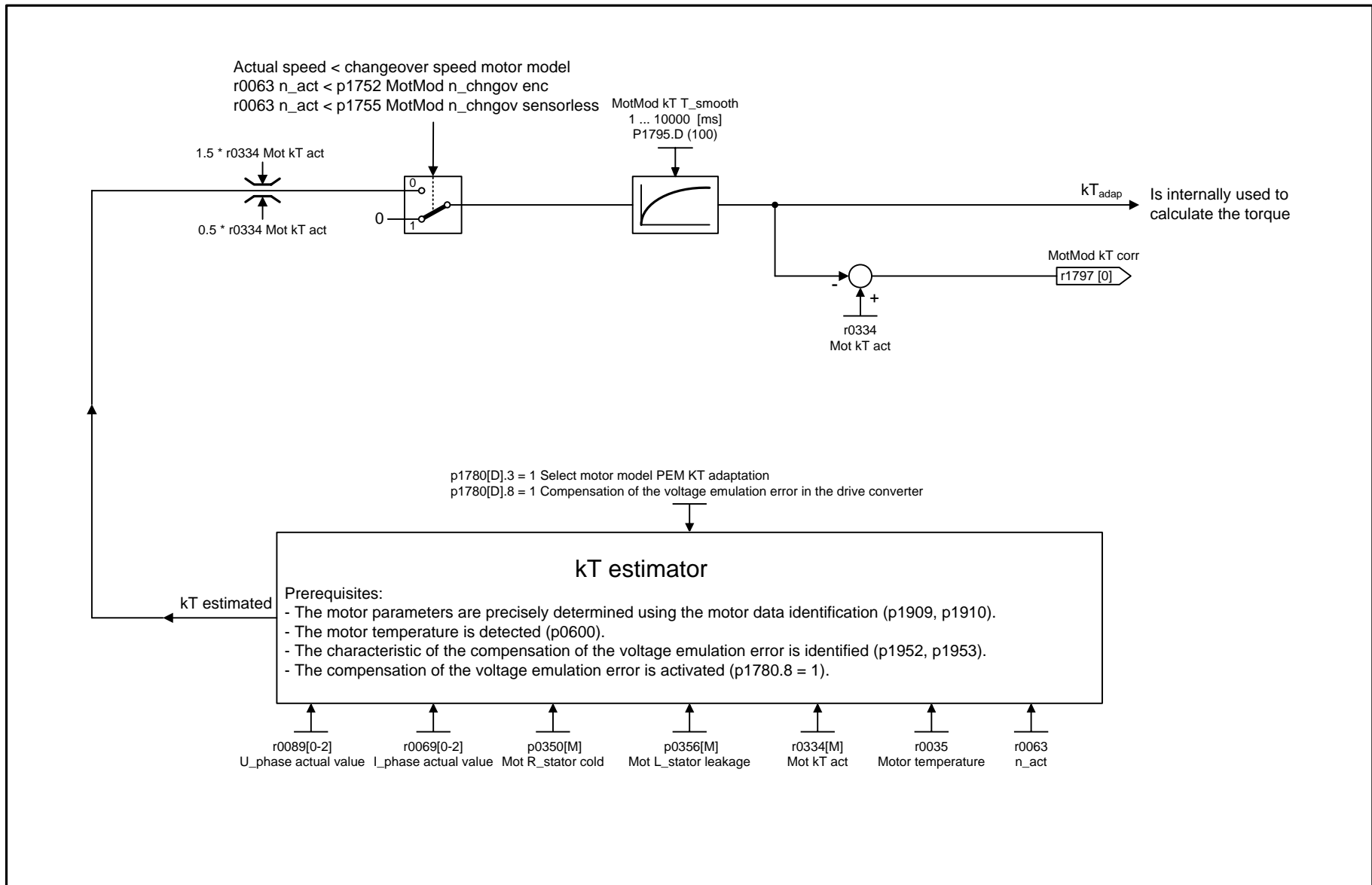


Figure 2-170 7008 – kT estimator

1	2	3	4	5	6	7	8
DO: SERVO					fp_7008_01_eng.vsd	Function diagram	
Technology functions – kT estimator					16.02.06 V02.04.00	SINAMICS S	
							- 7008 -

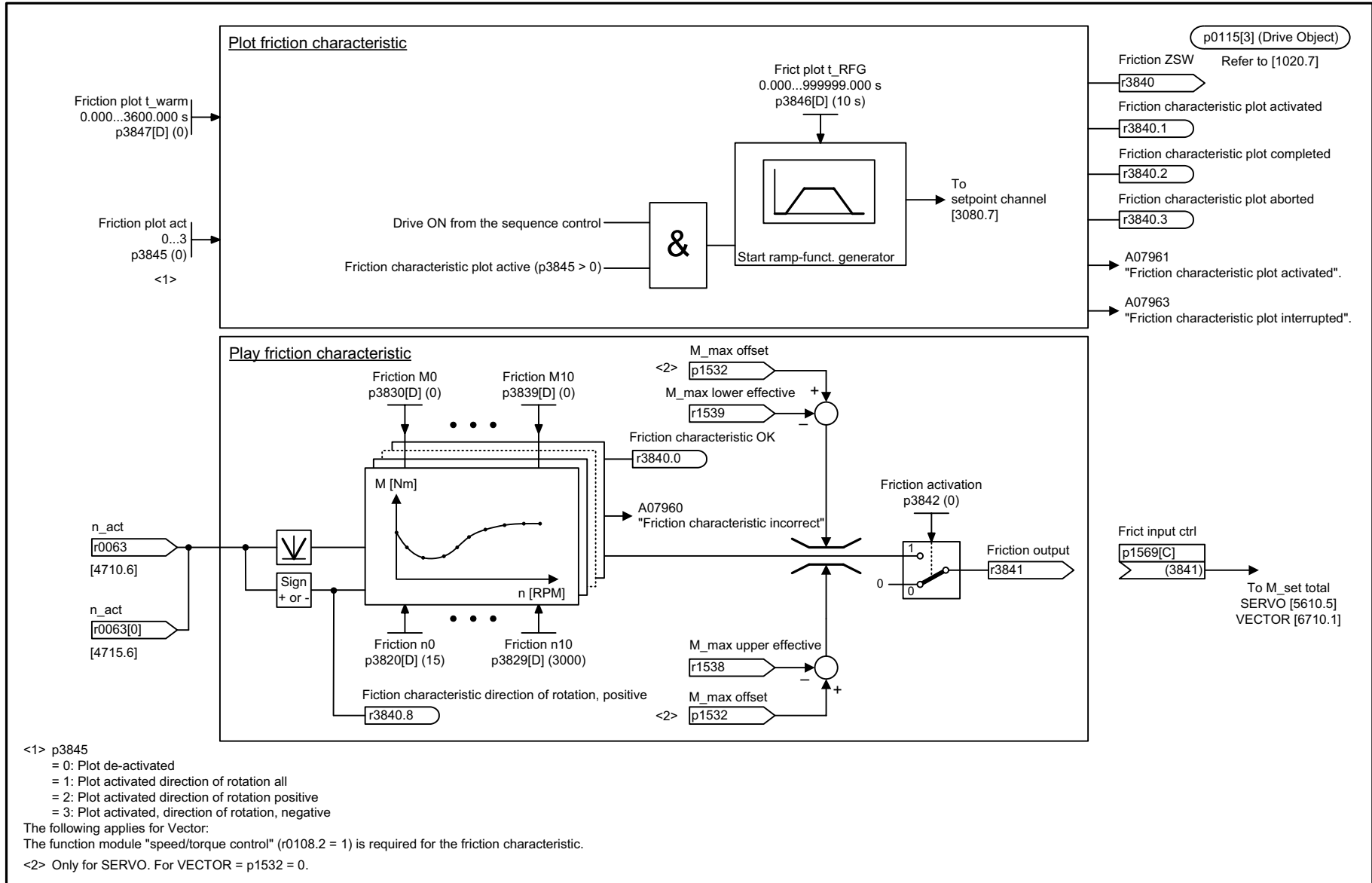
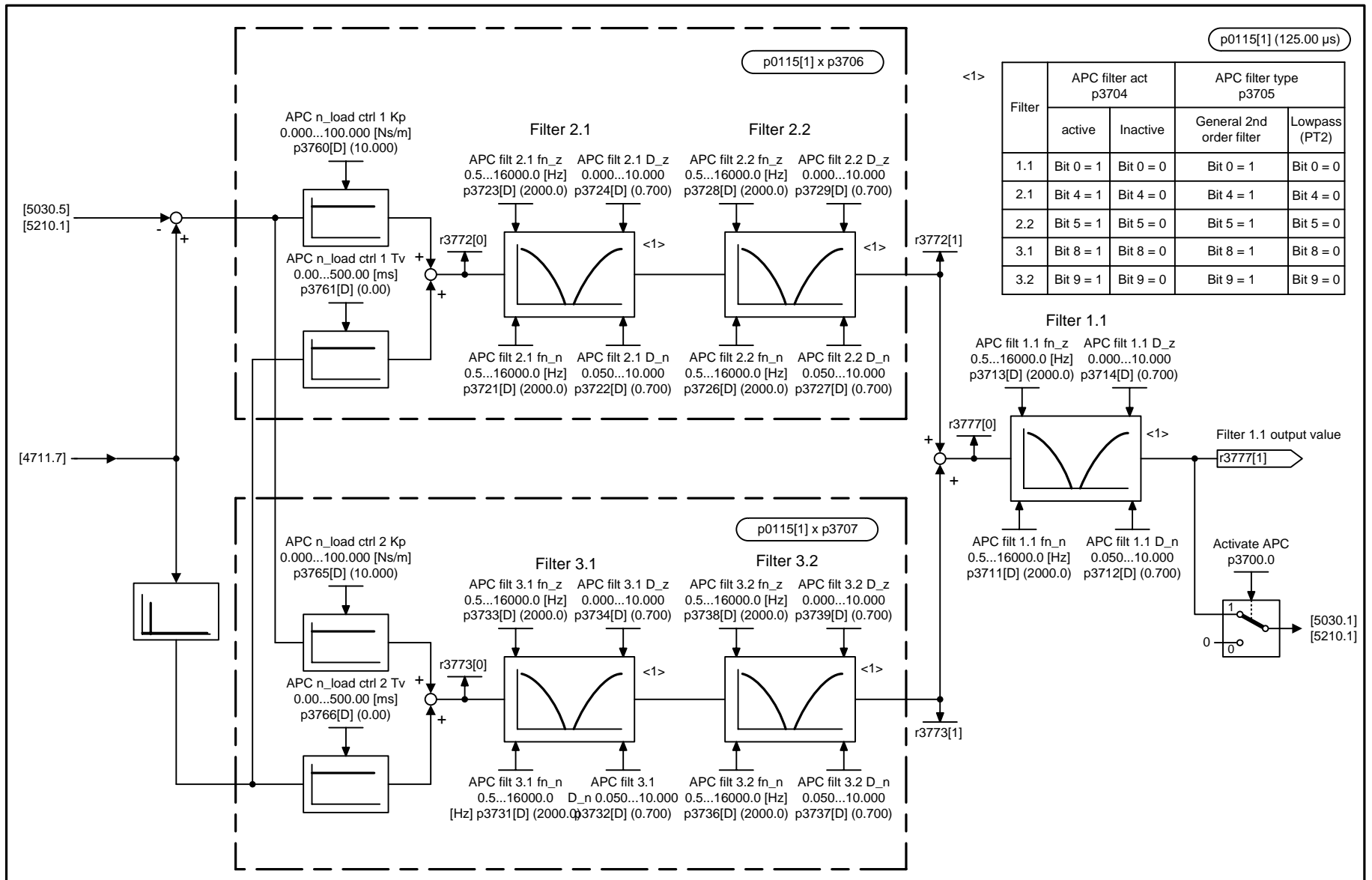


Figure 2-171 7010 – Friction characteristic

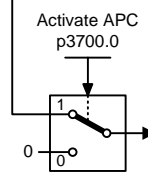
2-1104

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_7010_01_eng.vsd	Function diagram	
Technology functions - friction characteristic					23.03.06 V02.04.00	SINAMICS S	
							- 7010 -



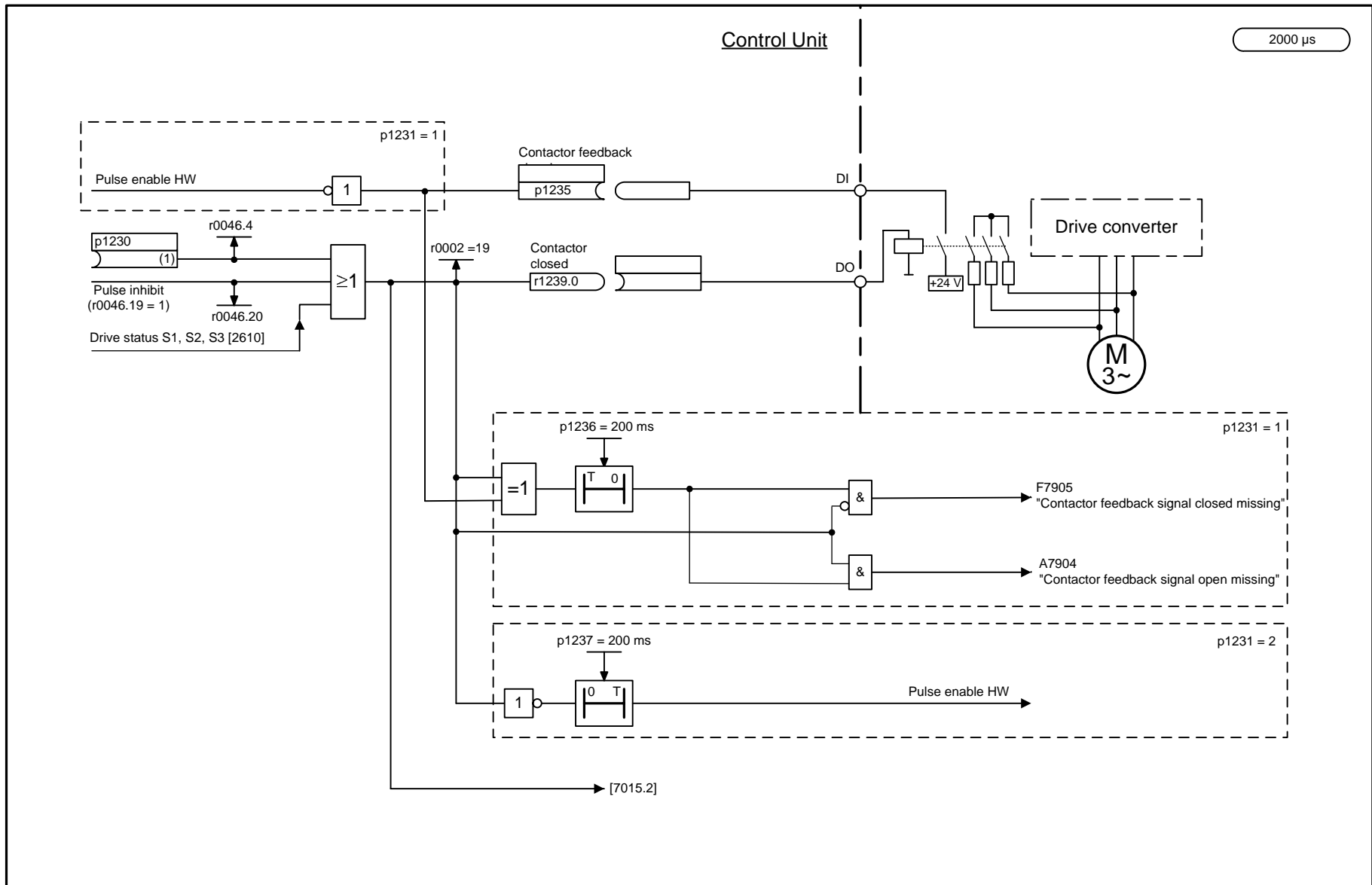
p0115[1] (125.00 μs)

Filter	APC filter act p3704		APC filter type p3705	
	active	Inactive	General 2nd order filter	Lowpass (PT2)
1.1	Bit 0 = 1	Bit 0 = 0	Bit 0 = 1	Bit 0 = 0
2.1	Bit 4 = 1	Bit 4 = 0	Bit 4 = 1	Bit 4 = 0
2.2	Bit 5 = 1	Bit 5 = 0	Bit 5 = 1	Bit 5 = 0
3.1	Bit 8 = 1	Bit 8 = 0	Bit 8 = 1	Bit 8 = 0
3.2	Bit 9 = 1	Bit 9 = 0	Bit 9 = 1	Bit 9 = 0



1	2	3	4	5	6	7	8
DO: SERVO					fp_7012_01_eng.vsd	Function diagram	
Technology functions - Advanced Positioning Control (APC, r0108.7 = 1)					03.01.06 V02.04.00	SINAMICS	
							- 7012 -

Figure 2-172 7012 – Advanced Positioning Control (APC, r0108.7 = 1))



2000 µs

Figure 2-173 7014 – External armature short circuit (EASC, p0300 = 2xx or 4xx)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_7014_01_eng.vsd	Function diagram	
Technology functions – External armature short circuit (EASC, p0300 = 2xx or 4xx)					15.12.05 V02.04.00	SINAMICS S	
							- 7014 -

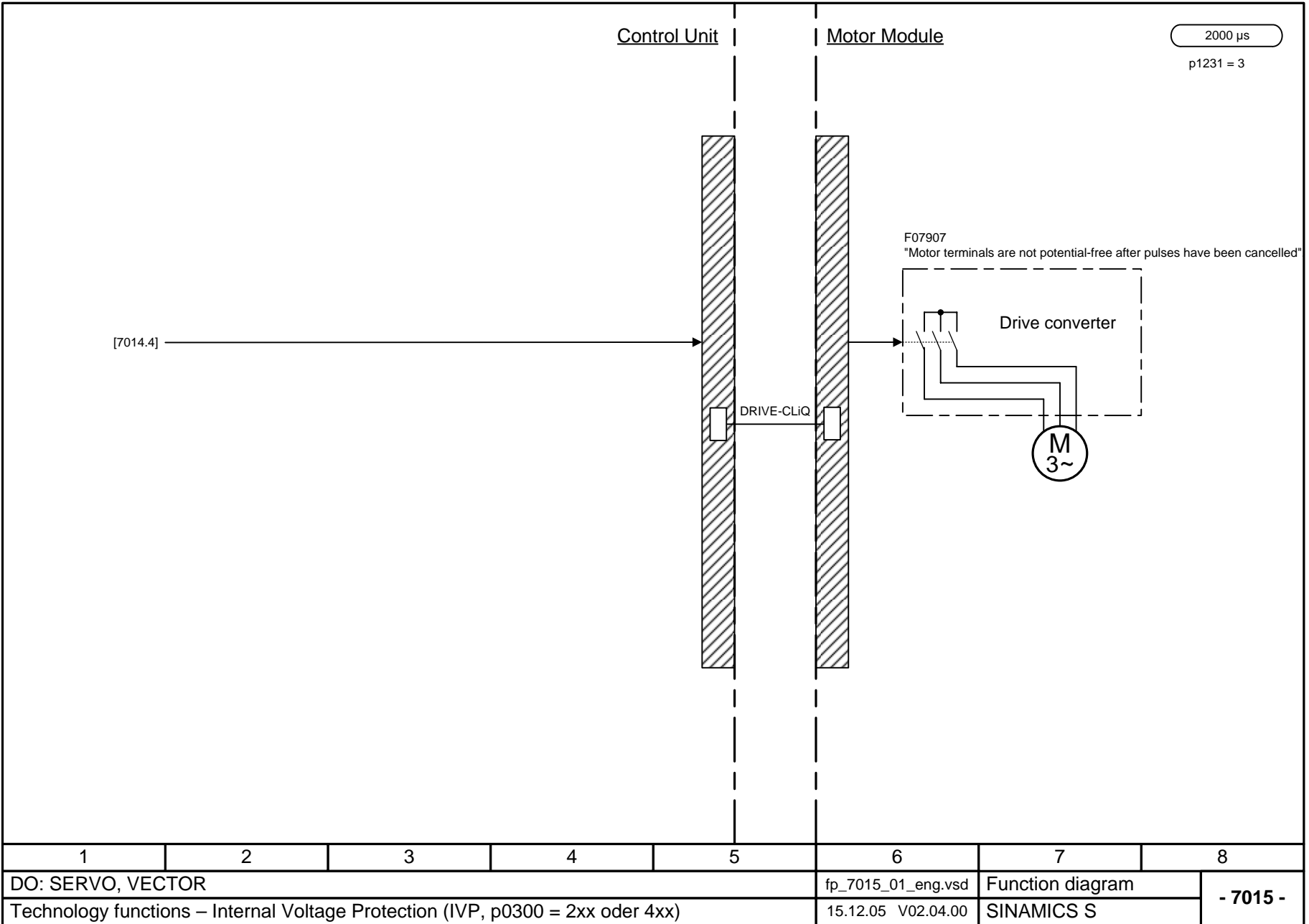
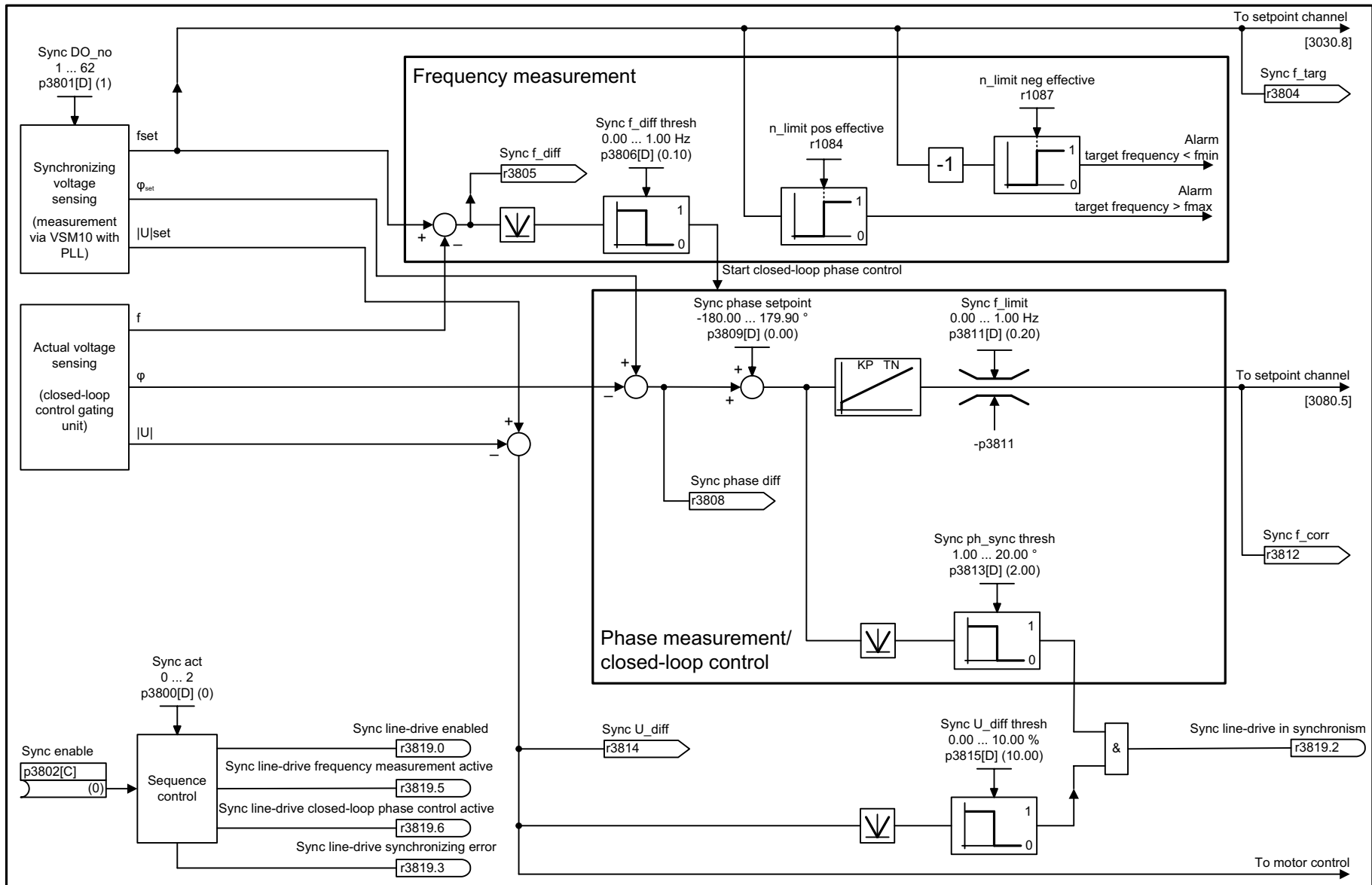


Figure 2-174 7015 – Internal voltage protection (IVP, p0300 = 2xx or 4xx)



1	2	3	4	5	6	7	8
DO: VECTOR					fp_7020_01_eng.vsd	Function diagram	
Technology functions - Synchronisation					27.02.06 V02.04.00	SINAMICS S	
							- 7020 -

Figure 2-175 7020 – Synchronization

2.21 Technology controller

Function diagrams

7950 – Fixed values (r0108.16 = 1)	2-1110
7954 – Motorized potentiometer (r0108.16 = 1)	2-1111
7958 – Closed-loop control (r0108.16 = 1)	2-1112

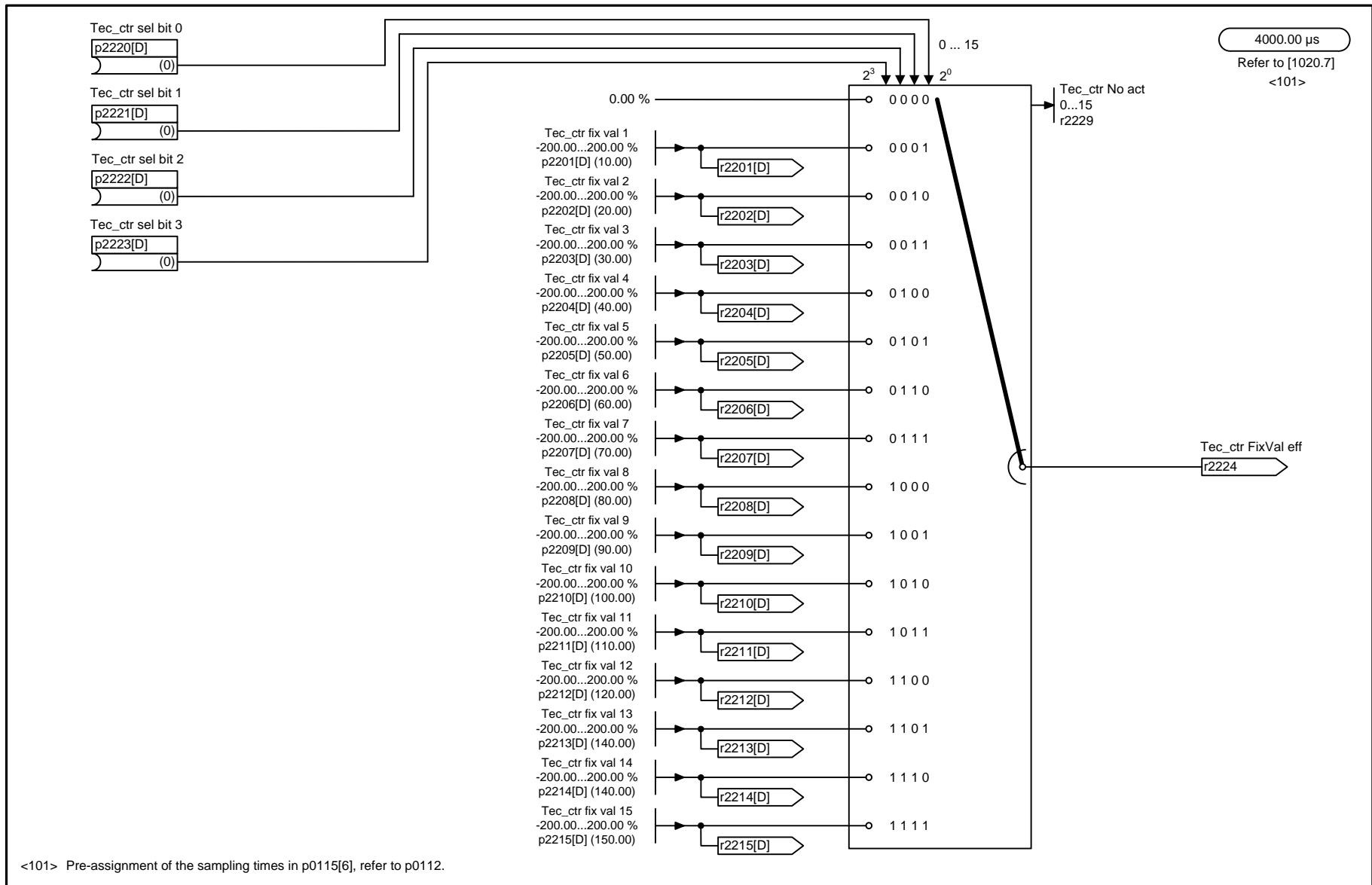
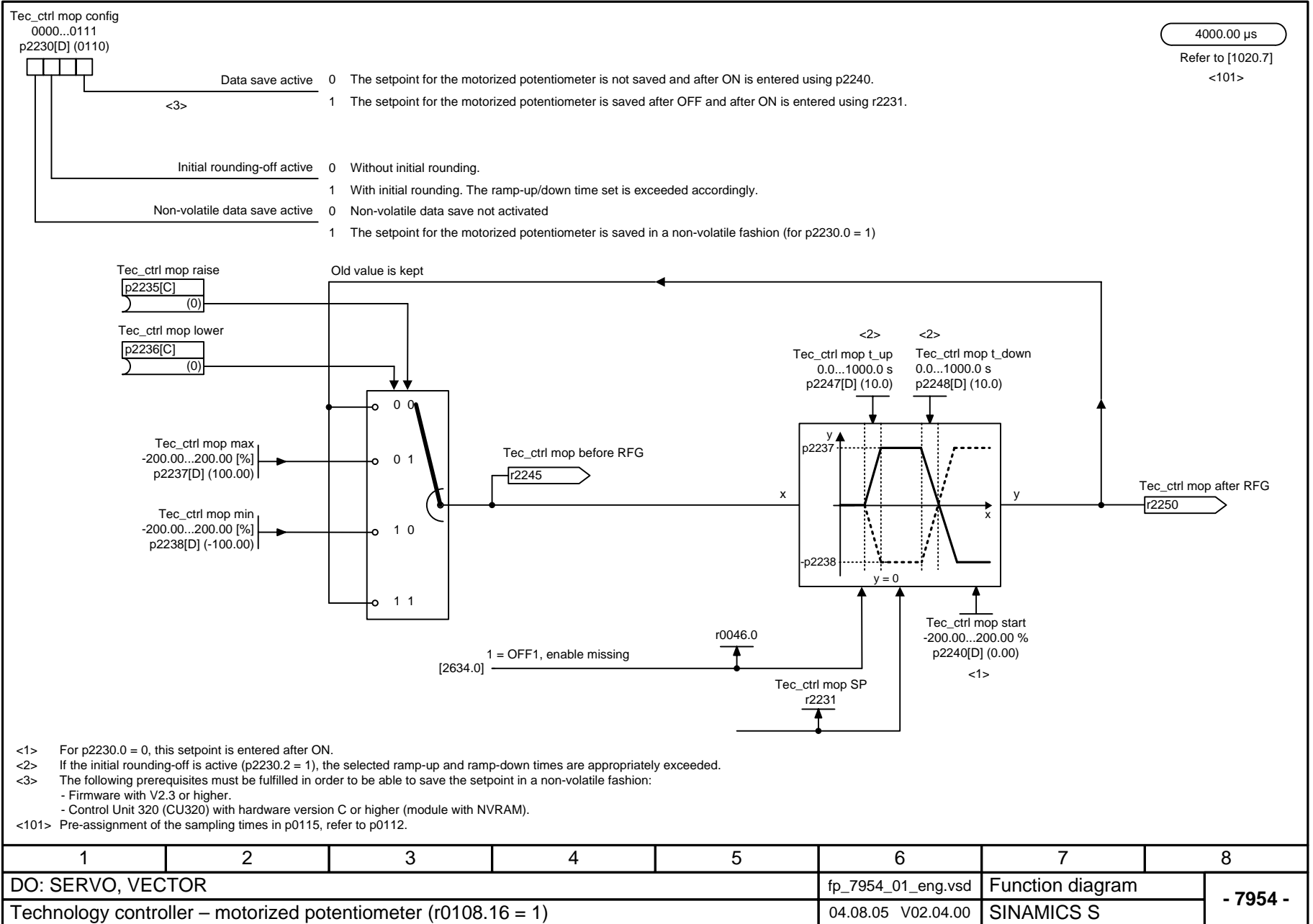


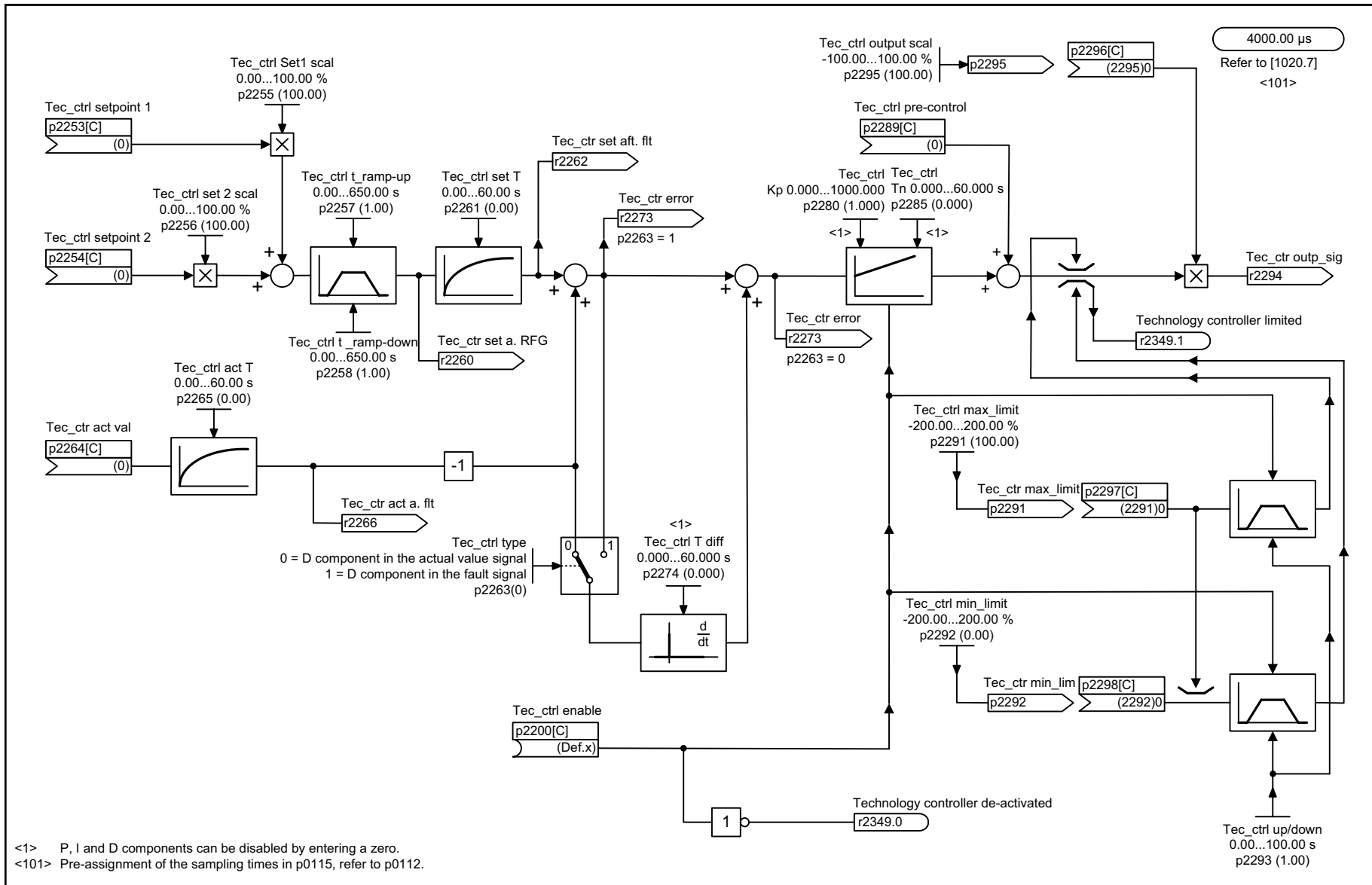
Figure 2-176 7950 – Fixed values (r0108.16 = 1)

2-11110

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_7950_01_eng.vsd	Function diagram	
Technology controller - fixed values (r0108.16 = 1)					03.05.05 V02.04.00	SINAMICS S	
							- 7950 -

Figure 2-177 7954 – Motorized potentiometer (r0108.16 = 1)





<1> P, I and D components can be disabled by entering a zero.
 <101> Pre-assignment of the sampling times in p0115, refer to p0112.

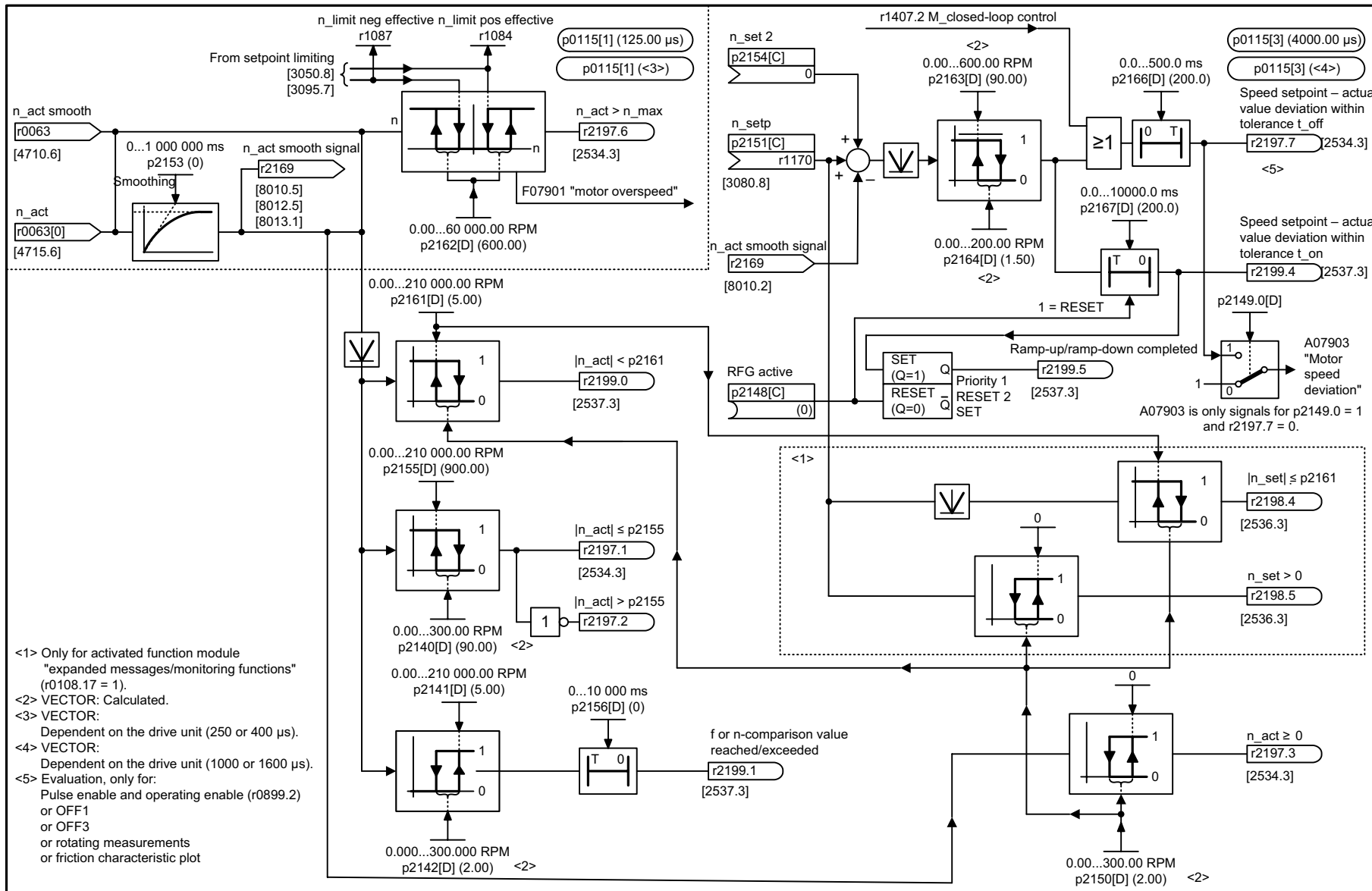
1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_7958_01_eng.vsd	Function diagram	
Technology controller - control (r0108.16 = 1)					03.05.05 V02.04.00	SINAMICS S	
							- 7958 -

Figure 2-178 7958 – Closed-loop control (r0108.16 = 1)

2.22 Messages and monitoring functions

Function diagrams

8010 – Speed messages/signals	2-1114
8012 – Torque messages/signals, motor locked/stalled	2-1115
8013 – Load monitoring (r0108.17 = 1)	2-1116
8014 – Thermal monitoring, power unit	2-1117
8016 – Thermal monitoring, motor	2-1118
8018 – Separately excited synchronous motor (FEM, p0300 = 5)	2-1119



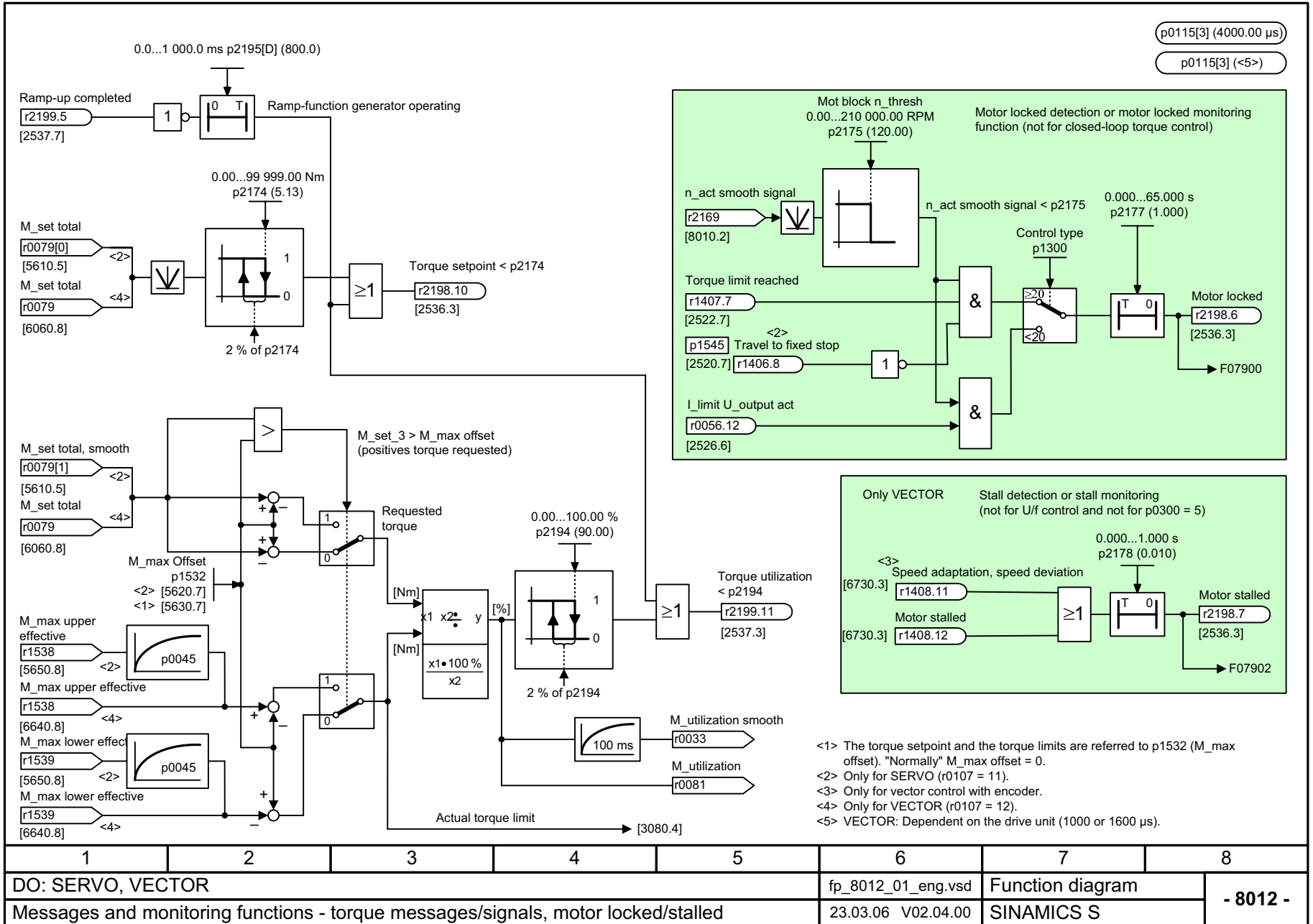
<1> Only for activated function module "expanded messages/monitoring functions" (r0108.17 = 1).
 <2> VECTOR: Calculated.
 <3> VECTOR: Dependent on the drive unit (250 or 400 μs).
 <4> VECTOR: Dependent on the drive unit (1000 or 1600 μs).
 <5> Evaluation, only for: Pulse enable and operating enable (r0899.2) or OFF1 or OFF3 or rotating measurements or friction characteristic plot

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8010_01_eng.vsd	Function diagram	
Signals and monitoring functions - speed signals					17.03.06 V02.04.00	SINAMICS S	
							- 8010 -

Figure 2-179 8010 – Speed messages/signals

2-1114

Figure 2-180 8012 – Torque messages/signals, motor locked/stalled



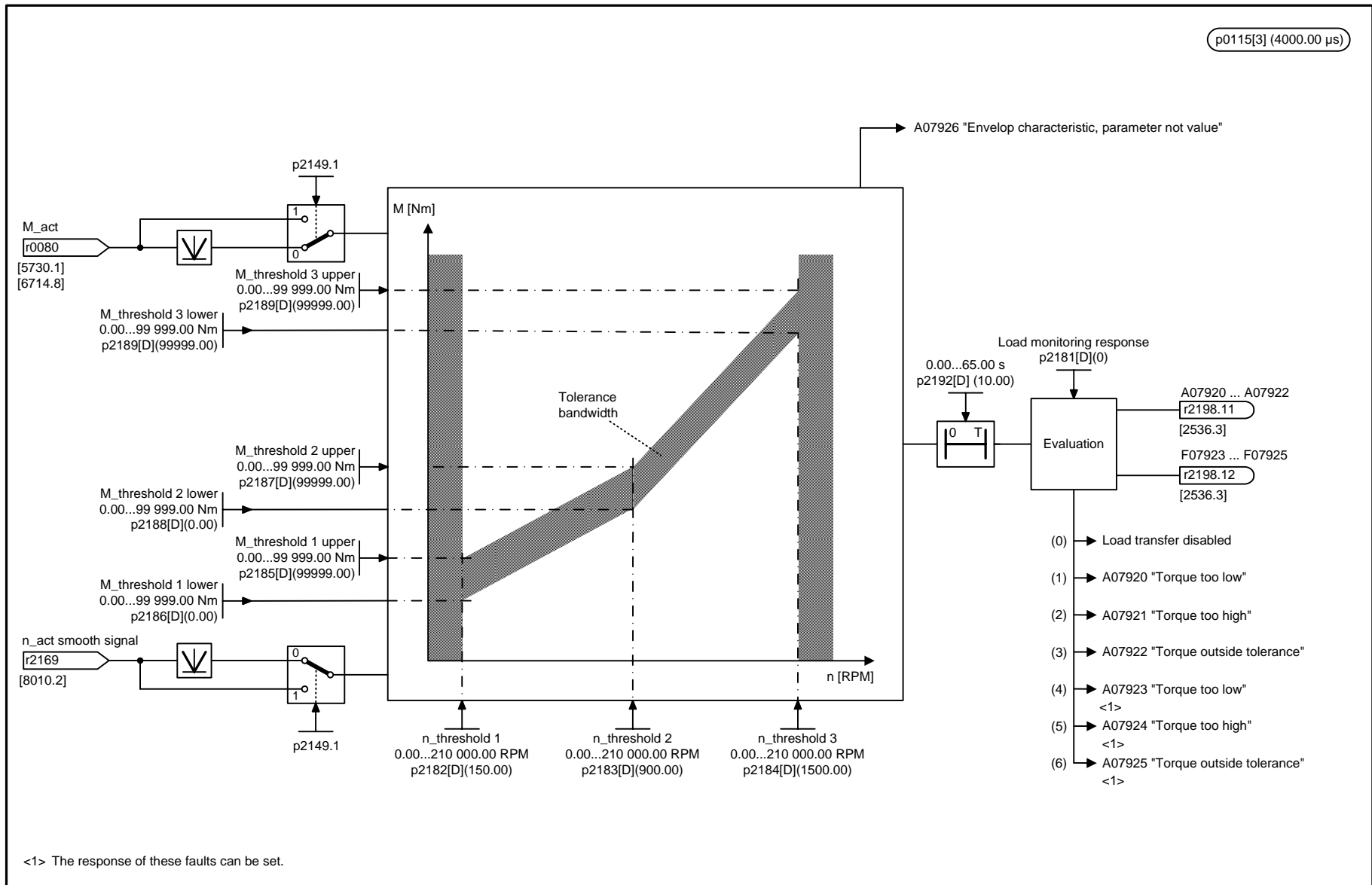
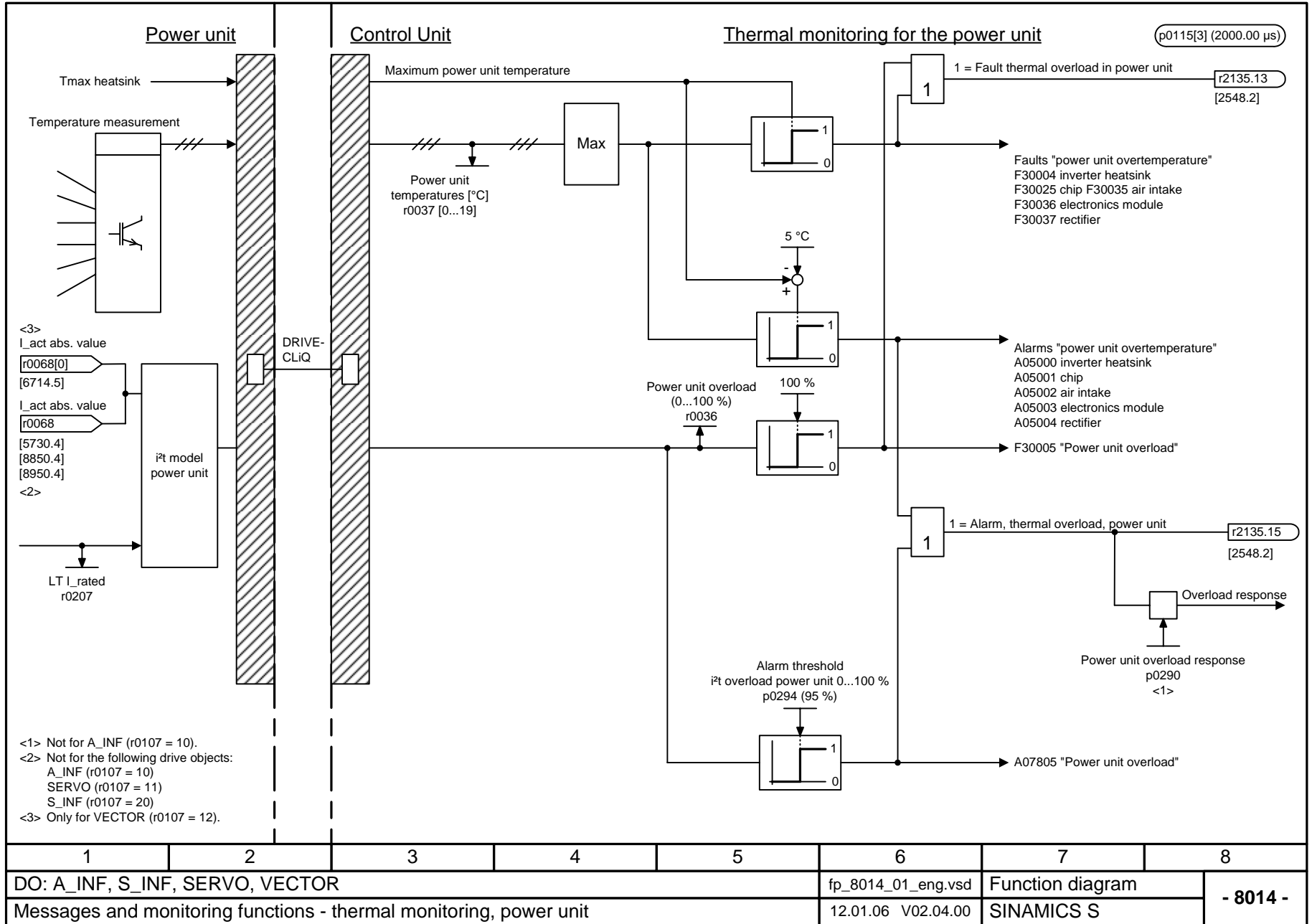


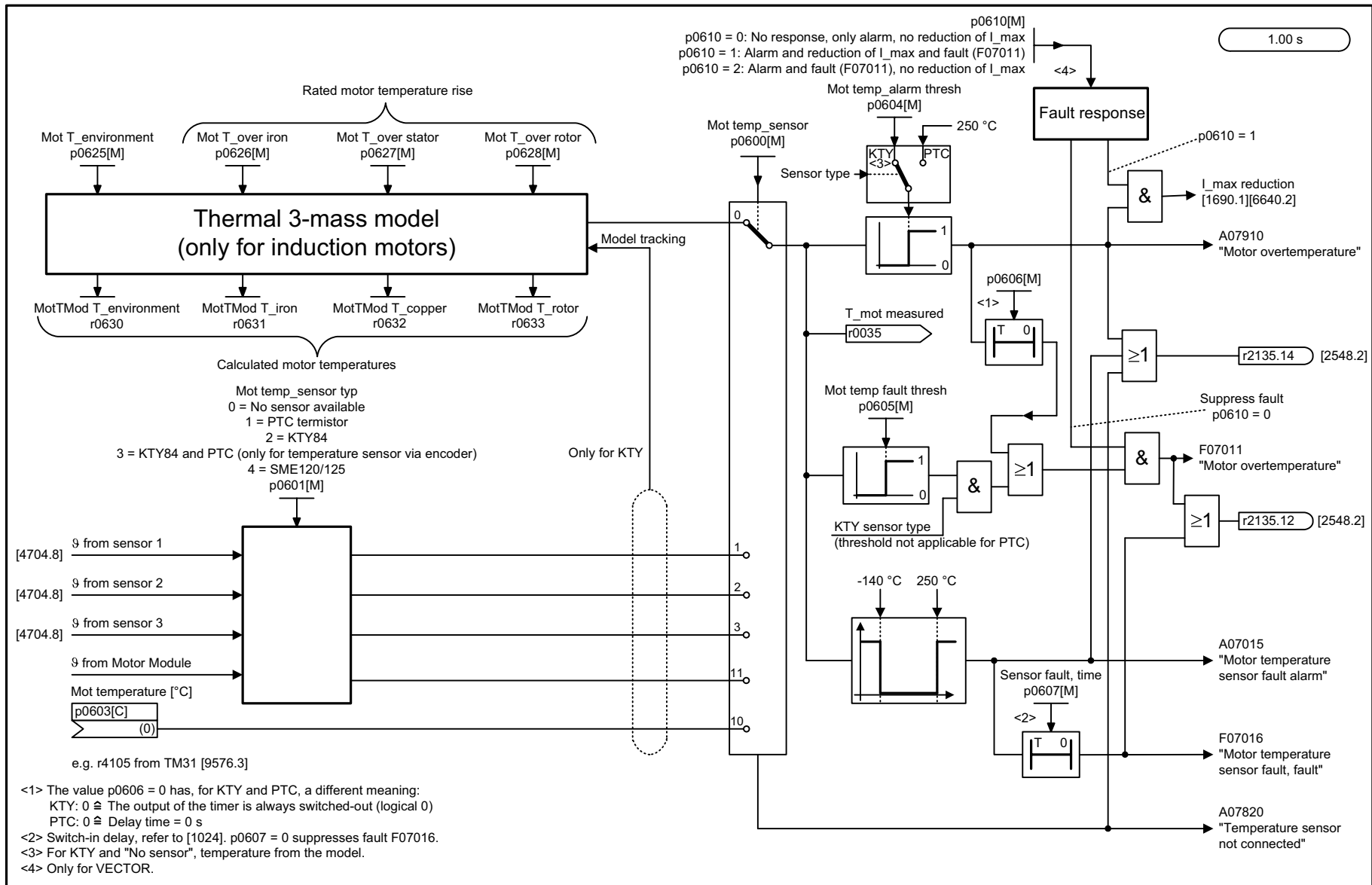
Figure 2-181 8013 – Load monitoring (r0108.17 = 1)

p0115[3] (4000.00 μs)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8013_01_eng.vsd	Function diagram	
Messages and monitoring functions - load monitoring (r0108.17 = 1)					06.09.05 V02.04.00	SINAMICS S	
							- 8013 -

Figure 2-182 8014 – Thermal monitoring, power unit



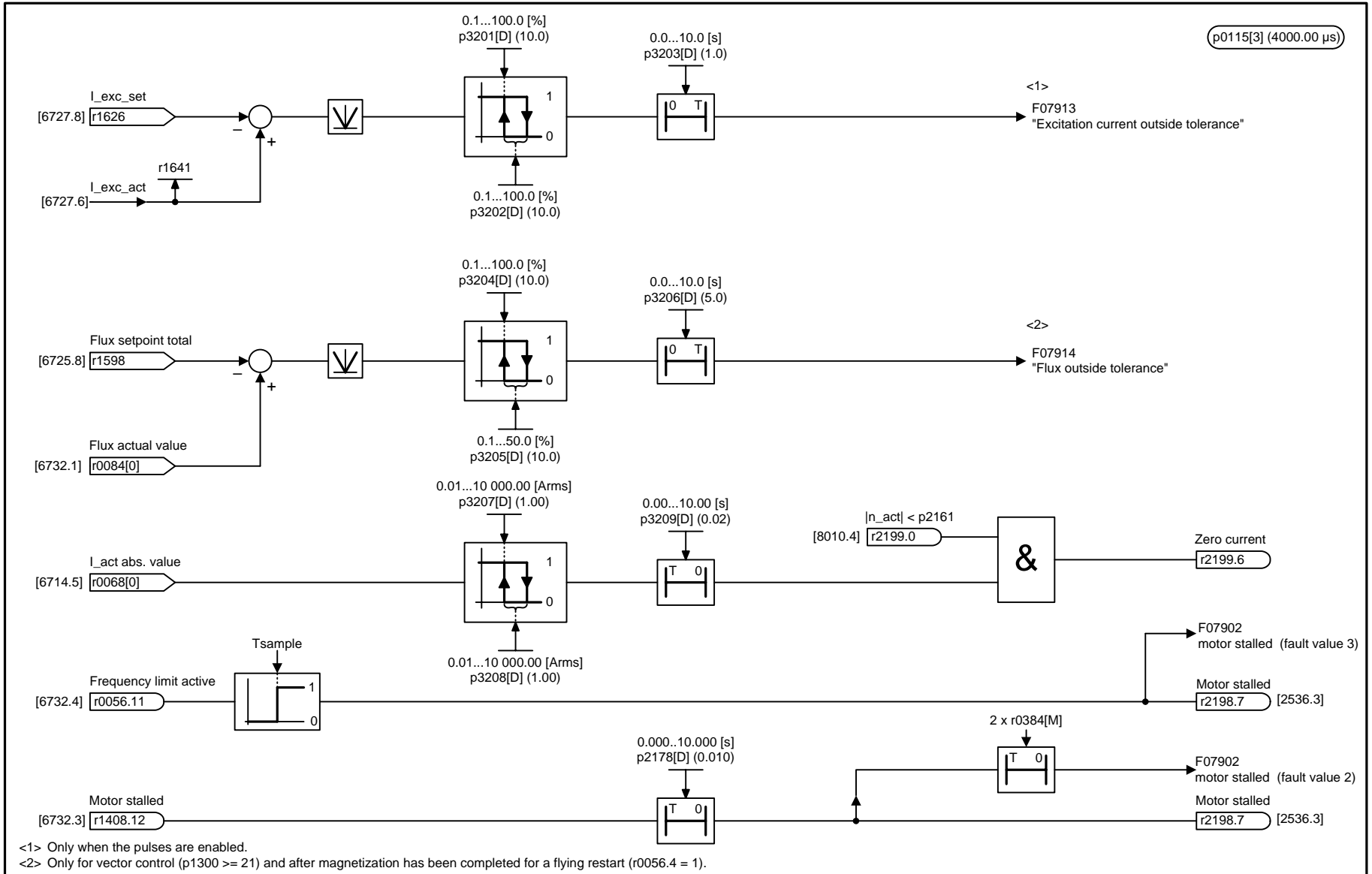


1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8016_01_eng.vsd	Function diagram	
Messages and monitoring functions - thermal monitoring, motor					23.03.06 V02.04.00	SINAMICS S	
							- 8016 -

Figure 2-183 8016 – Thermal monitoring, motor

2-1118

Figure 2-184 8018 – Separately excited synchronous motor (FEM, p0300 = 5)



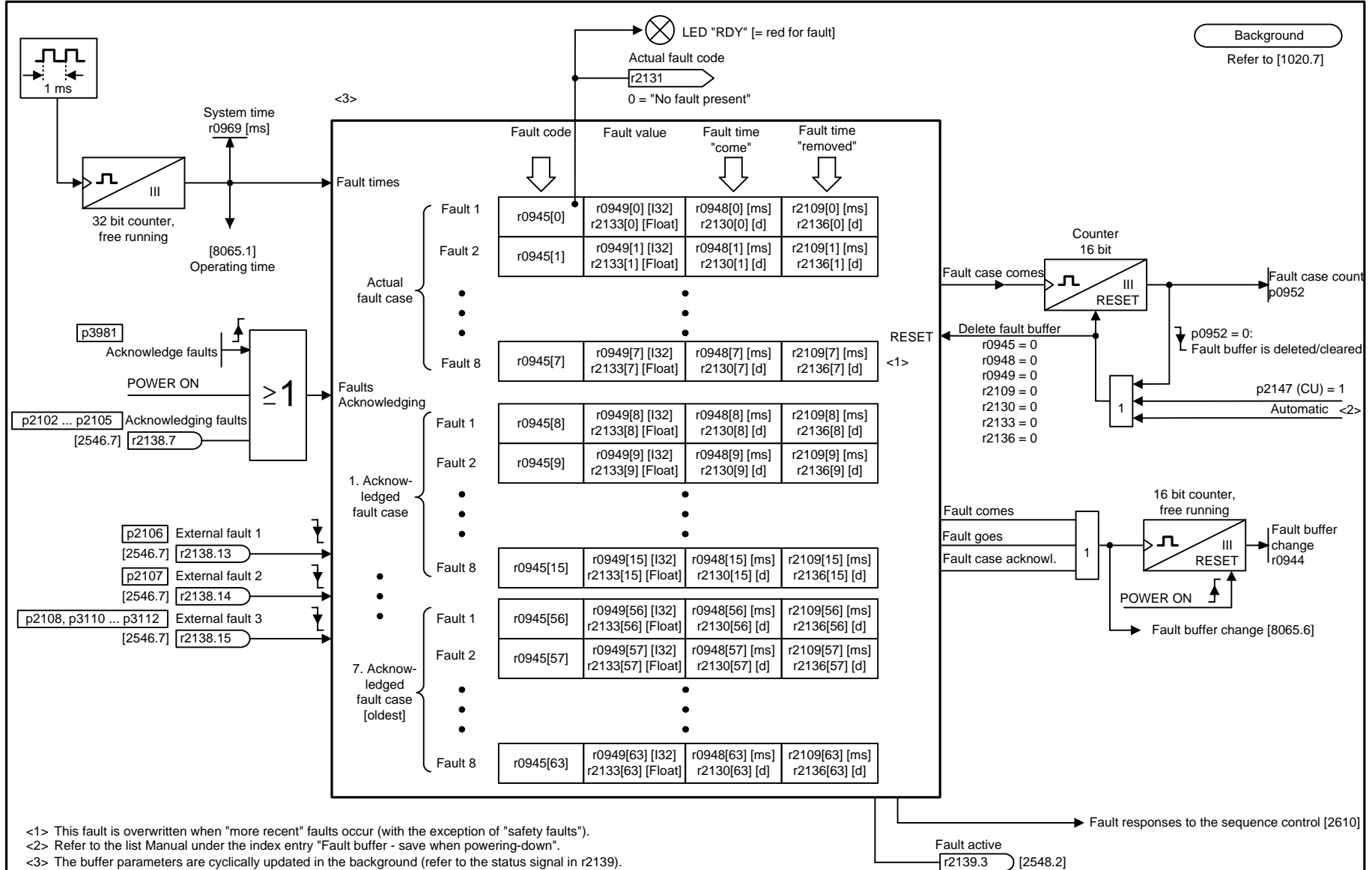
1	2	3	4	5	6	7	8
DO: VECTOR					fp_8018_01_eng.vsd	Function diagram	
Signals and monitoring functions – separately-excited synchronous motor (FEM, p0300 = 5)					21.02.06 V02.04.00	SINAMICS S	
							- 8018 -

2.23 **Faults and alarms**

Function diagrams

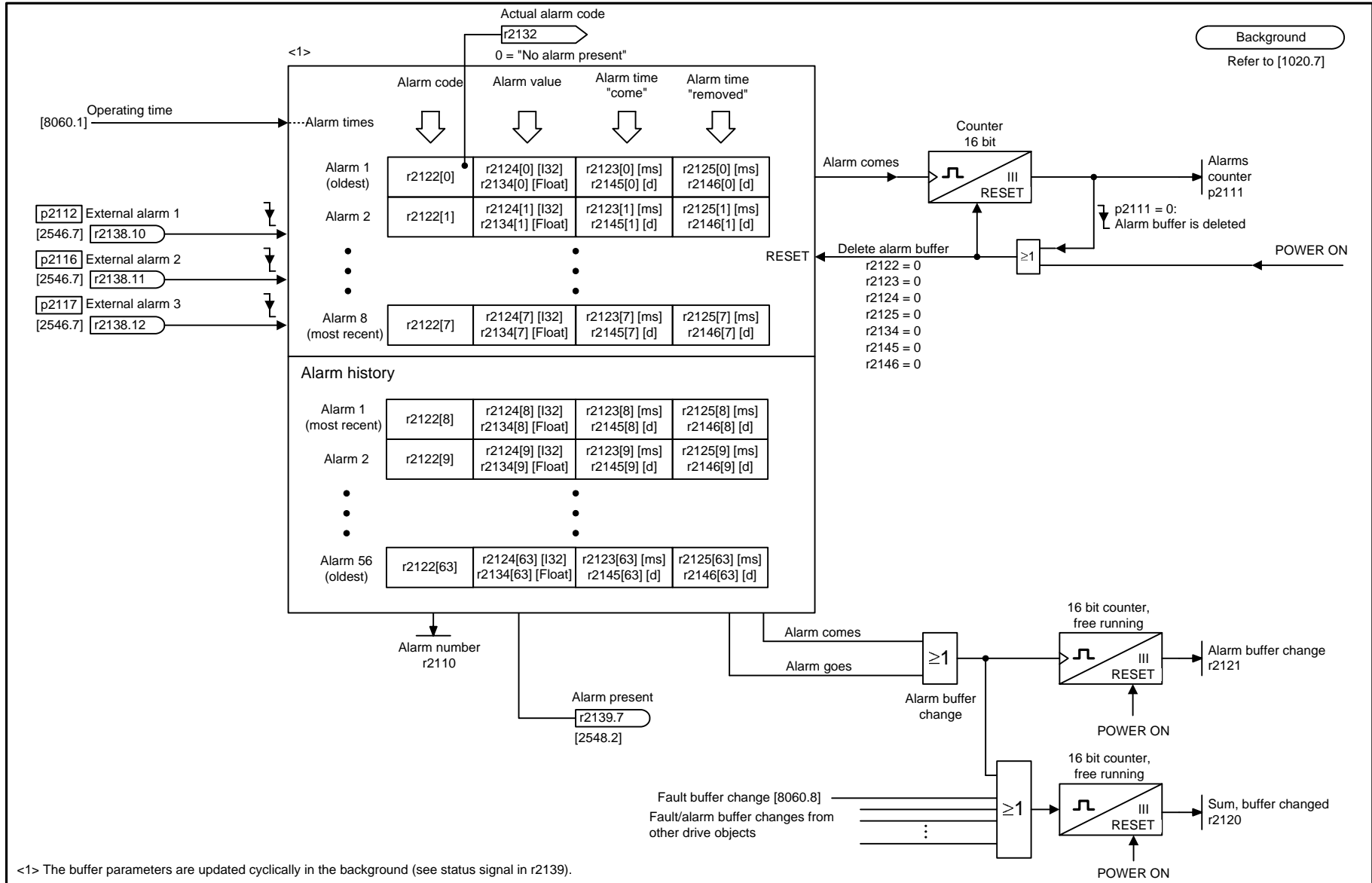
8060 – Fault buffer	2-1121
8065 – Alarm buffer	2-1122
8070 – Fault/warning trigger word (r2129)	2-1123
8075 – Fault/alarm configuration	2-1124

Figure 2-185 8060 – Fault buffer



<1> This fault is overwritten when "more recent" faults occur (with the exception of "safety faults").
 <2> Refer to the list Manual under the index entry "Fault buffer - save when powering-down".
 <3> The buffer parameters are cyclically updated in the background (refer to the status signal in r2139).

1	2	3	4	5	6	7	8
DO: All objects					fp_8060_01_eng.vsd	Function diagram	
Faults and alarms - fault buffer					25.01.06 V02.04.00	SINAMICS S	
							- 8060 -



1	2	3	4	5	6	7	8
DO: All objects					fp_8065_01_eng.vsd	Function diagram	
Faults and alarms - alarm buffer					28.06.05 V02.04.00	SINAMICS S	

Figure 2-186 8065 – Alarm buffer

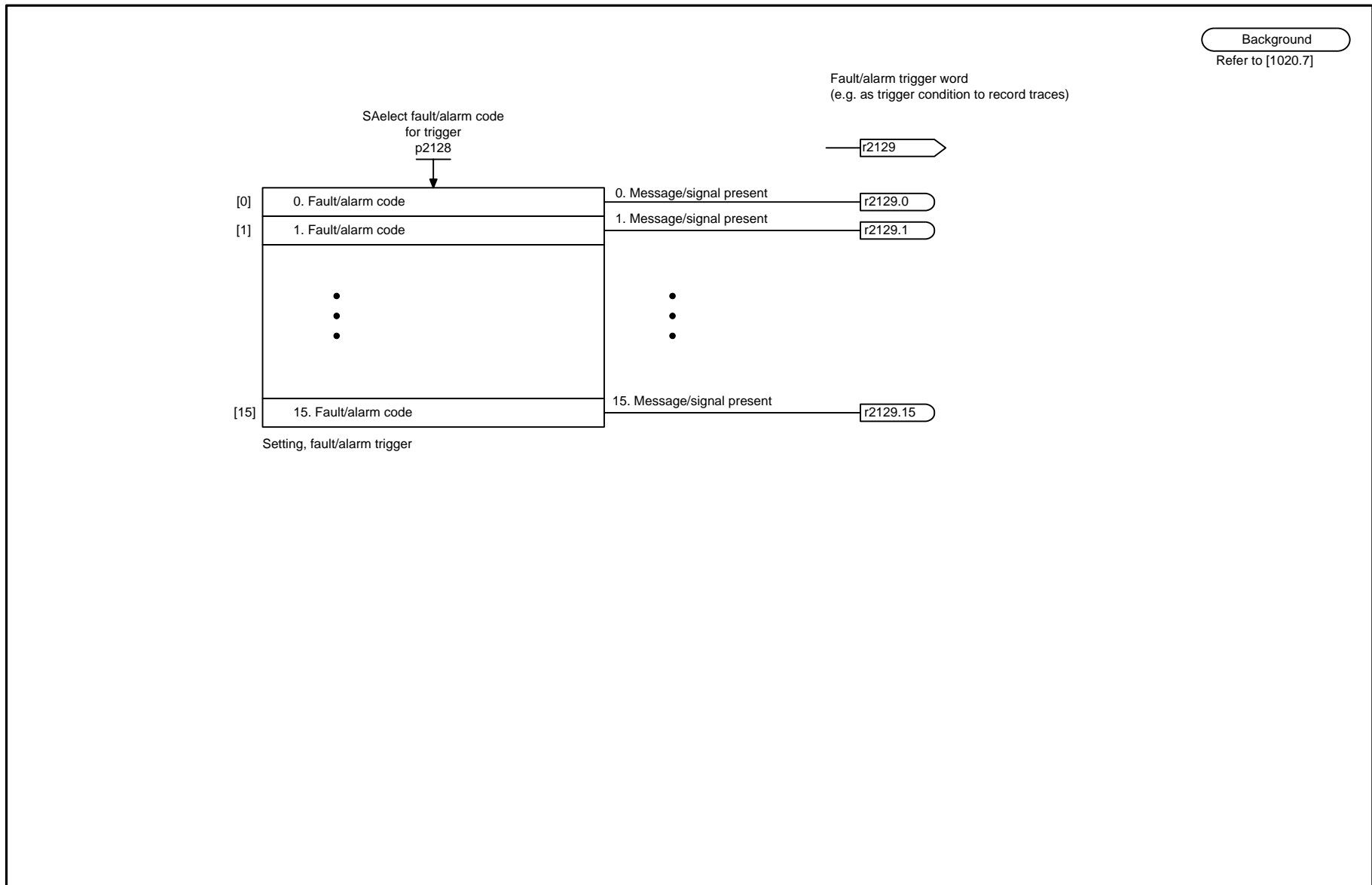
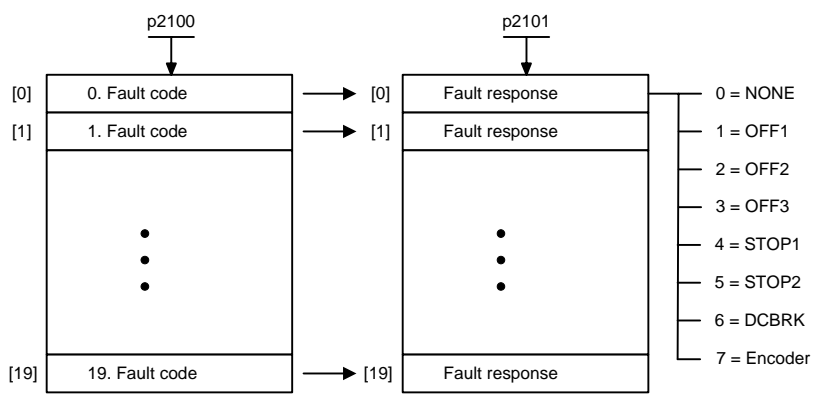


Figure 2-187 8070 – Fault/warning trigger word (r2129)

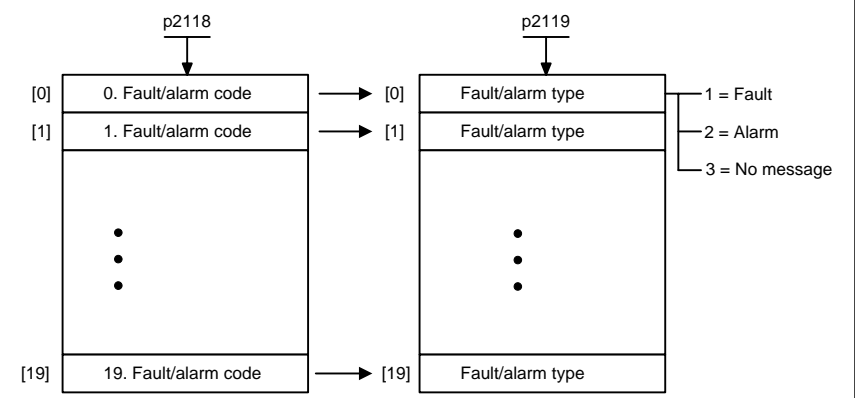
1	2	3	4	5	6	7	8
DO: All objects					fp_8070_01_eng.vsd	Function diagram	
Faults and alarms - Fault/alarm trigger word (r2129)					18.05.05 V02.04.00	SINAMICS S	
							- 8070 -

Background
Refer to [1020.7]

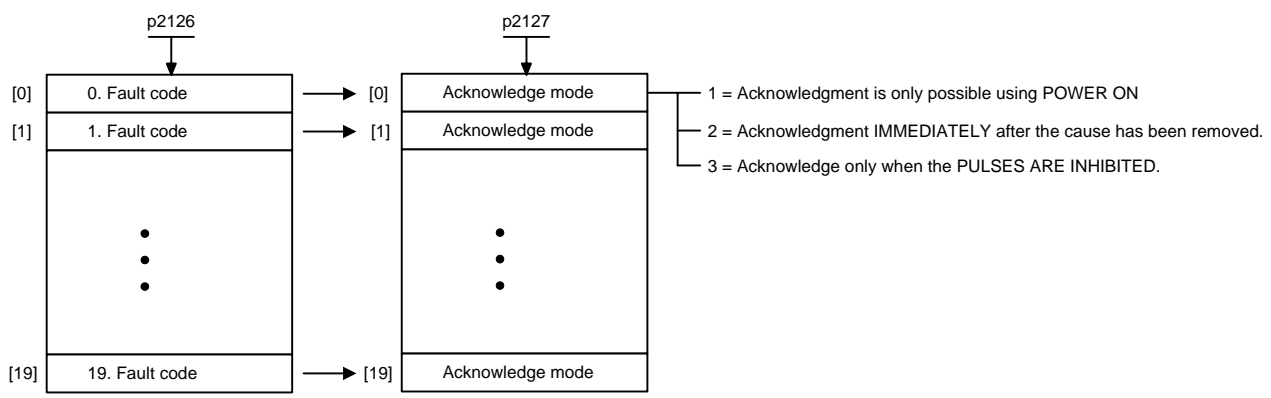
Changing the fault response for maximum 20 faults <1>



Changing the message type - fault <==> alarm for maximum 20 faults/alarms <1>



Changing the acknowledge mode for maximum 20 faults <1>



<1> Fault response, acknowledge mode and message type for all faults and alarms are practically pre-set as default in the factory setting. Changes that may be required are only possible in specific value ranges that SIEMENS has specified. When the message type is changed, the supplementary information "wanders" from fault value r0949 to the alarm value r2124 and vice versa.

1	2	3	4	5	6	7	8
DO: All objects					fp_8075_01_eng.vsd	Function diagram	
Faults and alarms - fault/alarm configuration					06.03.06 V02.04.00	SINAMICS S	
							- 8075 -

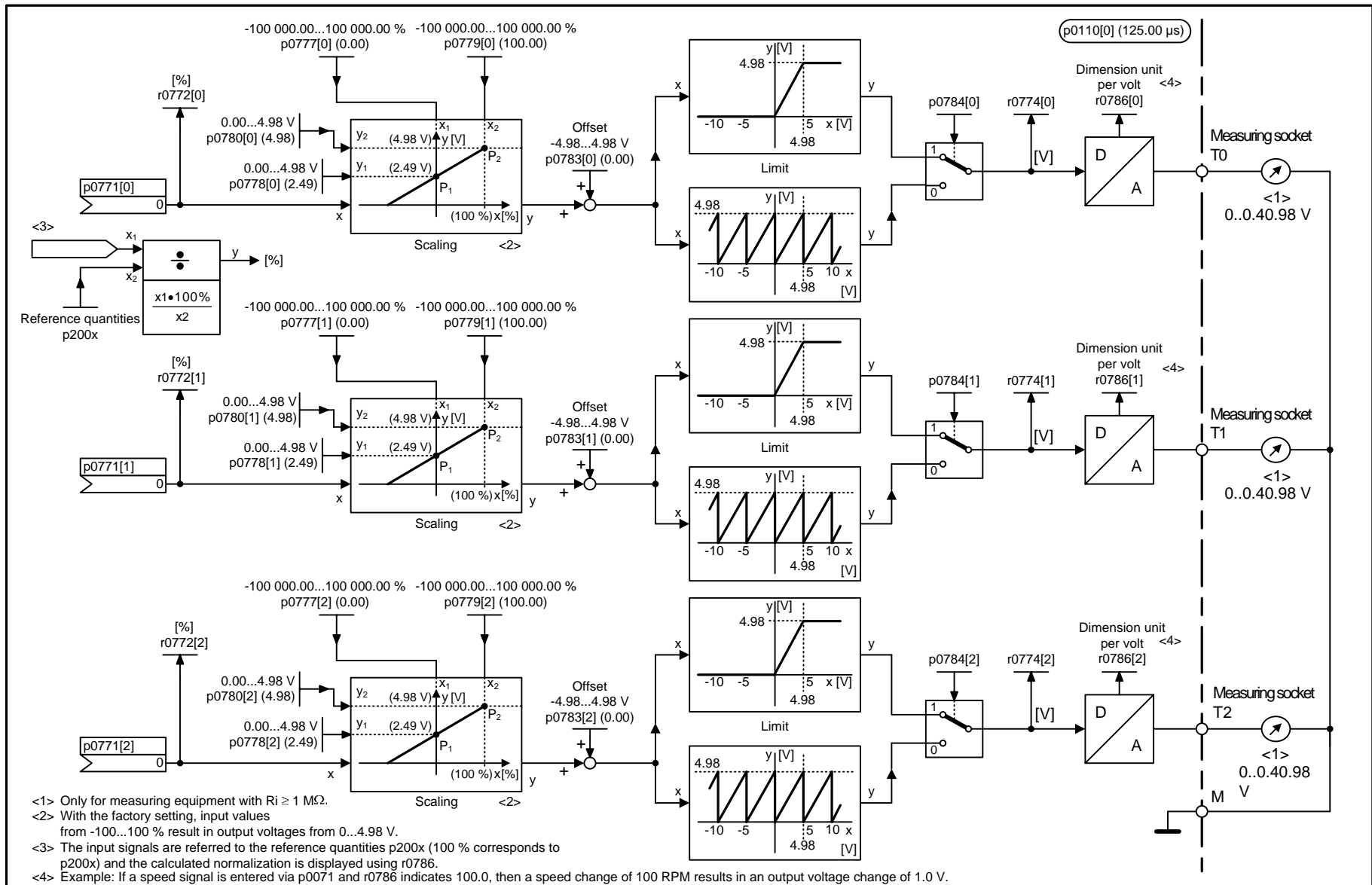
Figure 2-188 8075 – Fault/alarm configuration

2.24 Test sockets

Function diagrams

8134 – Measuring sockets

2-1126



- <1> Only for measuring equipment with $R_i \geq 1 \text{ M}\Omega$.
- <2> With the factory setting, input values from -100...100 % result in output voltages from 0...4.98 V.
- <3> The input signals are referred to the reference quantities p200x (100 % corresponds to p200x) and the calculated normalization is displayed using r0786.
- <4> Example: If a speed signal is entered via p0071 and r0786 indicates 100.0, then a speed change of 100 RPM results in an output voltage change of 1.0 V.

1	2	3	4	5	6	7	8
DO: CU320					fp_8134_01_eng.vsd	Function diagram	
Measuring sockets					31.08.04 V02.04.00	SINAMICS S	
							- 8134 -

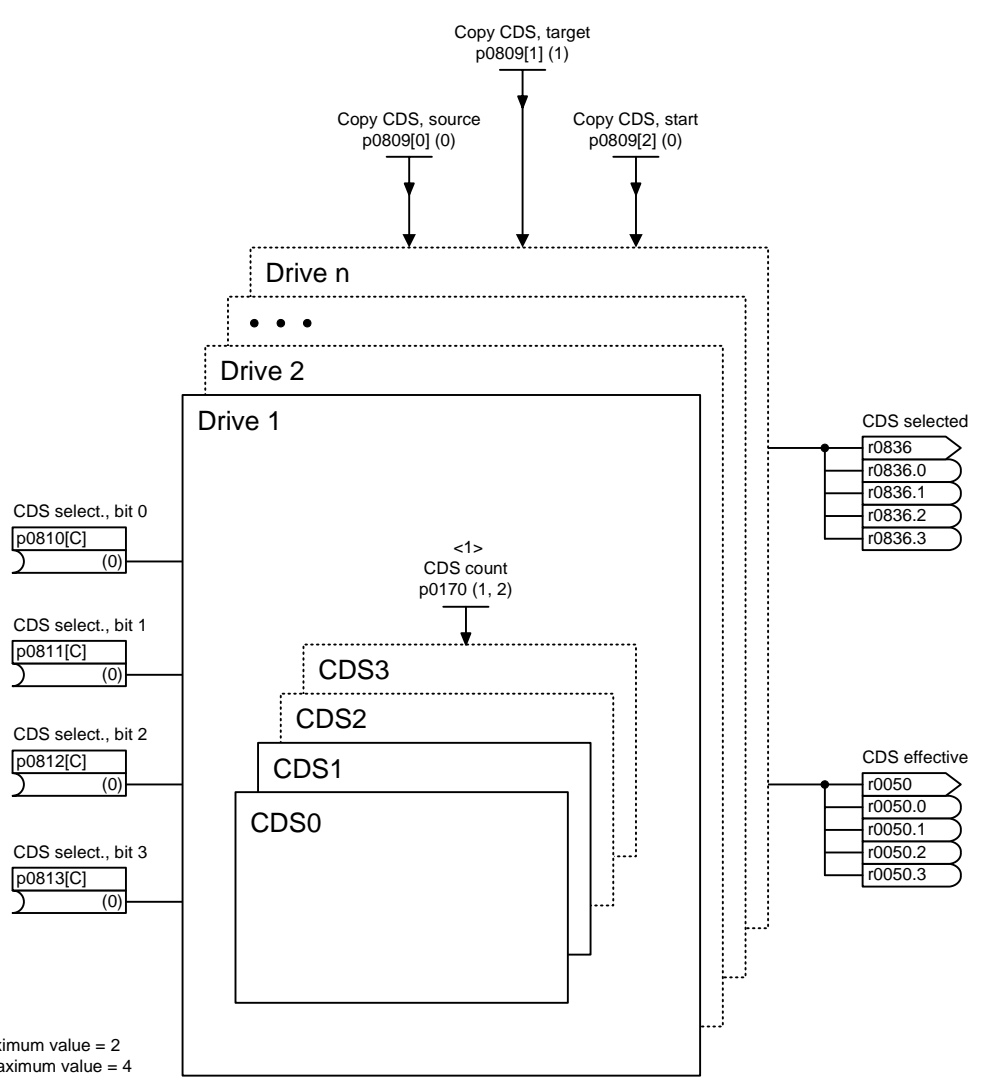
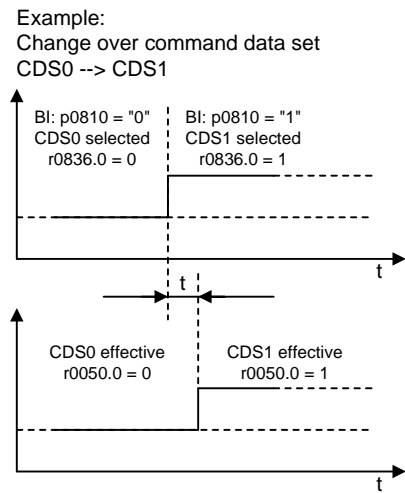
Figure 2-189 8134 – Measuring sockets

2.25 Data sets

Function diagrams

8560 – Command data set (CDS)	2-1128
8565 – Drive data set (DDS)	2-1129
8570 – Encoder data set (EDS)	2-1130
8575 – Motor data set (MDS)	2-1131
8580 – Power unit data set (PDS)	2-1132

Not relevant
Refer to [1020.7]



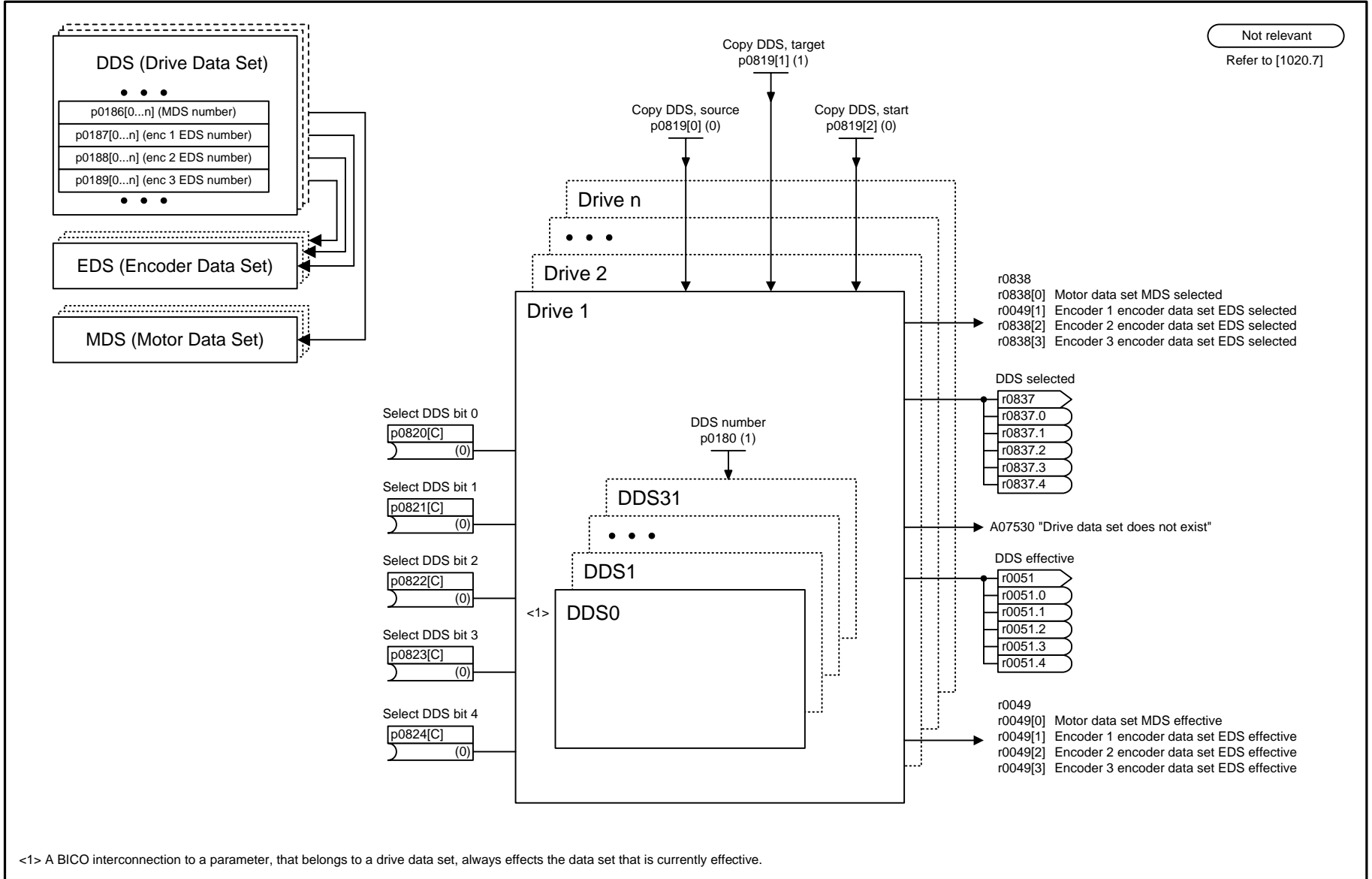
<1>
For SERVO, the following applies: Factory setting = 1 and maximum value = 2
For VECTOR, the following applies: Factory setting = 2 and maximum value = 4

Figure 2-190 8560 – Command data set (CDS)

2-1128

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8560_01_eng.vsd	Function diagram	
Data set - command data set (CDS)					01.02.06 V02.04.00	SINAMICS S	
							- 8560 -

Figure 2-191 8565 – Drive data set (DDS)



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR, TM41					fp_8565_01_eng.vsd	Function diagram	
Data sets – Drive Data Set, DDS					03.02.06 V02.04.00	SINAMICS S	
							- 8565 -

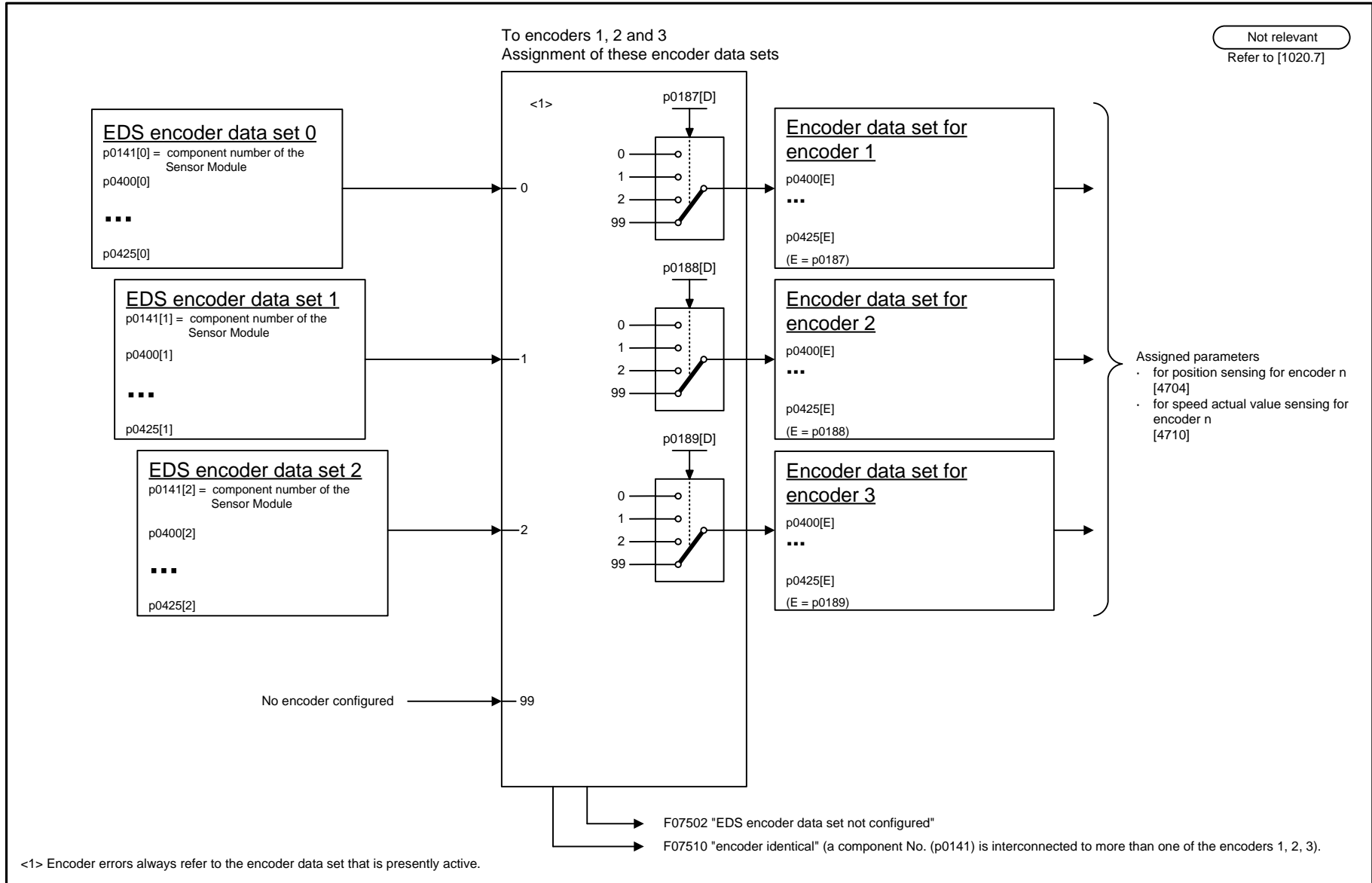
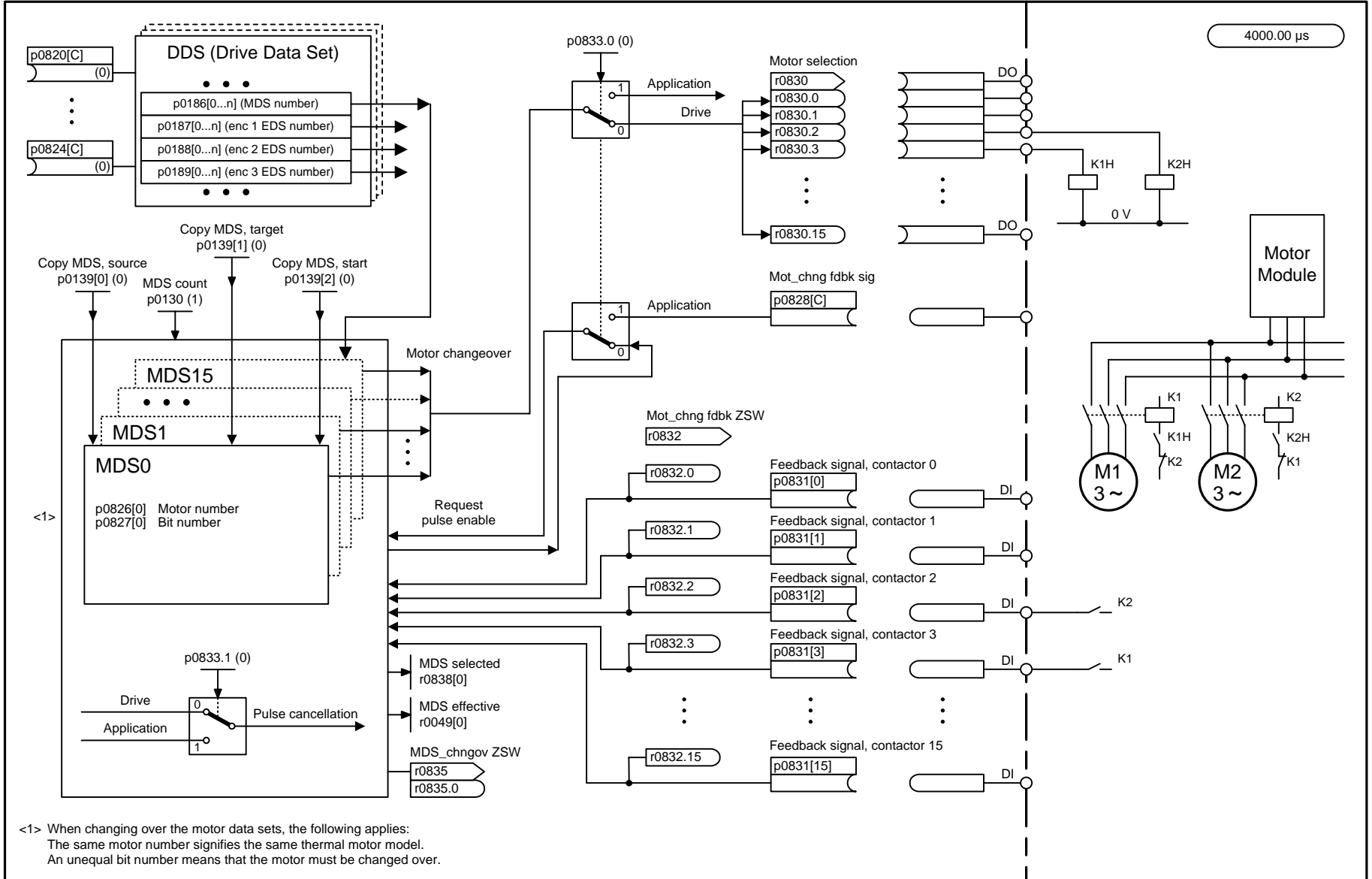


Figure 2-192 8570 – Encoder data set (EDS)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8570_01_eng.vsd	Function diagram	
Data sets – Encoder Data Set, EDS					14.03.06 V02.04.00	SINAMICS S	
							- 8570 -

Figure 2-193 8575 – Motor data set (MDS)



<1> When changing over the motor data sets, the following applies:
 The same motor number signifies the same thermal motor model.
 An unequal bit number means that the motor must be changed over.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8575_01_eng.vsd	Function diagram	
Data set – motor data set (MDS)					23.08.05 V02.04.00	SINAMICS S	
							- 8575 -

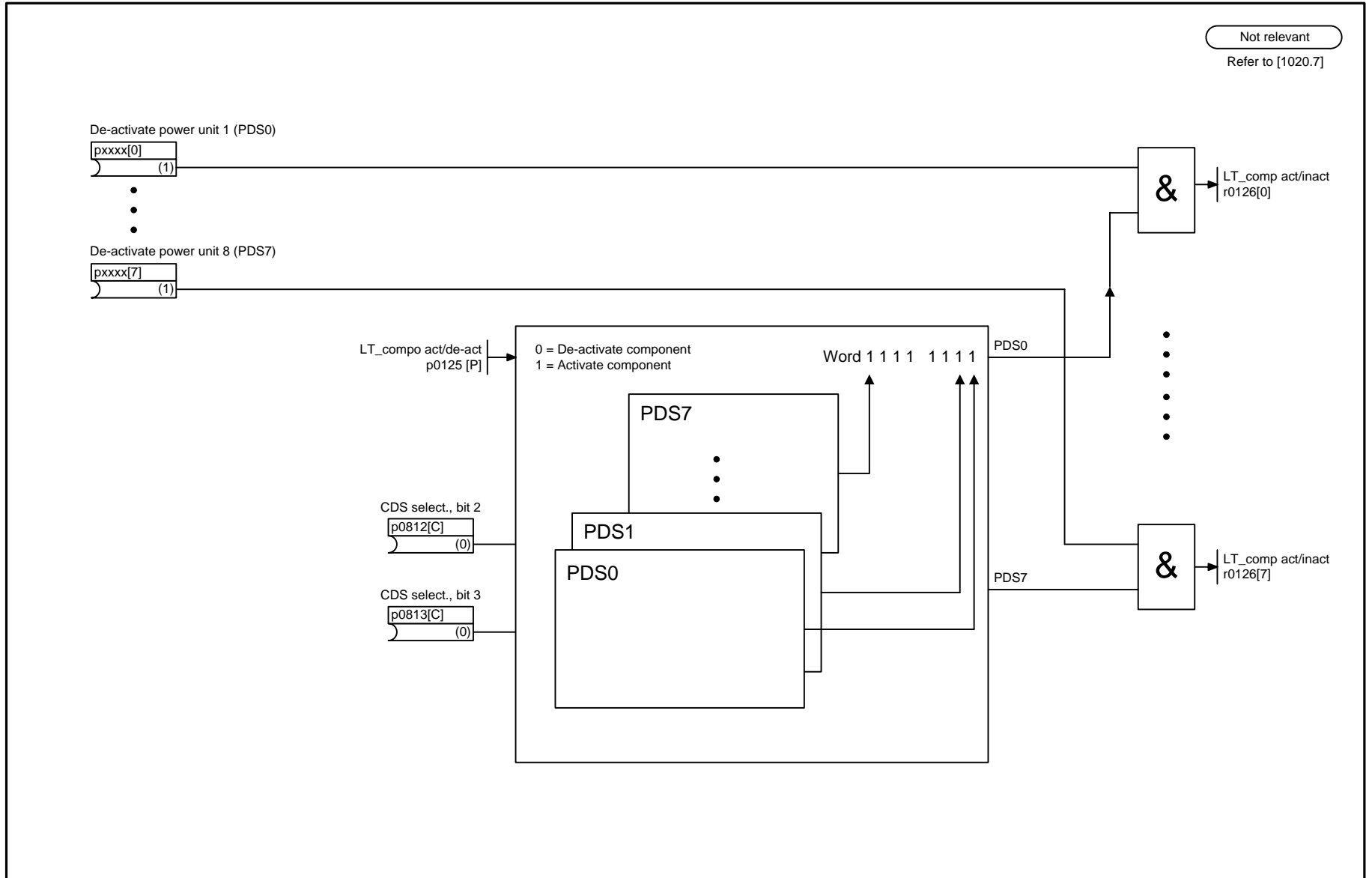


Figure 2-194 8580 – Power unit data set (PDS)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_8580_01_eng.vsd	Function diagram	
Data sets – Power unit Data Set, PDS					15.02.06 V02.04.00	SINAMICS S	
							- 8580 -

2.26 Basic Infeed

Function diagrams

8720 – Control word sequence control infeed	2-1134
8726 – Status word sequence control infeed	2-1135
8732 – Sequence control	2-1136
8734 – Missing enable signals, line contactor control	2-1137
8750 – Interface to the basic infeed power unit (control signals, actual values)	2-1138
8760 – Messages and monitoring functions (p3400.0 = 0)	2-1139

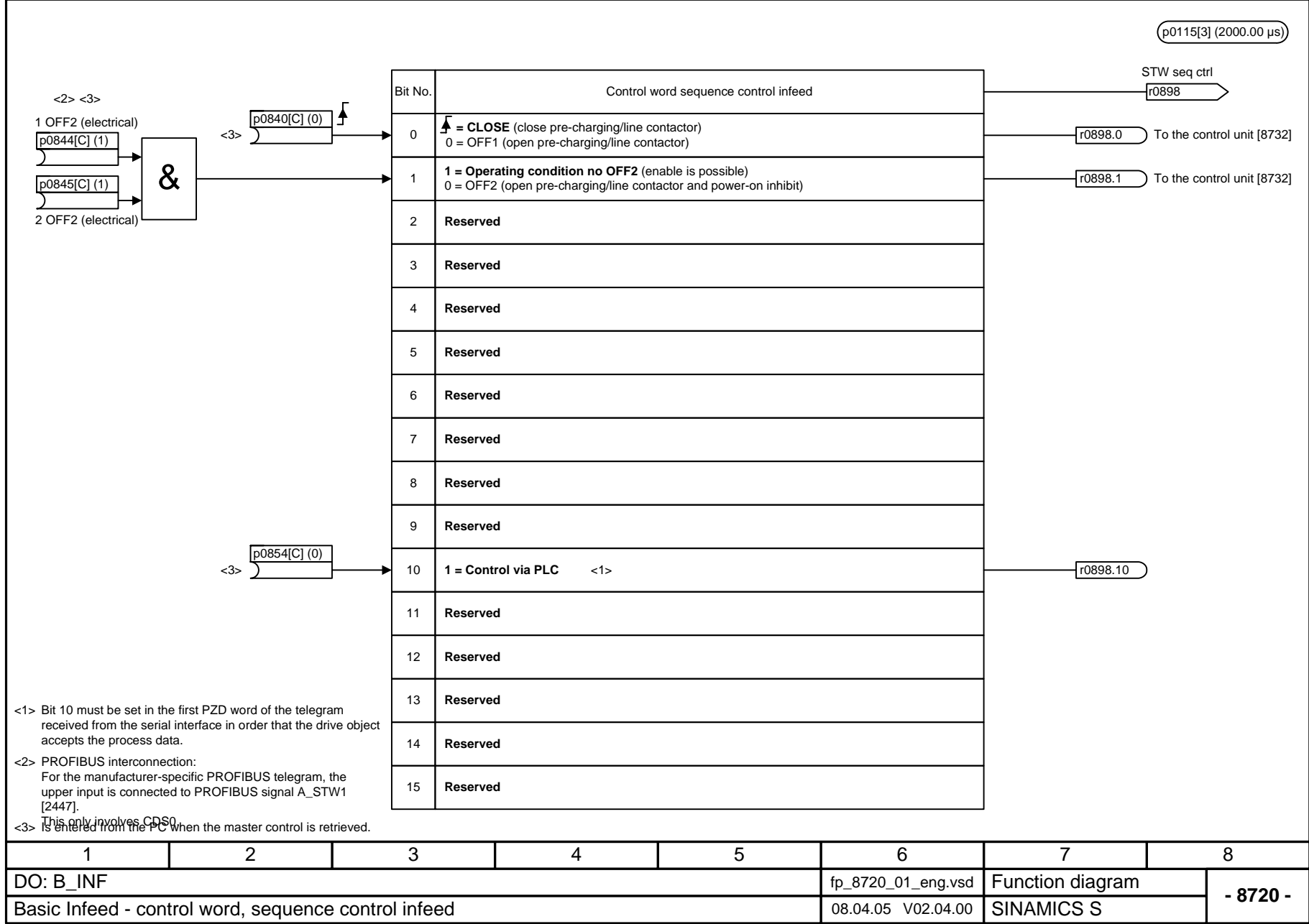
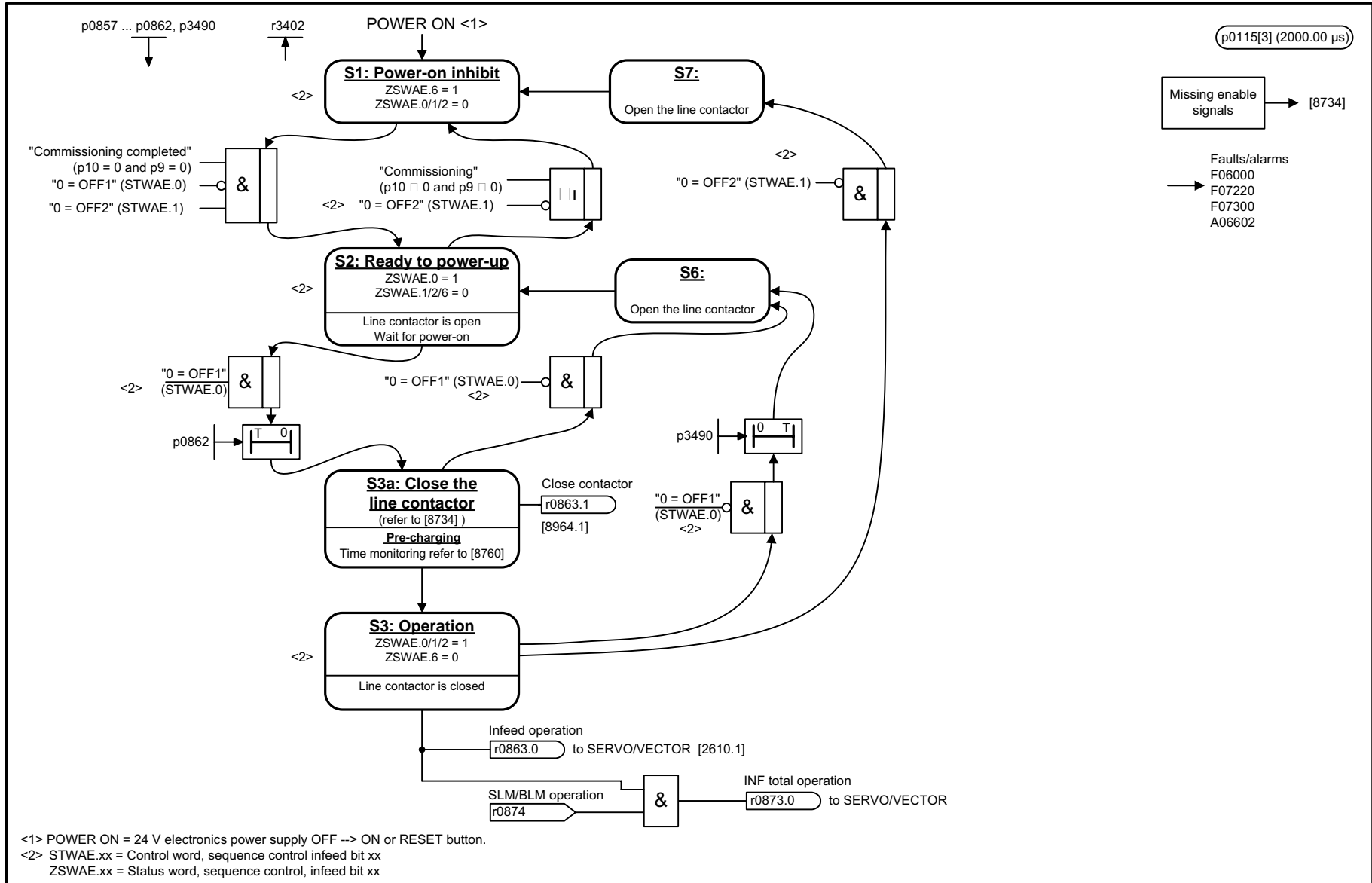


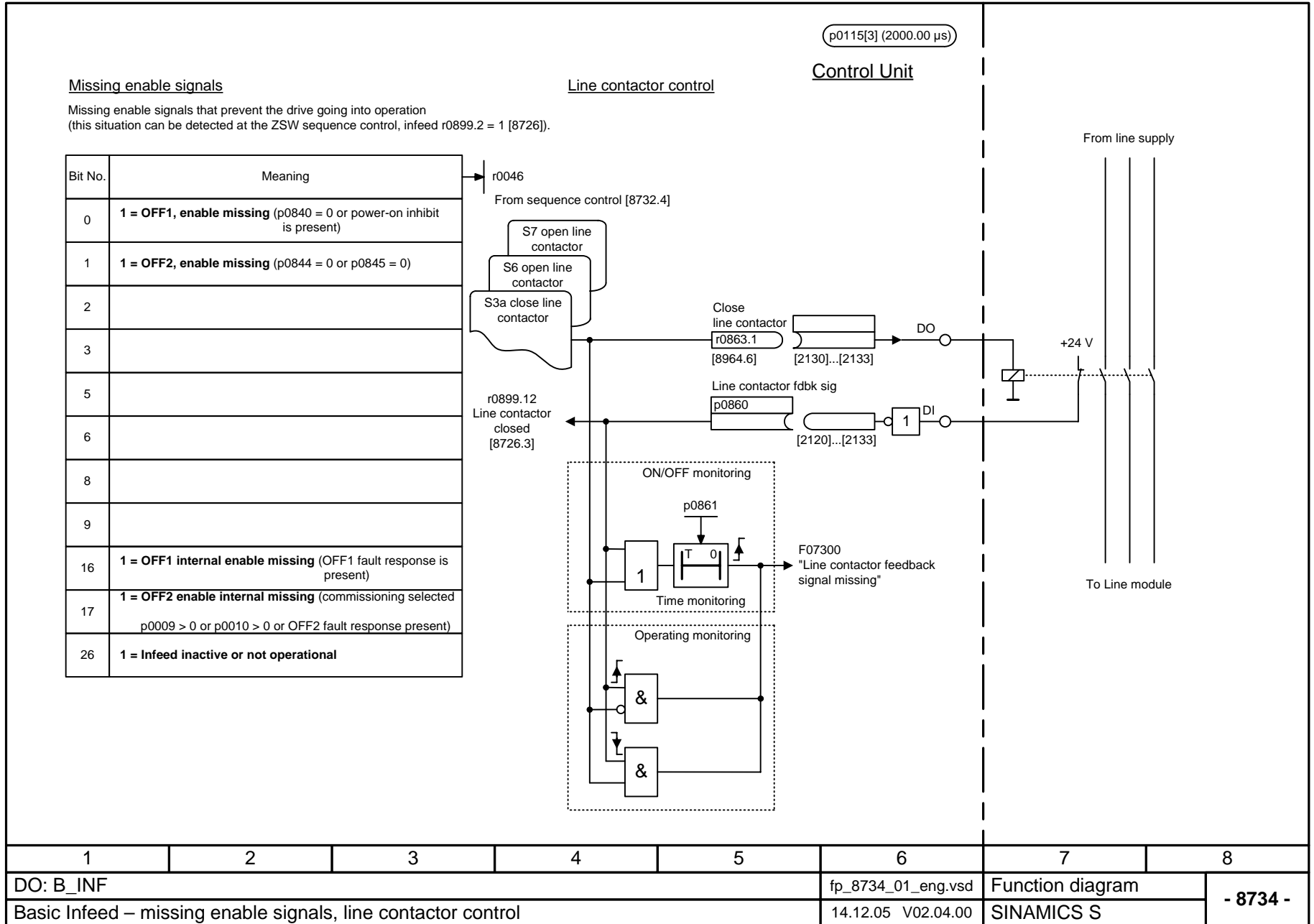
Figure 2-195 8720 – Control word sequence control infeed



1	2	3	4	5	6	7	8
DO: B_INF					fp_8732_01_eng.vsd	Function diagram	
Basic Infeed – sequence control					12.09.05 V02.04.00	SINAMICS S	
							- 8732 -

Figure 2-197 8732 – Sequence control

Figure 2-198 8734 – Missing enable signals, line contactor control



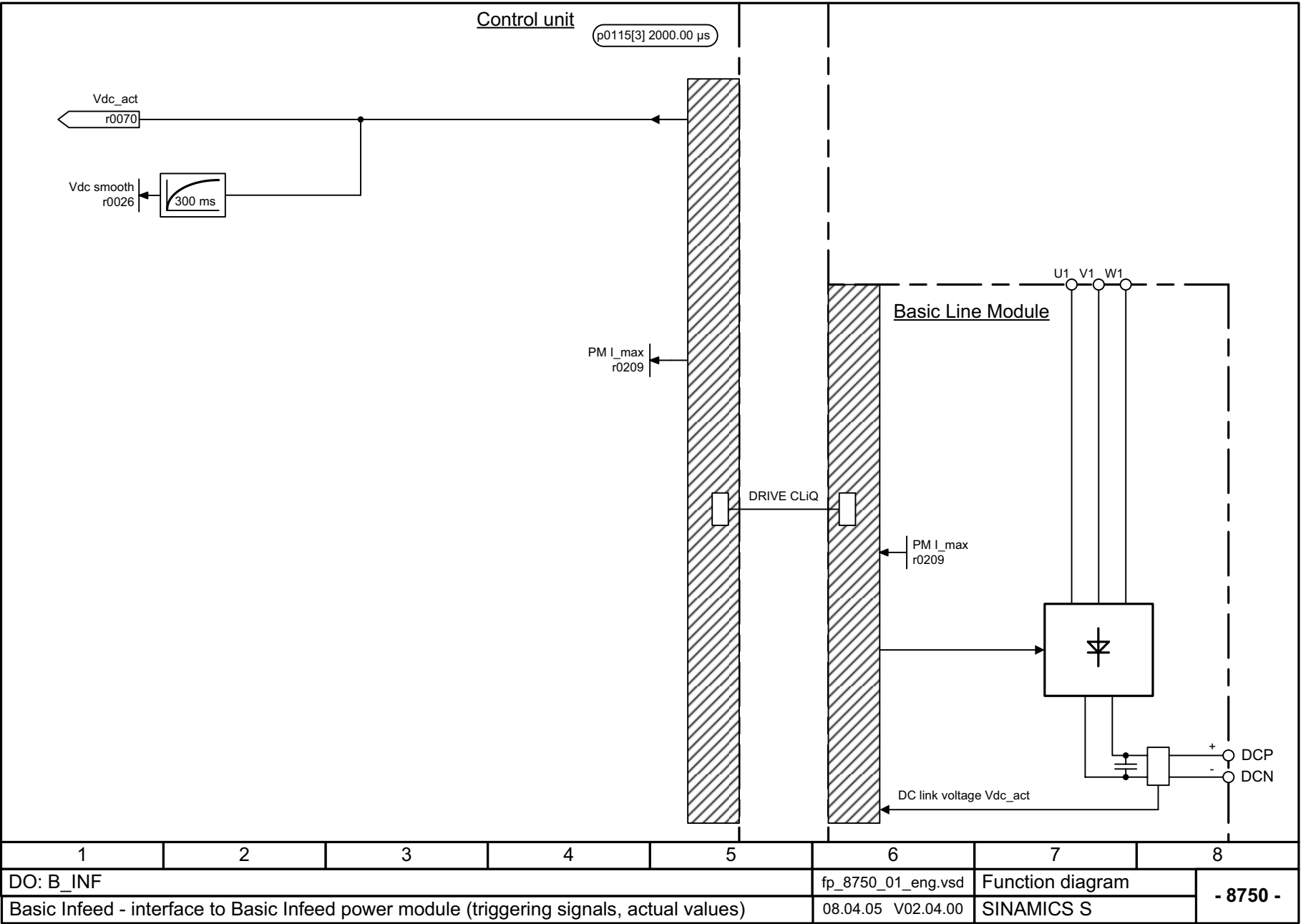
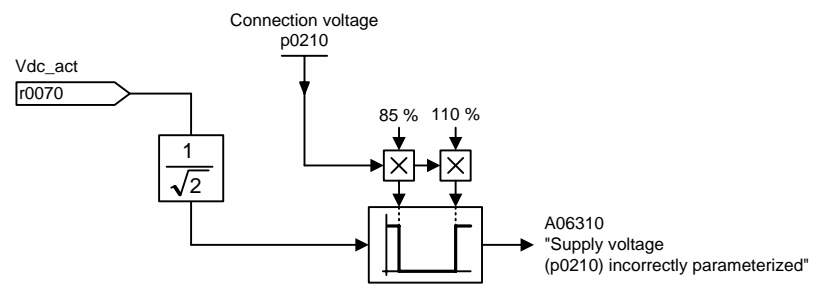


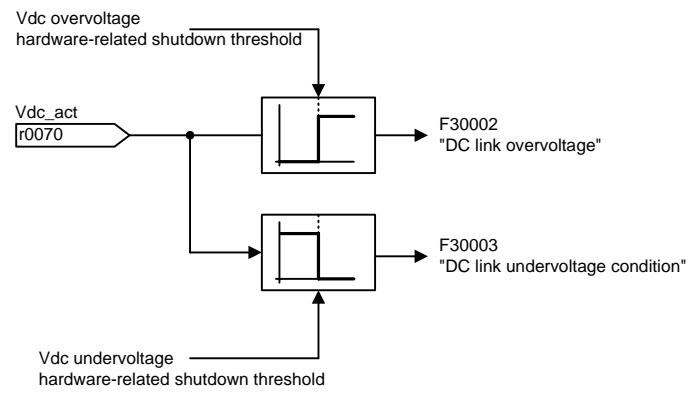
Figure 2-199 8750 – Interface to the basic Infeed power unit (control signals, actual values)

1	2	3	4	5	6	7	8
DO: B_INF					fp_8750_01_eng.vsd	Function diagram	
Basic Infeed - interface to Basic Infeed power module (triggering signals, actual values)					08.04.05 V02.04.00	SINAMICS S	
- 8750 -							

Line voltage monitoring when powering-up



DC link monitoring



Precharge monitoring for the DC link

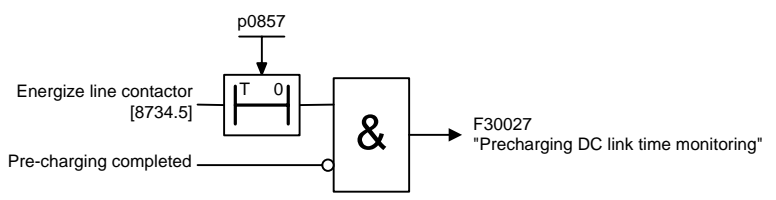


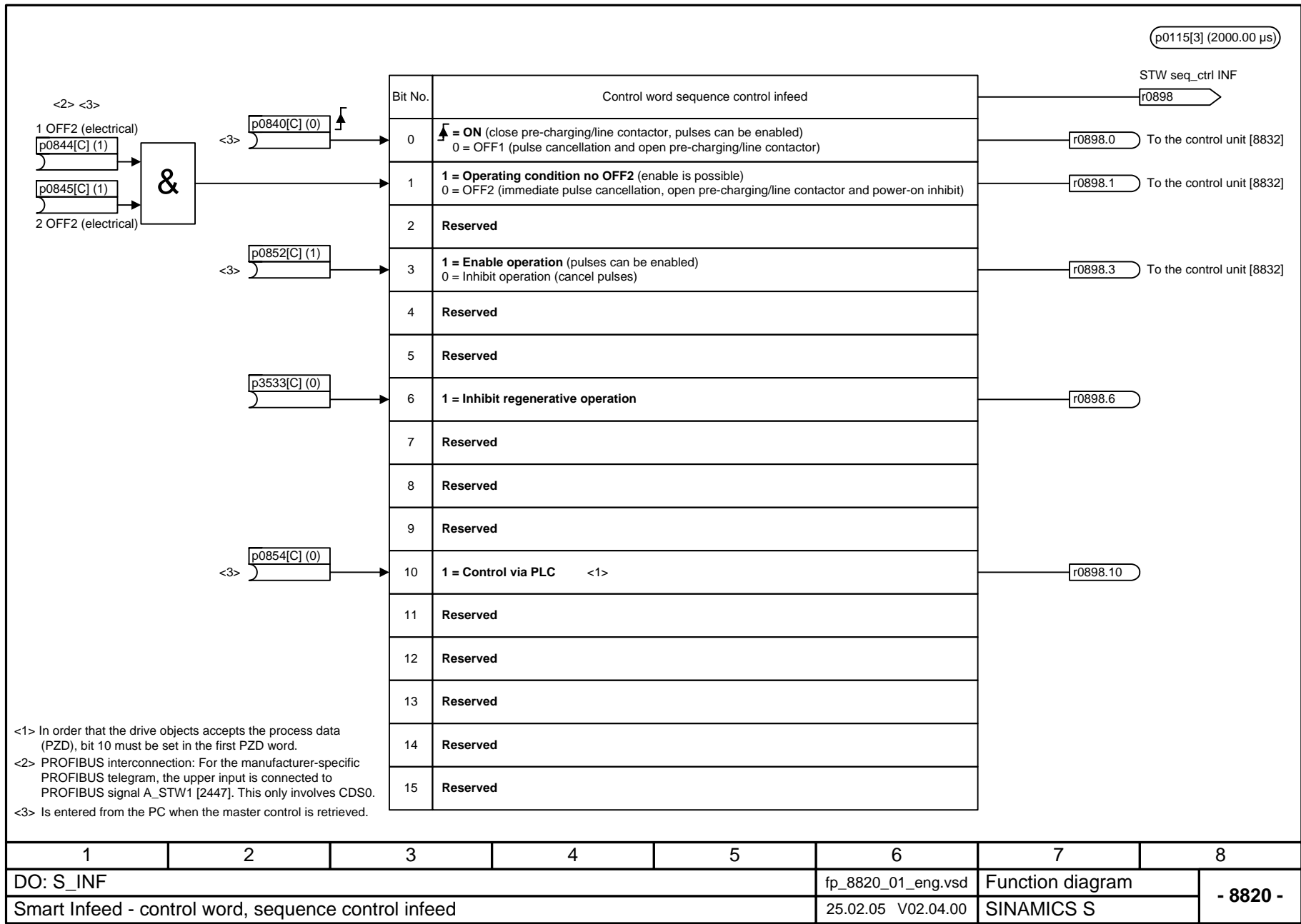
Figure 2-200 8760 – Messages and monitoring functions (p3400.0 = 0)

1	2	3	4	5	6	7	8
DO: B_INF					fp_8760_01_eng.vsd	Function diagram	
Basic infeed - messages/signals and monitoring functions (p3400.0 = 0)					12.04.05 V02.04.00	SINAMICS S	
							- 8760 -

2.27 Smart Infeed

Function diagrams

8820 – Control word sequence control infeed	2-1141
8826 – Status word sequence control infeed	2-1142
8828 – Status word infeed	2-1143
8832 – Sequence control	2-1144
8834 – Missing enable signals, line contactor control	2-1145
8850 – Interface to the smart infeed (gating signals, actual values)	2-1146
8860 – Messages/signals and monitoring functions, line supply voltage monitoring	2-1147
8864 – Messages/signals and monit. fcts., line supply frequency and Vdc monitoring	2-1148



1	2	3	4	5	6	7	8
DO: S_INF					fp_8820_01_eng.vsd	Function diagram	
Smart Infeed - control word, sequence control infeed					25.02.05 V02.04.00	SINAMICS S	
							- 8820 -

Figure 2-201 8820 – Control word sequence control infeed

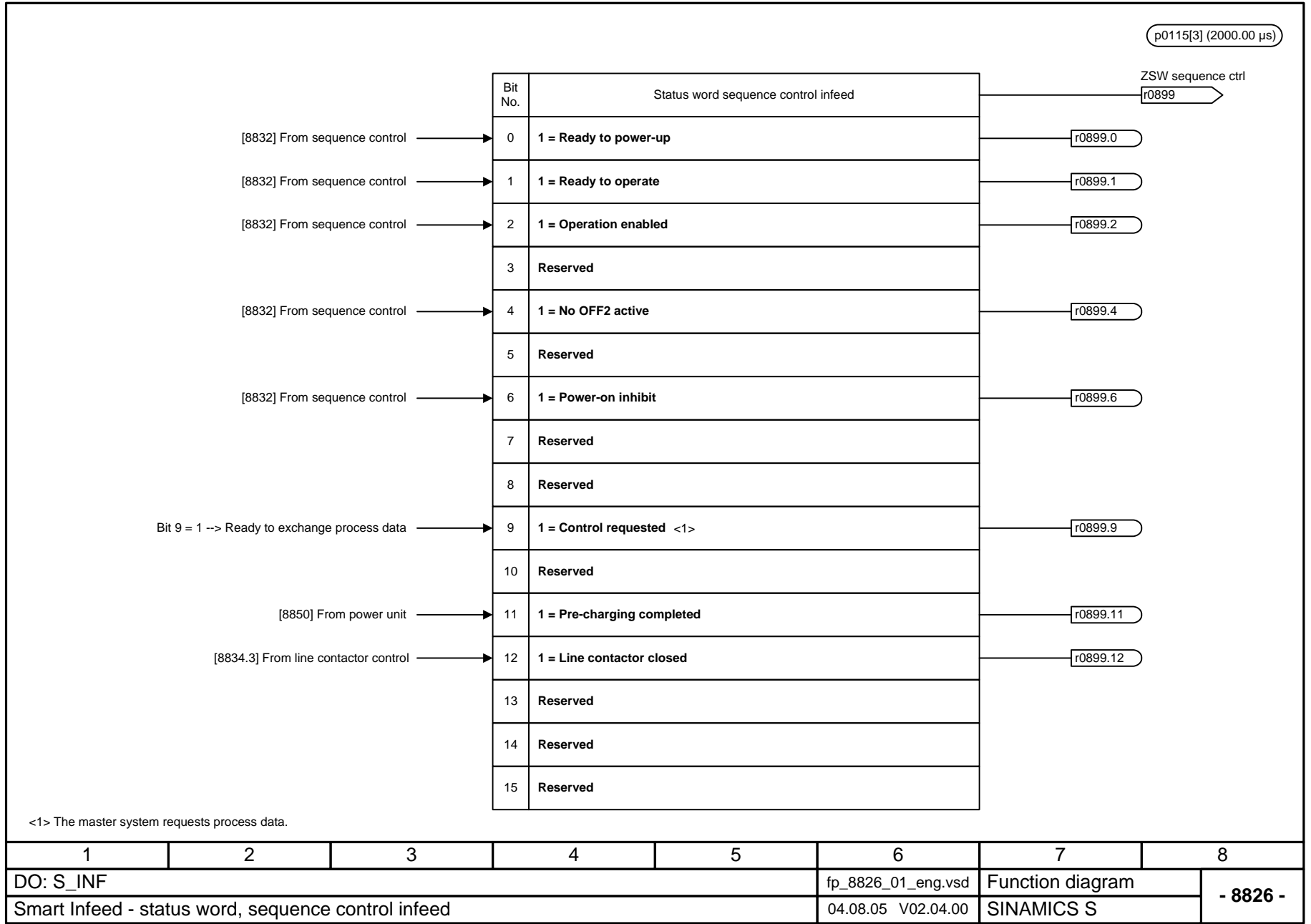


Figure 2-202 8826 – Status word sequence control infeed

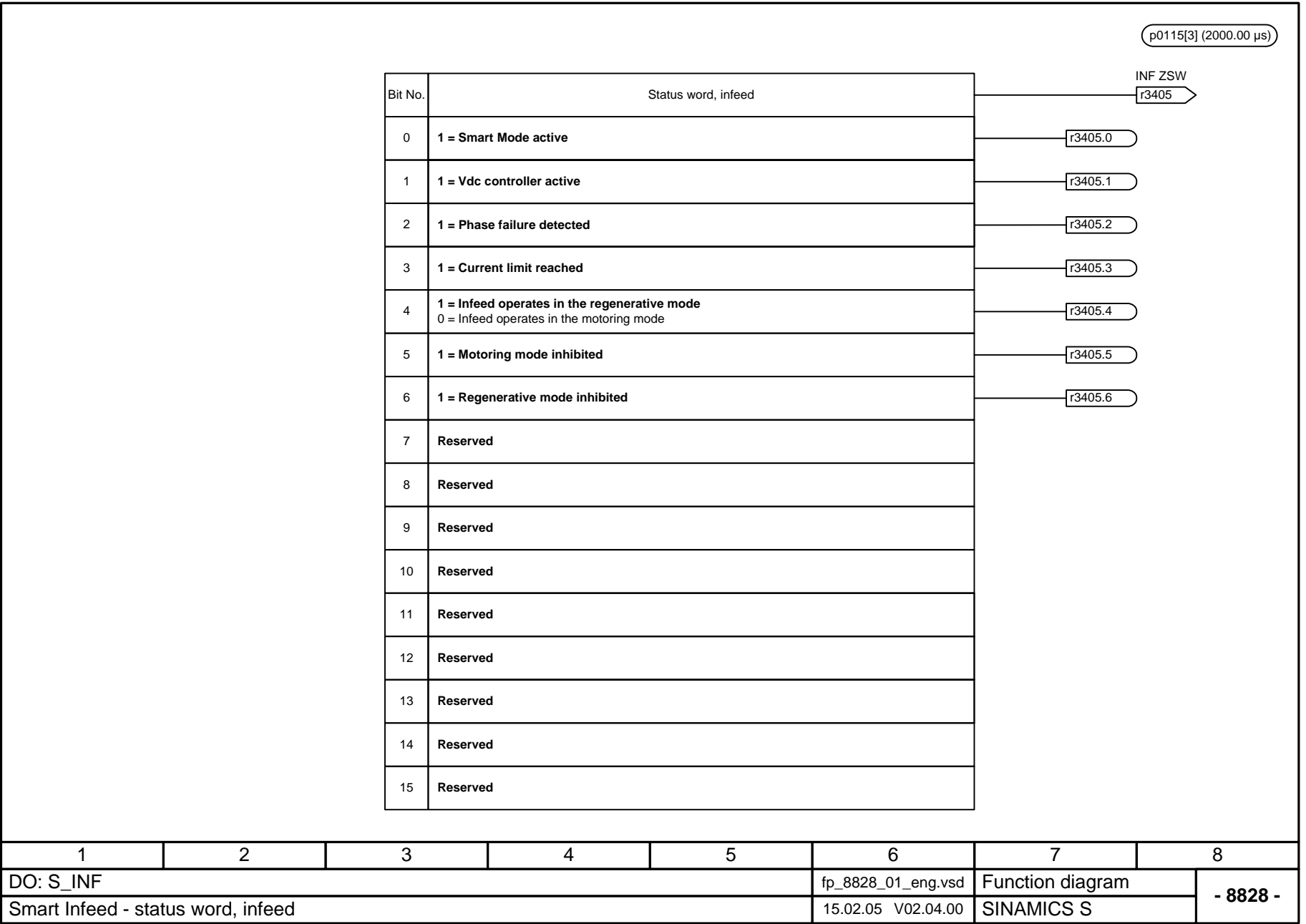
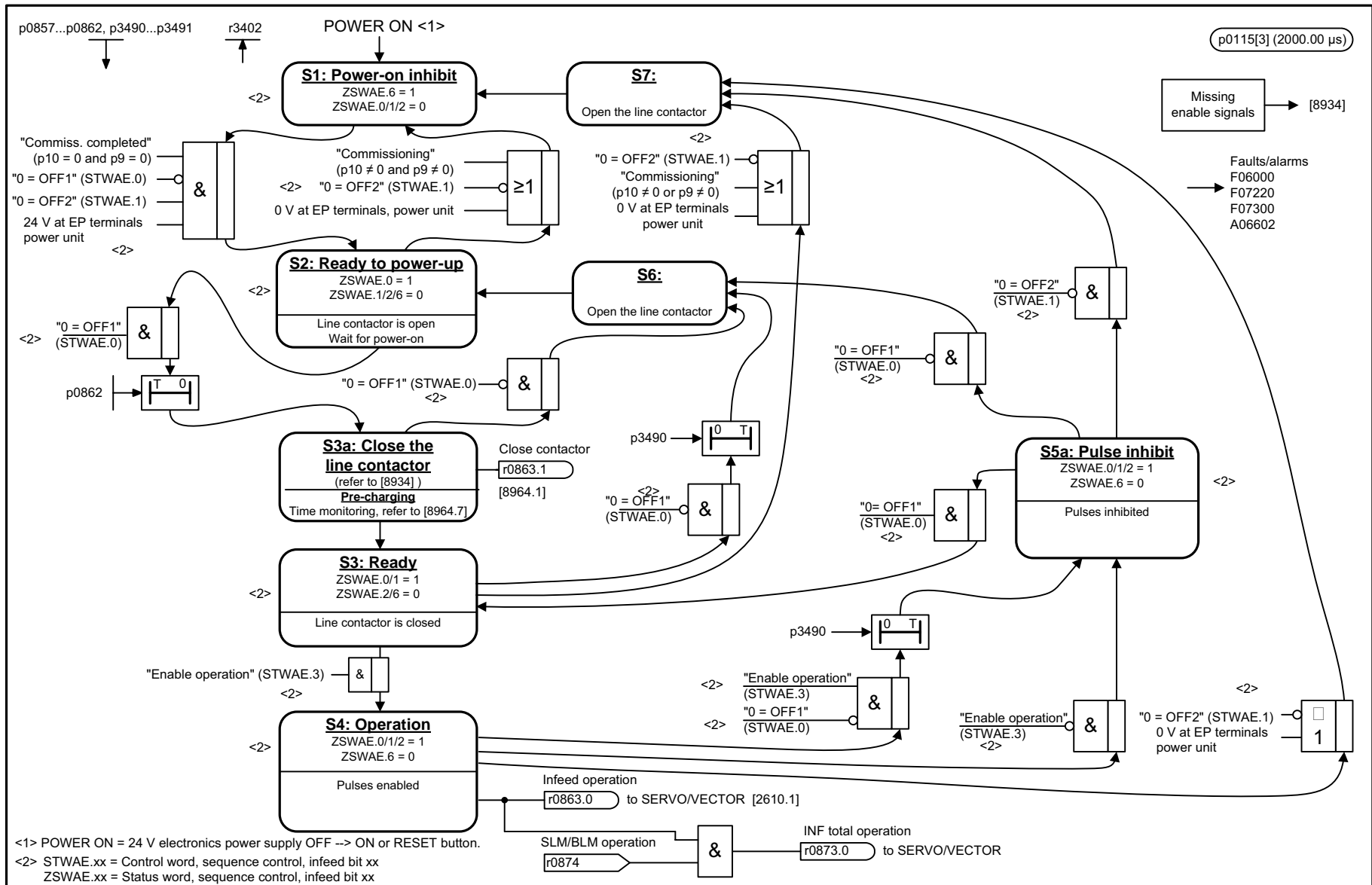


Figure 2-203 8828 – Status word infeed

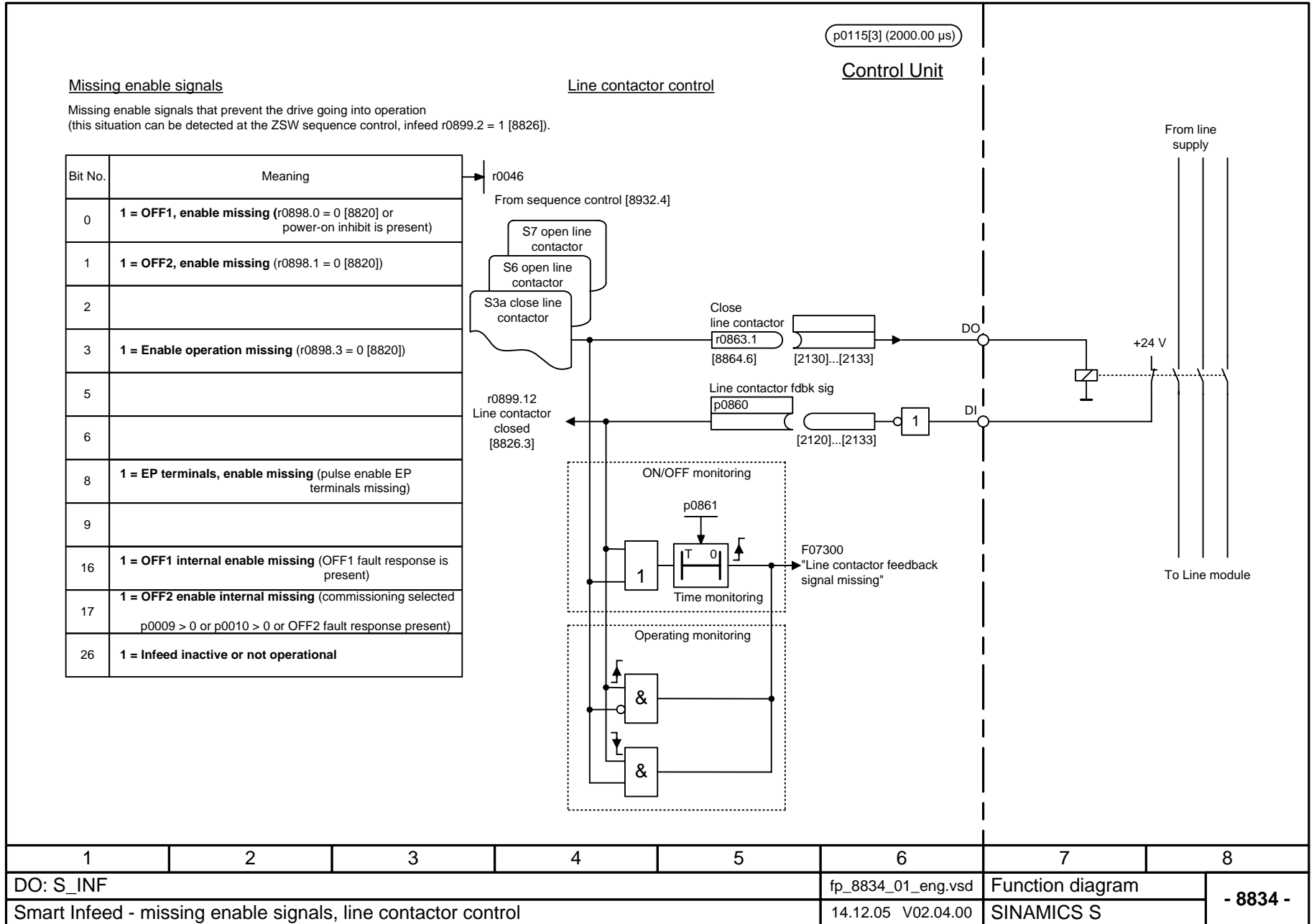


<1> POWER ON = 24 V electronics power supply OFF -> ON or RESET button.
 <2> STWAE.xx = Control word, sequence control, infeed bit xx
 ZSWAE.xx = Status word, sequence control, infeed bit xx

1	2	3	4	5	6	7	8
DO: S_INF					fp_8832_01_eng.vsd	Function diagram	
Smart infeed - sequence control					12.09.05 V02.04.00	SINAMICS S	
							- 8832 -

Figure 2-204 8832 – Sequence control

Figure 2-205 8834 – Missing enable signals, line contactor control



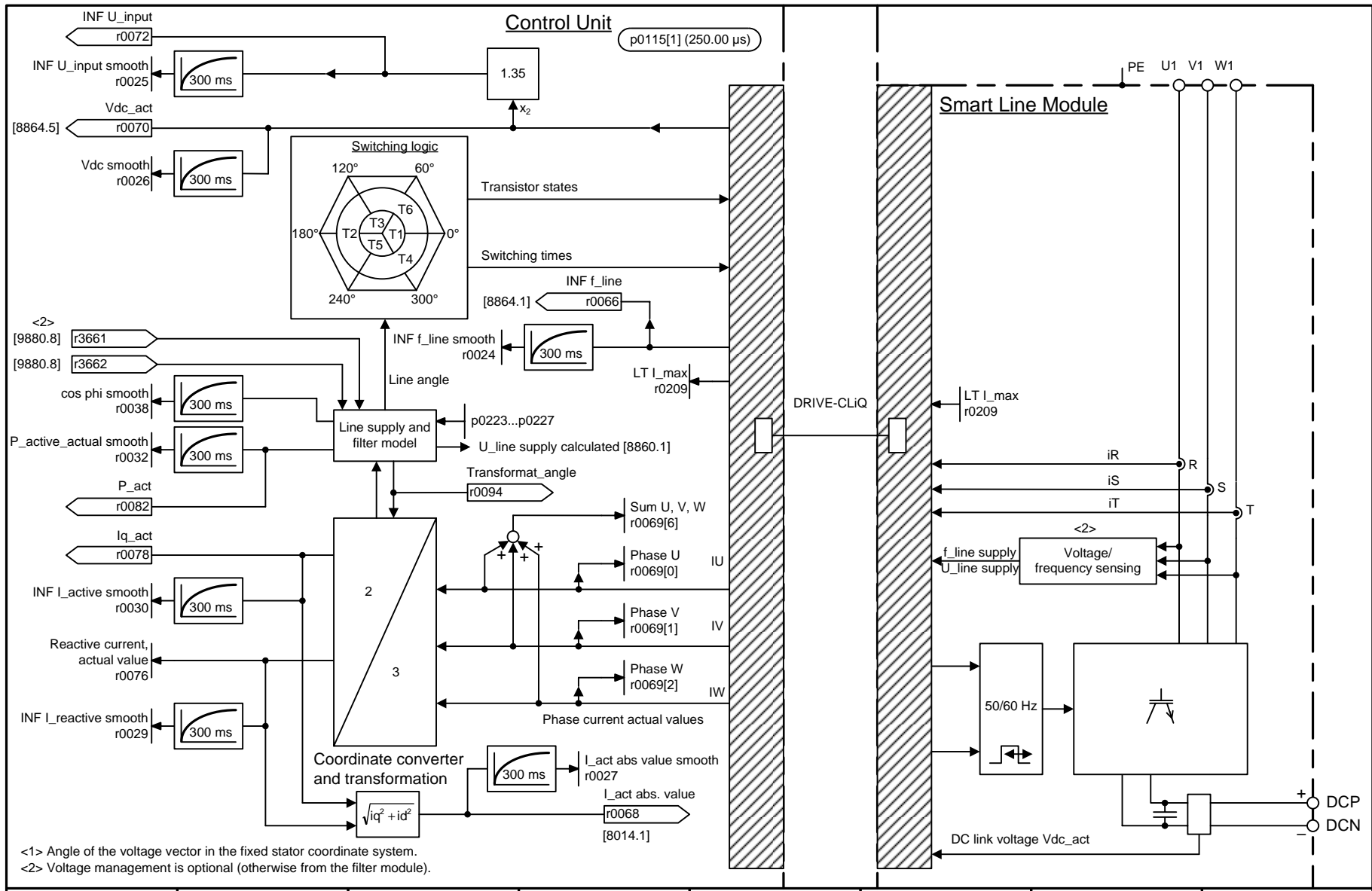


Figure 2-206 8850 – Interface to the smart infeed (gating signals, actual values)

1	2	3	4	5	6	7	8
DO: S_INF					fp_8850_01_eng.vsd	Function diagram	
Smart infeed - interface to the smart infeed (gating signals, actual values)					15.11.05 V02.04.00	SINAMICS S	
- 8850 -							

p0115[3] (2000.00 μs)

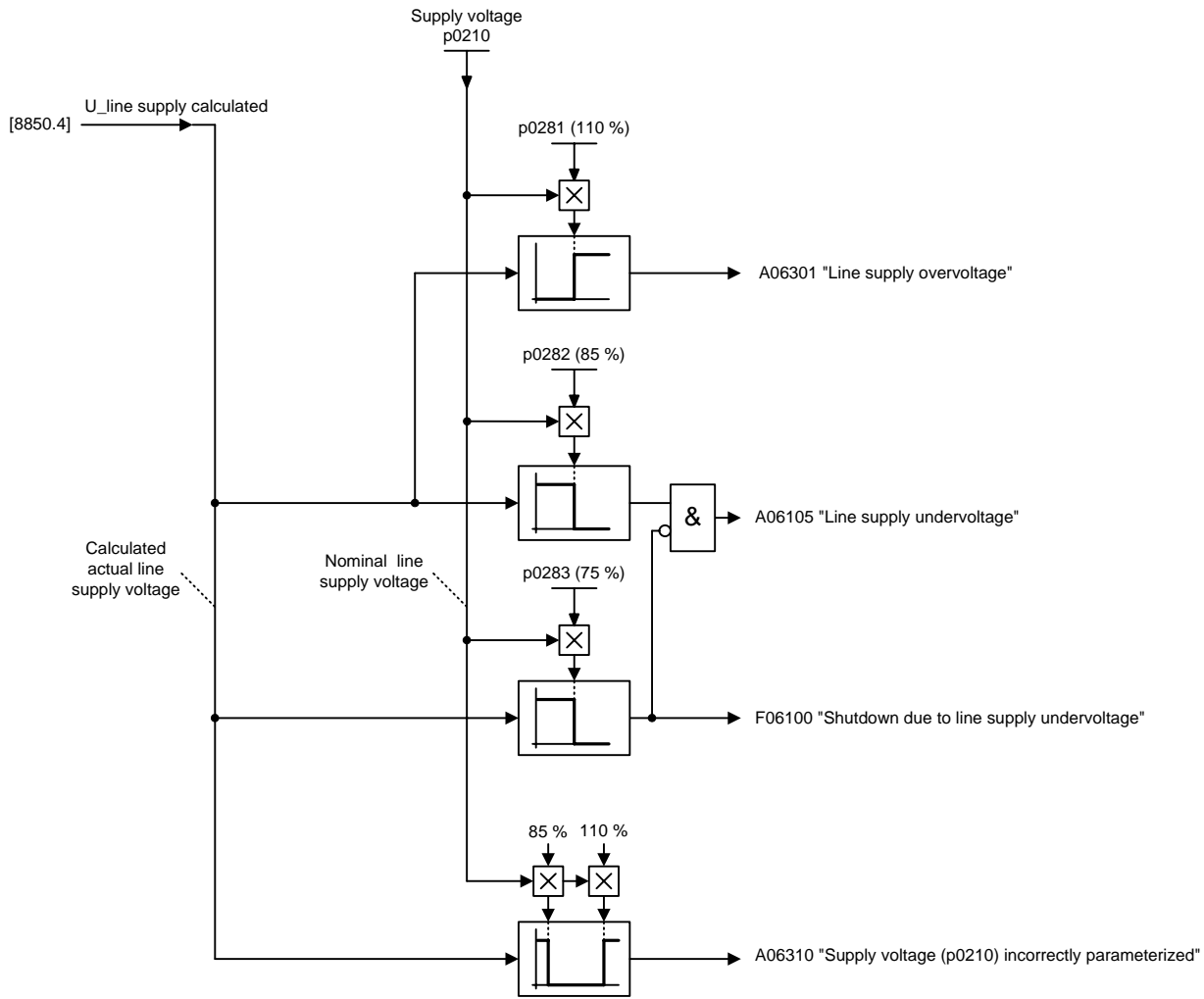
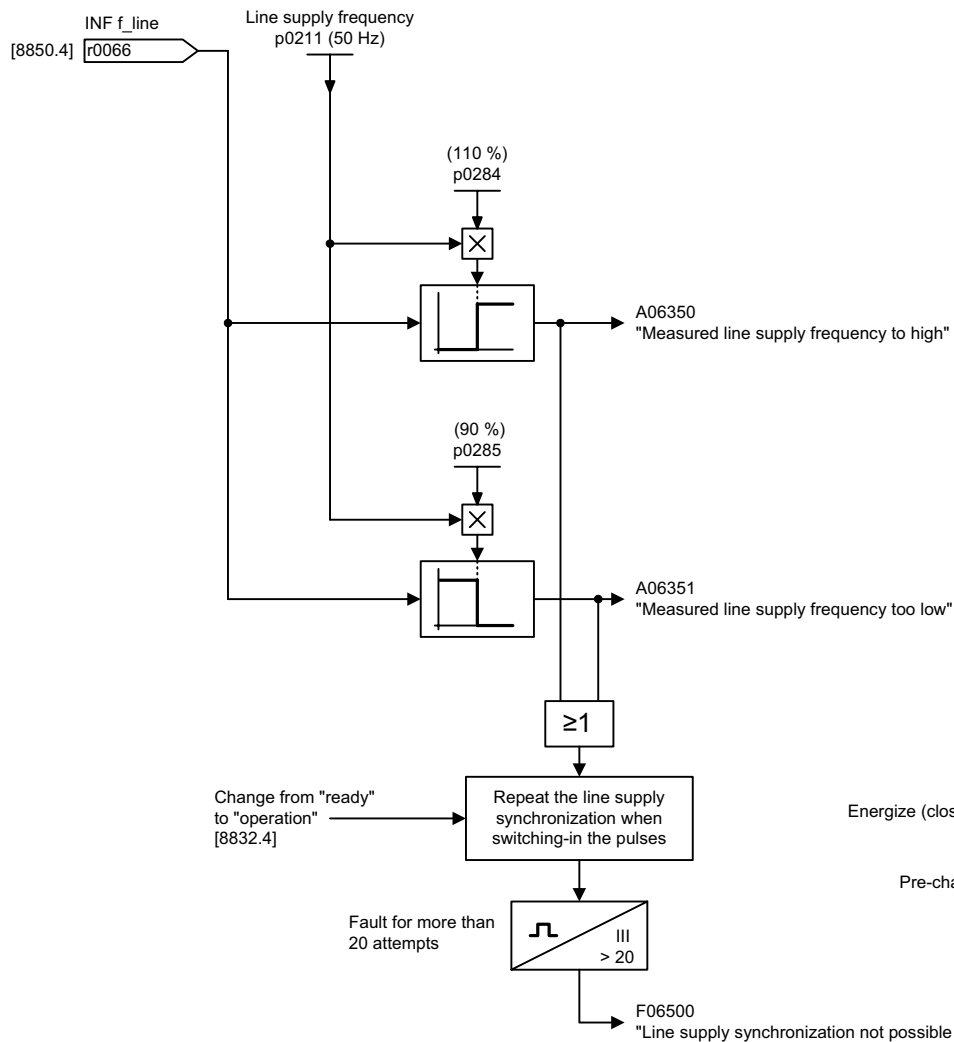


Figure 2-207 8860 – Messages/signals and monitoring functions, line supply voltage monitoring

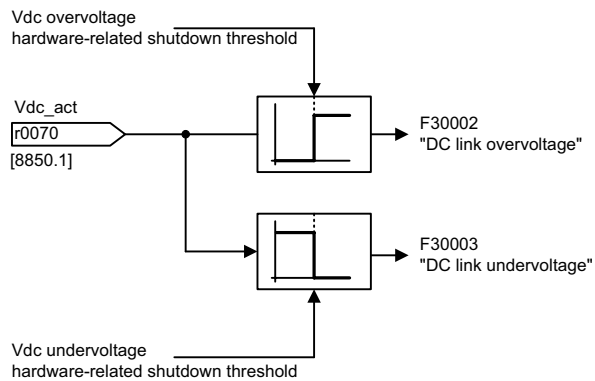
1	2	3	4	5	6	7	8
DO: S_INF					fp_8860_01_eng.vsd	Function diagram	
Smart infeed - messages/signals and monitoring functions, line supply voltage monitoring					13.05.05 V02.04.00	SINAMICS S	
							- 8860 -

p0115[3] (2000.00 μs)

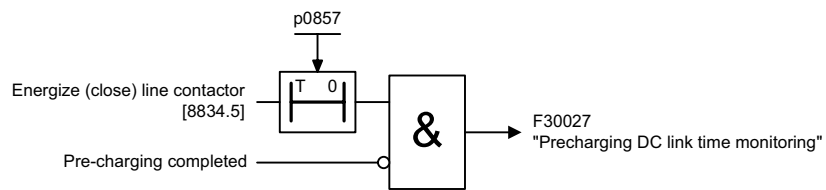
Line frequency monitoring



DC link monitoring



Precharging monitoring for the DC link



1	2	3	4	5	6	7	8
DO: S_INF					fp_8864_01_eng.vsd	Function diagram	
Smart infeed - messages/signals and monit. fcts., line supply frequency & Vdc monitoring					12.05.05 V02.04.00	SINAMICS S	
- 8864 -							

Figure 2-208 8864 – Messages/signals and monit. fcts., line supply frequency and Vdc monitoring

2.28 Active Infeed

Function diagrams

8920 – Control word sequence control infeed	2-1150
8926 – Status word sequence control infeed	2-1151
8928 – Status word infeed	2-1152
8932 – Sequence control	2-1153
8934 – Missing enable signals, line contactor control	2-1154
8940 – Controller control factor reserve/controller DC link voltage (p3400.0 = 0)	2-1155
8946 – Current pre-control/current controller/gating unit (p3400.0 = 0)	2-1156
8950 – Interface to the active infeed (gating signals, actual values) (p3400.0 = 0)	2-1157
8960 – Messages/signals and monit. fcts., line supply voltage monit. (p3400.0 = 0)	2-1158
8964 – Messages/signals and monit. fcts., line frequency and Vdc monit. (p3400.0 = 0)	2-1159

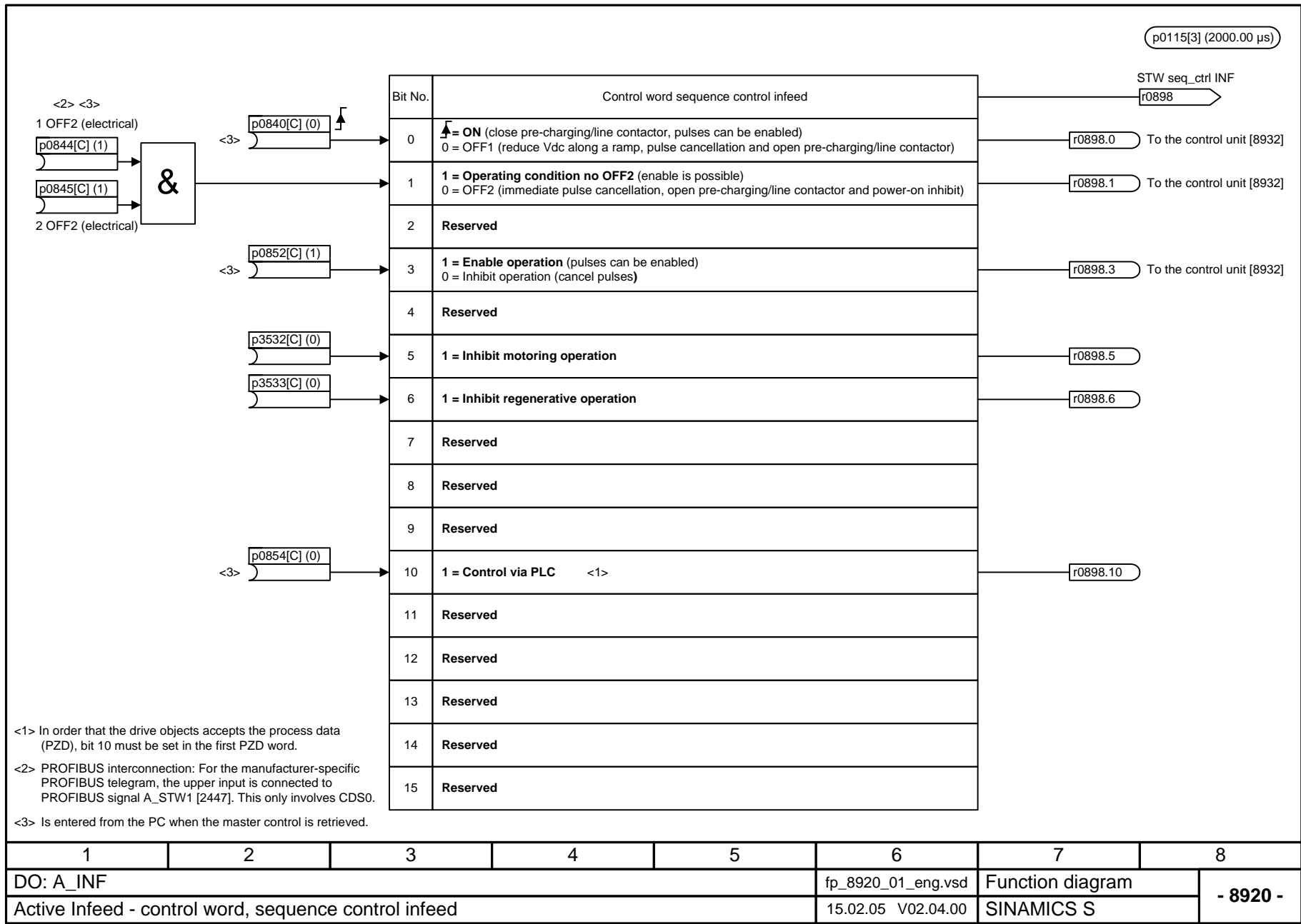


Figure 2-209 8920 – Control word sequence control infeed

1	2	3	4	5	6	7	8
DO: A_INF					fp_8920_01_eng.vsd	Function diagram	
Active Infeed - control word, sequence control infeed					15.02.05 V02.04.00	SINAMICS S	
							- 8920 -

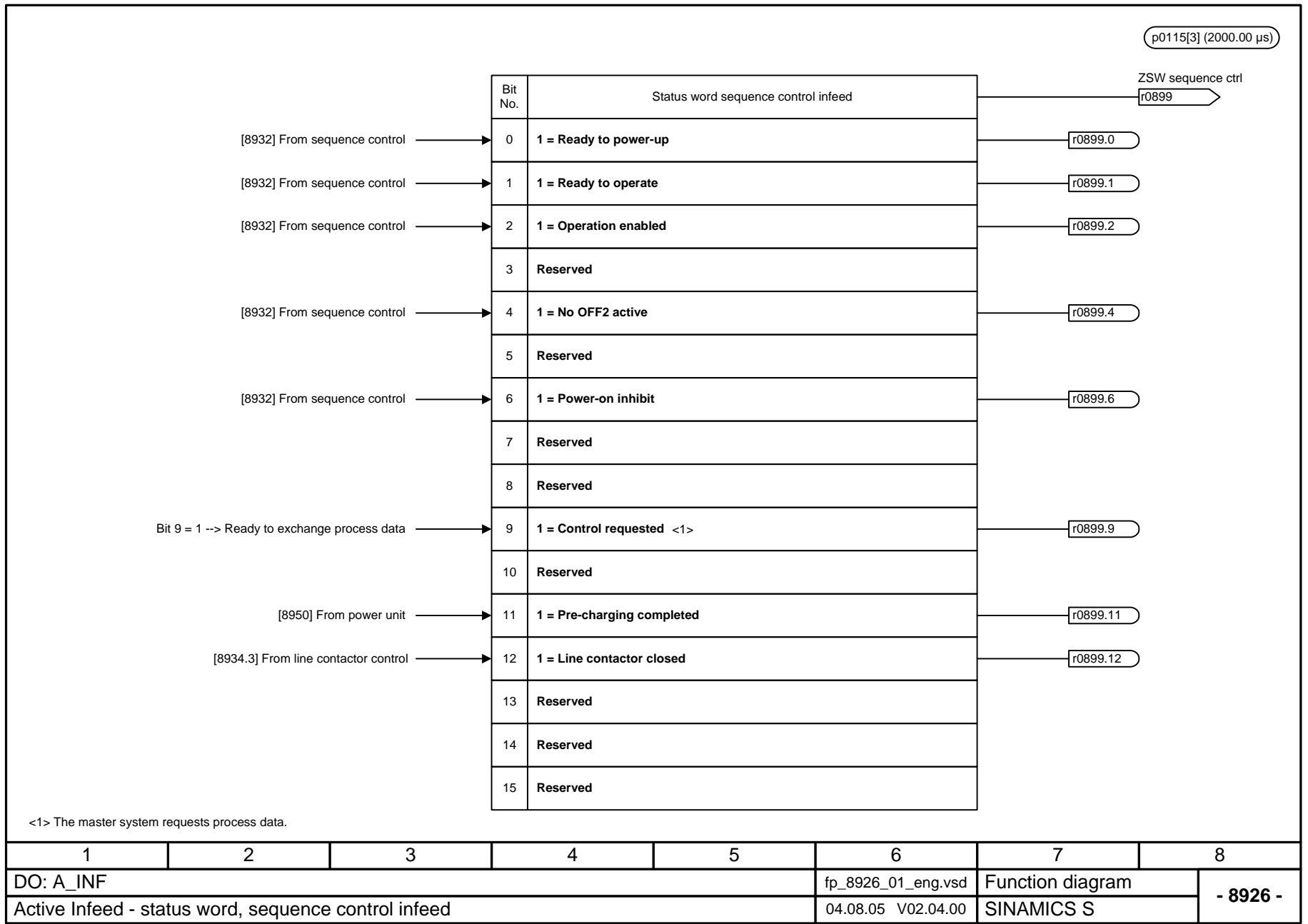


Figure 2-210 8926 – Status word sequence control infeed

1	2	3	4	5	6	7	8
DO: A_INF					fp_8926_01_eng.vsd	Function diagram	
Active Infeed - status word, sequence control infeed					04.08.05 V02.04.00	SINAMICS S	
							- 8926 -

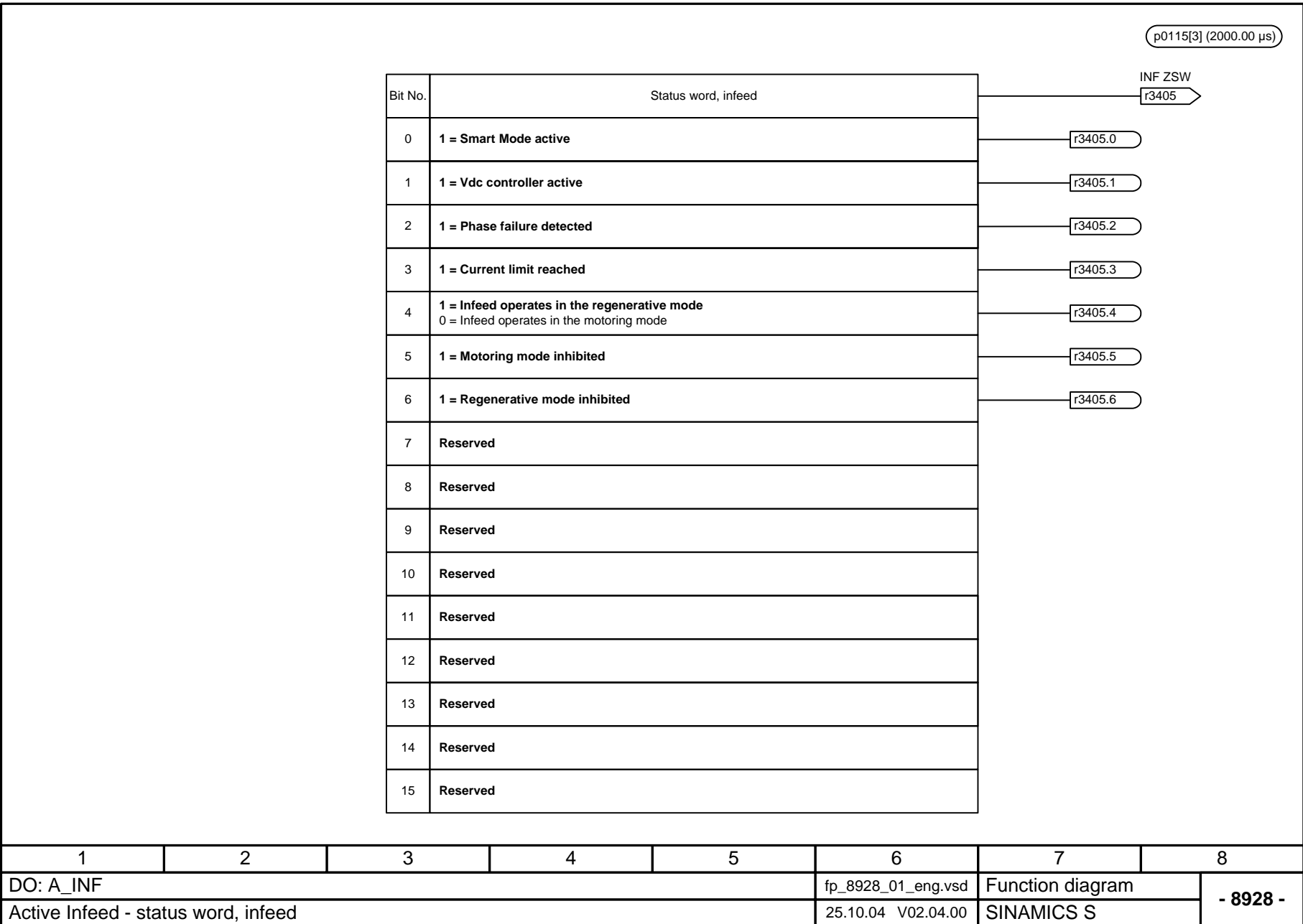
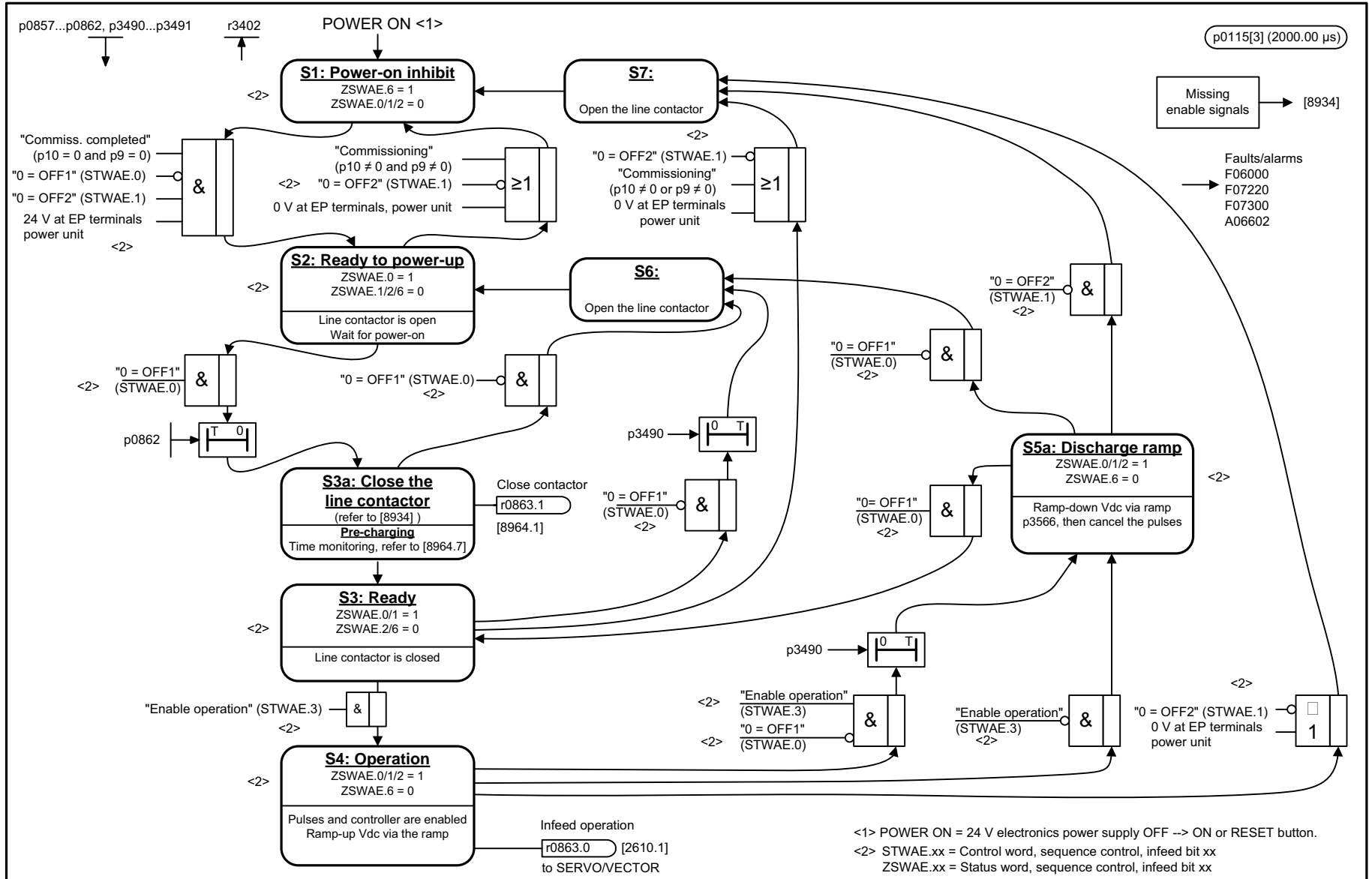


Figure 2-211 8928 – Status word infeed

Figure 2-212 8932 – Sequence control



1	2	3	4	5	6	7	8
DO: A_INF					fp_8932_01_eng.vsd	Function diagram	
Active infeed - sequence control					12.09.05 V02.04.00	SINAMICS S	
							- 8932 -

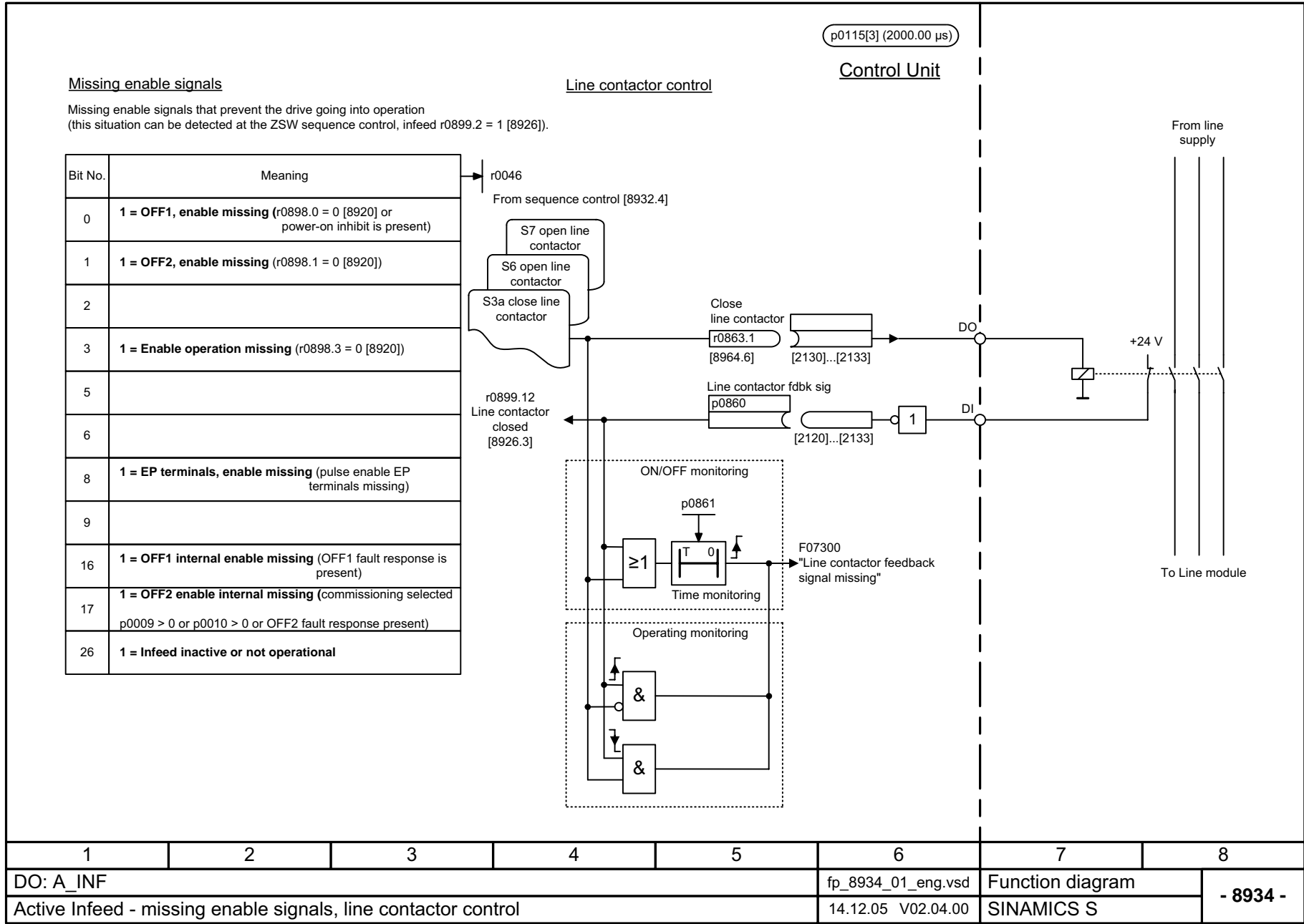
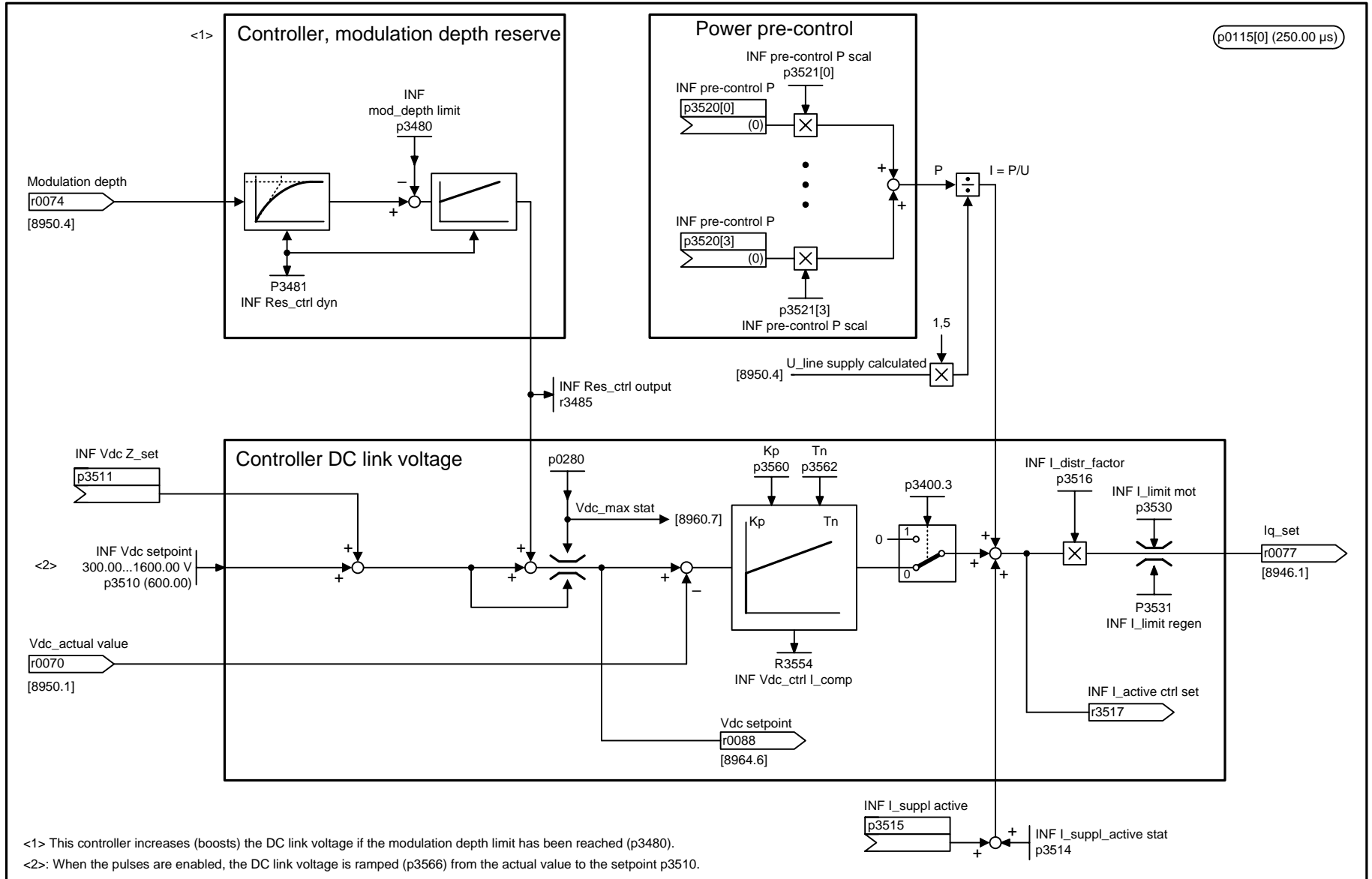


Figure 2-213 8934 – Missing enable signals, line contactor control

Figure 2-214 8940 – Controller control factor reserve/controller DC link voltage (p3400.0 = 0)



1	2	3	4	5	6	7	8
DO: A_INF					fp_8940_01_eng.vsd	Function diagram	
Active infeed - controller modulation depth reserve/controller DC link voltage (p3400.0 = 0)					03.02.06 V02.04.00	SINAMICS S	
							- 8940 -

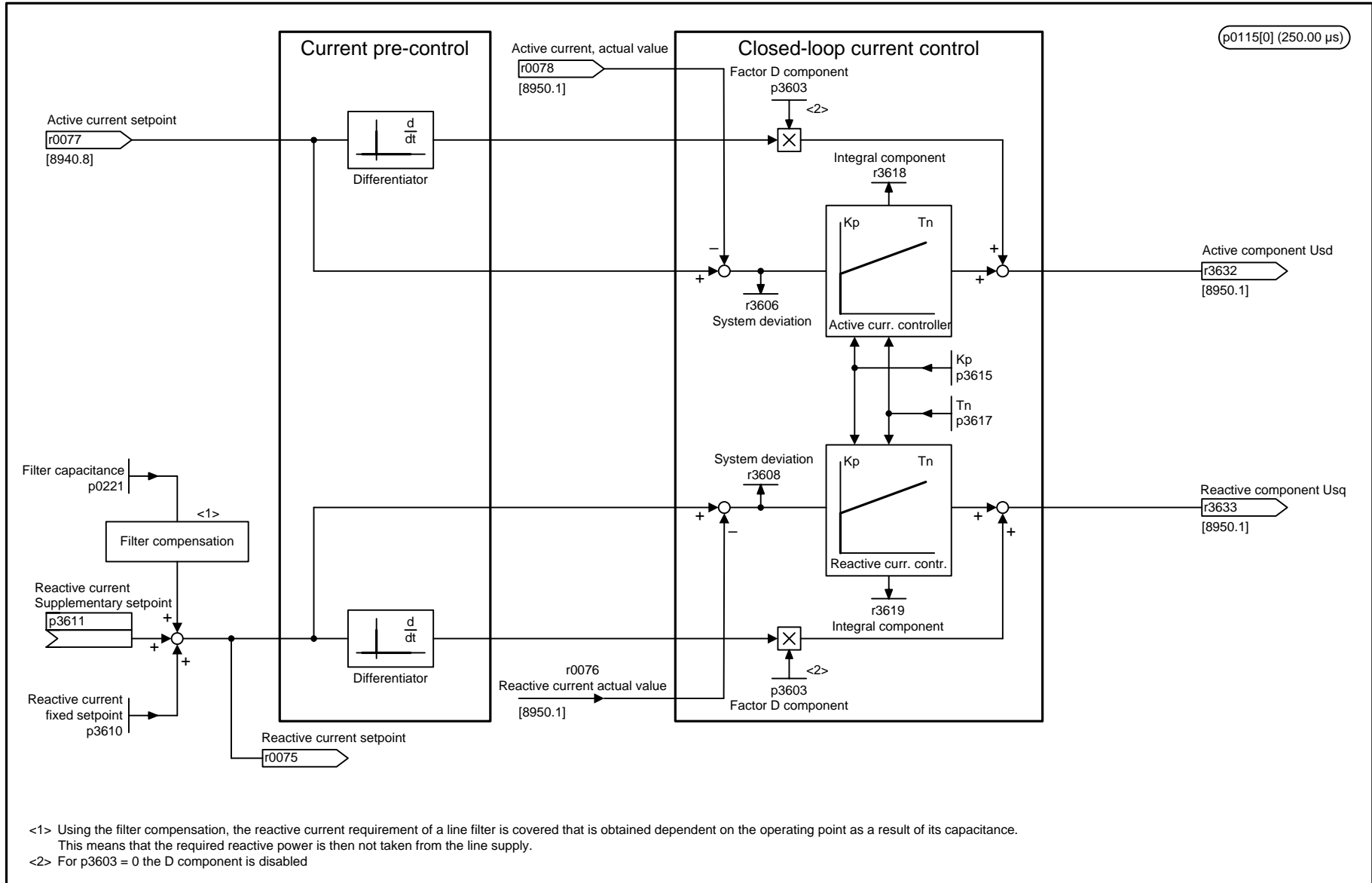
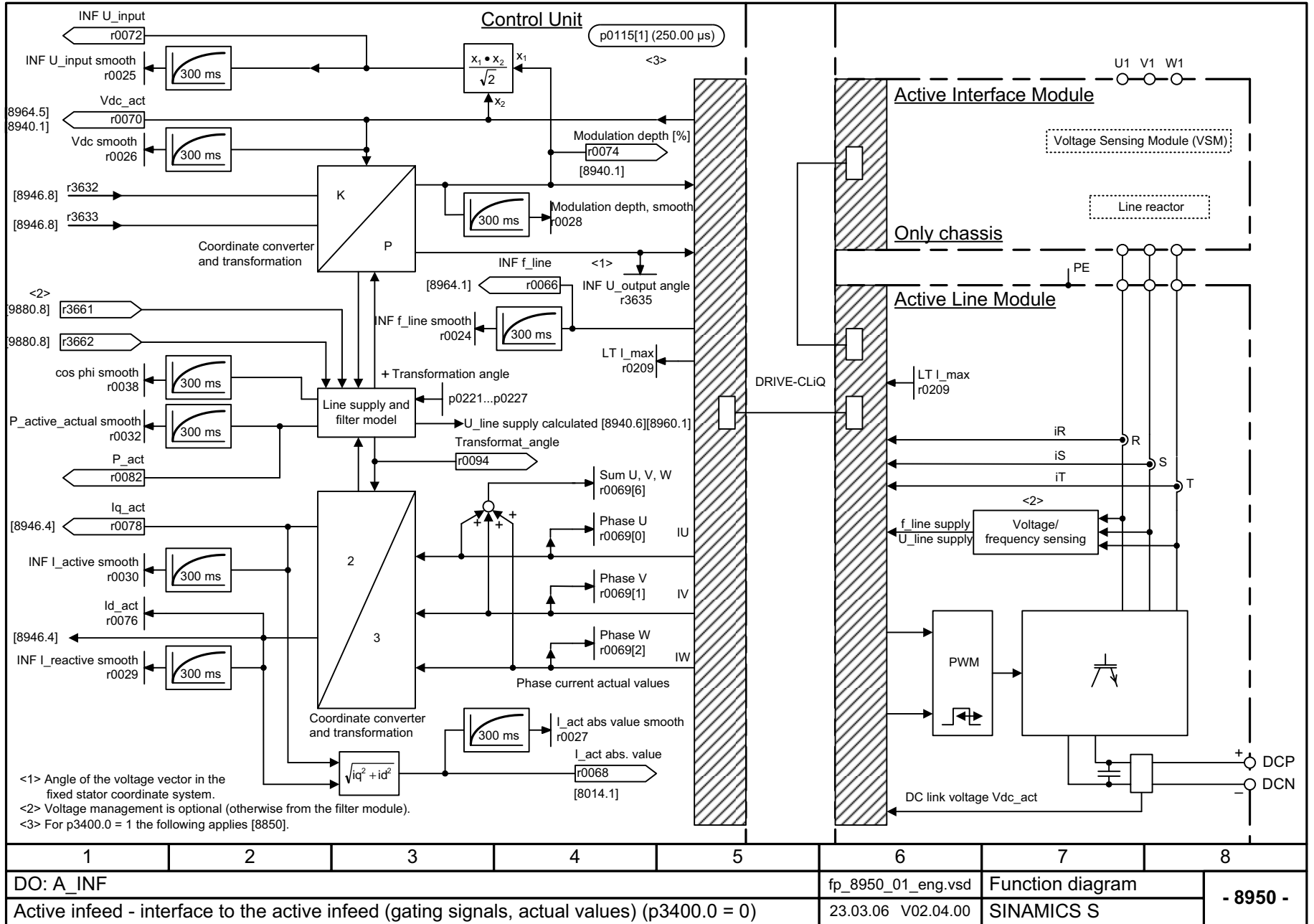
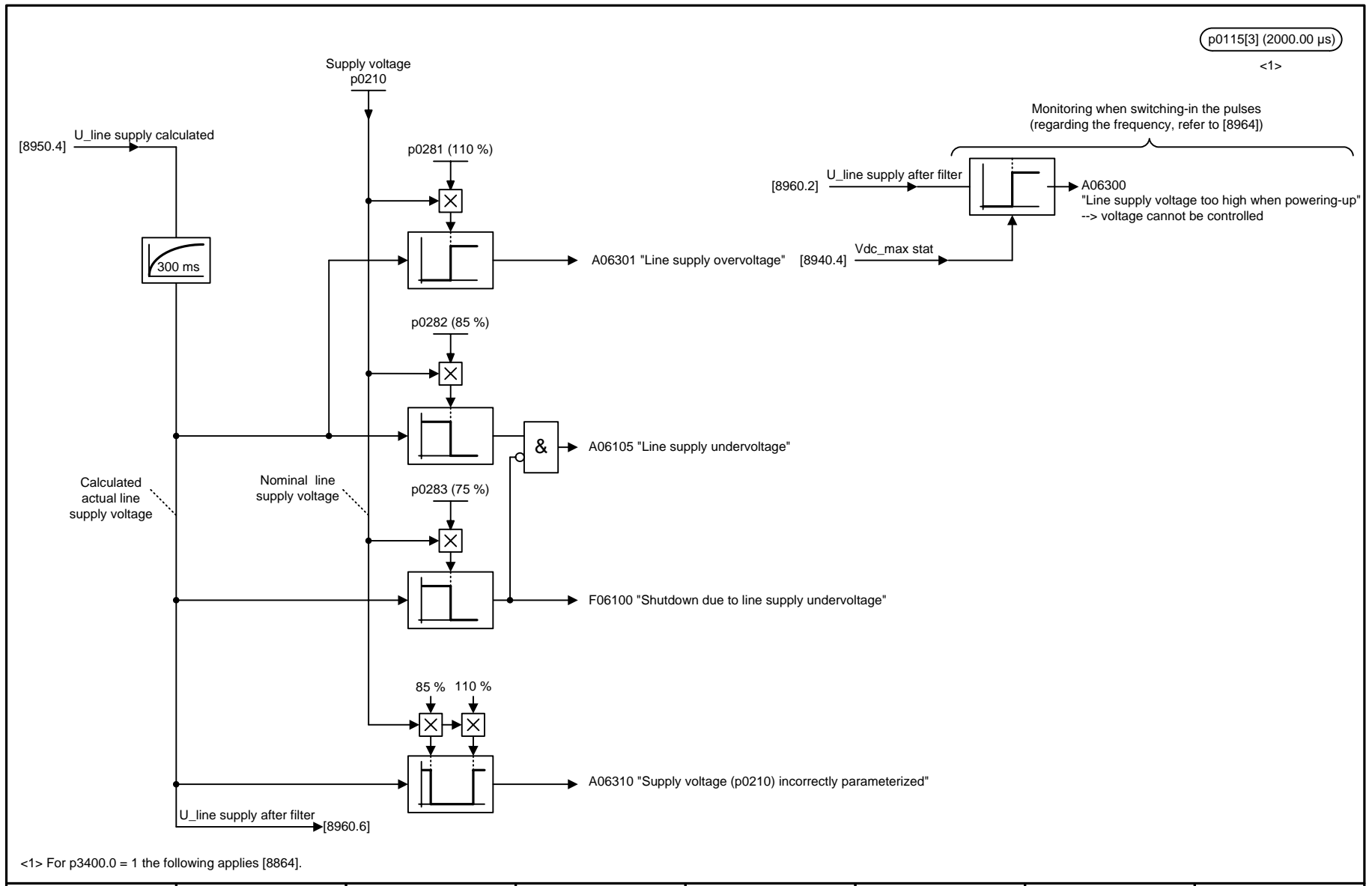


Figure 2-215 8946 – Current pre-control/current controller/gating unit (p3400.0 = 0)

1	2	3	4	5	6	7	8
DO: A_INF					fp_8946_01_eng.vsd	Function diagram	
Active infeed - power pre-control/current controller/gating unit (p3400.0 = 0)					13.04.05 V02.04.00	SINAMICS S	
							- 8946 -

Figure 2-216 8950 – Interface to the active infeed (gating signals, actual values) (p3400.0 = 0)





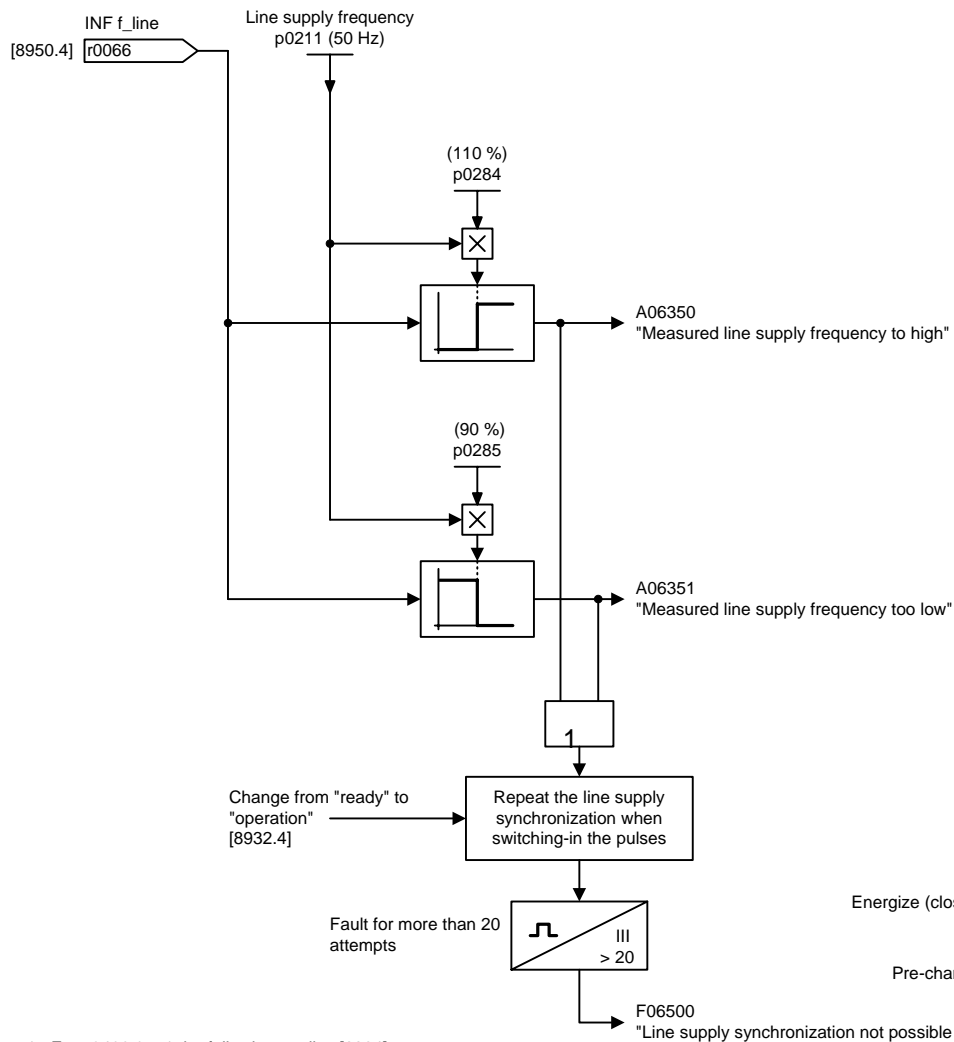
1	2	3	4	5	6	7	8
DO: A_INF					fp_8960_01_eng.vsd	Function diagram	
Active infeed - signals and monitoring functions, line supply voltage monitoring (p3400.0 = 0)					13.05.05 V02.04.00	SINAMICS S	
							- 8960 -

Figure 2-217 8960 – Messages/signals and monit. fcts., line supply voltage monit. (p3400.0 = 0)

p0115[3] (2000.00 μs)

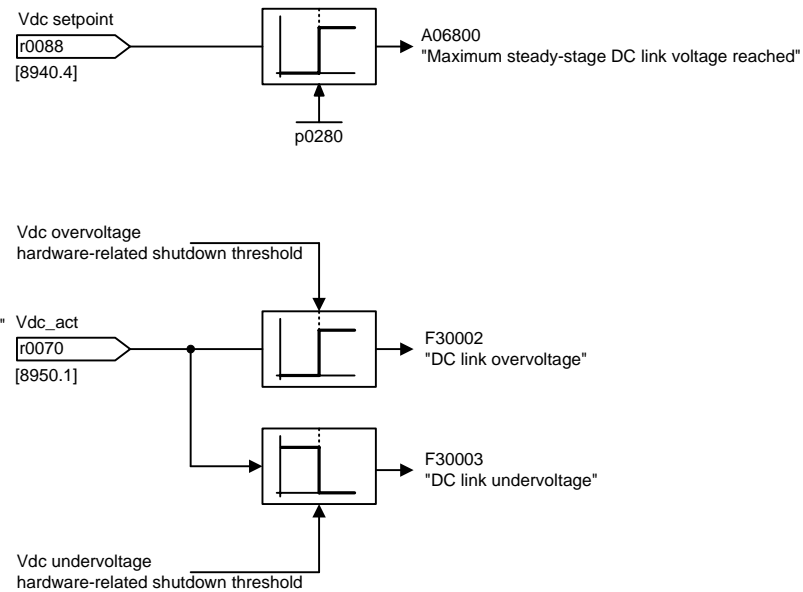
<1>

Line frequency monitoring



<1> For p3400.0 = 1 the following applies [8864].

DC link monitoring



Precharging monitoring for the DC link

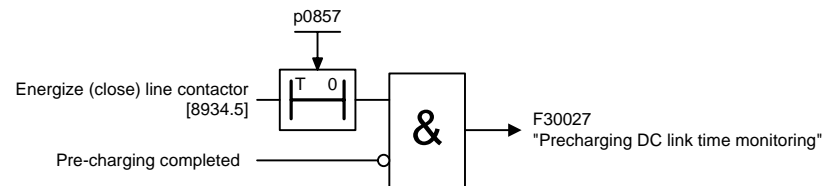


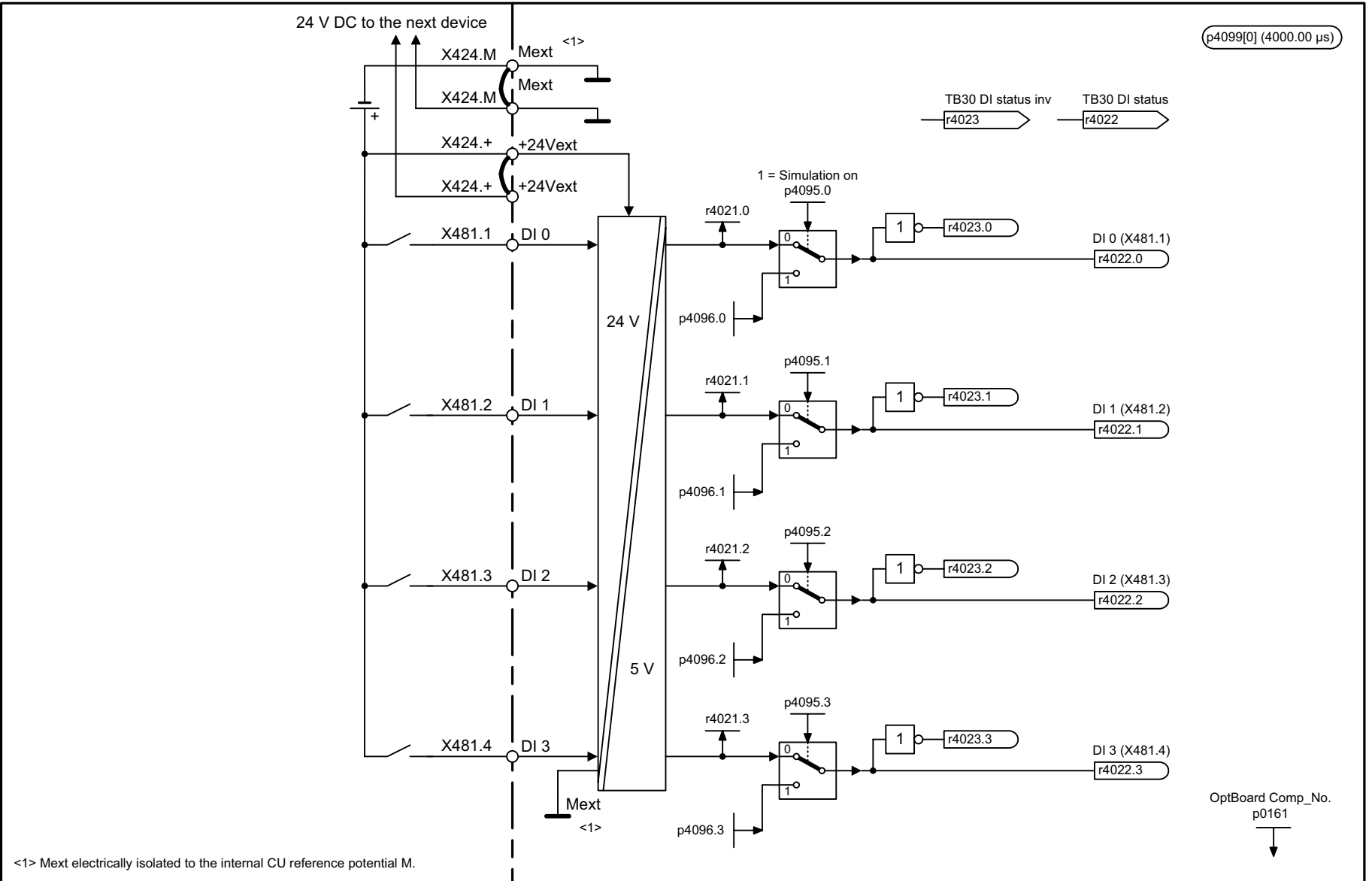
Figure 2-218 8964 – Messages/signals and monit. fcts., line frequency and Vdc monit. (p3400.0 = 0)

1	2	3	4	5	6	7	8
DO: A_INF					fp_8964_01_eng.vsd	Function diagram	
Active infeed – mess./sign. and monit. functions, line supply freq. and Vdc monit. (p3400.0 = 0)					13.05.05 V02.04.00	SINAMICS S	
							- 8964 -

2.29 Terminal Board 30 (TB30)

Function diagrams

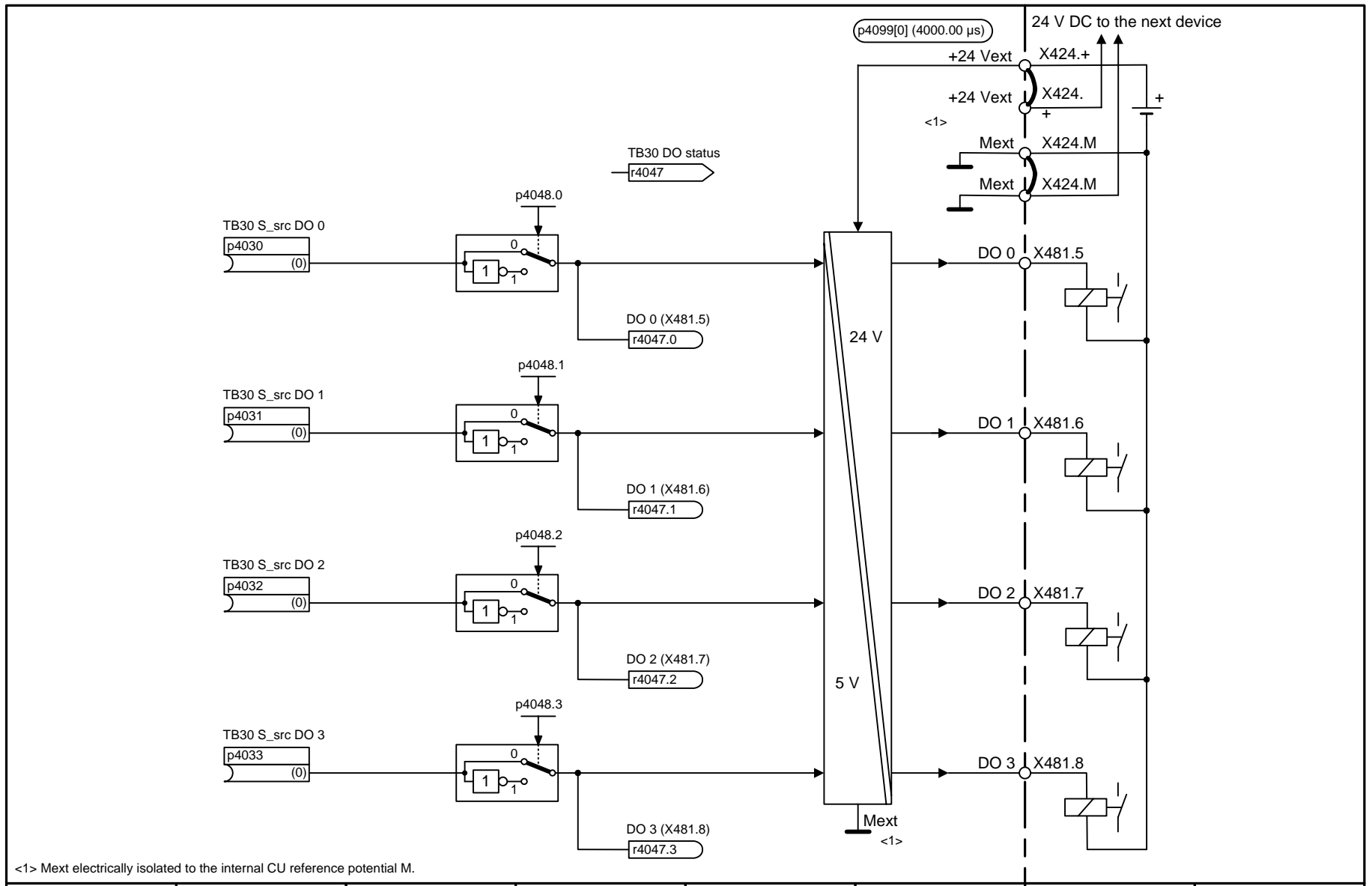
9100 – Digital inputs, electrically isolated (DI 0 ... DI 3)	2-1161
9102 – Digital outputs, electrically isolated (DO 0 ... DO 3)	2-1162
9104 – Analog inputs (AI 0 ... AI 1)	2-1163
9106 – Analog outputs (AO 0 ... AO 1)	2-1164



<1> Mext electrically isolated to the internal CU reference potential M.

1	2	3	4	5	6	7	8
DO: TB30					fp_9100_01_eng.vsd	Function diagram	
Terminal board 30 (TB30) - electrically isolated digital inputs (DI 0 ... DI 3)					21.06.05 V02.04.00	SINAMICS S	
							- 9100 -

Figure 2-219 9100 – Digital inputs, electrically isolated (DI 0 ... DI 3)

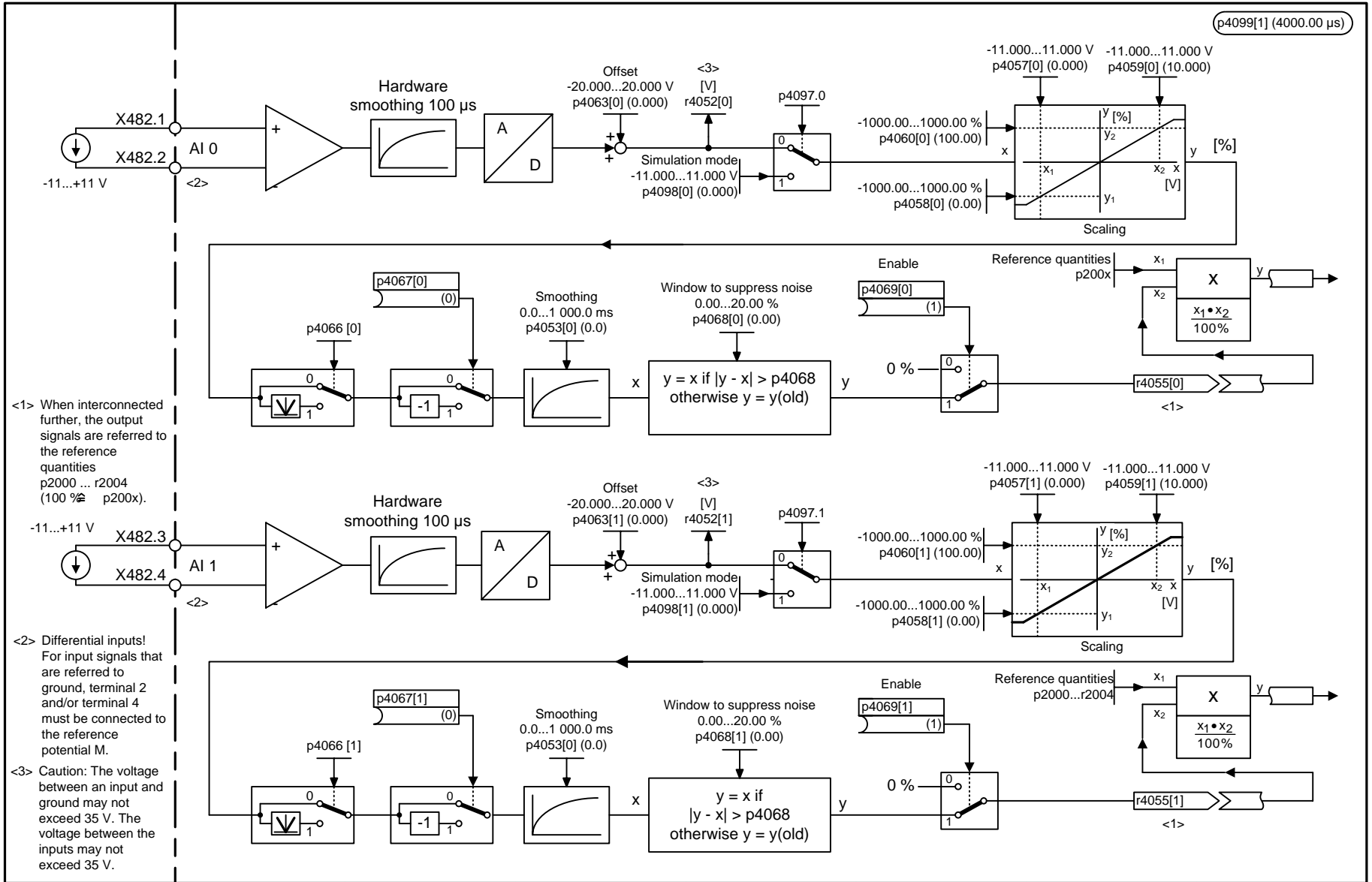


<1> Mext electrically isolated to the internal CU reference potential M.

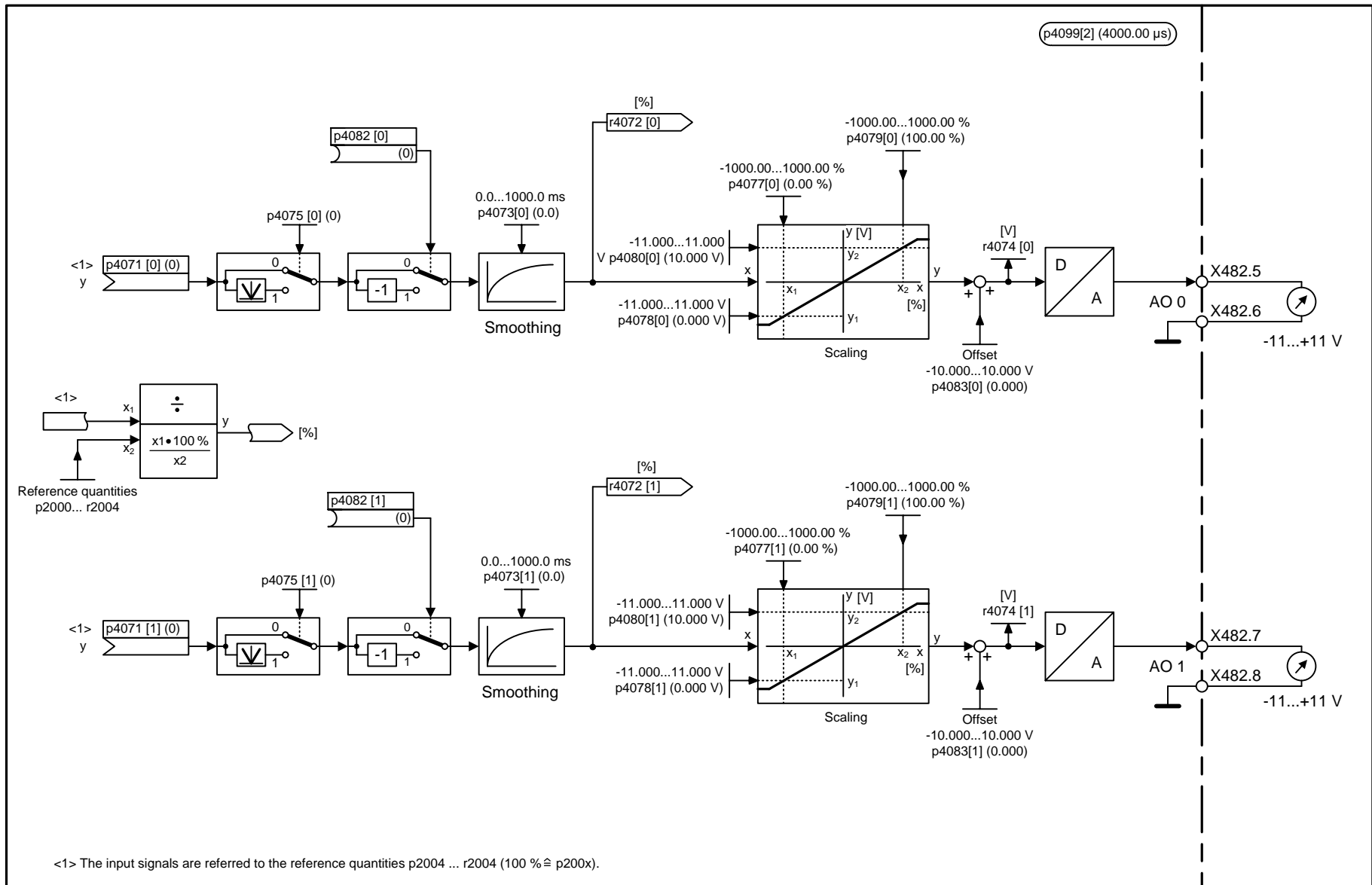
1	2	3	4	5	6	7	8
DO: TB30					fp_9102_01_eng.vsd	Function diagram	
Terminal Board 30 (TB30) - digital outputs, electrically isolated (DO 0 ... DO 3)					19.01.06 V02.04.00	SINAMICS S	
							- 9102 -

Figure 2-220 9102 – Digital outputs, electrically isolated (DO 0 ... DO 3)

Figure 2-221 9104 – Analog inputs (AI 0 ... AI 1)



1	2	3	4	5	6	7	8
DO: TB30					fp_9104_01_eng.vsd	Function diagram	
Terminal board 30 (TB30) - analog inputs (AI 0 and AI 1)					21.06.05 V02.04.00	SINAMICS S	
							- 9104 -



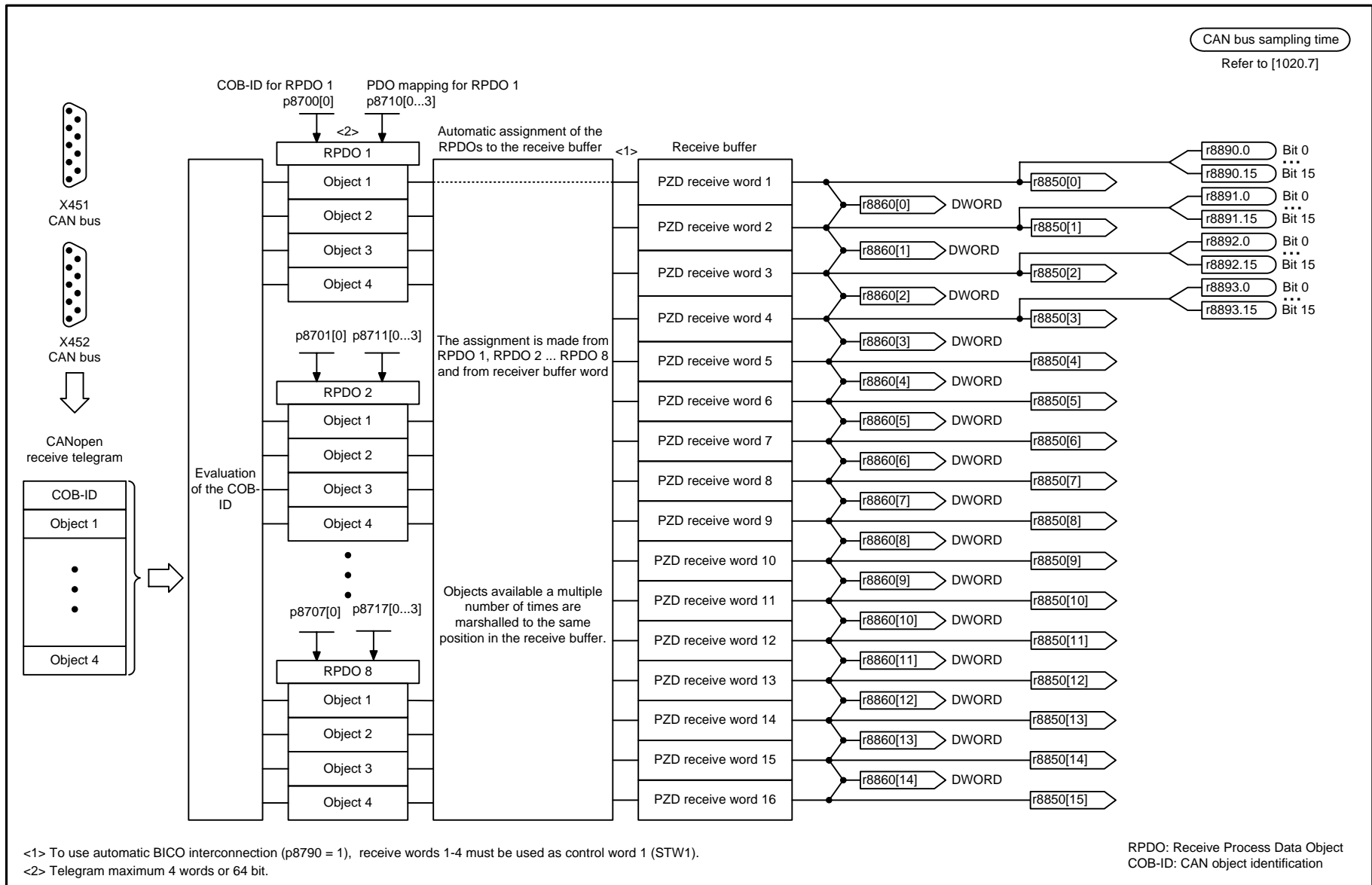
1	2	3	4	5	6	7	8
DO: TB30					fp_9106_01_eng.vsd	Function diagram	
Terminal Board 30 (TB30) - analog outputs (AO 0 ... AO 1)					25.10.05 V02.04.00	SINAMICS S	
							- 9106 -

Figure 2-222 9106 – Analog outputs (AO 0 ... AO 1)

2.30 Communication Board CAN 10 (CBC10)

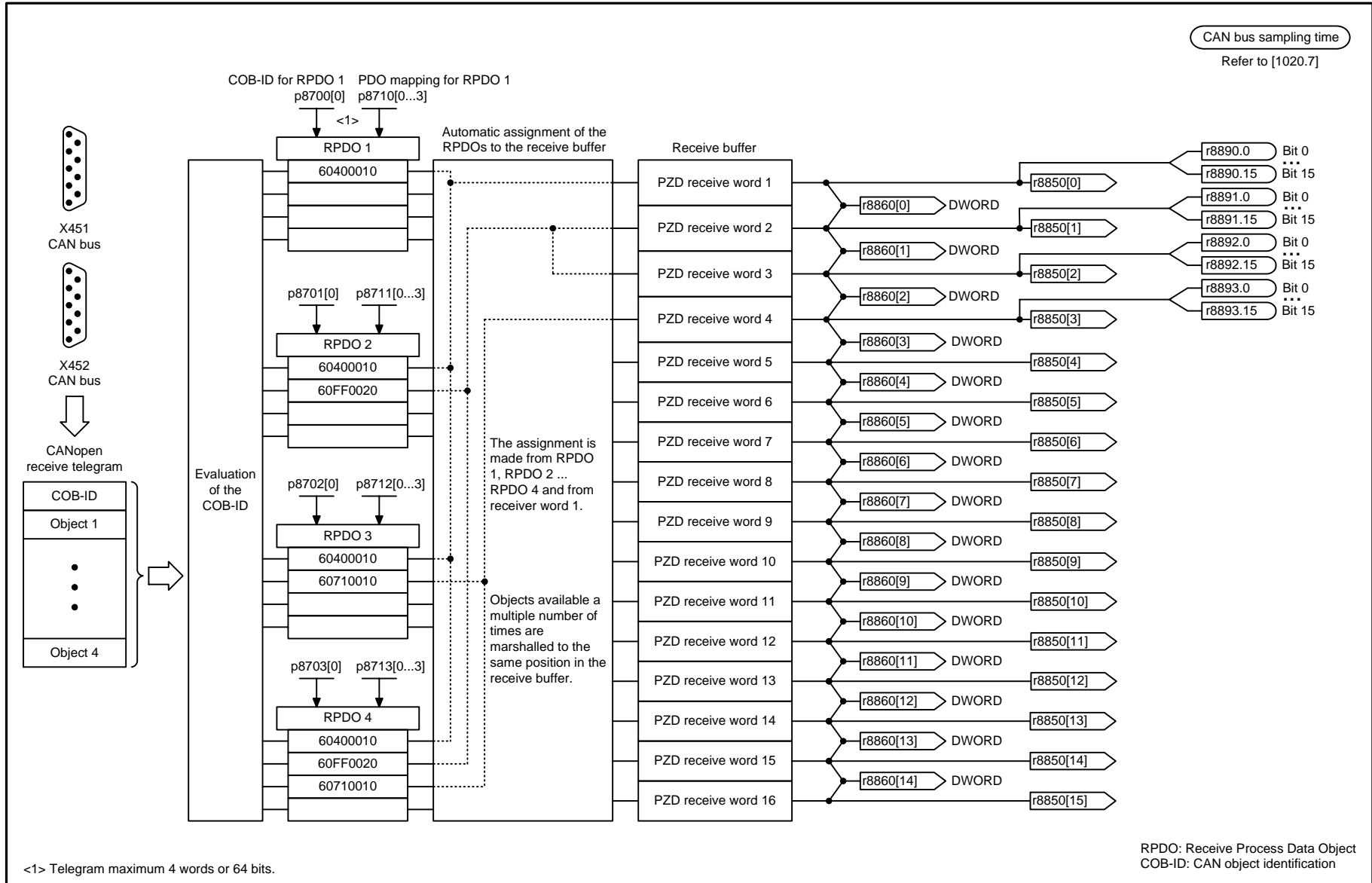
Function diagrams

9204 – Receive telegram, free PDO mapping (p8744 = 2)	2-1166
9206 – Receive telegram, predefined connection set (p8744 = 1)	2-1167
9208 – Send telegram, free PDO mapping (p8744 = 2)	2-1168
9210 – Send telegram, predefined connection set (p8744 = 1)	2-1169
9220 – Control word CANopen	2-1170
9226 – Status word CANopen	2-1171



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_9204_01_eng.vsd	Function diagram	
Communication Board CAN 10 (CBC10) - receive telegram for free PDO mapping (p8744 = 2)					16.12.04 V02.04.00	SINAMICS S	
							- 9204 -

Figure 2-223 9204 – Receive telegram, free PDO mapping (p8744 = 2)



1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_9206_01_eng.vsd	Function diagram	
Communication Board CAN 10 (CBC10) - receive telegram predef. conn. set (p8744 = 1)					16.12.04 V02.04.00	SINAMICS S	
							- 9206 -

Figure 2-224 9206 – Receive telegram, predefined connection set (p8744 = 1)

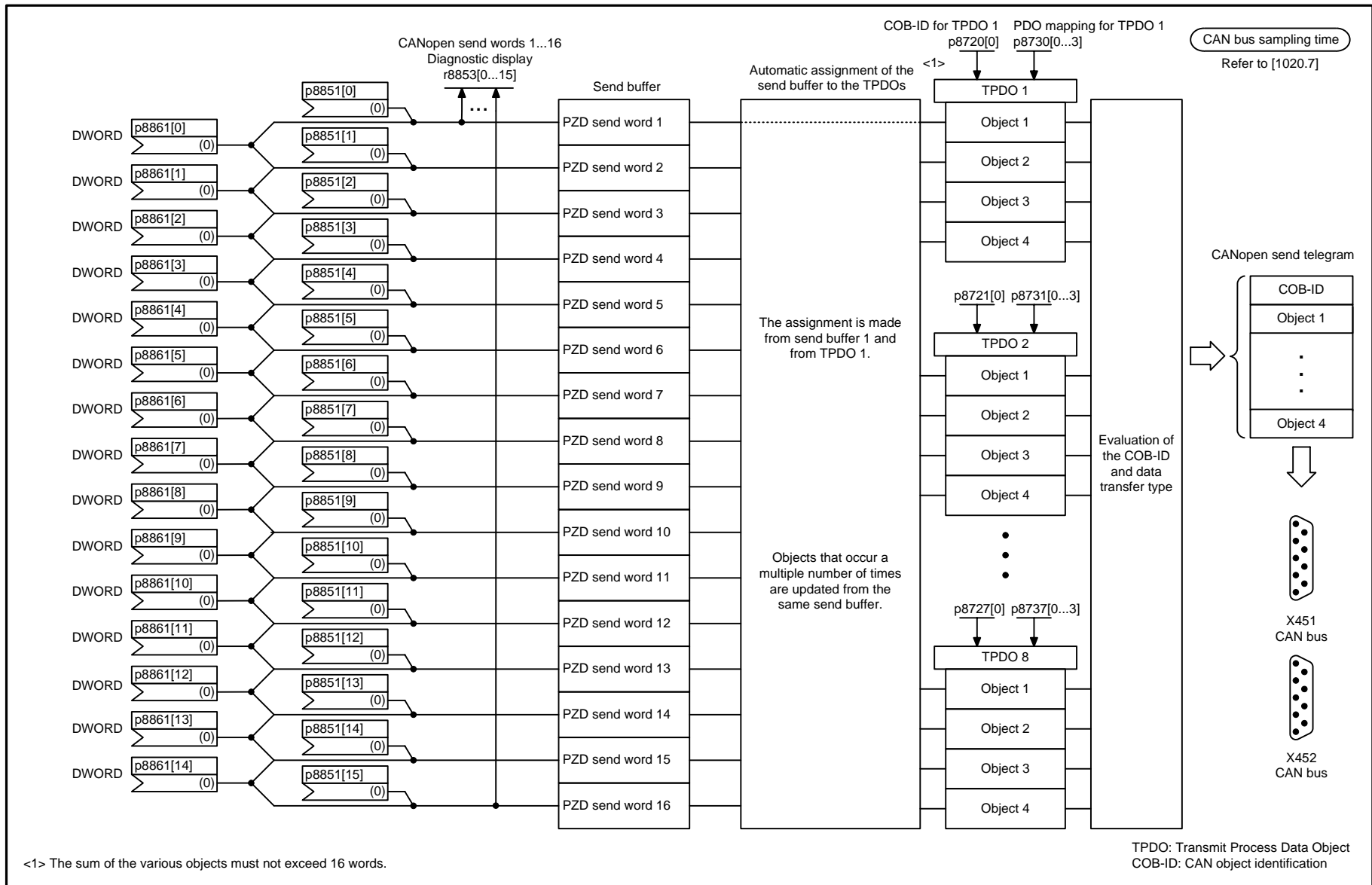


Figure 2-225 9208 – Send telegram, free PDO mapping (p8744 = 2)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_9208_01_eng.vsd	Function diagram	
Communication Board CAN10 (CBC10) - send telegram free PDO mapping (p8744 = 2)					15.12.04 V02.04.00	SINAMICS S	
							- 9208 -

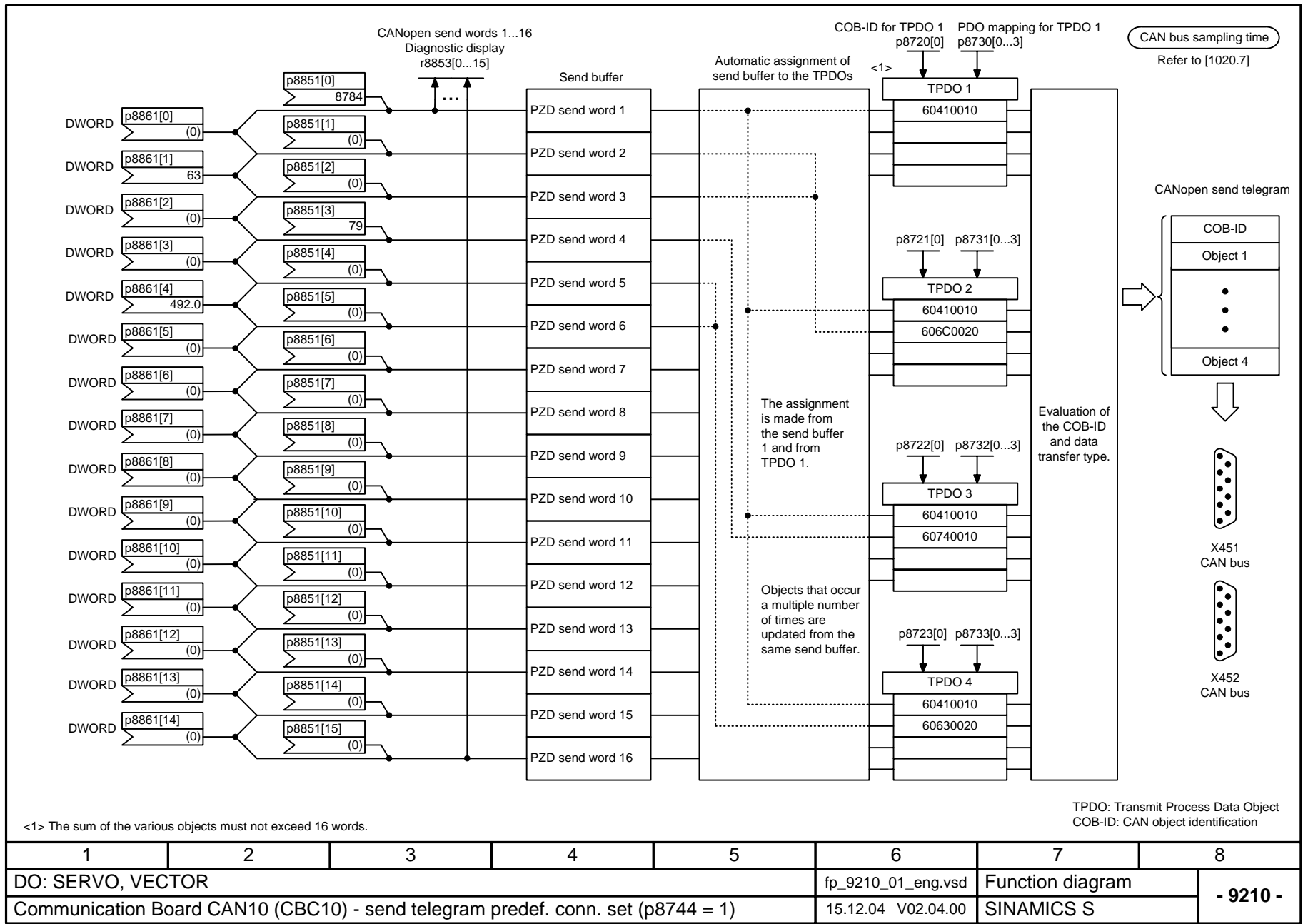




Figure 2-226 9210 – Send telegram, predefined connection set (p8744 = 1)

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_9210_01_eng.vsd	Function diagram	
Communication Board CAN10 (CBC10) - send telegram predef. conn. set (p8744 = 1)					15.12.04 V02.04.00	SINAMICS S	
							- 9210 -

CANopen sampling time
Refer to [1020.7]

Signal targets for control word CANopen

Signal	Meaning	Interconnection parameters <1>	[Function diagram] internal control word	[Function diagram] signal target	Inverted
STW1.0	 = ON (pulses can be enabled) 0 = OFF1 (braking with ramp-function generator, then pulse cancellation and ready-to-power-up)	p0840[0] = r8890.0	[2501.3]	[2610]	-
STW1.1	1 = No coast-down activated (enable possible) 0 = Activate coast-down (immediate pulse cancellation and power-on inhibit)	p0844[0] = r8890.1	[2501.3]	[2610]	-
STW1.2	1 = No fast stop activated (enable possible) 0 = Activate fast stop (braking along an OFF3 ramp p1135, then pulse cancellation and power-on inhibit)	p0848[0] = r8890.2	[2501.3]	[2610]	-
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (cancel pulses)	p0852[0] = r8890.3	[2501.3]	[2610]	-
STW1.4	Reserved	-	-	-	-
STW1.5	Reserved	-	-	-	-
STW1.6	Reserved	-	-	-	-
STW1.7	 = Acknowledge fault	p2103[0] = r8890.7	[2546.1]	[8060]	-
STW1.8	Reserved	-	-	-	-
STW1.9	Reserved	-	-	-	-
STW1.10	Reserved	-	-	-	-
STW1.11	Can be freely connected	pxxxx[y] = r8890.11	-	-	-
STW1.12	Can be freely connected	pxxxx[y] = r8890.12	-	-	-
STW1.13	Can be freely connected	pxxxx[y] = r8890.13	-	-	-
STW1.14	Can be freely connected	pxxxx[y] = r8890.14	-	-	-
STW1.15	Can be freely connected	pxxxx[y] = r8890.15	-	-	-

<1> Depending on the position of the CANopen control word in p8750, the number of the binector to be connected changes.

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_9220_01_eng.vsd	Function diagram	
Communication board CAN 10 (CBC10) - control word CANopen					15.12.05 V02.04.00	SINAMICS S	
							- 9220 -

Figure 2-227 9220 – Control word CANopen

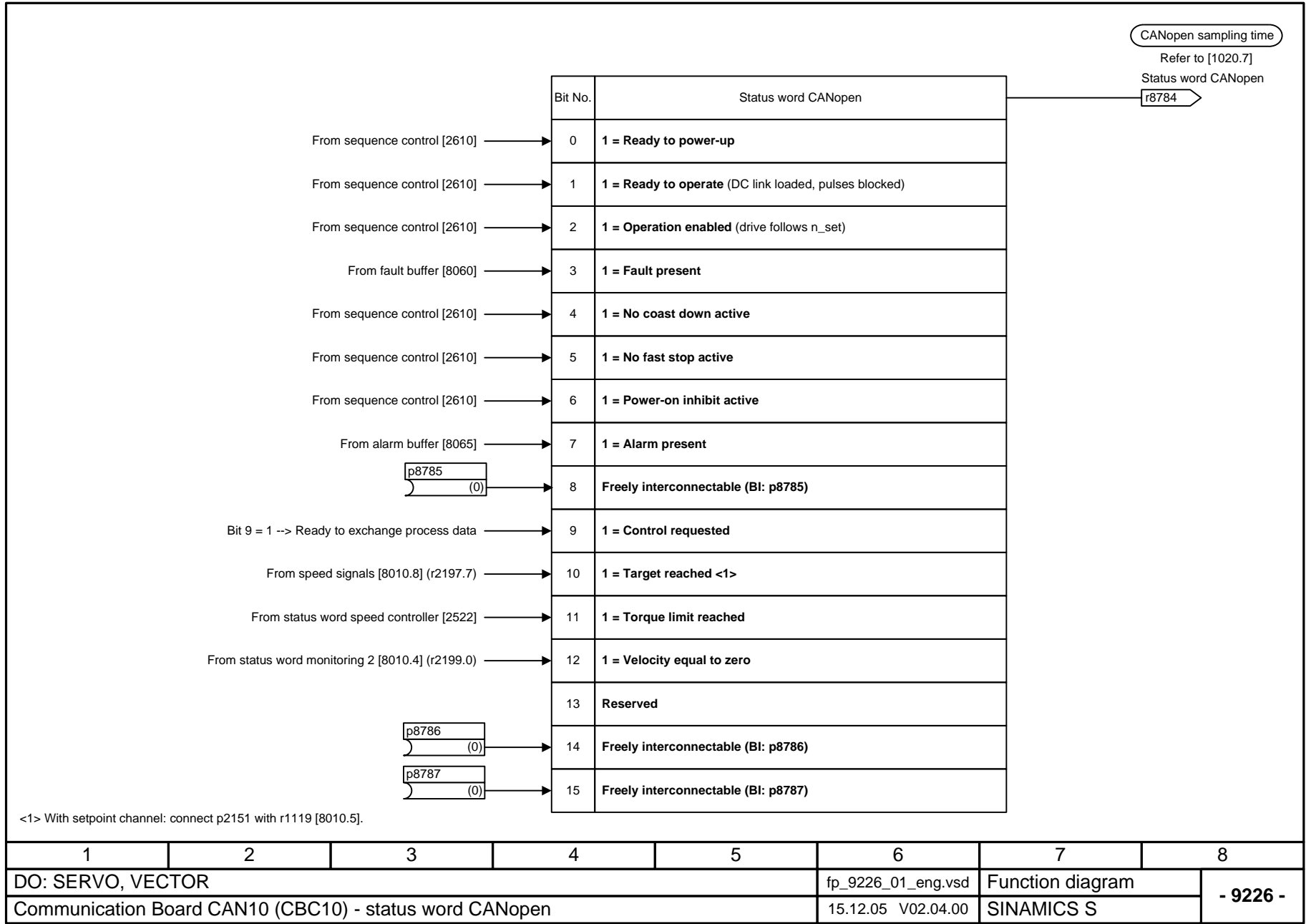


Figure 2-228 9226 – Status word CANopen

1	2	3	4	5	6	7	8
DO: SERVO, VECTOR					fp_9226_01_eng.vsd	Function diagram	
Communication Board CAN10 (CBC10) - status word CANopen					15.12.05 V02.04.00	SINAMICS S	
							- 9226 -

2.31 Terminal Module 15 for SINAMICS (TM15DI/DO)

Function diagrams

9400 – Digital inputs/outputs, bidirectional (DI/DO 0 ... DI/DO 7)	2-1173
9401 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 15)	2-1174
9402 – Digital inputs/outputs, bidirectional (DI/DO 16 ... DI/DO 23)	2-1175

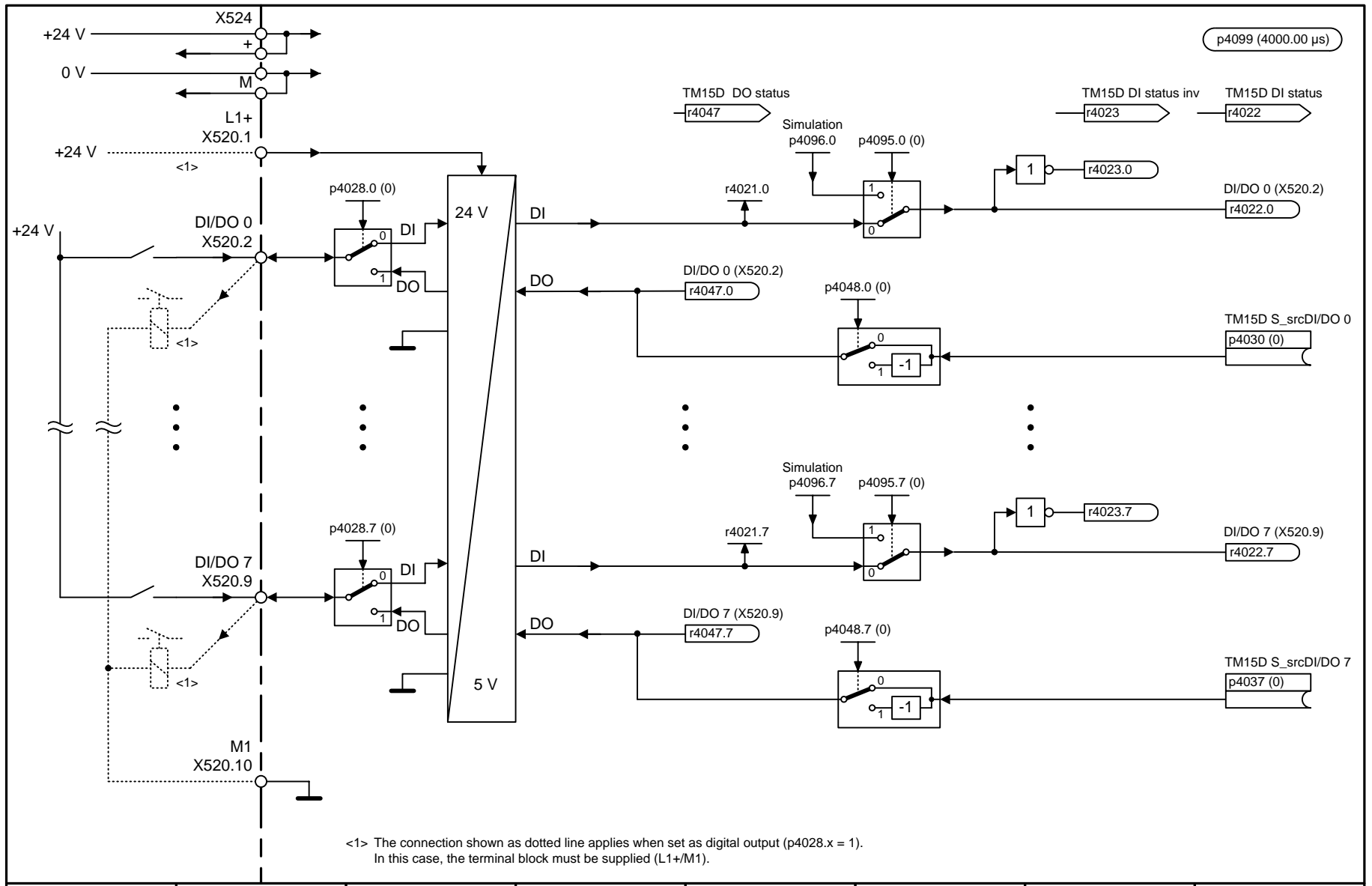


Figure 2-229 9400 – Digital inputs/outputs, bidirectional (DI/DO 0 ... DI/DO 7)

1	2	3	4	5	6	7	8
DO: TM15DI/DO					fp_9400_01_eng.vsd	Function diagram	
Terminal Module 15 (TM15) - bidirectional digital inputs/outputs (DI/DO 0 ... DI/DO 7)					18.03.05 V02.04.00	SINAMICS S	
							- 9400 -

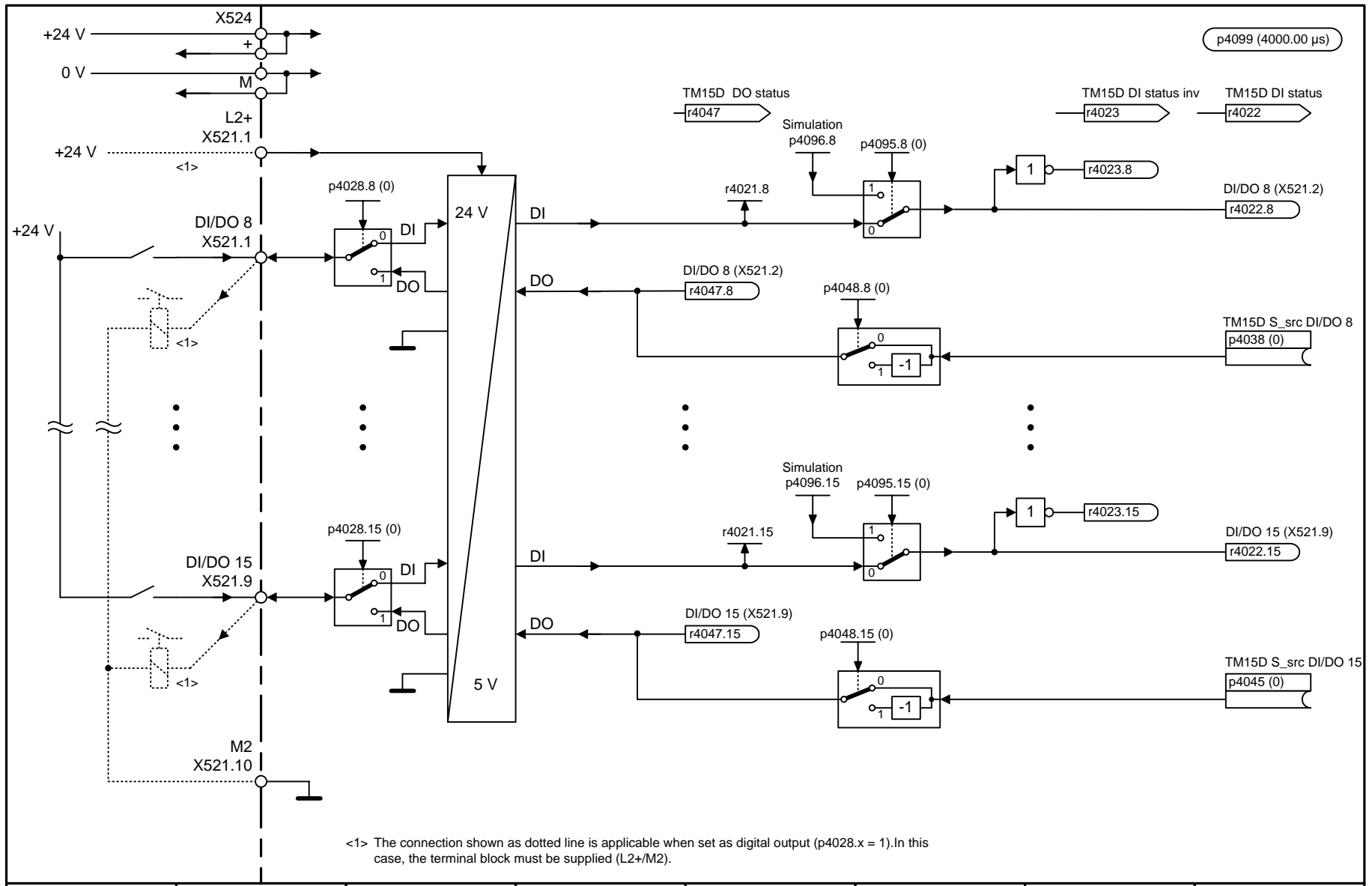


Figure 2-230 9401 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 15)

1	2	3	4	5	6	7	8
DO: TM15DI/DO					fp_9401_01_eng.vsd	Function diagram	
Terminal Module 15 (TM15) - bidirectional digital inputs/outputs (DI/DO 8 ... DI/DO 15)					18.05.05 V02.04.00	SINAMICS S	
							- 9401 -

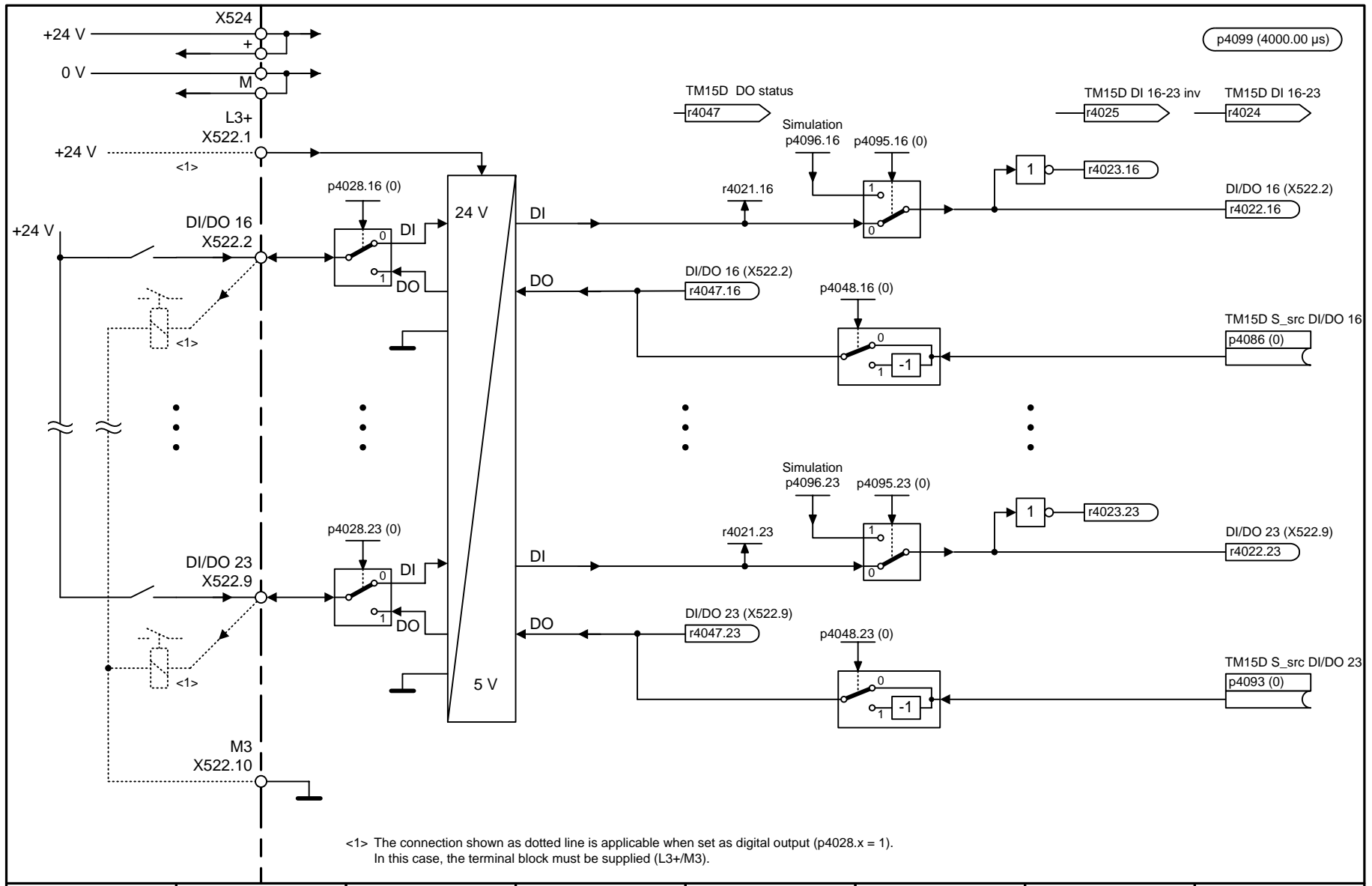


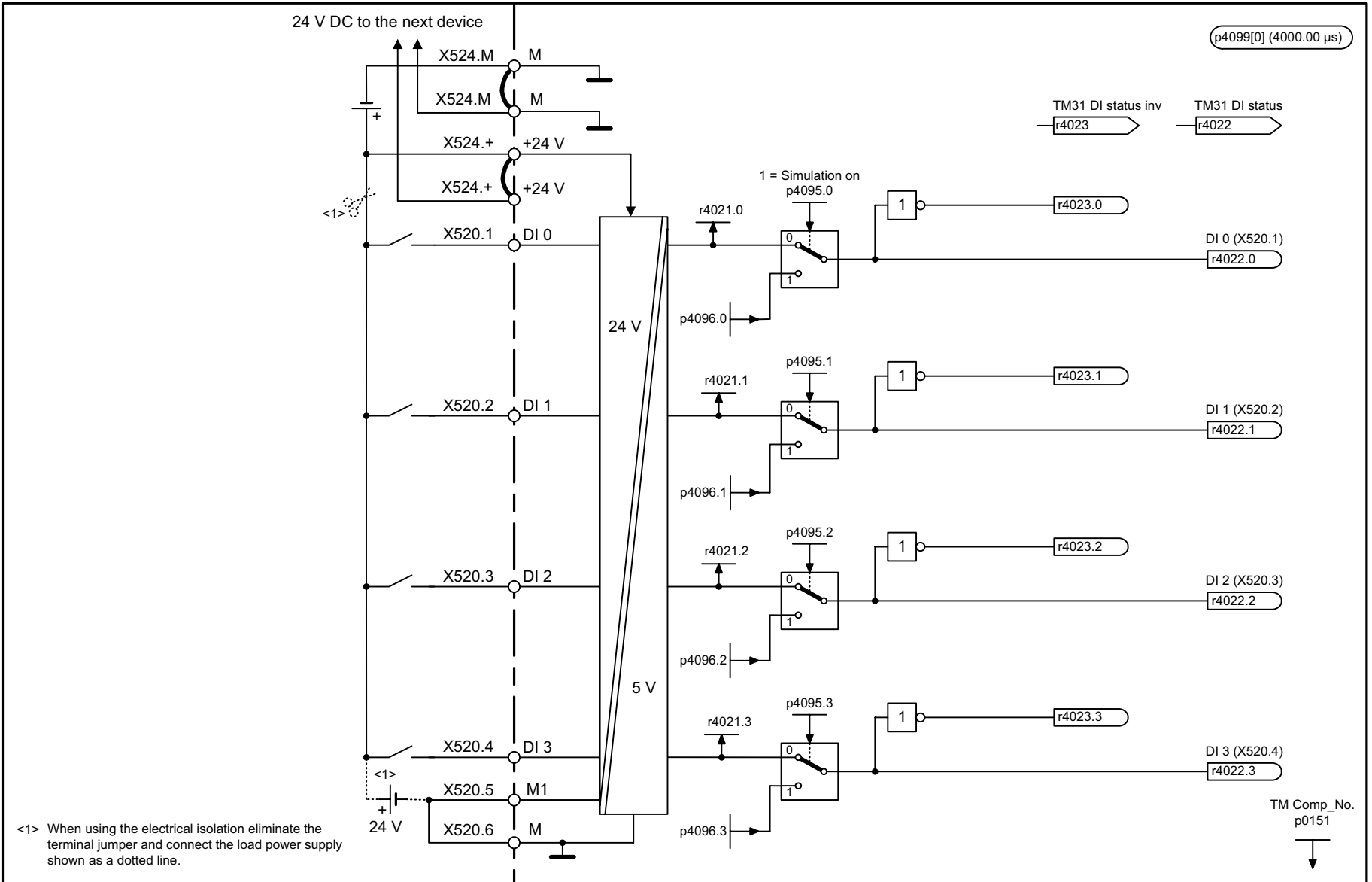
Figure 2-231 9402 – Digital inputs/outputs, bidirectional (DI/DO 16 ... DI/DO 23)

1	2	3	4	5	6	7	8
DO: TM15DI/DO					fp_9402_01_eng.vsd	Function diagram	
Terminal Module 15 (TM15) - bidirectional digital inputs/outputs (DI/DO 16 ... DI/DO 23)					17.01.06 V02.04.00	SINAMICS S	
							- 9402 -

2.32 Terminal Module 31 (TM31)

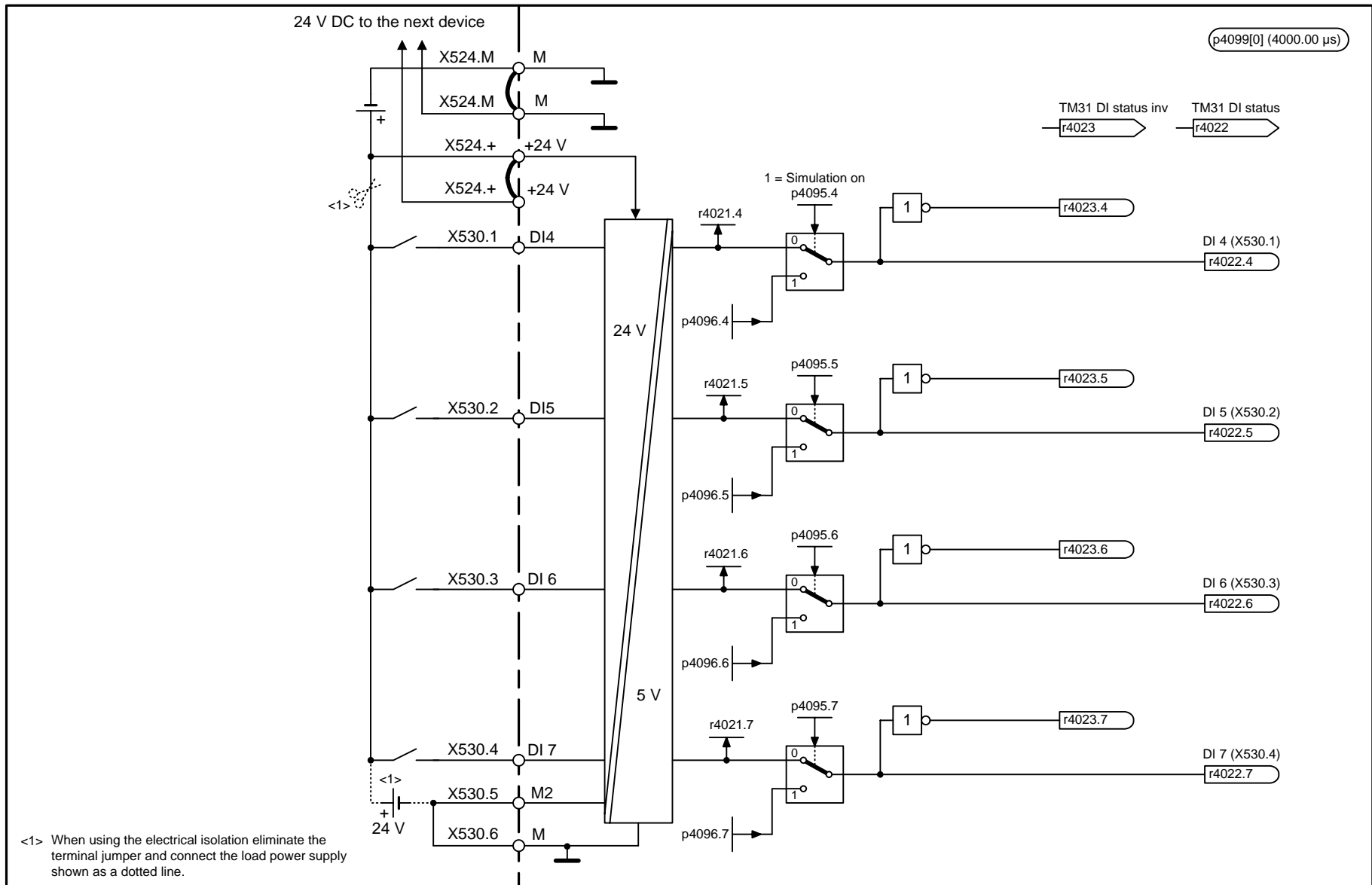
Function diagrams

9550 – Digital inputs, electrically isolated (DI 0 ... DI 3)	2-1177
9552 – Digital inputs, electrically isolated (DI 4 ... DI 7)	2-1178
9556 – Digital relay outputs, electrically isolated (DO 0 ... DO 1)	2-1179
9560 – Digital inputs/outputs, bidirectional (DI/DO 8 ... DI/DO 9)	2-1180
9562 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)	2-1181
9566 – Analog input 0 (AI 0)	2-1182
9568 – Analog input 1 (AI 1)	2-1183
9572 – Analog outputs (AO 0 ... AO 1)	2-1184
9576 – Temperature evaluation KTY/PTC	2-1185
9577 – Sensor monitoring KTY/PTC	2-1186



1	2	3	4	5	6	7	8
DO: TM31					fp_9550_01_eng.vsd	Function diagram	
Terminal board 31 (TB31) - electrically isolated digital inputs (DI 0 ... DI 3)					23.03.06 V02.04.00	SINAMICS S	
							- 9550 -

Figure 2-232 9550 – Digital inputs, electrically isolated (DI 0 ... DI 3)



1	2	3	4	5	6	7	8
DO: TM31					fp_9552_01_eng.vsd	Function diagram	
Terminal board 31 (TB31) - electrically isolated digital inputs (DI 4 ... DI 7)					21.07.04 V02.04.00	SINAMICS S	
							- 9552 -

Figure 2-233 9552 – Digital inputs, electrically isolated (DI 4 ... DI 7)

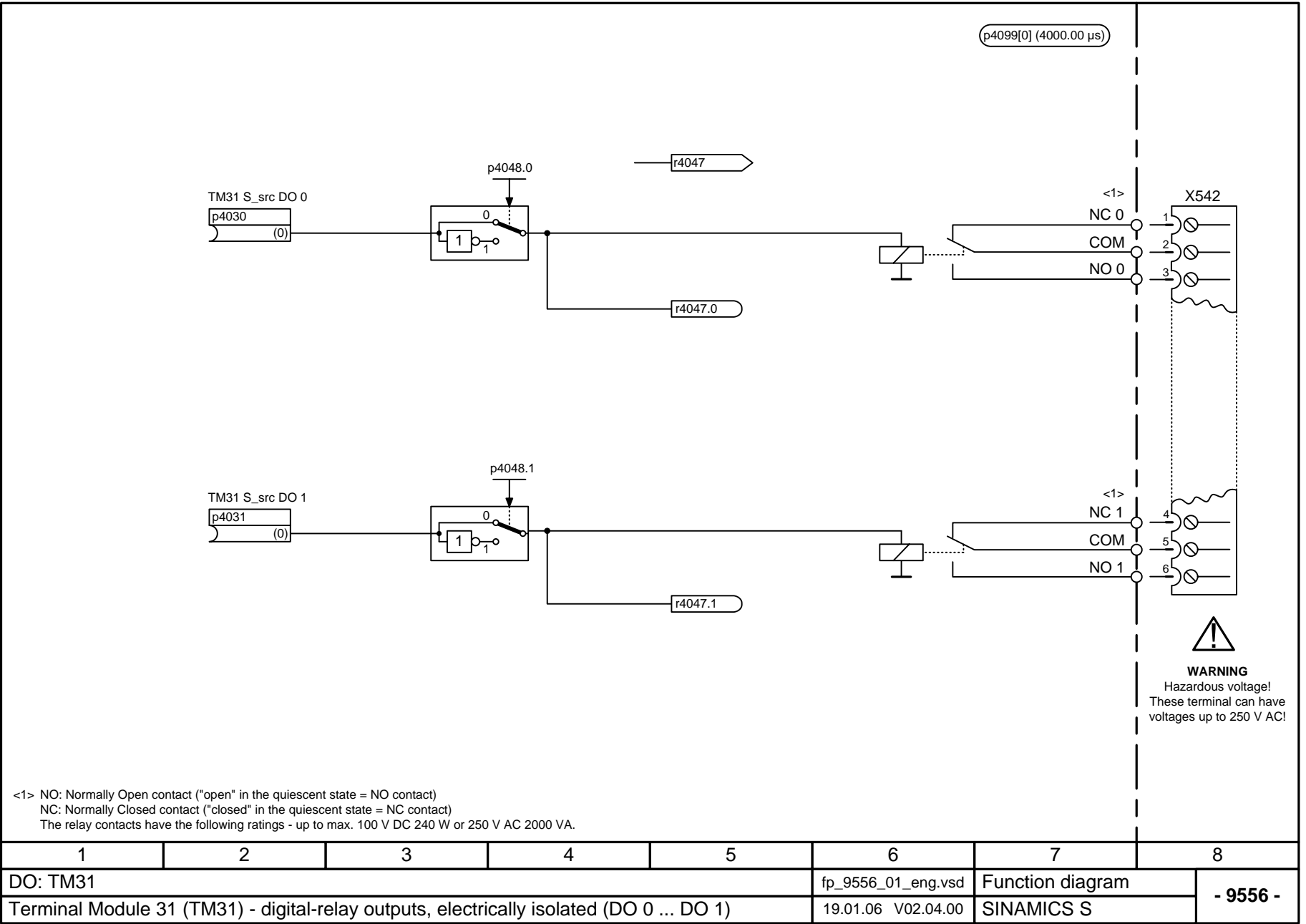
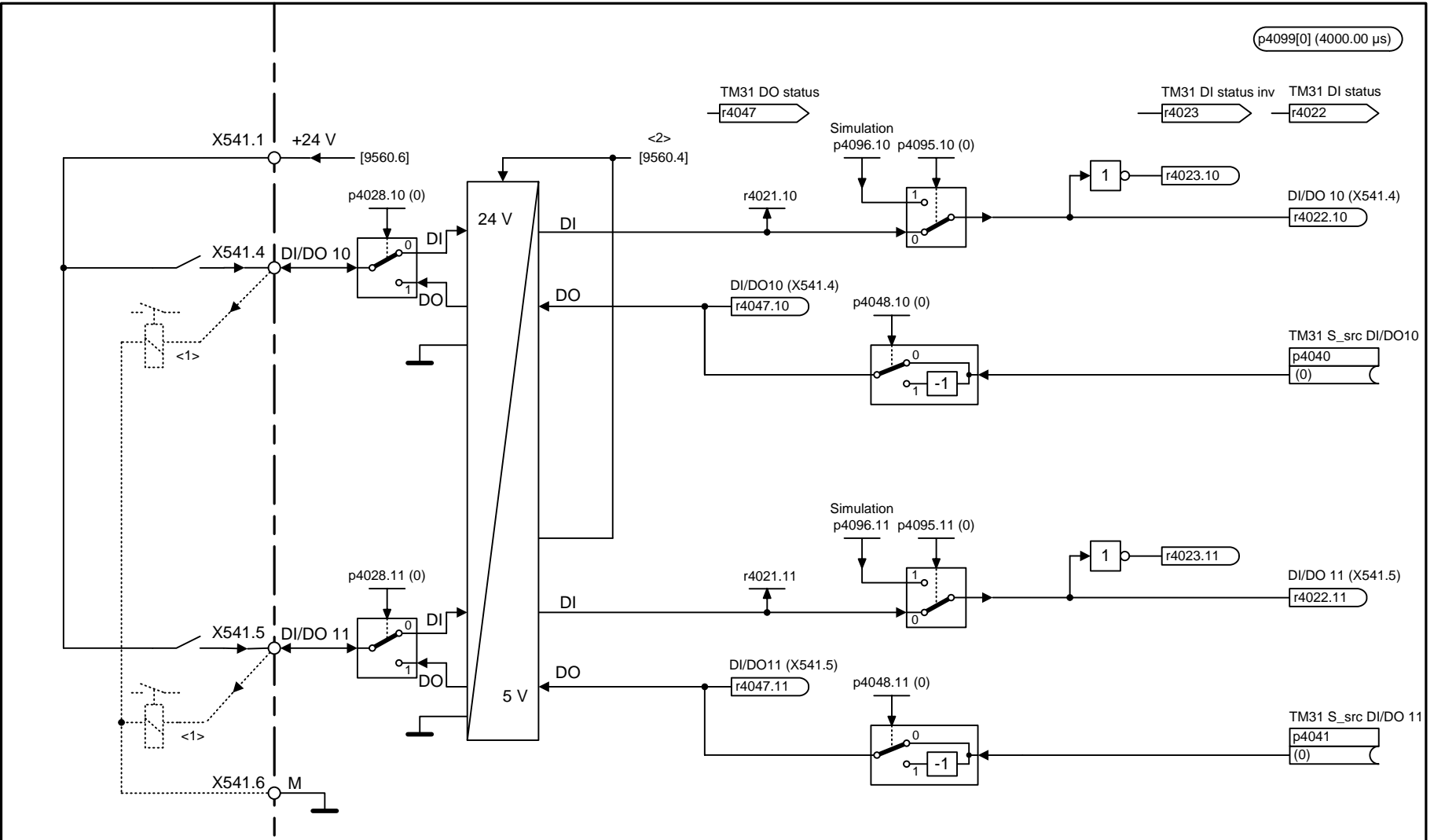


Figure 2-234 9556 – Digital relay outputs, electrically isolated (DO 0 ... DO 1)



<1> The connection shown as dotted line is applicable when set as digital output (p4028.x = 1).
 <2> Limits the summed (total output current of terminals X541.2, X541.3, X541.4 and X541.5 to 0.1 A (p4046 = 0) or 1 A (p4046 = 1).

1	2	3	4	5	6	7	8
DO: TM31					fp_9562_01_eng.vsd	Function diagram	
Terminal Module 31 (TM31) - bidirectional digital inputs/outputs (DI/DO 10 and DI/DO 11)					07.12.04 V02.04.00	SINAMICS S	
							- 9562 -

Figure 2-236 9562 – Digital inputs/outputs, bidirectional (DI/DO 10 ... DI/DO 11)

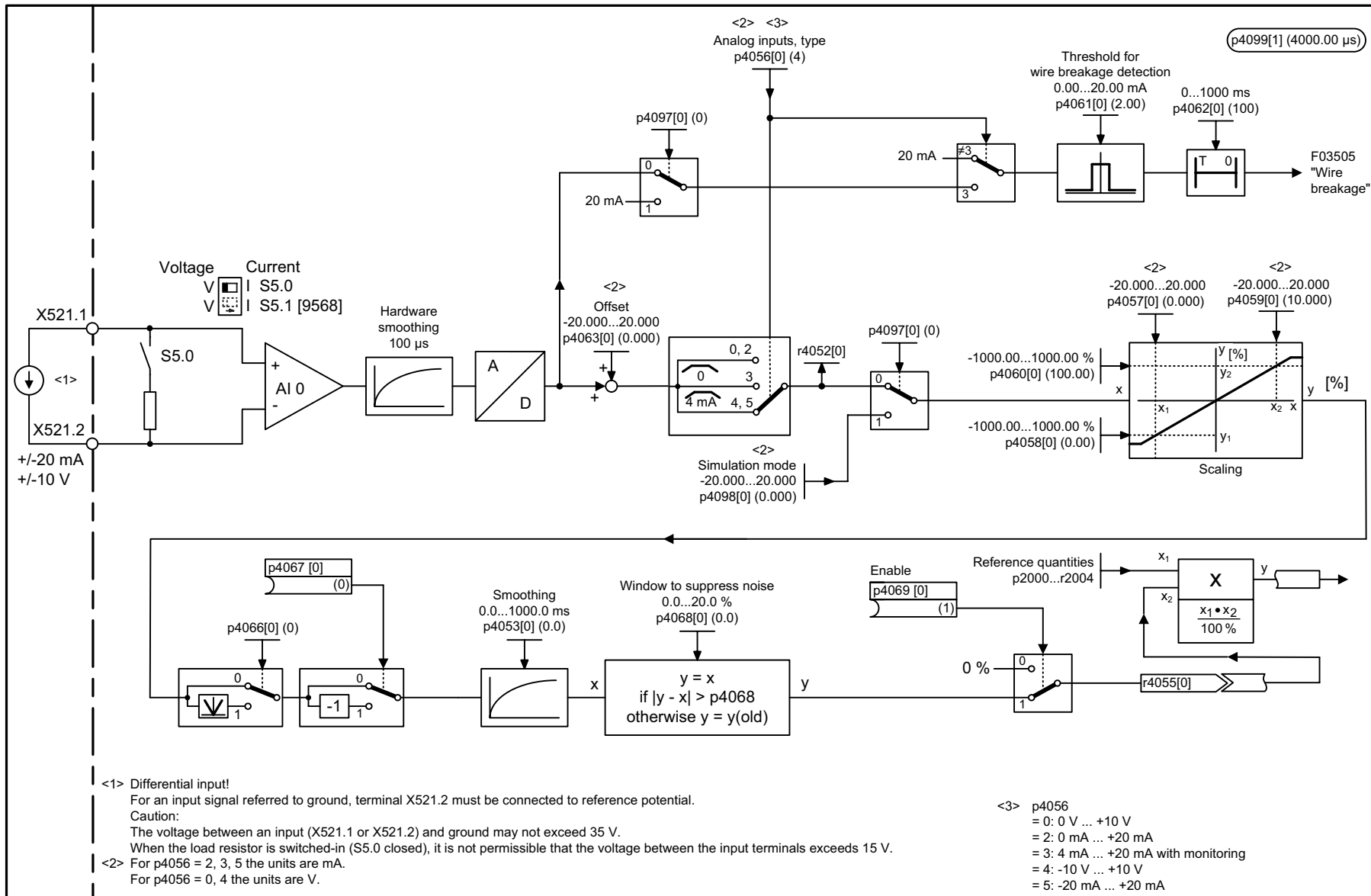


Figure 2-237 9566 – Analog input 0 (AI 0)

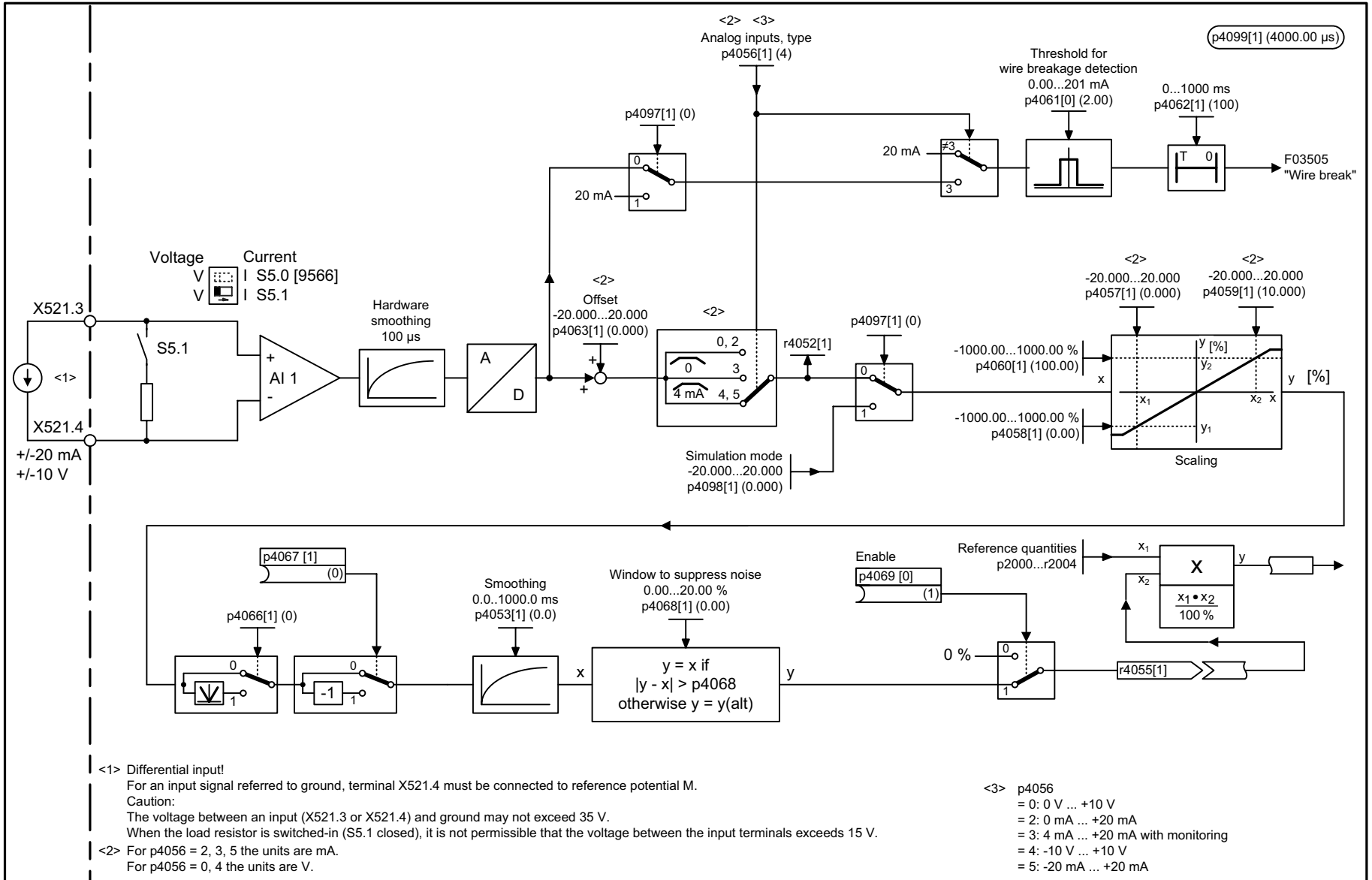
<1> Differential input!
For an input signal referred to ground, terminal X521.2 must be connected to reference potential.
Caution:
The voltage between an input (X521.1 or X521.2) and ground may not exceed 35 V.
When the load resistor is switched-in (S5.0 closed), it is not permissible that the voltage between the input terminals exceeds 15 V.

<2> For p4056 = 2, 3, 5 the units are mA.
For p4056 = 0, 4 the units are V.

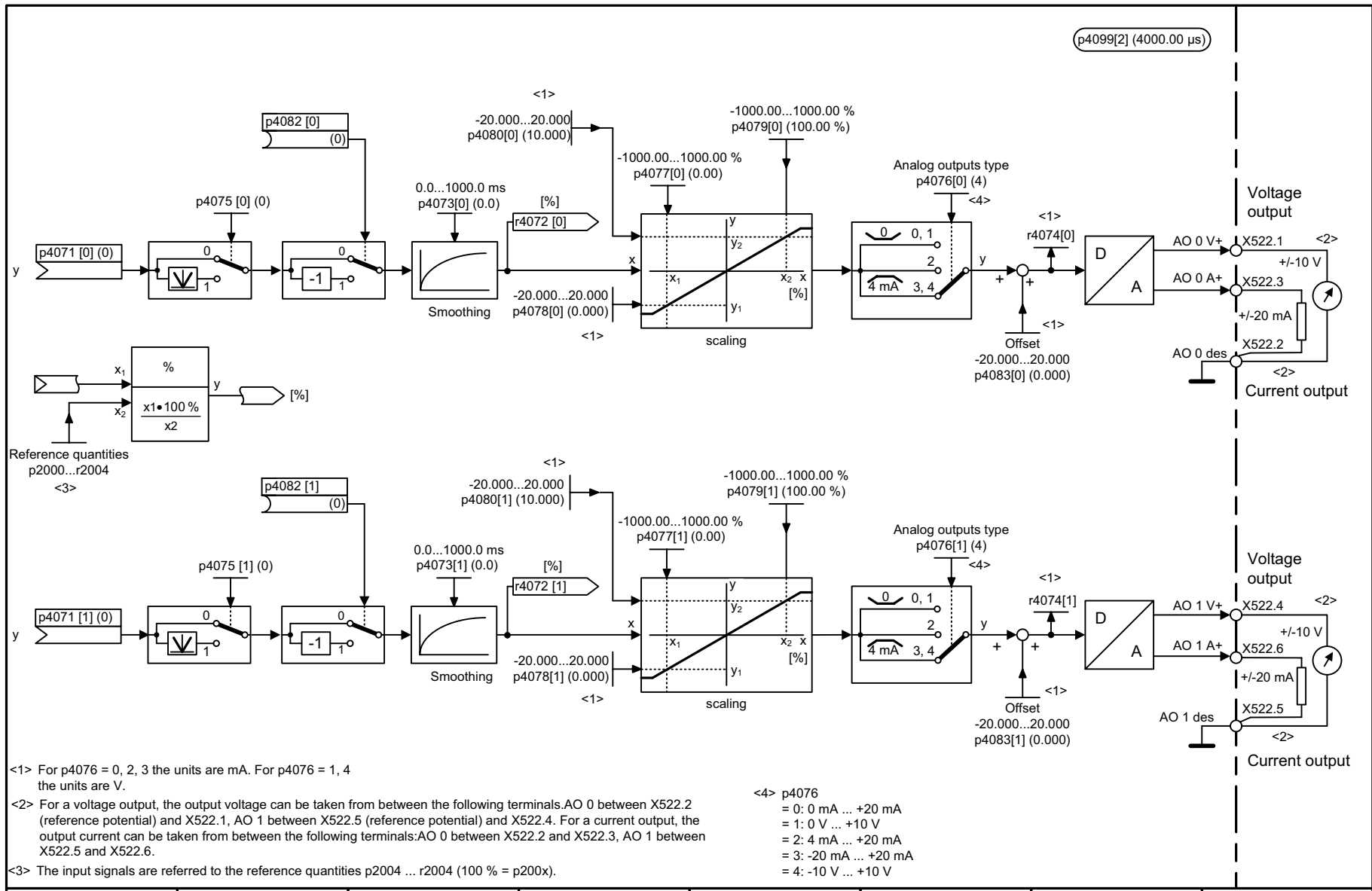
<3> p4056
= 0: 0 V ... +10 V
= 2: 0 mA ... +20 mA
= 3: 4 mA ... +20 mA with monitoring
= 4: -10 V ... +10 V
= 5: -20 mA ... +20 mA

1	2	3	4	5	6	7	8
DO: TM31					fp_9566_01_eng.vsd	Function diagram	
Terminal Module 31 (TM31) – analog input 0 (AI 0)					21.03.06 V02.04.00	SINAMICS S	
							- 9566 -

Figure 2-238 9568 – Analog input 1 (AI 1)



1	2	3	4	5	6	7	8
DO: TM31					fp_9568_01_eng.vsd	Function diagram	
Terminal Module 31 (TM31) – analog input 1 (AI 1)					20.02.06 V02.04.00	SINAMICS S	
							- 9568 -



<1> For $p4076 = 0, 2, 3$ the units are mA. For $p4076 = 1, 4$ the units are V.

<2> For a voltage output, the output voltage can be taken from between the following terminals: AO 0 between X522.2 (reference potential) and X522.1, AO 1 between X522.5 (reference potential) and X522.4. For a current output, the output current can be taken from between the following terminals: AO 0 between X522.2 and X522.3, AO 1 between X522.5 and X522.6.

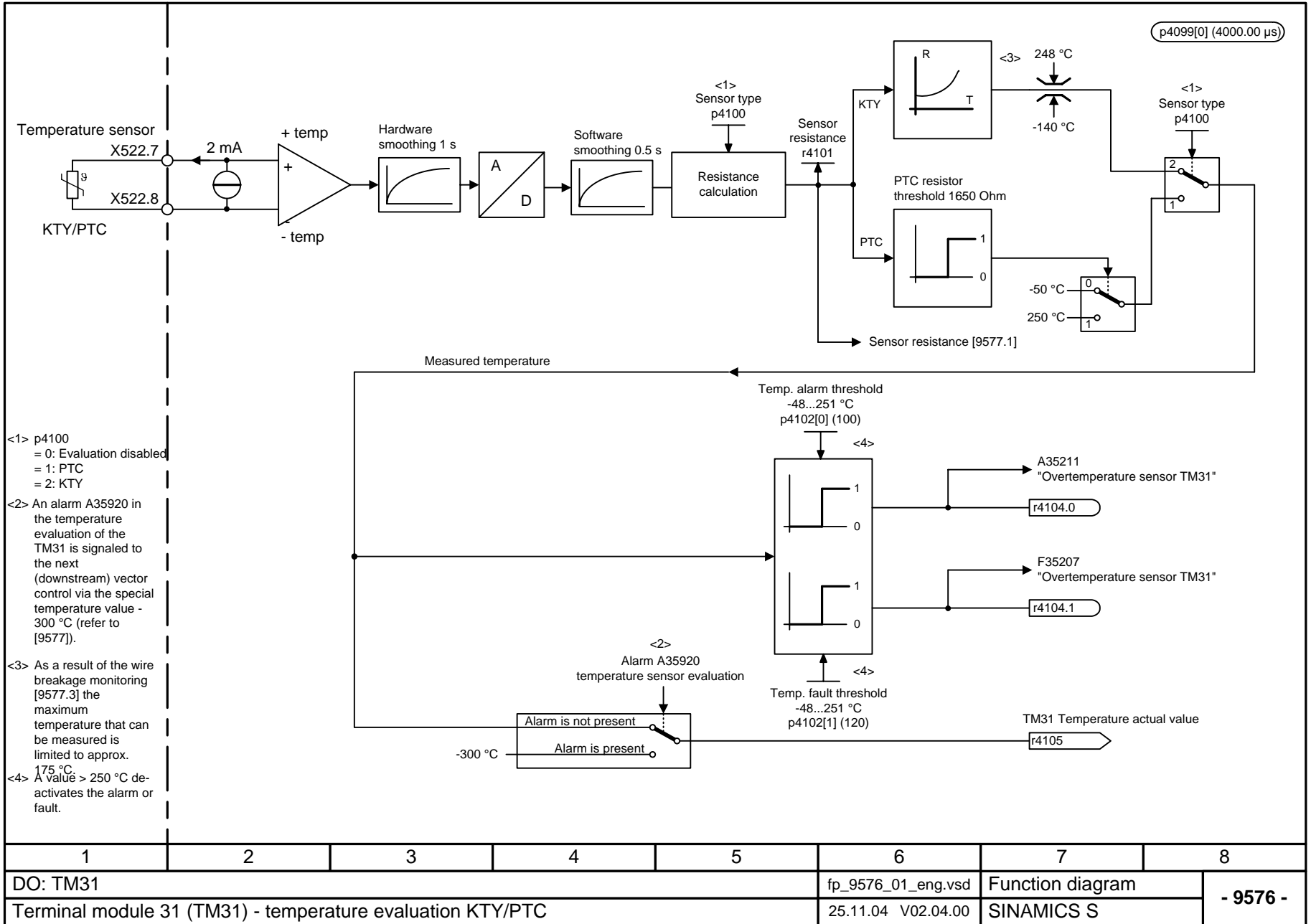
<3> The input signals are referred to the reference quantities $p2004 \dots r2004$ ($100\% = p200x$).

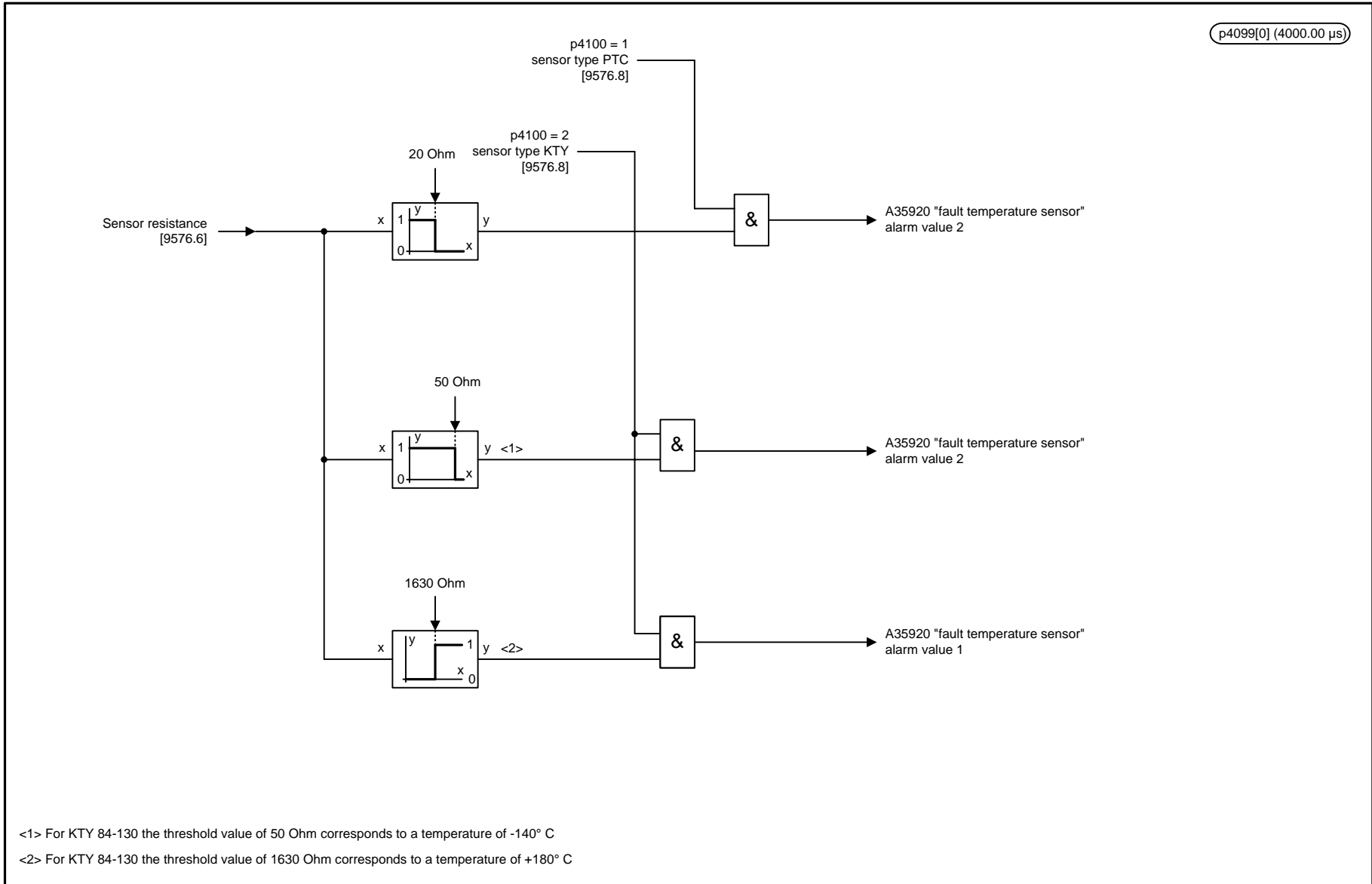
<4> $p4076$
 = 0: 0 mA ... +20 mA
 = 1: 0 V ... +10 V
 = 2: 4 mA ... +20 mA
 = 3: -20 mA ... +20 mA
 = 4: -10 V ... +10 V

1	2	3	4	5	6	7	8
DO: TM31					fp_9572_01_eng.vsd	Function diagram	
Terminal Module 31 (TM31) – analog outputs (AO 0 ... AO 1)					23.03.06 V02.04.00	SINAMICS S	
							- 9572 -

Figure 2-239 9572 – Analog outputs (AO 0 ... AO 1)

Figure 2-240 9576 – Temperature evaluation KTY/PTC





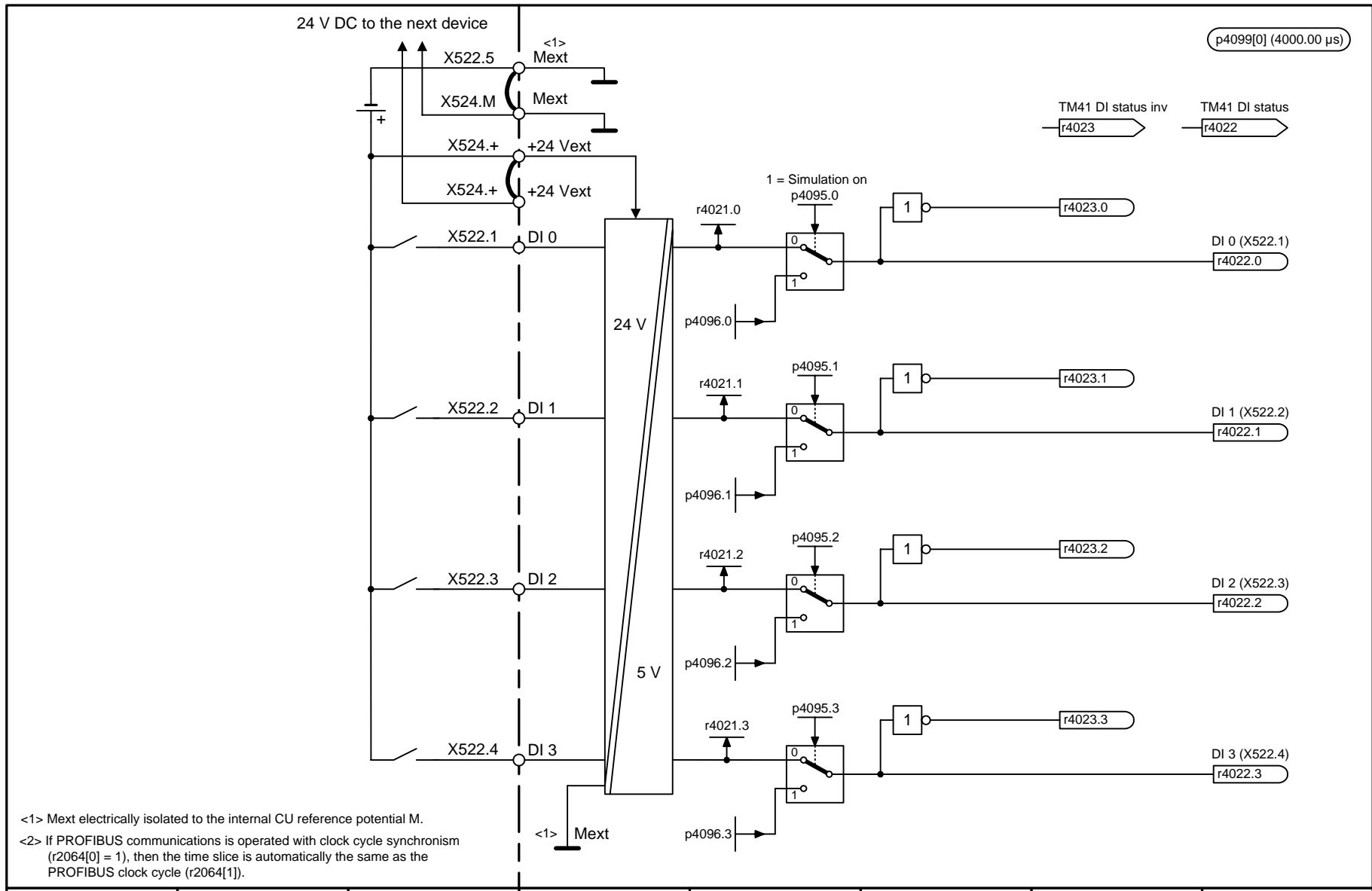
1	2	3	4	5	6	7	8
DO: TM31					fp_9577_01_eng.vsd	Function diagram	
Terminal module 31 (TM31) - sensor monitoring KTY/PTC					03.11.04 V02.04.00	SINAMICS S	
							- 9577 -

Figure 2-241 9577 – Sensor monitoring KTY/PTC

2.33 Terminal Module 41 (TM41)

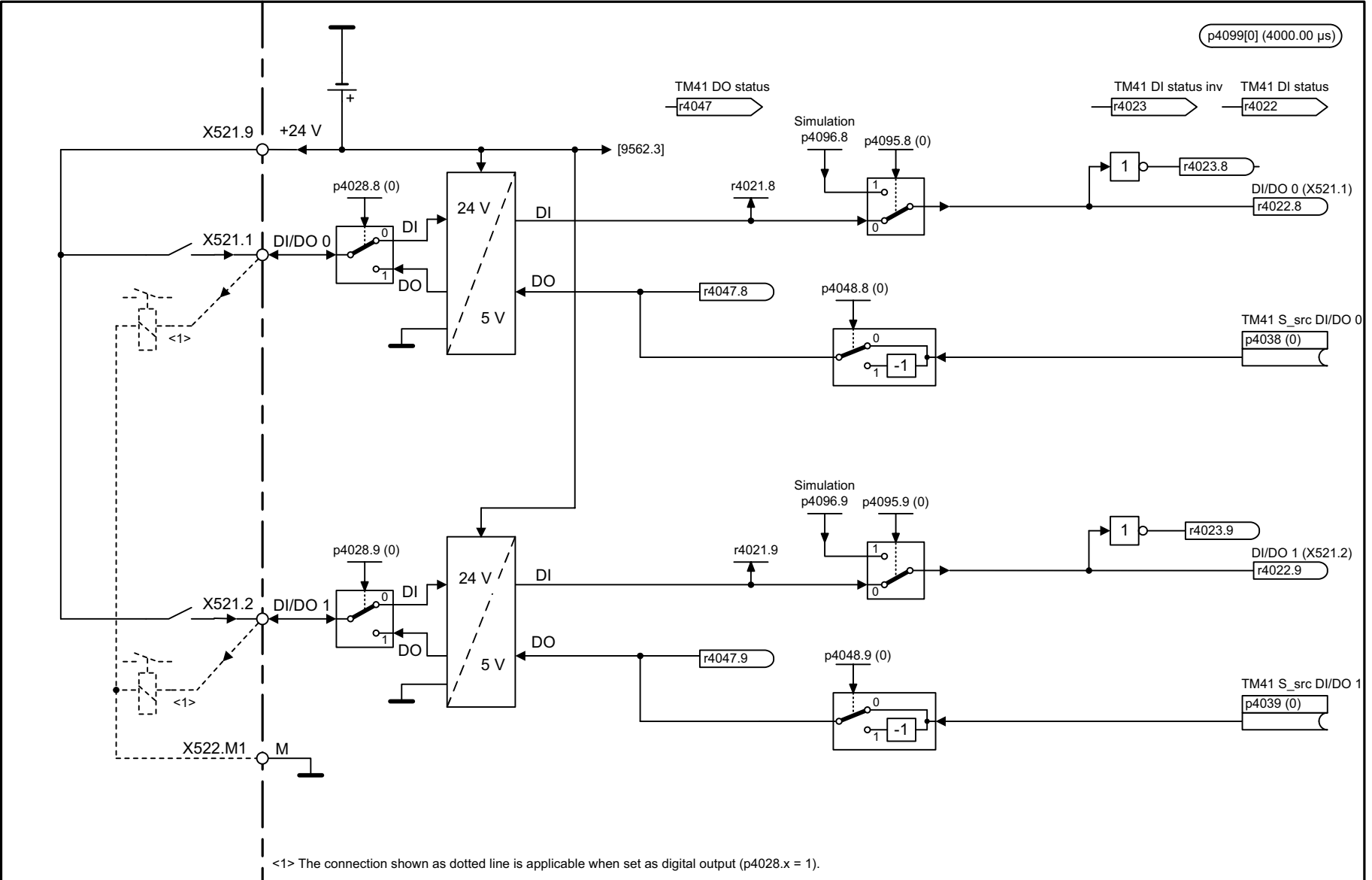
Function diagrams

9660 – Digital inputs, electrically isolated (DI 0 ... DI 3)	2-1188
9661 – Digital inputs/outputs, bidirectional (DI/DO 0 ... DI/DO 1)	2-1189
9662 – Digital inputs/outputs, bidirectional (DI/DO 2 ... DI/DO 3)	2-1190
9663 – Analog input (AI 0)	2-1191
9674 – Incremental encoder emulation (p4400 = 0)	2-1192
9676 – Incremental encoder emulation (p4400 = 1)	2-1193
9682 – Sequence control	2-1194



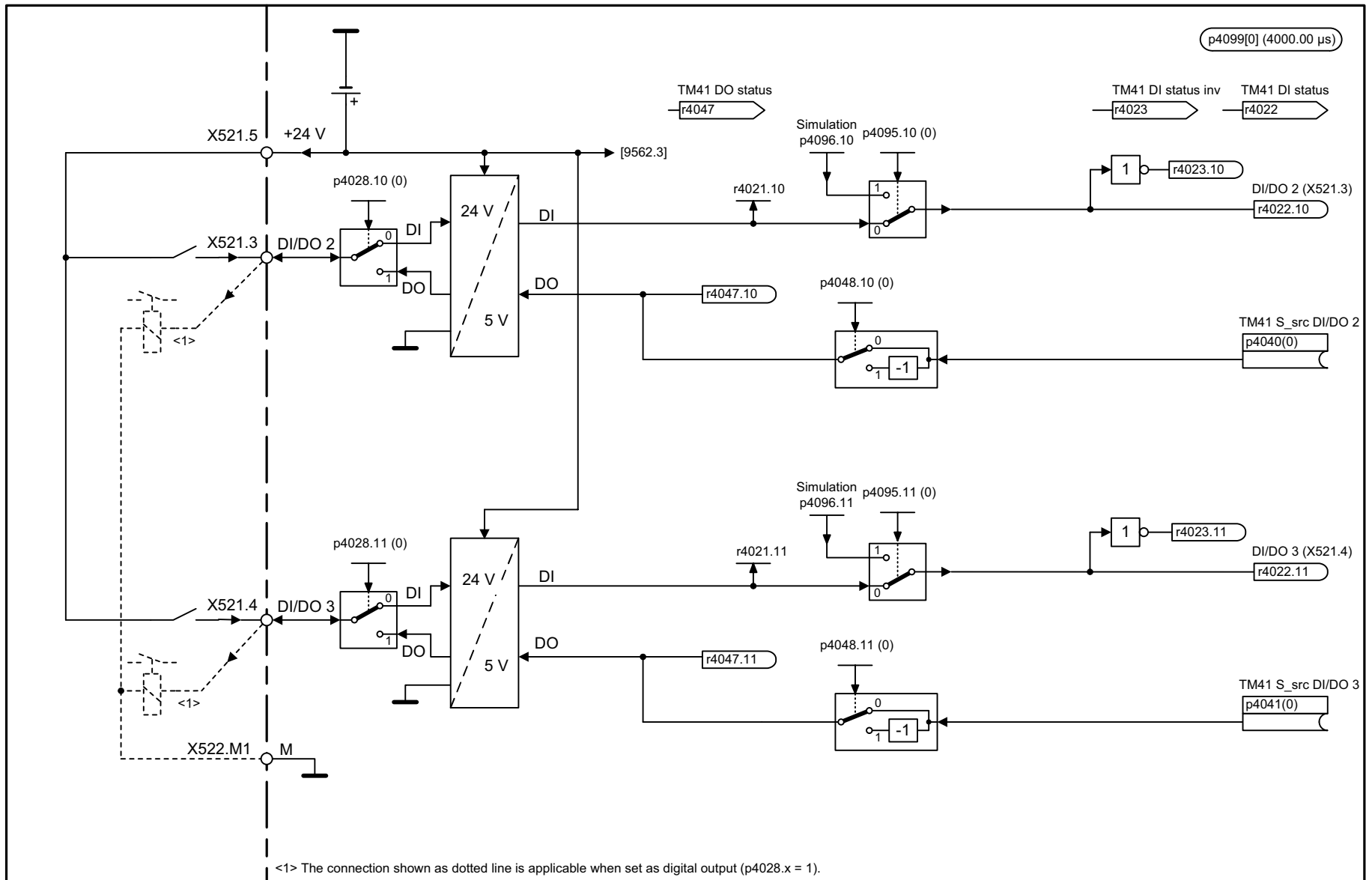
1	2	3	4	5	6	7	8
DO: TM41					fp_9660_01_eng.vsd	Function diagram	
Terminal Module 41 (TM41) - digital inputs, electrically isolated (DI 0 ... DI 3)					05.12.05 V02.04.00	SINAMICS S	
							- 9660 -

Figure 2-242 9660 – Digital inputs, electrically isolated (DI 0 ... DI 3)



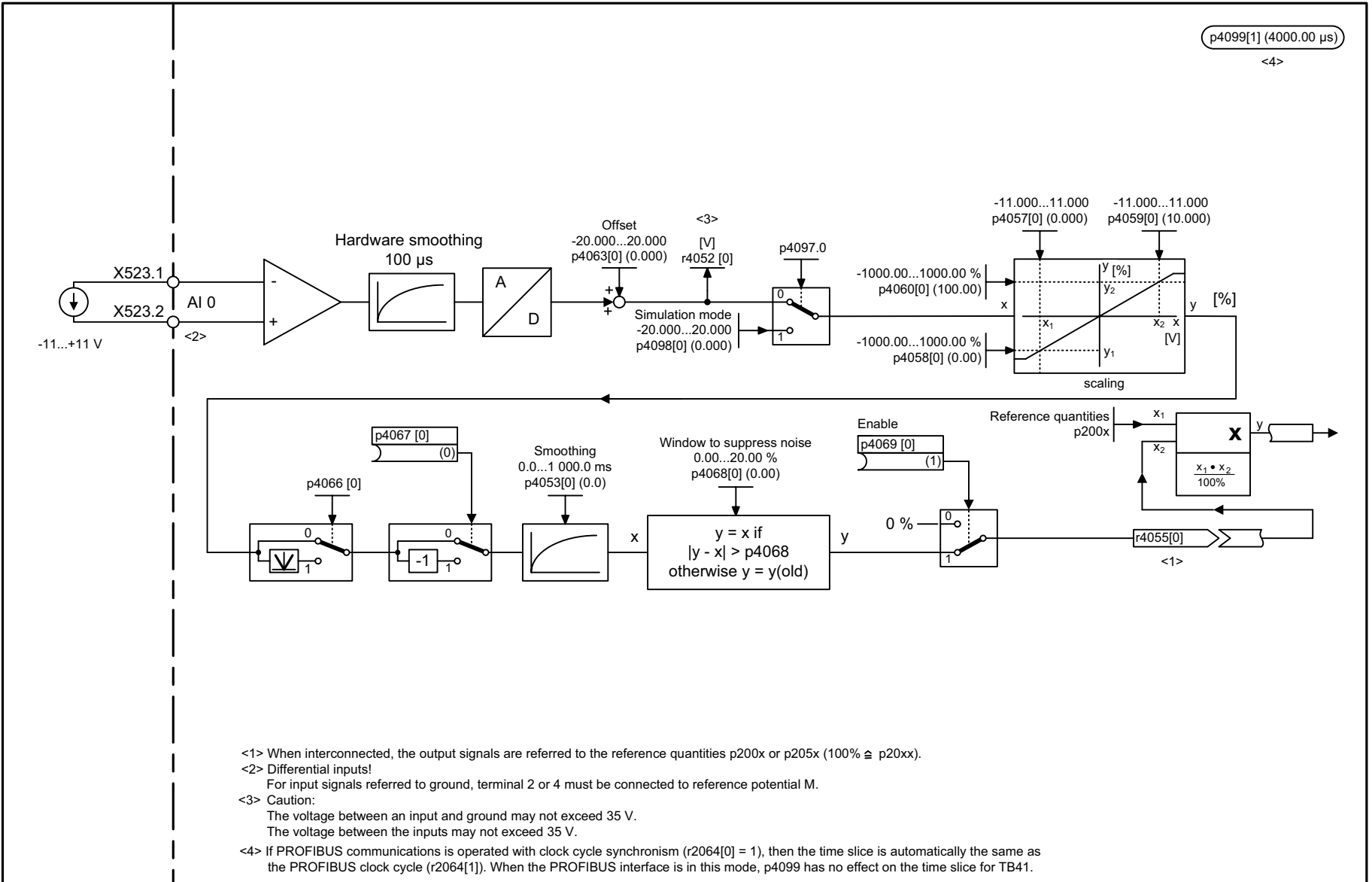
1	2	3	4	5	6	7	8
DO: TM41			fp_9661_01_eng.vsd			Function diagram	
Terminal Module 41 (TM41) - bidirectional digital inputs/outputs (DI/DO 0 ... DI/DO 1)			23.03.06 V02.04.00			SINAMICS S	
							- 9661 -

Figure 2-243 9661 – Digital inputs/outputs, bidirectional (DI/DO 0 ... DI/DO 1)



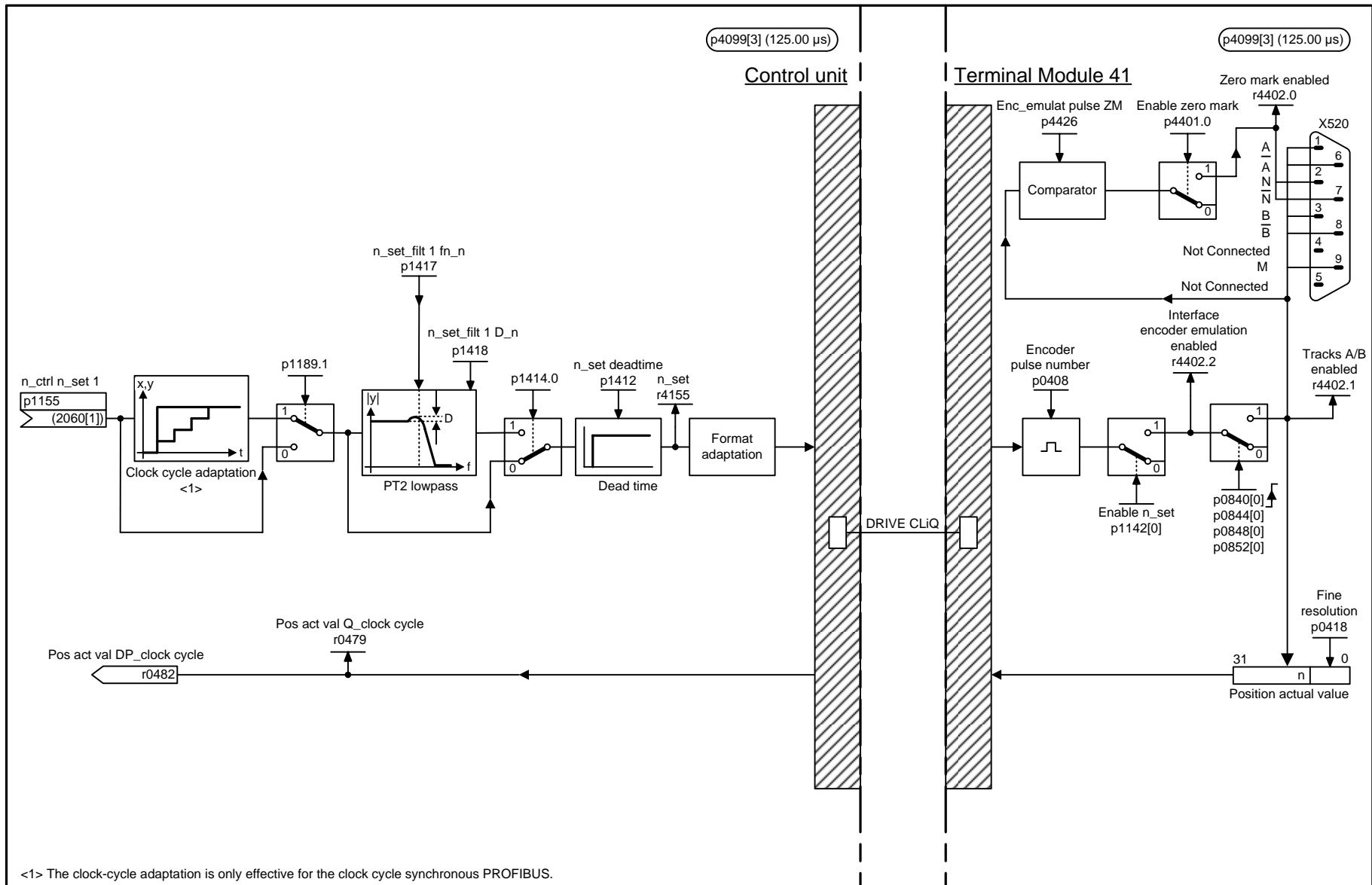
1	2	3	4	5	6	7	8
DO: TM41			fp_9662_01_eng.vsd			Function diagram	
Terminal Module 41 (TM41) - bidirectional digital inputs/outputs (DI/DO 2 ... DI/DO 3)			23.03.06 V02.04.00			SINAMICS S	
							- 9662 -

Figure 2-244 9662 – Digital inputs/outputs, bidirectional (DI/DO 2 ... DI/DO 3)



1	2	3	4	5	6	7	8
DO: TM41					fp_9663_01_eng.vsd	Function diagram	
Terminal Module 41 (TM41) - analog input (AI 0)					23.03.06 V02.04.00	SINAMICS S	
							- 9663 -

Figure 2-245 9663 – Analog input (AI 0)

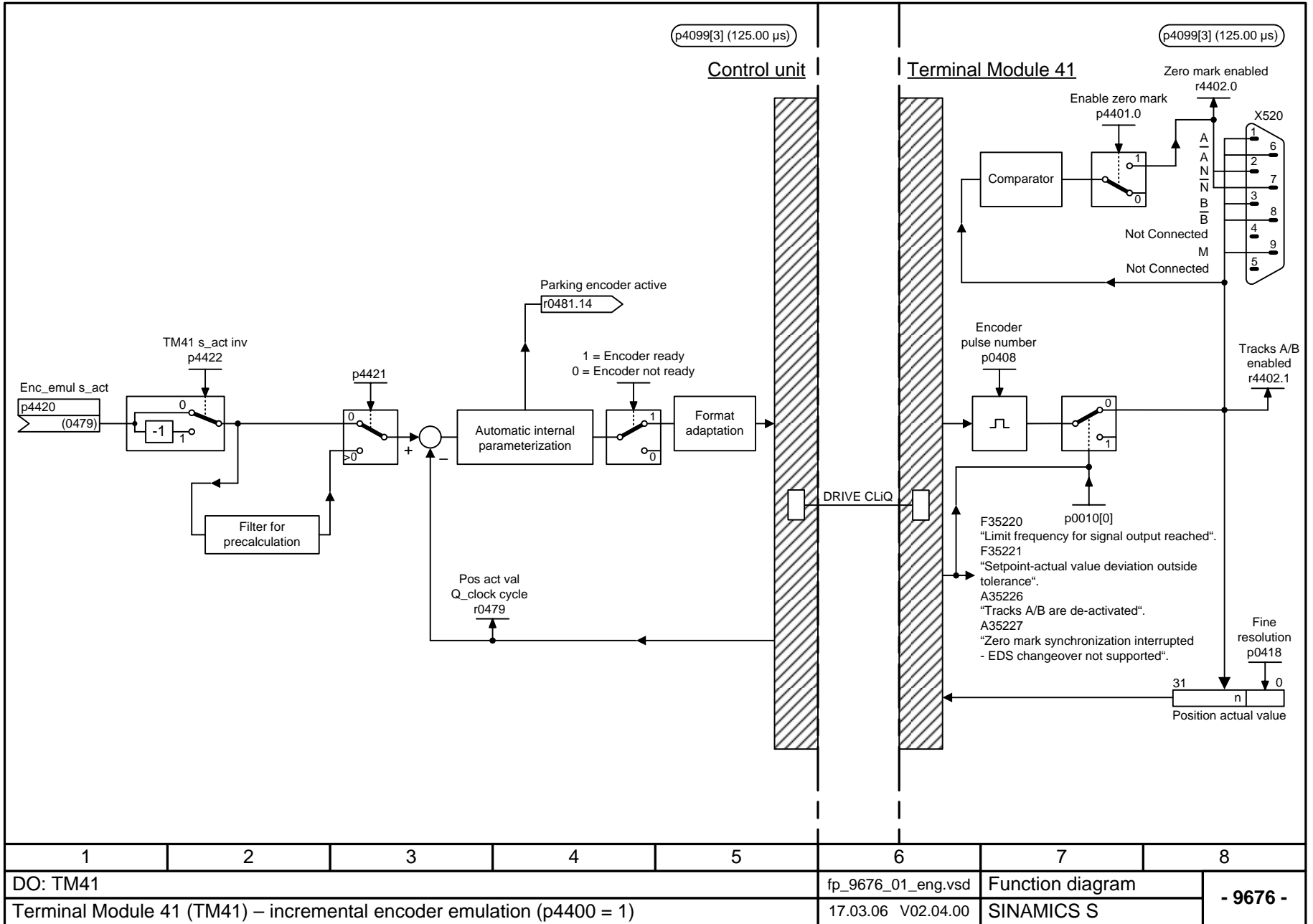


<1> The clock-cycle adaptation is only effective for the clock cycle synchronous PROFIBUS.

1	2	3	4	5	6	7	8
DO: TM41					fp_9674_01_eng.vsd	Function diagram	
Terminal Module 41 (TM41) – incremental encoder emulation (p4400 = 0)					09.03.06 V02.04.00	SINAMICS S	
							- 9674 -

Figure 2-246 9674 – Incremental encoder emulation (p4400 = 0)

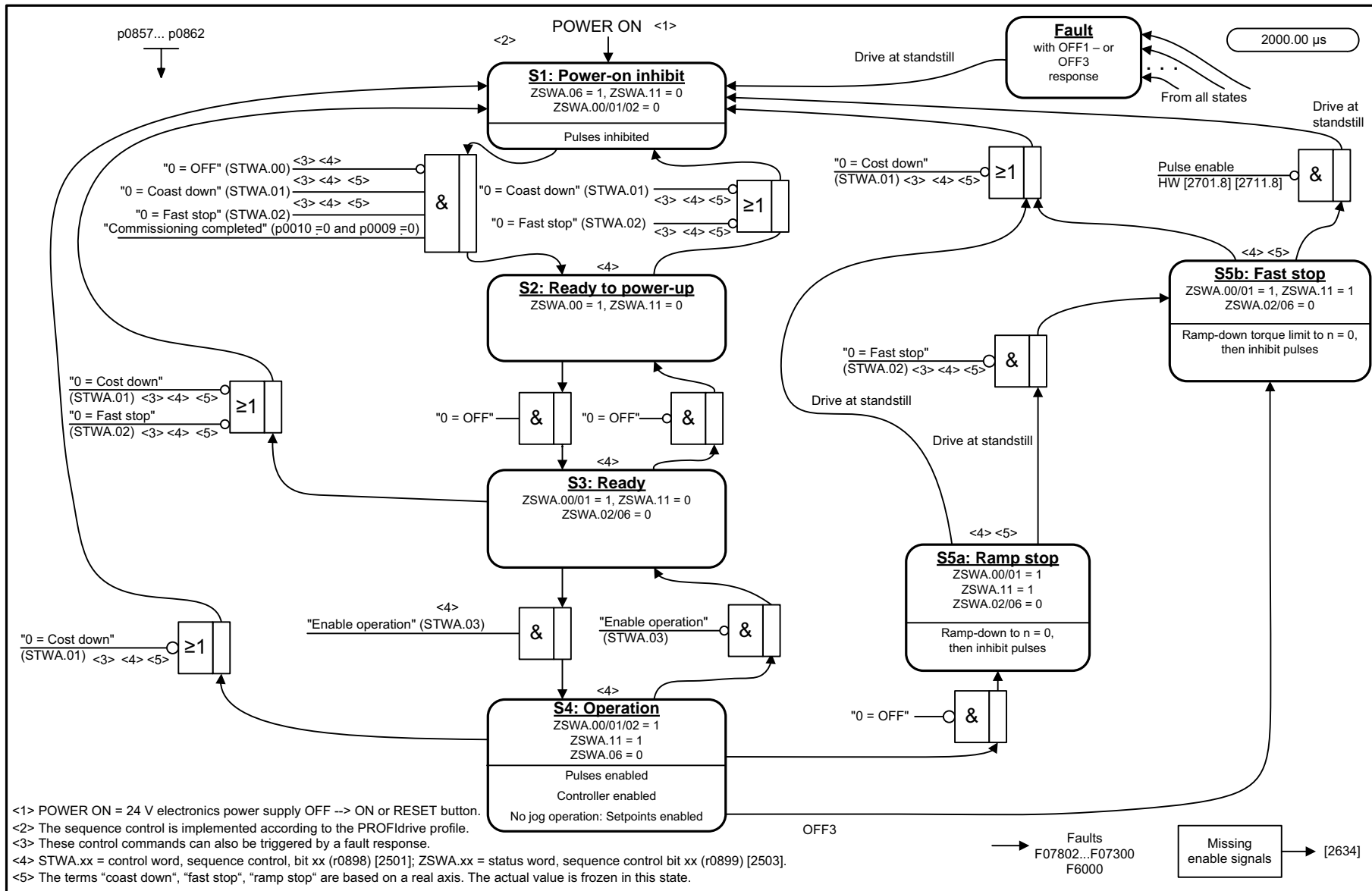
Figure 2-247 9676 – Incremental encoder emulation (p4400 = 1)



Terminal Module 41 (TM41)

Function diagrams

1	2	3	4	5	6	7	8
DO: TM41					fp_9676_01_eng.vsd	Function diagram	
Terminal Module 41 (TM41) – incremental encoder emulation (p4400 = 1)					17.03.06 V02.04.00	SINAMICS S	
							- 9676 -



<1> POWER ON = 24 V electronics power supply OFF --> ON or RESET button.
 <2> The sequence control is implemented according to the PROFIdrive profile.
 <3> These control commands can also be triggered by a fault response.
 <4> STWA.xx = control word, sequence control, bit xx (r0898) [2501]; ZSWA.xx = status word, sequence control bit xx (r0899) [2503].
 <5> The terms "coast down", "fast stop", "ramp stop" are based on a real axis. The actual value is frozen in this state.

1	2	3	4	5	6	7	8
DO: TM41					fp_9682_01_eng.vsd	Function diagram	
Terminal Module 41 (TM41) – sequence control (p4400 = 0)					06.03.06 V02.04.00	SINAMICS S	
							- 9682 -

Figure 2-248 9682 – Sequence control

2.34 Voltage Sensing Module (VSM)

Function diagrams

9880 – Analog inputs (AI 0 ... AI 3)	2-1196
9886 – Temperature evaluation	2-1197
9887 – Sensor monitoring KTY/PTC	2-1198

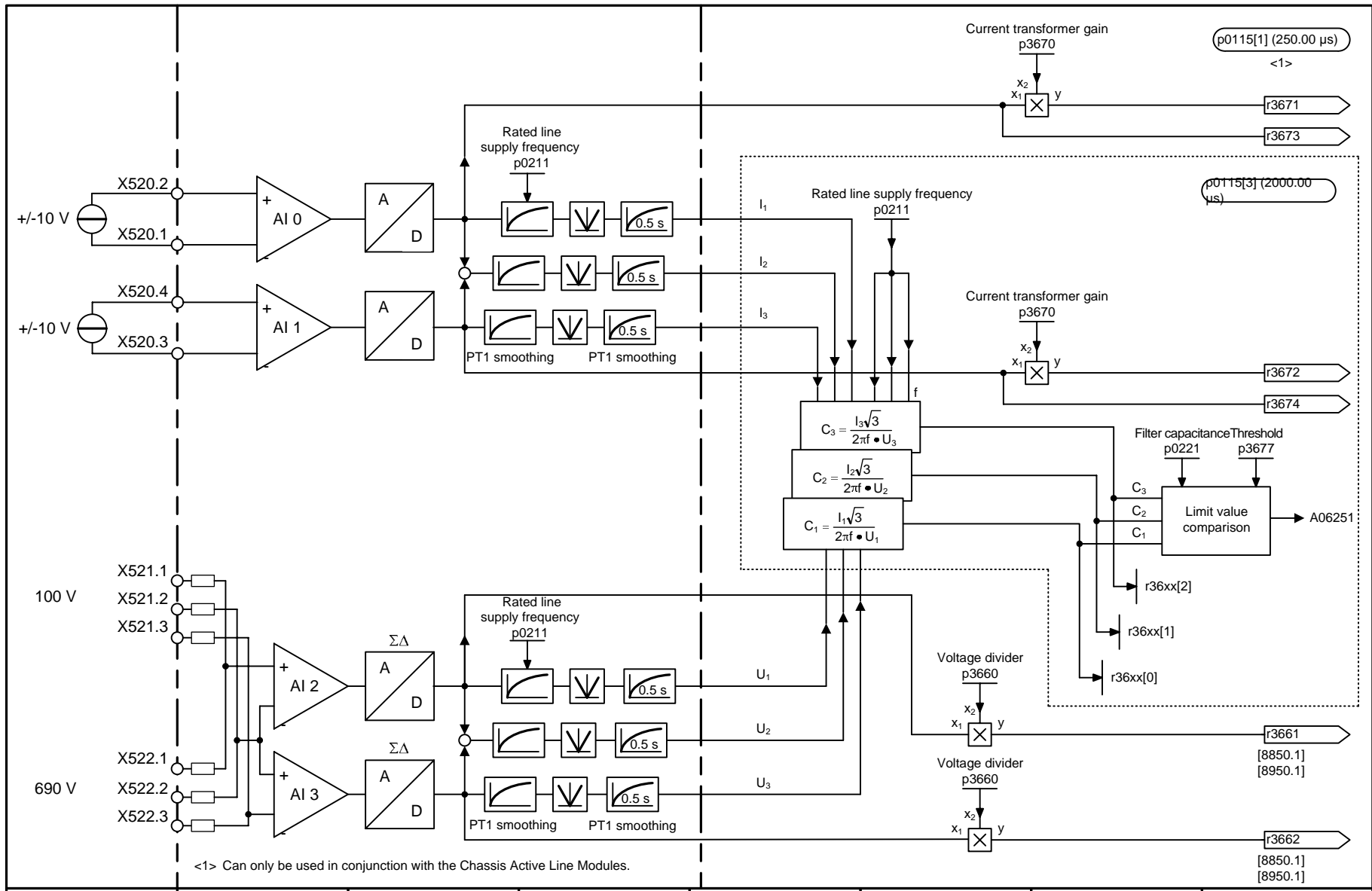
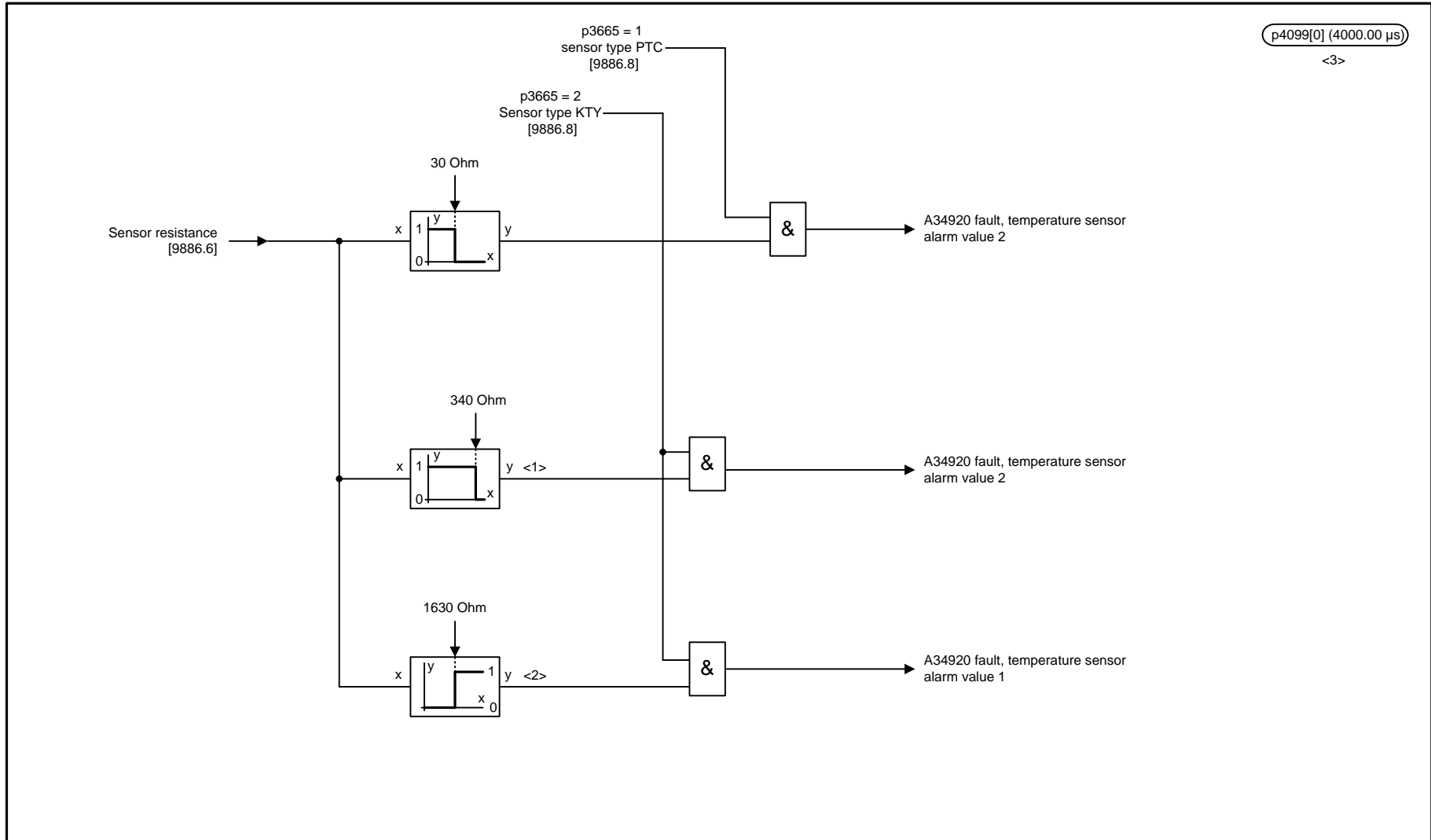


Figure 2-249 9880 – Analog inputs (AI 0 ... AI 3)

1	2	3	4	5	6	7	8
DO: A_INF, S_INF					fp_9880_01_eng.vsd	Function diagram	
Voltage Sensing Module (VSM) - analog inputs (AI 0 ... AI 3)					13.07.05 V02.04.00	SINAMICS S	
							- 9880 -



<1> For KTY 84-130 temperature sensor, the following applies: A threshold value 340 Ohm corresponds to -40 °C.
 <2> For KTY 84-130 temperature sensor, the following applies: A threshold value 1630 Ohm corresponds to +180 °C.
 <3> Can only be used in conjunction with the Chasis Active Line Modules.

1	2	3	4	5	6	7	8
DO: A_INF					fp_S01_9887_en.vsd	Function diagram	
Voltage Sensing Module (VSM) - sensor monitoring KTY/PTC					29.11.04 V02.04.00	SINAMICS S	
							- 9887 -

Figure 2-251 9887 – Sensor monitoring KTY/PTC

2.35 Basic Operator Panel 20 (BOP20)

Function diagrams

9912 – Control word BOP20 interconnection

2-1200

PROFIBUS sampling time
Refer to [1020.7]

Interconnection STW BOP (r0019)		<1>
Signal	Meaning	Interconnection parameters
STW BOP.0	1 = On 0 = OFF (OFF1)	p0840[0] = r0019.0
STW BOP.1	1 = No coast down 0 = Coast down (OFF2)	p0844[0] = r0019.1
STW BOP.2	1 = No fast stop 0 = Fast stop (OFF3)	p0848[0] = r0019.2
STW BOP.3	Reserved	-
STW BOP.4	Reserved	-
STW BOP.5	Reserved	-
STW BOP.6	Reserved	-
STW BOP.7	▲ = Acknowledge fault	p2102[0] = r0019.7
STW BOP.8	Reserved	-
STW BOP.9	Reserved	-
STW BOP.10	Reserved	-
STW BOP.11	Reserved	-
STW BOP.12	Reserved	-
STW BOP.13	1 = Motorized potentiometer, raise	p1035[0] = r0019.13
STW BOP.14	1 = Motorized potentiometer, lower	p1036[0] = r0019.14
STW BOP.15	Reserved	-

<1> The BICO interconnection represents an example that can be changed by customers.

1	2	3	4	5	6	7	8
DO: CU_S					fp_9912_01_eng.vsd	Function diagram	
Basic Operator Panel 20 (BOP20) – control word BOP20 interconnection					09.03.06 V02.04.00	SINAMICS S	
							- 9912 -

Figure 2-252 9912 – Control word BOP20 interconnection

Faults and alarms

3

Contents

3.1	Overview of faults and alarms	3-1202
3.2	List of faults and alarms	3-1211

3.1 Overview of faults and alarms

3.1.1 General information about faults and alarms

Displaying faults/alarms

If a fault occurs, the drive indicates the fault and/or alarm.

The following methods for displaying faults and alarms are available:

- Display via the fault and alarm buffer with PROFIBUS.
- Display online via the commissioning software.

Differences between faults and alarms

The differences between faults and alarms are as follows:

Table 3-1 Differences between faults and alarms

Type	Description
Faults	What happens when a fault occurs? <ul style="list-style-type: none"> • The appropriate fault reaction is triggered. • Status signal ZSW1.3 is set. • The fault is entered in the fault buffer. How are faults eliminated? <ul style="list-style-type: none"> • Remove the original cause of the fault. • Acknowledge the fault.
Alarms	What happens when an alarm occurs? <ul style="list-style-type: none"> • Status signal ZSW1.7 is set. • The alarm is entered in the alarm buffer. How are alarms eliminated? <ul style="list-style-type: none"> • Alarms acknowledge themselves. If the cause of the alarm is no longer present, then they automatically reset themselves.

Fault responses

The following fault responses are defined:

Table 3-2 Fault responses

List	PROFI-drive	Reaction	Description
NONE	-	None	No response when a fault occurs.
OFF1	ON/ OFF	Brake along the ramp generator deceleration ramp followed by pulse disable	<p>Closed-loop speed control (p1300 = 20, 21)</p> <ul style="list-style-type: none"> • n_set = 0 is input immediately to brake the drive along the deceleration ramp (p1121). • When zero speed is detected, the motor holding brake (if parameterized) is closed (p1215). The pulses are suppressed when the brake application time (p1217) expires. <p>Zero speed is detected if the actual speed drops below the threshold in p1226 or if the monitoring time (p1227) started when speed setpoint <= speed threshold (p1226) has expired.</p> <p>Closed-loop torque control (p1300 = 23)</p> <ul style="list-style-type: none"> • The following applies to closed-loop torque control mode: Reaction as for OFF2. • When changing over to closed-loop control using p1501, the following applies: There is no dedicated braking response. If the actual speed drops below the speed threshold (p1226), or the timer stage (p1277) has expired, the motor holding brake (if parameterized) is closed. The pulses are suppressed when the brake application time (p1217) expires.
OFF2	COAST STOP	Internal/external pulse disable	<p>Closed-loop speed and torque control</p> <ul style="list-style-type: none"> • Instantaneous pulse suppression, the drive "coasts" to a standstill. • The motor holding brake (if one is being used) is closed immediately. • Power-on disable is activated.

Table 3-2 Fault responses, continued

List	PROFI-drive	Reaction	Description
OFF3	QUICK STOP	Brake along the OFF3 deceleration ramp followed by pulse disable	<p>Closed-loop speed control (p1300 = 20, 21)</p> <ul style="list-style-type: none"> n_set=0 is input immediately to brake the drive along the OFF3 deceleration ramp (p1135). When zero speed is detected, the motor holding brake (if parameterized) is closed. The pulses are suppressed when the brake application time (p1217) expires. Zero speed is detected if the actual speed drops below the threshold in p1226 or if the monitoring time (p1227) started when speed setpoint <= speed threshold (p1226) has expired. Power-on disable is activated. <p>Closed-loop torque control (p1300 = 23)</p> <ul style="list-style-type: none"> Switchover to speed-controlled operation and other reactions as described for speed-controlled operation.
STOP1	-	-	In preparation
STOP2	-	n_set = 0	<ul style="list-style-type: none"> n_set=0 is input immediately to brake the drive along the OFF3 deceleration ramp (p1135). The drive remains in closed-loop speed control mode.
DCBRAKE	-	-	In preparation
ENCODER	-	Internal/external pulse disable (p0491)	<p>The fault reaction ENCODER is applied as a function of the setting in p0491.</p> <p>Factory setting: p0491 = 0 --> Encoder fault causes OFF2</p>

Acknowledgement of faults

The list of faults and alarms specifies how to acknowledge each fault after the cause has been remedied.

Table 3-3 Acknowledgement of faults

Acknowledgement	Description
POWER ON	<p>The fault is acknowledged by a POWER ON process (switch drive unit off and on again).</p> <p>Note: If this action has not eliminated the fault cause, the fault is displayed again immediately after power up.</p>
IMMEDIATELY	<p>Faults can be acknowledged at an individual drive object (Points 1 to 3) or at all drive objects (point 4) as follows:</p> <p>1 Acknowledge by setting parameter: p3981 = 0 --> 1</p> <p>2 Acknowledge via binector inputs:</p> <p>p2103 BI: 1. Acknowledge faults p2104 BI: 2. Acknowledge faults p2105 BI: 3. Acknowledge faults</p> <p>3 Acknowledge using PROFIBUS control signal: STW1.7 = 0 --> 1 (edge)</p> <p>4 Acknowledging all faults p2102 BI: Acknowledging all faults</p> <p>All of the faults at all of the drive objects of the drive system can be acknowledged using this binector input.</p> <p>Note:</p> <ul style="list-style-type: none"> • These faults can also be acknowledged by a POWER ON operation. • If this action has not eliminated the fault cause, the fault is displayed again immediately after power up. • Safety Integrated faults The "Safe Stop" (SH) function must be deselected before these faults are acknowledged.
PULSE INHIBIT	<p>The fault can only be acknowledged when the pulses are inhibited (r0899.11 = 0). To acknowledge, the same possibilities exist as described under IMMEDIATE acknowledgement.</p>

Save fault buffer on POWER OFF

The contents of the fault buffer are saved to non-volatile storage when the Control Unit 320 (CU320) is powered down, i.e. the fault buffer history is still available when the unit is powered up again.

Note:

Prerequisites:

- Firmware with version V2.2 or later.
- Control Unit 320 (CU320) with hardware version C or higher.
The hardware version is shown on the rating plate or can be displayed online with the commissioning software (in Project Navigator under "Drive Unit" --> Configuration --> Version Overview).

If these conditions are not fulfilled, the contents of the fault buffer are deleted on every POWER ON.

The fault buffer of a drive object comprises the following parameters:

- r0945[0...63], r0947[0...63], r0948[0...63], r0949[0...63]
- r2109[0...63], r2130[0...63], r2133[0...63], r2136[0...63]

The fault buffer contents can be deleted manually as follows:

- Delete fault buffer for all drive objects:
p2147 = 1 --> p2147 = 0 is automatically set after execution.
- Delete fault buffer for a specific drive object:
p0952 = 0 --> The parameter belongs to the specified drive object.

The fault buffer contents are automatically deleted in response to the following events:

- Restore factory setting (p0009 = 30 and p0976 = 1).
- Download with modified structure (e.g. number of drive objects changed).
- Power-up after other parameter values have been loaded (e.g. p0976 = 10).
- Firmware release upgrade.

3.1.2 Explanation of the list of faults and alarms

The data in the following example has been chosen at random. A description can contain the information listed below. Some of the information is optional.

The list of faults and alarms (see Section 3.2) has the following layout:

----- **Start of example** -----

Axxxxx (F, N)	Fault location (optional): Name
Reaction:	NONE
Acknowledgement:	NONE
Cause:	Description of possible causes. Fault value (r0949, interpret format): or alarm value (r2124, interpret format): (optional) Information about fault or alarm values (optional).
Remedy:	Description of possible remedies.
Reaction to F:	A_INFEED: OFF2 (OFF1, NONE) SERVO: NONE (OFF1, OFF2, OFF3) VECTOR: NONE (OFF1, OFF2, OFF3)
Acknowledgement for F:	IMMEDIATELY (POWER ON)
Reaction to N:	NONE
Acknowledgement for N:	NONE

- Axxxxx** Alarm xxxxx
- Axxxxx (F, N)** Alarm xxxxx (message type can be changed to F or N)
- Fxxxxx** Fault xxxxx
- Fxxxxx (A, N)** Fault xxxxx (report type can be changed to A or N)
- Nxxxxx** No message
- Nxxxxx (A)** No message (message type can be changed to A)
- Cxxxxx** Safety message (separate message buffer)

A report comprises a letter followed by the relevant number.

The meaning of the letters is as follows:

- A means "Alarm"
- F means "Fault"
- N means "No Report" or "Internal Report"
- C means "Safety message"

The optional brackets indicate whether the type specified for this report can be changed and which report types can be adjusted via parameter (p2118, p2119).

Information about reaction and acknowledgement are specified independently for a report with adjustable report type (e.g. reaction to F, acknowledgement for F).

Note:

You can change the default properties of a fault or alarm by setting parameters.

References: //IH1/ SINAMICS S120 Installation and Start-Up Manual
"Diagnosis" section

The list of faults and alarms (see Section 3.2) provide information referred to the properties of a message/report that have been set as standard. If the properties of a specific message/report are changed, then the appropriate information may have to be modified in this list.

Fault location (optional): Name

The fault location (optional), the name of the fault or alarm and the report number all serve to identify the report (e.g. with the commissioning software).

Reaction: Default fault reaction (adjustable fault reaction)

Specifies the default reaction in the event of a fault.

The optional brackets indicate whether the default fault reaction can be changed and which fault reactions can be adjusted via parameter (p2100, p2101).

Note:

See Subsection 3.1.1

Acknowledgement: Default acknowledgement (adjustable acknowledgement)

Specifies the default method of fault acknowledgement after the cause has been eliminated.

The optional brackets indicate whether the default acknowledgement can be changed and which acknowledgement can be adjusted via parameter (p2126, p2127).

Note:

See Subsection 3.1.1

Cause:

Description of the possible causes of the fault/alarm A fault or alarm value is also specified as an option.

Fault value (r0949, format):

The fault value is entered in the fault buffer in r0949[0...63] and specifies additional, precise information about a fault.

Alarm value (r2124, format):

The alarm value specifies additional, precise information about an alarm.

The alarm value is entered in the alarm buffer in r2124[0...7] and specifies additional, precise information about an alarm.

Remedy:

Description of the potential methods for eliminating the cause of the active fault or alarm.



Warning

In individual cases, the servicing and maintenance personnel are responsible for choosing a suitable method for eliminating the cause of faults.

3.1.3 Numerical ranges of faults and alarms

Faults and alarms are organized into the following numerical ranges:

Table 3-4 Numerical ranges of faults and alarms

from	to	Section
1000	2999	Control Unit
3000	4999	Reserved
5000	5999	Power unit
6000	6999	Infeed
7000	7999	Drives
8000	8999	Option Board
9000	29999	Reserved
30000	30999	DRIVE-CLiQ component power section
31000	31999	DRIVE-CLiQ component encoder 1
32000	32999	DRIVE-CLiQ component encoder 2
33000	33999	DRIVE-CLiQ component encoder 3
34000	34999	Reserved
35000	35999	Terminal Module 31 (TM31)
36000	49999	Reserved
50000	50399	Communication Board (COMM BOARD)
50400	65535	Reserved

3.2 List of faults and alarms

Product: SINAMICS S, Version: 2402300, Language: eng

F01000 Internal software error
Reaction: OFF2
Acknowledge: POWER ON
Cause: An internal software error has occurred.
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.
Remedy:
- carry-out a POWER ON (power off/on) for all components.
- upgrade the firmware release.
- contact the Hotline.
- replace the Control Unit.

F01001 Internal software error
Reaction: OFF2
Acknowledge: POWER ON
Cause: An internal software error has occurred.
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.
Remedy:
- carry-out a POWER ON (power off/on) for all components.
- upgrade the firmware release.
- contact the Hotline.

F01002 Internal software error
Reaction: OFF2
Acknowledge: POWER ON
Cause: An internal software error has occurred.
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.
Remedy:
- carry-out a POWER ON (power off/on) for all components.
- upgrade the firmware release.
- contact the Hotline.

F01003 Acknowledgment delay when accessing the memory
Reaction: OFF2
Acknowledge: POWER ON
Cause: A memory area was accessed that does not return a "READY".
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.
Remedy:
- carry-out a POWER ON (power off/on) for all components.
- contact the Hotline.

F01005	Firmware download DRIVE-CLiQ component unsuccessful
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Firmware was not able to be downloaded into a DRIVE-CLiQ component. Fault value (r0949): xxyyyy hex: xx = component number, yyyy = cause of the fault. Cause of the fault (decimal): 011: DRIVE-CLiQ component has detected a checksum error. 015: The selected DRIVE-CLiQ component did not accept the contents of the firmware file. 101: After several communication attempts, not response from the DRIVE-CLiQ component. 140: Firmware file for the DRIVE-CLiQ component not available on the CompactFlash card. 143: Component is not changed in the firmware download mode. 156: Component with the specified component number is not available (p7828). Additional values: Only for internal Siemens troubleshooting.
Remedy:	- check the selected component number (p7828). - check the DRIVE-CLiQ connection. - save suitable firmware file for download in the directory /siemens/sinamics/code/sac/. - after POWER ON has been carried-out again for the DRIVE-CLiQ component, download the firmware again.
A01006	Firmware update DRIVE-CLiQ component required
Reaction:	NONE
Acknowledge:	NONE
Cause:	The firmware of a DRIVE CLiQ component must be updated as there is no suitable firmware or firmware version in the component for operation with the Control Unit. Alarm value (r2124, decimal): Component number of the DRIVE-CLiQ component.
Remedy:	Firmware update using the commissioning software: The firmware version of all of the components on the "version overview" page can be read in the Project Navigator under "Configuration" of the associated drive unit and an appropriate firmware update can be carried-out. Firmware update via parameter: - take the component number from the alarm value and enter into p7828. - start the firmware download with p7829 = 1.
A01007	POWER ON DRIVE-CLiQ component required
Reaction:	NONE
Acknowledge:	NONE
Cause:	A DRIVE-CLiQ component must be powered-up again (POWER ON) as, for example, the firmware was updated. Alarm value (r2124, decimal): Component number of the DRIVE-CLiQ component.
Remedy:	Switch-out the power supply of the specified DRIVE-CLiQ component and switch-in again.
F01010	Drive type unknown
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	An unknown drive type was found. Fault value (r0949, decimal): Drive object type (refer to p0101, p0107).
Remedy:	- carry-out a POWER ON (power off/on) for all components. - upgrade the firmware release. - contact the Hotline.

F01015 Internal software error

Reaction: OFF2
Acknowledge: POWER ON
Cause: An internal software error has occurred.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.
Remedy: - carry-out a POWER ON (power off/on) for all components.
 - upgrade the firmware release.
 - contact the Hotline.

A01016 (F) CompactFlash card changed

Reaction: NONE
Acknowledge: NONE
Cause: On the CompactFlash card, at least one file in the directory /SIEMENS/SINAMICS/ has been illegally changed with respect to that supplied from the factory. No changes are permitted in this directory.
 Alarm value (r2124, decimal):
 0: Checksum of one file is incorrect.
 1: File missing.
 2: Too many files.
 3: Incorrect firmware version.
 4: Incorrect checksum of the back-up file.
 See also: r9925 (CompactFlash card file error)
Remedy: For the CompactFlash card, restore the status when originally supplied from the factory.
 Note:
 The file involved can be read-out using parameter r9925.
 See also: r9926 (CompactFlash card check status)
 Reaction upon F: OFF2
 Acknowledge upon F: POWER ON

A01017 Component lists changed

Reaction: NONE
Acknowledge: NONE
Cause: On the CompactFlash card, one file in the directory /SIEMENS/SINAMICS/DATA or /ADDON/SINAMICS/DATA has been illegally changed with respect to that supplied from the factory. No changes are permitted in this directory.
 Alarm value (r2124, decimal):
 The problem is indicated in the first digit of the alarm value:
 1: File does not exist.
 2: Firmware version of the file does not match-up with the software version.
 3: The file checksum is incorrect.
 The second digit of the alarm value indicates in which directory the file is located:
 0: Directory /SIEMENS/SINAMICS/DATA/
 1: Directory /ADDON/SINAMICS/DATA/
 The third digit of the alarm value indicates the file:
 0: File MOTARM.ACX
 1: File MOTSRM.ACX
 2: File MOTSLM.ACX
 3: File ENCDATA.ACX
 4: File FILTDATA.ACX
 5: File BRKDATA.ACX
Remedy: For the CompactFlash card file involved, restore the status when originally supplied from the factory.

F01030	Monitoring, master control: Sign of life failure PC
Reaction:	OFF1
Acknowledge:	IMMEDIATELY
Cause:	For active PC master control, no sign-of-life was received within the monitoring time. The master control was returned to the active BICO interconnection.
Remedy:	Set the monitoring time higher at the PC/AOP or disable completely. Notice: The monitoring time should be set as short as possible. A long monitoring time means a late response when the communications fail! The monitoring time is set in milliseconds. - in the AOP using the Main menu -> Settings -> Control settings -> Timeout monitoring - In STARTER using <Drive> -> Commissioning -> Control panel -> Button "Fetch master control" -> a window is displayed in which the monitoring time can be set.
F01033	Units changeover: Reference parameter value invalid
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	When changing over the units into the referred representation type, it is not permissible that any of the reference parameters required are equal to 0.0 Fault value (r0949, parameter): Reference parameter, whose value is 0.0. See also: p0349 (Selects system of units, motor equivalent circuit diagram data), p0505 (Selecting the system of units), p0595 (Selecting technological units)
Remedy:	Set the value of the reference parameter to a number different than 0.0. See also: p0304 (Rated motor voltage), p0305 (Rated motor current), p0310 (Rated motor frequency), p0596 (Reference quantity, technological units), p2000 (Reference frequency), p2001 (Reference voltage), p2002 (Reference current), p2003 (Reference torque), r2004 (Reference power)
F01034	Units changeover: Calculation parameter values after reference value change unsuccessful
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The change of a reference parameter meant that for a parameter involved, the selected value was not able to be recalculated in the per unit notation. The change was rejected, the original parameter values were restored. Fault value (r0949, parameter): Parameter, whose value was not able to be re-calculated. See also: p0304 (Rated motor voltage), p0305 (Rated motor current), p0310 (Rated motor frequency), p0596 (Reference quantity, technological units), p2000 (Reference frequency), p2001 (Reference voltage), p2002 (Reference current), p2003 (Reference torque), r2004 (Reference power)
Remedy:	Select the value of the reference parameters so that the parameter involved can be calculated in the per unit notation. See also: p0304 (Rated motor voltage), p0305 (Rated motor current), p0310 (Rated motor frequency), p0596 (Reference quantity, technological units), p2000 (Reference frequency), p2001 (Reference voltage), p2002 (Reference current), p2003 (Reference torque), r2004 (Reference power)
A01035 (F)	ACX: Boot from the back-up parameter back-up files
Reaction:	NONE
Acknowledge:	NONE
Cause:	When the Control Unit booted, no complete data set was found from the parameter back-up files. The last time that the parameterization was saved, it was not completely carried-out. Instead, a back-up data set or a back-up parameter back-up file is downloaded. Alarm value (r2124, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	If you saved the project in the commissioning software, download your project again and save using the function "Copy RAM to ROM" or with p0977 = 1. This means that all of the parameter files are again completely written into the CompactFlash card.

Reaction upon F: A_INFEED: NONE (OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY

F01036 (A) ACX: Parameter back-up file missing

Reaction: A_INFEED: NONE (OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: When downloading the device parameterization, a parameter back-up file associated with a drive object cannot be found. Neither a PSxxxxxyy.ACX, a PSxxxxxyy.NEW nor a PSxxxxxyy.BAK parameter back-up file exists on the CompactFlash card for this drive object.
 Fault value (r0949, interpret hexadecimal):
 Byte 1: yyy in the file name PSxxxxxyy.ACX
 yyy = 000 --> consistency back-up file
 yyy = 001 ... 062 --> drive object number
 yyy = 099 --> PROFIBUS parameter back-up file
 Byte 2, 3, 4:
 Only for internal Siemens troubleshooting.

Remedy: If you have saved your project data using the commissioning software, carry-out a new download for your project. Save using the function "Copy RAM to ROM" or with p0977 = 1 so that all of the parameter files are again completely written into the CompactFlash card.
 If you have not saved the project data, then the system must be again commissioned for the first time.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F01037 (A) ACX: Re-naming the parameter back-up file not successful

Reaction: A_INFEED: NONE (OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The re-naming after saving a parameter back-up file on the CompactFlash card or in the volatile memory was unsuccessful.
 One of the parameter back-up files to be re-named had the "read only" attribute. The parameter back-up files are saved on the CompactFlash card in the directory \USER\SINAMICS\DATA.
 It is possible that the CompactFlash card is defective.
 Fault value (r0949, interpret hexadecimal):
 Byte1: yyy in file names PSxxxxxyy.* or CAxxxxxyy.* or CCxxxxxyy.*
 yyy = 000 --> consistency back-up file
 yyy = 099 --> PROFIBUS parameter back-up file PSxxx099.*
 Byte 2: xxx in the file name PSxxxxxyy.*
 xxx = 000 --> data save started with p0977 = 1
 xxx = 010 --> data save started with p0977 = 10
 xxx = 011 --> data save started with p0977 = 11
 xxx = 012 --> data save started with p0977 = 12
 Byte 4, 3:
 Only for internal Siemens troubleshooting.

Remedy: - check whether one of the files to be overwritten has the attribute "read only" and change this file attribute into "writable". Check all of the files (PSxxxxxyy.*, CCxxxxxyy.*, CAxxxxxyy.*) that belong to drive yyy designated in the fault value.
 - replace the CompactFlash card.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F01038 (A) ACX: Loading the parameter back-up file not successful

Reaction: A_INFEED: NONE (OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: An error occurred when loading PSxxxxxyy.ACX or PTxxxxyy.ACX files from the CompactFlash card or from the volatile memory of the Control Unit.
 Fault value (r0949, interpret hexadecimal):
 Byte 1: yyy in the file name PSxxxxyy.ACX
 yyy = 000 --> consistency back-up file
 yyy = 001 ... 062 --> drive object number
 yyy = 099 --> PROFIBUS parameter back-up file
 Byte 4, 3, 2:
 Only for internal Siemens troubleshooting.

Remedy: - if you have saved your project data using the commissioning software, carry-out a new download for your project. Save using the function "Copy RAM to ROM" or with p0977 = 1 so that all of the parameter files are again completely written into the CompactFlash card.
 - replace the CompactFlash card.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F01039 (A) ACX: Writing to the parameter back-up file was unsuccessful

Reaction: A_INFEED: NONE (OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Writing to at least one parameter-back-up file PSxxxxyy.NEW on the CompactFlash card was unsuccessful.
 - on the CompactFlash card in the directory /USER/SINAMICS/DATA/ at least one parameter back-up file has the "read only" file attribute and cannot be overwritten.
 - there is not sufficient free memory space on the CompactFlash card.
 - the CompactFlash card is defective and cannot be written to.
 Fault value (r0949, interpret hexadecimal):
 Byte 1: yyy in the file name PSxxxxyy.NEW
 yyy = 000 --> consistency back-up file
 yyy = 001 ... 062 --> drive object number
 yyy = 099 --> PROFIBUS parameter back-up file
 Byte 2: xxx in the file name PSxxxxyy.NEW
 xxx = 000 --> data save started with p0977 = 1
 xxx = 010 --> data save started with p0977 = 10
 xxx = 011 --> data save started with p0977 = 11
 xxx = 012 --> data save started with p0977 = 12
 Byte 4, 3:
 Only for internal Siemens troubleshooting.

Remedy: - check the file attribute of the files (PSxxxxyy.*, Cxxxxyy.*, CCxxxxyy.*) and, if required, change from "read only" to "writeable".
 - check the free memory space on the CompactFlash card. Approx. 40 kbyte of free memory space is required for every drive object in the system.
 - replace the CompactFlash card.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F01040 Save parameter settings and carry-out a POWER ON

Reaction: OFF2

Acknowledge: POWER ON

Cause: A parameter was changed in the drive system that means that it is necessary to save the parameters and re-boot (e.g. p0110).

Remedy:
- save the parameters (p0971/p0977).
- carry-out a POWER ON (power off/on) for all components.

F01041 Parameter save necessary

Reaction: NONE

Acknowledge: IMMEDIATELY

Cause: Defective or missing files were detected on the CompactFlash card when booting.

Fault value (r0949, decimal):
-1: Source file cannot be opened.
-2: Source file cannot be read.
-3: Target directory cannot be set-up.
-4: Target file cannot be set-up/opened.
-5: Target file cannot be written into.

Additional values:
Only for internal Siemens troubleshooting.

Remedy:
- save the parameters (p0977).
- download the project again into the drive unit.

F01042 Parameter error during project download

Reaction:
A_INFEED: OFF2 (NONE, OFF1)
SERVO: OFF2 (NONE, OFF1, OFF3)
VECTOR: OFF2 (NONE, OFF1, OFF3)

Acknowledge: IMMEDIATELY

Cause: An error was detected when downloading a project using the commissioning (start-up) software (e.g. incorrect parameter value).
For the specified parameter, it was detected that dynamic limits were exceeded that could possibly depend on other parameters.

Fault value (r0949, decimal):
Low word: Parameter number (16 bits without sign)
Byte 3: Parameter index
Byte 4: Error ID
0: Parameter number illegal.
1: Parameter value cannot be changed.
2: Lower or upper value limit exceeded.
3: Sub-index incorrect.
4: No array, no sub-index.
5: Data type incorrect.
6: Setting not permitted (only resetting).
7: Descriptive element cannot be changed.
9: Descriptive data not available.
11: No master control.
15: No text array present.
17: Task cannot be executed due to operating status.
20: Illegal value.
21: Response too long.
22: Parameter address illegal.
23: Format illegal.
24: Number of values not consistent.
25: Drive object does not exist.
101: Presently de-activated.
104: Illegal value.
107: Write access not permitted when controller enabled.
108: Units unknown.
109: Write access only in the commissioning state, encoder (p0010 = 4).

- 110: Write access only in the commissioning state, motor (p0010 = 3).
- 111: Write access only in the commissioning state, power unit (p0010 = 2).
- 112: Write access only in the quick commissioning mode (p0010 = 1).
- 113: Write access only in the ready mode (p0010 = 0).
- 114: Write access only in the commissioning state, parameter reset (p0010 = 30).
- 115: Write access only in the Safety Integrated commissioning state (p0010 = 95).
- 116: Write access only in the commissioning state, technological application/units (p0010 = 5).
- 117: Write access only in the commissioning state (p0010 not equal to 0).
- 118: Write access only in the commissioning state, download (p0010 = 29).
- 119: Parameter may not be written into in download.
- 120: Write access only in the commissioning state – drive basis configuration (device: p0009 = 3).
- 121: Write access only in the commissioning state – define drive type (device: p0009 = 2).
- 122: Write access only in the commissioning state – data set basis configuration (device: p0009 = 4).
- 123: Write access only in the commissioning state – device configuration (device: p0009 = 1).
- 124: Write access only in the commissioning state – device download (device: p0009 = 29).
- 125: Write access only in the commissioning state – device parameter reset (device: p0009 = 30).
- 126: Write access only in the commissioning state – device ready (device: p0009 = 0).
- 127: Write access only in the commissioning state – device (device: p0009 not equal to 0).
- 129: Parameter may not be written into in download.
- 130: Transfer of the master control is inhibited via BI: p0806.
- 131: Required BICO interconnection not possible, because BICO output does not supply floating value
- 132: Free BICO interconnection inhibited via p0922.
- 133: Access method not defined.
- 200: Below the valid values.
- 201: Above the valid values.
- 202: Cannot be accessed from the Basic Operator Panel (BOP).
- 203: Cannot be read from the Basic Operator Panel (BOP).
- 204: Write access not permitted.

Remedy:

- enter the correct value into the specified parameter.
- identify the parameter that narrows (restricts) the limits of the specified parameter.

F01043 Fatal error when downloading a project

Reaction: A_INFEED: OFF2 (OFF1)
 SERVO: OFF2 (OFF1, OFF3)
 VECTOR: OFF2 (OFF1, OFF3)

Acknowledge: IMMEDIATELY

Cause: A fatal error was detected when downloading a project using the commissioning (start-up) software.
 Fault value (r0949, decimal):

- 1: Device status cannot be changed to Device Download (drive object ON?).
- 2: Drive object ID incorrect
- 3: A drive object that has already been deleted is deleted again.
- 4: Deletes drive object that has already been registered for generation.
- 5: Deletes a drive object that no longer exists.
- 6: Generating an undeleted drive object that already existed.
- 7: Regeneration of a drive object already registered for generation.
- 8: Maximum number of drive objects that can be generated exceeded.
- 9: Error while generating a device drive object.
- 10: Error while generating target topology parameters (p9902 and p9903).
- 11: Error when generating a drive object (global component).
- 12: Error when generating a drive object (drive component).
- 13: Unknown drive object type.
- 14: Drive status cannot be changed to Ready (p0947 and p0949).
- 15: Drive status cannot be changed to Drive Download.
- 16: Device status cannot be changed to Ready.
- 17: It is not possible to download the topology. The component wiring should be checked, taking into account the various messages/signals.
- 18: A new download is only possible if the factory settings are re-established for the drive unit.
- 19: The slot for the option module has been configured several times (e.g. CAN and COMM BOARD)
- 20: The configuration is inconsistent (e.g. CAN for Control Unit, however no CAN configured for drive objects - Active Line Module, servo or vector).

Remedy:

- use the actual version of the commissioning software.
- modify the offline project and carry-out a new download (e.g. compare the number of drive objects, motor, encoder, power unit in the offline project and at the drive).
- change the drive system (is a drive rotating or is there a message/signal?).
- carefully note any other messages/signals and remove their cause.

F01044 CU CompactFlash: Message incorrectly written

Reaction: OFF2

Acknowledge: POWER ON

Cause: An error was detected when loading the message descriptions (FDxxxxxy.ACX) saved on the CompactFlash card. Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy: Replace the CompactFlash card.

A01045 CU CompactFlash: Configuring data invalid

Reaction: NONE

Acknowledge: NONE

Cause: An invalid data type was detected when evaluating parameter files PSxxxxxy.ACX, PTxxxxxy.ACX, CAxxxxxy.ACX or CCxxxxxy.ACX, saved on the CompactFlash card. Alarm value (r2124, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy: Restore the factory setting using (p0976 = 1) and re-load the project into the drive unit. Operation without any restrictions is then possible.
After downloading the project, save the parameterization in STARTER using the function "Copy RAM to ROM" or with p0977 = 1. This means that the incorrect parameter files are overwritten on the CompactFlash card.

A01046 (F) CU CompactFlash: Configuring data invalid

Reaction: NONE

Acknowledge: NONE

Cause: An invalid data type was detected when evaluating the parameter files PSxxxxxy.ACX, PTxxxxxy.ACX, CAxxxx-yy.ACX or CCxxxxxy.ACX saved on the CompactFlash card. Alarm value (r2124, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy: Restore the factory setting using (p0976 = 1) and re-load the project into the drive unit. Operation without any restrictions is then possible.
After downloading the project, save the parameterization in STARTER using the function "Copy RAM to ROM" or with p0977 = 1 so that the incorrect parameter files are overwritten on the CompactFlash card.

Reaction upon F: A_INFEED: NONE (OFF2)
SERVO: NONE (OFF1, OFF2, OFF3)
VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY

A01047 (F) ACX: Write to parameter error

Reaction: NONE

Acknowledge: NONE

Cause: When evaluating the parameters files PSxxxxxy.ACX, PTxxxxxy.ACX, CAxxxxxy.ACX or CCxxxxxy.ACX, saved on the CompactFlash card, a parameter value was not able to be transferred into the Control Unit memory. Alarm value (r2124, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy: Restore the factory setting using (p0976 = 1) and re-load the project into the drive unit. Operation without any restrictions is then possible.
After downloading the project, save the parameterization in STARTER using the function "Copy RAM to ROM" or with p0977 = 1. This means that the incorrect parameter files are overwritten on the CompactFlash card.

Reaction upon F: A_INFEED: NONE (OFF2)
SERVO: NONE (OFF1, OFF2, OFF3)
VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY

A01049	CU CompactFlash: It is not possible write to file
Reaction:	NONE
Acknowledge:	NONE
Cause:	It is not possible to write into a write-protective file (PSxxxxxx.acx). The write request was interrupted. Alarm value (r2124, decimal): Drive object number.
Remedy:	Check whether the write-protected attribute has been set for the files on the CompactFlash card under .../USER/SINAMICS/DATA/... When required, remove write protection and save again (e.g. set p0971 to 1).
F01050	CompactFlash card and device not compatible
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF2 (NONE, OFF1, OFF3) VECTOR: OFF2 (NONE, OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The CompactFlash card and the device type do not match (e.g. a CompactFlash card for SINAMICS S is inserted in SINAMICS G).
Remedy:	- insert the matching CompactFlash card - use the matching Control Unit or power unit.
F01051	Drive object type is not available
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The drive object type in conjunction with the selected application-specific perspective is not available. The required descriptive file (PDxxxxyy.ACX) does not exist on the CompactFlash card. Fault value (r0949, decimal): Index of p0103 and p0107. See also: p0103 (Application-specific view), r0103 (Application-specific view), p0107 (Drive object type), r0107 (Drive object type)
Remedy:	- for this drive object type (p0107), select a valid application-specific perspective (p0103). - save the required descriptive file (PDxxxxyy.ACX) on the CompactFlash card. See also: p0103 (Application-specific view), r0103 (Application-specific view), p0107 (Drive object type), r0107 (Drive object type)
A01052	CU: System overload calculated for the complete target topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	A system overload was calculated based on a complete active target topology. Alarm value (r2124, decimal): 2: Computation time load too high. 6: Cyclic computation time load too high.
Remedy:	- reduce the sampling time. - only use one data set (CDS, DDS). - de-activate the function module. - de-activate the drive object. - remove the drive object from the target topology. Note: After executing the appropriate counter-measure, a new calculation must be initiated with p9974 = 1.
A01053	CU: System overload measured
Reaction:	NONE
Acknowledge:	NONE
Cause:	A system overload was determined based on measured values. Alarm value (r2124, decimal): 2: Computation time load too high. 6: Cyclic computation time load too high. See also: r9976 (System load)

Remedy:

- reduce the sampling time.
- only use one data set (CDS, DDS).
- de-activate the function module.
- de-activate the drive object.
- remove the drive object from the target topology.

A01054 Parameter save necessary

Reaction: NONE
Acknowledge: NONE
Cause:
Remedy:

A01064 Parameter save necessary

Reaction: NONE
Acknowledge: NONE
Cause:
Remedy:

A01065 Drive: Error, inactive encoder

Reaction: NONE
Acknowledge: NONE
Cause: On or several inactive encoders indicate an error.
Remedy: Remove the error for the inactive encoder.

A01099 Tolerance window of the timer synchronization exited

Reaction: NONE
Acknowledge: NONE
Cause: The clock (time) master exited the selected tolerance window for clock synchronization.
See also: p3109 (RTC real time synchronization, tolerance window)
Remedy: Select the re-synchronization interval so that the synchronization deviation between the clock master and drive system lies within the tolerance window.
See also: r3108 (RTC last synchronization deviation)

A01100 CU: CompactFlash card withdrawn

Reaction: NONE
Acknowledge: NONE
Cause: The CompactFlash card (non-volatile memory) was withdrawn in operation.
Notice:
It is not permissible that the CompactFlash card is withdrawn or inserted under voltage.
Remedy:

- power-down the drive system.
- re-insert the CompactFlash card that was withdrawn - this card must match the drive system.
- power-up the drive system again.

F01105 (A) CU: Insufficient memory

Reaction: OFF1
Acknowledge: IMMEDIATELY (POWER ON)
Cause: Two many functions, data sets or drives configured on this Control Unit.
Fault value (r0949, decimal):
Only for internal Siemens troubleshooting.
Remedy:

- change the configuration on this Control Unit.
- use an additional Control Unit.

Reaction upon A: NONE
Acknowledge upon A: NONE

F01107	CU: Save to CompactFlash card unsuccessful
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A data save on the CompactFlash card was not able to be successfully carried-out. - CompactFlash card is defective. - CompactFlash card does not have sufficient memory space. Fault value (r0949, decimal): -1: The file on the RAM was not able to be opened. -2: The file on the RAM was not able to be read. -3: A new directory was not able to be set-up on the CompactFlash card. -4: A new file was not able to be set-up on the CompactFlash card. -5: A new file was not able to be written onto the CompactFlash card.
Remedy:	- try to save again. - use another CompactFlash card.
F01110	CU: More than one SINAMICS G on one Control Unit
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	More than one SINAMICS G power unit type is being operated from the Control Unit. Fault value (r0949, decimal): Number of the second drive with a SINAMICS G power unit type.
Remedy:	Only one SINAMICS G drive type is permitted.
F01111	CU: SINAMICS S and G together on one Control Unit
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	SINAMICS S and G drive units are being operated together on one Control Unit. Fault value (r0949, decimal): Number of the first drive object with a different power unit type.
Remedy:	Only power units of one particular drive type may be operated with one CU.
F01112	CU: Power unit not permissible
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The connected power unit cannot be used together with this Control Unit. Fault value (r0949, decimal): 1: Power unit is not supported (e.g. PM240). 2: DC/AC power unit connected to CU310 not permissible.
Remedy:	Replace the power unit that is not permissible by a component that is permissible.
F01120 (A)	Terminal initialization has failed
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	An internal software error has occurred when initializing the terminal functions on the CU3xx, the TB30 or the TM31. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	- carry-out a POWER ON (power off/on) for all components. - upgrade the firmware release. - contact the Hotline. - replace the Control Unit.
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F01122 (A)	Frequency at the measuring probe input too high
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY
Cause:	The frequency of the pulses at the measuring probe input is too high. Fault value (r0949, decimal): 1: DI/DO 9 (X122.8) 2: DI/DO 10 (X122.10) 4: DI/DO 11 (X122.11) 8: DI/DO 13 (X132.8) 16: DI/DO 14 (X132.10) 32: DI/DO 15 (X132.11) 1001: DI/DO 9 (X122.8) initialization error 1002: DI/DO 10 (X122.10) initialization error 1004: DI/DO 11 (X122.11) initialization error 1008: DI/DO 13 (X132.8) initialization error 1016: DI/DO 14 (X132.10) initialization error 1032: DI/DO 15 (X132.11) initialization error
Remedy:	Reduce the frequency of the pulses at the measuring probe input.
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F01150	CU: Number of instances of a drive object type exceeded
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The maximum permissible number of instances of a drive object type was exceeded. Fault value (r0949, decimal): Byte 1: Drive object type (p0107). Byte 2: Max. permissible number of instances for this drive object type. Byte 3: Actual number of instances for this drive object type.
Remedy:	- power-down the unit. - suitably restrict the number of instances of a drive object type by reducing the number of inserted components. - re-commission the unit.

F01205	CU: Time slice overflow
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	Insufficient processing time is available for the existing topology. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	- reduce the number of drives. - increase the sampling times.

F01210	CU: Basic clock cycle selection and DRIVE-CLiQ clock cycles do not match
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The parameter to select the basic clock cycle does not match the drive topology. Drives connected to the same DRIVE-CLiQ port of the Control Unit have been assigned different basic clock cycles. Fault value (r0949, decimal): The fault value specifies the parameter involved. See also: r0111 (DRIVE-CLiQ basis sampling time selection)
Remedy:	Only those drive objects may be connected to the same DRIVE-CLiQ socket of the Control Unit that should run with the same basic clock cycle. For example, Active Line Modules and Motor Modules should be inserted at different DRIVE-CLiQ ports as their basic clock cycles and current controller clock cycles are generally different. See also: r0111 (DRIVE-CLiQ basis sampling time selection)

F01220	CU: Bas clk cyc too low
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The parameter for the basic clock cycle is set too short for the number of connected drives. Fault value (r0949, decimal): The fault value specifies the parameter involved. See also: r0110 (DRIVE-CLiQ basis sampling times)
Remedy:	- increase the basic clock cycle. - reduce the number of connected drives and start to re-commission the unit. See also: r0110 (DRIVE-CLiQ basis sampling times)
F01221	CU: Bas clk cyc too low
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The closed-loop control / monitoring cannot maintain the intended clock cycle. The runtime of the closed-loop control/monitoring is too longer for the particular clock cycle or the computation time remaining in the system is not sufficient for the closed-loop control/monitoring. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	Increase the basic clock cycle of DRIVE-CLiQ communications. See also: p0112 (Sampling times pre-setting p0115)
A01223	CU: Sampling time inconsistent
Reaction:	NONE
Acknowledge:	NONE
Cause:	When changing a sampling time (p0115[0], p0799 or p4099), inconsistency between the clock cycles has been identified. Alarm value (r2124, decimal): 1: Value, low minimal value. 2: Value, high maximum value. 3: Value not a multiple of 1.25 µs. 4: Value does not match clock cycle synchronous PROFIBUS operation. 5: Value not a multiple of 125 µs. 6: Value not a multiple of 250 µs. 7: Value not a multiple of 375 µs. 8: Value not a multiple of 400 µs. 10: Special restriction of the drive object violated. 20: For a SERVO with a 62.5 µs sampling time, more than a maximum of two SERVO-type drive objects were detected on the DRIVE-CLiQ line. 21: Value is not a multiple of the current controller sampling time of a servo or vector drive that is in the system. 30: Value less than 31.25 µs. 31: Value less than 62.5 µs. 32: Value less than 125 µs. 40: Nodes (devices) have been identified on the DRIVE-CLiQ line whose highest common denominator of the sampling times is less than 125 µs. Further, none of the nodes (devices) has a sampling time of less than 125 µs. 41: A chassis unit was identified on the DRIVE-CLiQ line. Further, the highest common denominator of the sampling times of the all of the nodes (devices) connected to the line is less than 250 µs. 42: An Active Line Module was identified on the DRIVE-CLiQ line as device. Further, the highest common denominator of the sampling times of the all of the nodes (devices) connected to the line is less than 125 µs. 43: A Voltage Sensing Module (VSM) was identified on the DRIVE-CLiQ line as device. Further, the highest common denominator of the sampling times of the all of the nodes (devices) connected to the line is not equal to the current controller sampling time of the drive object of the VSM. 52: Nodes (devices) have been identified on the DRIVE-CLiQ line whose highest common denominator of the sampling times is less than 31.25 µs. 54: Nodes (devices) have been identified on the DRIVE-CLiQ line whose highest common denominator of the sampling times is less than 62.5 µs.

56: Nodes (devices) have been identified on the DRIVE-CLiQ line whose highest common denominator of the sampling times is less than 125 µs.
 58: Nodes (devices) have been identified on the DRIVE-CLiQ line whose highest common denominator of the sampling times is less than 250 µs.
 99: Inconsistency identified cross drive objects.
 116: Recommended clock cycle in r0116[0...1].

Remedy:
 - check the DRIVE-CLiQ cables.
 - set a valid sampling time.
 See also: p0115 (Sampling time for supplementary functions), p0799 (CU inputs/outputs, sampling time), p4099 (TB30 inputs/outputs, sampling time)

A01224 CU: Pulse frequency inconsistent

Reaction: NONE

Acknowledge: NONE

Cause: When changing the minimum pulse frequency (p0113) inconsistency between the pulse frequencies was identified.
 Alarm value (r2124, decimal):
 1: Value, low minimal value.
 2: Value, high maximum value.
 3: Resulting sampling time is not a multiple of 1.25 µs.
 4: Value does not match clock cycle synchronous PROFIBUS operation.
 10: Special restriction of the drive object violated.
 99: Inconsistency identified cross drive objects.
 116: Recommended clock cycle in r0116[0...1].

Remedy: Set a valid pulse frequency.
 See also: p0113 (Pulse frequency, minimum selection)

F01250 CU: CU-EEPROM incorrect read-only data

Reaction: NONE (OFF2)

Acknowledge: POWER ON

Cause: Error when reading the read-only data of the EEPROM in the Control Unit.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy:
 - carry-out a POWER ON.
 - replace the Control Unit

A01251 CU: CU-EEPROM incorrect read-write data

Reaction: NONE

Acknowledge: NONE

Cause: Error when reading the read-write data of the EEPROM in the Control Unit.
 Alarm value (r2124, decimal):
 Only for internal Siemens troubleshooting.

Remedy: For alarm value r2124 < 256, the following applies:
 - carry-out a POWER ON.
 - replace the Control Unit.
 For alarm value r2124 >= 256, the following applies:
 - for the drive object with this alarm, clear the fault memory (p0952 = 0).
 - as an alternative, clear the fault memory of all drive objects (p2147 = 1).
 - replace the Control Unit.

F01255 CU: Opt.module EEPROM incorrect read-only data

Reaction: NONE (OFF2)

Acknowledge: POWER ON

Cause: Error when reading the read-only data of the EEPROM in the option module.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy:
 - carry-out a POWER ON.
 - replace the Control Unit.

A01256	CU: Opt.module EEPROM incorrect read-write data
Reaction:	NONE
Acknowledge:	NONE
Cause:	Error when reading the read-write data of the EEPROM in the option module. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.
Remedy:	- carry-out a POWER ON. - replace the Control Unit.
F01303	DRIVE-CLiQ component does not support the required function
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A function requested by the Control Unit is not supported by a DRIVE-CLiQ component. Fault value (r0949, decimal): 1: The component does not support the de-activation. 101: The Motor Module does not support an internal armature short-circuit. 102: The Motor Module does not support the de-activation. 201: The Encoder Module does not support actual value inversion (p0410.0 = 1) when using a Hall sensor (p0404.6 = 1) for the commutation. 202: The Encoder Module does not support parking/unparking. 203: The Encoder Module does not support the de-activation. 204: The firmware of this Terminal Module 15 (TM15) does not support the application TM15DI/DO. 205: The encoder module does not support the selected temperature evaluation (refer to r0458). 206: The firmware of this Terminal Module 41 refers to an old firmware version. In order to ensure error-free operation is absolutely necessary that the firmware is upgraded.
Remedy:	Upgrade the firmware of the DRIVE-CLiQ component involved. Re 205: Adapts parameter p0600 or p0601.
F01305	Topology: Component number missing
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The component number from the topology was not parameterized (p0121 (for power unit, refer to p0107), p0131 (for servo/vector drives, refer to p0107), p0141, p0151, p0161). Fault value (r0949, decimal): The fault value includes the particular data set number. The fault also occurs if speed encoders were configured (p0187 ... p0189), however, no component numbers exist for them. In this case, the fault value includes the drive data set number plus 100 * encoder number (e.g. 3xx, if a component number was not entered into p0141 for the third encoder (p0189)). See also: p0121 (Power unit component number), p0131 (Motor component number), p0141 (Encoder interface (Sensor Module) component number), p0142 (Encoder component number), p0151 (Voltage Sensing Module component number), p0161 (Option board, component number), p0186 (Motor Data Sets (MDS) number), p0187 (Encoder 1 encoder data set number), p0188 (Encoder 2 encoder data set number), p0189 (Encoder 3 encoder data set number)
Remedy:	Enter the missing component number or remove the component and restart commissioning. See also: p0121 (Power unit component number), p0131 (Motor component number), p0141 (Encoder interface (Sensor Module) component number), p0142 (Encoder component number), p0151 (Voltage Sensing Module component number), p0161 (Option board, component number), p0186 (Motor Data Sets (MDS) number), p0187 (Encoder 1 encoder data set number), p0188 (Encoder 2 encoder data set number), p0189 (Encoder 3 encoder data set number)

A01315	Drive object not ready for operation
Reaction:	NONE
Acknowledge:	NONE
Cause:	For the active drive object involved, at least one activated component is missing. Note: All other active and operational drive objects can be in the "RUN" state.
Remedy:	The alarm automatically disappears again with the following actions: - de-activate the drive object involved (p0105 = 0). - de-activate the components involved (p0125 = 0, p0145 = 0, p0155 = 0, p0165 = 0). - re-insert the components involved. See also: p0105 (Activate/de-activate drive object), p0125 (Activate/de-activate power unit components), p0145 (Voltage Sensing Module, activate/de-activate), p0155 (Voltage Sensing Module, activate/de-activate)

A01316	Drive object inactive and again ready for operation
Reaction:	NONE
Acknowledge:	NONE
Cause:	If, when inserting a component of the target topology, an inactive, non-operational drive object becomes operational again. The associated parameter of the component is, in this case, set to "activate" (p0125, p0145, p0155, p0165). Note: This is the only message, that is displayed for a de-activated drive object.
Remedy:	The alarm automatically disappears again with the following actions: - activate the drive object involved (p0105 = 1). - again withdraw the components involved. See also: p0105 (Activate/de-activate drive object)

A01317	De-activated component again present
Reaction:	NONE
Acknowledge:	NONE
Cause:	If a component of the target topology for an active drive object is inserted and the associated parameter of the component is set to "de-activate" (p0125, p0145, p0155, p0165). Note: This is the only message, that is displayed for a de-activated component.
Remedy:	The alarm automatically disappears again with the following actions: - activate the components involved (p0125 = 1, p0145 = 1, p0155 = 1, p0165 = 1). - again withdraw the components involved. See also: p0125 (Activate/de-activate power unit components), p0145 (Voltage Sensing Module, activate/de-activate), p0155 (Voltage Sensing Module, activate/de-activate)

A01318	BICO: De-activated interconnections present
Reaction:	NONE
Acknowledge:	NONE
Cause:	This alarm is output: If an inactive/non-operational drive object is again active/ready for operation and r9498[] or r9499[] are not empty and the connections listed in r9498[] and r9499 have actually been changed
Remedy:	Clear alarm: Set p9496 to 1 or 2 or de-activate DO

A01319	Inserted component not initialized
Reaction:	NONE
Acknowledge:	NONE
Cause:	The inserted component has still not been initiated, as the pulses are enabled.
Remedy:	Pulse inhibit

A01320 Topology: Drive object number does not exist in configuration

Reaction: NONE
Acknowledge: NONE
Cause: A drive object number is missing in p0978
 Alarm value (r2124, decimal):
 Index of p0101 under which the missing drive object number can be determined.
Remedy: Set p0009 to 1 and change p0978:
 Rules:
 - p0978 must include all of the drive object numbers (p0101).
 - it is not permissible that a drive object number is repeated.
 - by entering a 0, the drive objects with PZD are separated from those without PZD.
 - only 2 partial lists are permitted. After the second 0, all values must be 0.
 - dummy drive object numbers (255) are only permitted in the first partial list.

A01321 Topology: Drive object number does not exist in configuration

Reaction: NONE
Acknowledge: NONE
Cause: p0978 contains a drive object number that does not exist.
 Alarm value (r2124, decimal):
 Index of p0978 under which the drive object number can be determined.
Remedy: Set p0009 to 1 and change p0978:
 Rules:
 - p0978 must include all of the drive object numbers (p0101).
 - it is not permissible that a drive object number is repeated.
 - by entering a 0, the drive objects with PZD are separated from those without PZD.
 - only 2 partial lists are permitted. After the second 0, all values must be 0.
 - dummy drive object numbers (255) are only permitted in the first partial list.

A01322 Topology: Drive object number present twice in configuration

Reaction: NONE
Acknowledge: NONE
Cause: A drive object number is present more than once in p0978.
 Alarm value (r2124, decimal):
 Index of p0978 under which the involved drive object number is located.
Remedy: Set p0009 to 1 and change p0978:
 Rules:
 - p0978 must include all of the drive object numbers (p0101).
 - it is not permissible that a drive object number is repeated.
 - by entering a 0, the drive objects with PZD are separated from those without PZD.
 - only 2 partial lists are permitted. After the second 0, all values must be 0.
 - dummy drive object numbers (255) are only permitted in the first partial list.

A01323 Topology: More than two part lists set-up

Reaction: NONE
Acknowledge: NONE
Cause: Partial lists are available more than twice in p0978. After the second 0, all must be 0.
 Alarm value (r2124, decimal):
 Index of p0978, under which the illegal value is located.
Remedy: Set p0009 to 1 and change p0978:
 Rules:
 - p0978 must include all of the drive object numbers (p0101).
 - it is not permissible that a drive object number is repeated.
 - by entering a 0, the drive objects with PZD are separated from those without PZD.
 - only 2 partial lists are permitted. After the second 0, all values must be 0.
 - dummy drive object numbers (255) are only permitted in the first partial list.

A01324	Topology: Dummy drive object number incorrectly set-up
Reaction:	NONE
Acknowledge:	NONE
Cause:	In p0978, dummy drive object numbers (255) are only permitted in the first partial list. Alarm value (r2124, decimal): Index of p0978, under which the illegal value is located.
Remedy:	Set p0009 to 1 and change p0978: Rules: - p0978 must include all of the drive object numbers (p0101). - it is not permissible that a drive object number is repeated. - by entering a 0, the drive objects with PZD are separated from those without PZD. - only 2 partial lists are permitted. After the second 0, all values must be 0. - dummy drive object numbers (255) are only permitted in the first partial list.

A01330	Topology: Quick commissioning not possible
Reaction:	NONE
Acknowledge:	NONE
Cause:	Unable to carry-out a quick commissioning. The existing actual topology does not fulfill the requirements. Alarm value (r2124, interpret hexadecimal): The cause is in byte 1 supplementary information is included in byte 2 and the high word. Byte 1 = 1: For a component, illegal connections were detected. - Byte 2 = 1: For a Motor Module, more than one motor with DRIVE-CLiQ was detected. - Byte 2 = 2: For a motor with DRIVE-CLiQ, the DRIVE-CLiQ cable is not connected to a Motor Module. - high word = preliminary component number of the component with illegal connection. Byte 1 = 2: The topology contains too many components of a particular type. - Byte 2 = 1: There is more than one Master Control Unit. - Byte 2 = 2: There is more than 1 infeed (8 for a parallel circuit configuration). - Byte 2 = 3: There are more than 10 Motor Modules (8 for a parallel circuit configuration). - Byte 2 = 4: There are more than 9 encoders. - Byte 2 = 5: There are more than 8 Terminal Modules. - Byte 2 = 7: Unknown component type. - Byte 2 = 8: There are more than 6 drive slaves. - Byte 2 = 9: Connection of a drive slave not permitted. - Byte 2 = 10: There is no Drive Master. - Byte 2 = 11: There is more than one motor with DRIVE-CLiQ for a parallel circuit. - high word = not used. Byte 1 = 3: More than 16 components are connected at a DRIVE-CLiQ socket of the Control Unit. - byte 2 = 0, 1, 2, 3 means e.g. detected at the DRIVE-CLiQ socket X100, X101, X102, X103. - high word = not used. Byte 1 = 4: The number of components connected one after the other is greater than 125. - byte 2 = not used. - high word = preliminary component number of the first component and component that resulted in the fault. Byte 1 = 5: The component is not permissible for SERVO. - Byte 2 = 1: SINAMICS G is being used. - Byte 2 = 2: Chassis is being used. - high word = preliminary component number of the first component and component that resulted in the fault. Byte 1 = 6: For a component, illegal EEPROM data was detected. These must be corrected before the system continues to boot. - Byte 2 = 1: The Order No. [MLFB] of the power unit that was replaced includes a space retainer. The space retainer (*) must be replaced by a correct character. - high word = preliminary component number of the component with illegal EEPROM data. Byte 1 = 7:

The actual topology contains an illegal combination of components.
 - Byte 2 = 1: Active Line Module (ALM) and Basic Line Module (BLM).
 - Byte 2 = 2: Active Line Module (ALM) and Smart Line Module (SLM).
 - Byte 2 = 3: SIMOTION control (e.g. SIMOTION D445) and SINUMERIK component (e.g. NX15).
 - Byte 2 = 4: SINUMERIK control (e.g. SINUMERIK 730.net) and SIMOTION component (e.g. CX32).
 - high word = not used.

Note:

Connection type and connection number are described in F01375.

See also: p0097 (Select drive object type), r0098 (Actual device topology), p0099 (Device target topology)

Remedy:

- adapt the output topology to the permissible requirements.
 - carry-out commissioning using the commissioning software.
 - for motors with DRIVE-CLiQ, connect the power and DRIVE-CLiQ cable to the same Motor Module (Single Motor Module: DRIVE-CLiQ at X202, Double Motor Module: DRIVE-CLiQ from motor 1 (X1) to X202, from motor 2 (X2) to X203).

Re byte 1 = 6 and byte 2 = 1:

Correct the order number when commissioning using the commissioning software.

See also: p0097 (Select drive object type), r0098 (Actual device topology), p0099 (Device target topology)

A01331

Topology: At least one component not assigned to a drive object

Reaction:

NONE

Acknowledge:

NONE

Cause:

At least one component is not assigned to a drive object.
 - when commissioning, a component was not able to be automatically assigned to a drive object.
 - the parameters for the data sets are not correctly set.

Alarm value (r2124, decimal):

Component number of the unassigned component.

Remedy:

This component is assigned to a drive object.

Check the parameters for the data sets.

Examples:

- power unit (p0121).
- motor (p0131, p0186).
- encoder interface (p0140, p0141, p0187 ... p0189).
- encoder (p0140, p0142, p0187 ... p0189).
- Terminal Module (p0151).
- option board (p0161).

F01340

Topology: Too many components on one line

Reaction:

NONE

Acknowledge:

IMMEDIATELY

Cause:

For the selected communications clock cycle, too many DRIVE-CLiQ components are connected to one line of the Control Unit.

Fault value (r0949, interpret hexadecimal):

xyy hex: x = fault cause, yy = component number or connection number.

1yy: The communications clock cycle of the DRIVE-CLiQ connection on the CU is not sufficient for all read transfers.

2yy: The communications clock cycle of the DRIVE-CLiQ connection on the CU is not sufficient for all write transfers.

3yy: Cyclic communications is fully utilized.

4yy:

The DRIVE-CLiQ cycle starts before the earliest end of the application. An additional deadtime must be added to the control. Sign-of-life errors can be expected.

5yy: Internal buffer overflow for net data of a DRIVE-CLiQ connection.

6yy: Internal buffer overflow for receive data of a DRIVE-CLiQ connection.

7yy: Internal buffer overflow for send data of a DRIVE-CLiQ connection.

Remedy:

Check the DRIVE-CLiQ connection:

Reduce the number of components on the DRIVE-CLiQ line involved and distribute these to other DRIVE-CLiQ connections of the Control Unit. This means that communication is uniformly distributed over several communication lines.

Re fault value = 1yy - 4yy in addition:

- increase the sampling times (p0112, p0115).

F01355	Topology: Actual topology changed
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The unit target topology p0099 does not correspond to the unit actual topology r0098. The fault only occurs if the topology was commissioned using the automatic internal device mechanism and not using the commissioning software. Fault value (r0949, decimal): Only for internal Siemens troubleshooting. See also: r0098 (Actual device topology), p0099 (Device target topology)
Remedy:	One of the following counter-measures can be selected if no faults have occurred in the topology detection itself. If commissioning was still not completed: - carry-out a self-commissioning routine (starting from p0009 = 1). General: Set p0099 to r0098, set p0009 to 0; for existing Motor Modules, this results in servo drives being automatically generated (refer to p0107). or, to generate servo drives: Set p0097 to 1, set p0009 to 0; or, to generate vector drives: Set p0097 to 2, set p0009 to 0. or, to generate vector drives with parallel circuit: Set p0097 to 12, set p0009 to 0. In order to set configurations in p0108, before setting p0009 to 0, it is possible to first set p0009 to 2 and p0108 modified (the index corresponds to the drive object, also refer to p0107). If commissioning was already completed: - re-establish the original connections and re-connect power to the Control Unit. - restore the factory setting for the complete equipment (all of the drives) and allow automatic self-commissioning again. - change the device parameterization to match the connections (this is only possible using the commissioning software). Notice: Topology changes, that result in this fault being generated, cannot be accepted by the automatic function in the device, but must be transferred using the commissioning software and parameter download. The automatic function in the device only allows constant topology to be used. Otherwise, when the topology is changed, all of the previous parameter settings are lost and replaced by the factory setting. See also: r0098 (Actual device topology)
F01360	Topology: Actual topology is illegal
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The detected actual topology is not permissible. Fault value (r0949, interpret hexadecimal): Byte 1 (cause): 1: Too many components were detected at the Control Unit. The maximum permissible number of components is 199. 2: The component type of a component is not known. The preliminary component number is in the high word. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	Re fault value = 1: Change the configuration. Connect less than 199 components to the Control Unit. Re fault value = 2: Remove the component with unknown component type.
A01361	Topology: Actual topology contains SINUMERIK and SIMOTION components
Reaction:	NONE
Acknowledge:	NONE
Cause:	The detected actual topology contains SINUMERIK and SIMOTION components. Fault value (r0949, interpret hexadecimal): Byte 1: Component number of the component. Byte 2: Component class of the actual topology. Byte 3 (cause): 1: An NX10 or NX15 was connected to a SIMOTION control. 2: A CX32 was connected to a SINUMERIK control. The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	Re fault value = 1: Replace all NX10 or NX15 by a CX32. Re fault value = 2: Replace all CX32 by an NX10 or NX15.

F01375	Topology: Actual topology, duplicate connection between two components
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>When detecting the actual topology, a ring-type connection was detected. Fault value (r0949, interpret hexadecimal): Low word: Preliminary component number of a component included in the ring Byte 3: Component class Byte 4: Connection number Example: Fault value = 33751339 dec = 203012B hex Byte 4 = 02 hex = 2 dec, byte 3 = 03 hex = 3 dec, low word = 012B hex = 299 dec Component class: 1: Control unit 2: Motor Module 3: Line Module 4: Sensor Module (SM) 5: Voltage Sensing Module (VSM) 6: Terminal Module (TM) 7: DRIVE-CLiQ Module Cabinet (DMC) 8: Controller Extension 32 (CX32) 49: DRIVE-CLiQ components (non-listed components) 50: Option slot (e.g. Terminal Board 30) 60: Encoder (e.g. EnDat) 70: Motor with DRIVE-CLiQ Component type: Precise designation within a component class (e.g. "SMC20"). Connection number: Consecutive numbers, starting from zero, of the appropriate connection or slot (e.g. DRIVE-CLiQ connection X100 on the Control Unit has the connection number 0).</p>
Remedy:	<p>Output the fault value and remove the specified connection. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p>
F01380	Topology: Actual topology, defective EEPROM
Reaction:	NONE
Acknowledge:	POWER ON
Cause:	<p>When detecting the actual topology, a component with a defective EEPROM was detected. Fault value (r0949, interpret hexadecimal): Low word: Preliminary component number of the defective components.</p>
Remedy:	Output the fault value and remove the defected component.
A01381	Topology: Comparison, power unit shifted
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The topology comparison has detected a power unit in the actual topology that has been shifted with respect to the target topology. Alarm value (r2124, interpret hexadecimal): Byte 1: Component number of the component shifted in the target topology. The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4. Byte 2: Component class Byte 3: Component number Byte 4: Connection number Note: Component class and connection number are described in F01375. The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>

Remedy: Adapting the topologies:
 - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
 - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
 - automatically remove the topology error (p9904).
Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01382 Topology: Comparison, Sensor Module shifted

Reaction: NONE
Acknowledge: NONE
Cause: The topology comparison has detected a Sensor Module in the actual topology that has been shifted with respect to the target topology.
 Alarm value (r2124, interpret hexadecimal):
 Byte 1: Component number of the component shifted in the target topology
 The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.
 Byte 2: Component class
 Byte 3: Component number
 Byte 4: Connection number
Note:
 Component class and connection number are described in F01375.
 The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Adapting the topologies:
 - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
 - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
 - automatically remove the topology error (p9904).
Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01383 Topology: Comparison, Terminal Module shifted

Reaction: NONE
Acknowledge: NONE
Cause: The topology comparison has detected a Terminal Module in the actual topology that has been shifted with respect to the target topology.
 Alarm value (r2124, interpret hexadecimal):
 Byte 1: Component number of the component shifted in the target topology
 The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.
 Byte 2: Component class
 Byte 3: Component number
 Byte 4: Connection number
Note:
 Component class and connection number are described in F01375.
 The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Adapting the topologies:
 - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
 - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
 - automatically remove the topology error (p9904).
Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01384	Topology: Comparison, DMC shifted
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The topology comparison has detected a DRIVE-CLiQ Hub Module Cabinet (DMC) in the actual topology that has been shifted with respect to the target topology.</p> <p>Alarm value (r2124, interpret hexadecimal):</p> <p>Byte 1: Component number of the component shifted in the target topology</p> <p>The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.</p> <p>Byte 2: Component class</p> <p>Byte 3: Component number</p> <p>Byte 4: Connection number</p> <p>Note:</p> <p>Component class and connection number are described in F01375.</p> <p>The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>
Remedy:	<p>Adapting the topologies:</p> <ul style="list-style-type: none"> - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables. - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project. - automatically remove the topology error (p9904). <p>Note:</p> <p>Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p>
A01385	Topology: Comparison, CX32 shifted
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The topology comparison has detected a controller extension 32 (CX32) in the actual topology that has been shifted with respect to the target topology.</p> <p>Alarm value (r2124, interpret hexadecimal):</p> <p>Byte 1: Component number of the component shifted in the target topology</p> <p>The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.</p> <p>Byte 2: Component class</p> <p>Byte 3: Component number</p> <p>Byte 4: Connection number</p> <p>Note:</p> <p>Component class and connection number are described in F01375.</p> <p>The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>
Remedy:	<p>Adapting the topologies:</p> <ul style="list-style-type: none"> - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables. - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project. - automatically remove the topology error (p9904). <p>Note:</p> <p>Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p>
A01386	Topology: Comparison, DRIVE-CLiQ component shifted
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The topology comparison has detected a DRIVE-CLiQ component in the actual topology that has been shifted with respect to the target topology.</p> <p>Alarm value (r2124, interpret hexadecimal):</p> <p>Byte 1: Component number of the component shifted in the target topology</p> <p>The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.</p> <p>Byte 2: Component class</p> <p>Byte 3: Component number</p> <p>Byte 4: Connection number</p> <p>Note:</p> <p>Component class and connection number are described in F01375.</p> <p>The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>

Remedy: Adapting the topologies:
 - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
 - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
 - automatically remove the topology error (p9904).
Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01387 Topology: Comparison, option slot component shifted

Reaction: NONE

Acknowledge: NONE

Cause: The topology comparison has detected a option slot component in the actual topology that has been shifted with respect to the target topology.
 Alarm value (r2124, interpret hexadecimal):
 Byte 1: Component number of the component shifted in the target topology
 The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.
 Byte 2: Component class
 Byte 3: Component number
 Byte 4: Connection number
Note:
 Component class and connection number are described in F01375.
 The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Adapting the topologies:
 - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
 - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
 - automatically remove the topology error (p9904).
Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01388 Topology: Comparison, EnDat encoder shifted

Reaction: NONE

Acknowledge: NONE

Cause: The topology comparison has detected an EnDat encoder in the actual topology that has been shifted with respect to the target topology.
 Alarm value (r2124, interpret hexadecimal):
 Byte 1: Component number of the component shifted in the target topology
 The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.
 Byte 2: Component class
 Byte 3: Component number
 Byte 4: Connection number
Note:
 Component class and connection number are described in F01375.
 The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Adapting the topologies:
 - undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
 - commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
 - automatically remove the topology error (p9904).
Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01389 **Topology: Comparison, motor with DRIVE-CLiQ shifted**

Reaction: NONE

Acknowledge: NONE

Cause: The topology comparison has detected a motor with DRIVE-CLiQ in the actual topology that has been shifted with respect to the target topology.
Alarm value (r2124, interpret hexadecimal):
Byte 1: Component number of the component shifted in the target topology
The connection in the actual topology where the shifted component was detected, is described in bytes 2, 3 and 4.
Byte 2: Component class
Byte 3: Component number
Byte 4: Connection number
Note:
Component class and connection number are described in F01375.
The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Adapting the topologies:
- undo the change to the actual topology by changing-over the DRIVE-CLiQ cables.
- commissioning software: Go online, upload the drive unit, adapt the topology offline and download the modified project.
- automatically remove the topology error (p9904).
Note:
Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01416 **Topology: Comparison, additional component in actual topology**

Reaction: NONE

Acknowledge: NONE

Cause: The topology comparison has found a component in the actual topology which is not specified in the target topology. The alarm value includes the component number and connection number of the component with which the additional component is connected.
Alarm value (r2124, interpret hexadecimal):
Byte 1: Component number
Byte 2: Component class of the additional component
Byte 3: Connection number
Note:
Component class and connection number are described in F01375.

Remedy: Adapting the topologies:
- remove the additional component in the actual topology.
- download the target topology that matches the actual topology (commissioning software).
Note:
Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01420 **Topology: Comparison, a component is different**

Reaction: NONE

Acknowledge: NONE

Cause: The topology comparison has detected differences in the actual and target topologies in relation to one component. There are differences in the electronic rating plate.
 Alarm value (r2124, interpret hexadecimal):
 Byte 1: Component number of the component
 Byte 2: Component class of the target topology
 Byte 3: Component class of the actual topology
 Byte 4 (cause):
 1: Different component type
 2: Different order number
 3: Different manufacturer
 4: Connection changed-over for a multi-component slave (e.g. double Motor Module) or defective EEPROM data in the electronic rating plate
 5: A CX32 was replaced by an NX10 or NX15.
 6: An NX10 or NX15 was replaced by a CX32.
 Note:
 Component class and component type are described in F01375.
 The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Adapting the topologies:
 - check the component soft-wired connections against the hardware configuration of the drive unit in the commissioning software and correct differences.
 - parameterize the topology comparison of all components (p9906).
 - parameterize the topology comparison of one components (p9907, p9908).
 Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01421 **Topology: Comparison, different components**

Reaction: NONE

Acknowledge: NONE

Cause: The topology comparison has detected differences in the actual and target topologies in relation to one component. The component class, the component type or the number of connections differ.
 Alarm value (r2124, interpret hexadecimal):
 Byte 1: Component number of the component
 Byte 2: Component class of the target topology
 Byte 3: Component class of the actual topology
 Byte 4 (cause):
 1: Different component class
 2: Different component type
 3: Different order number
 4: Different number of connections
 Note:
 Component class, component type and connection number are described in F01375.
 The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.

Remedy: Check the component soft-wired connections against the hardware configuration of the drive unit in the commissioning software and correct differences.
 Note:
 Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01425	Topology: Comparison, serial number of a component is different
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The topology comparison has detected differences in the actual and target topologies in relation to one component. The serial number is different.</p> <p>Alarm value (r2124, interpret hexadecimal):</p> <p>Byte 1: Component number of the component</p> <p>Byte 2: Component class</p> <p>Byte 3: Number of differences</p> <p>Note:</p> <p>The component class is described in F01375.</p> <p>The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>
Remedy:	<p>Adapting the topologies:</p> <ul style="list-style-type: none"> - change over the actual topology to match the target topology. - download the target topology that matches the actual topology (commissioning software). <p>Re byte 3:</p> <p>Byte 3 = 1 --> can be acknowledged using p9904 or p9905.</p> <p>Byte 3 > 1 --> can be acknowledged using p9905 and can be de-activated using p9906 or p9907/p9908.</p> <p>Note:</p> <p>Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p> <p>See also: p9904 (Topology comparison, acknowledge differences), p9905 (Device specialization), p9906 (Topology comparison, comparison stage of all components), p9907 (Topology comparison, comparison stage of the component number), p9908 (Topology comparison, comparison stage of a component)</p>
A01428	Topo: Comparison, connection of a component is different
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The topology comparison has detected differences in the actual and target topologies in relation to one component. A component was connected to another connection.</p> <p>The different connections of a component are described in the alarm value:</p> <p>Alarm value (r2124, interpret hexadecimal):</p> <p>Byte 1: Component number</p> <p>Byte 2: Component class</p> <p>Byte 3: Connection number of the actual topology</p> <p>Byte 4: Connection number of the target topology</p> <p>Note:</p> <p>Component class and connection number are described in F01375.</p> <p>The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>
Remedy:	<p>Adapting the topologies:</p> <ul style="list-style-type: none"> - change over the actual topology to match the target topology. - download the target topology that matches the actual topology (commissioning software). - automatically remove the topology error (p9904). <p>Note:</p> <p>Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p> <p>See also: p9904 (Topology comparison, acknowledge differences)</p>

A01429	Topology: Comparison, connection is different for more than component
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>A topology comparison has found differences between the actual and target topology for several components. A component was connected to another connection.</p> <p>The different connections of a component are described in the alarm value: Alarm value (r2124, interpret hexadecimal): Byte 1: Component number Byte 2: Component class Byte 3: Connection number of the actual topology Byte 4: Connection number of the target topology</p> <p>Note: Component class and connection number are described in F01375. The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.</p>
Remedy:	<p>Adapting the topologies:</p> <ul style="list-style-type: none"> - change over the actual topology to match the target topology. - download the target topology that matches the actual topology (commissioning software). <p>Note: In the software, a double Motor Module behaves just like two separate DRIVE-CLiQ nodes. If a double Motor Module is re-inserted, this can result in several differences in the actual topology.</p> <p>Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p>

F01451	Topology: Target topology is invalid
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>An error has occurred when writing into the target topology. The write operation was interrupted due to an invalid target topology. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.</p>
Remedy:	Reload the target topology using the commissioning software.

F01470	Topology: Target topology ring-type connection
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>A ring-type connection was detected when writing into the target topology. Fault value (r0949, interpret hexadecimal): Byte 1: Component number of a component included in the ring Byte 2: Component class Byte 3: Connection number</p> <p>Note: Component class and connection number are described in F01375.</p>
Remedy:	<p>Read-out the fault value and remove one of the specified connections. Then, download the target topology again using the commissioning software.</p> <p>Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).</p>

F01475	Topology: Target topology, duplicate connection between two components
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	When writing the target topology, a duplicate connection between two components was detected. Fault value (r0949, interpret hexadecimal): Byte 1: Component number of one of the components connected twice Byte 2: Component class Byte 3: Connection number 1 of the duplicate connection Byte 4: Connection number 2 of the duplicate connection Note: Component class and connection number are described in F01375.
Remedy:	Read-out the fault value and remove one of the two specified connections. Then, download the target topology again using the commissioning software. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).
A01481	Topology: Comparison, power unit missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a power unit in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- delete the drive belonging to the power unit in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).
A01482	Topology: Comparison, Sensor Module missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a Sensor Module in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- re-configure the drive belonging to the Sensor Module in the commissioning software project (encoder configuration) and download the new configuration into the drive unit. - delete the drive belonging to the Sensor Module in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01483	Topology: Comparison, Terminal Module missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a Terminal Module in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- delete the Terminal Module in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01484	Topology: Comparison, DMC missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a DRIVE-CLiQ Hub Module Cabinet (DMC) in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- delete the DRIVE-CLiQ Hub Module Cabinet (DMC) in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01485	Topology: Comparison, CX32 missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a controller extension 32 (CX32) in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- delete the CX32 in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01486	Topology: Comparison, DRIVE-CLiQ components missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a DRIVE-CLiQ component in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- delete the drive belonging to this component in the commissioning software project and download the new configuration into the drive unit. - re-configure the drive belonging to this component in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).
A01487	Topology: Comparison, option slot components missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected an option slot module in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- delete the option board in the commissioning software project and download the new configuration into the drive unit. - re-configure the drive unit in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).
A01488	Topology: Comparison, EnDat encoder missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected an EnDat encoder in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- re-configure the drive belonging to the encoder in the commissioning software project (encoder configuration) and download the new configuration into the drive unit. - delete the drive belonging to the encoder in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).

A01489	Topology: Comparison, motor with DRIVE-CLiQ missing in the actual topology
Reaction:	NONE
Acknowledge:	NONE
Cause:	The topology comparison has detected a motor with DRIVE-CLiQ in the target topology that is not available in the actual topology. Alarm value (r2124, decimal): Component number of the additional target components. Note: The drive system is no longer booted. In this state, the drive control (closed-loop) cannot be enabled.
Remedy:	- re-configure the drive belonging to this motor in the commissioning software project and download the new configuration into the drive unit. - delete the drive belonging to this motor in the commissioning software project and download the new configuration into the drive unit. - check that the actual topology matches the target topology and if required, change over. - check DRIVE-CLiQ cables for interruption and contact problems. Note: Under "Topology --> Topology view" the commissioning software offers improved diagnostics capability (e.g. set-point/actual value comparison).
F01505 (A)	BICO: Interconnection cannot be established
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A PROFIBUS telegram has been set (p0922). An interconnection contained in the telegram, was not able to be established. Fault value (r0949, decimal): Parameter receiver that should be changed.
Remedy:	Establish another interconnection.
Reaction upon A:	NONE
Acknowledge upon A:	NONE
F01506 (A)	BICO: No standard telegram
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The standard telegram in p0922 is not maintained and therefore p0922 is set to 999. Fault value (r0949, decimal): BICO parameter for which the write attempt was unsuccessful.
Remedy:	Again set the required standard telegram (p0922).
Reaction upon A:	NONE
Acknowledge upon A:	NONE
F01507 (N, A)	BICO: Interconnections to inactive objects present
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2) VECTOR: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	There are BICO interconnections as signal drain from a drive object that is either inactive/not operational. The BI/CI parameters involved are listed in r9498. The associated BO/CO parameters are listed in r9499. The list of the BICO interconnections to other drive objects is displayed in r9491 and r9492 of the de-activated drive object. Note: r9498 and r9499 are only written into, if p9495 is not set to 0. Alarm value (r2124, decimal): Number of BICO interconnections found to inactive drive objects.
Remedy:	- set all open BICO interconnections centrally to the factory setting with p9495 = 2. - make the non-operational drive object active/operational again (re-insert or activate components).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F01510 BICO: Signal source is not float type

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: The selected connector output does not have the correct data type. This interconnection is not established.
 Fault value (r0949, decimal):
 Parameter number to which an interconnection should be made (connector output).
Remedy: Interconnect this connector input with a connector output having a float data type.

F01511 (A) BICO: Interconnection between various normalizations

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: The requested interconnection was set up. However, a conversion is made between the BICO output and BICO input using the reference values.
 - the BICO output has different normalized units than the BICO input.
 - message only for interconnections within a drive object.
 Message during commissioning and download inactive.
 Example:
 The BICO output has, as normalized unit, voltage and the BICO input has current.
 This means that the factor p2002 (contains the reference value for current) / p2001 (contains the reference value for voltage) is calculated between the BICO output and BICO input.
 Fault value (r0949, decimal):
 Parameter number of the BICO input (signal receiver).
Remedy: No correction needed.
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F01512 BICO: No normalization available

Reaction: A_INFEED: OFF2 (OFF1)
 SERVO: OFF2
 VECTOR: OFF2
Acknowledge: POWER ON
Cause: An attempt was made to determine a conversion factor for a normalization that does not exist.
 Fault value (r0949, decimal):
 Unit (e.g. corresponding to SPEED) for which an attempt was made to determine a factor.
Remedy: Apply normalization or check the transfer value.

F01513 (A) BICO: Spanning DO between different normalizations

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: The requested interconnection was set up. However, a conversion is made between the BICO output and BICO input using the reference values.
 An interconnection is made between different drive objects and the BICO output has different normalized units than the BICO input or the normalized units are the same but the reference values are different.
 Example:
 The BICO output has, as standard unit, voltage and the BICO input has current; both lie in different drive objects.
 This means that the factor p2002 (contains the reference value for current) / p2001 (contains the reference value for voltage) is calculated between the BICO output and BICO input.
 Fault value (r0949, decimal):
 Parameter number of the BICO input (signal receiver).
Remedy: No correction needed.

Reaction upon A: NONE
 Acknowledge upon A: NONE

A01514 (F) BICO: Error when writing during a reconnect

Reaction: NONE
Acknowledge: NONE
Cause: During a reconnect operation (e.g. while booting or downloading - but cannot occur in normal operation) a parameter was not able to be written into.
 Example: When writing to a double word BICO input in the second index, the memory areas overlap (e.g. p8861). The parameter is then reset to the factory setting.
 Alarm value (r2124, decimal): Parameter number of the BICO input (signal receiver).
Remedy: None necessary.
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY

F01515 (A) BICO: Writing to parameter not permitted as the master control is active

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: While changing the number of CDS or when copying from CDS, the master control was active.
Remedy: None necessary.
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A01590 (F) Drive: Motor maintenance interval expired

Reaction: NONE
Acknowledge: NONE
Cause: The selected service/maintenance interval for this motor was reached.
 Alarm value (r2124, decimal): Motor data set number.
 See also: p0650 (Actual motor operating hours), p0651 (Motor operating hours maintenance interval)
Remedy: Carry-out service/maintenance and reset the service/maintenance interval (p0651).
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY

F01600 SI CU: STOP A initiated

Reaction: OFF2
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The drive-based "Safety Integrated" function in the Control Unit (CU) has detected a fault and initiated a STOP A (pulse cancellation via the safety shutdown path of the Control Unit).
 - forced checking procedure of the safety shutdown path of the Control Unit unsuccessful.
 - subsequent response to fault F01611 (defect in a monitoring channel).
 Fault value (r0949, decimal):
 0: Stop request from the Motor Module.
 1005: Pulses cancelled although SH not selected and there is not internal STOP A present.
 1010: Pulses enabled although SH is selected or an internal STOP A is present.
 1015: Feedback of the safe pulse cancellation for Motor Modules connected in parallel are different.
 9999: Subsequent response to fault F01611.
Remedy:
 - select safe standstill and then de-select again.
 - replace the Motor Module involved.
 Re fault value = 9999:
 - carry-out diagnostics for fault F01611.
 Note: CU: Control Unit
 MM: Motor Module
 SH: Safe standstill, SI: Safety Integrated

F01611	SI CU: Defect in a monitoring channel".
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>The drive-based "Safety Integrated" function in the Control Unit (CU) has detected a fault in the crosswise data comparison between the CU and Motor Module (MM) and initiated a STOP F.</p> <p>As a result of this fault, after the parameterized transition has expired (p9658), fault F01600 (SI CU: STOP A initiated) is output.</p> <p>Fault value (r0949, decimal):</p> <p>0: Stop request from the Motor Module.</p> <p>1 to 999:</p> <p>Number of the crosswise compared data that resulted in this fault.</p> <p>1: SI monitoring clock cycle (r9780, r9880).</p> <p>2: SI enable safety functions (p9601, p9801).</p> <p>3: SI SGE changeover tolerance time (p9650, p9850).</p> <p>4: SI transition period STOP F to STOP A (p9658, p9858).</p> <p>5: SI enable Safe Brake Control (p9602, p9802).</p> <p>6: SI motion enable, safety-relevant functions (p9501, internal value). This number is also displayed in r9795.</p> <p>7: SI pulse cancellation delay time for Safe Stop 1 (p9652, p9852).</p> <p>8: SI PROFIsafe address (p9610, p9810).</p> <p>1000: Watchdog timer has expired. Within the time of approx. $5 * p9650$ too many switching operations have occurred at terminal EP of the Motor Module.</p> <p>1001: Initialization error, change timer / check timer.</p> <p>2000: Status of the SH terminals on the Control Unit and Motor Module are different.</p> <p>2001: Feedback signal for safe pulse cancellation on the Control Unit and Motor Module are different.</p> <p>2002: Status of the delay timer SS1 on the Control Unit and Motor Module are different.</p> <p>2004: Status of the SH selection for modules connected in parallel are different.</p> <p>2005: Feedback signal of the safe pulse cancellation on the Control Unit and Motor Modules connected in parallel are different.</p>
Remedy:	<p>Re fault value = 1 to 999:</p> <ul style="list-style-type: none"> - check the crosswise compared data that resulted in a STOP F. - carry-out a POWER ON (power off/on) for all components. - upgrade the Motor Module software. - upgrade the Control Unit software. <p>Re fault value = 1000:</p> <ul style="list-style-type: none"> - check the EP terminal at the Motor Module (contact problems). <p>Re fault value = 1001, 1002:</p> <ul style="list-style-type: none"> - carry-out a POWER ON (power off/on) for all components. - upgrade the Motor Module software. - upgrade the Control Unit software. <p>Re fault value = 2000, 2001, 2002, 2004, 2005:</p> <ul style="list-style-type: none"> - check the tolerance time SGE changeover and if required, increase the value (p9650/p9850, p9652/p9852). - check the wiring of the safety-relevant inputs (SGE) (contact problems). - replace the Motor Module involved. <p>Note:</p> <p>CU: Control Unit</p> <p>EP: Enable Pulses (pulse enable)</p> <p>MM: Motor Module</p> <p>SGE: Safety-relevant input</p> <p>SH: Safe standstill</p> <p>SI: Safety Integrated</p> <p>SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)</p>

N01620 (F, A) SI CU: Safe standstill active

Reaction: NONE
Acknowledge: NONE
Cause: The "safe standstill" function has been selected on the Control Unit (CU) and is active.
Note:
This message does not result in a safety stop response.
Remedy: None necessary.
Note:
CU: Control Unit
SI: Safety Integrated
Reaction upon F: OFF2
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon A: NONE
Acknowledge upon A: NONE

N01621 (F, A) SI CU: Safe Stop 1 active

Reaction: NONE
Acknowledge: NONE
Cause: The "Safe Stop 1" (SS1) function has been selected on the Control Unit (CU) and is active.
Note:
This message does not result in a safety stop response.
Remedy: None necessary.
Note:
CU: Control Unit
SI: Safety Integrated
SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)
Reaction upon F: OFF3
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon A: NONE
Acknowledge upon A: NONE

F01625 SI CU: Sign-of-life error in safety data

Reaction: OFF2
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The drive-based "Safety Integrated" function in the Control Unit (CU) has detected an error in the sign-of-life of the safety data between the CU and Motor Module (MM) and initiated a STOP A.
- there is either a DRIVE-CLiQ communications error or communications have failed.
- a time slice overflow of the safety software has occurred.
Fault value (r0949, decimal):
Only for internal Siemens troubleshooting.
Remedy:
- select safe standstill and then de-select again.
- carry-out a POWER ON (power off/on) for all components.
- check whether there is a DRIVE-CLiQ communications error between the Control Unit and the Motor Module involved and if required, carry-out a diagnostics routine for the faults identified.
- de-select all drive functions that are not absolutely necessary.
- reduce the number of drives.
- check the electrical cabinet design and cable routing for EMC compliance
Note:
CU: Control Unit
MM: Motor Module
SI: Safety Integrated

F01630 **SI CU: Braking signal error**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive-based "Safety Integrated" function in the Control Unit (CU) has detected a braking signal error and initiated a STOP A.

- no motor holding brake connected.
 - the motor holding brake control on the Motor Module is faulty.
 - a DRIVE-CLiQ communications error has occurred between the Control Unit and the Motor Module involved.
- Fault value (r0949, decimal):
- 10: No brake connected or fault in the Motor Module brake control circuit ("open brake" operation).
 - 11: Defect in the brake control circuit of the Motor Module ("brake open" operation).
 - 20: Short-circuit in the brake winding or fault in the brake control circuit of the Motor Module ("brake open" state).
 - 30: No brake connected, short-circuit in the brake winding or fault in the Motor Module brake control circuit ("close brake" operation).
 - 31: Defect in the brake control circuit of the Motor Module ("close brake" operation).
 - 40: Defect in the brake control circuit of the Motor Module ("brake closed" state).
 - 50: Defect in the brake control circuit of the Motor Module or communications fault between the Control Unit and the Motor Module (braking signal diagnostics).

Remedy:

- select safe standstill and then de-select again.
- check the motor holding brake connection.
- check the function of the motor holding brake.
- check whether there is a DRIVE-CLiQ communications error between the Control Unit and the Motor Module involved and if required, carry-out a diagnostics routine for the faults identified.
- check the electrical cabinet design and cable routing for EMC compliance
- replace the Motor Module involved.

Operation with Safe Brake Module:

- check the Safe Brake Modules connection.
- replace the Safe Brake Module.

Note:

CU: Control Unit

MM: Motor Module

SI: Safety Integrated

F01649 **SI CU: Internal software error**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: An internal error in the Safety Integrated software on the Control Unit has occurred.

Note:

This fault results in a STOP A that cannot be acknowledged.

Fault value (r0949, interpret hexadecimal):

Only for internal Siemens troubleshooting.

Remedy:

- carry-out a POWER ON (power off/on) for all components.
- re-commission the "Safety Integrated" function and carry-out a POWER ON.
- upgrade the Control Unit software.
- contact the Hotline.
- replace the Control Unit.

Note:

CU: Control Unit

MM: Motor Module

SI: Safety Integrated

F01650	SI CU: Acceptance test required
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>The drive-based "Safety Integrated" function in the Control Unit requires an acceptance test.</p> <p>Note:</p> <p>This fault results in a STOP A that can be acknowledged.</p> <p>Fault value (r0949, decimal):</p> <p>130: No safety parameters available for the Motor Module.</p> <p>1000: Reference and actual checksum on the Control Unit are not identical (booting).</p> <ul style="list-style-type: none"> - at least one checksum-checked piece of data is defective. <p>2000: Reference and actual checksum on the Control Unit are not identical (commissioning mode).</p> <ul style="list-style-type: none"> - reference checksum incorrectly entered into the Control Unit (p9799 not equal to r9798). <p>2001: Reference and actual checksum on the Motor Module are not identical (commissioning mode).</p> <ul style="list-style-type: none"> - reference checksum incorrectly entered into the Motor Module (p9899 not equal to r9898). <p>2002: Enable of safety-related functions between the Control Unit and Motor Module differ (p9601 not equal to p9801).</p> <p>2003: Acceptance test is required as a safety parameter has been changed.</p> <p>2004: An acceptance test is required because a project with enabled safety-functions has been downloaded.</p> <p>2010: Safe Brake Control is enabled differently between the Control Unit and Motor Module (p9602 not equal to p9802).</p> <p>2020: Error when saving the safety parameters for the Motor Module.</p> <p>9999: Subsequent response of another safety-related fault that occurred when booting that requires an acceptance test.</p>
Remedy:	<p>Re fault value = 130:</p> <ul style="list-style-type: none"> - carry-out safety commissioning routine. <p>Re fault value = 1000:</p> <ul style="list-style-type: none"> - again carry-out safety commissioning routine. - replace the CompactFlash card. <p>Re fault value = 2000:</p> <ul style="list-style-type: none"> - check the safety parameters in the Control Unit and adapt the reference checksum (p9799). <p>Re fault value = 2001:</p> <ul style="list-style-type: none"> - check the safety parameters in the Motor Module and adapt the reference checksum (p9899). <p>Re fault value = 2002:</p> <ul style="list-style-type: none"> - enable the safety-related functions on the Control Unit and check on the Motor Module (p9601 = p9801). <p>Re fault value = 2003, 2004:</p> <ul style="list-style-type: none"> - Carry-out an acceptance test and generate an acceptance report. The procedure when carrying-out an acceptance test as well as an example of the acceptance report are provided in the documentation for SINAMICS Safety Integrated. <p>Re fault value = 2010:</p> <ul style="list-style-type: none"> - enable the Safe Brake Control in the Control Unit and check on the Motor Module (p9602 = p9802). <p>Re fault value = 2020:</p> <ul style="list-style-type: none"> - again carry-out safety commissioning routine. - replace the CompactFlash card. <p>Re fault value = 9999:</p> <ul style="list-style-type: none"> - carry-out diagnostics for the other safety-related fault that is present. <p>Note:</p> <p>CU: Control Unit</p> <p>MM: Motor Module</p> <p>SI: Safety Integrated</p> <p>See also: p9799 (SI reference checksum SI parameters (Control Unit)), p9899 (SI reference checksum SI parameters (Motor Module))</p>

F01651 **SI CU: Synchronization safety time slices unsuccessful**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The "Safety Integrated" function requires a synchronization of the safety time slices between the Control Unit (CU) and Motor Module (MM) and between the Control Unit and the higher-level control. This synchronization routine was not successful.

Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy: - carry-out a POWER ON (power off/on) for all components.
 - upgrade the Motor Module software.
 - upgrade the Control Unit software.
 - upgrade the software of the higher-level control.

Note:
 CU: Control Unit
 MM: Motor Module
 SI: Safety Integrated

F01652 **SI CU: Illegal monitoring clock cycle**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: One of the Safety Integrated monitoring clock cycles is not permissible:

- the drive-based monitoring clock cycle cannot be maintained due to the communication conditions required in the system.
- the monitoring clock cycle for safe motion monitoring functions with the higher-level control is not permissible (p9500).

Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, decimal):
 - for enabled drive-based SI monitoring (p9601/p9801 > 0):
 Minimum setting for the monitoring clock cycle (in μ s).
 - with the motion monitoring function enabled (p9501 > 0):
 100: No matching monitoring clock cycle was able to be found.
 101: The monitoring clock cycle is not an integer multiple of the position controller clock cycle.
 102: An error has occurred when transferring the DP clock cycle to the Motor Module (MM).
 103: An error has occurred when transferring the DP clock cycle to the Sensor Module.

Remedy: For enabled drive-based SI monitoring (p9601/p9801 > 0):
 - upgrade the Control Unit software.
 For enabled motion monitoring function (p9501 > 0):
 - correct the monitoring clock cycle (p9500) and carry-out POWER ON.

Note:
 CU: Control Unit
 MM: Motor Module
 SI: Safety Integrated

F01655	SI CU: Align monitoring functions
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>An error has occurred when aligning the Safety Integrated monitoring functions on the Control Unit (CU) and Motor Module (MM). Control unit and Motor Module were not able to determine a common set of supported SI monitoring functions.</p> <ul style="list-style-type: none"> - there is either a DRIVE-CLIQ communications error or communications have failed. - Safety Integrated software releases on the Control Unit and Motor Module are not compatible with one another. <p>Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - carry-out a POWER ON (power off/on) for all components. - upgrade the Motor Module software. - upgrade the Control Unit software. - check the electrical cabinet design and cable routing for EMC compliance <p>Note: CU: Control Unit MM: Motor Module SI: Safety Integrated</p>

F01656	SI CU: Motor Module parameter error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>When accessing the Safety Integrated parameters for the Motor Module (MM) on the CompactFlash card, an error has occurred.</p> <p>Note: This fault results in a STOP A that can be acknowledged. Fault value (r0949, decimal): 129: Safety parameters for the Motor Module corrupted. 131: Internal Motor Module software error. 132: Communication errors when uploading or downloading the safety parameters for the Motor Module. 255: Internal software error on the Control Unit.</p>
Remedy:	<ul style="list-style-type: none"> - re-commission the safety functions. - upgrade the Control Unit software. - upgrade the Motor Module software. - replace the CompactFlash card. <p>Re fault value = 132: - check the electrical cabinet design and cable routing for EMC compliance</p> <p>Note: CU: Control Unit MM: Motor Module SI: Safety Integrated</p>

F01659	SI CU: Write request for parameter rejected
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The write request for one or several Safety Integrated parameters on the Control Unit (CU) was rejected. Note: This fault does not result in a safety stop response. Fault value (r0949, decimal): 1: The Safety Integrated password is not set. 2: It was selected that the drive parameters are reset. However, the Safety Integrated parameters cannot be reset, as Safety Integrated is presently enabled. 3: The interlocked SH input is in the simulation mode. 10: An attempt was made to enable the SH function although this cannot be supported. 11: An attempt was made to enable the SBC function although this cannot be supported. 12: An attempt was made to enable the SBC function although this cannot be supported for a parallel circuit configuration. 13: An attempt was made to enable the SS1 function although this cannot be supported. 14: An attempt was made to enable the PROFIsafe communications although this cannot be supported. 15: An attempt was made to enable the motion monitoring functions integrated in the drive although these cannot be supported. 16: An attempt was made to enable the SH function although this cannot be supported when the internal voltage protection (p1231) is enabled. See also: p0970 (Reset infeed parameter), p3900 (Completion of quick commissioning), r9771 (SI common functions (Control Unit)), r9871 (SI common functions (Motor Module))
Remedy:	Re fault value = 1: - set the Safety Integrated password (p9761). Re fault value = 2: - inhibit Safety Integrated and again reset the drive parameters. Re fault value = 3: - simulation mode for the digital input has ended (p0795). Re fault value = 10, 11, 12, 13, 14, 15: - check whether there are faults in the safety function alignment between the Control Unit and the Motor Module involved (F01655, F30655) and if required, carry-out diagnostics for the faults involved. - use a Motor Module that supports the required function ("safe standstill", "Safe Brake Control", "PROFIsafe", "motion monitoring functions integrated in the drive"). - upgrade the Motor Module software. - upgrade the Control Unit software. Re fault value = 16: - inhibit the internal voltage protection (p1231). Note: CU: Control Unit SBC: Safe Brake Control SH: Safe standstill SI: Safety Integrated SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204) See also: p9501 (SI motion enable safety-relevant functions), p9601 (SI enable, functions integrated in the drive (Control Unit)), p9620 (SI signal source for SH/SBC/SS1 (Control Unit)), p9761 (SI password input), p9801 (SI enable, functions integrated in the drive (Motor Module))
F01660	SI CU: Safety-related functions not supported
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The Motor Module (MM) does not support the safety-related functions (e.g. the Motor Module version is not the correct one). Safety Integrated cannot be commissioned. Note: This fault results in a STOP A that cannot be acknowledged.
Remedy:	- use a Motor Module that supports the safety-related functions. - upgrade the Motor Module software. Note: CU: Control Unit MM: Motor Module SI: Safety Integrated

F01670	SI Motion: Invalid parameterization, Sensor Module
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The parameterization of a Sensor Module used for Safety Integrated is not permissible. Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, decimal): 1: No encoder was parameterized for Safety Integrated. 2: An encoder was parameterized for Safety Integrated that does not have an A/B track (sinusoidal/cosinusoidal). 3: The encoder data set selected for Safety Integrated is still not valid. 4: A communications error to the encoder has occurred. 10: For an encoder used for Safety Integrated, not all of the Drive Data Sets (DDS) are assigned to the same Encoder Data Set (EDS) (p0187 ... p0189).
Remedy:	Re fault value = 1, 2: - use and parameterize an encoder that Safety Integrated supports (encoder with track A/B sinusoidal, p0404.4 = 1). Re fault value = 3: - check whether the drive or drive commissioning function is active and if required, exit this (p0009 = p00010 = 0), save the parameters (p0971 = 1) and carry-out a POWER ON Re fault value = 4: - check whether there is a DRIVE-CLiQ communications error between the Control Unit and the Sensor Module involved and if required, carry-out a diagnostics routine for the faults identified. Re fault value = 10: - align the EDS assignment of all of the encoders used for safety integrated (p0187 ... p0189). Note: SI: Safety Integrated

F01671	SI Motion: Parameterization error, encoder
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The parameterization of the encoder used by Safety Integrated is different than the parameterization of the standard encoder. Fault value (r0949, decimal): Parameter number of the non-corresponding safety parameter.
Remedy:	Align the encoder parameterization between the safety encoder and the standard encoder. Note: SI: Safety Integrated

F01672	SI Motion: Motor Module software incompatible
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The existing Motor Module software does not support the safe motion monitoring function with the higher-level control. Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.
Remedy:	- check whether there are faults in the safety function alignment between the Control Unit and the Motor Module involved (F01655, F30655) and if required, carry-out the appropriate diagnostics routine for the particular faults. - use a Motor Module that supports safe motion monitoring - upgrade the Motor Module software. Note: SI: Safety Integrated

F01673 **SI Motion: Sensor Module software incompatible**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The existing Sensor Module software does not support the safe motion monitoring function with the higher-level control.
 Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy: - use a Sensor Module that supports safe motion monitoring function.
 - upgrade the Sensor Module software.
 Note:
 SI: Safety Integrated

F01680 **SI Motion: Checksum error, safety monitoring functions**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The actual checksum calculated by the drive and entered in r9728 over the safety-relevant parameters does not match the target checksum saved in p9729 at the last machine acceptance.
 Safety-relevant parameters have been changed or a fault is present.
 Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, decimal):
 0: Checksum error for SI parameters for motion monitoring.
 1: Checksum error for SI parameters for actual values.

Remedy: - Check the safety-relevant parameters and if required, correct.
 - carry-out a POWER ON.
 - carry-out an acceptance test.
 Note:
 SI: Safety Integrated

C01681 **SI Motion: Incorrect parameter value**

Reaction: NONE

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The parameter value cannot be parameterized with this value.
 Fault value (r0949, decimal):
 Parameter number with the incorrect value

Remedy: Correct parameter value

F01682 **SI Motion: Monitoring function not supported**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The monitoring function enabled in p9501, p9601 or p9801 is not supported in this firmware version.
 Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, decimal):
 1: Monitoring function SE not supported (p9501.1).
 2: Monitoring function SN not supported (p9501.7 and p9501.8 - 15 and p9503).
 3: Monitoring function SG override not supported (p9501.5).
 10: Monitoring functions only supported in the servo mode.
 20: Drive-based motion monitoring functions are only supported in conjunction with PROFIsafe (p9501 and p9601.1 - 2 and p9801.1 - 2).
 21: PROFIsafe only supported in conjunction with motion monitoring functions in the drive (p9501 and p9601.1 - 2 and p9801.1 - 2).

Remedy: De-select the monitoring function involved (p9501, p9503, p9601, p9801).
 Note: SE: Safe software limit switch, SG: Safely-reduced speed
 SI: Safety Integrated
 SN: Safe software cam
 See also: p9501 (SI motion enable safety-relevant functions)

F01683 **SI Motion: SBH/SG enable missing**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The safety-relevant basic function "SBH/SG" is not enabled in p9501 although other safety-relevant monitoring functions are enabled.

 Note:
 This fault results in a STOP A that cannot be acknowledged.

Remedy: Enable the function "SBH/SG" (p9501.0) and carry-out a POWER ON.

 Note:
 SBH: Safe operating stop
 SG: Safely-reduced speed
 SI: Safety Integrated
 See also: p9501 (SI motion enable safety-relevant functions)

F01684 **SI Motion: Safe software limit switch limit values interchanged**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: For the function "safe software limit switch" (SE), a lower value is in p9534 as in p9535.

 Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, decimal):
 1: Limit values SE1 interchanged.
 2: Limit values SE2 interchanged.

Remedy: Correct the limit values in p9534 and p9535 and carry-out a POWER ON.

 Note:
 SE: Safe software limit switch
 SI: Safety Integrated

F01685 **SI Motion: Safe velocity limit value too high**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The limit value for the function "safely reduced speed" (SG) is greater than the speed that corresponds to an encoder limit frequency of 500 kHz.

 Fault value (r0949, decimal):
 Maximum permissible speed.

Remedy: Correct the limit values for SG and carry-out a POWER ON.

 Note:
 SG: Safely-reduced speed
 SI: Safety Integrated
 See also: p9531 (SI motion SG limit values)

F01686 **SI Motion: Illegal parameterization, cam position**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: At least one enabled "safety software cam" (SN) is parameterized in p9536 or p9537 too close at the tolerance range around the modulo position.

 Fault value (r0949, decimal):
 Number of the "safe software cam" with an illegal position.
 See also: p9501 (SI motion enable safety-relevant functions)

Remedy: Correct the cam position and carry-out a POWER ON.

 Note:
 SI: Safety Integrated
 SN: Safe software cam
 See also: p9536 (SI motion SN plus cam position), p9537 (SI motion SN minus cam position)

F01687	SI Motion: Illegal parameterization, modulo value SN
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The parameterized modulo value for the "safe software cam" (SN) function is not a multiple of 360 000 mDegrees.
Remedy:	Correct the modulo value for SN and carry-out a POWER ON. Note: SI: Safety Integrated SN: Safe software cam See also: p9505 (SI motion SN modulo value)
F01688	SI Motion: Actual value synchronization not permissible
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	It is not permissible to simultaneously enable the actual value synchronization and a monitoring function with absolute reference (SE/SN).
Remedy:	Either carry-out the monitoring functions with absolute reference (SE/SN) or de-select the "actual value synchronization" function and carry-out a POWER ON. Note: SE: Safe software limit switch SI: Safety Integrated SN: Safe software cam See also: p9501 (SI motion enable safety-relevant functions)
C01689	SI Motion: Axis re-configured
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	The axis configuration was changed. Parameter p0108.13 is internally set to the correct value. Fault value (r0949, decimal): Parameter number that initiated the change. See also: p9502 (SI motion axis type)
Remedy:	Initiate data back-up on the complete Control Unit and carry-out a POWER ON.
A01698 (F)	SI CU: Commissioning mode active
Reaction:	NONE
Acknowledge:	NONE
Cause:	The commissioning of the "Safety Integrated" function is selected. This message is withdrawn after the safety functions have been commissioned. Note: This message does not result in a safety stop response. See also: p0010 (Infeed commissioning parameter filter)
Remedy:	None necessary. Note: CU: Control Unit SI: Safety Integrated
Reaction upon F:	NONE (OFF1, OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY (POWER ON)

A01699 (F)	SI CU: Shutdown path must be tested
Reaction:	NONE
Acknowledge:	NONE
Cause:	The time set in p9659 for the forced checking procedure of the safety shutdown paths has been exceeded. The safety shutdown paths must be re-tested. After the next time that the "safe standstill" function (SH) is de-selected, the message is withdrawn and the monitoring time is reset. Note: This message does not result in a safety stop response. See also: p9659 (SI forced checking procedure timer)
Remedy:	Select safe standstill and then deselect again. Note: CU: Control Unit SH: Safe standstill SI: Safety Integrated
Reaction upon F:	NONE (OFF1, OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY (POWER ON)

C01700	SI Motion: STOP A initiated
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive is stopped via a STOP A (pulses are cancelled via the safety shutdown path of the Control Unit). Possible causes: - stop request from the higher-level control. - pulses not cancelled after a parameterized time (p9557) after test stop selection. - subsequent response to the message C01706 "SI Motion: Safe braking ramp exceeded". - subsequent response to the message C01714 "SI Motion: Safely reduced speed exceeded". - subsequent response to the message C01701 "SI Motion: STOP B initiated".
Remedy:	- remove the fault cause in the control and carry-out a POWER ON. - check the value in p9557, if necessary, increase the value, and carry-out POWER ON. - check the shutdown path of Control Unit (check DRIVE-CLiQ communications). - carry-out a diagnostics routine for message C01706. - carry-out a diagnostics routine for message C01714. - carry-out a diagnostics routine for message C01701. - replace Motor Module. - replace Control Unit. Note: SI: Safety Integrated

C01701	SI Motion: STOP B initiated
Reaction:	OFF3
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive is stopped via a STOP B (braked along the current limit). As a result of this fault, after the time, parameterized in p9556 has expired, or the speed threshold, parameterized in p9560 has been fallen below, message C01700 "STOP A initiated" is output. Possible causes: - stop request from the higher-level control. - subsequent response to the message C01714 "SI Motion: Safely reduced speed exceeded". - subsequent response to the message C01711 "SI Motion: Defect in a monitoring channel".
Remedy:	- remove the fault cause in the control and carry-out a POWER ON. - carry-out a diagnostics routine for message C01714. - carry-out a diagnostics routine for message C01711. Note: SI: Safety Integrated

C01706 SI Motion: Safe braking ramp exceeded

Reaction: NONE

Acknowledge: IMMEDIATELY (POWER ON)

Cause: After initiating STOP B or STOP C, the velocity has exceeded the selected tolerance. The drive is shut down by the message C01700 "SI Motion: STOP A initiated".

Remedy: Check the braking behavior, if required, adapt the tolerance for "safe braking ramp" (SBR).

Note:
SBR: Safe braking ramp
SI: Safety Integrated
See also: p9548 (SI motion SBR actual speed tolerance)

C01707 SI Motion: Tolerance for safe operating stop exceeded

Reaction: NONE

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The actual position has distanced itself further from the target position than the standstill tolerance. The drive is shut down by the message C01701 "SI Motion: STOP B initiated".

Remedy:

- check whether safety faults are present and if required carry-out the appropriate diagnostic routines for the particular faults.
- check whether the standstill tolerance matches the accuracy and control dynamic performance of the axis.
- carry-out a POWER ON.

Note:
SBH: Safe operating stop
SI: Safety Integrated
See also: p9530 (SI motion standstill tolerance)

C01708 SI Motion: STOP C initiated

Reaction: STOP2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive is stopped via a STOP C (braked along the current limit). "Safe operating stop" (SBH) is activated after the parameterized timer stage has expired.

Possible causes:

- stop request from the higher-level control.
- subsequent response to the message C01714 "SI Motion: Safely reduced speed exceeded".
- subsequent response to the message C01715 "SI Motion: Safe end stop exceeded".

See also: p9552 (SI motion transition time STOP C to SBH)

Remedy:

- remove the fault cause in the control and carry-out a POWER ON.
- carry-out a diagnostics routine for message C01714.

Note:
SBH: Safe operating stop
SI: Safety Integrated

C01709 SI Motion: STOP D initiated

Reaction: NONE

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive is stopped via a STOP D (braking along the path). "Safe operating stop" (SBH) is activated after the parameterized timer stage has expired.

Possible causes:

- stop request from the higher-level control.
- subsequent response to the message C01714 "SI Motion: Safely reduced speed exceeded".
- subsequent response to the message C01715 "SI Motion: Safe end stop exceeded".

See also: p9553 (SI motion transition time STOP D to SBH)

Remedy:

- remove the fault cause in the control and carry-out a POWER ON.
- carry-out a diagnostics routine for message C01714.

Note:
SBH: Safe operating stop
SI: Safety Integrated

C01710	SI Motion: STOP E initiated
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive is stopped via a STOP E (retraction motion). "Safe operating stop" (SBH) is activated after the parameterized timer stage has expired. Possible causes: - stop request from the higher-level control. - subsequent response to the message C01714 "SI Motion: Safely reduced speed exceeded". - subsequent response to the message C01715 "SI Motion: Safe end stop exceeded". See also: p9554 (SI motion transition time STOP E to SBH)
Remedy:	- remove the fault cause in the control and carry-out a POWER ON. - carry-out a diagnostics routine for message C01714. Note: SBH: Safe operating stop SI: Safety Integrated

C01711	SI Motion: Defect in a monitoring channel"
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	When cross-checking and comparing the two monitoring channels, the drive detected a difference between the input data or results of the monitoring functions and initiated a STOP F. One of the monitoring function functions no longer reliably functions - i.e. safe operation is no longer possible. If at least one monitoring function is active, then after the parameterized timer stage has expired, the message C01701 "SI Motion: STOP B initiated" is output. The message value that resulted in a STOP F is displayed in r9725. Message value (r9749, decimal): Value, that resulted in a STOP F. See also: p9555 (SI motion transition time STOP F to STOP B), r9725 (SI motion, diagnostics STOP F)
Remedy:	The message value contained in r9725 is described in message 27001 of the higher-level control. Note: SI: Safety Integrated

C01714	SI Motion: Safely reduced speed exceeded
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive had moved faster than that specified by the velocity limit value (p9531). The drive is stopped as a result of the configured stop response (p9563). Message value (r9749, decimal): 100: SG1 exceeded. 200: SG2 exceeded.. 300: SG3 exceeded. 400: SG4 exceeded. 1000: Encoder limit frequency exceeded.
Remedy:	- check the traversing/motion program in the control. - check the limits for "safely reduced speed (SG) and if required, adapt (p9531). Note: SG: Safely-reduced speed SI: Safety Integrated See also: p9531 (SI motion SG limit values), p9563 (SI motion SG-specific stop response)

A01796 (F, N)	SI Motion: Wait for communications to the control
Reaction:	NONE
Acknowledge:	NONE
Cause:	The drive waits for communications to be established with the higher-level control to execute the safety-relevant motion monitoring functions.
	Note: In this state, the pulses are safely deleted.
Remedy:	If, after a longer period of time, the message is not automatically withdrawn, then the following checks are made: - correct assignment of the axes on the higher-level control to the drives in the drive unit. - enable signal of the safety-relevant motion monitoring functions for the corresponding axis on the higher-level control.
Reaction upon F:	NONE (OFF1, OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
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C01798	SI Motion: Test stop running
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The test stop is active.
Remedy:	None necessary. The message is withdrawn when the test stop is ended.
	Note: SI: Safety Integrated
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C01799	SI Motion: Acceptance test mode active
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The acceptance test mode is active. The POWER ON signals of the safety-relevant motion monitoring functions can be acknowledged during the acceptance test using the RESET button of the higher-level control.
Remedy:	None necessary. The message is withdrawn when exiting the acceptance test mode.
	Note: SI: Safety Integrated

F01800	DRIVE-CLiQ: Hardware/configuration error
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	A DRIVE-CLiQ connection fault has occurred. Fault value (r0949, decimal): 0 ... 7: Communications via DRIVE-CLiQ socket 0 ... 7 has not been switched to cyclic operation. The cause can be an incorrect structure or a configuration that results in an impossible bus timing. 10: Loss of the DRIVE-CLiQ connection. The cause can be, for example, that the DRIVE-CLiQ cable was withdrawn from the Control Unit or as a result of a short-circuit for motors with DRIVE-CLiQ. This fault can only be acknowledged in cyclic communication. 11: Repeated fault when detecting the connection. This fault can only be acknowledged in cyclic communication. 12: A connection was detected but the node ID exchange mechanism does not function. The reason is probably that the component is defective. This fault can only be acknowledged in cyclic communication.
Remedy:	Re fault value = 0 ... 7: - ensure that the DRIVE-CLiQ components have the same firmware releases. - avoid longer topologies for short current controller clock cycles. Re fault value = 10: - check the DRIVE-CLiQ cables at the Control Unit. - remove any short-circuit for motors with DRIVE-CLiQ. - carry-out a POWER ON. Re fault value = 11: - check the electrical cabinet design and cable routing for EMC compliance Re fault value = 12: - replace the component involved.
F01802 (A)	CU DRIVE-CLiQ: POWER ON due to basis sampling times
Reaction:	A_INFEED: OFF2 (OFF1) SERVO: OFF2 (DCBRAKE, OFF1) VECTOR: OFF2 (DCBRAKE, OFF1)
Acknowledge:	POWER ON
Cause:	It is not possible to change the DRIVE-CLiQ basic sampling times p0110 in operation. POWER ON is required. Fault value (r0949, decimal): Index of p0110.
Remedy:	- save (p0971 = 1). - carry-out a POWER ON.
Reaction upon A:	NONE
Acknowledge upon A:	NONE
A01900 (F)	PROFIBUS: Configuration telegram error
Reaction:	NONE
Acknowledge:	NONE
Cause:	A PROFIBUS master attempts to establish a connection using an incorrect configuring telegram. Alarm value (r2124, decimal): 50: Syntax error. 51: Connection established to more drive objects than configured in the device. The drive objects for process data exchange and their sequence was defined using p0978. 52: Too many data words for input or output to a drive object. A max. of 16 words is permitted for SERVO and VECTOR; max. 5 words, for A_INFEED, TB30, TM31 and CU320. 53: Uneven number of bytes for input or output.
Remedy:	Check the bus configuring on the master and slave sides. Re alarm value = 51: Check the list of the drive objects with process data exchange (p0978). With p0978[x] = 0, all of the following drive objects in the list are excluded from the process data exchange.

Reaction upon F: NONE (OFF1)
 Acknowledge upon F: IMMEDIATELY

A01901 (F) PROFIBUS: Parameterizing telegram error

Reaction: NONE
Acknowledge: NONE
Cause: A PROFIBUS master attempts to establish a connection using an incorrect parameterizing telegram.
 Alarm value (r2124, decimal):
 1: Incorrect parameterizing bits
 10: Illegal length of an optional parameterizing block
 11: Illegal ID of an optional parameterizing block
 20: Double parameterizing block for clock synchronization
 21: Incorrect parameterizing block for clock synchronization
 22: Incorrect parameterizing bits for clock synchronization

Remedy: Check the bus configuration:
 - bus addresses
 - slave configuring

Reaction upon F: NONE (OFF1)
 Acknowledge upon F: IMMEDIATELY

A01902 PROFIBUS: Illegal parameterizing telegram

Reaction: NONE
Acknowledge: NONE
Cause: Alarm value (r2124, decimal):
 0: Bus cycle time Tdp < 0.5 ms.
 1: Bus cycle time Tdp > 32 ms.
 2: Bus cycle time Tdp is not a integer multiple of the current controller clock cycle.
 3: Instant of the actual value sensing Ti > Bus cycle time Tdp.
 4: Instant of the actual value sensing Ti is not an integer multiple of the current controller clock cycle.
 5: Instant of the setpoint transfer To >= Bus cycle time Tdp.
 6: Instant of the setpoint transfer To is not an integer multiple of the current controller clock cycle.
 7: Master application cycle time Tmapc is not an integer multiple of the speed controller clock cycle.
 8: Bus reserve bus cycle time Tdp - data exchange time Tdx less than two current controller clock cycles.
 9: Bus cycle time Tdp has been modified with respect to the first time that the connection was established.
 10: Instant of the setpoint transfer not To <= data exchange time Tdx + To_min.
 11: Master application cycle time Tmapc > 14.
 12: PLL tolerance window Tpll_w > Tpll_w_max.
 13: Bus cycle time Tdp is not a multiple of all basic clock cycles p0110[x].
 14: For COMM BOARD with the setting To - 1 = Tdp - Ti, the instant of the setpoint transfer is not To <= Data Exchange time Tdx + 2 * To_min.
 15: This configuration is not permitted for Tdp < 1 ms.
 16: Instant of the actual value sensing Ti is less than the permitted value (COMM BOARD: Ti >= 2).
 17: The setting (To + Ti = Tdp + 2) is not permitted for COMM BOARD.

Remedy:
 - adapt the parameterizing telegram.
 - adapt the current and speed controller clock cycle.
 Re alarm value = 9:
 - carry-out a POWER ON.
 Re alarm value = 15:
 - check the number of specific drive object types in the configuration.

A01903 (F)	COMM INT: Receive configuration data invalid
Reaction:	NONE
Acknowledge:	NONE
Cause:	The drive unit did not accept the receive-configuration data. Alarm value (r2124, decimal): Return value of the receive-configuration data check. 0: Configuration accepted. 1: Connection established to more drive objects than configured in the device. The drive objects for process data exchange and their sequence was defined using p0978. 2: Too many data words for input or output to a drive object. A max. of 16 words is permitted for SERVO and VECTOR; max. 5 words, for A_INFEED, TB30, TM31 and CU320. 3: Uneven number of bytes for input or output. 4: Setting data for synchronization not accepted. 5: Drive still not in cyclic operation. 6: Buffer system not accepted. 7: Cyclic channel length too short for this setting. 8: Cyclic channel address not initialized. 9: 3-buffer system not permitted. 10: DRIVE-CLiQ fault. 11: CU link fault. 12: CX32 not in cyclic operation.
Remedy:	Check the receive configuration data. Re alarm value = 1: Check the list of the drive objects with process data exchange (p0978). With p0978[x] = 0, all of the following drive objects in the list are excluded from the process data exchange.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (OFF1, OFF2, OFF3) VECTOR: NONE (OFF1, OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY
F01910 (N, A)	PROFIBUS: Setpoint timeout
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF3 (DCBRAKE, NONE, OFF1, OFF2, STOP1, STOP2) VECTOR: OFF3 (DCBRAKE, NONE, OFF1, OFF2, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	The receipt of setpoints from the PROFIBUS interface is interrupted because the bus connection is interrupted or the PROFIBUS master is switched off or was set into the STOP state.
Remedy:	Restore the bus connection and set the PROFIBUS master to RUN.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE
F01911	PROFIBUS: Clock synchronous operation, clock cycle failure
Reaction:	OFF1
Acknowledge:	IMMEDIATELY
Cause:	The global control telegram to synchronize the clock cycles has failed - in cyclic operation - for several DP clock cycles or has violated the time grid specified in the parameterizing telegram over several consecutive DP clock cycles (refer to the bus cycle time, Tdp and Tdplw).
Remedy:	- check the PROFIBUS cables and connectors. - check whether communications were briefly or permanently interrupted. - check the bus and master for utilization level (e.g. bus cycle time Tdp was set too short).

F01912 PROFIBUS: Clock synchronous operation sign-of-life missing

Reaction: OFF1

Acknowledge: IMMEDIATELY

Cause: The maximum permissible number of errors in the master sign-of-life (clock synchronous PROFIBUS) has been exceeded in cyclic operation.

Remedy:

- check the physical bus configuration (terminating resistor, shielding, etc.).
- check the interconnection of the master sign-of-life (p2045).
- check whether the master correctly sends the sign-of-life (e.g. set-up a trace with STW2.12 ... STW2.15 and trigger signal ZSW1.3).
- check the permissible telegram failure rate (p0925).
- check the bus and master for utilization level (e.g. bus cycle time Tdp was set too short).

F01913 (N, A) COMM INT: Monitoring time, sign-of-life expired

Reaction: A_INFEED: OFF1 (NONE, OFF2)
SERVO: OFF1 (NONE, OFF2, OFF3)
VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The monitoring time for the sign-of-life counter has expired.

Remedy:

- acknowledge faults that are present.
- carry-out a POWER ON (power off/on) for all components.
- upgrade the firmware release.
- contact the Hotline.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F01914 (N, A) COMM INT: Monitoring time, configuration expired

Reaction: A_INFEED: OFF1 (NONE, OFF2)
SERVO: OFF1 (NONE, OFF2, OFF3)
VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The monitoring time for the configuration has expired.
Fault value (r0949, decimal):
0: The transfer of the send-configuration data has been exceeded (time).
1: The transfer of the receive-configuration data has been exceeded (time).

Remedy:

- acknowledge faults that are present.
- carry-out a POWER ON (power off/on) for all components.
- upgrade the firmware release.
- contact the Hotline.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

A01920 (F) PROFIBUS: Interruption, cyclic connection

Reaction: NONE

Acknowledge: NONE

Cause: The cyclic connection to the PROFIBUS master is interrupted.

Remedy: Set up the PROFIBUS connection and activate the PROFIBUS master in the cyclic mode.

Reaction upon F: NONE (OFF1)

Acknowledge upon F: IMMEDIATELY

A01921 (F)	PROFIBUS: Clock cycle synchronization
Reaction:	NONE
Acknowledge:	NONE
Cause:	Output data of PROFIBUS master (setpoints) received at the incorrect instant in time within the PROFIBUS clock cycle.
Remedy:	Check the bus configuration: - parameter for clock cycle synchronization: Ensure the instant in time for setpoint acceptance $T_o >$ data exchange time T_{dx}
Reaction upon F:	NONE (OFF1)
Acknowledge upon F:	IMMEDIATELY

A01930	PROFIBUS: Current controller clock cycle for clock synchronous operation not the same
Reaction:	NONE
Acknowledge:	NONE
Cause:	The current controller clock cycle of all drives must be set the same for the clock synchronous PROFIBUS. Alarm value (r2124, decimal): Number of the drive object with the different current controller clock cycle.
Remedy:	- set current controller clock cycles to identical values (p0115[0]). See also: p0115 (Sampling time for supplementary functions)

A01931	PROFIBUS: Speed controller clock cycle for clock synchronous operation not the same
Reaction:	NONE
Acknowledge:	NONE
Cause:	The speed controller clock cycle of all drives must be set the same for the clock synchronous PROFIBUS. Alarm value (r2124, decimal): Number of the drive object with the different speed controller clock cycle.
Remedy:	- set the speed controller clock cycles the same (p0115[1]). See also: p0115 (Sampling time for supplementary functions)

A01940	PROFIBUS: Clock cycle synchronism not reached
Reaction:	NONE
Acknowledge:	NONE
Cause:	PROFIBUS is in the data exchange state and clock synchronous operation has been selected using the parameterizing telegram. It was not possible to synchronize to the clock cycle specified by the master. - the master doesn't send a clock synchronous global control telegram although the clock synchronous operation was selected when configuring the bus. - the master is using another clock synchronous DP clock cycle than was transferred to the slave in the parameterizing telegram. - at least one drive object (that is not controlled from PROFIBUS) has a pulse enable.
Remedy:	- check the master application and bus configuration. - check the consistency between the clock cycle input when configuring the slave and clock cycle setting at the master. - ensure that the pulses of drive objects, not controlled from PROFIBUS, are not enabled. Only enable the pulses after synchronizing the PROFIBUS drives.

A01941	PROFIBUS: Clock cycle signal missing when the bus is being established
Reaction:	NONE
Acknowledge:	NONE
Cause:	PROFIBUS is in the data exchange state and clock synchronous operation has been selected using the parameterizing telegram. The global control telegram for synchronization is not being received.
Remedy:	Check the master application and bus configuration.

A01943	PROFIBUS: Clock cycle signal error when the bus is being established
Reaction:	NONE
Acknowledge:	NONE
Cause:	PROFIBUS is in the data exchange state and clock synchronous operation has been selected using the parameterizing telegram. The global control telegram for synchronization is being irregularly received. - the master is sending an irregular global control telegram. - the master is using another clock synchronous DP clock cycle than was transferred to the slave in the parameterizing telegram.
Remedy:	- check the master application and bus configuration. - check the consistency between the clock cycle input when configuring the slave and clock cycle setting at the master.
A01944	PROFIBUS: Sign-of-life synchronism not reached
Reaction:	NONE
Acknowledge:	NONE
Cause:	PROFIBUS is in the data exchange state and clock synchronous operation has been selected using the parameterizing telegram. Synchronization with the master sign-of-life (STW2.12 ... STW2.15) could not be completed because the sign-of-life is changing differently than configured in the Tmapc time grid.
Remedy:	- ensure that the master correctly increments the sign-of-life in the master application clock cycle. - check the interconnection of the master sign-of-life (p2045).
A01945	PROFIBUS: Connection to the Publisher faulted
Reaction:	NONE
Acknowledge:	NONE
Cause:	For PROFIBUS peer-to-peer data transfer, the connection to at least one Publisher is faulted. Alarm value (r2124, interpret binary): Bit 0 = 1: Publisher with address in r2077[0], connection faulted. ... Bit 15 = 1: Publisher with address in r2077[15], connection faulted.
Remedy:	- check the PROFIBUS cables. - carry-out a first commissioning of the Publisher that has the faulted connection. See also: r2077 (PROFIBUS diagnostics peer-to-peer data transfer addresses)
F01946 (A)	PROFIBUS: Connection to the Publisher interrupted
Reaction:	A_INFEED: OFF1 (NONE, OFF2) SERVO: OFF1 (NONE, OFF2, OFF3) VECTOR: OFF1 (NONE, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	At this drive object, the connection to at least one Publisher for PROFIBUS peer-to-peer data transfer in cyclic operation was interrupted. Alarm value (r2124, interpret binary): Bit 0 = 1: Publisher with address in r2077[0], connection interrupted. ... Bit 15 = 1: Publisher with address in r2077[15], connection interrupted.
Remedy:	- check the PROFIBUS cables. - check the state of the Publisher that has the interrupted connection. See also: r2077 (PROFIBUS diagnostics peer-to-peer data transfer addresses)
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F01950 (N, A)	PROFIBUS: Clock synchronous operation, synchronization unsuccessful
Reaction:	OFF1 (NONE)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	Synchronization of the internal clock cycle to the global control telegram has failed. The internal clock cycle exhibits an unexpected shift.
Remedy:	Siemens-internal
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F01951	CU DRIVE-CLiQ: Synchronization application clock cycle missing
Reaction:	OFF2 (NONE)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	If DRIVE-CLiQ components with different application clock cycle are operated at a DRIVE-CLiQ port, then this requires synchronization with the Control Unit. This synchronization routine was not successful. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.
Remedy:	- carry-out a POWER ON (power off/on) for all components. - upgrade the Motor Module software. - upgrade the Control Unit software.

F01952	CU DRIVE-CLiQ: Synchronization of component not supported
Reaction:	OFF2 (NONE)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The existing system configuration requires at the connected DRIVE-CLiQ components support the synchronization between the basic clock cycle, DRIVE-CLiQ clock cycle and the application clock cycle. However, not all DRIVE-CLiQ components have this functionality. Fault value (r0949, decimal): Component number of the first faulted DRIVE-CLiQ component.
Remedy:	Upgrade the firmware of the component specified in the fault value. Note: If required, also upgrade additional components in the DRIVE-CLiQ line.

A01953	CU DRIVE-CLiQ: Synchronization not completed
Reaction:	NONE
Acknowledge:	NONE
Cause:	After the drive system is powered-up, the synchronization between the basic clock cycle, DRIVE-CLiQ clock cycle and application clock cycle was started but was not completed within the selected time (tolerance). Alarm value (r2124, decimal): Only for internal Siemens troubleshooting.
Remedy:	Carry-out a POWER ON (power off/on) for all components.

F01954	CU DRIVE-CLiQ: Synchronization unsuccessful
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	After the drive system is powered-up, the synchronization between the basic clock cycle, DRIVE-CLiQ clock cycle and application clock cycle was started and was not able to be successfully completed. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.

Remedy:

1. Ensure perfect functioning of the DRIVE-CLiQ.
2. Initiate a new synchronization, e.g. by:
 - remove the PROFIBUS master and re-insert again.
 - restart the PROFIBUS master.
 - power-down the Control Unit and power-up again.
 - press the Control Unit reset button.
 - reset the parameter and download the saved parameters (p0009 = 30, p0976 = 2).

A01955 CU DRIVE-CLiQ: Synchronization DO not completed

Reaction: NONE
Acknowledge: NONE
Cause: After the drive system is powered-up, the synchronization between the basic clock cycle, DRIVE-CLiQ clock cycle and application clock cycle was started but was not completed within the selected time (tolerance).
 Alarm value (r2124, decimal):
 Only for internal Siemens troubleshooting.
Remedy: Carry-out a POWER ON (power off/on) for all components of the DO.

A02000 Function generator: Start not possible

Reaction: NONE
Acknowledge: NONE
Cause: The function generator has already been started.
Remedy: Stop the function generator and restart again if necessary.
 See also: p4800 (Function generator control)

A02005 Function generator: Drive does not exist

Reaction: NONE
Acknowledge: NONE
Cause: The drive object specified for connection does not exist.
 See also: p4815 (Function generator drive number)
Remedy: Use the existing drive object with the corresponding number.
 See also: p4815 (Function generator drive number)

A02006 Function generator: No drive specified for connection

Reaction: NONE
Acknowledge: NONE
Cause: No drive specified for connection in p4815.
 See also: p4815 (Function generator drive number)
Remedy: At least one drive to be connected must be specified in p4815.
 See also: p4815 (Function generator drive number)

A02007 Function generator: Drive not SERVO

Reaction: NONE
Acknowledge: NONE
Cause: The drive object specified for connection is not a SERVO.
 See also: p4815 (Function generator drive number)
Remedy: Use a SERVO drive object with the corresponding number.

A02008 Function generator: Drive specified a multiple number of times

Reaction: NONE
Acknowledge: NONE
Cause: The drive object specified for connection is already specified.
 Alarm value (r2124, decimal):
 Drive object number of the drive object that is specified a multiple number of times.
Remedy: Specify a different drive object.

A02010	Function generator: Speed setpoint from the drive is not zero
Reaction:	NONE
Acknowledge:	NONE
Cause:	The speed setpoint of a drive - selected to be connected to - is greater than the value for the standstill detection set using p1226. Alarm value (r2124, decimal): Number of the drive object involved.
Remedy:	For all of the drives specified for connection, set the speed setpoints to 0.

A02011	Function generator: The actual drive speed is not zero
Reaction:	NONE
Acknowledge:	NONE
Cause:	The speed actual value of a drive - selected to be connected to - is greater than the value for the standstill detection set using p1226. Alarm value (r2124, decimal): Number of the drive object involved.
Remedy:	Set the relevant drives to zero speed before starting the function generator.

A02015	Function generator: Drive enable signals missing
Reaction:	NONE
Acknowledge:	NONE
Cause:	The master control and/or enable signals are missing to connect to the specified drive. Alarm value (r2124, decimal): Number of the drive object involved. See also: p4815 (Function generator drive number)
Remedy:	Fetch the master control to the specified drive object and set all enable signals.

A02020	Function generator: Parameter cannot be changed
Reaction:	NONE
Acknowledge:	NONE
Cause:	This parameter setting cannot be changed when the function generator is active (p4800 = 1). See also: p4810 (Function generator mode), p4812 (Function generator physical address), p4813 (Function generator physical address reference value), p4815 (Function generator drive number), p4820 (Function generator signal shape), p4821 (Function generator period), p4822 (Function generator pulse width), p4823 (Function generator bandwidth), p4824 (Function generator amplitude), p4825 (Function generator 2nd amplitude), p4826 (Function generator offset), p4827 (Function generator ramp-up time to offset), p4828 (Function generator lower limit), p4829 (Function generator upper limit)
Remedy:	- stop before parameterizing the function generator (p4800 = 0). - if required, start the function generator (p4800 = 1). See also: p4800 (Function generator control)

A02025	Function generator: Period too short
Reaction:	NONE
Acknowledge:	NONE
Cause:	The value for the period is too short. See also: p4821 (Function generator period)
Remedy:	Check and adapt the value for the period. See also: p4821 (Function generator period)

A02026	Function generator: Pulse width too wide
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected pulse width is too high. The pulse width must be less than the period duration. See also: p4822 (Function generator pulse width)
Remedy:	Reduce pulse width. See also: p4821 (Function generator period), p4822 (Function generator pulse width)

A02030	Function generator: Physical address equals zero
Reaction:	NONE
Acknowledge:	NONE
Cause:	The specified physical address is zero. See also: p4812 (Function generator physical address)
Remedy:	Set a physical address with a value other than zero. See also: p4812 (Function generator physical address)
A02040	Function generator: Impermissible value for offset
Reaction:	NONE
Acknowledge:	NONE
Cause:	The value for the offset is higher than the value for the upper limit or lower than the value for the lower limit. See also: p4826 (Function generator offset)
Remedy:	Adjust the offset value accordingly. See also: p4826 (Function generator offset), p4828 (Function generator lower limit), p4829 (Function generator upper limit)
A02041	Function generator: Impermissible value for bandwidth
Reaction:	NONE
Acknowledge:	NONE
Cause:	The bandwidth, referred to the time slice clock cycle of the function generator has either been set too low or too high. Depending on the time slice clock cycle, the bandwidth is defined as follows: Bandwidth_max = 1 / (2 * time slice clock cycle) Bandwidth_min = Bandwidth_max / 100000 Example: Assumption: p4830 = 125 µs --> Bandwidth_max = 1 / (2 * 125 µs) = 4000 Hz --> Bandwidth_min = 4000 Hz / 100000 = 0.04 Hz Note: p4823: Function generator bandwidth p4830: Function generator time slice clock cycle See also: p4823 (Function generator bandwidth), p4830 (Function generator time slice cycle)
Remedy:	Check the value for the bandwidth and appropriately adapt.
A02047	Function generator: Time slice clock cycle invalid
Reaction:	NONE
Acknowledge:	NONE
Cause:	The time slice cycle selected does not match any of the existing time slices. See also: p4830 (Function generator time slice cycle)
Remedy:	Input an existing time slice cycle. The existing time slices can be read out via p7901. See also: r7901 (Time slice cycle times)
A02050	Trace: Start not possible
Reaction:	NONE
Acknowledge:	NONE
Cause:	The trace has already been started. See also: p4700 (Trace control)
Remedy:	Stop the trace and, if necessary, start again.
A02055	Trace: Recording time too short
Reaction:	NONE
Acknowledge:	NONE
Cause:	The trace duration is too short. The minimum is twice the value of the trace clock cycle. See also: p4721 (Trace recording time)
Remedy:	Check the selected recording time and, if necessary, adjust.

A02056	Trace: Recording cycle too short
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected recording cycle is shorter than the selected basis clock cycle 0 (p0110[0]). See also: p4720 (Trace recording cycle)
Remedy:	Increase the value for the trace cycle.

A02057	Trace: Time slice clock cycle invalid
Reaction:	NONE
Acknowledge:	NONE
Cause:	The time slice cycle selected does not match any of the existing time slices. See also: p4723 (Time slice cycle for trace)
Remedy:	Input an existing time slice cycle. The existing time slices can be read out via p7901. See also: r7901 (Time slice cycle times)

A02060	Trace: Signal to be traced missing
Reaction:	NONE
Acknowledge:	NONE
Cause:	- a signal to be traced was not specified. - the specified signals are not valid. See also: p4730 (Trace record signal 0), p4731 (Trace record signal 1), p4732 (Trace record signal 2), p4733 (Trace record signal 3)
Remedy:	- specify the signal to be traced. - check whether the relevant signal can be traced.

A02061	Trace: Invalid signal
Reaction:	NONE
Acknowledge:	NONE
Cause:	- the specified signal does not exist. - the specified signal can no longer be traced (recorded). See also: p4730 (Trace record signal 0), p4731 (Trace record signal 1), p4732 (Trace record signal 2), p4733 (Trace record signal 3)
Remedy:	- specify the signal to be traced. - check whether the relevant signal can be traced.

A02062	Trace: Invalid trigger signal
Reaction:	NONE
Acknowledge:	NONE
Cause:	- a trigger signal was not specified. - the specified signal does not exist. - the specified signal is not a fixed-point signal. - the specified signal cannot be used as trigger signal for the trace. See also: p4711 (Trace trigger signal)
Remedy:	Specify a valid trigger signal.

A02063	Trace: Invalid data type
Reaction:	NONE
Acknowledge:	NONE
Cause:	The specified data type to select a signal using a physical address is invalid. See also: p4711 (Trace trigger signal), p4730 (Trace record signal 0), p4731 (Trace record signal 1), p4732 (Trace record signal 2), p4733 (Trace record signal 3)
Remedy:	Use a valid data type.

A02070	Trace: Parameter cannot be changed
Reaction:	NONE
Acknowledge:	NONE
Cause:	The trace parameter settings cannot be changed when the trace is active. See also: p4700 (Trace control), p4710 (Trace trigger condition), p4711 (Trace trigger signal), p4712 (Trace trigger threshold), p4713 (Trace tolerance band trigger threshold), p4714 (Trace tolerance band trigger threshold), p4715 (Trace bit mask trigger, bit mask), p4716 (Trace, bit mask trigger, trigger condition), p4720 (Trace recording cycle), p4721 (Trace recording time), p4722 (Trace trigger delay), p4730 (Trace record signal 0), p4731 (Trace record signal 1), p4732 (Trace record signal 2), p4733 (Trace record signal 3), p4780 (Trace physical address signal 0), p4781 (Trace physical address signal 1), p4782 (Trace physical address signal 2), p4783 (Trace physical address signal 3), p4789 (Trace physical address trigger signal), p4795 (Trace memory bank changeover)
Remedy:	- stop the trace before parameterization. - if required, start the trace.
A02075	Trace: Pretrigger time too long
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected pretrigger time must be shorter than the recording time. See also: p4721 (Trace recording time), p4722 (Trace trigger delay)
Remedy:	Check the pretrigger time setting and change if necessary.
A02099	Trace: Insufficient Control Unit memory
Reaction:	NONE
Acknowledge:	NONE
Cause:	The memory space still available on the Control Unit is no longer sufficient for the trace function.
Remedy:	Reduce the memory required, e.g. as follows: - reduce the trace (record) time. - increase the trace clock cycle. - reduce the number of signals to be traced (recorded). See also: r4708 (Trace memory space required), r4799 (Trace memory location free)
A02100	CU: Computation deadtime current controller too short
Reaction:	NONE
Acknowledge:	NONE
Cause:	The value in p0118 produces a dead time of one clock cycle because it lies before the setpoint becomes available. A possible cause could be, for example, that the system characteristics no longer match those parameterized after a component has been replaced. Alarm value (r2134, floating point): The minimum value for p0118 where a deadtime no longer occurs.
Remedy:	- set p0118 to a value greater than or equal to the alarm value. - set p0117 to an automatic setting. - check the firmware releases of the components involved. See also: p0117 (Current controller computation deadtime mode), p0118 (Current controller computation deadtime)
A02150	OA application cannot be loaded
Reaction:	NONE
Acknowledge:	NONE
Cause:	The system was not able to load an OA application. Alarm value (r2124, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	- carry-out a POWER ON (power off/on) for all components. - upgrade the firmware release. - contact the Hotline. See also: r4950 (OA application count), r4955 (OA application identifier), p4956 (OA application activation), r4957 (OA application version)

F02151 (A) OA application, internal software error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: OFF2 (NONE, OFF1, OFF3)
VECTOR: OFF2 (NONE, OFF1, OFF3)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: An internal software error has occurred within an OA application.
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy: - carry-out a POWER ON (power off/on) for all components.
- upgrade the firmware release.
- contact the Hotline.
- replace the Control Unit.
See also: r4950 (OA application count), r4955 (OA application identifier), p4956 (OA application activation), r4957 (OA application version)

Reaction upon A: NONE
Acknowledge upon A: NONE

F02152 (A) OA application, insufficient memory

Reaction: OFF1

Acknowledge: IMMEDIATELY (POWER ON)

Cause: Two many functions, data sets or drives configured on this Control Unit.
Fault value (r0949, decimal):
Only for internal Siemens troubleshooting.

Remedy: - change the configuration on this Control Unit.
- use an additional Control Unit.
See also: r4950 (OA application count), r4955 (OA application identifier), p4956 (OA application activation), r4957 (OA application version)

Reaction upon A: NONE
Acknowledge upon A: NONE

F03500 (A) TM: Initialization

Reaction: OFF1 (OFF2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: When initializing the Terminal Modules, the terminals of the Control Unit or the Terminal Board 30, an internal software error has occurred.
Fault value (r0949, decimal):
The thousands location = 1 ... 3:
The component number (p0151) of the module involved is specified at the ones, tens and hundreds position.

Remedy: - power-down the power supply for the Control Unit and power-up again.
- check the DRIVE-CLiQ connection.
- if required, replace the Terminal Module.
The Terminal Module should be directly connected to a DRIVE-CLiQ socket of the Control Unit.
If the fault occurs again, replace the Terminal Module.

Reaction upon A: NONE
Acknowledge upon A: NONE

A03501 TM: Sampling time change

Reaction: NONE

Acknowledge: NONE

Cause: The sampling times of the inputs/outputs were changed.
This change only becomes valid after the next boot.

Remedy: Carry-out a POWER ON.

F03505 (N, A)	TM: Analog input, wire breakage
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The input current of the TM analog input has exceeded the threshold value parameterized in p4061[x]. This fault can only occur, if p4056[x] = 3 (4 ... 20 mA with monitoring) is set. Index x = 0: Analog input 0 (X522.1 to .3) Index x = 1: Analog input 1 (X522.4 to .5) Fault value (r0949, decimal): The component number (p0151) of the module involved is specified at the ones, tens and hundreds position. The thousands position specifies the analog input involved: 0: Analog input 0 (AI 0), 1: Analog input 1 (AI 1)
Remedy:	Check the connection to the signal source for interruptions. Check the magnitude of the impressed current - it is possible that the impressed signal is too low. Please note that the input has a load resistor of 250 Ohm. The input current measured by the TM can be read-out of r4052[x].
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

A03550	TM: Speed setpoint filter natural frequency > Shannon frequency
Reaction:	NONE
Acknowledge:	NONE
Cause:	The natural filter frequency of the speed setpoint filter (p1417) is greater than the Shannon frequency. The Shannon frequency is calculated according to the following formula: $0.5 / p0115[0]$ See also: p1417 (Speed setpoint filter 1 denominator natural frequency)
Remedy:	Reduce the natural frequency of the speed setpoint filter (PT2 low pass) (p1417).

F03590 (N, A)	TM: Module not ready
Reaction:	A_INFEED: OFF2 (NONE) SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The Terminal Module involved does not send a ready signal and no valid cyclic data. Fault value (r0949, decimal): Drive object number.
Remedy:	- check the 24 V power supply. - check the DRIVE-CLiQ connection.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

A05000 (N)	Power unit: Heatsink overtemperature
Reaction:	NONE
Acknowledge:	NONE
Cause:	The alarm threshold for overtemperature at the inverter heatsink has been reached. The response is set using p0290. If the temperature of the heatsink increases by an additional 5 K, then fault F30004 is initiated.
Remedy:	Check the following: - is the ambient temperature within the defined limit values? - have the load conditions and the load duty cycle been appropriately dimensioned? - has the cooling failed?

Reaction upon N: NONE
Acknowledge upon N: NONE

A05001 (N) Power unit: Chip overtemperature

Reaction: NONE

Acknowledge: NONE

Cause: Alarm threshold for overtemperature of the power semiconductor in the AC converter has been reached. The response is set using p0290.
If the chip temperature increases by an additional 15 K, then fault F30025 is initiated.

Remedy: Check the following:
- is the ambient temperature within the defined limit values?
- have the load conditions and the load duty cycle been appropriately dimensioned?
- has the cooling failed?
- pulse frequency too high?
See also: r0037 (Power unit temperatures), p0290 (Power unit overload response)

Reaction upon N: NONE
Acknowledge upon N: NONE

A05002 (N) Power unit: Air intake overtemperature

Reaction: NONE

Acknowledge: NONE

Cause: The alarm threshold for the air intake overtemperature has been reached. For air-cooled power units, the threshold is 42 degrees Celcius (hysteresis 2 K). The response is set using p0290.
If the air intake temperature increases by an additional 13 K, then fault F30035 is output.

Remedy: Check the following:
- is the ambient temperature within the defined limit values?
- has the fan failed? Check the direction of rotation.

Reaction upon N: NONE
Acknowledge upon N: NONE

A05003 (N) Power unit: Electronics board overtemperature

Reaction: NONE

Acknowledge: NONE

Cause: The alarm threshold for the overtemperature of the electronics module has been reached. The response is set using p0290.
If the temperature of the electronics module increases by an additional 5 K, then fault F30036 is initiated.

Remedy: Check the following:
- is the ambient temperature within the defined limit values?
- has the fan failed? Check the direction of rotation.

Reaction upon N: NONE
Acknowledge upon N: NONE

A05004 (N) Power unit: Rectifier overtemperature

Reaction: NONE

Acknowledge: NONE

Cause: The alarm threshold for the overtemperature of the rectifier has been reached. The response is set using p0290.
If the temperature of the rectifier increases by an additional 5 K, then fault F30037 is initiated.

Remedy: Check the following:
- is the ambient temperature within the defined limit values?
- have the load conditions and the load duty cycle been appropriately dimensioned?
- has the fan failed? Check the direction of rotation.
- has a phase of the line supply failed?
- is an arm of the supply (incoming) rectifier defective?

Reaction upon N: NONE
 Acknowledge upon N: NONE

A05005 Cooling system: Cooling medium flow rate too low

Reaction: NONE
Acknowledge: NONE
Cause: Cooling system: Alarm - flow rate has fallen below the alarm value
Remedy:

F05050 Parallel circuit: Pulse enable in spite of pulse inhibit

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 VECTOR: OFF2 (NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY
Cause: A power unit signals that the pulses are enabled although the pulses are inhibited.
 Fault value (r0949, decimal):
 Number of the power unit involved.
Remedy: The power unit is defective and must be replaced.

F05051 Parallel circuit: Power unit pulse enable missing

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 VECTOR: OFF2 (NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY
Cause: For one or several power units, the pulses were not able to be enabled.
 Fault value (r0949, decimal):
 Number of the power unit involved.
Remedy: - acknowledge power unit faults that are still present.
 - inhibit the pulses of the power unit involved (p7001).

A05052 (F) Parallel circuit: Impermissible current dissymmetry

Reaction: NONE
Acknowledge: NONE
Cause: The deviation of the individual currents of the power units exceeds the alarm threshold specified in p7010.
 Alarm value (r2124, decimal):
 1: Phase U.
 2: Phase V.
 3: Phase W.
Remedy: - inhibit the pulses of the faulted power unit (p7001).
 - check the connecting cables. Loose contacts can cause current spikes.
 - the motor reactors are non-symmetrical or faulty and must be replaced.
 - the CTs must be calibrated or replaced.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY

A05053 (F) Parallel circuit: Inadmissible DC link voltage dissymmetry

Reaction: NONE
Acknowledge: NONE
Cause: The deviation of the DC link voltage measured values exceeds the alarm threshold specified in p7011.
Remedy: - inhibit the pulses of the faulted power unit (p7001).
 - check the DC link connecting cables.
 - the DC link voltage measurement is incorrect and must be calibrated or renewed.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY

A05054	Parallel circuit: Power unit de-activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	For the drive object involved, fewer power unit components connected in parallel are active than exist in the target topology. Operation is only possible at reduced power (power de-rating).
Remedy:	Re-activate the de-activated power unit components. See also: p0125 (Activate/de-activate power unit components), p0895 (Activate/de-activate power unit components), p0897 (Parking axis selection)
F05055	Power circuit: Power units with different code numbers
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The code numbers of the power units do not match. Fault value (r0949, decimal): Parameter in which the first different power unit code number was detected.
Remedy:	For parallel circuit configurations, only power units with identical power unit data may be used.
F05056	Parallel circuit: Power unit EPROM versions differ
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The EEPROM versions of the power units do not match. Fault value (r0949, decimal): Parameter in which the first different version number was detected.
Remedy:	For parallel circuit configurations, only power units with identical EEPROM versions may be used.
F05057	Parallel circuit: Power unit firmware versions differ
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The firmware versions of the power units connected in parallel do not match. Fault value (r0949, decimal): Parameter in which the first different version number was detected.
Remedy:	For parallel circuit configurations, only power units with identical firmware versions may be used.
F05058	Parallel circuit: VSM EEPROM versions differ
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The EEPROM versions of the Voltage Sensing Modules (VSM) do not match. Fault value (r0949, decimal): Parameter in which the first different version number was detected.
Remedy:	For parallel circuit configurations, only Voltage Sensing Modules (VSM) with identical EEPROM versions may be used.
F05059	Parallel circuit: VSM firmware versions differ
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The firmware versions of the Voltage Sensing Modules (VSM) do not match. Fault value (r0949, decimal): Parameter in which the first different version number was detected.
Remedy:	For parallel circuit configurations, only Voltage Sensing Modules (VSM) with identical firmware versions may be used.
F05060	Parallel circuit: Power unit firmware version does not match
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Firmware from version V02.30.01.00 is required when connecting the power units in parallel.
Remedy:	Update the firmware of the power units (at least V02.30.01.00).

F05061	Infeed, number of VSM
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The number of active Voltage Sensing Modules (VSM) for the drive object infeed with chassis power units is not correct. For A_Infeed, each active power unit must be assigned an active VSM also for a parallel circuit configuration. For S_Infeed, the active drive object, must be assigned at least one active VSM. Fault value (r0949, decimal): Number of VSMs that are currently assigned to the drive object.
Remedy:	Adapts the number of active Voltage Sensing Modules (VSM).
F06000	Infeed: Precharging monitoring time expired
Reaction:	OFF2 (OFF1)
Acknowledge:	IMMEDIATELY
Cause:	After the line contactor closes the power unit does not signal the READY state within the monitoring time (p0857). The end of the DC link pre-charging was not detected due to one of the following reasons: - there is not line supply voltage. - the line contactor is not closed. - the line supply voltage is too low. - the power unit has detected an internal fault. - there is a DC link short-circuit. - the DC link has a ground fault. - the pre-charging resistors are overheated as there were too many pre-charging operations per time unit. - the pre-charging resistors are overheated as the DC link capacitance is too high (max. 20 mF). - line supply voltage incorrectly set. See also: p0857 (Power unit monitoring time)
Remedy:	- check the line supply voltage - check or energize the line contactor. - check and if required increase the monitoring time p0857. - if relevant, carefully note additional power unit fault messages. - check the DC link regarding short-circuit or ground fault. - wait until the pre-charging resistors have cooled down. - reduce the DC link capacitance by removing the power units or supplementary modules. - check the line supply voltage setting (p0210).
F06010	Infeed: Power unit EP 24 V missing in operation
Reaction:	OFF2 (OFF1)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	In operation, withdraw the pulse enable at terminal EP at the Line Module (X21.3, X21.4).
Remedy:	- do not open the line breaker in operation - only when the pulses are inhibited. - check the wiring of the DP input (X21.3, X21.4) at the Line Module to exclude any poor contacts.
F06050	Infeed: Smart Mode not supported
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The power unit does not support the Smart Mode.
Remedy:	- set the sampling time p0115[0] >= 250 µs by setting the pre-setting (default) of the sampling time (p0112) to the factory setting. - de-activate the Smart Mode with p3400 and supply voltage p0210 <= 415 V. - upgrade the power unit software and/or hardware for the smart mode (r0192). See also: r0192 (Power unit firmware properties)

F06100 Infeed: Shutdown due to line supply undervoltage condition

Reaction: OFF2 (OFF1)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The filtered (steady-state) value of the line supply voltage is less than the fault threshold (p0283).
 Alarm condition: $V_{rms} < p0283 * p0210$.
 Fault value (r0949, floating point):
 Actual steady-state line supply voltage.
 See also: p0283 (Line supply undervoltage, shutdown (trip) threshold)
Remedy:
 - check the line supply.
 - check the line supply voltage (p0210).
 - check the fault threshold (p0283).

A06105 (F) Infeed: Line supply undervoltage

Reaction: NONE
Acknowledge: NONE
Cause: The filtered (steady-state) value of line supply voltage is lower than the alarm threshold (p0282).
 Alarm condition: $V_{rms} < p0282 * p0210$.
 Alarm value (r2124, floating point):
 Actual steady-state line supply voltage.
 See also: p0282 (Line supply undervoltage, alarm threshold)
Remedy:
 - check the line supply.
 - check the line supply voltage (p0210).
 - check the alarm threshold (p0282).
 Reaction upon F: NONE (OFF1, OFF2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

F06200 Infeed: Failure of one or several line phases

Reaction: OFF2 (OFF1)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: Failure of one or several line phases.
 The fault can be output in two operating states:
 1. During the power-on phase of the infeed unit.
 The measured line supply angle deviates from the regular characteristic for a 3-phase system - the PLL cannot be synchronized.
 The fault occurs immediately after power-up if, when operating with a VSM, the phase assignment L1, L2, L3 at the VSM differs from the phase assignment at the power unit.
 2. While the infeed is operational.
 After a voltage dip has been detected (A06205) in one or several line phases a fault occurred within 100 ms (also refer to other relevant messages).
 Probable causes of the fault:
 - voltage dip on the line side or phase phase failure lasting longer than 10 ms.
 - overload condition on the load side with peak current.
 - commutating reactor missing.
Remedy:
 - check the line supply and fuses.
 - check the connection and size (rating) of the line commutating reactor.
 - check and correct the phase assignment at the VSM and at the power unit.
 - check the load.
 See also: p3463 (Infeed, line angle change, phase failure detection)

A06205 (F)	Infeed: Voltage dip in at least one line supply phase
Reaction:	NONE
Acknowledge:	NONE
Cause:	Voltage dip or overvoltage in one or several line supply phases has been detected in operation. The pulses are then cancelled for 10 ms. The operating signal of the infeed unit in r0863.0 remains and the pulse inhibit due to the phase failure is displayed in r3405.2. Alarm value (r2124, decimal): Internal fault type of the line angle characteristic.
Remedy:	- check the line supply and fuses. - check the line supply quality and system fault level. - check the load. See also: r3405 (Status word infeed), p3463 (Infeed, line angle change, phase failure detection)
Reaction upon F:	NONE (OFF1, OFF2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)
F06210	Infeed: Summed current too high
Reaction:	OFF2 (OFF1)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	Smoothed sum of the phase currents ($i_1 + i_2 + i_3$) greater than 4 % of the maximum power unit current (r0209). Possible causes: - the DC link has a ground fault that results in a high summed current (r0069.6). The DC component in the line currents can damage/destroy the power unit, commutating reactor or line filter! - the zero point calibration of the current measurement was not carried-out (p3491, A06602). - defective current measurement in the power unit. Fault value (r0949, floating point): Smoothed sum of the phase currents.
Remedy:	- check the DC link for a low-ohmic or high-ohmic ground fault and if one is present, remove. - increase the monitoring time of the current-offset measurement (p3491). - if required, replace the power unit.
A06215 (F)	Infeed: Summed current high
Reaction:	NONE
Acknowledge:	NONE
Cause:	Smoothed sum of the phase currents ($i_1 + i_2 + i_3$) greater than 3 % of the maximum power unit current (r0209). Possible causes: - the DC link has a ground fault that results in a high summed current (r0069.6). The DC component in the line currents can damage/destroy the power unit, commutating reactor or line filter! - the zero point calibration of the current measurement was not carried-out (p3491, A06602). - defective current measurement in the power unit. Alarm value (r2124, floating point): Smoothed sum of the phase currents.
Remedy:	- check the DC link for a low-ohmic or high-ohmic ground fault and if one is present, remove. - increase the monitoring time of the current-offset measurement (p3491). - if required, replace the power unit.
Reaction upon F:	NONE (OFF1, OFF2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)

A06250 (F)	Infeed: Defective capacitor(s) in at least one phase of line filter
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>A change in the line filter capacitance was detected in at least line phase. The voltages and phase currents of the line filter, measured using a Voltage Sensing Module (VSM), indicated a deviation of the filter capacitances from the value parameterized in p0221. A change or a defect of the line filter capacitors results in a shift of the resonant frequencies and can result in severe damage to the drive system. Alarm value (r2124, floating point): The calculated actual capacitance in μF (rounded-off to an integer number). The 1st decimal point specifies the number of the phase (1, 2, 3) where the capacitance deviates from the specified value.</p>
Remedy:	<ul style="list-style-type: none"> - check the parameterized value of the filter capacitance (p0221). - check the correct wiring of the Voltage Sensing Module (VSM): Differential voltages u12 and u23 must be present at the 100 V/690 V inputs of the VSM; the phase currents of the line filter must be connected to the 10 V inputs through a current - voltage converter. - check the alarm limits for the permissible filter capacitance deviation (p3676). - check the normalization of the line supply voltage measurement using the VSM (p3660). - check the normalization of the filter current measurement using the VSM (p3670). - check the line filter capacitors and if required, replace the line filter. <p>See also: p0221 (Infeed filter capacitance), p3660 (VSM input line supply voltage, voltage scaler), p3670 (VSM 10 V input CT gain), p3676 (VSM line filter capacitance alarm threshold)</p>
Reaction upon F:	NONE (OFF1, OFF2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)

F06300	Infeed: Line voltage too high at power on
Reaction:	OFF2 (NONE, OFF1)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>The RMS line supply voltage V_{rms} was so high when powering-up that controlled operation is not possible without exceeding the permissible maximum voltage in the DC link (p0280). Fault condition: $V_{\text{rms}} * 1.5 > p0280$. Fault value (r0949, floating point): Lowest possible controlled DC link voltage for the line supply voltage presently connected. See also: p0280 (DC link voltage maximum steady-state)</p>
Remedy:	<ul style="list-style-type: none"> - check the line supply voltage - check the maximum DC link voltage and if required, increase (p0280). - check the line supply voltage and compare with the actual line supply voltage (p0210). - check whether the power unit is dimensioned for the line supply voltage actually being used. <p>See also: p0210 (Drive unit line supply voltage), p0280 (DC link voltage maximum steady-state)</p>

A06301 (F)	Infeed: Line supply overvoltage
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The filtered (steady-state) value of the rms line supply voltage V_{rms} is higher than the alarm threshold (p0281). Alarm condition: $V_{\text{rms}} > p0281 * p0210$. Alarm value (r2124, floating point): Actual steady-state line supply voltage. See also: p0281 (Line supply overvoltage, warning threshold)</p>
Remedy:	<ul style="list-style-type: none"> - check the line supply. - check the line supply voltage (p0210). - check the alarm threshold (p0281). <p>See also: p0210 (Drive unit line supply voltage), p0281 (Line supply overvoltage, warning threshold)</p>
Reaction upon F:	NONE (OFF1, OFF2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)

F06310 (A) Infeed: Supply voltage (p0210) incorrectly parameterized

Reaction: NONE (OFF1, OFF2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: After pre-charging was completed, the line supply voltage V_{rms} was calculated using the measured DC link voltage. This voltage V_{rms} is not within the tolerance range of the supply voltage.
 The following applies for the tolerance range: $85\% * p0210 < V_{rms} < 110\% * p0210$.
 Alarm value (r2124, floating point):
 Line supply voltage V_{rms} present.
 See also: p0210 (Drive unit line supply voltage)
Remedy: - check the parameterized supply voltage and if required change (p0210).
 - check the line supply voltage.
 See also: p0210 (Drive unit line supply voltage)
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A06350 (F) Infeed: Measured line frequency too high

Reaction: NONE
Acknowledge: NONE
Cause: The actual line frequency f_{line} is higher than the parameterized alarm threshold ($f_{line} > p0211 * p0284$).
 The alarm can be output in two operating states:
 1. During the power-on phase of the infeed unit.
 Consequence:
 Synchronization of the infeed to the line supply is interrupted and is restarted.
 2. While the infeed is operational.
 Consequence:
 The infeed remains in the operating (run) state and alarm A6350 is output. This signifies a critical operational fault.
 Alarm value (r2124, floating point):
 Actual line frequency determined.
 See also: p0284 (Line supply frequency exceeded, alarm threshold)
Remedy: - check the parameterized line frequency and if required change (p0211).
 - check the alarm threshold (p0284).
 - check the line supply.
 - check the line supply quality.
 See also: p0211 (Rated line freq), p0284 (Line supply frequency exceeded, alarm threshold)
 Reaction upon F: NONE (OFF1, OFF2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

A06351 (F) Infeed: Measured line frequency too low

Reaction: NONE
Acknowledge: NONE
Cause: The actual line frequency f_{line} is lower than the parameterized alarm threshold ($f_{line} < p0211 * p0285$).
 The alarm can be output in two operating states:
 1. During the power-on phase of the infeed unit.
 Consequence:
 Synchronization of the infeed to the line supply is interrupted and is restarted.
 2. While the infeed is operational.
 Consequence:
 The infeed remains in the operating (run) state and alarm A06351 is output. This signifies a critical operational fault.
 Alarm value (r2124, floating point):
 Actual line frequency determined.
 See also: p0285 (Line supply frequency fallen below, alarm threshold)
Remedy: - check the parameterized line frequency and if required change (p0211).
 - check the alarm threshold (p0285).
 - check the line supply.
 - check the line supply quality.
 See also: p0211 (Rated line freq), p0285 (Line supply frequency fallen below, alarm threshold)

Reaction upon F: NONE (OFF1, OFF2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

A06400 Infeed: Line supply data identification selected/active

Reaction: NONE
Acknowledge: NONE
Cause: The line supply data identification is selected and active.
 The line inductance and the DC link capacitance are measured at the next pulse enable.
 SM150: The Active Line Module is synchronized the next time that the pulses are enabled and the identification mode, selected in p3410 is carried-out or the identification mode, displayed in r6442 is presently active. The INFEED_READY signal is not generated.
 See also: p3410 (Infeed identification method)
Remedy: No remedial action required.

F06500 Infeed: Line synchronization not possible

Reaction: OFF2 (OFF1)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The line synchronization is not possible within the monitoring time.
 The infeed was re-synchronized to the line supply because it was interrupted due to a line frequency that was determined to be either too low or too high.
 After 20 attempts, synchronization - and therefore also the power-on operation - were interrupted.
Remedy:
 - check the parameterized line frequency and if required change (p0211).
 - check the fault thresholds (p0284, p0285).
 - check the line supply.
 - check the line supply quality.
 See also: p0211 (Rated line freq), p0284 (Line supply frequency exceeded, alarm threshold), p0285 (Line supply frequency fallen below, alarm threshold)

A06601 (F) Infeed: Current offset measurement interrupted

Reaction: NONE
Acknowledge: NONE
Cause: Defective current measurement or a DC current is present during the offset measurement.
 Alarm value (r2124, decimal):
 1: Excessively high phase current has occurred during the current-offset calibration.
 2: The measured current - offset is greater than the 3% of the maximum permissible converter current (e.g. due to a ground fault in the DC link).
Remedy:
 Re alarm value = 1:
 - possible counter-measure if there is no line contactor: Power-up an adequately long time before OFF1 = 1.
 Re alarm value = 2:
 - defective current measurement or a DC current is present during the offset measurement.
 - check the DC link for a ground fault.
 Reaction upon F: NONE (OFF1, OFF2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

A06602 (F) Infeed: Current offset measurement not possible

Reaction: NONE
Acknowledge: NONE
Cause: After an OFF1 = 1 no valid current offset measurement was able to be made within the monitoring time (p3491) before closing the line contactor. The current offset is set to 0.
 See also: p3491 (Infeed I-offset measurement monitoring time)
Remedy:
 - check the DC link for a ground fault. A ground fault can destroy parts and components!
 - Check the monitoring time setting and if required increase (p3491). At least 100 ms is required for a valid measurement (p3491 > 100 ms).
 Notice:
 If there is no valid measurement, then under certain circumstances the quality of the DC link control will be reduced.
 See also: p3491 (Infeed I-offset measurement monitoring time)

Reaction upon F: NONE (OFF1, OFF2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

F06700 (A) Infeed: Switch line contactor for load condition
Reaction: NONE (OFF2)
Acknowledge: IMMEDIATELY
Cause: For an on command, the infeed line contactor should be switched under load.
Remedy: - do not load the DC link if the infeed has not issued an operating signal (r0863.0 = 1).
 - after the infeed has been powered-down, all power units connected to the DC link should be powered-down. To realize this, the operating signal of the infeed (r0863.0) must be suitable interconnected.

Reaction upon A: NONE
 Acknowledge upon A: NONE

A06800 (F) Infeed: Maximum steady-state DC link voltage reached
Reaction: NONE
Acknowledge: NONE
Cause: The DC link voltage setpoint has reached the maximum steady-state voltage parameterized in p0280. The DC link voltage is increased by the modulation depth reserve controller for the following reasons:
 - modulation depth reserve is too low (p3480).
 - line supply voltage is too high.
 - supply voltage (p0210) parameterized to be too low.
 - excessively high setpoint for the reactive line current.
Remedy: - check the line supply voltage setting (p0210).
 - check the line supply for an overvoltage condition.
 - reduce the modulation depth reserve (p3480).
 - reduce the reactive current setpoint.
 See also: p0210 (Drive unit line supply voltage), p0280 (DC link voltage maximum steady-state), p3480 (Infeed modulation depth limit)

Reaction upon F: NONE (OFF1, OFF2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

A06900 (F) Braking Module: Fault (1 -> 0)
Reaction: NONE
Acknowledge: NONE
Cause: The Braking Module signals "Fault (1 -> 0)" via terminal X21.4. This signal is interconnected via binector input BI: p3866[0...7]. See also: p3866 (Braking Module fault)
Remedy: - reduce the number of braking operations.
 - check binector input BI: p3866[0...7] and the wiring to terminal X21.4 of the particular braking module.

Reaction upon F: NONE (OFF2)
 Acknowledge upon F: IMMEDIATELY

A06901 Braking Module: Pre-alarm I*t shutdown
Reaction: NONE
Acknowledge: NONE
Cause: The Braking Module signals "Pre-alarm I*t shutdown" via terminal X21.3. This signal is interconnected via binector input p3865[0...7]. The pre-alarm I*t shutdown is only possible for Braking Modules, "booksize" type, "chassis" devices do not support this function.
Remedy: - reduce the number of braking operations.
 - check binector input BI: p3865[0...7] and the wiring to terminal X21.3 of the particular Braking Module.

F07011	Drive: Motor overtemperature
Reaction:	OFF2 (NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	<p>KTY: The motor temperature has exceeded the fault threshold (p0605) or the timer stage (p0606) after the alarm threshold was exceeded (p0604) has expired.</p> <p>VECTOR: The response parameterized in p0610 becomes active.</p> <p>PTC: The response threshold of 1650 Ohm was exceeded and the timer stage (p0606) has expired.</p> <p>VECTOR: The response parameterized in p0610 becomes active.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - motor is overloaded. - motor ambient temperature too high. - wire breakage or sensor not connected <p>Fault value (r0949, decimal), if SME is selected in p0601 (p0601=10): The number specifies the sensor channel that resulted in the alarm being output.</p> <p>See also: p0604 (Motor overtemperature alarm threshold), p0605 (Motor overtemperature fault threshold), p0606 (Motor overtemperature timer), p0610 (Response to motor overtemperature condition)</p>
Remedy:	<ul style="list-style-type: none"> - reduce the motor load. - check the ambient temperature. - check the wiring and sensor connector. <p>See also: p0604 (Motor overtemperature alarm threshold), p0605 (Motor overtemperature fault threshold), p0606 (Motor overtemperature timer)</p>
A07015	Drive: Motor temperature sensor alarm
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>An error was detected when evaluating the temperature sensor set in p0600 and p0601.</p> <p>With the fault, the time in p0607 is started. If the fault is still present after this time has expired, then fault F07016 is output; however, at the earliest, 1 s after alarm A07015.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - wire breakage or sensor not connected (KTY: R > 1630 Ohm). - measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm). <p>Alarm value (r2124, decimal), if SME is selected in p0601 (p0601=10): The number specifies the sensor channel that resulted in the alarm being output.</p>
Remedy:	<ul style="list-style-type: none"> - check that the sensor is connected correctly. - check the parameterization (p0600, p0601). <p>See also: r0035 (Motor temperature), p0600 (Motor temperature sensor for monitoring), p0601 (Motor temperature sensor type), p0607 (Temperature sensor fault timer)</p>
F07016	Drive: Motor temperature sensor fault
Reaction:	OFF1 (NONE, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	<p>An error was detected when evaluating the temperature sensor set in p0600 and p0601.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - wire breakage or sensor not connected (KTY: R > 1630 Ohm). - measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm). <p>Note: If alarm A07015 is present, the time in p0607 is started. If the fault is still present after this time has expired, then fault F07016 is output; however, at the earliest, 1 s after alarm A07015.</p> <p>Fault value (r0949, decimal), if SME is selected in p0601 (p0601=10): The number specifies the sensor channel that resulted in the alarm being output.</p> <p>See also: p0607 (Temperature sensor fault timer)</p>
Remedy:	<ul style="list-style-type: none"> - check that the sensor is connected correctly. - check the parameterization (p0600, p0601). - induction motors: De-activate temperature sensor fault (p0607 = 0). <p>See also: r0035 (Motor temperature), p0600 (Motor temperature sensor for monitoring), p0601 (Motor temperature sensor type), p0607 (Temperature sensor fault timer)</p>

F07080	Drive: Incorrect control parameter
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>The closed-loop control parameters have been parameterized incorrectly (e.g. p0356 = L_spread = 0). Fault value (r0949, decimal): The fault value includes the parameter number involved. The following parameter numbers only occur as fault values for vector drives: p0310, for synchronous motors: p0341, p0344, p0350, p0357 The following parameter numbers do not occur as fault values for synchronous motors: p0354, p0358, p0360 See also: p0310 (Rated motor frequency), p0311 (Rated motor speed), p0341 (Motor moment of inertia), p0344 (Motor weight), p0350 (Motor stator resistance, cold), p0354 (Motor rotor resistance cold / damping resistance d axis), p0356 (Motor stator leakage inductance), p0357 (Motor stator inductance, d axis), p0358 (Motor rotor leakage inductance / damping inductance, d axis), p0360 (Motor magnetizing inductance/magn. inductance, d axis saturated), p0400 (Enc type selection), p0640 (Current limit), p1082 (Maximum speed), p1300 (Open-loop/closed-loop control operating mode)</p>
Remedy:	<p>Modify the parameter indicated in the fault value (r0949) (e.g. p0640 = current limit > 0). See also: p0311 (Rated motor speed), p0341 (Motor moment of inertia), p0344 (Motor weight), p0350 (Motor stator resistance, cold), p0354 (Motor rotor resistance cold / damping resistance d axis), p0356 (Motor stator leakage inductance), p0358 (Motor rotor leakage inductance / damping inductance, d axis), p0360 (Motor magnetizing inductance/magn. inductance, d axis saturated), p0400 (Enc type selection), p0640 (Current limit), p1082 (Maximum speed)</p>
F07082	Macro: Execution not possible
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>The macro cannot be executed. Fault value (r0949, interpret hexadecimal): The fault code is in byte 1, possibly supplementary information is in byte 2 and the high word contains the parameter number involved if this is available. Fault codes: Fault for the trigger parameter itself: -20: Called file is not valid for parameter 15. -21: Called file is not valid for parameter 700. -22: Called file is not valid for parameter 1000. -23: Called file is not valid for parameter 1500. -24: Data type of a TAG is incorrect (e.g.: Index, number or bit is not U16). Faults for the parameters to be set: -25: Error level has an undefined value. -26: Mode has an undefined value. -27: A value was entered as string in the tag value that is not "DEFAULT". -31: Entered drive object type unknown. -32: A device was not able to be found for the determined drive object number. -34: A trigger parameter was recursively called. -35: It is not permissible to write to the parameter via macro. -36: Check, writing to a parameter unsuccessful, parameter can only be read, not available, incorrect data type, value range or assignment incorrect. -37: Source parameter for a BICO interconnection was not able to be determined. -38: An index was set for a non-indexed parameter. -39: No index was set for an indexed parameter. -41: A bit operation is only permissible for parameters with the parameter format DISPLAY_BIN. -42: A value not equal to 0 or 1 was set for a BitOperation. -43: Reading the parameter to be changed by the BitOperation was unsuccessful. -51: Factory setting for DEVICE may only be executed on the DEVICE. -61: The setting of a value was unsuccessful.</p>
Remedy:	<p>- check the parameter involved. - check the macro file and BICO interconnection. See also: p0015 (Macro drive unit), p0700 (Macro Binector Input (BI)), p1000 (Macro Connector Inputs (CI) for speed setpoints), p1500 (Macro Connector Inputs (CI) for torque setpoints)</p>

F07083	Macro: ACX file not found
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The ACX file (macro) to be executed was not able to be found in the appropriate directory. Fault value (r0949, decimal): Parameter number with which the execution was started. See also: p0015 (Macro drive unit), p0700 (Macro Binector Input (BI)), p1000 (Macro Connector Inputs (CI) for speed setpoints), p1500 (Macro Connector Inputs (CI) for torque setpoints)
Remedy:	- check whether the file is saved in the appropriate directory on the CompactFlash card. Example: If p0015 is set to 1501, then the selected ACX file must be located in the following directory: ... /PMACROS/DEVICE/P15/PM001501.ACX
F07084	Macro: Condition for WaitUntil not fulfilled
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The wait condition set in the macro was not fulfilled in a certain number of attempts. Fault value (r0949, decimal): Parameter number for which the condition was set.
Remedy:	Check and correct the conditions for the WaitUntil loop.
F07085	Drive: Open-loop/closed-loop control parameters changed
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	Parameters of the open-loop/closed-loop control had to be changed as they exceeded dynamic limits as a result of other parameters. Fault value (r0949, decimal): The fault value includes the modified parameter number. See also: p0640 (Current limit), p1082 (Maximum speed), p1300 (Open-loop/closed-loop control operating mode), p1800 (Pulse frequency)
Remedy:	It is not necessary to change the parameters as they have already been correctly limited.
F07086	Units changeover: Calculating parameter values after an int. system ref. value change unsuccessful
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A reference parameter was changed in the system. This resulted in the fact that for the parameter involved, the selected value was not able to be written in the per unit notation (cause, e.g. the minimum or maximum limit was violated). The value of this parameter was set to default. Fault value (r0949, parameter): Parameter involved that was not able to be recalculated. See also: p0304 (Rated motor voltage), p0305 (Rated motor current), p0310 (Rated motor frequency), p0596 (Reference quantity, technological units), p2000 (Reference frequency), p2001 (Reference voltage), p2002 (Reference current), p2003 (Reference torque), r2004 (Reference power)
Remedy:	Check, and if required, correct the adapted parameter value. See also: p0304 (Rated motor voltage), p0305 (Rated motor current), p0310 (Rated motor frequency), p0596 (Reference quantity, technological units), p2000 (Reference frequency), p2001 (Reference voltage), p2002 (Reference current), p2003 (Reference torque), r2004 (Reference power)
F07090	Drive: Upper torque limit less than the lower torque limit
Reaction:	OFF2 (NONE, OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The upper torque limit is lower than the lower torque limit.
Remedy:	P1 must be >= P2 if parameter P1 is connected to p1522 and parameter P2 to p1523.

F07100	Drive: Sampling times cannot be reset
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	When resetting drive parameter (p0976) sampling times cannot be reset using p0111, p0112, p0115. Fault value (r0949, decimal): Parameter whose setting prevents the sampling times being reset. See also: r0110 (DRIVE-CLiQ basis sampling times)
Remedy:	- continue to work with the set sampling times. - before resetting the drive parameters, set the basic clock cycle p0110[0] to the original value. See also: r0110 (DRIVE-CLiQ basis sampling times)
F07110	Drive: Sampling times and basic clock cycle do not match
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The parameterized sampling times do not match the basic clock cycle. Fault value (r0949, decimal): The fault value specifies the parameter involved. See also: r0110 (DRIVE-CLiQ basis sampling times), r0111 (DRIVE-CLiQ basis sampling time selection), p0115 (Sampling time for supplementary functions)
Remedy:	Enter the current controller sampling times so that they are identical to the basic clock cycle, e.g. by selecting p0112. Note which basic clock cycle is selected in p0111. The sampling times in p0115 can only be changed manually in the sampling times preset "Expert" (p0112). See also: r0110 (DRIVE-CLiQ basis sampling times), r0111 (DRIVE-CLiQ basis sampling time selection), p0112 (Sampling times pre-setting p0115), p0115 (Sampling time for supplementary functions)
A07200	Drive: Master control ON/OFF1 command present
Reaction:	NONE
Acknowledge:	NONE
Cause:	The ON/OFF1 command is not 0, either via binector input p0840 (current CDS) or in control word p3982 bit 0.
Remedy:	The signal at binector input p0840 (actual CDS) as well as p3982 bit 0 must be 0.
F07210	Master control PC/AOP inhibited
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The transfer of master control is disabled via binector input p3985.
Remedy:	Change the signal via binector input p3985.
F07220 (N, A)	Drive: Control by PLC missing
Reaction:	A_INFEED: OFF1 (NONE, OFF2) SERVO: OFF1 (NONE, OFF2, OFF3, STOP1, STOP2) VECTOR: OFF1 (NONE, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	The "control by PLC" signal was missing in operation. - interconnection of the binector input for "control by PLC" is incorrect (p0854). - the higher-level control has withdrawn the "control by PLC" signal. - data transfer via the fieldbus (master - drive) was interrupted.
Remedy:	- check the interconnection of the binector input for "control by PLC" (p0854). - check the "control by PLC" signal and, if required, switch-in. - check the data transfer via the fieldbus (master - drive). Note: If the drive should continue to operate after withdrawing "control by PLC" then fault response must be parameterized to NONE or the message type should be parameterized as alarm.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F07300 (A) Drive: Line contactor feedback signal missing
Reaction: OFF2 (NONE)
Acknowledge: IMMEDIATELY
Cause:

- the line contactor was not able to be closed within the time in p0861.
- the line contactor was not able to be opened within the time in p0861.
- the line contactor has dropped-out in operation.
- the line contactor has closed although the drive converter is powered-down.

Remedy:

- check the setting of p0860.
- check the feedback circuit from the line contactor.
- increase the monitoring time in p0861.

 See also: p0860 (Line cont. fdbk sig), p0861 (Line contactor monitoring time)
Reaction upon A: NONE
Acknowledge upon A: NONE

F07311 Bypass motor switch
Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause:
 Fault value: Bit field BYPASS_CONTACTOR_ERROR_STATE
 Bit 1
 BYPASS_CONTACTOR_ERR_FBK_ON_MISSING
 Switch "closed" feedback signal missing
 Bit 2
 BYPASS_CONTACTOR_ERR_FBK_OFF_MISSING
 Switch "opened" feedback signal missing
 Bit 3
 BYPASS_CONTACTOR_ERR_TOO_SLOW
 Switch feedback signal too slow:
 After switching, the system waits for the positive feedback signal. If the feedback signal is received later than the specified time, then a fault trip (shutdown) is issued.
 Bit 6
 BYPASS_CONTACTOR_ERR_BYPASS_INCONSISTENCY
 Drive switch feedback signal is not consistent with the bypass state:
 When powering-up or for STAGING, the drive switch is closed.
 See also: p1260 (Bypass configuration), r1261 (Bypass control/status word), p1266 (Bypass, control command), p1267 (Bypass changeover source configuration), p1269 (Bypass switch feedback signal), p1274 (Bypass switch monitoring time)
Remedy:

- check the transfer of the feedback signal.
- check the switch

F07312 Bypass line supply switch
Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause:
 Fault value: Bit field BYPASS_CONTACTOR_ERROR_STATE
 Bit 1
 BYPASS_CONTACTOR_ERR_FBK_ON_MISSING
 Switch "closed" feedback signal missing
 Bit 2
 BYPASS_CONTACTOR_ERR_FBK_OFF_MISSING
 Switch "opened" feedback signal missing
 Bit 3
 BYPASS_CONTACTOR_ERR_TOO_SLOW
 Switch feedback signal too slow:
 After switching, the system waits for the positive feedback signal. If the feedback signal is received later than the specified time, then a fault trip (shutdown) is issued.
 Bit 6
 BYPASS_CONTACTOR_ERR_BYPASS_INCONSISTENCY

Line switch feedback signal is not consistent with the bypass state:

When powering-up or for STAGING, the line switch is closed without this having been requested from the bypass. See also: p1260 (Bypass configuration), r1261 (Bypass control/status word), p1266 (Bypass, control command), p1267 (Bypass changeover source configuration), p1269 (Bypass switch feedback signal), p1274 (Bypass switch monitoring time)

Remedy:

- check the transfer of the feedback signal.
- check the switch

F07320 Drive: Automatic restart interrupted

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause:

- The specified number of restart attempts (p1211) has been completely used up because within the monitoring time p1213 the alarms were not able to be acknowledged. The number of restart attempts (p1211) is decremented at each new start attempt.
- there is no active ON command.
- the monitoring time for the power unit (p0857) has expired.
- when exiting commissioning or at the end of the motor identification routine or the speed controller optimization, the drive unit is not automatically powered-up again.

Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy:

- increase the number of restart attempts (p1211). The actual number of starting attempts is displayed in r1214.
- increase the delay time in p1212 and/or the monitoring time in p1213.
- issue an ON command (p0840).
- either increase or disable the monitoring time of the power unit (p0857).

A07321 Drive: Automatic restart active

Reaction: NONE

Acknowledge: NONE

Cause: The automatic restart (AR) is active. When the line supply returns and/or the causes of the existing faults are removed the drive is automatically restarted. The pulses are enabled and the motor starts to rotate.

Remedy:

- the automatic restart (AR) should, if required, be inhibited (p1210 = 0).
- an automatic restart can be directly interrupted by withdrawing the power-on command (BI: p0840).

A07329 (N) Drive: kT estimator active without functioning compensation of the voltage emulation error

Reaction: NONE

Acknowledge: NONE

Cause: The kT estimator is active (p1780.3 = 1) without a functioning compensation of the voltage emulation error in the drive converter. This means that the accuracy is severely restricted.

Fault value (r0949, decimal):

- 1: The drive converter voltage emulation error, final value is 0 (p1952).
- 2: The drive converter voltage emulation error, current offset is 0 (p1953).
- 3: The compensation of the voltage emulation error is disabled (p1780.8 = 0).

Remedy:

Re fault value 1, 2:

- carry-out an identification of the voltage emulation error in the drive converter (p1909.14 = 1, p1910 = 1).
- set the parameter to compensation the voltage emulation error in the drive converter (p1952, p1953).

Re fault value 3:

- enable the compensation of the voltage emulation error in the drive converter (p1780.8 = 1).

Reaction upon N: NONE

Acknowledge upon N: NONE

F07330 Flying restart: Measured search current too low

Reaction: OFF2 (NONE, OFF1)

Acknowledge: IMMEDIATELY

Cause: During a flying restart, it was identified that the search current reached is too low. It is possible that the motor is not connected.

Remedy: Check the motor feeder cables.

F07331	FlyRestart: Not supported
Reaction:	OFF2 (NONE, OFF1)
Acknowledge:	IMMEDIATELY
Cause:	It is not possible to power-up with the motor rotating (no flying restart). In the following cases, the "flying restart" function is not supported: Permanent-magnet and separately-excited synchronous motors (PEM, FEM): Operation with U/f characteristic. Permanent-magnet synchronous motor (PEM): Sensorless operation without a Voltage Sensing Module (VSM) being connected.
Remedy:	<ul style="list-style-type: none">- de-activate the "flying restart" function (p1200 = 0).- change the open-loop/closed-loop control mode (p1300).- connect a Voltage Sensing Module (VSM) (voltage measurement).

A07350 (F)	Drive: Measuring probe parameterized to a digital output
Reaction:	NONE
Acknowledge:	NONE
Cause:	The measuring probe is connected to a bi-directional digital input/output and the terminal is set as output. Alarm value (r2124, decimal): 9: DI/DO 9 (X122.8) 10: DI/DO 10 (X122.10) 11: DI/DO 11 (X122.11) 13: DI/DO 13 (X132.8) 14: DI/DO 14 (X132.10) 15: DI/DO 15 (X132.11)
Remedy:	<ul style="list-style-type: none">- set the terminal as input (p0728).- de-select the measuring probe (p0488, p0489, p0580).
Reaction upon F:	OFF1
Acknowledge upon F:	IMMEDIATELY

A07400 (N)	Drive: DC link voltage maximum controller active
Reaction:	NONE
Acknowledge:	NONE
Cause:	The DC link voltage controller has been activated because the upper switch-in threshold has been exceeded (r1242). The ramp-down times are automatically increased in order to maintain the DC link voltage (r0026) within the permissible limits. There is a system deviation between the setpoint and actual speeds. When the DC link voltage controller is switched-out (disabled), this is the reason that the ramp-function generator output is set to the speed actual value. See also: p1240 (Vdc controller or Vdc monitoring configuration)
Remedy:	If the controller is not to intervene: <ul style="list-style-type: none">- increase the ramp-down times.- disable the Vdc max controller If the ramp-down times are not to be changed: <ul style="list-style-type: none">- use a chopper or regenerative feedback unit
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A07401 (N)	Drive: DC link voltage maximum controller de-activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	The Vdc_max controller can no longer maintain the DC link voltage (r0026) below the limit value (r1242) and was therefore switched-out (disabled). <ul style="list-style-type: none">- the line supply voltage is permanently higher than specified for the power unit.- the motor is permanently in the regenerative mode as a result of a load that is driving the motor.
Remedy:	<ul style="list-style-type: none">- check whether the input voltage is within the permissible range.- check whether the load duty cycle and load limits are within the permissible limits.

Reaction upon N: NONE
 Acknowledge upon N: NONE

A07402 (N) Drive: DC link voltage minimum controller active
Reaction: NONE
Acknowledge: NONE
Cause: The DC link voltage controller has been activated as the lower switch-in threshold has been fallen below (r1246). The kinetic energy of the motor is used in order to buffer the DC link. This brakes the drive. See also: p1240 (Vdc controller or Vdc monitoring configuration)
Remedy: The alarm disappears when power supply returns.
 Reaction upon N: NONE
 Acknowledge upon N: NONE

F07403 Drive: Lower DC link voltage threshold reached
Reaction: OFF1 (NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: The DC link voltage monitoring is active (p1240 = 2, 3) and the lower DC link voltage threshold (p1248) was reached in the "Operation" state.
Remedy:
 - check the line supply voltage.
 - check the infeed module
 - reduce the lower DC link threshold (p1248).
 - switch-out (disable) the DC link voltage monitoring (p1240 = 0).

F07404 Drive: Upper DC link voltage threshold reached
Reaction: OFF2 (NONE, OFF1, OFF3)
Acknowledge: IMMEDIATELY
Cause: The DC link voltage monitoring is active (p1240 = 1, 3) and the upper DC link voltage threshold (p1244) was reached in the "Operation" state.
Remedy:
 - check the line supply voltage.
 - check the infeed module or the Braking Module.
 - increase the upper DC link voltage threshold (p1244).
 - switch-out (disable) the DC link voltage monitoring (p1240 = 0).

F07405 (N, A) Drive: Kinetic buffering minimum speed not reached
Reaction: OFF2 (DCBRAKE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY
Cause: During kinetic buffering the speed fell below minimum speed (p1257) and the line supply did not return.
Remedy: Check the speed threshold for the Vdc_min controller (kinetic buffering) (p1257). See also: p1257 (Vdc_min controller speed threshold)
 Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F07406 (N, A) Drive: Kinetic buffering maximum time exceeded
Reaction: OFF3 (DCBRAKE, OFF1, OFF2, STOP1, STOP2)
Acknowledge: IMMEDIATELY
Cause: The maximum buffer time (p1255) has been exceeded but the line supply has not returned.
Remedy: Check the time threshold for Vdc-min controller (kinetic buffering) (p1255). See also: p1255 (Vdc_min controller time threshold)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

Reaction upon A: NONE
Acknowledge upon A: NONE

A07409 Drive: U/f control, current limiting controller active
Reaction: NONE
Acknowledge: NONE
Cause: The current limiting controller of the U/f control was activated because the current limit was exceeded.
Remedy: The alarm is automatically withdrawn when increasing the current limit (p0640), reducing the load or using a slower up ramp for the setpoint (reference) speed.

F07410 Drive: Current controller output limited
Reaction: OFF2 (NONE, OFF1)
Acknowledge: IMMEDIATELY
Cause: The condition " $I_{act} = 0$ and $U_{q_set_1}$ longer than 16 ms at its limit" is present and can be caused by the following:
- motor not connected or motor contactor open.
- no DC link voltage present.
- Motor Module defective.
- the "flying restart" function is not activated.
Remedy:
- connect the motor or check the motor contactor.
- check the DC link voltage (r0070).
- check the Motor Module.
- activate the "flying restart" function (p1200).

F07411 Drive: Flux controller output limited
Reaction: OFF2 (NONE, OFF1)
Acknowledge: IMMEDIATELY
Cause: The specified flux setpoint cannot be reached although 90% of the maximum current has been specified.
- incorrect motor data.
- motor data and motor configuration (star/delta) do not match.
- the current limit has been set too low for the motor.
- induction motor (sensorless, open-loop controlled) in I2t limiting.
- the Motor Module is too small.
Remedy:
- correct the motor data.
- check the motor configuration.
- correct the current limits (p0640, p0323).
- reduce the induction motor load.
- if required, use a larger Motor Module.

F07412 Drive: Commutation angle incorrect (motor model)
Reaction: ENCODER (NONE, OFF2)
Acknowledge: IMMEDIATELY
Cause: An incorrect commutation angle was detected, that can result in a positive coupling in the speed controller.
Servo:
Supplementary value 0: The comparison of the pole position angle from the encoder and the motor model resulted in an excessively high value ($> 80^\circ$ electrical).
Supplementary value 1: -
Vector:
Supplementary value 0: The comparison of the pole position angle from the encoder and the motor model resulted in an excessively high value ($> 45^\circ$ electrical).
Supplementary value 1: The change in the speed signal from the motor encoder has changed by $> P0492$ within a current controller clock cycle.

Possible causes:

- the motor encoder is incorrectly adjusted with respect to the magnet position.
- the motor encoder is damaged.
- the angular commutation offset is incorrectly set (p0431).
- data to calculate the motor model has been incorrectly set (p0356 (motor-stator leakage inductance) and/or p0350 (motor-stator resistance) and/or p0352 (cable resistance)).
- the changeover speed for the motor model is too low (p1752). The monitoring function only becomes effective above the changeover speed.
- the motor encoder speed signal is faulted.
- the control loop is instable due to incorrect parameterization.

Remedy:

- if the encoder mounting was changed - re-adjust the encoder.
- replace the defective motor encoder.
- correctly set the angular commutation offset (p0431).
- correctly set the motor stator leakage inductance, motor-stator resistance and cable resistance (p0356, p0350, p0352).
- increase the changeover speed for the motor model (p1752).

F07413 Drive: Commutation angle incorrect (pole position identification)

Reaction: ENCODER (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: An incorrect commutation angle was detected, that can result in a positive coupling in the speed controller.

- within the pole position identification routine (p1982 = 2):
A difference of > 45° electrical to the encoder angle was determined.
- for VECTOR, within the encoder adjustment (p1990 = 2):
A difference of > 6° electrical to the encoder angle was determined.

Remedy:

- correctly set the angular commutation offset (p0431).
- re-adjust the motor encoder after the encoder has been replaced.
- replace the defective motor encoder.
- check the pole position identification routine. If the pole position identification routine is not suitable for this motor type, then disable the plausibility check (p1982 = 0).

F07414 Drive: Encoder serial number changed

Reaction: ENCODER (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: The serial number of the motor encoder of a synchronous motor has changed. The change was only checked for encoders with serial number (e.g. EnDat encoders) and build-in motors (e.g. p300 = 401) or third-party motors (p0300 = 2).

Cause 1:

The motor with integrated and adjusted encoder was replaced.

Cause 2:

The encoder was replaced.

Cause 3:

A third-party, build-in or linear motor was re-commissioned.

Cause 4:

The firmware was updated to a version that checks the encoder serial number.

Remedy:

Re causes 1, 4:

Accept the new serial number with p0440 = 1.

Re causes 2, 3:

Carry-out an automatic adjustment using the pole position identification routine. First, accept the serial number with p0440 = 1. Acknowledge the fault. Initiate the pole position identification routine with p1990 = 1. Then check that the pole position identification routine is correctly executed.

SERVO: If a pole position identification technique is selected in p1980, and if p0301 does not contain a motor type with an encoder adjusted in the factory, then p1990 is automatically activated.

or

Set the adjustment using parameter p0431. In this case, the new serial number is automatically accepted.

or

Mechanically adjust the encoder. Accept the new serial number with p0440 = 1.

N07415 (F)	Drive: Angular commutation offset transfer running
Reaction:	OFF2
Acknowledge:	NONE
Cause:	The angular commutation offset was automatically determined using $p1990 = 1$. This fault causes the pulses to be cancelled - this is necessary to transfer the angular commutation offset to p0431. See also: p1990 (Angular commutation offset, commissioning support)
Remedy:	The fault can be acknowledged without any additional measures.
Reaction upon F:	OFF2
Acknowledge upon F:	IMMEDIATELY

F07420	Drive: Current setpoint filter natural frequency > Shannon frequency
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	One of the filter natural frequencies is greater than the Shannon frequency. The Shannon frequency is calculated according to the following formula: $0.5 / p0115[0]$ Fault value (r0949, interpret hexadecimal): Bit 0: Filter 1 (p1658, p1660) Bit 1: Filter 2 (p1663, p1665) Bit 2: Filter 3 (p1668, p1670) Bit 3: Filter 4 (p1673, p1675) Bit 8 ... 15: Data set number (starting from zero).
Remedy:	- reduce the numerator or denominator natural frequency of the current setpoint filter involved. - reduce the current controller sampling time (p0115[0]). - switch-out the filter involved (p1656).

F07421	Drive: Speed setpoint filter natural frequency > Shannon frequency
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	One of the filter natural frequencies is greater than the Shannon frequency. The Shannon frequency is calculated according to the following formula: $0.5 / p0115[1]$ Fault value (r0949, interpret hexadecimal): Bit 0: Filter 1 (p1417, p1419) Bit 1: Filter 2 (p1423, p1425) Bit 8 ... 15: Data set number (starting from zero).
Remedy:	- reduce the numerator or denominator natural frequency of the speed setpoint filter involved. - reduce the speed controller sampling time (p0115[1]). - switch-out the filter involved (p1414).

F07422	Drive: Reference model natural frequency > Shannon frequency
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The natural filter frequency of the PT2 element for the reference model (p1433) is greater than the Shannon frequency. The Shannon frequency is calculated according to the following formula: $0.5 / p0115[1]$
Remedy:	- reduce the natural frequency of PT2 element for reference model (p1433). - reduce the speed controller sampling time (p0115[1]).

F07423	Drive: APC filter natural frequency > Shannon frequency
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	One of the filter natural frequencies is greater than the Shannon frequency. The Shannon frequency is calculated according to the following formula: $0.5 / (p0115[1] * x)$ Fault value (r0949, interpret hexadecimal): Bit 0: Filter 1.1 (p3711, p3713), x = 1 Bit 4: Filter 2.1 (p3721, p3723), x = p3706 Bit 5: Filter 2.2 (p3726, p3728), x = p3706 Bit 8: Filter 3.1 (p3731, p3733), x = p3707 Bit 9: Filter 3.2 (p3736, p3738), x = p3707 Bit 16 ... 32: Data set number (starting from zero)
Remedy:	- reduce the numerator or denominator natural frequency of the filter involved. - reduce the speed controller sampling time (p0115[1]) or the sub-sampling (p3706, p3707). - switch-out the filter involved (p3704).
A07424	Drive: Operating condition for APC not valid
Reaction:	NONE
Acknowledge:	NONE
Cause:	The APC function (Advanced Positioning Control) has identified an invalid operating condition. Alarm value (r2124, interpret hexadecimal): Bit 0 = 1: APC is operating without encoder (sensorless). Bit 1 = 1: The load measuring system for APC, selected using p3701, has a fault. The APC function is disabled. Bit 2 = 1: The load measuring system for APC, selected using p3701, has a fault. The pulse de-coupling is disabled, i.e. the speed of the motor measuring system is used as speed for the closed-loop motor speed control.
Remedy:	Re bit 0: Only use the APC function in operation with an encoder. Re Bit 1, 2: Check the load measuring system.
F07429	Drive: DSC without encoder not possible
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The function DSC (Dynamic Servo Control) was activated although there is no encoder. See also: p1191 (DSC position controller gain KPC)
Remedy:	If there is no encoder and CI: p1191 (DSC position controller gain) is interconnected, then connector input CI: p1191 must have a 0 signal.
F07430	Drive: Changeover to open-loop torque controlled operation not possible
Reaction:	OFF2 (NONE, OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	For sensorless operation, the converter cannot change over to closed-loop torque-controlled operation (BI: p1501).
Remedy:	Do not attempt to cover over to closed-loop torque-controlled operation.
F07431	Drive: Changeover to sensorless operation not possible
Reaction:	OFF2 (OFF1)
Acknowledge:	IMMEDIATELY
Cause:	For closed-loop torque control, the converter cannot change over to sensorless operation (p1404).
Remedy:	Do not attempt to change over to sensorless operation.

F07432	Drive: Synchronous motor without overvoltage protection
Reaction:	OFF2 (OFF1)
Acknowledge:	IMMEDIATELY
Cause:	Under voltage conditions, a synchronous motor can generate an overvoltage condition that can destroy the drive system. Fault value (r0949, interpret hexadecimal): Associated Drive Data Set (DDS).
Remedy:	Overvoltage protection can be implemented in the following ways: - limit the maximum speed (p1082) without any additional protection. The maximum speed without protection is calculated as follows: Rotary motors: $p1082[\text{RPM}] \leq 9590/p0316[\text{Nm/A}]$ Linear motors: $p1082 [\text{m/min}] \leq 60257.45/p0316 [\text{N/A}]$ - use a voltage protection module (VPM) in conjunction with the function "safe standstill" (p9601, p9801). When a fault condition exists, the VPM short-circuits the motors. During the short-circuit, the pulses must be cancelled - this means that the terminals for the safe standstill must be connected to the VPM. When using a VPM, p0643 must be set to 1. - activating the internal voltage protection (IVP) with p1231 = 3. See also: p0643 (Overvoltage protection for synchronous motors), p1231 (Configuration, armature short-circuit)
F07433	Drive: Closed-loop control with encoder is not possible as the encoder has not been unparked
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The changeover to closed-loop control with encoder is not possible as the encoder has not been unparked.
Remedy:	- check whether the encoder firmware supports the "parking" function (r0481.6 = 1). - upgrade the firmware. Note: For long-stator motors (p3870.0 = 1), the following applies: The encoder must have completed the unparking procedure (r3875.0 = 1) before a changeover can be made to closed-loop control with encoder. The encoder is unparked with a 0/1 edge at BI: p3876 and remains unparked until a 0 signal is again present.
F07434	Drive: It is not possible to change the direction using p1821 with the pulses enabled
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A drive data set was selected - with the pulses enabled - that has a different parameterized direction (p1821). It is only possible to change the motor direction using p1821 when the pulses are inhibited.
Remedy:	- change over the drive data set with the pulses inhibited. - ensure that the changeover to a drive data set does not result in the motor direction of rotation being reversed (i.e. for these drive data sets, the same value must be in p1821). See also: p1821 (Direction reversal)
F07435 (N)	Drive: Setting the ramp-function generator for sensorless vector control
Reaction:	OFF2 (DCBRAKE, NONE, OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	Only for vector drives (refer to r0107): During operation with sensorless vector control (r1407 bit1), the ramp-function generator was held (p1141) or bypassed (p1122) so that an internal setting command of the ramp-function generator output caused the speed setpoint to be frozen or was not able to be implemented.
Remedy:	- de-activate the holding command for the ramp-function generator (p1141). - do not bypass the ramp-function generator (p1122). - suppress the fault message (p2101, p2119). This is necessary if the ramp-function generator is held using jogging and the speed setpoint is simultaneously inhibited (0898 bit 6). Note: For sensorless vector control it is not practical to read-in the main setpoint of the speed control via p1155 or p1160 (also refer to p0922). In this case, the main setpoint should be injected before the ramp-function generator (refer to p1070). The reason for this is that the ramp-function generator output is automatically set when transitioning from closed-loop speed controlled into open-loop speed controlled operation.
Reaction upon N:	NONE
Acknowledge upon N:	NONE

F07450 LR: Standstill monitoring has responded

Reaction: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: After the standstill monitoring time (p2543) expired, the drive left the standstill window (p2542).

- position actual value inversion incorrectly set (p0410).
- standstill window set too small (p2542).
- standstill monitoring time set too low (p2543).
- position loop gain too low (p2538).
- position loop gain too high (instability/oscillation, p2538).
- mechanical overload.
- check the connecting cable, motor/drive converter (phase missing, interchange).
- when selecting motor identification, select tracking operation (BI: p2655[0] = 1 signal).
- when selecting function generator, select tracking operation (BI: p2655[0] = 1 signal) and de-activate position control (BI:p2550 = 0 signal).

Remedy: Check the causes and resolve.

F07451 LR: Position monitoring has responded

Reaction: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: When the position monitoring time (p2545) expired, the drive had still not reached the positioning window (p2544).

- positioning window parameterized too small (p2544).
- position monitoring time parameterized too short (p2545).
- position loop gain too low (p2538).
- position loop gain too high (instability/oscillation, p2538).
- drive mechanically locked.

Remedy: Check the causes and resolve.

F07452 (A) LR: Following error too high

Reaction: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The difference between the position setpoint position actual value (following error dynamic model, r2563) is greater than the tolerance (p2546).

- the drive torque or accelerating capacity exceeded.
- position measuring system fault.
- position control sense incorrect.
- mechanical system locked.
- excessively high traversing velocity or excessively high position reference value (setpoint) differences

Remedy: Check the causes and resolve.

Reaction upon A: NONE

Acknowledge upon A: NONE

F07453 LR: Position actual value conditioning error

Reaction: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: An error has occurred during the position actual value conditioning.

Remedy: Check the encoder for the position actual value conditioning.
See also: p2502 (LR encoder assignment)

A07454 EPOS: Position actual value conditioning does not have a valid encoder

Reaction: NONE

Acknowledge: NONE

Cause: One of the following problems has occurred with the position actual value conditioning:

- an encoder is not assigned for the position actual value conditioning (p2502 = 0).
- an encoder is assigned, but no encoder data set (p0187 = 99 or p0188 = 99 or p0189 = 99).
- an encoder an an encoder data set have been assigned, however, the encoder data set does not contain any encoder data (p0400 = 0) or invalid data (e.g. p0408 = 0).

Remedy: Check the drive data sets, encoder data sets and encoder assignment.
See also: p0187 (Encoder 1 encoder data set number), p0188 (Encoder 2 encoder data set number), p0189 (Encoder 3 encoder data set number), p0400 (Enc type selection), p2502 (LR encoder assignment)

A07455 EPOS: Maximum velocity limited

Reaction: NONE

Acknowledge: NONE

Cause: The maximum velocity (p2571) is too high to correctly calculate the modulo correction.
Within the sampling time for positioning (p0115[5]), with the maximum velocity, a maximum of the half modulo length must be moved through. p2571 was limited to this value.

Remedy: - reduce the maximum velocity (p2571).
- increase the sampling time for positioning (p0115[5]).

A07456 EPOS: Setpoint velocity limited

Reaction: NONE

Acknowledge: NONE

Cause: The actual setpoint velocity is greater than the parameterized maximum velocity (p2571) and is therefore limited.

Remedy: - check the entered setpoint velocity.
- reduce the velocity override (CI: p2646).
- increase the maximum velocity (p2571).

A07457 EPOS: Combination of input signals illegal

Reaction: NONE

Acknowledge: NONE

Cause: An illegal combination of input signals that are simultaneously set was identified.
Alarm value (r2124, decimal):
0: Jogging 1 and jogging 2 (p2589, p2590).
1: Jogging 1 or jogging 2 and direct setpoint input/MDI (p2589, p2590, p2647).
2: Jogging 1 or jogging 2 and start referencing (p2589, p2590, p2595).
3: Jogging 1 or jogging 2 and activate traversing task (p2589, p2590, p2631).
4: Direct setpoint input/MDI and starting referencing (p2647, p2595).
5: Direct setpoint input/MDI and activate traversing task (p2647, p2631).
6: Start referencing and activate traversing task (p2595, p2631).

Remedy: Check the appropriate input signals and correct.

F07458 EPOS: Reference cam not found

Reaction: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: After starting the search for reference, the axis moved through the maximum permissible distance to search for the reference cam without actually finding the reference cam.

Remedy: - check the "reference cam" binector input (BI: p2612).
- check the maximum permissible distance to the reference cam (p2606).
- if axis does not have any reference cam, then set p2607 to 0.
See also: p2606 (EPOS search for reference, reference cam, maximum distance), p2607 (EPOS search for reference, reference cam present), p2612 (EPOS search for reference, reference cam)

F07459 EPOS: No zero mark

Reaction: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: After leaving the reference cam, the axis has traversed the maximum permissible distance between the reference cam and zero mark without finding the zero mark.

Remedy: - check the encoder regarding the zero mark
- check the maximum permissible distance between the reference cam and zero mark (p2609).
- use an external encoder zero mark (equivalent zero mark) (p0495).
See also: p0495 (Equivalent zero mark, input terminal), p2609 (EPOS search for reference, max. distance ref. cam and zero mark)

F07460	EPOS: End of reference cam not found
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	During the search for reference, when the axis reached the zero mark it also reached the end of the traversing range without detecting an edge at the binector input "reference cam" (BI: p2612). Maximum traversing range: -2147483648 [LU] ... -2147483647 [LU]
Remedy:	- check the "reference cam" binector input (BI: p2612). - repeat the search for reference. See also: p2612 (EPOS search for reference, reference cam)
A07461	EPOS: Reference point not set
Reaction:	NONE
Acknowledge:	NONE
Cause:	When starting a traversing block, a reference point is not set (r2684.11 = 0).
Remedy:	Reference the system (search for reference, flying referencing, set reference point).
A07462	EPOS: Selected traversing block number does not exist
Reaction:	NONE
Acknowledge:	NONE
Cause:	A traversing block was selected using an edge of the binector input "activate traversing block (0 -> 1)" (BI: p2631) and is not available. Alarm value (r2124, decimal): Number of the selected traversing block that is also not available.
Remedy:	- correct the traversing program. - select an available traversing block number.
F07464	EPOS: Traversing block is inconsistent
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The traversing block does not contain valid information. Alarm value (r2124, decimal): Number of the traversing block with invalid information.
Remedy:	Check the traversing block and where relevant, take into consideration alarms that are present.
A07465	EPOS: Traversing block does not have a subsequent block
Reaction:	NONE
Acknowledge:	NONE
Cause:	There is no subsequent block in the traversing block. Alarm value (r2124, decimal): Number of the traversing block with the missing subsequent block.
Remedy:	- parameterize this traversing block with the block change enable END. - parameterize additional traversing blocks with a higher block number and for the last block, using the block change enable END.
A07466	EPOS: Traversing block number assigned a multiple number of times
Reaction:	NONE
Acknowledge:	NONE
Cause:	The same traversing block number was assigned a multiple number of times. Alarm value (r2124, decimal): Number of the traversing block that was assigned a multiple number of times.
Remedy:	Correct the traversing blocks.

A07467	EPOS: Traversing block has illegal task parameters
Reaction:	NONE
Acknowledge:	NONE
Cause:	The task parameter in the traversing block contains an illegal value. Alarm value (r2124, decimal): Number of the traversing block with an illegal task parameter.
Remedy:	Correct the task parameter in the traversing block.

A07468	EPOS: Traversing block jump destination does not exist
Reaction:	NONE
Acknowledge:	NONE
Cause:	In a traversing block, a jump was programmed to a non-existent block. Alarm value (r2124, decimal): Number of the traversing block with a jump destination that does not exist.
Remedy:	- correct the traversing block. - add the missing traversing block.

A07469	EPOS: Traversing block < target position < software limit switch minus
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the traversing block the specified absolute target position lies outside the range limited by the software limit switch minus. Alarm value (r2124, decimal): Number of the traversing block with illegal target position.
Remedy:	- correct the traversing block. - change software limit switch minus (CI: p2578, p2580).

A07470	EPOS: Traversing block > target position > software limit switch plus
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the traversing block the specified absolute target position lies outside the range limited by the software limit switch plus. Alarm value (r2124, decimal): Number of the traversing block with illegal target position.
Remedy:	- correct the traversing block. - change software limit switch plus (CI: p2579, p2581).

A07471	EPOS: Traversing block target position outside the modulo range
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the traversing block the target position lies outside the modulo range. Alarm value (r2124, decimal): Number of the traversing block with illegal target position.
Remedy:	- in the traversing block, correct the target position. - change the modulo range (p2576).

A07472	EPOS: Traversing block ABS_POS/ABS_NEG not possible
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the traversing block the positioning mode ABS_POS or ABS_NEG were parameterized with the modulo correction not activated. Alarm value (r2124, decimal): Number of the traversing block with the illegal positioning mode.
Remedy:	Correct the traversing block.

A07473 (F) EPOS: Beginning of traversing range reached

Reaction: NONE
Acknowledge: NONE
Cause: When traversing, the axis has moved to the traversing range limit.
Remedy: Move away in the positive direction.
 Reaction upon F: OFF1 (OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY

A07474 (F) EPOS: End of traversing range reached

Reaction: NONE
Acknowledge: NONE
Cause: When traversing, the axis has moved to the traversing range limit.
Remedy: Move away in the negative direction.
 Reaction upon F: OFF1 (OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY

F07475 (A) EPOS: Target position < start of traversing range

Reaction: OFF1 (OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: The target position for relative traversing lies outside the traversing range.
Remedy: Correct the target position.
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F07476 (A) EPOS: Target position > end of the traversing range

Reaction: OFF1 (OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: The target position for relative traversing lies outside the traversing range.
Remedy: Correct the target position.
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A07477 (F) EPOS: Target position < software limit switch minus

Reaction: NONE
Acknowledge: NONE
Cause: In the actual traversing operation, the target position is less than the software limit switch minus.
Remedy: - correct the target position.
 - change software limit switch minus (CI: p2578, p2580).
 See also: p2578 (EPOS software limit switch minus signal source), p2580 (EPOS software limit switch minus), p2582 (EPOS software limit switch activation)
 Reaction upon F: OFF1 (OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY

A07478 (F)	EPOS: Target position > software limit switch plus
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the actual traversing operation, the target position is greater than the software limit switch plus.
Remedy:	- correct the target position. - change software limit switch plus (CI: p2579, p2581). See also: p2579 (EPOS software limit switch plus signal source), p2581 (EPOS software limit switch plus), p2582 (EPOS software limit switch activation)
Reaction upon F:	OFF1 (OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY

A07479	EPOS: Software limit switch minus reached
Reaction:	NONE
Acknowledge:	NONE
Cause:	The axis is at the position of the software limit switch minus. An active traversing block was interrupted.
Remedy:	- correct the target position. - change software limit switch minus (CI: p2578, p2580). See also: p2578 (EPOS software limit switch minus signal source), p2580 (EPOS software limit switch minus), p2582 (EPOS software limit switch activation)

A07480	EPOS: Software limit switch plus reached
Reaction:	NONE
Acknowledge:	NONE
Cause:	The axis is at the position of the software limit switch plus. An active traversing block was interrupted.
Remedy:	- correct the target position. - change software limit switch plus (CI: p2579, p2581). See also: p2579 (EPOS software limit switch plus signal source), p2581 (EPOS software limit switch plus), p2582 (EPOS software limit switch activation)

F07481 (A)	EPOS: Axis position < software limit switch minus
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The actual position of the axis is less than the position of the software limit switch minus.
Remedy:	- correct the target position. - change software limit switch minus (CI: p2578, p2580). See also: p2578 (EPOS software limit switch minus signal source), p2580 (EPOS software limit switch minus), p2582 (EPOS software limit switch activation)
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F07482 (A)	EPOS: Axis position > software limit switch plus
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The actual position of the axis is greater than the position of the software limit switch plus.
Remedy:	- correct the target position. - change software limit switch plus (CI: p2579, p2581). See also: p2579 (EPOS software limit switch plus signal source), p2581 (EPOS software limit switch plus), p2582 (EPOS software limit switch activation)
Reaction upon A:	NONE
Acknowledge upon A:	NONE

A07486	EPOS: Intermediate stop missing
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the modes "traversing blocks" or "direct setpoint input/MDI" at the start of motion, the binector input "no intermediate stop/intermediate stop" (BI: p2640) did not have a 1 signal.
Remedy:	Connect a 1 signal to the binector input "no intermediate stop/intermediate stop" (BI: p2640) and re-start motion.
A07487	EPOS: Reject traversing task missing
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the modes "traversing blocks" or "direct setpoint input/MDI" at the start of motion, the binector input "do not reject traversing task/reject traversing task" (BI: p2641) does not have a 1 signal.
Remedy:	Connect a 1 signal to the binector input "do not reject traversing task/reject traversing task" (BI: p2641) and re-start motion.
F07488	EPOS: Relative positioning not possible
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	In the mode "direct setpoint input/MDI", for continuous transfer (p2649 = 1) relative positioning was selected (BI: p2648 = 0 signal).
Remedy:	Check the control.
A07489	EPOS: Reference point correction (offset) outside the window
Reaction:	NONE
Acknowledge:	NONE
Cause:	For the function "flying referencing" the difference between the measured position at the measuring probe and the reference point coordinate lies outside the parameterized window.
Remedy:	- check the mechanical system. - check the parameterization of the window (p2602).
F07490	EPOS: Enable signal withdrawn while traversing
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	- for a standard assignment, another fault may have occurred as a result of withdrawing the enable signals. - the drive is in the "power-on inhibit" state (for a standard assignment).
Remedy:	- set the enable signals or check the cause of the fault that first occurred and then result (for a standard assignment). - check the assignment to enable the basic positioning function.
F07491 (A)	EPOS: STOP cam minus reached
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A zero signal was detected at binector input BI: p2569, i.e. the STOP cam minus was reached.
Remedy:	Leave the STOP cam minus in the positive traversing direction and return the axis to the valid traversing range.
Reaction upon A:	NONE
Acknowledge upon A:	NONE
F07492 (A)	EPOS: STOP cam plus reached
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A zero signal was detected at binector input BI: p2570, i.e. the STOP cam plus was reached.
Remedy:	Leave the STOP cam plus in the negative traversing direction and return the axis to the valid traversing range.
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F07493	LR: Overflow of the value range for the position actual value
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The value range (-2147483648 ... 2147483647) for the position actual value representation was exceeded. When the overflow occurs, the status "referenced" or the status "adjustment absolute measuring system" is reset. Fault value (r0949, decimal): 1: r2521 has exceeded the value range for the position actual value display. 2: r483 has exceeded the value range for the position actual value display.
Remedy:	If required, reduce the traversing range or position resolution.
F07494	LR: DDS changeover in operation
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	A drive data set changeover (DDS) with a change of the mechanical relationships and the encoder assignment (p2502) was requested in operation.
Remedy:	To changeover the drive data set, initially, exit the "operation" mode.
A07495 (F)	LR: Reference function interrupted
Reaction:	NONE
Acknowledge:	NONE
Cause:	An activated reference function (reference mark search or measuring probe evaluation) was interrupted. - an encoder fault has occurred (Gn_ZSW.15 = 1). - position actual value was set during an activated reference function. - simultaneously activate reference mark search and measuring probe evaluation (BI: p2508 and BI: p2509 = 1 signal). - activated reference function (reference mark search or measuring probe evaluation) was de-activated (BI: p2508 and BI: p2509 = 0 signal).
Remedy:	- check the causes and resolve. - reset the control (BI: p2508 and BI: p2509 = 0 signal) and activate the requested function.
Reaction upon F:	OFF1 (OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY
A07496	EPOS: Enable not possible
Reaction:	NONE
Acknowledge:	NONE
Cause:	It is not possible to enable the basic positioner for the following reasons. Alarm value (r2124, decimal): 1: EPOS enable missing (BI: p2656). 2: Position actual value, valid feedback signal missing (BI: p2658). See also: p2656 (EPOS enable basic positioner), p2658 (EPOS pos. actual value valid, feedback signal)
Remedy:	Check the appropriate binector inputs and signals.
A07497	LR: Position setting value activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	The position actual value is set to the value received via CI: p2515 while BI: p2514 = 1 signal. A possible system deviation cannot be corrected.
Remedy:	None necessary. The alarm automatically disappears with BI: p2514 = 0 signal.

F07500	Drive: Power unit data set PDS not configured
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Only for controlled line supply infeed/regenerative feedback units: The power unit data set was not configured - this means that a data set number was not entered into the drive data set. Fault value (r0949, decimal): Drive data set number of p0185.
Remedy:	The index of the power unit data set associated with the drive data set should be entered into p0185.
F07501	Drive: Motor Data Set MDS not configured
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Only for power units: The motor data set was not configured - this means that a data set number was not entered into the associated drive data set. Fault value (r0949, decimal): The fault value includes the drive data set number of p0186.
Remedy:	The index of the motor data set associated with the drive data set should be entered into p0186. See also: p0186 (Motor Data Sets (MDS) number)
F07502	Drive: Encoder Data Set EDS not configured
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Only for power units: The encoder data set was not configured - this means that a data set number was not entered into the associated drive data set. Fault value (r0949, decimal): The fault value includes the drive data set number of p0187, p0188 and p0189. The fault value is increased by 100 * encoder number (e.g. for p0189: Fault value 3xx with xx = data set number).
Remedy:	The index of the encoder data set associated with the drive data set should be entered into p0187 (1st encoder), p0188 (2nd encoder) and p0189 (3rd encoder).
A07504	Drive: Motor data set is not assigned to a drive data set
Reaction:	NONE
Acknowledge:	NONE
Cause:	A motor data set is not assigned to a drive object. All of the existing motor data sets in the drive data sets must be assigned using the MDS number (p0186[0...n]). Alarm value (r2124, decimal): Number of the motor data set that has not been assigned.
Remedy:	In the drive data sets, assign the non-assigned motor data set using the MDS number (p0186[0...n]). See also: p0186 (Motor Data Sets (MDS) number)
F07510	Drive: Identical encoder in the drive data set
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	More than one encoder with identical component number is assigned to a single drive data set. In one drive data set, it is not permissible that identical encoders are operated together. Fault value (r0949, decimal): 1000 * first identical encoder + 100 * second identical encoder + drive data set. Example: Fault value = 1203 means: In drive data set 3, the first (p0187[3]) and second encoder (p0188[3]) are identical.
Remedy:	Assign the drive data set to different encoders. See also: p0141 (Encoder interface (Sensor Module) component number), p0187 (Encoder 1 encoder data set number), p0188 (Encoder 2 encoder data set number), p0189 (Encoder 3 encoder data set number)

F07511	Drive: Encoder used a multiple number of times
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Each encoder may only be assigned to one drive and within a drive must - in each drive data set - either always be encoder 1, always encoder 2 or always encoder 3. This unique assignment has been violated. Fault value (r0949, decimal): The two parameters in coded form, that refer to the same component number. First parameter: Index: First and second decimal place (99 for EDS, not assigned DDS) Parameter number: Third decimal place (1 for p0187, 2 for p0188, 3 for p0189, 4 for EDS not assigned DDS) Drive number: Fourth and fifth decimal place Second parameter: Index: Sixth and seventh decimal place (99 for EDS, not assigned DDS) Parameter number: Eighth decimal place (1 for p0187, 2 for p0188, 3 for p0189, 4 for EDS, not assigned DDS) Drive number: Ninth and tenth decimal place See also: p0141 (Encoder interface (Sensor Module) component number)
Remedy:	Correct the double use of a component number using the two parameters coded in the fault value.
A07512	Drive: Encoder data set changeover cannot be parameterized
Reaction:	NONE
Acknowledge:	NONE
Cause:	Using p0141, a changeover of the encoder data set is prepared that is illegal. In this firmware release, an encoder data set changeover is only permitted for the components in the actual topology. Commissioning can only be exited with the correct parameterization. Alarm value (r2124, decimal): Incorrect EDS data set number. See also: p0187 (Encoder 1 encoder data set number), p0188 (Encoder 2 encoder data set number), p0189 (Encoder 3 encoder data set number)
Remedy:	Every encoder data set must be assigned its own dedicated DRIVE-CLiQ socket. The component numbers of the encoder interfaces (p0141) must have different values within a drive object. The following must apply: p0141[0] not equal to p0141[1] not equal to ... not equal to p0141[n]
A07514	Drive: Data structure does not correspond to the interface module
Reaction:	NONE
Acknowledge:	NONE
Cause:	The interface mode "SIMODRIVE 611 universal" was set (p2038 = 1) and the data structure does not correspond to this mode. For the data structure, the following rule must be complied with. Within the group of 8 drive data sets, the assignment to the motor data set must be set the same: p0186[0] = p0186[1] = ... = p0186[7] p0186[8] = p0186[9] = ... = p0186[15] p0186[16] = p0186[17] = ... = p0186[23] p0186[24] = p0186[25] = ... = p0186[31] See also: p0180 (Number of Drive Data Sets (DDS)), p0186 (Motor Data Sets (MDS) number), p2038 (PROFIBUS STW/ZSW interface mode)
Remedy:	- structure the data according to the rules of the "SIMODRIVE 611 universal" interface mode. - check the interface mode (p2038).
A07515	Drive: Power unit and motor incorrectly connected
Reaction:	NONE
Acknowledge:	NONE
Cause:	A power unit (via PDS) was assigned to a motor (via MDS) in a drive data set that is not connected in the target topology. Alarm value (r2124, decimal): Number of the incorrectly parameterized drive data set.
Remedy:	- assign the drive data set to a combination of motor and power unit permitted by the target topology. - adapt the target topology. See also: p0121 (Power unit component number), p0131 (Motor component number), p0186 (Motor Data Sets (MDS) number)

F07516	Drive: Re-commission the data set
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The assignment between the drive data set and motor data set (p0186) or between the drive data set and the encoder data set was modified (p0187). This is the reason that the drive data set must re-commissioned. Fault value (r0949, decimal): Drive data set to be re-commissioned.
Remedy:	Commission the drive data set specified in the fault value (r0949).
A07517	Drive: Encoder data set changeover incorrectly parameterized
Reaction:	NONE
Acknowledge:	NONE
Cause:	An MDS cannot have different motor encoders in two different DDS. The following parameterization therefore results in an error: p0186[0] = 0 p0187[0] = 0 p0186[0] = 0 p0187[0] = 1 Alarm value (r2124, decimal): The lower 16 bits indicate the first DDS and the upper 16 bits indicate the second DDS.
Remedy:	If you wish to operate a motor once with one motor encoder and then another time with the other motor encoder, then you must set-up two different MDSs, in which the motor data are the same. Example: p0186[0] = 0 p0187[0] = 0 p0186[0] = 1 p0187[0] = 1
F07518	Drive: Motor data set changeover incorrectly parameterized
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The system has identified that two motor data sets were incorrectly parameterized. Parameter r0313 (calculated from p0314, p0310, p0311), r0315 and p1982 may only have different values if the motor data sets are assigned different motors. p0827 is used to assign the motors and/contactors. It is not possible to toggle between motor data sets. Alarm value (r2124, interpret hexadecimal): xxxxyyyy: xxxx: First DDS with assigned MDS, yyyy: Second DDS with assigned MDS
Remedy:	Correct the parameterization of the motor data sets.
A07519	Drive: Motor cannot be changed over
Reaction:	NONE
Acknowledge:	NONE
Cause:	With the setting p0833.1, a motor changeover via the application is selected. This is the reason that p0827 must have different values in the appropriate motor data set. Alarm value (r2124, interpret hexadecimal): xxxxyyyy: xxxx: First MDS, yyyy: Second MDS
Remedy:	- parameterize the appropriate motor data sets differently (p0827). - select the setting p0833.0 = 0 (motor changeover via the drive).
A07530	Drive: Drive Data Set DDS not present
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected drive data set is not available (p0837 > p0180). The drive data set was not changed-over. See also: p0180 (Number of Drive Data Sets (DDS)), p0820 (Drive data set selection DDS bit 0), p0821 (Drive data set selection DDS bit 1), p0822 (Drive data set selection DDS bit 2), p0823 (Drive data set selection DDS bit 3), p0824 (Drive data set selection DDS bit 4), r0837 (Drive Data Set DDS selected)
Remedy:	- select the existing drive data set. - set-up additional drive data sets.

A07541 Drive: Data set changeover not possible
Reaction: NONE
Acknowledge: NONE
Cause: The selected drive data set changeover and the assigned motor changeover are not possible and are not carried-out. For synchronous motors, the motor contactor may only be switched for actual speeds less than the speed at the start of field weakening (r0063 < p0348).
 See also: r0063 (Actual speed, smoothed), p0348 (Speed at the start of field weakening Vdc = 600 V)
Remedy: Reduce the speed below the speed at the start of field weakening.

A07550 (F, N) Drive: Not possible to reset encoder parameters
Reaction: NONE
Acknowledge: NONE
Cause: When carrying-out a factory setting (e.g. using p0970 = 1), it was not possible to reset the encoder parameters. The encoder parameters are directly read out of the encoder via DRIVE-CLiQ.
 Alarm value (r2124, decimal):
 Component number of the encoder involved.
Remedy:
 - repeat the operation.
 - check the DRIVE-CLiQ connection.
 Reaction upon F: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

F07551 Drive encoder: No commutation angle information
Reaction: OFF2 (DCBRAKE)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The angular commutation information is missing. This means that synchronous motors cannot be controlled (closed-loop control)
 Fault value (r0949, decimal):
 Low word: Drive data set number
 High word: Cause:
 1: The motor encoder used does not supply an absolute commutation angle.
 2: The selected ratio of the measuring gearbox does not match the motor pole pair number
Remedy:
 Re cause 1:
 - check the encoder parameterization (p0404).
 - use an encoder with track C/D, EnDat interface or Hall sensors.
 - use an encoder with sinusoidal A/B track for which the motor pole pair number (p0313) is an integer multiple of the encoder pulse number (p0408).
 - activate the pole position identification routine (p1982 = 1).
 Re cause 2:
 - the quotient of the pole pair number divided by the measuring gearbox ratio must be an integer number: (p0314*p0433) / p0432.
 See also: p0402 (Gearbox type selection), p0404 (Encoder configuration effective), p0432 (Gearbox factor, encoder revolutions), p0433 (Gearbox factor, motor/load revolutions)

F07552 (A) Drive encoder: Encoder configuration not supported

Reaction: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The requested encoder configuration is not supported. Only bits may be requested in p0404 that are signaled as being supported by the encoder evaluation in r0456.
 Fault value (r0949, decimal):
 Low word low byte: Encoder data set number
 Low word high byte: Component number
 High word:
 The encoder evaluation does not support a function selected in p0404.
 1: sin/cos encoder with absolute track (this is supported by SME25).
 3: Squarewave encoder (this is supported by SMC30).
 4: sin/cos encoder (this is supported by SMC20, SMI20, SME20, SME25).
 12: sin/cos encoder with reference mark (this is supported by SME20).
 15: Commutation with zero mark for separately-excited synchronous motors with VECTORMV.
 23: Resolver (this is supported by SMC10, SMI10).
 65535: Other function (compare r0456 and p0404).
 See also: p0404 (Encoder configuration effective), r0456 (Encoder configuration supported)
Remedy:
 - check the encoder parameterization (p0400, p0404).
 - use the matching encoder evaluation (r0456).
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F07553 (A) Drive encoder: Sensor Module configuration not supported

Reaction: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The Sensor Module does not support the requested configuration.
 Possible causes:
 - bits are set in p0430 (requested functions) that are not set in r0458 (supported functions). This does not apply for bit 19 (safety position actual value sensing), bit 29 (phase correction), bit 30 (amplitude correction) and bit 31 (offset correction).
 - $p1982 > 0$ (pole position identification requested), but r0458 bit 16 = 0 (pole position identification not supported).
 Fault value (r0949, decimal):
 Encoder data set number.
Remedy:
 - check the encoder parameterization (p0430).
 - check the pole position identification routine (p1982).
 - use the matching encoder evaluation (r0458).
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F07555 (A) Drive encoder: Configuration position tracking

Reaction: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The configuration of the position tracking is not supported.
 Position tracking can only be activated for absolute encoders.
 Fault value (r0949, decimal):
 Low word low byte: Encoder data set number
 Low word high byte: Component number
 See also: p0404 (Encoder configuration effective), p0411 (Measuring gearbox, configuration)
Remedy:
 - use an absolute encoder.
 - de-select position tracking (p0411).
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F07560 Drive encoder: Number of pulses is not to the power of two

Reaction: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: For rotary absolute encoders, the pulse number in p0408 must be to the power of two.
 Fault value (r0949, decimal):
 The fault value includes the encoder data set number involved.
Remedy:
 - check the parameterization (p0408, p0404.1, r0458.5).
 - if required, upgrade the Sensor Module firmware.

F07561 Drive encoder: Number of multiturn pulses is not to the power of two

Reaction: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The multi-turn resolution in p0421 must be to the power of two.
 Fault value (r0949, decimal):
 The fault value includes the encoder data set number involved.
Remedy:
 - check the parameterization (p0421, p0404.1, r0458.5).
 - if required, upgrade the Sensor Module firmware.

A07565 (F, N) Drive: Encoder error in PROFIdrive encoder interface 1

Reaction: NONE
Acknowledge: NONE
Cause: An encoder error was signaled for encoder 1 via the PROFIdrive encoder interface (G1_ZSW.15).
 Alarm value (r2124, decimal):
 Error code from G1_XIST2, refer to the description regarding r0483.
Remedy: Acknowledge the encoder error using the encoder control word (G1_STW.15 = 1).
 Reaction upon F: NONE (OFF1, OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A07566 (F, N) Drive: Encoder error in PROFIdrive encoder interface 2

Reaction: NONE
Acknowledge: NONE
Cause: An encoder error was signaled for encoder 2 via the PROFIdrive encoder interface (G2_ZSW.15).
 Alarm value (r2124, decimal):
 Error code from G2_XIST2, refer to the description regarding r0483.
Remedy: Acknowledge the encoder error using the encoder control word (G2_STW.15 = 1).
 Reaction upon F: NONE (OFF1, OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A07567 (F, N)	Drive: Encoder error in PROFIdrive encoder interface 32
Reaction:	NONE
Acknowledge:	NONE
Cause:	An encoder error was signaled for encoder 3 via the PROFIdrive encoder interface (G3_ZSW.15). Alarm value (r2124, decimal): Error code from G3_XIST2, refer to the description regarding r0483.
Remedy:	Acknowledge the encoder error using the encoder control word (G3_STW.15 = 1).
Reaction upon F:	NONE (OFF1, OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
F07575	Drive: Motor encoder not ready
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The motor encoder signals that it is not ready. - initialization of encoder 1 (motor encoder) was unsuccessful. - the function "parking encoder" is active (selected using the encoder control word G1_STW.14 = 1). - the Sensor Module is defective.
Remedy:	Evaluate other queued faults via encoder 1.
A07576	Drive: Sensorless operation active due to a fault
Reaction:	NONE
Acknowledge:	NONE
Cause:	Sensorless control is active due to a fault (refer to r1407.13). The required response when an encoder fault occurs is parameterized in p0491. See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	
A07580 (F, N)	Drive: No Sensor Module with matching component number
Reaction:	NONE
Acknowledge:	NONE
Cause:	A Sensor Module with the component number specified in p0141 was not found. Alarm value (r2124, decimal): Encoder data set involved (index of p0141).
Remedy:	Correct p0141.
Reaction upon F:	OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)
Reaction upon N:	NONE
Acknowledge upon N:	NONE
F07800	Drive: No power unit present
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The power unit parameters cannot be read or no parameters are stored in the power unit. This fault also occurs if an incorrect topology was selected in the commissioning software and this parameterization is then downloaded into the CU. See also: r0200 (Power unit, actual code number)
Remedy:	Connect the data line to power unit and restart the Control Unit (POWER ON). Drive:

F07801 Drive: Motor overcurrent

Reaction: OFF2 (NONE, OFF1, OFF3)

Acknowledge: IMMEDIATELY

Cause: The permissible motor limit current was exceeded.

- effective current limit set too low.
- current controller not correctly set.
- motor was braked with an excessively high stall torque correction factor.
- U/f operation: Up ramp was set too short or the load is too high.
- U/f operation: Short-circuit in the motor cable or ground fault.
- U/f operation: Motor current does not match the current of Motor Module.

Note:

Synchronous motor: Limit current= 1.3 * p0323

Induction motor: Limit current= 1.3 * r0209

Remedy:

- check the current limits (p0323, p0640).
- check the current controller (p1715, p1717).
- reduce the stall torque correction factor (p0326).
- increase the up ramp (p1318) or reduce the load.
- check the motor and motor cables for short-circuit and ground fault.
- check the Motor Module and motor combination.

F07802 Drive: Infeed or power unit not ready

Reaction: OFF2 (NONE)

Acknowledge: IMMEDIATELY

Cause: After an internal power-on command, the infeed or drive does not signal ready.

- monitoring time is too short.
- DC link voltage is not present.
- associated infeed or drive of the signaling component is defective.
- supply voltage incorrectly set.

Remedy:

- increase the monitoring time (p0857).
- ensure that there is a DC link voltage. Check the DC-link busbar. Enable the infeed.
- replace the associated infeed or drive of the signaling component.
- check the line supply voltage setting (p0210).

See also: p0857 (Power unit monitoring time)

A07805 (N) Drive: Power unit I2T overload

Reaction: NONE

Acknowledge: NONE

Cause: Alarm threshold for I2t overload (p0294) of the power unit exceeded.
The response parameterized in p0290 becomes active.
See also: p0290 (Power unit overload response)

Remedy:

- reduce the continuous load.
- adapt the load duty cycle.
- check the assignment of the rated currents of the motor and Motor Module.

Reaction upon N: NONE

Acknowledge upon N: NONE

upon N:

F07810 Drive: Power unit EEPROM without rated data

Reaction: NONE

Acknowledge: IMMEDIATELY

Cause: No rated data are stored in the power unit EEPROM.
See also: p0205 (Power unit application), r0206 (Rated power unit power), r0207 (Rated power unit current), r0208 (Rated power unit line supply voltage), r0209 (Power unit, maximum current)

Remedy: Replace the power unit or inform Siemens Customer Service.

F07815	Drive: Power unit has been changed
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The code number of the actual power unit does not match the saved number. Fault value (r0949, decimal): Number of the incorrect parameter. See also: r0200 (Power unit, actual code number), p0201 (Power unit code number)
Remedy:	Connect the original power unit and power-up the Control Unit again (POWER ON) or set p0201 to r0200 and exit commissioning with p0010 = 0. For infeeds, the following applies: Commutating reactors or line filters must be used that are clearly specified for the new power unit. A line supply and DC link identification routine (p3410 = 5) must then be carried-out. It is not possible to change the power unit without re-commissioning the system if the type of infeed (A_Infeed, B_Infeed, S_Infeed), the type of construction/design (Booksize, Chassis) or the voltage class differ between the old and new power units. For inverters, the following applies: If the new power unit is accepted, then if required, the current limit p0640 can be reduced by a lower maximum current of the power unit (r0209) (torque limits stay the same). If not only the power unit is changed, but also the motor, then the motor must be re-commissioning (e.g. using p0010 = 1). This is also necessary if motor data is still to be downloaded via DRIVE-CLiQ. See also: r0200 (Power unit, actual code number)
A07820	Drive: Temperature sensor not connected
Reaction:	NONE
Acknowledge:	NONE
Cause:	The temperature sensor for motor temperature monitoring, specified in p0600, is not available. - parameter download with "incorrect" setting. - module with sensor evaluation has been, in the meantime, been removed.
Remedy:	- connect the module with temperature sensor. - set the available temperature sensor (p0600, p0601). See also: p0600 (Motor temperature sensor for monitoring), p0601 (Motor temperature sensor type)
A07825 (N)	Drive: Simulation operation activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	The simulation mode is activated. The drive can only be powered-up if the DC link voltage is less than 40 V.
Remedy:	The alarm automatically disappears if simulation operation is de-activated with p1272 = 0.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
F07826	Drive: Simulation operation with DC link voltage too high
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The simulation mode is activated and the DC link voltage is greater than the permissible value of 40 V.
Remedy:	- switch-out (disable) simulation operation (p1272 = 0) and acknowledge the fault. - reduce the input voltage in order to reach a DC link voltage below 40 V.
F07840	Drive: Infeed operation missing
Reaction:	OFF2 (NONE)
Acknowledge:	IMMEDIATELY
Cause:	The signal "infeed operation" is not present although the enable signals for the drive have been present for longer than the parameterized monitoring time (p0857). - infeed not operational. - interconnection of the binector input for the ready signal is either incorrect or missing (p0864). - infeed is presently carrying-out a line supply identification routine.

Remedy:

- bring the infeed into an operational state.
- check the interconnection of the binector input for the signal "infeed operation" (p0864).
- increase the monitoring time (p0857).
- wait until the infeed has completed the line supply identification routine.

See also: p0857 (Power unit monitoring time), p0864 (Infeed operation)

F07841 Drive: Infeed operation withdrawn

Reaction: OFF2 (NONE, OFF1, OFF3)

Acknowledge: IMMEDIATELY

Cause:

The signal "infeed operation" was withdrawn in operation.

- interconnection of the binector input for the signal "infeed operation" is either incorrect or missing (p0864).
- the enable signals of the infeed were disabled.
- due to a fault, the infeed withdraws the signal "infeed operation".

Remedy:

- check the interconnection of the binector input for the signal "infeed operation" (p0864).
- check the enable signals of the infeed and if required, enable.
- remove and acknowledge an infeed fault.

Note:

If this drive is intended to back-up the DC link regeneratively, then the fault response must be parameterized for NONE so that the drive can continue to operate even after the infeed fails.

A07850 (F) External alarm 1

Reaction: NONE

Acknowledge: NONE

Cause:

The BICO signal for "external alarm 1" was triggered.
 The condition for this external alarm is fulfilled.
 See also: p2112 (External alarm 1)

Remedy: Eliminate the causes of this alarm.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY (POWER ON)

A07851 (F) External alarm 2

Reaction: NONE

Acknowledge: NONE

Cause:

The BICO signal for "external alarm 2" was triggered.
 The condition for this external alarm is fulfilled.
 See also: p2116 (External alarm 2)

Remedy: Eliminate the causes of this alarm.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY (POWER ON)

A07852 (F) External alarm 3

Reaction: NONE

Acknowledge: NONE

Cause:

The BICO signal for "external alarm 3" was triggered.
 The condition for this external alarm is fulfilled.
 See also: p2117 (External alarm 3)

Remedy: Eliminate the causes of this alarm.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY (POWER ON)

F07860 (A) External fault 1

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The BICO signal "external fault 1" was triggered.
 See also: p2106 (External fault 1)

Remedy: Eliminate the causes of this fault.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F07861 (A) External fault 2

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The BICO signal "external fault 2" was triggered.
 See also: p2107 (External fault 2)

Remedy: Eliminate the causes of this fault.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F07862 (A) External fault 3

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The BICO signal "external fault 3" was triggered.
 See also: p2108 (External fault 3), p3111 (External fault 3, enable), p3112 (External fault 3 enable negated)

Remedy: Eliminate the causes of this fault.

Reaction upon A: NONE
 Acknowledge upon A: NONE

F07900 (N, A) Drive: Motor locked/speed controller at its limit

Reaction: OFF2 (NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: Motor has been operating at the torque limit longer than the time specified in p2177 and below the speed threshold set in p2175.
 This signal can also be initiated if the speed actual value is oscillating and the speed controller output repeatedly goes to its limit.
 See also: p2175 (Motor locked speed threshold), p2177 (Motor locked delay time)

Remedy:

- check that the motor can freely rotate.
- check the torque limit: For a positive direction of rotation r1538, for a negative direction of rotation r1539.
- check the parameter, message "Motor locked" and if required, correct (p2175, p2177).
- check the inversion of the actual value (p0410).
- check the motor encoder connection.
- check the encoder pulse number (p0408).
- for SERVO with sensorless operation and motors with low power ratings (< 300 W), increase the pulse frequency (p1800).

Reaction upon N: NONE
 Acknowledge upon N: NONE

Reaction upon A: NONE
 Acknowledge upon A: NONE

F07901 Drive: Motor overspeed
Reaction: OFF2 (OFF1)
Acknowledge: IMMEDIATELY
Cause: The maximum permissible speed was either positively or negatively exceeded.
 The maximum permissible positive speed is formed as follows: Minimum(p1082, Cl: p1085) + p2162. The maximum permissible negative speed is formed as follows: Maximum(-p1082, Cl: 1088) - p2162.
Remedy: For a positive direction of rotation:
 - check r1084 and if required, correct p1082, Cl:p1085 and p2162.
 For a negative direction of rotation:
 - check r1087 and if required, correct p1082, Cl:p1088 and p2162.

F07902 (N, A) Drive: Motor stalled
Reaction: OFF2 (NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY
Cause: For a vector drive the system has identified that the motor has stall for a time longer than is set in p2178.
 Fault value (r0949, decimal):
 1: Stall detection using r1408.11 (p1744).
 2: Stall detection using r1408.12 (p1745).
 3: Stall detection using r0056.11 (only for separately excited synchronous motors).
 See also: p1744 (Motor model speed threshold stall detection), p2178 (Motor stalled delay time)
Remedy: For closed-loop speed and torque control with speed encoder, the following applies:
 - check the speed signal (interrupted cable, polarity, pulse number).
 If there is no fault, then the fault tolerance can be increased (p1744).
 For closed-loop speed and torque control without speed encoder, the following applies:
 - check whether the drive stalls due to the load if the speed setpoint is still zero. If yes, then increase the current setpoint using p1610.
 - if the motor excitation (magnetizing) time (r0346) was significantly reduced, then it should be increased again.
 - check the current limits (p0640, r0067). If these are too low, then the drive cannot be magnetized.
 - check the current controller (p1715, p1717) and the speed adaptation controller (p1764, p1767). If the dynamic response was significantly reduced, then this should be increased again.
 If there is no fault, then the fault tolerance (p1745) or the delay time (p2178) can be increased.
 For separately-excited synchronous motors (closed-loop control with speed encoder), the following applies:
 - check the speed signal (interrupted cable, polarity, pulse number).
 - ensure the correct motor parameterization (rating plate and equivalent circuit diagram parameters).
 - check the excitation equipment and the interface to the closed-loop control.
 - encoder the highest possible dynamic response of the closed-loop excitation current control.
 - check the speed control for any tendency to oscillate and if resonance effects occur, use a bandstop filter.
 - do not exceed the maximum speed (p2162).
 If there is no fault, then the delay time can be increased (p2178).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A07903 Drive: Motor speed deviation

Reaction: NONE

Acknowledge: NONE

Cause: The absolute value of the speed difference from the two setpoints (p2151, p2154) and the speed actual value (r2169) exceeds the tolerance threshold (p2163) longer than tolerated (p2164, p2166).
The alarm is only enabled for p2149.0 = 1.
Possible causes could be:

- the load torque is greater than the torque setpoint.
- when accelerating, the torque/current/power limit is reached. If the limits are not sufficient, then it is possible that the drive has been dimensioned too small.
- the speed controller is inhibited (refer to p0856; refer to Kp/Tn adaptation of the speed controller).
- for closed-loop torque control, the speed setpoint does not track the speed actual value.
- for active Vdc controller.
- the encoder pulse number was incorrectly parameterized (p0408).

The signal is not generated if the ramp-function generator tracking prevents the setpoint and actual speed from drifting (moving) apart.

Only for vector drives:
For U/f control, the overload condition is detected as the I_{max} controller is active.
See also: p2149 (Monitoring, configuration)

Remedy:

- increase p2163 and/or p2166.
- increase the torque/current/power limits.
- enable the speed controller.
- for closed-loop torque control: The speed setpoint should track the speed actual value.
- correct the encoder pulse number in p0408 or mount the correct tachometer.

A07904 (N) External armature short-circuit: Contactor feedback signal "closed" missing

Reaction: NONE

Acknowledge: NONE

Cause: When closing, the contactor feedback signal (p1235) did not issue the signal "closed" (r1239.1 = 1) within the monitoring time (p1236).

Remedy:

- check that the contactor feedback signal is correctly connected (p1235).
- check the logic of the contactor feedback signal (r1239.1 = 1: "closed", r1239.1 = 0: "open").
- increase the monitoring time (p1236).
- if required, set the external armature short-circuit without contactor feedback signal (p1231=2).

Reaction upon N: NONE

Acknowledge upon N: NONE

F07905 (N, A) External armature short-circuit: Contactor feedback signal "open" missing

Reaction: OFF2 (NONE)

Acknowledge: IMMEDIATELY

Cause: When opening, the contactor feedback signal (p1235) did not issue the signal "open" (r1239.1 = 0) within the monitoring time (p1236).

Remedy:

- check that the contactor feedback signal is correctly connected (p1235).
- check the logic of the contactor feedback signal (r1239.1 = 1: "closed", r1239.1 = 0: "open").
- increase the monitoring time (p1236).
- if required, set the external armature short-circuit without contactor feedback signal (p1231=2).

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F07906	Armature short-circuit: Parameterization error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The armature short-circuit is incorrectly parameterized.</p> <p>Fault value (r0949, decimal):</p> <p>Low word: Motor data set number</p> <p>High word: Cause:</p> <p>1: A permanent-magnet synchronous motor has not been selected.</p> <p>101: External armature short-circuit: Output (r1239.0) not connected-up.</p> <p>102: External armature short-circuit with contactor feedback signal: no feedback signal connected (BI:p1235)</p> <p>103: External armature short-circuit without contactor feedback signal: Delay time when opening (p1237) is 0.</p> <p>201: Internal voltage protection: The maximum output current of the motor module (r0289) is less than 1.8* of the motor short-circuit current (r0331).</p> <p>202: Internal voltage protection: A booksize motor module is not being used.</p> <p>203: Internal voltage protection: The motor short-circuit current (p0320) is greater than the maximum motor current (p0323).</p>
Remedy:	<p>Re cause 1:</p> <ul style="list-style-type: none"> - an armature short-circuit is only permissible for permanent-magnetic synchronous motors. The highest position of the motor type in p0300 must either be 2 or 4. <p>Re cause 101:</p> <ul style="list-style-type: none"> - the contactor for the external armature short-circuit configuration should be controlled using output signal r1239.0. The signal can, e.g. be connected to an output terminal BI: p0738. Before this fault can be acknowledged, parameter p1231 must be set again. <p>Re cause 102:</p> <ul style="list-style-type: none"> - if the external armature short-circuit with contactor feedback signal (p1231=1) is selected, this feedback signal must be connected to an input terminal (e.g. r722.x) and then connected to BI:p1235. - alternatively, the external armature short-circuit without contactor feedback signal (p1231=2) can be selected. <p>Re cause 103:</p> <ul style="list-style-type: none"> - if the external armature short-circuit without contactor feedback signal (p1231=2) is selected, then a delay time must be parameterized in p1237. This time must always be greater than the actual contactor opening time, as otherwise the motor module would be short-circuited! <p>Re cause 201:</p> <ul style="list-style-type: none"> - a Motor Module with a higher maximum current or a motor with a lower short-circuit current must be used. The maximum Motor Module current must be 1.8 * higher than the short-circuit current of the motor. <p>Re cause 202:</p> <ul style="list-style-type: none"> - a Booksize Motor Module must be used for the internal voltage protection. <p>Re cause 203:</p> <ul style="list-style-type: none"> - for internal voltage protection, only short-circuit proof motors may be used.
F07907	Internal voltage protection: Motor terminals are not at zero potential after pulse cancellation
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<ul style="list-style-type: none"> - when the internal voltage protection is active (p1231 = 3), after pulse cancellation, all of the motor terminals are at half of the DC link voltage (without an internal voltage protection, the motor terminals are at zero potential)! - in order to ensure safe function of IVP when the power fails, an external 24 V power supply (UPS) must be used for all of the components.
Remedy:	<p>None necessary.</p> <p>This a note for the user.</p>

A07910 (N)	Drive: Motor overtemperature
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>KTY: The motor temperature has exceeded the alarm threshold (p0604). VECTOR: The response parameterized in p0610 becomes active.</p> <p>PTC: The response threshold of 1650 Ohm was exceeded. Alarm value (r2124, decimal): SME not selected in p0601: 1: No output current reduction. 1: Output current reduction active. SME selected in p0601 (p0601=10) The number specifies the sensor channel that resulted in the alarm being output. See also: p0604 (Motor overtemperature alarm threshold), p0610 (Response to motor overtemperature condition)</p>
Remedy:	<ul style="list-style-type: none"> - check the motor load. - check the motor ambient temperature.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
F07913	Excitation current outside the tolerance range
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The difference between the excitation current actual value and setpoint has exceeded the tolerance: $\text{abs}(r1641 - r1626) > p3201 + p3202$ The cause of this fault is again reset for $\text{abs}(r1641 - r1626) < p3201$.</p>
Remedy:	<ul style="list-style-type: none"> - check the parameterization (p1640, p3201, p3202). - check the interfaces to the excitation equipment (r1626, p1640). - check the excitation equipment.
F07914	Flux out of tolerance
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The difference between the flux actual value and setpoint has exceeded the tolerance: $\text{abs}(r0084 - r1598) > p3204 + p3205$ The cause of this fault is again reset for $\text{abs}(r0084 - r1598) < p3204$.</p>
Remedy:	<ul style="list-style-type: none"> - check the parameterization (p3204, p3205). - check the interfaces to the excitation equipment (r1626, p1640). - check the excitation equipment. - check the flux control (p1592, p1592, p1597). - check the control for oscillation and take the appropriate counter measures (e.g. optimize the speed control loop, parameterize a bandstop filter).
A07918 (N)	Three-phase setpoint generator operation selected/active
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>Only for separately excited synchronous motors (p0300 = 5): The actual open-loop/closed-loop control mode is I/f control (open-loop) with a fixed current (p1300 = 18). The speed is entered via the setpoint channel and the current setpoint is given by the minimum current (p1620). It must be ensured that in this mode, the control dynamic performance is very limited. This is the reason that longer ramp-up times should be set for the setpoint speed than for normal operation. See also: p1620 (Stator current, minimum)</p>
Remedy:	<p>Select another open-loop/closed-loop control mode See also: p1300 (Open-loop/closed-loop control operating mode)</p>
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A07920 **Drive: Torque too low**
Reaction: NONE
Acknowledge: NONE
Cause: The torque deviates from the torque/speed envelope characteristic in the negative direction (too low).
See also: p2181 (Load monitoring, response)
Remedy: Adapt the load.

A07921 **Drive: Torque too high**
Reaction: NONE
Acknowledge: NONE
Cause: The torque deviates from the torque/speed envelope characteristic in the positive direction (too high).
Remedy: Adapt the load.

A07922 **Drive: Torque outside the tolerance**
Reaction: NONE
Acknowledge: NONE
Cause: The torque deviates from the torque/speed envelope characteristic.
Remedy: Adapt the load.

F07923 **Drive: Torque too low**
Reaction: OFF1 (NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: The torque deviates from the torque/speed envelope characteristic in the negative direction (too low).
Remedy: Adapt the load.

F07924 **Drive: Torque too high**
Reaction: OFF1 (NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: The torque deviates from the torque/speed envelope characteristic in the positive direction (too high).
Remedy: Adapt the load.

F07925 **Drive: Torque outside the tolerance**
Reaction: OFF1 (NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: The torque deviates from the torque/speed envelope characteristic.
Remedy: Adapt the load.

A07926 **Drive: Envelope curve, parameter invalid**
Reaction: NONE
Acknowledge: NONE
Cause: Invalid parameter values were entered for the envelope characteristic of the load monitoring.
The following rules apply for the speed thresholds:
p2182 < p2183 < p2184
The following rules apply for the torque thresholds:
p2185 > p2186
p2187 > p2188
p2189 > p2190
Alarm value (r2124, decimal):
Number of the parameter with the invalid value.
Remedy: Set the parameters for the load monitoring according to the applicable rules.

F07930	Drive: Braking signal error
Reaction:	OFF1 (NONE, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	<p>The Control Unit has detected a braking signal error.</p> <ul style="list-style-type: none"> - no motor holding brake connected. - motor holding brake type incorrectly parameterized. - the motor holding brake control on the Motor Module is faulty. - a DRIVE-CLiQ communications error has occurred between the Control Unit and the Motor Module involved. <p>Fault value (r0949, decimal):</p> <p>10: No brake connected or fault in the Motor Module brake control circuit ("open brake" operation).</p> <p>11: Defect in the brake control circuit of the Motor Module ("brake open" operation).</p> <p>20: Short-circuit in the brake winding or fault in the brake control circuit of the Motor Module ("brake open" state).</p> <p>30: No brake connected, short-circuit in the brake winding or fault in the Motor Module brake control circuit ("close brake" operation).</p> <p>31: Defect in the brake control circuit of the Motor Module ("close brake" operation).</p> <p>40: Defect in the brake control circuit of the Motor Module ("brake closed" state).</p> <p>50: Defect in the brake control circuit of the Motor Module or communications fault between the Control Unit and the Motor Module (braking signal diagnostics).</p> <p>See also: p1278 (Motor holding brake type)</p>
Remedy:	<ul style="list-style-type: none"> - check the motor holding brake connection. - check the motor holding brake type. - check the function of the motor holding brake. - check whether there is a DRIVE-CLiQ communications error between the Control Unit and the Motor Module involved and if required, carry-out a diagnostics routine for the faults identified. - check the electrical cabinet design and cable routing for EMC compliance - replace the Motor Module involved. - if a motor holding brake has still not been connected, then the brake control can be disabled with p1215 = 0 in order to suppress the fault (e.g. for a rotating measurement (p1960)). <p>Operation with Safe Brake Module:</p> <ul style="list-style-type: none"> - check the Safe Brake Modules connection. - replace the Safe Brake Module.
A07931	Brake does not open
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>This alarm is output for r1229.4 = 1.</p> <p>See also: p1216 (Motor holding brake, opening time), r1229 (Motor holding brake status word)</p>
Remedy:	<ul style="list-style-type: none"> - check the functionality of the motor holding brake. - check the feedback signal (p1223).
A07932	Brake does not close
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>This alarm is output for r1229.5 = 1.</p> <p>See also: p1217 (Motor holding brake closing time), r1229 (Motor holding brake status word)</p>
Remedy:	<ul style="list-style-type: none"> - check the functionality of the motor holding brake. - check the feedback signal (p1222).
F07935 (N)	Drv: Motor holding brake detected
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	<p>A motor with integrated motor holding brake was detected where the braking signal has not been configured (p1215 = 0). The braking signal configuration was then set to "motor holding brake the same as sequence control" (p1215 = 1).</p>
Remedy:	<p>None necessary.</p> <p>See also: p1215 (Motor holding brake configuration)</p>
Reaction upon N:	NONE
Acknowledge upon N:	NONE

F07940	Sync-line supply - drive: Synchronization error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	After synchronization has been completed, the phase difference (r3808) is greater than the threshold value, phase synchronism (p3813). OFF1 or OFF3 response, while the closed-loop phase control is active (r3819.6 = 1) or synchronism reached (r3819.2 = 1). Enable signal withdrawn (p3802 = 0), while the closed-loop phase control was active (r3819.6 = 1).
Remedy:	If required increase the threshold value phase synchronism (p3813) for synchronizing the line supply to the drive. Before OFF1 or OFF3, complete synchronizing (r03819.0 = 0). Before withdrawing the enable signal (p3802 = 0), reach synchronism (r3819.2 = 1). See also: p3813 (Sync line-drive phase synchronism threshold value)
A07941	Sync-line supply - drive: Target frequency not permissible
Reaction:	NONE
Acknowledge:	NONE
Cause:	The target frequency is outside the permissible value range. Alarm value (r2124, decimal): 1084: Target frequency greater than the positive speed limit, $f_{sync} > f_{max}$ (r1084). 1087: Target frequency less than the negative speed limit, $f_{sync} < f_{min}$ (r1087).
Remedy:	Fulfill the target frequency conditions for the synchronization line supply - drive. See also: r1084 (Speed limit positive effective), r1087 (Speed limit negative effective)
A07942	Sync-line supply - drive: Setpoint frequency is completely different than the target frequency
Reaction:	NONE
Acknowledge:	NONE
Cause:	There is a considerable difference between the setpoint frequency and the target frequency ($f_{set} \ll f_{target}$). The deviation that can be tolerated is set in p3806.
Remedy:	The alarm automatically disappears after the difference that can be tolerated (p3806) between the setpoint and target frequencies is reached. See also: p3806 (Sync line-drive frequency difference threshold value)
A07943	Sync-line supply - drive: Synchronization not permitted
Reaction:	NONE
Acknowledge:	NONE
Cause:	Synchronization not permitted. Alarm value (r2124, decimal): 1300: The control mode (p1300) has not been set to sensorless closed-loop speed control or U/f characteristic. 1910: Motor data identification activated. 1960: Speed controller optimization activated. 1990: Encoder adjustment activated. 3801: Voltage Sensing Module (VSM) not found. 3845: Friction characteristic plot activated.
Remedy:	Fulfill the conditions for the synchronization line supply - drive. Re alarm value = 1300: Set the control mode (p1300) to sensorless closed-loop speed control (p1300 = 20) or U/f characteristic (p1300 = 0 ... 19). Re alarm value = 1910: Exit the motor data identification routine (p1910). Re alarm value = 1960: Exit the speed controller optimization routine (p1960). Re alarm value = 1990: Exit the encoder adjustment (p1990). Re alarm value = 3801: Connect-up a Voltage Sensing Module (VSM) and when connecting to an adjacent drive object ensure that the drive objects have the same basis clock cycle. Re alarm value = 3845: Exit the friction characteristic plot (p3845).

F07950 (A)	Drive: Incorrect motor parameter
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The motor parameters were incorrectly entered while commissioning (e.g. p0300 = 0, no motor selected) Fault value (r0949, decimal): The fault value includes the parameter number involved. The following parameter numbers only occur as fault values for induction motors: p0304, p0310, p0320 The following parameter numbers only occur as fault values for synchronous motors: p0314; only for vector drives: p0305, p0307; only for servo drives: p0316, p0322, p0323; only for linear drives: p0315 See also: p0300 (Mot type selection), p0301 (Motor code number selection), p0304 (Rated motor voltage), p0305 (Rated motor current), p0307 (Rated motor power), p0310 (Rated motor frequency), p0311 (Rated motor speed), p0314 (Motor pole pair number), p0315 (Motor pole pair width), p0316 (Motor torque constant), p0320 (Motor rated magnetization current/short-circuit current), p0322 (Maximum motor speed), p0323 (Maximum motor current)
Remedy:	Compare the motor data with the rating plate data and if required, correct. See also: p0300 (Mot type selection), p0301 (Motor code number selection), p0304 (Rated motor voltage), p0305 (Rated motor current), p0307 (Rated motor power), p0310 (Rated motor frequency), p0311 (Rated motor speed), p0314 (Motor pole pair number), p0316 (Motor torque constant), p0320 (Motor rated magnetization current/short-circuit current), p0322 (Maximum motor speed), p0323 (Maximum motor current)
Reaction upon A:	NONE
Acknowledge upon A:	NONE
F07955	Drive: Motor has been changed
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The code number of the actual motor with DRIVE-CLiQ does not match the saved number. Fault value (r0949, decimal): Number of the incorrect parameter. See also: p0301 (Motor code number selection), r0302 (Motor code number of motor with DRIVE-CLiQ)
Remedy:	Connect the original motor, power-up the Control Unit again (POWER ON) and exit the quick commissioning by setting p0010 to 0. Or set p0300 = 10000 (load the motor parameter with DRIVE-CLiQ) and re-commission. Quick commissioning (p0010 = 1) is automatically exited with p3900 > 0. If quick commissioning was exited by setting p0010 to 0, then an automatic controller calculation (p0340 = 1) is not carried-out.
F07956	Drive: Motor code does not match the list (catalog) motor
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The motor code of the actual motor with DRIVE-CLiQ does not match the possible list motor types (refer to the selection, p0300). Fault value (r0949, decimal): Motor code of the motor with DRIVE-CLiQ
Remedy:	Use a motor with DRIVE-CLiQ and the matching motor code. The first three digits of the motor code generally correspond to the matching list motor type.

A07960	Drive: Incorrect friction characteristic
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The friction characteristic is incorrect.</p> <p>Alarm value (r2124, decimal): 1538: The friction torque is greater than the maximum from the upper effective torque limit (p1538) and zero. This is the reason that the output of the friction characteristic (r3841) is limited to this value.</p> <p>1539: The friction torque is less than the minimum from the lower effective torque limit (p1539) and zero. This is the reason that the output of the friction characteristic (r3841) is limited to this value.</p> <p>3820 ... 3829: Incorrect parameter number. The speeds entered in the parameters for the friction characteristic do not correspond to the following condition: $0.0 < p3820 < p3821 < \dots < p3829 \leq p0322$ or $p1082$, if $p0322 = 0$ Therefore the output of the friction characteristic (r3841) is set to zero.</p> <p>3830 ... 3839: Incorrect parameter number. The torques entered in the parameters for the friction characteristic do not correspond to the following condition: $0 \leq p3830, p3831 \dots p3839 \leq p0333$ Therefore the output of the friction characteristic (r3841) is set to zero. See also: r3840 (Friction characteristic, status word)</p>
Remedy:	<p>Fulfill the conditions for the friction characteristic.</p> <p>Re alarm value = 1538: Check the upper effective torque limit (e.g. in the field weakening range).</p> <p>Re alarm value = 1539: Check the lower effective torque limit (e.g. in the field weakening range).</p> <p>Re alarm value = 3820 ... 3839: Fulfill the conditions to set the parameters of the friction characteristic. If the motor data (e.g. the maximum speed p0322) are changed during commissioning ($p0010 = 1, 3$), then the technological limits and threshold values, dependent on this, must be re-calculated by selecting $p0340 = 5$.</p>
<hr/>	
A07961	Drive: Friction characteristic plot activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The automatic friction characteristic plot is activated.</p> <p>The friction characteristic is plotted at the next power-on command.</p>
Remedy:	<p>None necessary.</p> <p>The alarm disappears automatically after the friction characteristic plot has been successfully completed or the plot is de-activated ($p3845 = 0$).</p>

F07963	Drive: Friction characteristic plot interrupted
Reaction:	OFF1
Acknowledge:	IMMEDIATELY
Cause:	<p>The condition to plot the friction characteristic are not fulfilled.</p> <p>Fault value (r0949, decimal):</p> <p>0046: Missing enable signals (r0046).</p> <p>0840: OFF1 (p0840) is selected before the friction characteristic has been completely plotted.</p> <p>1082: The highest speed value to be approached (p3829) is greater than the maximum speed (p1082).</p> <p>1110: Friction characteristic plot, negative direction of rotation has be selected (p3845) and the negative direction of rotation is inhibited (p1110).</p> <p>1111: Friction characteristic plot, positive direction of rotation has be selected (p3845) and the positive direction of rotation is inhibited (p1111).</p> <p>1198: Friction characteristic plot selected (p3845 > 0) and the negative direction of rotation (p1110) and positive (p1111) are inhibited (r1198).</p> <p>1300: The control mode (p1300) has not been set to closed-loop speed control.</p> <p>1755: For sensorless closed-loop control (p1300 = 20), the lowest speed value to be approached (p3820) is less than or equal to the changeover speed, open-loop controlled operation (p1755).</p> <p>1910: Motor data identification activated.</p> <p>1960: Speed controller optimization activated.</p> <p>3820 - 3829: Speed (p382x) cannot be approached.</p> <p>3840: Friction characteristic incorrect.</p> <p>3845: Friction characteristic plot de-selected.</p>
Remedy:	<p>Fulfill the conditions to plot the friction characteristic.</p> <p>Re fault value = 0046: Establish missing enable signals.</p> <p>Re fault value = 0840: Select OFF1 (p0840) only after the friction characteristic plot has been completed.</p> <p>Re fault value = 1082: Select the highest speed value to be approached (p3829) less than or equal to the maximum speed (p1082).</p> <p>Re fault value = 1110: Select the frequency characteristic plot, positive direction of rotation (p3845).</p> <p>Re fault value = 1111: Select the frequency characteristic plot, negative direction of rotation (p3845).</p> <p>Re fault value = 1198: Enable the permitted direction of rotation (p1110, p1111, r1198).</p> <p>Re fault value = 1300: Set the control mode (p1300) on the closed-loop speed control (p1300 = 20, 21).</p> <p>Re fault value = 1755: For sensorless closed-loop speed control (p1300 = 20) select the lowest speed value to be approached (p3820) greater than the changeover speed of open-loop controlled operation (p1755).</p> <p>Re fault value = 1910: Exit the motor data identification routine (p1910).</p> <p>Re fault value = 1960: Exist the speed controller optimization routine (p1960).</p> <p>Re fault value 3820 - 3829: - check the load at speed p382x. - check the speed signal (r0063) for oscillation at speed p382x. If required, check the speed controller settings.</p> <p>Re fault value = 3840: Make the friction characteristic error-free (p3820 - p3829, p3830 - p3839, p3840).</p> <p>Re fault value = 3845: Activate the friction characteristic plot (p3845).</p>

F07966	Drive: Check the commutation angle
Reaction:	OFF2 (NONE)
Acknowledge:	IMMEDIATELY
Cause:	The speed actual value was inverted and the associated angular commutation offset is not equal to zero and is therefore possibly incorrect.
Remedy:	Angular commutation offset after the actual value inversion or determine it again (p1990=1).

F07967	Drive: Automatic encoder adjustment incorrect
Reaction:	OFF2 (NONE, OFF1)
Acknowledge:	IMMEDIATELY
Cause:	A fault has occurred during the automatic encoder adjustment or the pole position identification. Only for internal Siemens troubleshooting.
Remedy:	Carry-out a POWER ON.

F07968	Drive: Lq-Ld measurement incorrect
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A fault has occurred during the Lq-Ld measurement. Fault value (r0949, decimal): 10: Stage 1: The ratio between the measured current and zero current is too low. 12: Stage 1: The maximum current was exceeded. 15: Second harmonic too low. 16: Drive converter too small for the measuring technique. 17: Abort due to pulse inhibit.
Remedy:	Re fault value = 10: Check whether the motor is correctly connected. Replace the Motor Module involved. De-activate traversing (p1909). Re fault value = 12: Check whether motor data have been correctly entered. De-activate traversing (p1909). Re fault value = 16: De-activate traversing (p1909). Re fault value = 17: Repeat traversing.

F07969	Drive: Incorrect pole position identification
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A fault has occurred during the pole position identification routine. Fault value (r0949, decimal): 1: Current controller limited 2: Motor shaft locked. 4: Encoder speed signal not plausible. 10: Stage 1: The ratio between the measured current and zero current is too low. 11: Stage 2: The ratio between the measured current and zero current is too low. 12: Stage 1: The maximum current was exceeded. 13: Stage 2: The maximum current was exceeded. 14: Current difference to determine the +d axis too low. 15: Second harmonic too low. 16: Drive converter too small for the measuring technique. 17: Abort due to pulse inhibit. 18: First harmonic too low. 20: Pole position identification requested with the motor shaft rotating and activated flying restart function.
Remedy:	Re fault value = 1: Check whether the motor is correctly connected. Check whether motor data have been correctly entered. Replace the Motor Module involved. Re fault value = 2: Open the motor holding brake (p1215) and bring the motor into a no-load condition. Re fault value = 4: Check whether the encoder pulse number (p0408) and gearbox factor (p0432, p0433) are correct. Check whether the motor pole pair number is correct (p0314). Re fault value = 10: When selecting p1980 = 4: Increase the value for p0325. When selecting p1980 = 1: Increase the value for p0329. Check whether the motor is correctly connected.

Replace the Motor Module involved.
 Re fault value = 11:
 Increase the value for p0329.
 Check whether the motor is correctly connected.
 Replace the Motor Module involved.
 Re fault value = 12:
 When selecting p1980 = 4: Reduce the value for p0325.
 When selecting p1980 = 1: Reduce the value for p0329.
 Check whether motor data have been correctly entered.
 Re fault value = 13:
 Reduce the value for p0329.
 Check whether motor data have been correctly entered.
 Re fault value = 14:
 Increase the value for p0329.
 Re fault value = 15:
 Increase the value for p0325.
 Motor not sufficiently anisotropic, change the technique (p1980==1 or 10).
 Re fault value = 16:
 De-activate traversing/moving (p1982).
 Re fault value = 17:
 Repeat traversing.
 Re fault value 18:
 Increase the value for p0329.
 Saturation not sufficient, change the technique (p1980==10).
 Re fault value = 20:
 Before carrying-out a pole position identification routine ensure that the motor shaft is absolutely stationary (zero speed).

F07970	Drive: Automatic encoder adjustment incorrect
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>A fault has occurred during the automatic encoder adjustment. Fault value (r0949, decimal): 1: Current controller limited 2: Motor shaft locked. 4: Encoder speed signal not plausible. 10: Stage 1: The ratio between the measured current and zero current is too low. 11: Stage 2: The ratio between the measured current and zero current is too low. 12: Stage 1: The maximum current was exceeded. 13: Stage 2: The maximum current was exceeded. 14: Current difference to determine the +d axis too low. 15: Second harmonic too low. 16: Drive converter too small for the measuring technique. 17: Abort due to pulse inhibit.</p>
Remedy:	<p>Re fault value = 1: Check whether the motor is correctly connected. Check whether motor data have been correctly entered. Replace the Motor Module involved. Re fault value = 2: Open the motor holding brake (p1215) and bring the motor into a no-load condition. Re fault value = 4: Check whether the speed actual value inversion is correct (p0410.0). Check whether the motor is correctly connected. Check whether the encoder pulse number (p0408) and gearbox factor (p0432, p0433) are correct. Check whether the motor pole pair number is correct (p0314). Re fault value = 10: Increase the value for p0325. Check whether the motor is correctly connected. Replace the Motor Module involved. Re fault value = 11: Increase the value for p0329. Check whether the motor is correctly connected.</p>

Replace the Motor Module involved.
 Re fault value = 12:
 Reduce the value for p0325.
 Check whether motor data have been correctly entered.
 Re fault value = 13:
 Reduce the value for p0329.
 Check whether motor data have been correctly entered.
 Re fault value = 14:
 Increase the value for p0329.
 Re fault value = 15:
 Increase the value for p0325.
 Re fault value = 16:
 De-activate traversing/moving (p1982).
 Re fault value = 17:
 Repeat traversing.

A07971 (N) Drive: Automatic encoder adjustment activated

Reaction: NONE

Acknowledge: NONE

Cause: The automatic encoder adjustment is activated (p1990 = 1).
 The automatic encoder adjustment is carried-out with the next power-on command.
SERVO:
 If a pole position identification technique is selected in p1980, and if p0301 does not contain a motor type with an encoder adjusted in the factory, p1990 is automatically activated if fault F07414 is output.
 See also: p1990 (Angular commutation offset, commissioning support)

Remedy: None necessary.
 The alarm automatically disappears after the encoder has been successfully adjusted or for the setting p1990 = 0.

Reaction upon N: NONE

Acknowledge upon N: NONE

A07980 Drive: Rotating measurement activated

Reaction: NONE

Acknowledge: NONE

Cause: The rotating measurement (automatic speed controller optimization) is activated.
 The rotating measurement is carried-out at the next power-on command.
 See also: p1960 (Rotating measurement selection)

Remedy: None necessary.
 The alarm disappears automatically after the speed controller optimization has been successfully completed or for the setting p1900 = 0.

A07981 Drive: Enable signals for the rotating measurement missing

Reaction: NONE

Acknowledge: NONE

Cause: The rotating measurement cannot be started due to missing enable signals.

Remedy: - acknowledge faults that are present.
 - establish missing enable signals.
 See also: r0002 (Control Unit operating display), r0046 (Infeed missing enable signals)

F07982 Drive: Rotating measurement encoder test

Reaction: OFF1 (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: A fault has occurred during the encoder test.
 Fault value (r0949, decimal):
 1: The speed did not reach a steady-state condition.
 2: The speed setpoint was not able to be approached as the minimum limiting is active.
 3: The speed setpoint was not able to be approached as the suppression (skip) bandwidth is active.
 4: The speed setpoint was not able to be approached as the maximum limiting is active.
 5: The encoder does not supply a signal.
 6: Incorrect polarity.
 7: Incorrect pulse number.
 8: Encoder signal faults.
 9: Voltage Sensing Module (VSM) incorrectly connected.

Remedy: Re fault value = 1:
 - check the motor parameters.
 - carry-out a motor data identification routine (p1910).
 - if required, reduce the dynamic factor (p1967 < 25 %).
 Re fault value = 2:
 Adapt the speed setpoint (p1965) or minimum limiting (p1080).
 Re fault value = 3:
 Adapt the speed setpoint (p1965) or suppression (skip) bandwidths (p1091 ... p1094, p1101).
 Re fault value = 4:
 Adapt the speed setpoint (p1965) or maximum limiting (p1082, p1083 and p1086).
 Re fault value = 5:
 Check the encoder connection. If required, replace the encoder.
 Re fault value = 6:
 Check the connection assignment of the encoder cable. Adapt the polarity (p0410).
 Re fault value = 7:
 Adapt the pulse number (p0408).
 Re fault value = 8:
 Check the encoder connection and encoder cable. It is possible that there is a problem associated with the ground connection.
 Re fault value = 9:
 Check the connections of the Voltage Sensing Module (VSM).
Note:
 The encoder test can be switched-out (disabled) using p1959.0.
 See also: p1959 (Rotating measurement configuration)

F07983 Drive: Rotating measurement saturation characteristic

Reaction: OFF1 (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: A fault has occurred while determining the saturation characteristic.
 Fault value (r0949, decimal):
 1: The speed did not reach a steady-state condition.
 2: The rotor flux did not reach a steady-state condition.
 3: The adaptation circuit did not reach a steady-state condition.
 4: The adaptation circuit was not enabled.
 5: Field weakening active.
 6: The speed setpoint was not able to be approached as the minimum limiting is active.
 7: The speed setpoint was not able to be approached as the suppression (skip) bandwidth is active.
 8: The speed setpoint was not able to be approached as the maximum limiting is active.
 9: Several values of the determined saturation characteristic are not plausible.
 10: Saturation characteristic could not be sensibly determined because load torque too large.

Remedy:

Re fault value = 1:
 - the total drive moment of inertia is far higher than that of the motor (refer to p0341, p0342).
 De-select rotating measurement (p1960), enter the moment of inertia p342, re-calculate the speed controller p0340 = 4 and repeat the measurement.

Re fault value = 1 ... 4:
 - check the motor parameters (rating plate data).
 - carry-out a motor data identification routine (p1910).
 - if required, reduce the dynamic factor (p1967 < 25 %).

Re fault value = 5:
 The speed setpoint (p1961) is too high. Reduce the speed.

Re fault value = 6:
 Adapt the speed setpoint (p1961) or minimum limiting (p1080).

Re fault value = 7:
 Adapt the speed setpoint (p1961) or suppression (skip) bandwidths (p1091 ... p1094, p1101).

Re fault value = 8:
 Adapt the speed setpoint (p1961) or maximum limiting (p1082, p1083 and p1086).

Re fault value = 9, 10:
 The measurement was carried-out at an operating point where the load torque is too high. Select a more suitable operating point, either by changing the speed setpoint (p1961) or by reducing the load torque. The load torque may not be varied while making measurements.

Note:
 The saturation characteristic identification routine can be disabled using p1959.1.
 See also: p1959 (Rotating measurement configuration)

F07984 Drive: Speed controller optimization, moment of inertia

Reaction: OFF1 (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: A fault has occurred while identifying the moment of inertia.
 Fault value (r0949, decimal):

- 1: The speed did not reach a steady-state condition.
- 2: The speed setpoint was not able to be approached as the minimum limiting is active.
- 3: The speed setpoint was not able to be approached as the suppression (skip) bandwidth is active.
- 4: The speed setpoint was not able to be approached as the maximum limiting is active.
- 5: It is not possible to increase the speed by 10% as the minimum limiting is active.
- 6: It is not possible to increase the speed by 10% as the suppression (skip) bandwidth is active.
- 7: It is not possible to increase the speed by 10% as the maximum limiting is active.
- 8: The torque difference after the speed setpoint step is too low in order to be able to still reliably identify the moment of inertia.
- 9: Too few data to be able to reliably identify the moment of inertia.
- 10: After the setpoint step, the speed either changed too little or in the incorrect direction.
- 11: The identified moment of inertia is not plausible.

Remedy:

Re fault value = 1:
 - check the motor parameters (rating plate data).
 - carry-out a motor data identification routine (p1910).
 - if required, reduce the dynamic factor (p1967 < 25 %).

Re fault value = 2, 5:
 Adapt the speed setpoint (p1965) or minimum limiting (p1080).

Re fault value = 3, 6:
 Adapt the speed setpoint (p1965) or suppression (skip) bandwidths (p1091 ... p1094, p1101).

Re fault value = 4, 7:
 Adapt the speed setpoint (p1965) or maximum limiting (p1082, p1083 and p1086).

Re fault value = 8:
 Adapt the moment of inertia (p0341, p0342).

Note:
 The moment of inertia identification routine can be disabled using p1959.2.
 See also: p1959 (Rotating measurement configuration)

F07985 Drive: Speed controller optimization (oscillation test)

Reaction: OFF1 (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: A fault has occurred during the vibration test.
 Fault value (r0949, decimal):
 1: The speed did not reach a steady-state condition.
 2: The speed setpoint was not able to be approached as the minimum limiting is active.
 3: The speed setpoint was not able to be approached as the suppression (skip) bandwidth is active.
 4: The speed setpoint was not able to be approached as the maximum limiting is active.
 5: Torque limits too low for a torque step.
 6: No suitable speed controller setting was found.

Remedy: Re fault value = 1:
 - check the motor parameters.
 - carry-out a motor data identification routine (p1910).
 - if required, reduce the dynamic factor (p1967 < 25 %).
 Re fault value = 2:
 Adapt the speed setpoint (p1965) or minimum limiting (p1080).
 Re fault value = 3:
 Adapt the speed setpoint (p1965) or suppression (skip) bandwidths (p1091 ... p1094, p1101).
 Re fault value = 4:
 Adapt the speed setpoint (p1965) or maximum limiting (p1082, p1083 and p1086).
 Re fault value = 5:
 Increase the torque limits (e.g. p1520, p1521).
 Re fault value = 6:
 Reduce the dynamic factor (p1967).
 Note:
 The speed controller vibration test can be disabled using p1959.4.
 See also: p1959 (Rotating measurement configuration)

F07986 Drive: Rotating measurement ramp-function generator

Reaction: OFF1 (NONE, OFF2)

Acknowledge: IMMEDIATELY

Cause: During the rotating measurements, problems with the ramp-function generator occurred.
 Fault value (r0949, decimal):
 1: The positive and negative direction of rotation is inhibited.

Remedy: Re fault value = 1:
 Enable the direction of rotation (p1110 or p1111).

A07987 Drive: Rotating measurement, no encoder available

Reaction: NONE

Acknowledge: NONE

Cause: No encoder available. The rotating measurement was carried-out without encoder (sensorless).
 Alarm value (r2124, decimal):
 1: An encoder is not connected.
 2: It involves a SINAMICS G drive unit that only supports sensorless closed-loop control.

Remedy: Re alarm value = 1:
 Connect-up the encoder.
 Re alarm value = 2:
 None necessary.

F07988 Drive: Rotating measurement, no configuration selected

Reaction: OFF2 (NONE, OFF1)

Acknowledge: IMMEDIATELY

Cause: When configuring the rotating measurement (p1959), no function was selected.

Remedy: Select at least one function for automatic optimization of the speed controller (p1959).
 See also: p1959 (Rotating measurement configuration)

F07990 Drive: Incorrect motor data identification**Reaction:** OFF2 (NONE, OFF1)**Acknowledge:** IMMEDIATELY**Cause:** A fault has occurred during the identification routine.

Fault value (r0949, decimal):

1: Current limit value reached.

2: Identified stator resistance lies outside the expected range 0.1 ... 100 % of Z_n .3: Identified rotor resistance lies outside the expected range 0.1 ... 100 % of Z_n .4: Identified stator reactance lies outside the expected range 50 ... 500 % of Z_n .5: Identified magnetizing reactance lies outside the expected range 50 ... 500 % of Z_n .

6: Identified rotor time constant lies outside the expected range 10 ms ... 5 s.

7: Identified total leakage reactance lies outside the expected range 4 ... 50 % of Z_n .8: Identified stator leakage reactance lies outside the expected range 2 ... 50 % of Z_n .9: Identified rotor leakage reactance lies outside the expected range 2 ... 50 % of Z_n .

10: Motor has been incorrectly connected.

11: Motor shaft rotates.

20: Identified threshold voltage of the semiconductor devices lies outside the expected range 0 ... 10 V.

30: Current controller in voltage limiting.

40: At least one identification contains errors. The identified parameters are not saved to prevent inconsistencies.

50: With the selected current controller sampling rate, the pulse frequency cannot be implemented.

Note:

Percentage values are referred to the rated motor impedance:

 $Z_n = V_{mot,nom} / \sqrt{3} / I_{mot,nom}$

101: Voltage amplitude even at 30% maximum current amplitude is too low to measure the inductance.

102, 104: Voltage limiting while measuring the inductance.

103: Maximum frequency exceeded during the rotating inductance measurement.

110: Motor not finely synchronized before the rotating measurement.

120: Error when evaluating the magnetizing inductance.

125: Cable resistance greater than the total resistance.

126: Series inductance greater than the total leakage inductance.

127: Identified leakage inductance negative.

128: Identified stator resistance negative.

129: Identified rotor resistance negative.

130: Drive data set changeover during the motor data identification routine.

140: The setpoint channel inhibits both directions of rotation.

160: Accelerating time when determining the moment of inertia or reluctance torque too short.

173: Internal problem.

180: Identification speed (maximum speed, rated speed, $0.9 \cdot p0348$) less than $p1755$.

190: Speed setpoint not equal to zero.

191: An actual speed of zero is not reached.

192: Speed setpoint not reached.

200, 201: Not possible to identify the voltage emulation error characteristic of the drive converter ($p1952$, $p1953$).**Remedy:**

Re fault value = 0:

Check whether the motor is correctly connected. Observe the configuration (star-delta).

Re fault value = 1 ... 40:

- check whether the motor data have been correctly entered into $p0300$, $p0304$ - $p0311$.

- is there an appropriate relationship between the motor power rating and that of the Motor Module? The ratio of the Motor Module to the rated motor current should not be less than 0.5 and should not be greater than 4.

- check the motor configuration (star-delta).

Re fault value = 4, 7:

Check whether inductances are correctly entered in $p0233$ and $p0353$.

Re fault value = 50:

Reduce the current controller sampling rate.

Re fault value = 101:

Increase current limit ($p0640$).Check the current controller gain ($p1715$).Reduce the current controller sampling time ($p0115$).

It may be impossible to completely identify the L characteristic, as the required current amplitude is too high.

Suppress measurement ($p1909$, $p1959$).

Re fault value = 102, 104:

Reduce the current limit ($p0640$).

Check the current controller P gain.

Suppress measurement (p1909, p1959).
 Re fault value = 103:
 Increase the external moment of inertia (if possible).
 Reduce the current controller sampling time (p0115).
 Suppress measurement (p1909, p1959).
 Re fault value 110:
 Before the rotating measurement, traverse the motor over the zero mark.
 Re fault value 120:
 Check the current controller P gain (p1715) and if required, reduce.
 Increase the pulse frequency (p1800).
 Re fault 125:
 Reduce the cable resistance (p0352).
 Re fault 126:
 Reduce the series inductance (p0353).
 Re fault 127, 128, 129:
 It is possible that the current controller is oscillating. Reduce p1715 before the next measurement.
 Re fault 130:
 Do not initiate a drive data set changeover during the motor identification routine.
 Re fault value 140:
 Before the measurement, enable at least one direction of rotation (value of p1110 = 0 or value of p1111 = 0 or p1959.14 = 1 or p1959.15 = 1).
 Re fault value = 160:
 Extend the accelerating time when determining the moment of inertia and reluctance torque, e.g. by increasing the maximum speed (p1082), increasing the moment of inertia or reducing the maximum current (p0640).
 Increase the speed controller P-gain (p1460).
 Suppress measurement (p1959).
 Re fault value 173:
 -
 Re fault value 180:
 Increase the maximum speed (p1082).
 Reduce p1755.
 Suppress measurement (p1909, p1959).
 Re fault value 190:
 Set the speed setpoint to zero.
 Re fault value 191:
 Do not start the motor data identification routine while the motor is still rotating.
 Re fault value = 192:
 Check the closed-loop speed control (the motor rotor may be locked or the closed-loop speed control is not functioning).
 Ensure that the enable signals are present during the measurement.
 Remove any pulling loads from the motor.
 Increase the maximum current (p0640).
 Reduce the maximum speed (p1082).
 Suppress measurement (p1959).
 Re fault value = 200, 201:
 - set the pulse frequency to $0.5 \cdot$ current controller frequency (e.g. 4 kHz for a current controller clock cycle of 125 us).
 - reduce the cable length between the Motor Module and the motor.
 - read-out measured values (r1950, r1951) and therefore determine suitable values for p1952, p1953 according to your own estimation.

A07991 (N)	Drive: Motor data identification activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	The motor data identification routine is activated. The motor data identification routine is carried-out at the next power-on command. See also: p1910 (Motor data identification routine, stationary (standstill))
Remedy:	None necessary. The alarm automatically disappears after the motor data identification routine has been successfully completed or for the setting p1910 = 0 or p1960 = 0.
Reaction upon N:	NONE
Acknowledge upon N:	NONE

F07993	Drive: Incorrect direction of rotation of the field or encoder actual value inversion
Reaction:	OFF2 (NONE)
Acknowledge:	IMMEDIATELY
Cause:	Either the direction of the rotating field or the encoder actual value has an incorrect sign. The motor data identification automatically changed the actual value inversion (p0410) in order to correct the control sense. This can result in a direction of rotation change. To acknowledge this fault, the correctness of the direction of rotation must first be acknowledged with p1910 = -2.
Remedy:	Check the direction of rotation, also for the position controller, if one is being used. If the direction of rotation is correct, the following applies: No additional measures are required (except p1910 = -2 and acknowledge fault). If the direction of rotation is incorrect, the following applies: To change the direction of rotation, two phases must be interchanged and the motor identification routine must be repeated.

F07995	Drive: Pole position identification not successful
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The pole position identification routine was unsuccessful. Fault value (r0949, decimal): 1: No current is established. 2: The starting current is not zero. 3: The selected maximum distance was exceeded (p1981). 4x: The measuring signal does not permit a clear evaluation. 5: The maximum current was exceeded during the measurement. 6: The current measurement must be re-calibrated. 7x: The Sensor Module does not support the pole position identification routine. 70 ... 79: Only for internal Siemens troubleshooting. 8: The pole position identification routine current required is greater than the maximum current. 9: The set pole position identification routine current is zero. 10: Data set changeover during the pole position identification 100: Motion-based pole position identification, 1st and 2nd measurement different. Motor locked or current (p1993) too low. 101: Motion-based position position identification, insufficient motion, motor locked or current (p1993) too low. 102: Motion-based pole position identification, brake is being used and is closed. The motion-based position position identification in conjunction with the brake is not permitted. 103: Motion-based pole position identification without encoder. 104: Motion-based pole position identification, speed actual value not zero after stabilizing time. Note: x = 0 ... 9
Remedy:	Re fault value = 1: Check the motor connection and DC link voltage. For the following parameters, set practical values that are not zero (p0325, p0329). Re fault value = 3: Increase the maximum distance (p1981). Reduce the currents for the pole position identification routine (p0325, p0329). Stop the motor in order to carry-out the pole position identification routine. Re fault value = 40 ... 49: Increase the currents for the pole position identification routine (p0325, p0329). Stop the motor in order to carry-out the pole position identification routine. Select another technique for pole position identification routine (p1980). Use another motor, absolute encoder or Hall sensors. Re fault value = 5: Reduce the currents for the pole position identification routine (p0325, p0329). Re fault value = 6: Re-calibrate the Motor Module. Re fault value = 7x: Upgrade the software in the Sensor Module. Re fault value = 8: Reduce the currents for the pole position identification routine (p0329, p0325, p1993). The power unit cannot provide the necessary pole position identification routine current (p0209 < p0329, p0325, p1993), replace the power unit by a power unit with a higher maximum current.

List of faults and alarms

Re fault value = 9:
 Enter a value not equal to zero in the pole position identification routine current (p0329, p0325, p1993).
 Re fault value = 10:
 Do not initiate a data set changeover during the pole position identification.
 Re fault value = 100, 101:
 Check and ensure that the motor is free to move.
 Increase the current for motion-based pole position identification (p1993).
 Re fault value = 102:
 If the motor is to be operated with a brake: Select a different technique to identify the pole position (p1980).
 If the motor can be operated without a brake: Open the brake (p1215 = 2).
 Re fault value = 103:
 The motion-based pole position identification can only be carried-out using an encoder. Connect an encoder or select another technique for pole position identification routine (p1980).
 Re fault value = 104:
 Pole position identification, increase the smoothing time, motion-based (p1997).
 Pole position identification, increase the rise time, motion-based (p1994).
 Pole position identification, check the gain, motion-based (p1995).
 Pole position identification, check the integral time, motion-based (p1996).

F07996 Drive: Pole position identification routine not carried-out
Reaction: ENCODER (OFF2)
Acknowledge: IMMEDIATELY
Cause: The drive was changed over, flying, from sensorless operation to operation with encoder without having previously carried-out a pole position identification for the encoder. p1404 is then at a value between zero and the maximum speed and the pulses in the speed range above p1404 were enabled without a pole position identification routine having been previously carried-out in operation with encoder.
Remedy: For a flying changeover between operation with and without encoder with pole position identification after POWER ON or commissioning (p0010 not equal to zero) enable the pulses once at zero speed. This means that the pole position identification routine is carried-out and the result is available for operation.

F08000 (N, A) TB: +/-15 V power supply faulted
Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: Terminal Board 30 detects an incorrect internal power supply voltage.
 Fault value (r0949, decimal):
 0: Error when testing the monitoring circuit.
 1: Fault in normal operation.
Remedy:
 - replace Terminal Board 30.
 - replace Control Unit.
 Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F08010 (N, A) TB: Analog-digital converter
Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The analog/digital converter on Terminal Board 30 has not supplied any converted data.
Remedy:
 - check the power supply.
 - replace Terminal Board 30.
 Reaction upon N: NONE
 Acknowledge upon N: NONE

Reaction upon A: NONE
Acknowledge upon A: NONE

F08500 (A) COMM BOARD: Monitoring time, configuration expired

Reaction: A_INFEED: OFF1 (OFF2)
SERVO: OFF1 (OFF2, OFF3)
VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The monitoring time for the configuration has expired.
Fault value (r0949, decimal):
0: The transfer of the send-configuration data has been exceeded (time).
1: The transfer of the receive-configuration data has been exceeded (time).

Remedy: Check communication line.

Reaction upon A: NONE
Acknowledge upon A: NONE

F08501 (A) COMM BOARD: Monitoring time, process data expired

Reaction: A_INFEED: OFF1 (OFF2)
SERVO: OFF1 (OFF2, OFF3)
VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The set monitoring time expired while transferring process data via COMM BOARD.
See also: p2040 (COMM INT monitoring time)

Remedy: - check communications link.
- check the set monitoring time if the error persists.
See also: p2040 (COMM INT monitoring time)

Reaction upon A: NONE
Acknowledge upon A: NONE

F08502 (A) COMM BOARD: Monitoring time, sign-of-life expired

Reaction: A_INFEED: OFF1 (OFF2)
SERVO: OFF1 (OFF2, OFF3)
VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The monitoring time for the sign-of-life counter has expired.

Remedy: Check communication line.

Reaction upon A: NONE
Acknowledge upon A: NONE

A08504 (F) COMM BOARD: Internal cyclic data transfer error

Reaction: NONE

Acknowledge: NONE

Cause: The cyclic actual and/or setpoint values were not transferred within the specified times.
Alarm value (r2124, decimal):
Only for internal Siemens troubleshooting.

Remedy: Check the parameterizing telegram (Ti, To, Tdp, etc.).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE (OFF1, OFF2, OFF3)
VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY

F08510 (A) COMM BOARD: Send configuration data invalid

Reaction: A_INFEED: OFF1 (OFF2)
 SERVO: OFF1 (OFF2, OFF3)
 VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: COMM BOARD did not accept the send-configuration data.
 Fault value (r0949, decimal):
 Return value of the send-configuration data check.

Remedy: Check the send configuration data.

Reaction upon A: NONE

Acknowledge upon A: NONE

A08511 (F) COMM BOARD: Receive configuration data invalid

Reaction: NONE

Acknowledge: NONE

Cause: The drive unit did not accept the receive-configuration data.
 Alarm value (r2124, decimal):
 Return value of the receive-configuration data check.
 0: Configuration accepted.
 1: Connection established to more drive objects than configured in the device. The drive objects for process data exchange and their sequence was defined using p0978.
 2: Too many data words for input or output to a drive object. A max. of 16 words is permitted for SERVO and VECTOR; max. 5 words, for A_INFEED, TB30, TM31 and CU320.
 3: Uneven number of bytes for input or output.
 4: Setting data for synchronization not accepted.
 5: Drive still not in cyclic operation.
 6: Buffer system not accepted.
 7: Cyclic channel length too short for this setting.
 8: Cyclic channel address not initialized.
 9: 3-buffer system not permitted.
 10: DRIVE-CLiQ fault.
 11: CU link fault.
 12: CX32 not in cyclic operation.

Remedy: Check the receive configuration data.
 Re alarm value = 1:
 Check the list of the drive objects with process data exchange (p0978). With p0978[x] = 0, all of the following drive objects in the list are excluded from the process data exchange.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY

A08520 (F) COMM BOARD: Non-cyclic channel error

Reaction: NONE

Acknowledge: NONE

Cause: The memory or the buffer status of the non-cyclic channel has an error.
 Alarm value (r2124, decimal):
 0: Error in the buffer status.
 1: Error in the memory.

Remedy: Check communication line.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY

A08530 (F) COMM BOARD: Message channel error

Reaction: NONE
Acknowledge: NONE
Cause: The memory or the buffer status of the message channel has an error.
 Alarm value (r2124, decimal):
 0: Error in the buffer status., 1: Error in the memory.
Remedy: Check communication line.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY

F08700 (A) CBC: Communications error

Reaction: A_INFEED: NONE
 SERVO: OFF3 (NONE, OFF1, OFF2)
 VECTOR: OFF3 (NONE, OFF1, OFF2)
Acknowledge: IMMEDIATELY
Cause: A CAN communications error has occurred.
 Fault value (r0949, decimal):
 1: The error counter for the send telegrams has exceeded the BUS OFF value 255. The bus disables the CAN controller.
 - bus cable interrupted.
 - bus cable not connected.
 - incorrect baud rate.
 - incorrect bit timing.
 2: The master no longer interrogated the CAN node status longer than for its "life time". The "life time" is obtained from the "guard time" (p8604[0]) multiplied by the "life time factor" (p8604[1]).
 - bus cable interrupted.
 - bus cable not connected.
 - incorrect baud rate.
 - incorrect bit timing.
 - master fault.
Note:
 The fault response can be set as required using p8641.
 See also: p8604 (CBC node guarding), p8641 (CBC abort connection option code)
Remedy:
 - check the bus cable
 - check the baud rate (p8622).
 - check the bit timing (p8623).
 - check the master.
 See also: p8622 (CBC baud rate), p8623 (CBC bit timing selection)
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F08701 CBC: NMT state change

Reaction: A_INFEED: OFF2
 SERVO: OFF3
 VECTOR: OFF3
Acknowledge: IMMEDIATELY
Cause: A CANopen NMT state transition from "operational" to "pre-operational" or after "stopped".
 Fault value (r0949, decimal):
 1: CANopen NMT state transition from "operational" to "pre-operational".
 2: CANopen NMT state transition from "operational" to "stopped".
Note:
 In the NMT state "pre-operational", process data cannot be transferred and in the NMT state "stopped", no process data and no service data can be transferred.
Remedy: None necessary.
 Acknowledge the fault and continue operation.

A08751	CBC: Telegram loss
Reaction:	NONE
Acknowledge:	NONE
Cause:	The CAN controller has lost a receive message (telegram).
Remedy:	Reduce the cycle times of the receive messages.
A08752	CBC: Error counter for error passive exceeded
Reaction:	NONE
Acknowledge:	NONE
Cause:	The error counter for the send or receive telegrams has exceeded the value 127.
Remedy:	<ul style="list-style-type: none"> - check the bus cable - set a higher baud rate (p8622). - check the bit timing and if required optimize (p8623). See also: p8622 (CBC baud rate), p8623 (CBC bit timing selection)
A08753	CBC: Message buffer overflow
Reaction:	NONE
Acknowledge:	NONE
Cause:	A message buffer overflow. Alarm value (r2124, decimal): 1: Non-cyclic send buffer (SDO response buffer) overflow. 2: Non-cyclic receive buffer (SDO receive buffer) overflow. 3: Cyclic send buffer (PDO send buffer) overflow.
Remedy:	Check the bus cable. Set a higher baud rate (p8622). Check the bit timing and if required optimize (p8623). Re alarm value = 2: - reduce the cycle times of the SDO receive messages. See also: p8622 (CBC baud rate), p8623 (CBC bit timing selection)
A08754	CBC: Incorrect communications mode
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the "operational" mode, an attempt was made to change parameters p8700 ... p8737.
Remedy:	Change into the "pre-operational" or "stopped" mode.
A08755	CBC: Obj cannot be mapped
Reaction:	NONE
Acknowledge:	NONE
Cause:	The CANopen object is not provided for the Process Data Object (PDO) Mapping.
Remedy:	Use a CANopen object intended for the PDO mapping or enter 0. The following objects can be mapped in the Receive Process Data Object (RPDO) or Transmit Process Data Object (TPDO): - RPDO: 6040 hex, 6060 hex, 60FF hex, 6071 hex. - TPDO: 6041 hex, 6061 hex, 6063 hex, 6069 hex, 606B hex, 606C hex, 6074 hex. Note: As long as A08755 is present, the COB-ID cannot be set to valid.
A08756	CBC: Number of mapped bytes exceeded
Reaction:	NONE
Acknowledge:	NONE
Cause:	The number of bytes of the mapped objects exceeds the telegram size for net data. A maximum of 8 bytes is permissible.

Remedy: Map fewer objects or objects with a smaller data type.
 See also: p8710 (CBC receive mapping for RPDO 1), p8711 (CBC receive mapping for RPDO 2), p8712 (CBC receive mapping for RPDO 3), p8713 (CBC receive mapping for RPDO 4), p8714 (CBC receive mapping for RPDO 5), p8715 (CBC receive mapping for RPDO 6), p8716 (CBC receive mapping for RPDO 7), p8717 (CBC receive mapping for RPDO 8), p8730 (CBC send mapping for TPDO 1), p8731 (CBC send mapping for TPDO 2), p8732 (CBC send mapping for TPDO 3), p8733 (CBC send mapping for TPDO 4), p8734 (CBC send mapping for TPDO 5), p8735 (CBC send mapping for TPDO 6), p8736 (CBC send mapping for TPDO 7), p8737 (CBC send mapping for TPDO 8)

A08757 CBC: Set COB-ID invalid

Reaction: NONE
Acknowledge: NONE
Cause: For online operation, the appropriate COB-ID must be set invalid before mapping.
 Example:
 Mapping for RPDO 1 should be changed (p8710[0]).
 --> set p8700[0] = C00006E0 hex (invalid COB-ID)
 --> set p8710[0] as required.
 --> p8700[0] enter a valid COB-ID
Remedy: Set the COB-ID to invalid.

A08758 CBC: Number of PDO channels too low

Reaction: NONE
Acknowledge: NONE
Cause: The number of PDO channels in p8740 has either been set to 0 or too low.
 See also: p8740 (CBC channel assignment)
Remedy: The number of channels set in p8740 must be greater than or equal to the number of PDOs.
 There are 2 possibilities:
 Increase the number of channels in p8740 and confirm the selection using p8741.
 Reduce the number of PDOs by setting the COB-ID to invalid.
 See also: p8740 (CBC channel assignment), p8741 (CBC PDO configuration acknowledgement)

A08759 CBC: PDO COB-ID already available

Reaction: NONE
Acknowledge: NONE
Cause: An existing PDO COB-ID was allocated.
Remedy: Select another PDO COB-ID.

A13000 License not adequate

Reaction: NONE
Acknowledge: NONE
Cause: - for the drive unit, the options that require a license are being used but the licenses are not sufficient.
 - an error occurred when checking the existing licenses.
 Alarm value (r2124, decimal):
 0:
 The existing license is not sufficient.
 1:
 An adequate license was not able to be determined as the CompactFlash card with the required licensing data was withdrawn in operation.
 2:
 An adequate license was not able to be determined, as an error occurred when reading-out the required licensing data from the CompactFlash card.
 3:
 An adequate license was not able to be determined as there is a checksum error in the license key.
 4:
 An internal error occurred when checking the license.

Remedy:

- Alarm value 0:
Additional licenses are required and these must be activated (p9920, p9921).
- Alarm value 1:
With the system powered-down, re-insert the CompactFlash card that matches the system.
- Alarm value 2:
Enter and activate the license key (p9920, p9921).
- Alarm value 3:
Compare the license key (p9920) entered with the license key on the certificate of license.
Re-enter the license key and activate (p9920, p9921).
- Alarm value 4:
- carry-out a POWER ON.
- upgrade the firmware release.
- contact the Hotline.

A13001 Error in license checksum

Reaction: NONE
Acknowledge: NONE
Cause: When checking the checksum of the license key, an error was detected.
Remedy: Compare the license key (p9920) entered with the license key on the certificate of license.
 Re-enter the license key and activate (p9920, p9921).

F30001 Power unit: Overcurrent

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The power unit has detected an overcurrent condition.
 - closed-loop control is incorrectly parameterized.
 - motor has a short-circuit or fault to ground (frame).
 - U/f operation: Up ramp set too low.
 - U/f operation: Rated motor current is significantly greater than that of the Motor Module.
 - infeed: High discharge and post-charging current for line supply voltage interruptions.
 - infeed: High post-charging currents for overload when motoring and DC link voltage dip.
 - infeed: Short-circuit currents at power-on due to the missing commutating reactor.
 - power cables are not correctly connected.
 - power cables exceed the maximum permissible length.
 - power unit defective.
Fault value (r0949):
 Bit 0: Phase U.
 Bit 1: Phase V.
 Bit 2: Phase W.

Remedy:

- check the motor data - if required, carry-out commissioning.
- check the motor circuit configuration (star-delta).
- U/f operation: Increase up ramp.
- U/f operation: Check the assignment of the rated currents of the motor and Motor Module.
- infeed: Check the line supply quality.
- infeed: Reduce the load when motoring.
- infeed: Correct connection of the line commutating reactor.
- check the power cable connections.
- check the power cables for short-circuit or ground fault.
- check the length of the power cables.
- replace power unit.

F30002 Power unit: DC link overvoltage

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The power unit has detected an overvoltage condition in the DC link.

- motor regenerates too much energy.
- line supply voltage too high.
- when operating with a VSM, the phase assignment L1, L2, L3 at the VSM differs from the phase assignment at the power unit.

Fault value (r0949, decimal):
 DC link voltage [1 bit = 100 mV].
 For SINAMICS GM/SM, the following applies:
 Fault value (r0949, decimal):
 32: Overvoltage in the negative partial DC link (VdcP)
 64: Overvoltage in the positive partial DC link (VdcN)
 96: Overvoltage in both partial -DC links

Remedy:

- increase the ramp-down time.
- activate the DC link voltage controller.
- use a brake resistor or Active Line Module.
- increase the current limit of the infeed or use a larger module (for the Active Line Module).
- check the line supply voltage.
- check and correct the phase assignment at the VSM and at the power unit.

See also: p0210 (Drive unit line supply voltage), p1240 (Vdc controller or Vdc monitoring configuration)

F30003 Power unit: DC link undervoltage

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The power unit has detected an undervoltage condition in the DC link.

- line supply failure
- line supply voltage below the permissible value.
- line supply infeed failed or faulted.

Note:

The monitoring threshold for the DC link undervoltage is the minimum of the following values:

- 85% of the unit supply voltage (p0210).
- lowest permissible lower DC link voltage of the power units (descriptive data).

Remedy:

- check the line supply voltage
- check the line supply infeed and if necessary observe the fault messages of the line supply infeed.

Note:
 The ready signal of the infeed r0863 must be connected to the associated inputs p0864 of the drives.
 See also: p0210 (Drive unit line supply voltage)

F30004 Power unit: Overtemperature heatsink AC inverter

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The temperature of the power unit heatsink has exceeded the permissible limit value.

- insufficient cooling, fan failure.
- overload
- ambient temperature too high.
- pulse frequency too high.

Fault value (r0949):

Temperature [1 bit = 0.01 °C].

Remedy:

- check whether the fan is running.
- check the fan elements
- check whether the ambient temperature is in the permissible range.
- check the motor load.
- reduce the pulse frequency if this is higher than the rated pulse frequency.

Notice:

This fault can only be acknowledged after this alarm threshold for alarm A05000 has been fallen below.
 See also: p1800 (Pulse frequency)

F30005	Power unit: I2T overload
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The power unit was overloaded (r0036 = 100 %). - the permissible rated power unit current was exceeded for an inadmissibly long time. - the permissible load duty cycle was not maintained. Fault value (r0949, decimal): I2t [100 % = 16384].
Remedy:	- reduce the continuous load. - adapt the load duty cycle. - check the motor and power unit rated currents. See also: r0036 (Power unit overload I2t), r0206 (Rated power unit power), p0307 (Rated motor power)
F30006	Power unit: Thyristor Control Board
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The thyristor control board of the Basic Line Module signals a fault. - there is not line supply voltage. - the line contactor is not closed. - the line supply voltage is too low. - line supply frequency outside the permissible range (45 ... 66 Hz). - there is a DC link short-circuit. - there is a DC link short-circuit (during the pre-charging phase). - power supply thyristor control board outside the nominal range (5 ... 18 V) and supply voltage >30 V. - there is an internal fault in the thyristor control board.
Remedy:	The faults are saved in the TCB and are acknowledged by switching-out the TCB supply voltage for at least 10 s! - check the line supply voltage - check or energize the line contactor. - check the monitoring time and, if required, increase (p0857). - if required, observe additional power unit messages/signals. - check the DC link regarding short-circuit or ground fault. - observe the LED fault display of the thyristor control board.
F30008	Power unit: Sign-of-life error, cyclic data
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (OFF1, OFF2, OFF3) VECTOR: NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. The cyclic setpoint telegrams of the Control Unit were not received on time by the power unit for at least two clock cycles within a time interval of 20 ms.
Remedy:	- check the electrical cabinet design and cable routing for EMC compliance.
A30010 (F)	Power unit: Sign-of-life error, cyclic data
Reaction:	NONE
Acknowledge:	NONE
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. The cyclic setpoint telegrams of the Control Unit were not received on time by the power unit for at least one clock cycle.
Remedy:	- check the electrical cabinet design and cable routing for EMC compliance.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (OFF1, OFF2, OFF3) VECTOR: NONE (OFF1, OFF2, OFF3)
Acknowledge upon F:	IMMEDIATELY (POWER ON)

F30011 Power unit: Line phase failure in main circuit

Reaction: OFF2 (OFF1)
Acknowledge: IMMEDIATELY
Cause: A line phase failure was detected at the power unit.
- the fuse of a phase of a main circuit has ruptured.
- the DC link voltage ripple has exceeded the permissible limit value.
Remedy: Check the fuses in the main circuit.

F30012 Power unit: Temperature sensor heatsink wire breakage

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: The connection to one of the heatsink temperature sensors in the power unit is interrupted.
Fault value (r0949, interpret hexadecimal):
Bit 0: Module slot (electronics slot)
Bit 1: Air intake
Bit 2: Inverter 1
Bit 3: Inverter 2
Bit 4: Inverter 3
Bit 5: Inverter 4
Bit 6: Inverter 5
Bit 7: Inverter 6
Bit 8: Rectifier 1
Bit 9: Rectifier 2
See also: r0949 (Fault value)
Remedy: Contact the manufacturer.

F30013 Power unit: Temperature sensor heatsink short-circuit

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: The heatsink temperature sensor in the Motor Module is short-circuited.
Fault value (r0949, interpret hexadecimal):
Bit 0: Module slot (electronics slot)
Bit 1: Air intake
Bit 2: Inverter 1
Bit 3: Inverter 2
Bit 4: Inverter 3
Bit 5: Inverter 4
Bit 6: Inverter 5
Bit 7: Inverter 6
Bit 8: Rectifier 1
Bit 9: Rectifier 2
Remedy: Contact the manufacturer.

A30016 Power unit: Load supply switched-out

Reaction: NONE
Acknowledge: NONE
Cause: The following applies for CU31x and CUA31:
The DC link voltage is too low.
Fault value (r0949, decimal):
DC link voltage in [V].
Remedy: The following applies for CU31x and CUA31:
Under certain circumstances, the AC line supply is not switched-in.

F30017	Power unit: Hardware current limit has responded too often
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The hardware current limitation in the relevant phase (see A30031, A30032, A30033) has responded too often. The number of times the limit has been exceeded depends on the design and type of power unit.</p> <p>For infeed units, the following applies:</p> <ul style="list-style-type: none"> - closed-loop control is incorrectly parameterized. - load on the infeed is too high. - Voltage Sensing Module incorrectly connected. - commutating reactor missing or the incorrect type. - power unit defective. <p>The following applies to Motor Modules:</p> <ul style="list-style-type: none"> - closed-loop control is incorrectly parameterized. - fault in the motor or in the power cables. - the power cables exceed the maximum permissible length. - motor load too high - power unit defective. <p>Fault value (r0949, interpret binary): Bit 0: Phase U Bit 1: Phase V Bit 2: Phase W</p>
Remedy:	<p>For infeed units, the following applies:</p> <ul style="list-style-type: none"> - check the controller settings, if required, reset and identify the controller (p0340 = 2, p3410 = 5). - reduce the load, if required, increase the DC link capacitance or use a higher-rating infeed. - check the connection of the optional Voltage Sensing Module. - check the connection and technical data of the commutating reactor. - check the power cables for short-circuit or ground fault. - replace power unit. <p>The following applies to Motor Modules:</p> <ul style="list-style-type: none"> - check the motor data. - check the motor circuit configuration (star-delta). - check the motor load. - check the power cable connections. - check the power cables for short-circuit or ground fault. - check the length of the power cables. - replace power unit.

F30021	Power unit: Ground fault
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>Power unit has detected a ground fault.</p> <ul style="list-style-type: none"> - ground fault in the power cables - winding fault or ground fault at the motor. - CT defective. <p>Additional cause for CU310/CUA31: - when the brake is applied, this causes the hardware DC current monitoring to respond.</p> <p>Fault value (r0949, decimal): Absolute value, summed current [32767 = 271 % rated current].</p>
Remedy:	<ul style="list-style-type: none"> - check the power cable connections. - check the motor. - check the CT. <p>The following applies additionally for CU31x and CUA31: - check the cables and contacts of the brake connection (a wire is possibly broken). See also: p0287 (Ground fault monitoring thresholds)</p>

F30022 Power unit: Monitoring U_{ce}

Reaction: OFF2

Acknowledge: POWER ON

Cause: In the power unit, the monitoring of the collector-emitter voltage (U_{ce}) of the semiconductor has responded.

Possible causes:

- short-circuit at the Motor Module output.
- defective semiconductor in the power unit.

Fault value (r0949, interpret binary):

- Bit 0: Short-circuit in phase U
 - Bit 1: Short circuit in phase V
 - Bit 2: Short-circuit in phase W
 - Bit 3: Light transmitter enable defective
 - Bit 4: U_{ce} group fault signal interrupted
- See also: r0949 (Fault value)

Remedy:

- check the power cable connections.
- select the defective semiconductor and replace.

F30025 Power unit: Chip overtemperature

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: Chip temperature of the semiconductor has exceeded the permissible limit value.

- the permissible load duty cycle was not maintained.
- insufficient cooling, fan failure.
- overload
- ambient temperature too high.
- pulse frequency too high.

Fault value (r0949):

Temperature difference between the heatsink and chip [1 Bit = 0.01 °C].

Remedy:

- adapt the load duty cycle.
- check whether the fan is running.
- check the fan elements
- check whether the ambient temperature is in the permissible range.
- check the motor load.
- reduce the pulse frequency if this is higher than the rated pulse frequency.

Notice:

This fault can only be acknowledged after this alarm threshold for alarm A05001 has been fallen below.

See also: r0037 (Power unit temperatures)

F30027 Power unit: Precharging DC link time monitoring

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The power unit DC link was not able to be pre-charged within the expected time.

- line supply voltage too low.
- line supply phase fault.
- short-circuit or ground fault in the DC link.
- pre-charging circuit defective.

Fault value (r0949):

Missing internal enable signals, power unit (lower 16 bit):

(Inverted bit-coded notation FFFF hex -> all internal enable signals available)

- Bit 0: Power supply of the IGBT gating shut down
- Bit 1: Reserved
- Bit 2: Reserved
- Bit 3: Ground fault detected
- Bit 4: Peak current intervention
- Bit 5: I_{2t} exceeded
- Bit 6: Thermal model overtemperature calculated
- Bit 7: (heatsink, gating module, power unit) overtemperature measured
- Bit 8: Reserved
- Bit 9: Overvoltage detected

List of faults and alarms

Bit 10: Power unit has completed pre-charging, ready for pulse enable
 Bit 11: SH terminal missing
 Bit 12: Overcurrent detected
 Bit 13: Armature short-circuit active
 Bit 14: DRIVE-CLiQ fault active
 Bit 15: Uce fault detected, transistor de-saturated due to overcurrent/circuit-circuit
 Status, power unit (upper 16 bit, hexadecimal number):
 0: Fault status (wait for OFF and fault acknowledgment)
 1: Restart inhibit (wait for OFF)
 2: Overvoltage condition detected -> change into the fault state
 3: Undervoltage condition detected -> change into the fault state
 4: Wait for bypass contactor to open -> change into the fault state
 5: Wait for bypass contactor to open -> change into restart inhibit
 6: Commissioning
 7: Ready for pre-charging
 8: Pre-charging started, DC link voltage lower than the minimum switch-on voltage
 9: Pre-charging, DC link voltage end of pre-charging still not detected
 10: Wait for the end of the de-bounce time of the main contactor after pre-charging has been completed
 11: Pre-charging completed, ready for pulse enable
 12: It was detected that the SH terminal was energized at the power unit
 See also: p0210 (Drive unit line supply voltage)

Remedy:

- check the line supply voltage
- check the line supply.

Power unit:
 See also: p0210 (Drive unit line supply voltage)

A30031 Power unit: Hardware current limiting, phase U

Reaction: NONE
Acknowledge: NONE
Cause: Hardware current limit for phase U responded. The pulsing in this phase is inhibited for one pulse period.

- closed-loop control is incorrectly parameterized.
- fault in the motor or in the power cables.
- the power cables exceed the maximum permissible length.
- motor load too high
- power unit defective.

Remedy:

- check the motor data.
- check the motor circuit configuration (star-delta).
- check the motor load.
- check the power cable connections.
- check the power cables for short-circuit or ground fault.
- check the length of the power cables.

A30032 Power unit: Hardware current limiting, phase V

Reaction: NONE
Acknowledge: NONE
Cause: Hardware current limit for phase V responded. The pulsing in this phase is inhibited for one pulse period.

- closed-loop control is incorrectly parameterized.
- fault in the motor or in the power cables.
- the power cables exceed the maximum permissible length.
- motor load too high
- power unit defective.

Remedy:

- check the motor data.
- check the motor circuit configuration (star-delta).
- check the motor load.
- check the power cable connections.
- check the power cables for short-circuit or ground fault.
- check the length of the power cables.

A30033 Power unit: Hardware current limiting, phase W

Reaction: NONE

Acknowledge: NONE

Cause: Hardware current limit for phase W responded. The pulsing in this phase is inhibited for one pulse period.

- closed-loop control is incorrectly parameterized.
- fault in the motor or in the power cables.
- the power cables exceed the maximum permissible length.
- motor load too high
- power unit defective.

Remedy:

- check the motor data.
- check the motor circuit configuration (star-delta).
- check the motor load.
- check the power cable connections.
- check the power cables for short-circuit or ground fault.
- check the length of the power cables.

F30035 Power unit: Air intake overtemperature

Reaction: OFF1 (OFF2)

Acknowledge: IMMEDIATELY

Cause: Power unit air intake temperature has exceeded the permissible limit value. For air-cooled power units, the limit is at 55 degrees Celsius.

- ambient temperature too high.
- insufficient cooling, fan failure

Fault value (r0949):
Temperature [1 bit = 0.01 °C].

Remedy:

- check whether the fan is running.
- check the fan elements
- check whether the ambient temperature is in the permissible range.

Notice:

This fault can only be acknowledged after this alarm threshold for alarm A05002 has been fallen below.

F30036 Power unit: Electronics board overtemperature

Reaction: OFF1 (OFF2)

Acknowledge: IMMEDIATELY

Cause: Power unit temperature in the module slot of the drive converter has exceeded the permissible limit value.

- insufficient cooling, fan failure.
- overload
- ambient temperature too high.

Fault value (r0949):
Temperature [1 bit = 0.01 °C].

Remedy:

- check whether the fan is running.
- check the fan elements
- check whether the ambient temperature is in the permissible range.

Notice:

This fault can only be acknowledged after this alarm threshold for alarm A05003 has been fallen below.

F30037 Power unit: Rectifier overtemperature

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: Power unit rectifier temperature has exceeded the permissible limit value.

- insufficient cooling, fan failure.
- overload
- ambient temperature too high.
- line supply phase failure.

Fault value (r0949):
Temperature [1 bit = 0.01 °C].

Remedy:

- check whether the fan is running.
- check the fan elements
- check whether the ambient temperature is in the permissible range.
- check the motor load.
- check the line supply phases.

Notice:
This fault can only be acknowledged after this alarm threshold for alarm A05004 has been fallen below.

F30040 Power unit: Undervolt 24 V

Reaction: OFF2

Acknowledge: POWER ON

Cause: Failure of the 24 V power supply for the power unit.
- the 16 V threshold was fallen below for longer than 3 ms.
Fault value (r0949):
24 V voltage [1 bit = 0.1 V].

Remedy: Check the 24 V DC voltage supply to power unit.

A30041 (F) Power unit: Undervoltage 24 V alarm

Reaction: NONE

Acknowledge: NONE

Cause: 24 V power supply fault for the power unit.
- the 16 V threshold was fallen below.
Fault value (r0949):
24 V voltage [1 bit = 0.1 V].

Remedy: Check the 24 V DC voltage supply to power unit.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE (OFF1, OFF2, OFF3)
VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY (POWER ON)

A30042 Power unit: Fan operating time reached or exceeded

Reaction: NONE

Acknowledge: NONE

Cause: The maximum operating time of the fan in the power unit is set in p0252.
This message indicates the following:
Fault value (r0949, decimal):
0: The maximum fan operating time is 500 hours.
1: The maximum fan operating time has been exceeded.

Remedy: Replace the fan in the power unit and reset the operating hours counter to 0 (p0251 = 0).
See also: p0251 (Operating hours counter, power unit fan), p0252 (Maximum operating time, power unit fan)

F30043 Power unit: Overvolt 24 V

Reaction: OFF2

Acknowledge: POWER ON

Cause: The following applies for CU31x:
Overvoltage of the 24 V power supply for the power unit.
- the 31.5 V threshold was exceeded for more than 3 ms.
Fault value (r0949):
24 V voltage [1 bit = 0.1 V].

Remedy: Check the 24 V DC voltage supply to power unit.

A30044 (F) Power unit: Overvoltage 24 V alarm

Reaction: NONE
Acknowledge: NONE
Cause: The following applies for CU31x:
 24 V power supply fault for the power unit.
 - the 32.0 V threshold was exceeded.
 Fault value (r0949):
 24 V voltage [1 bit = 0.1 V].
Remedy: Check the 24 V DC voltage supply to power unit.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

F30045 Power unit: Supply undervoltage

Reaction: OFF2
Acknowledge: POWER ON
Cause: The following applies for CU31x:
 Power supply fault in the power unit.
 - the voltage monitoring on the DAC board signals an undervoltage fault on the module.
Remedy: Check the 24 V DC power supply for the power unit and if required replace the module.

A30046 (F) Power unit: Undervoltage, alarm

Reaction: NONE
Acknowledge: NONE
Cause: Before the last new start, a problem occurred at the power unit power supply.
 - the voltage monitoring in the internal FPGA of the PSA signals an undervoltage fault on the module.
 Fault value (r0949):
 Register value of the voltage fault register.
Remedy: Check the 24 V DC power supply for the power unit and if required replace the module.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)
 Acknowledge upon F: IMMEDIATELY (POWER ON)

F30047 Cooling system: Cooling medium flow rate too low

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: Cooling system: Fault - flow rate has fallen below the fault value
Remedy:

F30050 Power unit: Supply overvoltage

Reaction: OFF2
Acknowledge: POWER ON
Cause: The following applies for CU31x and CUA31:
 - the voltage monitoring on the DAC board signals an overvoltage fault on the module.
Remedy: Check the 24 V DC power supply of the CU and if required replace the module.

F30052 EEPROM data error

Reaction: NONE
Acknowledge: POWER ON
Cause: EEPROM data error of the power unit module.
 Fault value (r0949):
 0: The EEPROM data read-in from the power unit module is inconsistent.
 1: EEPROM data is not compatible to the firmware of the power unit application.
Remedy: Fault value (r0949):
 0: Replace the power unit module or update the EEPROM data.
 1: The following applies for CU31x and CUA31:
 Update the firmware \SIEMENS\SINAMICS\CODE\SAC\cu31xi.ufw (cua31.ufw)

F30070 The power unit does not support the requested cycle.

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The following applies for CU31x and CUA31:
 A cycle is requested that is not supported by the power unit.
 Fault value (r0949):
 The following applies for CU31x and CUA31:
 0: The current control cycle is not supported.
 1: The DriveCliQ cycle is not supported.
 2: Internal timing problem (clearance between RX and TX instants too low)
 3: Internal timing problem (TX instant too early)
Remedy: The following applies for CU31x and CUA31:
 The power unit only supports the following cycles:
 62.5us , 125us, 250us and 500us
 Fault value (r0949):
 The following applies for CU31x and CUA31:
 0: Set a permitted current control cycle.
 1: Set a permitted DriveCliQ cycle.
 2/3: Contact the manufacturer (there is possibly an incompatible firmware release)

F30071 The power unit is no longer receiving new actual values.

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The following applies for CU31x and CUA31:
 More than one actual value telegram from the power unit has failed.
Remedy: The following applies for CU31x and CUA31:
 Check the interface (adjustment and locking) to the power unit.

F30072 Setpoints are no longer being transferred to the power unit.

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The following applies for CU31x and CUA31:
 More than one setpoint telegram was not able to be transferred to the power unit.
Remedy: The following applies for CU31x and CUA31:
 Check the interface (adjustment and locking) to the power unit.

A30073 (N) The actual value/setpoint conditioning is no longer in synchronism with DriveCliQ.

Reaction: NONE
Acknowledge: NONE
Cause: The following applies for CU31x and CUA31:
 Communications to the power unit is no longer in synchronism with DriveCliQ.
Remedy: The following applies for CU31x and CUA31:
 Wait until synchronization is re-established.
 Reaction upon N: NONE
 Acknowledge upon N: NONE

F30074	Communications error to the power unit
Reaction:	NONE
Acknowledge:	POWER ON
Cause:	Communications is not possible to the power unit via the plug contact.
Remedy:	The following applies for CU31x and CUA31: Either replace the CU board or the power unit. You must check which of the two components must be replaced by replacing one and then the other component; if neither are available then both components must be returned.
F30105	LT: Actual value sensing fault
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	At least one incorrect actual value channel was detected on the Power Stack Adapter (PSA). The incorrect actual value channels are displayed in the following diagnostic parameters.
Remedy:	Evaluate the diagnostic parameters. If the actual value channel is incorrect, check the components and if required, replace.
F30600	SI MM: STOP A initiated
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-based "Safety Integrated" function in the Motor Module (MM) has detected a fault and initiated STOP A (pulse cancellation via the safety shutdown path of the Motor Module). - forced checking procedure of the safety shutdown path of the Motor Module unsuccessful. - subsequent response to fault F30611 (defect in a monitoring channel). Fault value (r0949, decimal): 0: Stop request from the Control Unit. 1005: Pulses cancelled although SH not selected and there is not internal STOP A present. 1010: Pulses enabled although SH is selected or an internal STOP A is present. 9999: Subsequent response to fault F30611.
Remedy:	- select safe standstill and then de-select again. - replace the Motor Module involved. Re fault value = 9999: - carry-out diagnostics for fault F30611. Note: CU: Control Unit MM: Motor Module SH: Safe standstill SI: Safety Integrated
F30611	SI MM: Defect in a monitoring channel".
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (OFF1, OFF2, OFF3) VECTOR: NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-based "Safety Integrated" function in the Motor Module (MM) has detected a fault in the crosswise data comparison between the Control Unit (CU) and MM and initiated a STOP F. As a result of this fault, after the parameterized transition has expired (p9858), fault F30600 is output (SI MM: STOP A initiated). Fault value (r0949, decimal): 0: Stop request from the Control Unit. 1 to 999: Number of the crosswise compared data that resulted in this fault. 1: SI monitoring clock cycle (r9780, r9880). 2: SI enable safety functions (p9601, p9801). 3: SI SGE changeover tolerance time (p9650, p9850). 4: SI transition period STOP F to STOP A (p9658, p9858). 5: SI enable Safe Brake Control (p9602, p9802). 6: SI motion enable, safety-relevant functions (p9501, internal value). This number is also displayed in r9895. 7: SI pulse cancellation delay time for Safe Stop 1 (p9652, p9852).

1000: Watchdog timer has expired. Within the time of approx. 5 * p9850 too many switching operations have occurred at the safety-related inputs of the Control Unit.
 1001, 1002: Initialization error, change timer / check timer.
 2000: Status of the SH terminals on the Control Unit and Motor Module are different.
 2001: Feedback signal for safe pulse cancellation on the Control Unit and Motor Module are different.
 2002: Status of the delay timer SS1 on the Control Unit and Motor Module are different.

Remedy:

Re fault value = 1 to 999:
 - check the crosswise compared data that resulted in a STOP F.
 - carry-out a POWER ON (power off/on) for all components.
 - upgrade the Motor Module software.
 - upgrade the Control Unit software.
 Re fault value = 1000:
 - check the wiring of the safety-relevant inputs (SGE) on the Control Unit (contact problems).
 Re fault value = 1001, 1002:
 - carry-out a POWER ON (power off/on) for all components.
 - upgrade the Motor Module software.
 - upgrade the Control Unit software.
 Re fault value = 2000, 2001, 2002:
 - check the tolerance time SGE changeover and if required, increase the value (p9650/p9850, p9652/p9852).
 - check the wiring of the safety-relevant inputs (SGE) (contact problems).
 - replace the Motor Module involved.
 Note:
 CU: Control Unit
 MM: Motor Module
 SGE: Safety-relevant input
 SH: Safe standstill
 SI: Safety Integrated
 SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)

N30620 (F, A) SI MM: Safe standstill active

Reaction: NONE
Acknowledge: NONE
Cause: The "safe standstill" function was selected on the Motor Module (MM) and is active.
 Note:
 This message does not result in a safety stop response.
Remedy: None necessary.
 Note:
 MM: Motor Module
 SI: Safety Integrated
 Reaction upon F: OFF2
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon A: NONE
 Acknowledge upon A: NONE

N30621 (F, A) SI MM: Safe Stop 1 active

Reaction: NONE
Acknowledge: NONE
Cause: The "Safe Stop 1" function (SS1) was selected on the Motor Module (MM) and is active.
 Note:
 This message does not result in a safety stop response.
Remedy: None necessary.
 Note:
 MM: Motor Module
 SI: Safety Integrated
 SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)

Reaction upon F: A_INFEED: OFF2
 SERVO: OFF3
 VECTOR: OFF3

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon A: NONE

Acknowledge upon A: NONE

F30625 SI MM: Sign-of-life error in safety data

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive-based "Safety Integrated" function on the Motor Module (MM) has detected an error in the sign-of-life of the safety data between the Control Unit (CU) and MM and initiated a STOP A.
 - there is either a DRIVE-CLiQ communications error or communications have failed.
 - a time slice overflow of the safety software has occurred.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy:

- select safe standstill and then de-select again.
- carry-out a POWER ON (power off/on) for all components.
- check whether there is a DRIVE-CLiQ communications error between the Control Unit and the Motor Module involved and if required, carry-out a diagnostics routine for the faults identified.
- de-select all drive functions that are not absolutely necessary.
- reduce the number of drives.
- check the electrical cabinet design and cable routing for EMC compliance

Note:
 CU: Control Unit
 MM: Motor Module
 SI: Safety Integrated

F30630 SI MM: Braking signal error

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive-based "Safety Integrated" function on the Motor Module (MM) has detected a braking signal error and initiated a STOP A.
 - no motor holding brake connected.
 - the motor holding brake control on the Motor Module or the Control Unit is faulty.
 - a DRIVE-CLiQ communications error has occurred between the Control Unit and the Motor Module.
 Fault value (r0949, decimal):
 10: No brake connected or fault in the Motor Module brake control circuit ("open brake" operation).
 30: Short-circuit in the brake winding or fault in the Motor Module brake control circuit ("close brake" operation).
 40: Defect in the brake control circuit of the Motor Module ("brake closed" state).
 60, 70: Fault in the braking signal of the Control Unit or communications fault between the Control Unit and Motor Module (braking signal).

Remedy:

- select safe standstill and then de-select again.
- check the motor holding brake connection.
- check the function of the motor holding brake.
- check whether there is a DRIVE-CLiQ communications error between the Control Unit and the Motor Module involved and if required, carry-out a diagnostics routine for the faults identified.
- check the electrical cabinet design and cable routing for EMC compliance
- replace the Motor Module involved.

Operation with Safe Brake Module:

- check the Safe Brake Modules connection.
- replace the Safe Brake Module. Note:

CU: Control Unit
 MM: Motor Module
 SI: Safety Integrated

F30640 **SI MM: Fault in the control shutdown path**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The Motor Module has detected a communications error with the higher-level control to transfer the shutdown information.

Note:
 This fault results in a STOP A that can be acknowledged.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy: - check the PROFIsafe address in the higher-level control and Motor Modules.
 - carry-out a POWER ON for all components.
 - upgrade the Motor Module software.

Note:
 MM: Motor Module
 SI: Safety Integrated
 See also: p9810 (SI PROFIsafe address (Motor Module))

F30649 **SI MM: Internal software error**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: An internal error in the Safety Integrated software on the Motor Module has occurred.

Note:
 This fault results in a STOP A that cannot be acknowledged.
 Fault value (r0949, interpret hexadecimal):
 Only for internal Siemens troubleshooting.

Remedy: - carry-out a POWER ON (power off/on) for all components.
 - re-commission the Safety Integrated function and carry-out a POWER ON.
 - upgrade the Motor Module software.
 - contact the Hotline.
 - replace the Motor Module.

Note:
 MM: Motor Module
 SI: Safety Integrated

F30650 **SI MM: Acceptance test required**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The "Safety Integrated" function on the Motor Module requires an acceptance test.

Note:
 This fault results in a STOP A that can be acknowledged.
 Fault value (r0949, decimal):
 130: No safety parameters available for the Motor Module.
 1000: Reference and actual checksum in the Motor Module are not identical (booting).
 - at least one checksum-checked piece of data is defective.
 2000: Reference and actual checksum on the Motor Module are not identical (commissioning mode).
 - reference checksum incorrectly entered into the Motor Module (p9899 not equal to r9898).
 2003: Acceptance test is required as a safety parameter has been changed.
 9999: Subsequent response of another safety-related fault, which occurred when booting and requires an acceptance test.

Remedy: Re fault value = 130:
 - carry-out safety commissioning routine.
 Re fault value = 1000:
 - again carry-out safety commissioning routine.
 - replace the CompactFlash card.
 Re fault value = 2000:
 - check the safety parameters in the Motor Module and adapt the reference checksum (p9899).

Re fault value = 2003:
 - carry-out an acceptance test.
 Re fault value = 9999:
 - carry-out diagnostics for the other safety-related fault that is present.
 Note:
 MM: Motor Module
 SI: Safety Integrated
 See also: p9799 (SI reference checksum SI parameters (Control Unit)), p9899 (SI reference checksum SI parameters (Motor Module))

F30651	SI MM: Synchronization with Control Unit unsuccessful
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-based "Safety Integrated" function is requesting synchronization of the safety time slices on the Control Unit and Motor Module. This synchronization routine was not successful. Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.
Remedy:	- carry-out a POWER ON (power off/on) for all components. - upgrade the Motor Module software. - upgrade the Control Unit software. Note: MM: Motor Module SI: Safety Integrated
F30652	SI MM: Illegal monitoring clock cycle
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The Safety Integrated monitoring clock cycle cannot be maintained due to the communication conditions requested in the system. Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.
Remedy:	Upgrade the Motor Module software. Note: MM: Motor Module SI: Safety Integrated
F30655	SI MM: Align monitoring functions
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	An error has occurred when aligning the Safety Integrated monitoring functions on the Control Unit (CU) and Motor Module (MM). Control unit and Motor Module were not able to determine a common set of supported SI monitoring functions. - there is either a DRIVE-CLIQ communications error or communications have failed. - Safety Integrated software releases on the Control Unit and Motor Module are not compatible with one another. Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	- carry-out a POWER ON (power off/on) for all components. - upgrade the Motor Module software. - upgrade the Control Unit software. - check the electrical cabinet design and cable routing for EMC compliance Note: CU: Control Unit MM: Motor Module SI: Safety Integrated

F30656 **SI MM: Motor Module parameter error**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: When accessing the Safety Integrated parameters for the Motor Module (MM) on the CompactFlash card, an error has occurred.

Note:
 This fault results in a STOP A that can be acknowledged.
 Fault value (r0949, decimal):
 129: Safety parameters for the Motor Module corrupted.
 131: Internal software error on the Control Unit.
 255: Internal Motor Module software error.

Remedy:
 - re-commission the safety functions.
 - upgrade the Control Unit software.
 - upgrade the Motor Module software.
 - replace the CompactFlash card.

Note:
 MM: Motor Module
 SI: Safety Integrated

F30659 **SI MM: Write request for parameter rejected**

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The write request for one or several Safety Integrated parameters on the Motor Module (MM) was rejected.

Note:
 This fault does not result in a safety stop response.
 Fault value (r0949, decimal):
 10: An attempt was made to enable the SH function although this cannot be supported.
 11: An attempt was made to enable the SBC function although this cannot be supported.
 13: An attempt was made to enable the SS1 function although this cannot be supported.
 14: An attempt was made to enable the safe motion monitoring function with the higher-level control, although this cannot be supported.
 See also: r9771 (SI common functions (Control Unit)), r9871 (SI common functions (Motor Module))

Remedy:
 Re fault value = 10, 11:
 - check whether there are faults in the safety function alignment between the Control Unit and the Motor Module involved (F01655, F30655) and if required, carry-out diagnostics for the faults involved.
 - use a Motor Module that supports the function safe standstill or Safe Brake Control.
 - upgrade the Motor Module software.
 - upgrade the Control Unit software.

Note:
 MM: Motor Module
 SBC: Safe Brake Control
 SH: Safe standstill
 SI: Safety Integrated, SS1: Safe Stop 1 (corresponds to Stop Category 1 acc. to EN60204)

F30801 **Power unit DRIVE-CLiQ: Sign-of-life missing**

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved.
 Fault value (r0949, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.

Remedy:
 - check the electrical cabinet design and cable routing for EMC compliance.
 - replace the component involved.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F30802 **Power unit: Time slice overflow**

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: Time slice overflow.

Remedy:

A30804 (F)	Power unit: CRC
Reaction:	NONE
Acknowledge:	NONE
Cause:	CRC error actuator
Remedy:	
Reaction upon F:	A_INFEED: OFF2 (OFF1) SERVO: OFF2 (OFF1, OFF3) VECTOR: OFF2 (OFF1, OFF3)
Acknowledge upon F:	IMMEDIATELY
F30805	Power unit: EPROM checksum error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	Internal parameter data is corrupted. Fault value (r0949, interpret hexadecimal): 01: EEPROM access error. 02: Too many blocks in the EEPROM.
Remedy:	Replace the module.
F30809	Power unit: Switching information not valid
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	For 3P gating unit: The last switching status word in the setpoint telegram is identified by the end ID. Such an end ID was not found.
Remedy:	
A30810 (F)	Power unit: Watchdog timer
Reaction:	NONE
Acknowledge:	NONE
Cause:	When booting it was detected that the cause of the previous reset was an SAC watchdog timer overflow.
Remedy:	
Reaction upon F:	NONE (OFF2)
Acknowledge upon F:	IMMEDIATELY
F30820	Power unit DRIVE-CLiQ: Telegram error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. Fault value (r0949, interpret hexadecimal): 01: CRC error. 02: Telegram is shorter than specified in the length byte or in the receive list. 03: Telegram is longer than specified in the length byte or in the receive list. 04: The length of the receive telegram does not match the receive list. 05: The type of the receive telegram does not match the receive list. 06: The address of the power unit in the telegram and in the receive list do not match. 07: Power unit expects a SYNC telegram, but the receive telegram is not a SYNC telegram. 08: Power unit does not expect a SYNC telegram, but the receive telegram is a SYNC telegram. 09: The error bit in the receive telegram is set. 10: The receive telegram is too early.
Remedy:	- carry-out a POWER ON. - check the electrical cabinet design and cable routing for EMC compliance. - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F30835	Power unit DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 21: The cyclic telegram has not been received. 22: Timeout in the telegram receive list. 40: Timeout in the telegram send list.
Remedy:	- carry-out a POWER ON. - replace the component involved. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F30836	Power unit DRIVE-CLiQ: Send error for DRIVE-CLiQ data
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. Data were not able to be sent. Fault value (r0949, interpret hexadecimal): 41: Telegram type does not match send list.
Remedy:	Carry-out a POWER ON.
F30837	Power unit DRIVE-CLiQ: Component fault
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded. Fault value (r0949, interpret hexadecimal): 20: Error in the telegram header. 23: Receive error: The telegram buffer memory contains an error. 42: Send error: The telegram buffer memory contains an error. 43: Send error: The telegram buffer memory contains an error.
Remedy:	- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). - check the electrical cabinet design and cable routing for EMC compliance. - if required, use another DRIVE-CLiQ socket (p9904). - replace the component involved.
F30845	Power unit DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. Fault value (r0949, interpret hexadecimal): 0B: Synchronization error during alternating cyclic data transfer.
Remedy:	Carry-out a POWER ON. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F30850	Power unit: Internal software error
Reaction:	A_INFEED: OFF1 (NONE, OFF2) SERVO: OFF1 (NONE, OFF2, OFF3) VECTOR: OFF1 (NONE, OFF2, OFF3)
Acknowledge:	POWER ON
Cause:	An internal software error in the power unit has occurred. Fault value (r0949, decimal): Only for internal Siemens troubleshooting.
Remedy:	- replace power unit. - if required, upgrade the firmware in the power unit. - contact the Hotline.

F30851	CU DRIVE-CLiQ: Sign-of-life missing
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF2 (NONE, OFF1, OFF3) VECTOR: OFF2 (NONE, OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit. Fault value (r0949, interpret hexadecimal): 0A: The sign-of-life bit in the receive telegram is not set.
Remedy:	Upgrade the firmware of the component involved.
F30860	CU DRIVE-CLiQ: Telegram error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. Fault value (r0949, interpret hexadecimal): 11: CRC error and the receive telegram is too early. 01: CRC error. 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early. 02: Telegram is shorter than specified in the length byte or in the receive list. 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early. 03: Telegram is longer than specified in the length byte or in the receive list. 14: The length of the receive telegram does not match the receive list and the receive telegram is too early. 04: The length of the receive telegram does not match the receive list. 15: The type of the receive telegram does not match the receive list and the receive telegram is too early. 05: The type of the receive telegram does not match the receive list. 16: The address of the power unit in the telegram and in the receive list does not match and the receive telegram is too early. 06: The address of the power unit in the telegram and in the receive list do not match. 19: The error bit in the receive telegram is set and the receive telegram is too early. 09: The error bit in the receive telegram is set. 10: The receive telegram is too early.
Remedy:	- carry-out a POWER ON. - check the electrical cabinet design and cable routing for EMC compliance. - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)
F30885	CU DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early. 21: The cyclic telegram has not been received. 22: Timeout in the telegram receive list. 40: Timeout in the telegram send list. 62: Error at the transition to cyclic operation.
Remedy:	- check the power supply voltage of the component involved. - carry-out a POWER ON. - replace the component involved. See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)
F30886	CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data
Reaction:	OFF2
Acknowledge:	IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

F30887 CU DRIVE-CLiQ: Component fault

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
 60: Response received too late during runtime measurement.
 61: Time taken to exchange characteristic data too long.

Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

F30895 CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the power unit involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F30896 CU DRIVE-CLiQ: Inconsistent component characteristics

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced.
 Fault value (r0949, decimal):
 Component ID.

Remedy:

- when replacing cables, only use cables with the same length as the original cables.
- when replacing components, use the same components and firmware releases.
- carry-out a POWER ON.

F30897 DRIVE-CLiQ: No communication to component

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: Communications with the DRIVE-CLiQ component specified by the fault value is not possible.
 One cause can be, e.g. that a DRIVE-CLiQ cable has been withdrawn.
 Fault value (r0949, decimal):
 Component ID.

Remedy:

- check the DRIVE-CLiQ connections.
- carry-out a POWER ON.

F30899 (N, A)	Power unit: Unknown fault
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	A fault occurred on the power unit that cannot be interpreted by the Control Unit firmware. This can occur if the firmware on the power unit is more recent than the firmware on the Control Unit. Fault value (r0949, decimal): Fault number. If required, the significance of this new fault can be read about in a more recent description of the Control Unit.
Remedy:	- replace the firmware on the power unit by an older firmware version (r0128). - upgrade the firmware on the Control Unit (r0018).
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

A30903	Power unit: I2C bus
Reaction:	NONE
Acknowledge:	NONE
Cause:	Communications with EPROM not possible. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	Replace the module.

F30907	Power unit: FPGA configuration unsuccessful
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2) VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	For the initialization within the power unit, an internal software error has occurred.
Remedy:	- replace power unit. - if required, upgrade the firmware in the power unit. - contact the Hotline.

A30920 (F)	Power unit: Temperature sensor fault
Reaction:	NONE
Acknowledge:	NONE
Cause:	When evaluating the temperature sensor, an error occurred. Alarm value (r2124, decimal): 1: Wire breakage or sensor not connected (KTY: R > 1630 Ohm). 2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).
Remedy:	- check that the sensor is connected correctly. - replace sensor.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY

A30999 (F, N)	Power unit: Unknown alarm
Reaction:	NONE
Acknowledge:	NONE
Cause:	An alarm occurred on the power unit that cannot be interpreted by the Control Unit firmware. This can occur if the firmware on the power unit is more recent than the firmware on the Control Unit. Alarm value (r2124, decimal): Alarm number. If required, the significance of this new alarm can be read about in a more recent description of the Control Unit.
Remedy:	- replace the firmware on the power unit by an older firmware version (r0128). - upgrade the firmware on the Control Unit (r0018).
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)
Reaction upon N:	NONE
Acknowledge upon N:	NONE
F31100 (N, A)	Encoder 1: Zero mark distance error
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: ENCODER (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: ENCODER (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	PULSE INHIBIT
Cause:	The measured zero mark distance does not correspond to the parameterized zero mark distance. For distance-coded encoders, the zero mark distance is determined from zero marks detected pairs. This means that if a zero mark is missing, depending on the pair generation, this cannot result in a fault and also has no effect in the system. The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder). Fault value (r0949, decimal): Last measured zero mark distance in increments (4 increments = 1 encoder pulse). The sign designates the direction of motion when detecting the zero mark distance. See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	- check that the encoder cables are routed in compliance with EMC. - check the plug connections. . check the encoder type (encoder with equidistant zero marks). - adapt the parameter for the distance between zero marks (p0424, p0425). - replace the encoder or encoder cable.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE
F31101 (N, A)	Encoder 1: Zero marked failed
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	PULSE INHIBIT
Cause:	The 1.5 x parameterized zero mark distance was exceeded. The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder). Fault value (r0949, decimal): Number of increments after POWER ON or since the last zero mark that was detected (4 increments = 1 encoder pulse). See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the clearance between zero marks (p0425).
- replace the encoder or encoder cable.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31110 (N, A) Encoder 1: Serial communications error

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: Serial communication protocol transfer error between the encoder and evaluation module.
 Fault value (r0949, interpret binary):
 Bit 0: Alarm bit in the position protocol.
 Bit 1: Incorrect quiescent level on the data line.
 Bit 2: Encoder does not respond (does not supply a start bit within 50 ms).
 Bit 3: CRC error: The checksum in the protocol from the encoder does not match the data.
 Bit 4: Encoder acknowledgement error: The encoder incorrectly understood the task (request) or cannot execute it.
 Bit 5: Internal error in the serial driver: An illegal mode command was requested.
 Bit 6: Timeout with cyclically reading.
 Bit 8: Protocol is too long (e.g. > 64 bits).
 Bit 9: Receive buffer overflow
 Bit 10: Frame error when reading twice.
 Bit 11: Parity error.
 Bit 12: Data line signal level error during the monoflop time.

Remedy: Re fault value:
 Bit 0 = 1: Encoder defective. F31111 may provide additional details.
 Bit 1 = 1: Incorrect encoder type / replace the encoder or encoder cable.
 Bit 2 = 1: Incorrect encoder type / replace the encoder or encoder cable.
 Bit 3 = 1: EMC / connect the cable shield, replace the encoder or encoder cable.
 Bit 4 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 5 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 6 = 1: Update the Sensor Module firmware.
 Bit 8 = 1: Check the parameterization (p0429.2).
 Bit 9 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 10 = 1: Check the parameterization (p0429.2, p0449).
 Bit 11 = 1: Check the parameterization (p0436).
 Bit 12 = 1: Check the parameterization (p0429.6).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31111 (N, A) Encoder 1: Absolute encoder EnDat, internal fault/error

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The EnDat encoder fault word contains fault bits that have been set.
 Fault value (r0949, interpret binary):
 Bit 0: Lighting system failed.
 Bit 1: Signal amplitude too low.
 Bit 2: Position value incorrect.
 Bit 3: Encoder power supply overvoltage condition.
 Bit 4: Encoder power supply undervoltage condition.
 Bit 5: Encoder power supply overcurrent condition.
 Bit 6: The battery must be changed.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Re fault value, bit 0 = 1:
 Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.
 Re fault value, bit 1 = 1:
 Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.
 Re fault value, bit 2 = 1:
 Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.
 Re fault value, bit 3 = 1:
 5 V power supply voltage fault.
 When using an SMC: Check the plug-in cable between the encoder and SMC or replace the SMC.
 When a motor encoder with a direct DRIVE-CLiQ connection is used: Replace the motor.
 Re fault value, bit 4 = 1:
 5 V power supply voltage fault.
 When using an SMC: Check the plug-in cable between the encoder and SMC or replace the SMC.
 When using a motor with DRIVE-CLiQ: Replace the motor.
 Re fault value, bit 5 = 1:
 Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.
 Re fault value, bit 6 = 1:
 The battery must be changed - only for encoders with battery back-up.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31112 (N, A) Encoder 1: The error bit is set in the serial protocol

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: Serial communication protocol transfer error between the encoder and evaluation module SMCxx.
 Fault value (r0949, interpret binary):

Remedy: Re fault value:

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31115 (N, A) Encoder 1: Amplitude error track A or B (A² + B²)

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The amplitude (A² + B²) does not lie within the tolerance bandwidth (software monitoring function).
 SMC20:
 The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
 On the other hand, the response threshold is < 230 mV (frequency characteristic).
 SMC10:
 The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is < 1070 mV.
 Fault value (r0949, decimal):
 Low word:
 Signal level, track A (16 bits with sign).
 High word:
 Signal level, track B (16 bits with sign).
 SMC20:
 A signal level of 500 mV peak value corresponds to the numerical value 5333 hex = 21299 dec.
 SMC10:
 A signal level of 2900 mV peak value corresponds to the numerical value 6666 hex = 26214 dec.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check the encoder module (e.g. contacts).
- with measuring systems without their own bearing system: Adjust the scanning head and check the bearing system of the measuring wheel.
- for measuring systems with their own bearing system: Ensure that the encoder housing is not subject to any axial force.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31116 (N, A) Encoder 1: Amplitude error, monitoring track A + B

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: The amplitude of the rectified encoder signals A and B is not within the tolerance bandwidth (hardware monitoring).
 The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
 On the other hand, the hardware response thresholds are at < 176 mV and > 1.35 V.
 Fault value (r0949, decimal):
 Low word: Signal level, track A (16 bits with sign).
 High word: Signal level, track B (16 bits with sign).
 A signal level of 500 mV corresponds to the numerical value 5333 hex = 21299 dec.
 These analog values are not measured at the same time with the hardware fault output.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check the encoder module (e.g. contacts).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31117 (N, A) Encoder 1: Inversion error, signals A and B and R

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: For a square-wave signal encoder (TTL. bipolar. double ended) the A* and B* and R* signals are not inverted with respect to signals A and B and R.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Check the setting of p0405: p0405.2 = 1 is only possible if the encoder is connected at X520.
 Check the encoder/cable: Does the encoder supply TTL signals and the associated inverted signals?

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31118 (N, A) Encoder 1: Speed difference outside the tolerance range

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: For an HTL/TTL encoder, the speed difference has exceeded the value in p0492 over several sampling cycles. Encoder 1 is used as motor encoder and can be effective has fault response to change over to sensorless operation.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - check the tachometer feeder cable for interruptions.
 - check the grounding of the tachometer shielding.
 - if required, increase the maximum speed difference per sampling cycle (p0492).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31120 (N, A) Encoder 1: Power supply voltage

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: Encoder power supply voltage fault.
 Note:
 If the encoder cables 6FX2002-2EQ00-.... and 6FX2002-2CH00-.... are interchanged, this can result in the encoder being destroyed because the pins of the operating voltage are reversed.
 Fault value (r0949, interpret binary):
 Bit 0: Undervoltage condition on the sense line (threshold 4.75 V).
 Bit 1: Encoder power supply voltage overcurrent condition (threshold 450 mA).
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: For fault value, bit 0 = 1:
 - correct encoder cable connected?
 - check the plug connections of the encoder cable.
 - SMC30: Check the parameterization (p0404.22).
 For fault value, bit 1 = 1:
 - correct encoder cable connected?
 - replace the encoder or encoder cable.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31121 (N, A) Encoder 1: Coarse position error

Reaction: A_INFEED: NONE
SERVO: ENCODER (NONE)
VECTOR: ENCODER (NONE)

Acknowledge: PULSE INHIBIT

Cause: For the actual value sensing, an error was detected on the module. As a result of this error, it must be assumed that the actual value sensing supplies an incorrect coarse position.
See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Replace the motor with DRIVE-CLiQ or the appropriate Sensor Module.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31125 (N, A) Encoder 1: Amplitude error track A or B overcontrolled

Reaction: A_INFEED: NONE
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The amplitude (track A or B) does not lie within the tolerance bandwidth (software monitoring function).
SMC20:
The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
On the other hand, the response threshold is > 760 mV (frequency characteristic).
SMC10:
The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is > 3582 mV.
Fault value (r0949, decimal):
Low word:
Signal level, track A (16 bits with sign).
High word:
Signal level, track B (16 bits with sign).
SMC20:
A signal level of 500 mV peak value corresponds to the numerical value 5333 hex = 21299 dec.
SMC10:
A signal level of 2900 mV peak value corresponds to the numerical value 6666 hex = 26214 dec.
See also: p0491 (Motor encoder fault response ENCODER)

Remedy:
- check that the encoder cables are routed in compliance with EMC.
- replace the encoder or encoder cable.
- with measuring systems without their own bearing system: Adjust the scanning head and check the bearing system of the measuring wheel.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31129 (N, A) Encoder 1: Position difference, hall sensor/track C/D and A/B too large

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The error of track C/D is greater than +/-15 ° mechanical or +/-60 ° electrical.
 One period of track C/D corresponds to 360 ° mechanical.
 One period of the Hall signal corresponds to 360 ° electrical.
 The monitoring responds if, for example, Hall sensors are connected as equivalent for the C/D tracks with the incorrect rotational sense or supply values that are not accurate enough.
 After the fine synchronization using one reference mark or 2 reference marks for distance-coded encoders, this fault is no longer initiated, but instead, Alarm A31429.
 Fault value (r0949, decimal):
 Measured deviation as mechanical angle (16 bits with sign, 182 dec corresponds to 1 °).
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- track C or D not connected.
- correct the direction of rotation of the Hall sensor possibly connected as equivalent for track C/D.
- check that the encoder cables are routed in compliance with EMC.
- check the adjustment of the Hall sensor.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31130 (N, A) Encoder 1: Zero mark and position error from the coarse synchronization

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: After initializing the pole position using track C/D, Hall signals or pole position identification routine, the zero mark was detected outside the permissible range. For distance-coded encoders, the test is carried-out after passing 2 zero marks. Fine synchronization was not carried-out.
 The deviation may be up to 18 ° mechanical or up to 60 ° electrical.
 Fault value (r0949, decimal):
 Normalization: 32768 = 180 °
 High word:
 Mechanical zero mark position determined.
 If the initialization via a track C/D is selected in p0404, then it is checked whether the zero mark occurs in an angular range of +/-18 ° mechanical.
 Low word:
 Deviation of the zero mark from the expected position as electrical angle.
 If the correction of the commutation position with the zero mark is selected in p0404, then a difference of a maximum of +/- 60 ° electrical is permitted.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- check p0431 and if required, correct
- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- if the Hall sensor is used as an equivalent for track C/D, check the connection.
- check the connection of track C or D.
- replace the encoder or encoder cable.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31131 (N, A) Encoder 1: Deviation, position incremental/absolute too large

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: Absolute encoder: When cyclically reading the absolute position, an excessively high difference to the incremental position was detected. The absolute position that was read is rejected.
 Limit value for the deviation:
 - EnDat encoder: Is supplied from the encoder and is a minimum of 2 quadrants (e.g. EQI 1325 > 2 quadrants, EQN 1325 > 50 quadrants).
 - other encoders: 15 pulses = 60 quadrants.
 Fault value (r0949, decimal):
 Deviation in quadrants (1 pulse = 4 quadrants).
 Incremental encoder: When the zero pulse is passed, a deviation in the incremental position was detected.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - check that the encoder cables are routed in compliance with EMC.
 - check the plug connections.
 - replace the encoder or encoder cable.
 - check whether the coding disk is dirty or there are strong ambient magnetic fields.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31150 (N, A) Encoder 1: Initialization error

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: Encoder functionality selected in p0404 is not operating correctly.
 Fault value (r0949, interpret hexadecimal):
 The fault value is a bit field. Every set bit indicates functionality that is faulted.
 The bit assignment corresponds to that of p0404 (e.g. bit 5 set: Error track C/D).
 See also: p0404 (Encoder configuration effective), p0491 (Motor encoder fault response ENCODER)

Remedy: - Check that p0404 is correctly set.
 - check the encoder type used (incremental/absolute value) and for SMCxx, the encoder cable.
 - if relevant, note additional fault/error messages that describe the fault in detail.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A31400 (F, N) Encoder 1: Alarm threshold, zero mark distance error

Reaction: NONE

Acknowledge: NONE

Cause: The measured zero mark distance does not correspond to the parameterized zero mark distance.
 For distance-coded encoders, the zero mark distance is determined from zero marks detected pairs. This means that if a zero mark is missing, depending on the pair generation, this cannot result in a fault and also has no effect in the system.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Alarm value (r2124, decimal):
 Last measured zero mark distance in increments (4 increments = 1 encoder pulse).
 The sign designates the direction of motion when detecting the zero mark distance.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the distance between zero marks (p0424, p0425).
- replace the encoder or encoder cable.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A31401 (F, N) Encoder 1: Alarm threshold, zero marked failed

Reaction: NONE

Acknowledge: NONE

Cause: The 1.5 x parameterized zero mark distance was exceeded.
The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
Alarm value (r2124, decimal):
Number of increments after POWER ON or since the last zero mark that was detected (4 increments = 1 encoder pulse).

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the clearance between zero marks (p0425).
- replace the encoder or encoder cable.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

F31405 (N, A) Encoder 1: Encoder evaluation temperature too high

Reaction: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The encoder evaluation for a motor with DRIVE-CLiQ has detected an excessively high temperature.
The fault threshold is 125 ° C.
Alarm value (r2124, decimal):
Measured board/module temperature in 0.1 °C.

Remedy: Reduce the ambient temperature for the DRIVE-CLiQ connection of the motor.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

A31410 (F, N) Encoder 1: Serial communications

Reaction: NONE

Acknowledge: NONE

Cause: Serial communication protocol transfer error between the encoder and evaluation module.
 Alarm value (r2124, interpret binary):
 Bit 0: Alarm bit in the position protocol.
 Bit 1: Incorrect quiescent level on the data line.
 Bit 2: Encoder does not respond (does not supply a start bit within 50 ms).
 Bit 3: CRC error: The checksum in the protocol from the encoder does not match the data.
 Bit 4: Encoder acknowledgement error: The encoder incorrectly understood the task (request) or cannot execute it.
 Bit 5: Internal error in the serial driver: An illegal mode command was requested.
 Bit 6: Timeout with cyclically reading.
 Bit 8: Protocol is too long (e.g. > 64 bits).
 Bit 9: Receive buffer overflow.
 Bit 10: Frame error when reading twice.
 Bit 11: Parity error.
 Bit 12: Data line signal level error during the monoflop time.

Remedy:
 - check that the encoder cables are routed in compliance with EMC.
 - check the plug connections.
 - replace the encoder.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A31411 (F, N) Encoder 1: EnDat encoder signals alarms

Reaction: NONE

Acknowledge: NONE

Cause: The error word of the EnDat encoder has alarm bits that have been set.
 Alarm value (r2124, interpret binary):
 Bit 0: Frequency exceeded (speed too high).
 Bit 1: Temperature exceeded.
 Bit 2: Control reserve, lighting system exceeded.
 Bit 3: Battery discharged.
 Bit 4: Reference point passed.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Replace encoder.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A31414 (F, N)	Encoder 1: Amplitude error track C or D (C² + D²)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The amplitude (C² + D²) of track C or D of the encoder or from the Hall signals, is not within the tolerance bandwidth.</p> <p>The nominal signal must be in the range 375 mV to 600 mV (500 mV -25 % / +20 %).</p> <p>On the other hand, the response thresholds are < 230 mV and > 750 mV (frequency characteristic).</p> <p>This fault also occurs if the A/D converter is overcontrolled.</p> <p>If the amplitude is not within the tolerance bandwidth, then it cannot be used to initialize the start position.</p> <p>Alarm value (r2124, decimal):</p> <p>Low word: Signal level, track C (16 bits with sign).</p> <p>High word: Signal level, track D (16 bits with sign).</p> <p>A signal level of 500 mV corresponds to the numerical value 5333 hex = 21299 dec.</p> <p>See also: p0491 (Motor encoder fault response ENCODER)</p>
Remedy:	<ul style="list-style-type: none"> - check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder or encoder cable. - check the encoder module (e.g. contacts). - check the Hall sensor box
Reaction upon F:	<p>A_INFEED: NONE (OFF1, OFF2)</p> <p>SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)</p> <p>VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)</p>
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
N31415 (F, A)	Encoder 1: Amplitude alarm track A or B (A² + B²)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The amplitude (A² + B²) of track A or B is not within the tolerance bandwidth.</p> <p>SMC20: The nominal signal level is at 500 mV (500 mV -25 % / +20 %). The response threshold is < 300 mV.</p> <p>SMC10: The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is < 1414 mV (1.0 Vrms).</p> <p>Alarm value (r2124, decimal):</p> <p>Low word: Amplitude square root(A*A + B*B).</p> <p>SMC20:</p> <p>A signal level of 500 mV peak value corresponds to the numerical value 299A hex = 10650 dec.</p> <p>SMC10:</p> <p>A signal level of 2900 mV peak value corresponds to the numerical value 3333 hex = 13107 dec.</p> <p>High word:</p> <p>Angle 0 to 65535 corresponds to 0 to 360 degrees of the fine position. Zero degrees is at the negative zero crossover of track B.</p> <p>See also: p0491 (Motor encoder fault response ENCODER)</p>
Remedy:	<ul style="list-style-type: none"> - check the speed range, frequency characteristic (amplitude characteristic) of the measuring equipment is not sufficient for the speed range. - check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder or encoder cable. - check the encoder module (e.g. contacts). - dirty code disk - aged lighting system.
Reaction upon F:	<p>A_INFEED: NONE (OFF1, OFF2)</p> <p>SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)</p> <p>VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)</p>
Acknowledge upon F:	IMMEDIATELY
Reaction upon A:	NONE
Acknowledge upon A:	NONE

A31418 (F, N) Encoder 1: Speed difference per sampling rate exceeded

Reaction: NONE
Acknowledge: NONE
Cause: For an HTL/TTL encoder, the speed difference between two sampling cycles has exceeded the value in p0492.
 Alarm value (r2124, decimal):
 Only for internal Siemens troubleshooting.
Remedy: - check the tachometer feeder cable for interruptions.
 - check the grounding of the tachometer shielding.
 - if required, increase the setting of p0492.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A31419 (F, N) Encoder 1: Track A or B outside the tolerance range

Reaction: NONE
Acknowledge: NONE
Cause: The amplitude, phase or offset correction for track A or B is at the limit.
 Amplitude error correction: Amplitude B / Amplitude A = 0.78 ... 1.27
 Phase: <84 degrees or >96 degrees
 SMC20: Offset correction: +/-140 mV
 SMC10: Offset correction: +/-650 mV
 Alarm value (r2124, interpret hexadecimal):
 xxx1: Minimum of the offset correction, track B
 xxx2: Maximum of the offset correction, track B
 xx1x: Minimum of the offset correction, track A
 xx2x: Maximum of the offset correction, track A
 x1xx: Minimum of the amplitude correction, track B/A
 x2xx: Maximum of the amplitude correction, track B/A
 1xxx: Minimum of the phase error correction
 2xxx: Maximum of the phase error correction
 See also: p0491 (Motor encoder fault response ENCODER)
Remedy: - check mechanical mounting tolerances for encoders without their own bearings (e.g. toothed-wheel encoders).
 - check the plug connections (also the transition resistance).
 - check the encoder signals.
 - replace the encoder or encoder cable.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A31429 (F, N)	Encoder 1: Position difference, hall sensor/track C/D and A/B too large
Reaction:	NONE
Acknowledge:	NONE
Cause:	The error of track C/D is greater than +/-15 ° mechanical or +/-60 ° electrical. One period of track C/D corresponds to 360 ° mechanical. One period of the Hall signal corresponds to 360 ° electrical. The monitoring responds if, for example, Hall sensors are connected as equivalent for the C/D tracks with the incorrect rotational sense or supply values that are not accurate enough. Alarm value (r2124, decimal): Measured deviation as mechanical angle (16 bits with sign, 182 dec corresponds to 1 °). See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	- track C or D not connected. - correct the direction of rotation of the Hall sensor possibly connected as equivalent for track C/D. - check that the encoder cables are routed in compliance with EMC. - check the adjustment of the Hall sensor.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
A31431 (F, N)	Encoder 1: Deviation, position incremental/absolute too large
Reaction:	NONE
Acknowledge:	NONE
Cause:	Absolute encoder: When cyclically reading the absolute position, an excessively high difference to the incremental position was detected. Alarm value (r2124, decimal): Deviation in quadrants (1 pulse = 4 quadrants). Incremental encoder: When the zero pulse is passed, a deviation in the incremental position was detected. See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	- check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder or encoder cable. - coding disk dirty or strong magnetic fields.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
F31501 (N, A)	Encoder 1: Position tracking encoder position outside tolerance window
Reaction:	A_INFEED: NONE SERVO: OFF1 (NONE, OFF2, OFF3) VECTOR: OFF1 (NONE, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	When powered-down, the drive/encoder was moved through a distance greater than what was set in the tolerance window. See also: p0413 (Measuring gearbox, position tracking tolerance window)
Remedy:	Re-adjust the drive.
Reaction upon N:	NONE
Acknowledge upon N:	NONE

Reaction upon A: NONE
Acknowledge upon A: NONE

F31502 (N, A) Encoder 1: Encoder with measuring gear, without valid signals

Reaction: A_INFEED: OFF1 (OFF2)
SERVO: OFF1 (OFF2, OFF3)
VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The encoder with measuring gear no longer provides any valid signals.

Remedy: It must be ensured that all of the encoders, with mounted measuring gear, provide valid actual values in operation.

Reaction upon N: NONE
Acknowledge upon N: NONE

Reaction upon A: NONE
Acknowledge upon A: NONE

F31801 (N, A) Encoder 1 DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: OFF2 (NONE)
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
Fault value (r0949, interpret hexadecimal):
0A: The sign-of-life bit in the receive telegram is not set.
See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - check the electrical cabinet design and cable routing for EMC compliance.
- replace the component involved.
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
Acknowledge upon N: NONE

Reaction upon A: NONE
Acknowledge upon A: NONE

F31802 (N, A) Encoder 1: Time slice overflow

Reaction: A_INFEED: OFF2 (NONE)
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: Time slice overflow, encoder 1.
Fault value (r0949, decimal):
9: Time slice overflow of the fast (current controller clock cycle) time slice.
10: Time slice overflow of the average time slice.
12: Time slice overflow of the slow time slice.
999: Timeout when waiting for SYNO, e.g. unexpected return to non-cyclic operation.
See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Reduce the current controller frequency.

Reaction upon N: NONE
Acknowledge upon N: NONE

Reaction upon A: NONE
Acknowledge upon A: NONE

F31804 (N, A) Encoder 1: CRC CODE RAM

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: The checksum via the CODE-RAM of the Sensor Module has changed in operation.
 Fault value (r0949, interpret hexadecimal):
 Difference between the checksum at POWER ON and the actual checksum.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Hardware defect: Replace the Sensor Module.
 Firmware error: If required, upgrade the firmware.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31805 (N, A) Encoder 1: EPROM checksum error

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: Internal parameter data is corrupted.
 Fault value (r0949, interpret hexadecimal):
 01: EEPROM access error.
 02: Too many blocks in the EEPROM.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Replace the module.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31806 (N, A) Encoder 1: Initialization error

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The encoder was not successfully initialized.
 Fault value (r0949, interpret hexadecimal):
 1, 2, 3: Encoder initialization with the motor rotating.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Acknowledge the fault.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31811 (N, A) Encoder 1: Encoder serial number changed

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: NONE (ENCODER, OFF2)
 VECTOR: NONE (ENCODER, OFF2)

Acknowledge: IMMEDIATELY

Cause: The serial number of the motor encoder of a synchronous motor has changed. The change was only checked for encoders with serial number (e.g. EnDat encoders) and build-in motors (e.g. p300 = 401) or third-party motors (p0300 = 2).
 Cause 1:
 The motor with integrated and adjusted encoder was replaced.
 Cause 2:
 The encoder was replaced.
 Cause 3:
 A third-party, build-in or linear motor was re-commissioned.
 Cause 4:
 The firmware was updated to a version that checks the encoder serial number.
 If the position control is active, the serial numbers of the adjusted encoders (p2507 = 3) are checked.
 If the serial number has changed, the adjustment is reset (p2507 = 1).
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: Re causes 1, 4:
 Accept the new serial number with p0440 = 1.
 Re causes 2, 3:
 Carry-out an automatic adjustment using the pole position identification routine. First, accept the serial number with p0440 = 1. Acknowledge the fault. Initiate the pole position identification routine with p1990 = 1. Then check that the pole position identification routine is correctly executed.
 SERVO:
 If a pole position identification technique is selected in p1980, and if p0301 does not contain a motor type with an encoder adjusted in the factory, then p1990 is automatically activated.
 or
 Set the adjustment using parameter p0431. In this case, the new serial number is automatically accepted.
 or
 Mechanically adjust the encoder. Accept the new serial number with p0440 = 1.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31812 (N, A) Encoder 1: A cycle requested from the CU or RX/TX timing is not supported

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: A cycle requested from the CU or RX/TX timing is not supported
 Fault value (r0949):
 0: Application cycle is not supported.
 1: DQ cycle is not supported.
 2: Clearance between RX and TX instants in time too low.
 3: TX instant in time too early.

Remedy:

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31820 (N, A) Encoder 1 DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: OFF2
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
Fault value (r0949, interpret hexadecimal):
01: CRC error.
02: Telegram is shorter than specified in the length byte or in the receive list.
03: Telegram is longer than specified in the length byte or in the receive list.
04: The length of the receive telegram does not match the receive list.
05: The type of the receive telegram does not match the receive list.
06: The address of the encoder in the telegram and in the receive list do not match.
07: The encoder expects a SYNC telegram, but the receive telegram is not a SYNC telegram.
08: The encoder does not expect a SYNC telegram, but the receive telegram is a SYNC telegram.
09: The error bit in the receive telegram is set.
10: The receive telegram is too early.
See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - carry-out a POWER ON.
- check the electrical cabinet design and cable routing for EMC compliance.
- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31835 (N, A) Encoder 1 DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. The nodes do not send and receive in synchronism.
Fault value (r0949, interpret hexadecimal):
21: The cyclic telegram has not been received.
22: Timeout in the telegram receive list.
40: Timeout in the telegram send list.
See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - carry-out a POWER ON.
- replace the component involved.
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31836 (N, A)	Encoder 1 DRIVE-CLiQ: Send error for DRIVE-CLiQ data
Reaction:	A_INFEED: OFF2 SERVO: ENCODER (DCBRAKE, NONE) VECTOR: ENCODER (DCBRAKE, NONE)
Acknowledge:	IMMEDIATELY
Cause:	DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Data were not able to be sent. Fault value (r0949, interpret hexadecimal): 41: Telegram type does not match send list. See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	Carry-out a POWER ON.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F31837 (N, A)	Encoder 1 DRIVE-CLiQ: Component fault
Reaction:	A_INFEED: OFF2 SERVO: ENCODER (DCBRAKE, NONE) VECTOR: ENCODER (DCBRAKE, NONE)
Acknowledge:	IMMEDIATELY
Cause:	Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded. Fault value (r0949, interpret hexadecimal): 20: Error in the telegram header. 23: Receive error: The telegram buffer memory contains an error. 42: Send error: The telegram buffer memory contains an error. 43: Send error: The telegram buffer memory contains an error. See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). - check the electrical cabinet design and cable routing for EMC compliance. - if required, use another DRIVE-CLiQ socket (p9904). - replace the component involved.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F31845 (N, A)	Encoder 1 DRIVE-CLiQ: Cyclic data transfer error
Reaction:	A_INFEED: OFF2 SERVO: ENCODER (DCBRAKE, NONE) VECTOR: ENCODER (DCBRAKE, NONE)
Acknowledge:	IMMEDIATELY
Cause:	DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Fault value (r0949, interpret hexadecimal): 0B: Synchronization error during alternating cyclic data transfer. See also: p0491 (Motor encoder fault response ENCODER)
Remedy:	Carry-out a POWER ON. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F31850 (N, A) Encoder 1: Sensor Module, internal software error

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: POWER ON

Cause: Internal software error in the Sensor Module of encoder 1.
 Fault value (r0949, decimal):
 1: Background time slice is blocked.
 2: Checksum over the code memory is not OK.
 10000: OEM memory of the EnDat encoder contains data that cannot be interpreted.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy:
 - replace the Sensor Module.
 - if required, upgrade the firmware in the Sensor Module.
 - contact the Hotline.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31851 (N, A) CU DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Sensor Module (encoder 1) involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit.
 Fault value (r0949, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.

Remedy: Upgrade the firmware of the component involved.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31860 (N, A) CU DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 11: CRC error and the receive telegram is too early.
 01: CRC error.
 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early.
 02: Telegram is shorter than specified in the length byte or in the receive list.
 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early.
 03: Telegram is longer than specified in the length byte or in the receive list.
 14: The length of the receive telegram does not match the receive list and the receive telegram is too early.
 04: The length of the receive telegram does not match the receive list.
 15: The type of the receive telegram does not match the receive list and the receive telegram is too early.
 05: The type of the receive telegram does not match the receive list.
 16: The address of the encoder in the telegram and in the receive list does not match and the receive telegram is too early.
 06: The address of the encoder in the telegram and in the receive list do not match.
 19: The error bit in the receive telegram is set and the receive telegram is too early.
 09: The error bit in the receive telegram is set.
 10: The receive telegram is too early.

Remedy: - carry-out a POWER ON.
 - check the electrical cabinet design and cable routing for EMC compliance.
 - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31885 (N, A) CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. The nodes do not send and receive in synchronism.
 Fault value (r0949, interpret hexadecimal):
 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early.
 21: The cyclic telegram has not been received.
 22: Timeout in the telegram receive list.
 40: Timeout in the telegram send list.
 62: Error at the transition to cyclic operation.

Remedy: - check the power supply voltage of the component involved.
 - carry-out a POWER ON.
 - replace the component involved.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31886 (N, A) CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data

Reaction: A_INFEED: NONE (OFF1, OFF2)
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Data were not able to be sent.
Fault value (r0949, interpret hexadecimal):
41: Telegram type does not match send list.

Remedy: - carry-out a POWER ON.
- check whether the firmware version of the encoder (r0148) matches the firmware version of Control Unit (r0018).

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31887 (N, A) CU DRIVE-CLiQ: Component fault

Reaction: A_INFEED: NONE (OFF1, OFF2)
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
Fault value (r0949, interpret hexadecimal):
20: Error in the telegram header.
23: Receive error: The telegram buffer memory contains an error.
42: Send error: The telegram buffer memory contains an error.
43: Send error: The telegram buffer memory contains an error.
60: Response received too late during runtime measurement.
61: Time taken to exchange characteristic data too long.

Remedy: - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31895 (N, A) CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: NONE (OFF1, OFF2)
SERVO: ENCODER (DCBRAKE, NONE)
VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
Fault value (r0949, interpret hexadecimal):
0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F31896 (N, A) CU DRIVE-CLiQ: Inconsistent component characteristics

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced.
 Fault value (r0949, decimal):
 Component ID.

Remedy: - when replacing cables, only use cables with the same length as the original cables.
 - when replacing components, use the same components and firmware releases.
 - carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31897 (N, A) DRIVE-CLiQ: No communication to component

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: Communications with the DRIVE-CLiQ component specified by the fault value is not possible.
 One cause can be, e.g. that a DRIVE-CLiQ cable has been withdrawn.
 Fault value (r0949, decimal):
 Component ID.

Remedy: - check the DRIVE-CLiQ connections.
 - carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31899 (N, A) Encoder 1: Unknown fault

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: A fault occurred on the Sensor Module for encoder 1 that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the Sensor Module for encoder 1 is more recent than the firmware on the Control Unit.
 Fault value (r0949, decimal):
 Fault number.
 If required, the significance of this new fault can be read about in a more recent description of the Control Unit.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - replace the firmware on the Sensor Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F31905 (N, A) Encoder 1: Parameterization error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: ENCODER (DCBRAKE, NONE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: A parameter of encoder 1 was detected as being incorrect.
 It is possible that the parameterized encoder type does not match the connected encoder.
 The parameter involved can be determined as follows:
 - determine the parameter number using the fault value (r0949).
 - determine the parameter index (p0187).
 Fault value (r0949, decimal):
 Parameter number.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - check whether the connected encoder type matches the encoder that has been parameterized.
 - correct the parameter specified by the fault value (r0949) and p0187.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A31920 (F, N) Encoder 1: Temperature sensor fault

Reaction: NONE

Acknowledge: NONE

Cause: When evaluating the temperature sensor, an error occurred.
 Alarm value (r2124, decimal):
 1: Wire breakage or sensor not connected (KTY: R > 1630 Ohm).
 2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - check that the encoder cable is the correct type and is correctly connected.
 - check the temperature sensor selection in p0600 to p0603.
 - replace the Sensor Module (hardware defect or incorrect calibration data).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE
 Acknowledge upon N: NONE

A31999 (F, N) Encoder 1: Unknown alarm

Reaction: NONE

Acknowledge: NONE

Cause: A alarm has occurred on the Sensor Module for encoder 1 that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the Sensor Module for encoder 1 is more recent than the firmware on the Control Unit.
 Alarm value (r2124, decimal):
 Alarm number.
 If required, the significance of this new alarm can be read about in a more recent description of the Control Unit.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy: - replace the firmware on the Sensor Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, ENCODER, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

F32100 (N, A) Encoder 2: Zero mark clearance error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: The measured zero mark distance does not correspond to the parameterized zero mark distance.
 For distance-coded encoders, the zero mark distance is determined from zero marks detected pairs. This means that if a zero mark is missing, depending on the pair generation, this cannot result in a fault and also has no effect in the system.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Fault value (r0949, decimal):
 Last measured zero mark distance in increments (4 increments = 1 encoder pulse).
 The sign designates the direction of motion when detecting the zero mark distance.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the distance between zero marks (p0424, p0425).
- replace the encoder or encoder cable.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F32101 (N, A) Encoder 2: Zero marked failed

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: The 1.5 x parameterized zero mark distance was exceeded.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Fault value (r0949, decimal):
 Number of increments after POWER ON or since the last zero mark that was detected (4 increments = 1 encoder pulse).

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the clearance between zero marks (p0425).
- replace the encoder or encoder cable.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F32110 (N, A) Encoder 2: Serial communications error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: Serial communication protocol transfer error between the encoder and evaluation module.
 Fault value (r0949, interpret binary):
 Bit 0: Alarm bit in the position protocol.
 Bit 1: Incorrect quiescent level on the data line.
 Bit 2: Encoder does not respond (does not supply a start bit within 50 ms).
 Bit 3: CRC error: The checksum in the protocol from the encoder does not match the data.
 Bit 4: Encoder acknowledgement error: The encoder incorrectly understood the task (request) or cannot execute it.
 Bit 5: Internal error in the serial driver: An illegal mode command was requested.
 Bit 6: Timeout with cyclically reading.
 Bit 8: Protocol is too long (e.g. > 64 bits).
 Bit 9: Receive buffer overflow
 Bit 10: Frame error when reading twice.
 Bit 11: Parity error.
 Bit 12: Data line signal level error during the monoflop time.

Remedy: Re fault value:
 Bit 0 = 1: Encoder defective. F31111 may provide additional details.
 Bit 1 = 1: Incorrect encoder type / replace the encoder or encoder cable.
 Bit 2 = 1: Incorrect encoder type / replace the encoder or encoder cable.
 Bit 3 = 1: EMC / connect the cable shield, replace the encoder or encoder cable.
 Bit 4 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 5 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 6 = 1: Update the Sensor Module firmware.
 Bit 8 = 1: Check the parameterization (p0429.2).
 Bit 9 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 10 = 1: Check the parameterization (p0429.2, p0449).
 Bit 11 = 1: Check the parameterization (p0436).
 Bit 12 = 1: Check the parameterization (p0429.6).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32111 (N, A) Encoder 2: Absolute encoder EnDat, internal fault/error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: The EnDat encoder fault word contains fault bits that have been set.
 Fault value (r0949, interpret binary):
 Bit 0: Lighting system failed.
 Bit 1: Signal amplitude too low.
 Bit 2: Position value incorrect.
 Bit 3: Encoder power supply overvoltage condition.
 Bit 4: Encoder power supply undervoltage condition.
 Bit 5: Encoder power supply overcurrent condition.
 Bit 6: The battery must be changed.

Remedy:

Re fault value, bit 0 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 1 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 2 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 3 = 1:
5 V power supply voltage fault.
When using an SMC: Check the plug-in cable between the encoder and SMC or replace the SMC.
When a motor encoder with a direct DRIVE-CLiQ connection is used: Replace the motor.

Re fault value, bit 4 = 1:
5 V power supply voltage fault.
When using an SMC: Check the plug-in cable between the encoder and SMC or replace the SMC.
When using a motor with DRIVE-CLiQ: Replace the motor.

Re fault value, bit 5 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 6 = 1:
The battery must be changed - only for encoders with battery back-up.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32112 (N, A) Encoder 2: The error bit is set in the serial protocol

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: Serial communication protocol transfer error between the encoder and evaluation module SMCxx.
Fault value (r0949, decimal):

Remedy: Re fault value:

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32115 (N, A) Encoder 2: Amplitude error track A or B (A² + B²)

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: The amplitude (A² + B²) does not lie within the tolerance bandwidth (software monitoring function).
 SMC20:
 The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
 On the other hand, the response threshold is < 230 mV (frequency characteristic).
 SMC10:
 The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is < 1070 mV.
 Fault value (r0949, decimal):
 Low word:
 Signal level, track A (16 bits with sign).
 High word:
 Signal level, track B (16 bits with sign).
 SMC20:
 A signal level of 500 mV peak value corresponds to the numerical value 5333 hex = 21299 dec.
 SMC10:
 A signal level of 2900 mV peak value corresponds to the numerical value 6666 hex = 26214 dec.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check the encoder module (e.g. contacts).
- with measuring systems without their own bearing system: Adjust the scanning head and check the bearing system of the measuring wheel.
- for measuring systems with their own bearing system: Ensure that the encoder housing is not subject to any axial force.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32116 (N, A) Encoder 2: Amplitude error, monitoring track A + B

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The amplitude of the rectified encoder signals A and B is not within the tolerance bandwidth (hardware monitoring).
 The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
 On the other hand, the hardware response thresholds are at < 176 mV and > 1.35 V.
 Fault value (r0949, decimal):
 Low word: Signal level, track A (16 bits with sign).
 High word: Signal level, track B (16 bits with sign).
 A signal level of 500 mV corresponds to the numerical value 5333 hex = 21299 dec.
 These analog values are not measured at the same time with the hardware fault output.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check the encoder module (e.g. contacts).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32117 (N, A) Encoder 2: Inversion error, signals A and B and R

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: For a square-wave signal encoder (TTL. bipolar. double ended) the A* and B* and R* signals are not inverted with respect to signals A and B and R.

Remedy: Check the setting of p0405: p0405.2 = 1 is only possible if the encoder is connected at X520.
Check the encoder/cable: Does the encoder supply TTL signals and the associated inverted signals?

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32118 (N, A) Encoder 2: Speed difference outside the tolerance range

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: For an HTL/TTL encoder, the speed difference has exceeded the value in p0492 over several sampling cycles.
Fault value (r0949, decimal):
Only for internal Siemens troubleshooting.

Remedy: - check the tachometer feeder cable for interruptions.
- check the grounding of the tachometer shielding.
- if required, increase the maximum speed difference per sampling cycle (p0492).

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32120 (N, A) Encoder 2: Power supply voltage

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: Encoder power supply voltage fault.
Note:
If the encoder cables 6FX2002-2EQ00-.... and 6FX2002-2CH00-.... are interchanged, this can result in the encoder being destroyed because the pins of the operating voltage are reversed.
Fault value (r0949, interpret binary):
Bit 0: Undervoltage condition on the sense line (threshold 4.75 V).
Bit 1: Encoder power supply voltage overcurrent condition (threshold 450 mA).

Remedy: For fault value, bit 0 = 1:
- correct encoder cable connected?
- check the plug connections of the encoder cable.
- SMC30: Check the parameterization (p0404.22).
For fault value, bit 1 = 1:
- correct encoder cable connected?
- replace the encoder or encoder cable.

Reaction upon N: NONE
Acknowledge upon N: NONE

Reaction upon A: NONE
 Acknowledge upon A: NONE

F32121 (N, A) Encoder 2: Coarse position error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: For the actual value sensing, an error was detected on the module. As a result of this error, it must be assumed that the actual value sensing supplies an incorrect coarse position.

Remedy: Replace the motor with DRIVE-CLiQ or the appropriate Sensor Module.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F32125 (N, A) Encoder 1: Amplitude error track A or B overcontrolled

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The amplitude (track A or B) does not lie within the tolerance bandwidth (software monitoring function).

SMC20:

The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).

On the other hand, the response threshold is > 760 mV (frequency characteristic).

SMC10:

The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is > 3582 mV.

Fault value (r0949, decimal):

Low word:

Signal level, track A (16 bits with sign).

High word:

Signal level, track B (16 bits with sign).

SMC20:

A signal level of 500 mV peak value corresponds to the numerical value 5333 hex = 21299 dec.

SMC10:

A signal level of 2900 mV peak value corresponds to the numerical value 6666 hex = 26214 dec.

See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- replace the encoder or encoder cable.
- with measuring systems without their own bearing system: Adjust the scanning head and check the bearing system of the measuring wheel.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F32129 (N, A)	Encoder 2: Position difference, hall sensor/track C/D and A/B too large
Reaction:	A_INFEED: NONE SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3) VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
Acknowledge:	PULSE INHIBIT
Cause:	The error of track C/D is greater than +/-15 ° mechanical or +/-60 ° electrical. One period of track C/D corresponds to 360 ° mechanical. One period of the Hall signal corresponds to 360 ° electrical. The monitoring responds if, for example, Hall sensors are connected as equivalent for the C/D tracks with the incorrect rotational sense or supply values that are not accurate enough. After the fine synchronization using one reference mark or 2 reference marks for distance-coded encoders, this fault is no longer initiated, but instead, Alarm A32429. Fault value (r0949, decimal): Measured deviation as mechanical angle (16 bits with sign, 182 dec corresponds to 1 °).
Remedy:	- track C or D not connected. - correct the direction of rotation of the Hall sensor possibly connected as equivalent for track C/D. - check that the encoder cables are routed in compliance with EMC. - check the adjustment of the Hall sensor.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F32130 (N, A)	Encoder 2: Zero mark and position error from the coarse synchronization
Reaction:	A_INFEED: NONE SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2) VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	PULSE INHIBIT
Cause:	After initializing the pole position using track C/D, Hall signals or pole position identification routine, the zero mark was detected outside the permissible range. For distance-coded encoders, the test is carried-out after passing 2 zero marks. Fine synchronization was not carried-out. The deviation may be up to 18 ° mechanical or up to 60 ° electrical. Fault value (r0949, decimal): Normalization: 32768 = 180 ° High word: Mechanical zero mark position determined. If the initialization via a track C/D is selected in p0404, then it is checked whether the zero mark occurs in an angular range of +/-18 ° mechanical. Low word: Deviation of the zero mark from the expected position as electrical angle. If the correction of the commutation position with the zero mark is selected in p0404, then a difference of a maximum of +/- 60 ° electrical is permitted.
Remedy:	- check that the encoder cables are routed in compliance with EMC. - check the plug connections. - if the Hall sensor is used as an equivalent for track C/D, check the connection. - check the connection of track C or D. - replace the encoder or encoder cable.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F32131 (N, A) Encoder 2: Deviation, position incremental/absolute too large

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: Absolute encoder: When cyclically reading the absolute position, an excessively high difference to the incremental position was detected. The absolute position that was read is rejected.
 Limit value for the deviation:
 - EnDat encoder: Is supplied from the encoder and is a minimum of 2 quadrants (e.g. EQI 1325 > 2 quadrants, EQN 1325 > 50 quadrants).
 - other encoders: 15 pulses = 60 quadrants.
 Fault value (r0949, decimal):
 Deviation in quadrants (1 pulse = 4 quadrants).
 Incremental encoder: When the zero pulse is passed, a deviation in the incremental position was detected.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check whether the coding disk is dirty or there are strong ambient magnetic fields.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32150 (N, A) Encoder 2: Initialization error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: Encoder functionality selected in p0404 is not operating correctly.
 Fault value (r0949, interpret hexadecimal):
 The fault value is a bit field. Every set bit indicates functionality that is faulted.
 The bit assignment corresponds to that of p0404 (e.g. bit 5 set: Error track C/D).

Remedy:

- Check that p0404 is correctly set.
- check the encoder type used (incremental/absolute value) and for SMCxx, the encoder cable.
- if relevant, note additional fault/error messages that describe the fault in detail.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A32400 (F, N) Encoder 2: Alarm threshold, zero mark distance error

Reaction: NONE

Acknowledge: NONE

Cause: The measured zero mark distance does not correspond to the parameterized zero mark distance.
 For distance-coded encoders, the zero mark distance is determined from zero marks detected pairs. This means that if a zero mark is missing, depending on the pair generation, this cannot result in a fault and also has no effect in the system.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Alarm value (r2124, decimal):
 Last measured zero mark distance in increments (4 increments = 1 encoder pulse).
 The sign designates the direction of motion when detecting the zero mark distance.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the distance between zero marks (p0424, p0425).
- replace the encoder or encoder cable.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A32401 (F, N) Encoder 2: Alarm threshold, zero marked failed

Reaction: NONE

Acknowledge: NONE

Cause: The 1.5 x parameterized zero mark distance was exceeded.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Alarm value (r2124, decimal):
 Number of increments after POWER ON or since the last zero mark that was detected (4 increments = 1 encoder pulse).

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the clearance between zero marks (p0425).
- replace the encoder or encoder cable.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

F32405 (N, A) Encoder 2: Encoder evaluation temperature too high

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The encoder evaluation for a motor with DRIVE-CLiQ has detected an excessively high temperature.
 The fault threshold is 125 ° C.
 Alarm value (r2124, decimal):
 Measured board/module temperature in 0.1 °C.

Remedy: Reduce the ambient temperature for the DRIVE-CLiQ connection of the motor.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

A32410 (F, N)	Encoder 2: Serial communications
Reaction:	NONE
Acknowledge:	NONE
Cause:	Serial communication protocol transfer error between the encoder and evaluation module. Alarm value (r2124, interpret binary): Bit 0: Alarm bit in the position protocol. Bit 1: Incorrect quiescent level on the data line. Bit 2: Encoder does not respond (does not supply a start bit within 50 ms). Bit 3: CRC error: The checksum in the protocol from the encoder does not match the data. Bit 4: Encoder acknowledgement error: The encoder incorrectly understood the task (request) or cannot execute it. Bit 5: Internal error in the serial driver: An illegal mode command was requested. Bit 6: Timeout with cyclically reading. Bit 8: Protocol is too long (e.g. > 64 bits). Bit 9: Receive buffer overflow. Bit 10: Frame error when reading twice. Bit 11: Parity error. Bit 12: Data line signal level error during the monoflop time.
Remedy:	- check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A32411 (F, N)	Encoder 2: EnDat encoder signals alarms
Reaction:	NONE
Acknowledge:	NONE
Cause:	The error word of the EnDat encoder has alarm bits that have been set. Alarm value (r2124, interpret binary): Bit 0: Frequency exceeded (speed too high). Bit 1: Temperature exceeded. Bit 2: Control reserve, lighting system exceeded. Bit 3: Battery discharged. Bit 4: Reference point passed.
Remedy:	Replace encoder.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A32414 (F, N) Encoder 2: Amplitude error track C or D (C² + D²)

Reaction: NONE
Acknowledge: NONE
Cause: The amplitude (C² + D²) of track C or D of the encoder or from the Hall signals, is not within the tolerance bandwidth.
 The nominal signal must be in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
 On the other hand, the response thresholds are < 230 mV and > 750 mV (frequency characteristic).
 This fault also occurs if the A/D converter is overcontrolled.
 If the amplitude is not within the tolerance bandwidth, then it cannot be used to initialize the start position.
 Alarm value (r2124, decimal):
 Low word: Signal level, track C (16 bits with sign).
 High word: Signal level, track D (16 bits with sign).
 A signal level of 500 mV corresponds to the numerical value 5333 hex = 21299 dec.
Remedy:
 - check that the encoder cables are routed in compliance with EMC.
 - check the plug connections.
 - replace the encoder or encoder cable.
 - check the encoder module (e.g. contacts).
 - check the Hall sensor box
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

N32415 (F, A) Encoder 2: Amplitude alarm track A or B (A² + B²)

Reaction: NONE
Acknowledge: NONE
Cause: The amplitude (A² + B²) of track A or B is not within the tolerance bandwidth.
 SMC20: The nominal signal level is at 500 mV (500 mV -25 % / +20 %). The response threshold is < 300 mV.
 SMC10:
 The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is < 1414 mV (1.0 Vrms).
 Alarm value (r2124, decimal):
 Low word:
 Amplitude square root(A*A + B*B).
 SMC20:
 A signal level of 500 mV peak value corresponds to the numerical value 299A hex = 10650 dec.
 SMC10:
 A signal level of 2900 mV peak value corresponds to the numerical value 3333 hex = 13107 dec.
 High word:
 Angle 0 to 65535 corresponds to 0 to 360 degrees of the fine position. Zero degrees is at the negative zero crossover of track B.
Remedy:
 - check the speed range, frequency characteristic (amplitude characteristic) of the measuring equipment is not sufficient for the speed range.
 - check that the encoder cables are routed in compliance with EMC.
 - check the plug connections.
 - replace the encoder or encoder cable.
 - check the encoder module (e.g. contacts).
 - dirty code disk
 - aged lighting system.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A32418 (F, N)	Encoder 2: Speed difference per sampling rate exceeded
Reaction:	NONE
Acknowledge:	NONE
Cause:	For an HTL/TTL encoder, the speed difference between two sampling cycles has exceeded the value in p0492. Alarm value (r2124, decimal): Only for internal Siemens troubleshooting.
Remedy:	- check the tachometer feeder cable for interruptions. - check the grounding of the tachometer shielding. - if required, increase the setting of p0492.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
A32419 (F, N)	Encoder 2: Track A or B outside the tolerance range
Reaction:	NONE
Acknowledge:	NONE
Cause:	The amplitude, phase or offset correction for track A or B is at the limit. Amplitude error correction: Amplitude B / Amplitude A = 0.78 ... 1.27 Phase: <84 degrees or >96 degrees SMC20: Offset correction: +/-140 mV SMC10: Offset correction: +/-650 mV Alarm value (r2124, interpret hexadecimal): xxx1: Minimum of the offset correction, track B xxx2: Maximum of the offset correction, track B xx1x: Minimum of the offset correction, track A xx2x: Maximum of the offset correction, track A x1xx: Minimum of the amplitude correction, track B/A x2xx: Maximum of the amplitude correction, track B/A 1xxx: Minimum of the phase error correction 2xxx: Maximum of the phase error correction
Remedy:	- check mechanical mounting tolerances for encoders without their own bearings (e.g. toothed-wheel encoders). - check the plug connections (also the transition resistance). - check the encoder signals. - replace the encoder or encoder cable.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE
A32429 (F, N)	Encoder 2: Position difference, hall sensor/track C/D and A/B too large
Reaction:	NONE
Acknowledge:	NONE
Cause:	The error of track C/D is greater than +/-15 ° mechanical or +/-60 ° electrical. One period of track C/D corresponds to 360 ° mechanical. One period of the Hall signal corresponds to 360 ° electrical. The monitoring responds if, for example, Hall sensors are connected as equivalent for the C/D tracks with the incorrect rotational sense or supply values that are not accurate enough. Alarm value (r2124, decimal): Measured deviation as mechanical angle (16 bits with sign, 182 dec corresponds to 1 °).

Remedy:

- track C or D not connected.
- correct the direction of rotation of the Hall sensor possibly connected as equivalent for track C/D.
- check that the encoder cables are routed in compliance with EMC.
- check the adjustment of the Hall sensor.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A32431 (F, N) Encoder 2: Deviation, position incremental/absolute too large

Reaction: NONE

Acknowledge: NONE

Cause: Absolute encoder: When cyclically reading the absolute position, an excessively high difference to the incremental position was detected.
 Alarm value (r2124, decimal):
 Deviation in quadrants (1 pulse = 4 quadrants).
 Incremental encoder: When the zero pulse is passed, a deviation in the incremental position was detected.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- coding disk dirty or strong magnetic fields.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

F32501 (N, A) Encoder 2: Position tracking encoder position outside tolerance window

Reaction: A_INFEED: NONE
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: When powered-down, the drive/encoder was moved through a distance greater than what was set in the tolerance window.
 See also: p0413 (Measuring gearbox, position tracking tolerance window)

Remedy: Re-adjust the drive.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F32502 (N, A) Encoder 2: Encoder with measuring gear, without valid signals

Reaction: A_INFEED: OFF1 (OFF2)
 SERVO: OFF1 (OFF2, OFF3)
 VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The encoder with measuring gear no longer provides any valid signals.

Remedy: It must be ensured that all of the encoders, with mounted measuring gear, provide valid actual values in operation.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32801 (N, A) Encoder 2 DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.

Remedy: - check the electrical cabinet design and cable routing for EMC compliance.
 - replace the component involved.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32802 (N, A) Encoder 2: Time slice overflow

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Time slice overflow, encoder 2.
 Fault value (r0949, decimal):
 9: Time slice overflow of the fast (current controller clock cycle) time slice.
 10: Time slice overflow of the average time slice.
 12: Time slice overflow of the slow time slice.
 999: Timeout when waiting for SYNO, e.g. unexpected return to non-cyclic operation.

Remedy: Reduce the current controller frequency.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32804 (N, A) Encoder 2: CRC CODE RAM

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The checksum via the CODE-RAM of the Sensor Module has changed in operation.
Fault value (r0949, interpret hexadecimal):
Difference between the checksum at POWER ON and the actual checksum.

Remedy: Hardware defect: Replace the Sensor Module.
Firmware error: If required, upgrade the firmware.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32805 (N, A) Encoder 2: EPROM checksum error

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Internal parameter data is corrupted.
Fault value (r0949, interpret hexadecimal):
01: EEPROM access error.
02: Too many blocks in the EEPROM.

Remedy: Replace the module.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32806 (N, A) Encoder 2: Initialization error

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: The encoder was not successfully initialized.
Fault value (r0949, interpret hexadecimal):
1, 2, 3: Encoder initialization with the motor rotating.

Remedy: Acknowledge the fault.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32812 (N, A) Encoder 2: A cycle requested from the CU or RX/TX timing is not supported

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: A cycle requested from the CU or RX/TX timing is not supported
 Fault value (r0949):
 0: Application cycle is not supported.
 1: DQ cycle is not supported.
 2: Clearance between RX and TX instants in time too low.
 3: TX instant in time too early.

Remedy:
 Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32820 (N, A) Encoder 2 DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 01: CRC error.
 02: Telegram is shorter than specified in the length byte or in the receive list.
 03: Telegram is longer than specified in the length byte or in the receive list.
 04: The length of the receive telegram does not match the receive list.
 05: The type of the receive telegram does not match the receive list.
 06: The address of the encoder in the telegram and in the receive list do not match.
 07: The encoder expects a SYNC telegram, but the receive telegram is not a SYNC telegram.
 08: The encoder does not expect a SYNC telegram, but the receive telegram is a SYNC telegram.
 09: The error bit in the receive telegram is set.
 10: The receive telegram is too early.

Remedy:
 - carry-out a POWER ON.
 - check the electrical cabinet design and cable routing for EMC compliance.
 - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32835 (N, A) Encoder 2 DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. The nodes do not send and receive in synchronism.
 Fault value (r0949, interpret hexadecimal):
 21: The cyclic telegram has not been received.
 22: Timeout in the telegram receive list.
 40: Timeout in the telegram send list.

Remedy:
 - carry-out a POWER ON.
 - replace the component involved.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32836 (N, A) Encoder 2 DRIVE-CLiQ: Send error for DRIVE-CLiQ data

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32837 (N, A) Encoder 2 DRIVE-CLiQ: Component fault

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.

Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32845 (N, A) Encoder 2 DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32850 (N, A) Encoder 2: Sensor Module, internal software error

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: POWER ON

Cause: Internal software error in the Sensor Module of encoder 2.
Fault value (r0949, decimal):
1: Background time slice is blocked.
2: Checksum over the code memory is not OK.
10000: OEM memory of the EnDat encoder contains data that cannot be interpreted.

Remedy: - replace the Sensor Module.
- if required, upgrade the firmware in the Sensor Module.
- contact the Hotline.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32851 (N, A) CU DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: NONE (OFF1, OFF2)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Sensor Module (encoder 2) involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit.
Fault value (r0949, interpret hexadecimal):
0A: The sign-of-life bit in the receive telegram is not set.

Remedy: Upgrade the firmware of the component involved.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F32860 (N, A) CU DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 11: CRC error and the receive telegram is too early.
 01: CRC error.
 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early.
 02: Telegram is shorter than specified in the length byte or in the receive list.
 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early.
 03: Telegram is longer than specified in the length byte or in the receive list.
 14: The length of the receive telegram does not match the receive list and the receive telegram is too early.
 04: The length of the receive telegram does not match the receive list.
 15: The type of the receive telegram does not match the receive list and the receive telegram is too early.
 05: The type of the receive telegram does not match the receive list.
 16: The address of the encoder in the telegram and in the receive list does not match and the receive telegram is too early.
 06: The address of the encoder in the telegram and in the receive list do not match.
 19: The error bit in the receive telegram is set and the receive telegram is too early.
 09: The error bit in the receive telegram is set.
 10: The receive telegram is too early.

Remedy: - carry-out a POWER ON.
 - check the electrical cabinet design and cable routing for EMC compliance.
 - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32885 (N, A) CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. The nodes do not send and receive in synchronism.
 Fault value (r0949, interpret hexadecimal):
 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early.
 21: The cyclic telegram has not been received.
 22: Timeout in the telegram receive list.
 40: Timeout in the telegram send list.
 62: Error at the transition to cyclic operation.

Remedy: - check the power supply voltage of the component involved.
 - carry-out a POWER ON.
 - replace the component involved.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32886 (N, A) CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32887 (N, A) CU DRIVE-CLiQ: Component fault

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
 60: Response received too late during runtime measurement.
 61: Time taken to exchange characteristic data too long.

Remedy: - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 - check the electrical cabinet design and cable routing for EMC compliance.
 - if required, use another DRIVE-CLiQ socket (p9904).
 - replace the component involved.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32895 (N, A) CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32896 (N, A) CU DRIVE-CLiQ: Inconsistent component characteristics

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced.
 Fault value (r0949, decimal):
 Component ID.

Remedy: - when replacing cables, only use cables with the same length as the original cables.
 - when replacing components, use the same components and firmware releases.
 - carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32897 (N, A) DRIVE-CLiQ: No communication to component

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: Communications with the DRIVE-CLiQ component specified by the fault value is not possible.
 One cause can be, e.g. that a DRIVE-CLiQ cable has been withdrawn.
 Fault value (r0949, decimal):
 Component ID.

Remedy: - check the DRIVE-CLiQ connections.
 - carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32899 (N, A) Encoder 2: Unknown fault

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: A fault occurred on the Sensor Module for encoder 2 that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the Sensor Module for encoder 2 is more recent than the firmware on the Control Unit.
 Fault value (r0949, decimal):
 Fault number.
 If required, the significance of this new fault can be read about in a more recent description of the Control Unit.

Remedy: - replace the firmware on the Sensor Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F32905 (N, A) Encoder 2: Parameterization error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: A parameter of encoder 2 was detected as being incorrect.
 It is possible that the parameterized encoder type does not match the connected encoder.
 The parameter involved can be determined as follows:
 - determine the parameter number using the fault value (r0949).
 - determine the parameter index (p0188).
 Fault value (r0949, decimal):
 Parameter number.

Remedy: - check whether the connected encoder type matches the encoder that has been parameterized.
 - correct the parameter specified by the fault value (r0949) and p0188.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A32920 (F, N) Encoder 2: Temperature sensor fault

Reaction: NONE

Acknowledge: NONE

Cause: When evaluating the temperature sensor, an error occurred. Alarm value (r2124, decimal):
 1: Wire breakage or sensor not connected (KTY: R > 1630 Ohm).
 2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).

Remedy: - check that the encoder cable is the correct type and is correctly connected.
 - check the temperature sensor selection in p0600 to p0603.
 - replace the Sensor Module (hardware defect or incorrect calibration data).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE
 Acknowledge upon N: NONE

A32999 (F, N) Encoder 2: Unknown alarm

Reaction: NONE

Acknowledge: NONE

Cause: A alarm has occurred on the Sensor Module for encoder 2 that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the Sensor Module for encoder 2 is more recent than the firmware on the Control Unit.
 Alarm value (r2124, decimal):
 Alarm number.
 If required, the significance of this new alarm can be read about in a more recent description of the Control Unit.

Remedy: - replace the firmware on the Sensor Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE
 Acknowledge upon N: NONE

F33100 (N, A) Encoder 3: Zero mark clearance error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: The measured zero mark distance does not correspond to the parameterized zero mark distance.
 For distance-coded encoders, the zero mark distance is determined from zero marks detected pairs. This means that if a zero mark is missing, depending on the pair generation, this cannot result in a fault and also has no effect in the system.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Fault value (r0949, decimal):
 Last measured zero mark distance in increments (4 increments = 1 encoder pulse).
 The sign designates the direction of motion when detecting the zero mark distance.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the distance between zero marks (p0424, p0425).
- replace the encoder or encoder cable.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33101 (N, A) Encoder 3: Zero marked failed

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: The 1.5 x parameterized zero mark distance was exceeded.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Fault value (r0949, decimal):
 Number of increments after POWER ON or since the last zero mark that was detected (4 increments = 1 encoder pulse).

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the clearance between zero marks (p0425).
- replace the encoder or encoder cable.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33110 (N, A) Encoder 3: Serial communications error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: Serial communication protocol transfer error between the encoder and evaluation module.
 Fault value (r0949, interpret binary):
 Bit 0: Alarm bit in the position protocol.
 Bit 1: Incorrect quiescent level on the data line.
 Bit 2: Encoder does not respond (does not supply a start bit within 50 ms).
 Bit 3: CRC error: The checksum in the protocol from the encoder does not match the data.
 Bit 4: Encoder acknowledgement error: The encoder incorrectly understood the task (request) or cannot execute it.
 Bit 5: Internal error in the serial driver: An illegal mode command was requested.
 Bit 6: Timeout with cyclically reading.
 Bit 8: Protocol is too long (e.g. > 64 bits).
 Bit 9: Receive buffer overflow
 Bit 10: Frame error when reading twice.
 Bit 11: Parity error.
 Bit 12: Data line signal level error during the monoflop time.

Remedy: Re fault value:
 Bit 0 = 1: Encoder defective. F31111 may provide additional details.
 Bit 1 = 1: Incorrect encoder type / replace the encoder or encoder cable.
 Bit 2 = 1: Incorrect encoder type / replace the encoder or encoder cable.
 Bit 3 = 1: EMC / connect the cable shield, replace the encoder or encoder cable.
 Bit 4 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 5 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 6 = 1: Update the Sensor Module firmware.
 Bit 8 = 1: Check the parameterization (p0429.2).
 Bit 9 = 1: EMC / connect the cable shield, replace the encoder or encoder cable, replace the Sensor Module.
 Bit 10 = 1: Check the parameterization (p0429.2, p0449).
 Bit 11 = 1: Check the parameterization (p0436).
 Bit 12 = 1: Check the parameterization (p0429.6).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33111 (N, A) Encoder 3: Absolute encoder EnDat, internal fault/error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: The EnDat encoder fault word contains fault bits that have been set.
 Fault value (r0949, interpret binary):
 Bit 0: Lighting system failed.
 Bit 1: Signal amplitude too low.
 Bit 2: Position value incorrect.
 Bit 3: Encoder power supply overvoltage condition.
 Bit 4: Encoder power supply undervoltage condition.
 Bit 5: Encoder power supply overcurrent condition.
 Bit 6: The battery must be changed.

Remedy:

Re fault value, bit 0 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 1 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 2 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 3 = 1:
5 V power supply voltage fault.
When using an SMC: Check the plug-in cable between the encoder and SMC or replace the SMC.
When a motor encoder with a direct DRIVE-CLiQ connection is used: Replace the motor.

Re fault value, bit 4 = 1:
5 V power supply voltage fault.
When using an SMC: Check the plug-in cable between the encoder and SMC or replace the SMC.
When using a motor with DRIVE-CLiQ: Replace the motor.

Re fault value, bit 5 = 1:
Encoder is defective. Replace the encoder, where the motor encoder has a direct DRIVE-CLiQ socket: Replace the motor.

Re fault value, bit 6 = 1:
The battery must be changed - only for encoders with battery back-up.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33112 (N, A) Encoder 3: The error bit is set in the serial protocol

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: Serial communication protocol transfer error between the encoder and evaluation module SMCxx.
Fault value (r0949, decimal):

Remedy: Re fault value:

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33115 (N, A) Encoder 3: Amplitude error track A or B (A² + B²)

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: The amplitude (A² + B²) does not lie within the tolerance bandwidth (software monitoring function).
SMC20:
The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
On the other hand, the response threshold is < 230 mV (frequency characteristic).
SMC10:
The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is < 1070 mV.
Fault value (r0949, decimal):
Low word:
Signal level, track A (16 bits with sign).
High word:
Signal level, track B (16 bits with sign).
SMC20:
A signal level of 500 mV peak value corresponds to the numerical value 5333 hex = 21299 dec.
SMC10:
A signal level of 2900 mV peak value corresponds to the numerical value 6666 hex = 26214 dec.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check the encoder module (e.g. contacts).
- with measuring systems without their own bearing system: Adjust the scanning head and check the bearing system of the measuring wheel.
- for measuring systems with their own bearing system: Ensure that the encoder housing is not subject to any axial force.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33116 (N, A) Encoder 3: Amplitude error, monitoring track A + B

Reaction: A_INFEED: NONE
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The amplitude of the rectified encoder signals A and B is not within the tolerance bandwidth (hardware monitoring).
The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
On the other hand, the hardware response thresholds are at < 176 mV and > 1.35 V.
Fault value (r0949, decimal):
Low word: Signal level, track A (16 bits with sign).
High word: Signal level, track B (16 bits with sign).
A signal level of 500 mV corresponds to the numerical value 5333 hex = 21299 dec.
These analog values are not measured at the same time with the hardware fault output.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check the encoder module (e.g. contacts).

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33117 (N, A) Encoder 3: Inversion error, signals A and B and R

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3), VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: For a square-wave signal encoder (TTL, bipolar, double ended) the A* and B* and R* signals are not inverted with respect to signals A and B and R.

Remedy: Check the setting of p0405: p0405.2 = 1 is only possible if the encoder is connected at X520.
 Check the encoder/cable: Does the encoder supply TTL signals and the associated inverted signals?

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33118 (N, A) Encoder 3: Speed difference outside the tolerance range

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: For an HTL/TTL encoder, the speed difference has exceeded the value in p0492 over several sampling cycles.
 Fault value (r0949, decimal):
 Only for internal Siemens troubleshooting.

Remedy: - check the tachometer feeder cable for interruptions.
 - check the grounding of the tachometer shielding.
 - if required, increase the maximum speed difference per sampling cycle (p0492).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33120 (N, A) Encoder 3: Power supply voltage

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: Encoder power supply voltage fault.
 Note:
 If the encoder cables 6FX2002-2EQ00-.... and 6FX2002-2CH00-.... are interchanged, this can result in the encoder being destroyed because the pins of the operating voltage are reversed.
 Fault value (r0949, interpret binary):
 Bit 0: Undervoltage condition on the sense line (threshold 4.75 V).
 Bit 1: Encoder power supply voltage overcurrent condition (threshold 450 mA).

Remedy: For fault value, bit 0 = 1:
 - correct encoder cable connected?
 - check the plug connections of the encoder cable.
 - SMC30: Check the parameterization (p0404.22).
 For fault value, bit 1 = 1:
 - correct encoder cable connected?
 - replace the encoder or encoder cable.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33121 (N, A) Encoder 3: Coarse position error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: For the actual value sensing, an error was detected on the module. As a result of this error, it must be assumed that the actual value sensing supplies an incorrect coarse position.

Remedy: Replace the motor with DRIVE-CLiQ or the appropriate Sensor Module.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33125 (N, A) Encoder 1: Amplitude error track A or B overcontrolled

Reaction: A_INFEED: NONE
 SERVO: ENCODER (DCBRAKE, NONE)
 VECTOR: ENCODER (DCBRAKE, NONE)

Acknowledge: PULSE INHIBIT

Cause: The amplitude (track A or B) does not lie within the tolerance bandwidth (software monitoring function).
 SMC20:
 The nominal signal level of the encoder must lie in the range 375 mV to 600 mV (500 mV -25 % / +20 %).
 On the other hand, the response threshold is > 760 mV (frequency characteristic).
 SMC10:
 The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is > 3582 mV.
 Fault value (r0949, decimal):
 Low word:
 Signal level, track A (16 bits with sign).
 High word:
 Signal level, track B (16 bits with sign).
 SMC20:
 A signal level of 500 mV peak value corresponds to the numerical value 5333 hex = 21299 dec.
 SMC10:
 A signal level of 2900 mV peak value corresponds to the numerical value 6666 hex = 26214 dec.
 See also: p0491 (Motor encoder fault response ENCODER)

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- replace the encoder or encoder cable.
- with measuring systems without their own bearing system: Adjust the scanning head and check the bearing system of the measuring wheel.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33129 (N, A)	Encoder 3: Position difference, hall sensor/track C/D and A/B too large
Reaction:	A_INFEED: NONE SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3) VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
Acknowledge:	PULSE INHIBIT
Cause:	The error of track C/D is greater than +/-15 ° mechanical or +/-60 ° electrical. One period of track C/D corresponds to 360 ° mechanical. One period of the Hall signal corresponds to 360 ° electrical. The monitoring responds if, for example, Hall sensors are connected as equivalent for the C/D tracks with the incorrect rotational sense or supply values that are not accurate enough. After the fine synchronization using one reference mark or 2 reference marks for distance-coded encoders, this fault is no longer initiated, but instead, Alarm A33429. Fault value (r0949, decimal): Measured deviation as mechanical angle (16 bits with sign, 182 dec corresponds to 1 °).
Remedy:	- track C or D not connected. - correct the direction of rotation of the Hall sensor possibly connected as equivalent for track C/D. - check that the encoder cables are routed in compliance with EMC. - check the adjustment of the Hall sensor.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F33130 (N, A)	Encoder 3: Zero mark and position error from the coarse synchronization
Reaction:	A_INFEED: NONE SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2) VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	PULSE INHIBIT
Cause:	After initializing the pole position using track C/D, Hall signals or pole position identification routine, the zero mark was detected outside the permissible range. For distance-coded encoders, the test is carried-out after passing 2 zero marks. Fine synchronization was not carried-out. The deviation may be up to 18 ° mechanical or up to 60 ° electrical. Fault value (r0949, decimal): Normalization: 32768 = 180 ° High word: Mechanical zero mark position determined. If the initialization via a track C/D is selected in p0404, then it is checked whether the zero mark occurs in an angular range of +/-18 ° mechanical. Low word: Deviation of the zero mark from the expected position as electrical angle. If the correction of the commutation position with the zero mark is selected in p0404, then a difference of a maximum of +/- 60 ° electrical is permitted.
Remedy:	- check that the encoder cables are routed in compliance with EMC. - check the plug connections. - if the Hall sensor is used as an equivalent for track C/D, check the connection. - check the connection of track C or D. - replace the encoder or encoder cable.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
Reaction upon A:	NONE
Acknowledge upon A:	NONE

F33131 (N, A) Encoder 3: Deviation, position incremental/absolute too large

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: Absolute encoder: When cyclically reading the absolute position, an excessively high difference to the incremental position was detected. The absolute position that was read is rejected.
 Limit value for the deviation:
 - EnDat encoder: Is supplied from the encoder and is a minimum of 2 quadrants (e.g. EQI 1325 > 2 quadrants, EQN 1325 > 50 quadrants).
 - other encoders: 15 pulses = 60 quadrants.
 Fault value (r0949, decimal):
 Deviation in quadrants (1 pulse = 4 quadrants).
 Incremental encoder: When the zero pulse is passed, a deviation in the incremental position was detected.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- check whether the coding disk is dirty or there are strong ambient magnetic fields.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33150 (N, A) Encoder 3: Initialization error

Reaction: A_INFEED: NONE
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: PULSE INHIBIT

Cause: Encoder functionality selected in p0404 is not operating correctly.
 Fault value (r0949, interpret hexadecimal):
 The fault value is a bit field. Every set bit indicates functionality that is faulted.
 The bit assignment corresponds to that of p0404 (e.g. bit 5 set: Error track C/D).

Remedy:

- Check that p0404 is correctly set.
- check the encoder type used (incremental/absolute value) and for SMCxx, the encoder cable.
- if relevant, note additional fault/error messages that describe the fault in detail.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A33400 (F, N) Encoder 3: Alarm threshold, zero mark distance error

Reaction: NONE

Acknowledge: NONE

Cause: The measured zero mark distance does not correspond to the parameterized zero mark distance.
 For distance-coded encoders, the zero mark distance is determined from zero marks detected pairs. This means that if a zero mark is missing, depending on the pair generation, this cannot result in a fault and also has no effect in the system.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Alarm value (r2124, decimal):
 Last measured zero mark distance in increments (4 increments = 1 encoder pulse).
 The sign designates the direction of motion when detecting the zero mark distance.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the distance between zero marks (p0424, p0425).
- replace the encoder or encoder cable.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A33401 (F, N) Encoder 3: Alarm threshold, zero marked failed

Reaction: NONE

Acknowledge: NONE

Cause: The 1.5 x parameterized zero mark distance was exceeded.
 The zero mark distance for the zero mark monitoring is set in p0425 (rotary encoder) or p0424 (linear encoder).
 Alarm value (r2124, decimal):
 Number of increments after POWER ON or since the last zero mark that was detected (4 increments = 1 encoder pulse).

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- . check the encoder type (encoder with equidistant zero marks).
- adapt the parameter for the clearance between zero marks (p0425).
- replace the encoder or encoder cable.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

F33405 (N, A) Encoder 3: Encoder evaluation temperature too high

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The encoder evaluation for a motor with DRIVE-CLiQ has detected an excessively high temperature.
 The fault threshold is 125 ° C.
 Alarm value (r2124, decimal):
 Measured board/module temperature in 0.1 °C.

Remedy: Reduce the ambient temperature for the DRIVE-CLiQ connection of the motor.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

A33410 (F, N)	Encoder 3: Serial communications
Reaction:	NONE
Acknowledge:	NONE
Cause:	Serial communication protocol transfer error between the encoder and evaluation module. Alarm value (r2124, interpret binary): Bit 0: Alarm bit in the position protocol. Bit 1: Incorrect quiescent level on the data line. Bit 2: Encoder does not respond (does not supply a start bit within 50 ms). Bit 3: CRC error: The checksum in the protocol from the encoder does not match the data. Bit 4: Encoder acknowledgement error: The encoder incorrectly understood the task (request) or cannot execute it. Bit 5: Internal error in the serial driver: An illegal mode command was requested. Bit 6: Timeout with cyclically reading. Bit 8: Protocol is too long (e.g. > 64 bits). Bit 9: Receive buffer overflow. Bit 10: Frame error when reading twice. Bit 11: Parity error. Bit 12: Data line signal level error during the monoflop time.
Remedy:	- check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A33411 (F, N)	Encoder 3: EnDat encoder signals alarms
Reaction:	NONE
Acknowledge:	NONE
Cause:	The error word of the EnDat encoder has alarm bits that have been set. Alarm value (r2124, interpret binary): Bit 0: Frequency exceeded (speed too high). Bit 1: Temperature exceeded. Bit 2: Control reserve, lighting system exceeded. Bit 3: Battery discharged. Bit 4: Reference point passed.
Remedy:	Replace encoder.
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A33414 (F, N)	Encoder 3: Amplitude error track C or D (C² + D²)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The amplitude (C² + D²) of track C or D of the encoder or from the Hall signals, is not within the tolerance bandwidth.</p> <p>The nominal signal must be in the range 375 mV to 600 mV (500 mV -25 % / +20 %).</p> <p>On the other hand, the response thresholds are < 230 mV and > 750 mV (frequency characteristic).</p> <p>This fault also occurs if the A/D converter is overcontrolled.</p> <p>If the amplitude is not within the tolerance bandwidth, then it cannot be used to initialize the start position.</p> <p>Alarm value (r2124, decimal):</p> <p>Low word: Signal level, track C (16 bits with sign).</p> <p>High word: Signal level, track D (16 bits with sign).</p> <p>A signal level of 500 mV corresponds to the numerical value 5333 hex = 21299 dec.</p>
Remedy:	<ul style="list-style-type: none"> - check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder or encoder cable. - check the encoder module (e.g. contacts). - check the Hall sensor box
Reaction upon F:	<p>A_INFEED: NONE (OFF1, OFF2)</p> <p>SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)</p> <p>VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)</p>
Acknowledge upon F:	IMMEDIATELY
Reaction upon N:	NONE
Acknowledge upon N:	NONE

N33415 (F, A)	Encoder 3: Amplitude alarm track A or B (A² + B²)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The amplitude (A² + B²) of track A or B is not within the tolerance bandwidth.</p> <p>SMC20:</p> <p>The nominal signal level is at 500 mV (500 mV -25 % / +20 %). The response threshold is < 300 mV.</p> <p>SMC10:</p> <p>The nominal signal level is at 2900 mV (2.0 Vrms). The response threshold is < 1414 mV (1.0 Vrms).</p> <p>Alarm value (r2124, decimal):</p> <p>Low word: Amplitude square root(A*A + B*B).</p> <p>SMC20: A signal level of 500 mV peak value corresponds to the numerical value 299A hex = 10650 dec.</p> <p>SMC10:</p> <p>A signal level of 2900 mV peak value corresponds to the numerical value 3333 hex = 13107 dec.</p> <p>High word:</p> <p>Angle 0 to 65535 corresponds to 0 to 360 degrees of the fine position. Zero degrees is at the negative zero crossover of track B.</p>
Remedy:	<ul style="list-style-type: none"> - check the speed range, frequency characteristic (amplitude characteristic) of the measuring equipment is not sufficient for the speed range. - check that the encoder cables are routed in compliance with EMC. - check the plug connections. - replace the encoder or encoder cable. - check the encoder module (e.g. contacts). - dirty code disk - aged lighting system.
Reaction upon F:	<p>A_INFEED: NONE (OFF1, OFF2)</p> <p>SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)</p> <p>VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)</p>
Acknowledge upon F:	IMMEDIATELY
Reaction upon A:	NONE
Acknowledge upon A:	NONE

A33418 (F, N) Encoder 3: Speed difference per sampling rate exceeded

Reaction: NONE
Acknowledge: NONE
Cause: For an HTL/TTL encoder, the speed difference between two sampling cycles has exceeded the value in p0492.
 Alarm value (r2124, decimal):
 Only for internal Siemens troubleshooting.
Remedy: - check the tachometer feeder cable for interruptions.
 - check the grounding of the tachometer shielding.
 - if required, increase the setting of p0492.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A33419 (F, N) Encoder 3: Track A or B outside the tolerance range

Reaction: NONE
Acknowledge: NONE
Cause: The amplitude, phase or offset correction for track A or B is at the limit.
 Amplitude error correction: Amplitude B / Amplitude A = 0.78 ... 1.27
 Phase: <84 degrees or >96 degrees
 SMC20: Offset correction: +/-140 mV
 SMC10: Offset correction: +/-650 mV
 Alarm value (r2124, interpret hexadecimal):
 xxx1: Minimum of the offset correction, track B
 xxx2: Maximum of the offset correction, track B
 xx1x: Minimum of the offset correction, track A
 xx2x: Maximum of the offset correction, track A
 x1xx: Minimum of the amplitude correction, track B/A
 x2xx: Maximum of the amplitude correction, track B/A
 1xxx: Minimum of the phase error correction
 2xxx: Maximum of the phase error correction
Remedy: - check mechanical mounting tolerances for encoders without their own bearings (e.g. toothed-wheel encoders).
 - check the plug connections (also the transition resistance).
 - check the encoder signals.
 - replace the encoder or encoder cable.
 Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A33429 (F, N) Encoder 3: Position difference, hall sensor/track C/D and A/B too large

Reaction: NONE
Acknowledge: NONE
Cause: The error of track C/D is greater than +/-15 ° mechanical or +/-60 ° electrical.
 One period of track C/D corresponds to 360 ° mechanical.
 One period of the Hall signal corresponds to 360 ° electrical.
 The monitoring responds if, for example, Hall sensors are connected as equivalent for the C/D tracks with the incorrect rotational sense or supply values that are not accurate enough.
 Alarm value (r2124, decimal):
 Measured deviation as mechanical angle (16 bits with sign, 182 dec corresponds to 1 °).

Remedy:

- track C or D not connected.
- correct the direction of rotation of the Hall sensor possibly connected as equivalent for track C/D.
- check that the encoder cables are routed in compliance with EMC.
- check the adjustment of the Hall sensor.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

A33431 (F, N) Encoder 3: Deviation, position incremental/absolute too large

Reaction: NONE

Acknowledge: NONE

Cause: Absolute encoder: When cyclically reading the absolute position, an excessively high difference to the incremental position was detected.
 Alarm value (r2124, decimal):
 Deviation in quadrants (1 pulse = 4 quadrants).
 Incremental encoder: When the zero pulse is passed, a deviation in the incremental position was detected.

Remedy:

- check that the encoder cables are routed in compliance with EMC.
- check the plug connections.
- replace the encoder or encoder cable.
- coding disk dirty or strong magnetic fields.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE

Acknowledge upon N: NONE

F33501 (N, A) Encoder 3: Position tracking encoder position outside tolerance window

Reaction: A_INFEED: NONE
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: When powered-down, the drive/encoder was moved through a distance greater than what was set in the tolerance window.
 See also: p0413 (Measuring gearbox, position tracking tolerance window)

Remedy: Re-adjust the drive.

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

F33502 (N, A) Encoder 3: Encoder with measuring gear, without valid signals

Reaction: A_INFEED: OFF1 (OFF2)
 SERVO: OFF1 (OFF2, OFF3)
 VECTOR: OFF1 (OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The encoder with measuring gear no longer provides any valid signals.

Remedy: It must be ensured that all of the encoders, with mounted measuring gear, provide valid actual values in operation.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33801 (N, A) Encoder 3 DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.

Remedy: - check the electrical cabinet design and cable routing for EMC compliance.
 - replace the component involved.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33802 (N, A) Encoder 3: Time slice overflow

Reaction: A_INFEED: OFF2 (NONE)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Time slice overflow, encoder 3.
 Fault value (r0949, decimal):
 9: Time slice overflow of the fast (current controller clock cycle) time slice.
 10: Time slice overflow of the average time slice.
 12: Time slice overflow of the slow time slice.
 999: Timeout when waiting for SYNO, e.g. unexpected return to non-cyclic operation.

Remedy: Reduce the current controller frequency.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33804 (N, A) Encoder 3: CRC CODE RAM

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The checksum via the CODE-RAM of the Sensor Module has changed in operation.
Fault value (r0949, interpret hexadecimal):
Difference between the checksum at POWER ON and the actual checksum.

Remedy: Hardware defect: Replace the Sensor Module.
Firmware error: If required, upgrade the firmware.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33805 (N, A) Encoder 3: EPROM checksum error

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Internal parameter data is corrupted.
Fault value (r0949, interpret hexadecimal):
01: EEPROM access error.
02: Too many blocks in the EEPROM.

Remedy: Replace the module.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33806 (N, A) Encoder 3: Initialization error

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: PULSE INHIBIT

Cause: The encoder was not successfully initialized.
Fault value (r0949, interpret hexadecimal):
1, 2, 3: Encoder initialization with the motor rotating.

Remedy: Acknowledge the fault.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33812 (N, A) Encoder 3: A cycle requested from the CU or RX/TX timing is not supported

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: A cycle requested from the CU or RX/TX timing is not supported
 Fault value (r0949):
 0: Application cycle is not supported.
 1: DQ cycle is not supported.
 2: Clearance between RX and TX instants in time too low.
 3: TX instant in time too early.

Remedy:
 Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33820 (N, A) Encoder 3 DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 01: CRC error.
 02: Telegram is shorter than specified in the length byte or in the receive list.
 03: Telegram is longer than specified in the length byte or in the receive list.
 04: The length of the receive telegram does not match the receive list.
 05: The type of the receive telegram does not match the receive list.
 06: The address of the encoder in the telegram and in the receive list do not match.
 07: The encoder expects a SYNC telegram, but the receive telegram is not a SYNC telegram.
 08: The encoder does not expect a SYNC telegram, but the receive telegram is a SYNC telegram.
 09: The error bit in the receive telegram is set.
 10: The receive telegram is too early.

Remedy:
 - carry-out a POWER ON.
 - check the electrical cabinet design and cable routing for EMC compliance.
 - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33835 (N, A) Encoder 3 DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
Acknowledge: IMMEDIATELY
Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. The nodes do not send and receive in synchronism.
 Fault value (r0949, interpret hexadecimal):
 21: The cyclic telegram has not been received.
 22: Timeout in the telegram receive list.
 40: Timeout in the telegram send list.

Remedy:
 - carry-out a POWER ON.
 - replace the component involved.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33836 (N, A) Encoder 3 DRIVE-CLiQ: Send error for DRIVE-CLiQ data

Reaction: A_INFEED: OFF2
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Data were not able to be sent.
Fault value (r0949, interpret hexadecimal):
41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33837 (N, A) Encoder 3 DRIVE-CLiQ: Component fault

Reaction: A_INFEED: OFF2
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
Fault value (r0949, interpret hexadecimal):
20: Error in the telegram header.
23: Receive error: The telegram buffer memory contains an error.
42: Send error: The telegram buffer memory contains an error.
43: Send error: The telegram buffer memory contains an error.

Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33845 (N, A) Encoder 3 DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
Fault value (r0949, interpret hexadecimal):
0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33850 (N, A) Encoder 3: Sensor Module, internal software error

Reaction: A_INFEED: OFF2 (NONE)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: POWER ON

Cause: Internal software error in the Sensor Module of encoder 3.
Fault value (r0949, decimal):
1: Background time slice is blocked.
2: Checksum over the code memory is not OK.
10000: OEM memory of the EnDat encoder contains data that cannot be interpreted.

Remedy: - replace the Sensor Module.
- if required, upgrade the firmware in the Sensor Module.
- contact the Hotline.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33851 (N, A) CU DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: NONE (OFF1, OFF2)
SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Sensor Module (encoder 3) involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit.
Fault value (r0949, interpret hexadecimal):
0A: The sign-of-life bit in the receive telegram is not set.

Remedy: Upgrade the firmware of the component involved.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

F33860 (N, A) CU DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 11: CRC error and the receive telegram is too early.
 01: CRC error.
 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early.
 02: Telegram is shorter than specified in the length byte or in the receive list.
 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early.
 03: Telegram is longer than specified in the length byte or in the receive list.
 14: The length of the receive telegram does not match the receive list and the receive telegram is too early.
 04: The length of the receive telegram does not match the receive list.
 15: The type of the receive telegram does not match the receive list and the receive telegram is too early.
 05: The type of the receive telegram does not match the receive list.
 16: The address of the encoder in the telegram and in the receive list does not match and the receive telegram is too early.
 06: The address of the encoder in the telegram and in the receive list do not match.
 19: The error bit in the receive telegram is set and the receive telegram is too early.
 09: The error bit in the receive telegram is set.
 10: The receive telegram is too early.

Remedy: - carry-out a POWER ON.
 - check the electrical cabinet design and cable routing for EMC compliance.
 - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33885 (N, A) CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. The nodes do not send and receive in synchronism.
 Fault value (r0949, interpret hexadecimal):
 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early.
 21: The cyclic telegram has not been received.
 22: Timeout in the telegram receive list.
 40: Timeout in the telegram send list.
 62: Error at the transition to cyclic operation.

Remedy: - check the power supply voltage of the component involved.
 - carry-out a POWER ON.
 - replace the component involved.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33886 (N, A) CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33887 (N, A) CU DRIVE-CLiQ: Component fault

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
 60: Response received too late during runtime measurement.
 61: Time taken to exchange characteristic data too long.

Remedy: - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 - check the electrical cabinet design and cable routing for EMC compliance.
 - if required, use another DRIVE-CLiQ socket (p9904).
 - replace the component involved.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33895 (N, A) CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: DRIVE-CLiQ communications error between the Control Unit and the encoder involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33896 (N, A) CU DRIVE-CLiQ: Inconsistent component characteristics

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
 VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced.
 Fault value (r0949, decimal):
 Component ID.

Remedy: - when replacing cables, only use cables with the same length as the original cables.
 - when replacing components, use the same components and firmware releases.
 - carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33897 (N, A) DRIVE-CLiQ: No communication to component

Reaction: A_INFEED: NONE (OFF1, OFF2)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: Communications with the DRIVE-CLiQ component specified by the fault value is not possible.
 One cause can be, e.g. that a DRIVE-CLiQ cable has been withdrawn.
 Fault value (r0949, decimal):
 Component ID.

Remedy: - check the DRIVE-CLiQ connections.
 - carry-out a POWER ON.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33899 (N, A) Encoder 3: Unknown fault

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: A fault occurred on the Sensor Module for encoder 3 that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the Sensor Module for encoder 3 is more recent than the firmware on the Control Unit.
 Fault value (r0949, decimal):
 Fault number.
 If required, the significance of this new fault can be read about in a more recent description of the Control Unit.

Remedy: - replace the firmware on the Sensor Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F33905 (N, A) Encoder 3: Parameterization error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)
 VECTOR: OFF1 (DCBRAKE, NONE, OFF2, OFF3, STOP1, STOP2)

Acknowledge: IMMEDIATELY

Cause: A parameter of encoder 3 was detected as being incorrect.
 It is possible that the parameterized encoder type does not match the connected encoder.
 The parameter involved can be determined as follows:
 - determine the parameter number using the fault value (r0949).
 - determine the parameter index (p0189).
 Fault value (r0949, decimal):
 Parameter number.

Remedy: - check whether the connected encoder type matches the encoder that has been parameterized.
 - correct the parameter specified by the fault value (r0949) and p0189.

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A33920 (F, N) Encoder 3: Temperature sensor fault

Reaction: NONE

Acknowledge: NONE

Cause: When evaluating the temperature sensor, an error occurred.
 Alarm value (r2124, decimal):
 1: Wire breakage or sensor not connected (KTY: R > 1630 Ohm).
 2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).

Remedy: - check that the encoder cable is the correct type and is correctly connected.
 - check the temperature sensor selection in p0600 to p0603.
 - replace the Sensor Module (hardware defect or incorrect calibration data).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY

Reaction upon N: NONE
 Acknowledge upon N: NONE

A33999 (F, N) Encoder 3: Unknown alarm

Reaction: NONE

Acknowledge: NONE

Cause: A alarm has occurred on the Sensor Module for encoder 3 that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the Sensor Module for encoder 3 is more recent than the firmware on the Control Unit.
 Alarm value (r2124, decimal):
 Alarm number.
 If required, the significance of this new alarm can be read about in a more recent description of the Control Unit.

Remedy: - replace the firmware on the Sensor Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
 VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE
Acknowledge upon N: NONE

F34207 (N, A) VSM: Temperature fault threshold exceeded

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE
VECTOR: NONE

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The temperature (r3666) measured using the Voltage Sensing Module (VSM) has exceeded the threshold value (p3668).
This fault can only be initiated if the temperature evaluation was activated (p3665 = 2 for a KTY sensor or p3665 = 1 for a PTC sensor).
Fault value (r0949, decimal):
The hundred thousands and ten thousands position specifies the component number of the VSM where the fault occurred.

Remedy:
- check the fan.
- reduce the power.

Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

A34211 (F, N) VSM: Temperature alarm threshold exceeded

Reaction: NONE

Acknowledge: NONE

Cause: The temperature (r3666) measured using the Voltage Sensing Module (VSM) has exceeded the threshold value (p3667).
Alarm value (r2124, decimal):
The hundred thousands and ten thousands position specifies the component number of the VSM where the fault occurred.

Remedy:
- check the fan.
- reduce the power.

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE
VECTOR: NONE
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon N: NONE
Acknowledge upon N: NONE

F34801 VSM DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE (OFF1, OFF2, OFF3)
VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module (VSM).
Fault value (r0949, interpret hexadecimal):
0A: The sign-of-life bit in the receive telegram is not set.

Remedy:
- check the DRIVE-CLiQ connection.
- replace the Terminal Module.

F34802 VSM: Time slice overflow

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Time slice overflow on the Voltage Sensing Module.

Remedy: Replace the Voltage Sensing Module.

F34803 VSM: Memory test

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: An error has occurred during the memory test on the Voltage Sensing Module.

Remedy: - check whether the permissible ambient temperature for the Voltage Sensing Module is being maintained.
 - replace the Voltage Sensing Module.

F34804 VSM: CRC

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: A checksum error has occurred when reading-out the program memory on the Voltage Sensing Module (VSM).

Remedy: - check whether the permissible ambient temperature for the component is maintained.
 - replace the Voltage Sensing Module.

F34805 VSM: EPROM checksum error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: Internal parameter data is corrupted.
 Fault value (r0949, interpret hexadecimal):
 01: EEPROM access error.
 02: Too many blocks in the EEPROM.

Remedy: - check whether the permissible ambient temperature for the component is maintained.
 - replace the Voltage Sensing Module (VSM).

F34806 VSM: Initialization

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: For the Voltage Sensing Module (VSM), a fault has occurred while initializing.

Remedy: Replace the Voltage Sensing Module.

A34807 (F, N) VSM: Sequence control, time monitoring

Reaction: NONE

Acknowledge: NONE

Cause: Error, timeout in the sequence control on the Voltage Sensing Module (VSM).

Remedy: Replace the Voltage Sensing Module.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE
Acknowledge upon N: NONE

F34820 VSM DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE (OFF1, OFF2)
VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module.
Fault value (r0949, interpret hexadecimal):
01: CRC error.
02: Telegram is shorter than specified in the length byte or in the receive list.
03: Telegram is longer than specified in the length byte or in the receive list.
04: The length of the receive telegram does not match the receive list.
05: The type of the receive telegram does not match the receive list.
06: The address of the encoder in the telegram and in the receive list do not match.
07: The encoder expects a SYNC telegram, but the receive telegram is not a SYNC telegram.
08: The encoder does not expect a SYNC telegram, but the receive telegram is a SYNC telegram.
09: The error bit in the receive telegram is set.
10: The receive telegram is too early.

Remedy: - carry-out a POWER ON.
- check the electrical cabinet design and cable routing for EMC compliance.
- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F34835 VSM DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE (OFF1, OFF2)
VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module. The nodes do not send and receive in synchronism.
Fault value (r0949, interpret hexadecimal):
21: The cyclic telegram has not been received.
22: Timeout in the telegram receive list.
40: Timeout in the telegram send list.

Remedy: - carry-out a POWER ON.
- replace the component involved.

F34836 VSM DRIVE-CLiQ: Send error for DRIVE-CLiQ data

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE (OFF1, OFF2)
VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module. Data were not able to be sent.
Fault value (r0949, interpret hexadecimal):
41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

F34837 VSM DRIVE-CLiQ: Component fault

Reaction: A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE (OFF1, OFF2)
VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.

Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

F34845 VSM DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module (VSM).
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.

Remedy: Carry-out a POWER ON.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F34850 VSM: Internal software error

Reaction: A_INFEED: OFF1 (NONE, OFF2)
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: POWER ON

Cause: An internal software error in the Voltage Sensing Module (VSM) has occurred.
 Fault value (r0949, decimal):
 1: Background time slice is blocked.
 2: Checksum over the code memory is not OK.

Remedy:

- replace the Voltage Sensing Module (VSM).
- if required, upgrade the firmware in the Voltage Sensing Module.
- contact the Hotline.

F34851 CU DRIVE-CLiQ: Sign-of-life missing

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module (VSM). The DRIVE-CLiQ component did not set the sign of life to the Control Unit.
 Fault value (r0949, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.

Remedy: Upgrade the firmware of the component involved.

F34860 CU DRIVE-CLiQ: Telegram error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module.
 Fault value (r0949, interpret hexadecimal):
 11: CRC error and the receive telegram is too early.
 01: CRC error.
 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early.

- 02: Telegram is shorter than specified in the length byte or in the receive list.
- 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early.
- 03: Telegram is longer than specified in the length byte or in the receive list.
- 14: The length of the receive telegram does not match the receive list and the receive telegram is too early.
- 04: The length of the receive telegram does not match the receive list.
- 15: The type of the receive telegram does not match the receive list and the receive telegram is too early.
- 05: The type of the receive telegram does not match the receive list.
- 16: The address of the Voltage Sensing Module in the telegram and in the receive list does not match and the receive telegram is too early.
- 06: The address of the Voltage Sensing Module in the telegram and in the receive list do not match.
- 19: The error bit in the receive telegram is set and the receive telegram is too early.
- 09: The error bit in the receive telegram is set.
- 10: The receive telegram is too early.

Remedy:

- carry-out a POWER ON.
- check the electrical cabinet design and cable routing for EMC compliance.
- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).

See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F34885 CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module. The nodes do not send and receive in synchronism.
 Fault value (r0949, interpret hexadecimal):
 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early.
 21: The cyclic telegram has not been received.
 22: Timeout in the telegram receive list.
 40: Timeout in the telegram send list.
 62: Error at the transition to cyclic operation.

Remedy:

- check the power supply voltage of the component involved.
- carry-out a POWER ON.
- replace the component involved.

See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F34886 CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the VSM involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.

Remedy: Carry-out a POWER ON.

F34887 CU DRIVE-CLiQ: Component fault

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: NONE (OFF1, OFF2)
 VECTOR: NONE (OFF1, OFF2)

Acknowledge: IMMEDIATELY

Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
 60: Response received too late during runtime measurement.
 61: Time taken to exchange characteristic data too long.

- Remedy:**
- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
 - check the electrical cabinet design and cable routing for EMC compliance.
 - if required, use another DRIVE-CLiQ socket (p9904).
 - replace the component involved.

F34895 CU DRIVE-CLiQ: Cyclic data transfer error

- Reaction:** A_INFEED: OFF2 (NONE, OFF1)
SERVO: NONE (OFF1, OFF2), VECTOR: NONE (OFF1, OFF2)
- Acknowledge:** IMMEDIATELY
- Cause:** A DRIVE-CLiQ communications error has occurred between the Control Unit and the Voltage Sensing Module.
Fault value (r0949, interpret hexadecimal):
0B: Synchronization error during alternating cyclic data transfer.
- Remedy:** Carry-out a POWER ON.
See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F34896 CU DRIVE-CLiQ: Inconsistent component characteristics

- Reaction:** A_INFEED: OFF2 (NONE, OFF1)
SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
- Acknowledge:** IMMEDIATELY
- Cause:** The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced.
Fault value (r0949, decimal):
Component ID.
- Remedy:**
- when replacing cables, only use cables with the same length as the original cables.
 - when replacing components, use the same components and firmware releases.
 - carry-out a POWER ON.

F34897 DRIVE-CLiQ: No communication to component

- Reaction:** A_INFEED: OFF2 (NONE, OFF1)
SERVO: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
VECTOR: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
- Acknowledge:** IMMEDIATELY (POWER ON)
- Cause:** Communications with the DRIVE-CLiQ component specified by the fault value is not possible.
One cause can be, e.g. that a DRIVE-CLiQ cable has been withdrawn.
Fault value (r0949, decimal):
Component ID.
- Remedy:**
- check the DRIVE-CLiQ connections.
 - carry-out a POWER ON.

F34899 (N, A) VSM: Unknown fault

- Reaction:** A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE (OFF1, OFF2, OFF3)
VECTOR: NONE (OFF1, OFF2, OFF3)
- Acknowledge:** IMMEDIATELY (POWER ON)
- Cause:** A fault occurred on the Voltage Sensing Module that cannot be interpreted by the Control Unit firmware. This can occur if the firmware on the Voltage Sensing Module is more recent than the firmware on the Control Unit.
Fault value (r0949, decimal):
Fault number.
If required, the significance of this new fault can be read about in a more recent description of the Control Unit.
- Remedy:**
- replace the firmware on the Voltage Sensing Module by an older firmware version (r0xyz).
 - upgrade the firmware on the Control Unit (r0018).
- Reaction upon N: NONE
Acknowledge upon N: NONE
Reaction upon A: NONE
Acknowledge upon A: NONE

A34903 (F, N) VSM: Error I2C bus

Reaction: NONE
Acknowledge: NONE
Cause: An error has occurred in while accessing via the internal TM I2C bus.
Remedy: Replace the Terminal Module.
Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE
VECTOR: NONE
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon N: NONE
Acknowledge upon N: NONE

A34904 (F, N) VSM: EEPROM

Reaction: NONE
Acknowledge: NONE
Cause: An error has occurred accessing the non-volatile memory on the Terminal Module.
Remedy: Replace the Terminal Module.
Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE
VECTOR: NONE
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon N: NONE
Acknowledge upon N: NONE

A34905 (F, N) VSM: Parameter access

Reaction: NONE
Acknowledge: NONE
Cause: The Control Unit attempted to write an illegal parameter value into the Voltage Sensing Module (VSM).
Remedy: - check whether the firmware version of the VSM (r0158) matches the firmware version of Control Unit (r0018).
- if required, replace the Voltage Sensing Module.
Note:
The firmware versions that match each other are in the readme.txt file on the CompactFlash card.
Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
SERVO: NONE
VECTOR: NONE
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon N: NONE
Acknowledge upon N: NONE

A34920 (F, N) VSM: Temperature sensor fault

Reaction: NONE
Acknowledge: NONE
Cause: When evaluating the temperature sensor, an error occurred.
Alarm value (r2124, decimal):
1: Wire breakage or sensor not connected (KTY: R > 1630 Ohm).
2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).
Remedy: - check that the sensor is connected correctly.
- replace sensor.

List of faults and alarms

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE
 VECTOR: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

A34999 (F, N) VSM: Unknown alarm

Reaction: NONE

Acknowledge: NONE

Cause: A fault occurred on the Voltage Sensing Module (VSM) an alarm has occurred that cannot be interpreted by the Control Unit firmware.
 This can occur if the firmware on the module is more recent than the firmware on the Control Unit.
 Alarm value (r2124, decimal):
 Alarm number.
 If required, the significance of this new alarm can be read about in a more recent description of the Control Unit.

Remedy:
 - replace the firmware on the Voltage Sensing Module by an older firmware version (r0148).
 - upgrade the firmware on the Control Unit (r0018).

Reaction upon F: A_INFEED: NONE (OFF1, OFF2)
 SERVO: NONE (OFF1, OFF2, OFF3)
 VECTOR: NONE (OFF1, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

A35200 (F, N) TM: Calibration data

Reaction: NONE

Acknowledge: NONE

Cause: An error was detected in the calibration data of the Terminal Module.
 Alarm value (r2124, decimal):
 The hundred thousands and ten thousands location specifies the component Id of the Terminal Module where the fault occurred.
 The thousands location specifies whether the analog input 0 (=0) or analog output 1 (= 1) is involved.
 The hundreds location specifies the fault type:
 0: No calibration data available.
 1: Offset too high (> 100 mV).
 The tens and ones location specifies the number of the input involved.

Remedy: Power-down the unit and power-up again.
 If the fault is still present, replace the module/board.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

F35207 (N, A) TM: Temperature fault threshold exceeded

Reaction: A_INFEED: OFF2 (NONE, OFF1)
 SERVO: OFF2 (NONE, OFF1, OFF3)
 VECTOR: OFF2 (NONE, OFF1, OFF3)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The temperature measured using the temperature sensing of the Terminal Module (TM) (r4105) has exceeded the threshold value to initiate this fault (p4102[1]).
 Please note that this fault can only be initiated if the temperature evaluation was activated (p4100 = 2 for KTY sensor or p4100 = 1 for PTC sensor).
 Fault value (r0949, decimal):
 The hundred thousands and ten thousands location specifies the component number of the TMxx where the fault occurred.
 Alarm:
 Please note that Fault F35207 only causes the drive to be shut down if there is at least one BICO interconnection between the drive and TM31.

Remedy: - allow the temperature sensor to cool down.
 - if required, set the fault response to NONE (p2100, p2101).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

A35211 (F, N) TM: Temperature alarm threshold exceeded

Reaction: NONE

Acknowledge: NONE

Cause: The temperature measured using the temperature sensing of the Terminal Module (TM) (r4105) has exceeded the threshold value to initiate this alarm (p4102[0]).
 Alarm value (r2124, decimal):
 The hundred thousands and ten thousands location specifies the component number of the TMxx where the fault occurred.

Remedy: Allow the temperature sensor to cool down.

Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

F35220 (N, A) TM: Frequency limit reached for signal output

Reaction: A_INFEED: OFF1 (NONE, OFF2)
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The signals output from the Terminal Module 41 (TM41) for tracks A/B have reached the limit frequency. The output signals are no longer in synchronism with the specified setpoint.

Remedy: - enter a lower speed setpoint (p1155).
 - reduce the encoder pulse number (p0408).

Reaction upon N: NONE
 Acknowledge upon N: NONE
 Reaction upon A: NONE
 Acknowledge upon A: NONE

F35221 (N, A) TM: Setpoint - actual value deviation, outside the tolerance range

Reaction: A_INFEED: OFF1 (NONE, OFF2)
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The deviation between the setpoint and the output signals (track A/B) exceeds the tolerance of +/-3 %.

Remedy: - reduce the basic clock cycle (p0110, p0111).
 - replace the module.

Reaction upon N: NONE
 Acknowledge upon N: NONE

Reaction upon A: NONE
 Acknowledge upon A: NONE

A35222 (F, N) TM: Encoder pulse number not permissible

Reaction: NONE

Acknowledge: NONE

Cause: The encoder pulse number entered does not match the permissible pulse number from a hardware perspective.
 Fault value (r0949, decimal):
 1: Encoder pulse number is too high.
 2: Encoder pulse number is too low.
 4: Encoder pulse number is less than the zero mark offset (p4426)

Remedy: Enter the encoder pulse number in the permissible range (p0408).

Reaction upon F: A_INFEED: OFF1 (NONE, OFF2)
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE
 Acknowledge upon N: NONE

A35223 (F, N) TM: ZM offset not permissible

Reaction: NONE

Acknowledge: NONE

Cause: The entered zero mark offset is not permissible.
 Fault value (r0949, decimal):
 1: Zero mark offset is too high.
 See also: p4426 (Incremental encoder emulation, pulses for zero mark)

Remedy: Enter the zero mark offset in the permissible range (p4426).

Reaction upon F: A_INFEED: OFF1 (NONE, OFF2)
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE
 Acknowledge upon N: NONE

A35224 (N)	TM: Zero mark synchronization interrupted
Reaction:	NONE
Acknowledge:	NONE
Cause:	The zero mark synchronization with the encoder to be emulated was interrupted. Alarm value (r2124, decimal): 0: The encoder is not in the ready state (e.g. encoder parked) 1: An absolute encoder was connected. 2: The encoder r0479[0...2] interconnected with CI: p4420 is already communicating with another TM41 (precisely one TM41 can be interconnected with a specific r0479[0...2]). 3: The BICO interconnection to TM41 was removed (CI: p4420 = 0 signal). 4: The encoder connected with CI: p4420 has carried-out an EDS changeover (this operation is not supported, set p4420 to 0 and interconnect again). 5: The maximum number of revolutions of the encoder was exceeded. 6: Encoder in an invalid state. 7: Encoder in an invalid state.
Remedy:	None necessary. - if the encoder changes into the ready state, then a synchronization operation that was previously interrupted is carried-out again. - if the synchronization was interrupted due to the maximum permissible synchronization duration, then a new synchronization is not carried-out. - for an absolute encoder, no synchronization is carried-out, the zero mark is always output at the zero revolution of the TM41.
Reaction upon N:	NONE
Acknowledge upon N:	NONE
A35225	TM: Zero mark synchronization held - encoder not in the ready state
Reaction:	NONE
Acknowledge:	NONE
Cause:	The zero mark synchronization with the encoder to be emulated was held. The encoder is not in the "ready" state.
Remedy:	Bring the encoder into the "ready" state.
A35226	TM: Tracks A/B are de-activated
Reaction:	NONE
Acknowledge:	NONE
Cause:	The output of tracks A/B of the TM41 has been held (frozen). - there was no interconnection established from CI: p4420. - the encoder is not in the "ready" state. - TM41 has a fault condition.
Remedy:	- establish an interconnection from CI: p4420. - bring the encoder into the "ready" state. - remove any TM41 faults.
A35227	TM: Zero mark synchronization interrupted - EDS changeover not supported
Reaction:	NONE
Acknowledge:	NONE
Cause:	The interconnected encoder has carried-out an EDS changeover. TM41 does not support this particular application case.
Remedy:	The BICO interconnection must be re-established (CI: p4420).

A35801 (F, N) TM DRIVE-CLiQ: Sign-of-life missing

Reaction: NONE

Acknowledge: NONE

Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved.
Alarm value (r2124, interpret hexadecimal):
0A: The sign-of-life bit in the receive telegram is not set.

Remedy: - check the DRIVE-CLiQ connection.
- replace the component involved.
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY

upon F:

Reaction upon N: NONE

Acknowledge upon N: NONE

upon N:

A35802 (F, N) TM: Time slice overflow

Reaction: NONE

Acknowledge: NONE

Cause: Time slice overflow on Terminal Module.

Remedy: Replace the Terminal Module.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

upon F:

Reaction upon N: NONE

Acknowledge upon N: NONE

upon N:

A35803 (F, N) TM: Memory test

Reaction: NONE

Acknowledge: NONE

Cause: An error has occurred during the memory test on the Terminal Module.

Remedy: - check whether the permissible ambient temperature for the Terminal Module is being maintained.
- replace the Terminal Module.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

upon F:

Reaction upon N: NONE

Acknowledge upon N: NONE

upon N:

A35804 (F, N) TM: CRC

Reaction: NONE

Acknowledge: NONE

Cause: A checksum error has occurred when reading-out the program memory on the Terminal Module.
Fault value (r0949, interpret hexadecimal):
Difference between the checksum at POWER ON and the actual checksum.

Remedy: - check whether the permissible ambient temperature for the component is maintained.
- replace the Terminal Module.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

upon F:

Reaction upon N: NONE

Acknowledge upon N: NONE

upon N:

A35805 (F, N) TM: EPROM checksum error

Reaction: NONE
Acknowledge: NONE
Cause: Internal parameter data is corrupted.
Alarm value (r2124, interpret hexadecimal):
01: EEPROM access error.
02: Too many blocks in the EEPROM.
Remedy: - check whether the permissible ambient temperature for the component is maintained.
- replace the Terminal Module 31 (TM31).
Reaction upon F: NONE
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon N: NONE
Acknowledge upon N: NONE

A35807 (F, N) TM: Sequence control, time monitoring

Reaction: NONE
Acknowledge: NONE
Cause: Error, timeout, sequence control on the Terminal Module.
Remedy: Replace the Terminal Module.
Reaction upon F: NONE
Acknowledge upon F: IMMEDIATELY (POWER ON)
Reaction upon N: NONE
Acknowledge upon N: NONE

F35820 TM DRIVE-CLiQ: Telegram error

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved.
Fault value (r0949, interpret hexadecimal):
01: CRC error.
02: Telegram is shorter than specified in the length byte or in the receive list.
03: Telegram is longer than specified in the length byte or in the receive list.
04: The length of the receive telegram does not match the receive list.
05: The type of the receive telegram does not match the receive list.
06: The address of the Terminal Module in the telegram and in the receive list do not match.
07: Terminal Module expects a SYNC telegram, but the receive telegram is not a SYNC telegram.
08: Terminal Module does not expect a SYNC telegram, but the receive telegram is a SYNC telegram.
09: The error bit in the receive telegram is set.
10: The receive telegram is too early.
Remedy: - carry-out a POWER ON.
- check the electrical cabinet design and cable routing for EMC compliance.
- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F35835 TM DRIVE-CLiQ: Cyclic data transfer error

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved. The nodes do not send and receive in synchronism.
Fault value (r0949, interpret hexadecimal):
21: The cyclic telegram has not been received.
22: Timeout in the telegram receive list.
40: Timeout in the telegram send list.

Remedy:

- carry-out a POWER ON.
- replace the component involved.

See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F35836 TM DRIVE-CLiQ: Send error for DRIVE-CLiQ data

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.
Remedy: Carry-out a POWER ON.

F35837 PTM DRIVE-CLiQ: Component fault

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

F35845 TM DRIVE-CLiQ: Cyclic data transfer error

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module (TM) involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.
Remedy: Carry-out a POWER ON.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F35850 TM: Internal software error

Reaction: A_INFEED: OFF1 (NONE, OFF2)
 SERVO: OFF1 (NONE, OFF2, OFF3)
 VECTOR: OFF1 (NONE, OFF2, OFF3)
Acknowledge: POWER ON
Cause: An internal software error in the Terminal Module (TM) has occurred.
 Fault value (r0949, decimal):
 1: Background time slice is blocked.
 2: Checksum over the code memory is not OK.
Remedy:

- replace the Terminal Module (TM).
- if required, upgrade the firmware in the Terminal Module.
- contact the Hotline.

F35851 CU DRIVE-CLiQ: Sign-of-life missing

Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module (TM) involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit.
 Fault value (r0949, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.
Remedy: Upgrade the firmware of the component involved.

F35860	CU DRIVE-CLiQ: Telegram error
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY
Cause:	<p>A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>11: CRC error and the receive telegram is too early.</p> <p>01: CRC error.</p> <p>12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early.</p> <p>02: Telegram is shorter than specified in the length byte or in the receive list.</p> <p>13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early.</p> <p>03: Telegram is longer than specified in the length byte or in the receive list.</p> <p>14: The length of the receive telegram does not match the receive list and the receive telegram is too early.</p> <p>04: The length of the receive telegram does not match the receive list.</p> <p>15: The type of the receive telegram does not match the receive list and the receive telegram is too early.</p> <p>05: The type of the receive telegram does not match the receive list.</p> <p>16: The address of the Terminal Module in the telegram and in the receive list does not match and the receive telegram is too early.</p> <p>06: The address of the Terminal Module in the telegram and in the receive list do not match.</p> <p>19: The error bit in the receive telegram is set and the receive telegram is too early.</p> <p>09: The error bit in the receive telegram is set.</p> <p>10: The receive telegram is too early.</p>
Remedy:	<p>- carry-out a POWER ON.</p> <p>- check the electrical cabinet design and cable routing for EMC compliance.</p> <p>- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).</p> <p>See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)</p>

F35885	CU DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY
Cause:	<p>A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved. The nodes do not send and receive in synchronism.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early.</p> <p>21: The cyclic telegram has not been received.</p> <p>22: Timeout in the telegram receive list.</p> <p>40: Timeout in the telegram send list.</p> <p>62: Error at the transition to cyclic operation.</p>
Remedy:	<p>- check the power supply voltage of the component involved.</p> <p>- carry-out a POWER ON.</p> <p>- replace the component involved.</p> <p>See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)</p>

F35886	CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY
Cause:	<p>A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved.</p> <p>Data were not able to be sent.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>41: Telegram type does not match send list.</p>
Remedy:	Carry-out a POWER ON.

F35887	CU DRIVE-CLiQ: Component fault
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY
Cause:	Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded. Fault value (r0949, interpret hexadecimal): 20: Error in the telegram header. 23: Receive error: The telegram buffer memory contains an error. 42: Send error: The telegram buffer memory contains an error. 43: Send error: The telegram buffer memory contains an error. 60: Response received too late during runtime measurement. 61: Time taken to exchange characteristic data too long.
Remedy:	- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). - check the electrical cabinet design and cable routing for EMC compliance. - if required, use another DRIVE-CLiQ socket (p9904). - replace the component involved.
F35895	CU DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF1 (OFF2)
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the Terminal Module involved. Fault value (r0949, interpret hexadecimal): 0B: Synchronization error during alternating cyclic data transfer.
Remedy:	Carry-out a POWER ON. See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)
F35896	CU DRIVE-CLiQ: Inconsistent component characteristics
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2) VECTOR: OFF2 (DCBRAKE, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced. Fault value (r0949, decimal): Component ID.
Remedy:	- when replacing cables, only use cables with the same length as the original cables. - when replacing components, use the same components and firmware releases. - carry-out a POWER ON.
F35897	DRIVE-CLiQ: No communication to component
Reaction:	A_INFEED: OFF2 (NONE, OFF1) SERVO: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2) VECTOR: OFF2 (DCBRAKE, ENCODER, NONE, OFF1, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	Communications with the DRIVE-CLiQ component specified by the fault value is not possible. One cause can be, e.g. that a DRIVE-CLiQ cable has been withdrawn. Fault value (r0949, decimal): Component ID.
Remedy:	- check the DRIVE-CLiQ connections. - carry-out a POWER ON.
F35899 (N, A)	TM: Unknown fault
Reaction:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)

Cause: A fault has occurred on the Terminal Module that cannot be interpreted by the Control Unit firmware. This can occur if the firmware on the Terminal Module is more recent than the firmware on the Control Unit. Fault value (r0949, decimal): Fault number. If required, the significance of this new fault can be read about in a more recent description of the Control Unit.

Remedy: - replace the firmware on the Terminal Module by an older firmware version (r0158).
- upgrade the firmware on the Control Unit (r0018).

Reaction upon N: NONE

Acknowledge upon N: NONE

Reaction upon A: NONE

Acknowledge upon A: NONE

A35903 (F, N) TM: Error I2C bus

Reaction: NONE

Acknowledge: NONE

Cause: An error has occurred while accessing the internal I2C bus of the Terminal Module.

Remedy: Replace the Terminal Module.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

A35904 (F, N) TM: EEPROM

Reaction: NONE

Acknowledge: NONE

Cause: An error has occurred accessing the non-volatile memory on the Terminal Module.

Remedy: Replace the Terminal Module.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

A35905 (F, N) TM: Parameter access

Reaction: NONE

Acknowledge: NONE

Cause: The Control Unit attempted to write an illegal parameter value into the Terminal Module.

Remedy: - check whether the firmware version of the TM (r0158) matches the firmware version of Control Unit (r0018).
- if required, replace the Terminal Module.

Note:

The firmware versions that match each other are in the readme.txt file on the CompactFlash card.

Reaction upon F: NONE

Acknowledge upon F: IMMEDIATELY (POWER ON)

Reaction upon N: NONE

Acknowledge upon N: NONE

A35906 (F, N) TM: 24 V power supply missing

Reaction: NONE
Acknowledge: NONE
Cause: The 24 V power supply for the digital outputs is missing.
 Alarm value (r2124, interpret hexadecimal):
 01: TM17 24 V power supply for DI/DO 0 ... 7 missing.
 02: TM17 24 V power supply for DI/DO 8 ... 15 missing.
 04: TM15 24 V power supply for DI/DO 0 ... 7 (X520) missing.
 08: TM15 24 V power supply for DI/DO 8 ... 15 (X521) missing.
 10: TM15 24 V power supply for DI/DO 16 ... 23 (X522) missing.
 20: TM41 24 V power supply for DI/DO 0 ... 3 missing.
Remedy: Check the terminals for the power supply voltage (L1+, L2+, L3+, M).
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A35907 (F, N) TM: Hardware initialization error

Reaction: NONE
Acknowledge: NONE
Cause: The Terminal Module was not successfully initialized.
 Alarm value (r2124, interpret hexadecimal):
 01: TM17 or TM41 - incorrect configuration request.
 02: TM17 or TM41 - programming not successful.
 04: TM17 or TM41 - invalid time stamp
Remedy: Carry-out a POWER ON.
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A35910 (F, N) TM: Module overtemperature

Reaction: NONE
Acknowledge: NONE
Cause: The temperature in the module has exceeded the highest permissible limit.
Remedy: - reduce the ambient temperature.
 - replace the Terminal Module.
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A35911 (F, N)	TM: PROFIBUS clock synchronous operation sign-of-life missing
Reaction:	NONE
Acknowledge:	NONE
Cause:	The maximum permissible number of errors in the master sign-of-life (clock synchronous PROFIBUS) has been exceeded in cyclic operation. When the alarm is output, the module outputs are reset up to the next synchronization.
Remedy:	<ul style="list-style-type: none"> - check the physical bus configuration (terminating resistor, shielding, etc.). - check the interconnection of the master sign-of-life (r4201 via p0915). - check whether the master correctly sends the sign-of-life (e.g. set-up a trace with r4201.12 ... r4201.15 and trigger signal r4301.9). - check the bus and master for utilization level (e.g. bus cycle time Tdp was set too short).
Reaction upon F:	NONE
Acknowledge upon F:	IMMEDIATELY (POWER ON)
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A35920 (F, N)	TM: Temperature sensor fault
Reaction:	NONE
Acknowledge:	NONE
Cause:	When evaluating the temperature sensor, an error occurred. Alarm value (r2124, decimal): 1: Wire breakage or sensor not connected (KTY: R > 1630 Ohm). 2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).
Remedy:	<ul style="list-style-type: none"> - check that the sensor is connected correctly. - replace sensor.
Reaction upon F:	NONE
Acknowledge upon F:	IMMEDIATELY (POWER ON)
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A35999 (F, N)	TM: Unknown alarm
Reaction:	NONE
Acknowledge:	NONE
Cause:	An alarm has occurred on the Terminal Module that cannot be interpreted by the Control Unit firmware. This can occur if the firmware on the Terminal Module is more recent than the firmware on the Control Unit. Alarm value (r2124, decimal): Alarm number. If required, the significance of this new alarm can be read about in a more recent description of the Control Unit.
Remedy:	<ul style="list-style-type: none"> - replace the firmware on the Terminal Module by an older firmware version (r0158). - upgrade the firmware on the Control Unit (r0018).
Reaction upon F:	A_INFEED: NONE (OFF1, OFF2) SERVO: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2) VECTOR: NONE (DCBRAKE, OFF1, OFF2, OFF3, STOP1, STOP2)
Acknowledge upon F:	IMMEDIATELY (POWER ON)
Reaction upon N:	NONE
Acknowledge upon N:	NONE

A36801 (F, N) DMC DRIVE-CLiQ: Sign-of-life missing

Reaction: NONE
Acknowledge: NONE
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved.
 Alarm value (r2124, interpret hexadecimal):
 0A: The sign-of-life bit in the receive telegram is not set.
Remedy:
 - check the DRIVE-CLiQ connection.
 - replace the component involved.
 See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A36804 (F, N) DMC: CRC

Reaction: NONE
Acknowledge: NONE
Cause: A checksum error has occurred when reading-out the program memory on the DRIVE-CLiQ Hub Module Cabinet (DMC).
 Fault value (r0949, interpret hexadecimal):
 Difference between the checksum at POWER ON and the actual checksum.
Remedy:
 - check whether the permissible ambient temperature for the component is maintained.
 - replace the DRIVE-CLiQ Hub Module Cabinet (DMC).
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

A36805 (F, N) DMC: EPROM checksum error

Reaction: NONE
Acknowledge: NONE
Cause: Internal parameter data is corrupted.
 Alarm value (r2124, interpret hexadecimal):
 01: EEPROM access error.
 02: Too many blocks in the EEPROM.
Remedy:
 - check whether the permissible ambient temperature for the component is maintained.
 - replace the DRIVE-CLiQ Hub Module Cabinet (DMC).
 Reaction upon F: NONE
 Acknowledge upon F: IMMEDIATELY (POWER ON)
 Reaction upon N: NONE
 Acknowledge upon N: NONE

F36820	DMC DRIVE-CLiQ: Telegram error
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. Fault value (r0949, interpret hexadecimal): 01: CRC error. 02: Telegram is shorter than specified in the length byte or in the receive list. 03: Telegram is longer than specified in the length byte or in the receive list. 04: The length of the receive telegram does not match the receive list. 05: The type of the receive telegram does not match the receive list. 06: The address of the Terminal Module in the telegram and in the receive list do not match. 07: Terminal Module expects a SYNC telegram, but the receive telegram is not a SYNC telegram. 08: Terminal Module does not expect a SYNC telegram, but the receive telegram is a SYNC telegram. 09: The error bit in the receive telegram is set. 10: The receive telegram is too early.
Remedy:	- carry-out a POWER ON. - check the electrical cabinet design and cable routing for EMC compliance. - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F36835	DMC DRIVE-CLiQ: Cyclic data transfer error
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 21: The cyclic telegram has not been received. 22: Timeout in the telegram receive list. 40: Timeout in the telegram send list.
Remedy:	- carry-out a POWER ON. - replace the component involved. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F36836	DMC DRIVE-CLiQ: Send error for DRIVE-CLiQ data
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. Data were not able to be sent. Fault value (r0949, interpret hexadecimal): 41: Telegram type does not match send list.
Remedy:	Carry-out a POWER ON.
F36837	DMC DRIVE-CLiQ: Component fault
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded. Fault value (r0949, interpret hexadecimal): 20: Error in the telegram header. 23: Receive error: The telegram buffer memory contains an error. 42: Send error: The telegram buffer memory contains an error. 43: Send error: The telegram buffer memory contains an error.
Remedy:	- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). - check the electrical cabinet design and cable routing for EMC compliance. - if required, use another DRIVE-CLiQ socket (p9904). - replace the component involved.

F36845	DMC DRIVE-CLiQ: Cyclic data transfer error
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. Fault value (r0949, interpret hexadecimal): 0B: Synchronization error during alternating cyclic data transfer.
Remedy:	Carry-out a POWER ON. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F36851	CU DRIVE-CLiQ: Sign-of-life missing
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit. Fault value (r0949, interpret hexadecimal): 0A: The sign-of-life bit in the receive telegram is not set.
Remedy:	Upgrade the firmware of the component involved.
F36860	CU DRIVE-CLiQ: Telegram error
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. Fault value (r0949, interpret hexadecimal): 11: CRC error and the receive telegram is too early. 01: CRC error. 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early. 02: Telegram is shorter than specified in the length byte or in the receive list. 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early. 03: Telegram is longer than specified in the length byte or in the receive list. 14: The length of the receive telegram does not match the receive list and the receive telegram is too early. 04: The length of the receive telegram does not match the receive list. 15: The type of the receive telegram does not match the receive list and the receive telegram is too early. 05: The type of the receive telegram does not match the receive list. 16: The address of the Terminal Module in the telegram and in the receive list does not match and the receive telegram is too early. 06: The address of the Terminal Module in the telegram and in the receive list do not match. 19: The error bit in the receive telegram is set and the receive telegram is too early. 09: The error bit in the receive telegram is set. 10: The receive telegram is too early.
Remedy:	- carry-out a POWER ON. - check the electrical cabinet design and cable routing for EMC compliance. - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
F36885	CU DRIVE-CLiQ: Cyclic data transfer error
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early. 21: The cyclic telegram has not been received. 22: Timeout in the telegram receive list. 40: Timeout in the telegram send list. 62: Error at the transition to cyclic operation.

Remedy:

- check the power supply voltage of the component involved.
- carry-out a POWER ON.
- replace the component involved.

F36886 CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved. Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.
Remedy: Carry-out a POWER ON.

F36887 CU DRIVE-CLiQ: Component fault

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
 60: Response received too late during runtime measurement.
 61: Time taken to exchange characteristic data too long.
Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

F36895 CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the DRIVE-CLiQ Hub Module Cabinet (DMC) involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.
Remedy: Carry-out a POWER ON.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F36896 CU DRIVE-CLiQ: Inconsistent component characteristics

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: The properties of the DRIVE-CLiQ component, specified by the fault value, have changed in an incompatible fashion with respect to the properties when booted. One cause can be, e.g. that a DRIVE-CLiQ cable or DRIVE-CLiQ component has been replaced.
 Fault value (r0949, decimal):
 Component ID.
Remedy:

- when replacing cables, only use cables with the same length as the original cables.
- when replacing components, use the same components and firmware releases.
- carry-out a POWER ON.

F40000 Fault on the drive object at the DRIVE-CLiQ socket X100

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault has occurred at the drive object at the DRIVE-CLiQ socket X100.
 Fault value (r0949, decimal):
 First fault that has occurred for this drive object.
Remedy: Evaluate the fault buffer of the specified object.

F40001 Fault on the drive object at the DRIVE-CLiQ socket X101

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault has occurred at the drive object at the DRIVE-CLiQ socket X101.
 Fault value (r0949, decimal):
 First fault that has occurred for this drive object.
Remedy: Evaluate the fault buffer of the specified object.

F40002 Fault on the drive object at the DRIVE-CLiQ socket X102

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault has occurred at the drive object at the DRIVE-CLiQ socket X102.
 Fault value (r0949, decimal):
 First fault that has occurred for this drive object.
Remedy: Evaluate the fault buffer of the specified object.

F40003 Fault on the drive object at the DRIVE-CLiQ socket X103

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault has occurred at the drive object at the DRIVE-CLiQ socket X103.
 Fault value (r0949, decimal):
 First fault that has occurred for this drive object.
Remedy: Evaluate the fault buffer of the specified object.

F40004 Fault on the drive object at the DRIVE-CLiQ socket X104

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault has occurred at the drive object at the DRIVE-CLiQ socket X104.
 Fault value (r0949, decimal):
 First fault that has occurred for this drive object.
Remedy: Evaluate the fault buffer of the specified object.

F40005 Fault on the drive object at the DRIVE-CLiQ socket X105

Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault has occurred at the drive object at the DRIVE-CLiQ socket X105.
 Fault value (r0949, decimal):
 First fault that has occurred for this drive object.
Remedy: Evaluate the fault buffer of the specified object.

A40100 Alarm on the drive object at the DRIVE-CLiQ socket X100

Reaction: NONE
Acknowledge: NONE
Cause: An alarm has occurred at the drive object at the DRIVE-CLiQ socket X100.
 Alarm value (r2124, decimal):
 First alarm that has occurred for this drive object.
Remedy: Evaluate the alarm buffer of the specified object.

A40101 Alarm on the drive object at the DRIVE-CLiQ socket X101

Reaction: NONE
Acknowledge: NONE
Cause: An alarm has occurred at the drive object at the DRIVE-CLiQ socket X101.
 Alarm value (r2124, decimal):
 First alarm that has occurred for this drive object.
Remedy: Evaluate the alarm buffer of the specified object.

A40102	Alarm on the drive object at the DRIVE-CLiQ socket X102
Reaction:	NONE
Acknowledge:	NONE
Cause:	An alarm has occurred at the drive object at the DRIVE-CLiQ socket X102. Alarm value (r2124, decimal): First alarm that has occurred for this drive object.
Remedy:	Evaluate the alarm buffer of the specified object.

A40103	Alarm on the drive object at the DRIVE-CLiQ socket X103
Reaction:	NONE
Acknowledge:	NONE
Cause:	An alarm has occurred at the drive object at the DRIVE-CLiQ socket X103. Alarm value (r2124, decimal): First alarm that has occurred for this drive object.
Remedy:	Evaluate the alarm buffer of the specified object.

A40104	Alarm on the drive object at the DRIVE-CLiQ socket X104
Reaction:	NONE
Acknowledge:	NONE
Cause:	An alarm has occurred at the drive object at the DRIVE-CLiQ socket X104. Alarm value (r2124, decimal): First alarm that has occurred for this drive object.
Remedy:	Evaluate the alarm buffer of the specified object.

A40105	Alarm on the drive object at the DRIVE-CLiQ socket X105
Reaction:	NONE
Acknowledge:	NONE
Cause:	An alarm has occurred at the drive object at the DRIVE-CLiQ socket X105. Alarm value (r2124, decimal): First alarm that has occurred for this drive object.
Remedy:	Evaluate the alarm buffer of the specified object.

F40799	CU-Link: Configured transfer end time exceeded
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The configured transfer end time when transferring the cyclic actual values was exceeded.
Remedy:	- carry-out a POWER ON (power off/on) for all components. - contact the Hotline.

F40801	CX32 DRIVE-CLiQ: Sign-of-life missing
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 0A: The sign-of-life bit in the receive telegram is not set.
Remedy:	- carry-out a POWER ON. - replace the component involved. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)

F40820	CX32 DRIVE-CLiQ: Telegram error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. Fault value (r0949, interpret hexadecimal): 01: CRC error. 02: Telegram is shorter than specified in the length byte or in the receive list. 03: Telegram is longer than specified in the length byte or in the receive list. 04: The length of the receive telegram does not match the receive list. 05: The type of the receive telegram does not match the receive list. 06: The address of the controller extension in the telegram and in the receive list do not match. 07: Controller extension expects a SYNC telegram, but the receive telegram is not a SYNC telegram. 08: Controller extension does not expect a SYNC telegram, but the receive telegram is a SYNC telegram. 09: The error bit in the receive telegram is set. 10: The receive telegram is too early.
Remedy:	- carry-out a POWER ON. - check the electrical cabinet design and cable routing for EMC compliance. - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F40835	CX32 DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 21: The cyclic telegram has not been received. 22: Timeout in the telegram receive list. 40: Timeout in the telegram send list.
Remedy:	- carry-out a POWER ON. - replace the component involved. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F40836	CX32 DRIVE-CLiQ: Send error for DRIVE-CLiQ data
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. Data were not able to be sent. Fault value (r0949, interpret hexadecimal): 41: Telegram type does not match send list.
Remedy:	Carry-out a POWER ON.
F40837	CX32 DRIVE-CLiQ: Component fault
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded. Fault value (r0949, interpret hexadecimal): 20: Error in the telegram header. 23: Receive error: The telegram buffer memory contains an error. 42: Send error: The telegram buffer memory contains an error. 43: Send error: The telegram buffer memory contains an error.
Remedy:	- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). - check the electrical cabinet design and cable routing for EMC compliance. - if required, use another DRIVE-CLiQ socket (p9904). - replace the component involved.

F40845	CX32 DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. Fault value (r0949, interpret hexadecimal): 0B: Synchronization error during alternating cyclic data transfer.
Remedy:	Carry-out a POWER ON. See also: p9916 (DRIVE-CLiQ data transfer error, shutdown threshold, slave)
F40851	CU DRIVE-CLiQ: Sign-of-life missing
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. The DRIVE-CLiQ component did not set the sign of life to the Control Unit. Fault value (r0949, interpret hexadecimal): 0A: The sign-of-life bit in the receive telegram is not set.
Remedy:	Upgrade the firmware of the component involved.
F40860	CU DRIVE-CLiQ: Telegram error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. Fault value (r0949, interpret hexadecimal): 11: CRC error and the receive telegram is too early. 01: CRC error. 12: The telegram is shorter than that specified in the length byte or in the receive list and the receive telegram is too early. 02: Telegram is shorter than specified in the length byte or in the receive list. 13: The telegram is longer than that specified in the length byte or in the receive list and the receive telegram is too early. 03: Telegram is longer than specified in the length byte or in the receive list. 14: The length of the receive telegram does not match the receive list and the receive telegram is too early. 04: The length of the receive telegram does not match the receive list. 15: The type of the receive telegram does not match the receive list and the receive telegram is too early. 05: The type of the receive telegram does not match the receive list. 16: The address of the controller extension in the telegram and in the receive list does not match and the receive telegram is too early. 06: The address of the controller extension in the telegram and in the receive list do not match. 19: The error bit in the receive telegram is set and the receive telegram is too early. 09: The error bit in the receive telegram is set. 10: The receive telegram is too early.
Remedy:	- carry-out a POWER ON. - check the electrical cabinet design and cable routing for EMC compliance. - check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...). See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)
F40885	CU DRIVE-CLiQ: Cyclic data transfer error
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved. The nodes do not send and receive in synchronism. Fault value (r0949, interpret hexadecimal): 0A: The sign-of-life bit in the receive telegram is not set. 1A: Sign-of-life bit in the receive telegram not set and the receive telegram is too early. 21: The cyclic telegram has not been received. 22: Timeout in the telegram receive list. 40: Timeout in the telegram send list. 62: Error at the transition to cyclic operation.

Remedy:

- check the power supply voltage of the component involved.
- carry-out a POWER ON.
- replace the component involved.

See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F40886 CU DRIVE-CLiQ: Error when sending DRIVE-CLiQ data

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved.
 Data were not able to be sent.
 Fault value (r0949, interpret hexadecimal):
 41: Telegram type does not match send list.
Remedy: Carry-out a POWER ON.

F40887 CU DRIVE-CLiQ: Component fault

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: Fault detected on the DRIVE-CLiQ component involved. Faulty hardware cannot be excluded.
 Fault value (r0949, interpret hexadecimal):
 20: Error in the telegram header.
 23: Receive error: The telegram buffer memory contains an error.
 42: Send error: The telegram buffer memory contains an error.
 43: Send error: The telegram buffer memory contains an error.
 60: Response received too late during runtime measurement.
 61: Time taken to exchange characteristic data too long.
Remedy:

- check the DRIVE-CLiQ wiring (interrupted cable, contacts, ...).
- check the electrical cabinet design and cable routing for EMC compliance.
- if required, use another DRIVE-CLiQ socket (p9904).
- replace the component involved.

F40895 CU DRIVE-CLiQ: Cyclic data transfer error

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: A DRIVE-CLiQ communications error has occurred between the Control Unit and the controller extension involved.
 Fault value (r0949, interpret hexadecimal):
 0B: Synchronization error during alternating cyclic data transfer.
Remedy: Carry-out a POWER ON.
 See also: p9915 (DRIVE-CLiQ data transfer error, shutdown threshold, master)

F49150 Cooling system: Fault occurred

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The cooling system signals a general fault.
Remedy:

- check the wiring between the cooling system and the input terminal (Terminal Module).
- check the external Control Unit for the cooling system.

See also: p0266 (Cooling system, signal source feedback signals)

F49151 Cooling system: Conductivity has exceeded the fault threshold

Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The conductivity of the cooling water has exceeded the selected fault threshold (p0269[2]).
 See also: p0261 (Cooling system, starting time 2), p0262 (Cooling system, fault conductivity delay time), p0266 (Cooling system, signal source feedback signals)
Remedy: Check the device to de-ionize the cooling water.

F49152 Cooling system: ON command, feedback signal missing

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The feedback signal of the ON command of the cooling system is missing.
- after the ON command, the feedback signal has not been received within the selected starting time (p0260).
- the feedback signal has failed in operation.
See also: p0260 (Cooling system, starting time 1), r0267 (Cooling system status word display)

Remedy:
- check the wiring between the cooling system and the input terminal (Terminal Module).
- check the external Control Unit for the cooling system.

F49153 Cooling system: Water flow too low

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The drive converter cooling system signals that the water flow is too low.
- after the ON command, the feedback signal has not been received within the selected starting time (p0260).
- in operation, the feedback signal has failed for longer than the permitted failure time (p0263).
See also: p0260 (Cooling system, starting time 1), p0263 (Cooling system fault water flow, delay time), r0267 (Cooling system status word display)

Remedy:
- check the wiring between the cooling system and the input terminal (Terminal Module).
- check the external Control Unit for the cooling system.

F49154 Cooling system: Water has leaked

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The leakage water monitoring function has responded.
See also: r0267 (Cooling system status word display)

Remedy:
- check the cooling system for leaks in the cooling circuit.
- check the wiring of the input terminal (Terminal Module) used to monitor the leakage water.

F49155 Cooling system: Power Stack Adapter, firmware version too old

Reaction: OFF2

Acknowledge: POWER ON

Cause: The firmware version in the Power Stack Adapter (PSA) is too old and does not support the water cooling.

Remedy: Upgrade the firmware version.

F49156 Cooling system: Cooling water temperature has exceeded the fault threshold

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The cooling water intake temperature has exceeded the permanently set fault threshold.

Remedy: Check the cooling system and the ambient conditions.

A49170 Cooling system: Alarm has occurred

Reaction: NONE

Acknowledge: NONE

Cause: The cooling system signals a general alarm.

Remedy:
- check the wiring between the cooling system and the input terminal (Terminal Module).
- check the external Control Unit for the cooling system.

A49171 Cooling system: Conductivity has exceeded the alarm threshold

Reaction: NONE

Acknowledge: NONE

Cause: The conductivity of the cooling water has exceeded the selected alarm threshold (p0269[1]).
See also: p0261 (Cooling system, starting time 2), p0262 (Cooling system, fault conductivity delay time), p0266 (Cooling system, signal source feedback signals)

Remedy: Check the device to de-ionize the cooling water.

A49172	Cooling system: Conductivity actual value is not valid
Reaction:	NONE
Acknowledge:	NONE
Cause:	When monitoring the conductivity of the cooling water, there is a fault in the wiring or in the sensor.
Remedy:	- check the wiring between the cooling system and the Power Stack Adapter (PSA). - check the function of the sensor to measure the conductivity.
A49173	Cooling system: Cooling water temperature has exceeded the alarm threshold
Reaction:	NONE
Acknowledge:	NONE
Cause:	The cooling water intake temperature has exceeded the permanently set alarm threshold.
Remedy:	Check the cooling system and the ambient conditions.
F49200	Excitation group signal fault
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The excitation sequence control signals a fault. Fault value (r0949, hexadecimal): Bit 0: When powered-down or when powering-down the excitation, the signal "excitation ready to power-up feedback signal" was not received within the monitoring time. Bit 1: After an ON command, the signal "excitation ready feedback signal" was not received within the monitoring time. Bit 2: After the pulses were enabled, the signal "excitation operational feedback signal" was not received within the monitoring time. Bit 3: The "excitation group signal fault" signal is present.
Remedy:	- check the excitation. - check commands, feedback signals and BICO interconnections.
A49201 (F)	Excitation, group signal alarm
Reaction:	NONE
Acknowledge:	NONE
Cause:	The "excitation group signal alarm" signal is present.
Remedy:	Check the excitation equipment.
Reaction upon F:	NONE
Acknowledge upon F:	IMMEDIATELY

List of Abbreviations

A

Abbreviation	German	English
A		
A...	Warnung	Alarm
AC	Wechselstrom	Alternating Current
ADC	Analog-Digital-Konverter	Analog Digital Converter
AI	Analogeingang	Analog Input
ALM	Active Line Module	Active Line Module
AO	Analogausgang	Analog Output
AOP	Advanced Operator Panel	Advanced Operator Panel
APC	Advanced Positioning Control	Advanced Positioning Control
ASC	Ankerkurzschluss	Armature Short-Circuit
ASCII	Amerikanische Code-Norm für den Informationsaustausch	American Standard Code for Information Interchange
ASM	Asynchronmotor	Induction motor
B		
BB	Betriebsbedingung	Operating condition
BERO	Firmenname für einen Näherungsschalter	Tradename for a type of proximity switch
BI	Binektoreingang	Binector Input
BIA	Berufsgenossenschaftliches Institut für Arbeitssicherheit	Berufsgenossenschaftliches Institut für Arbeitssicherheit (German Institute for Occupational Safety)
BICO	Binektor-Konnektor-Technologie	Binector Connector Technology
BLM	Basic Line Module	Basic Line Module
BOP	Basic Operator Panel	Basic Operator Panel
C		
C	Kapazität	Capacitance
C...	Safety-Meldung	Safety message
CAN	Serielles Bussystem	Controller Area Network
CBC	Kommunikationsbaugruppe CAN	Communication Board CAN
CD	Compact Disc	Compact Disc
CDS	Befehlsdatensatz	Command Data Set
CI	Konnectoreingang	Connector Input
CNC	Computerunterstützte numerische Steuerung	Computer Numerical Control
CO	Konnectorausgang	Connector Output

Abbreviation	German	English
CO/BO	Konnektor-/Binektorausgang	Connector Output/Binector Output
COB-ID	CAN Object-Identification	CAN Object-Identification
COM	Mittelkontakt eines Wechselkontaktes	Common contact of a change-over relay
CP	Kommunikationsprozessor	Communications Processor
CPU	Zentralbaugruppe	Central Processing Unit
CRC	Checksummenprüfung	Cyclic Redundancy Check
CSM	Control Supply Module	Control Supply Module
CU	Control Unit	Control Unit
D		
DAC	Digital-Analog-Konverter	Digital Analog Converter
DC	Gleichstrom	Direct Current
DCN	Gleichstrom negativ	Direct current negative
DCP	Gleichstrom positiv	Direct current positive
DDS	Antriebsdatensatz	Drive Data Set
DI	Digitaleingang	Digital Input
DI/DO	Digitaleingang/-ausgang bidirektional	Bidirectional Digital Input/Output
DMC	DRIVE-CLiQ Module Cabinet (Hub)	DRIVE-CLiQ Module Cabinet (Hub)
DO	Digitalausgang	Digital Output
DO	Antriebsobjekt	Drive Object
DPRAM	Speicher mit beidseitigem Zugriff	Dual Ported Random Access Memory
DRAM	Dynamischer Speicher	Dynamic Random Access Memory
DRIVE-CLiQ	Drive Component Link with IQ	Drive Component Link with IQ
DSC	Dynamic Servo Control	Dynamic Servo Control
E		
EDS	Geberdatensatz	Encoder Data Set
EGB	Elektrostatisch gefährdete Baugruppen	Electrostatic Sensitive Devices (ESD)
ELP	Erdschlussüberwachung	Earth Leakage Protection
EMK	Elektromagnetische Kraft	Electromagnetic Force (EMF)
EMV	Elektromagnetische Verträglichkeit	Electromagnetic Compatibility (EMC)
EN	Europäische Norm	European Standard
EnDat	Geber-Schnittstelle	Encoder-Data-Interface
EP	Impulsfreigabe	Enable Pulses
EPOS	Einfachpositionierer	Basic positioner
ES	Engineering System	Engineering System
ESB	Ersatzschaltbild	Equivalent circuit diagram
ESR	Erweitertes Stillsetzen und Rückziehen	Extended Stop and Retract
F		
F...	Störung	Fault
FAQ	Häufig gestellte Fragen	Frequently Asked Questions
FCC	Function Control Chart	Function Control Chart
FCC	Flussstromregelung	Flux Current Control

Abbreviation	German	English
FEM	Fremderregter Synchronmotor	Separately excited synchronous motor
FEPROM	Schreib- und Lesespeicher nichtflüchtig	Flash-EPROM
FG	Funktionsgenerator	Function Generator
FI	Fehlerstrom-Schutzschalter	Earth Leakage Circuit-Breaker (ELCB)
FP	Funktionsplan	Function diagram
FW	Firmware	Firmware
G		
GB	Gigabyte	Gigabyte
GC	Global-Control-Telegramm (Broadcast-Telegramm)	Global Control Telegram (Broadcast Telegram)
GSD	Gerätstammdatei: beschreibt die Merkmale eines PROFIBUS-Slaves	Device master file: describes the features of a PROFIBUS slave
GSV	Gate Supply Voltage	Gate Supply Voltage
H		
HF	Hochfrequenz	High frequency
HFD	Hochfrequenzdrossel	High frequency reactor
HLG	Hochlaufgeber	Ramp-function generator
HMI	Mensch-Maschine-Schnittstelle	Human Machine Interface
HTL	Logik mit hoher Störschwelle	High-Threshold Logic
HW	Hardware	Hardware
I		
i. V.	In Vorbereitung: diese Eigenschaft steht zur Zeit nicht zur Verfügung	In preparation: this feature is currently not available
IBN	Inbetriebnahme	Commissioning
I/O	Eingang/Ausgang	Input/Output
ID	Identifizierung	Identifier
IEC	Internationale Norm in der Elektrotechnik	International Electrotechnical Commission
IGBT	Bipolartransistor mit isolierter Steuerelektrode	Insulated Gate Bipolar Transistor
IL	Impulslöschung	Pulse suppression
IT	Drehstromversorgungsnetz ungeerdet	Insulated three-phase supply network
IVP	Interner Spannungsschutz	Internal Voltage Protection
J		
JOG	Tippen	Jogging
K		
KDV	Kreuzweiser Datenvergleich	Data cross-checking
KIP	Kinetische Pufferung	Kinetic buffering
Kp	Proportionalverstärkung	Proportional gain
KTY	Spezieller Temperatursensor	Special temperature sensor
L		
L	Induktivität	Inductance
LED	Leuchtdiode	Light Emitting Diode

Abbreviation	German	English
LIN	Linearmotor	Linear motor
LR	Lageregler	Position controller
LSB	Niederwertiges Bit	Least Significant Bit
LSS	Netzschalter	Line Side Switch
LU	Längeneinheit	Length Unit
M		
M	Masse	Reference potential, zero potential
MB	Megabyte	Megabyte
MCC	Motion Control Chart	Motion Control Chart
MDS	Motordatensatz	Motor Data Set
MLFB	Maschinenlesbare Fabrikatebezeichnung	Machine-readable product designation
MMC	Mensch Maschine Kommunikation	Man-Machine Communication
MSB	Höchstwertiges Bit	Most Significant Bit
MSCY_C1	Zyklische Kommunikation zwischen Master (Klasse 1) und Slave	Master Slave Cycle Class 1
MT	Messtaster	Measuring probe
N		
N. C.	Nicht angeschlossen	Not Connected
N...	Keine Meldung oder Interne Meldung	No Report
NAMUR	Normenarbeitsgemeinschaft für Mess- und Regeltechnik in der chemischen Industrie	Standardization association for measurement and control in chemical industries
NC	Öffner	Normally Closed (contact)
NC	Numerische Steuerung	Numerical Control
NEMA	Normengremium in USA (United States of America)	National Electrical Manufacturers Association
NM	Nullmarke	Zero Mark
NO	Schließer	Normally Open (contact)
O		
OA	Open Architecture	Open Architecture
OEM	Original Equipment Manufacturer	Original Equipment Manufacturer
OLP	Busstecker für Lichtleiter	Optical Link Plug
OMI	Option Module Interface	Option Module Interface
P		
p...	Einstellparameter	Adjustable parameter
PcCtrl	Steuerungshoheit	Master Control
PDS	Leistungsteildatensatz	Power unit Data Set
PE	Schutzerde	Protective Earth
PELV	Schutzkleinspannung	Protective Extra Low Voltage
PEM	Permanenterregter Synchronmotor	Permanent-magnet synchronous motor
PG	Programmiergerät	Programming terminal
PI	Proportional Integral	Proportional Integral

Abbreviation	German	English
PID	Proportional Integral Differential	Proportional Integral Differential
PLC	Speicherprogrammierbare Steuerung (SPS)	Programmable Logical Controller
PLL	Baustein zur Synchronisierung	Phase Locked Loop
PNO	PROFIBUS Nutzerorganisation	PROFIBUS user organisation
PPI	Punkt zu Punkt Schnittstelle	Point to Point Interface
PRBS	Weißes Rauschen	Pseudo Random Binary Signal
PROFIBUS	Serieller Datenbus	Process Field Bus
PS	Stromversorgung	Power Supply
PSA	Power Stack Adapter	Power Stack Adapter
PTC	Positiver Temperaturkoeffizient	Positive Temperature Coefficient
PTP	Punkt zu Punkt	Point To Point
PWM	Pulsweitenmodulation	Pulse Width Modulation
PZD	PROFIBUS Prozessdaten	PROFIBUS Process data
Q		
R		
r...	Beobachtungsparameter (nur lesbar)	Display parameter (read only)
RAM	Speicher zum Lesen und Schreiben	Random Access Memory
RCCB	Fehlerstrom-Schutzschalter	Residual Current Circuit Breaker
RCD	Fehlerstrom-Schutzschalter	Residual Current Device
RJ45	Norm. Beschreibt eine 8-polige Steckverbindung mit Twisted-Pair Ethernet.	Standard. Describes an 8-pole plug connector with twisted pair Ethernet.
RKA	Rückkühlanlage	Recooling system
RO	Nur lesbar	Read Only
RPDO	Receive Process Data Object	Receive Process Data Object
RS232	Serielle Schnittstelle	Serial Interface
RS485	Norm. Beschreibt die Physik einer digitalen seriellen Schnittstelle.	Standard. Describes the physical characteristics of a digital serial interface.
RTC	Echtzeituhr	Real Time Clock
S		
S1	Dauerbetrieb	Continuous operation
S3	Aussetzbetrieb	Periodic duty
SBC	Sichere Bremsenansteuerung	Safe Brake Control
SBH	Sicherer Betriebshalt	Safe operating stop
SBR	Sichere Bremsrampe	Safe braking ramp
SBT	Sicherer Bremsentest	Safe Brake Test
SCA	Sichere Nocke	Safe Cam
SDI	Sichere Richtung	Safe Direction
SE	Sicherer Software-Endschalter	Safe software limit switch
SG	Sicher reduzierte Geschwindigkeit	Safely reduced speed
SGA	Sicherheitsgerichteter Ausgang	Safety-related output
SGE	Sicherheitsgerichteter Eingang	Safety-related input
SH	Sicherer Halt	Safe standstill

Abbreviation	German	English
SI	Safety Integrated	Safety Integrated
SIL	Sicherheitsintegritätsgrad	Safety Integrity Level
SLI	Sicheres Schrittmaß	Safely Limited Increment
SLM	Smart Line Module	Smart Line Module
SLP	Sichere Endlage	Safely Limited Position
SLS	Sicher reduzierte Geschwindigkeit	Safely Limited Speed
SLVC	Geberlose Vektorregelung	Sensorless Vector Control
SM	Sensor Module	Sensor Module
SMC	Sensor Module Cabinet	Sensor Module Cabinet
SME	Sensor Module External	Sensor Module External
SN	Sicherer Software-Nocken	Safe software cam
SOS	Sicherer Betriebshalt	Safe Operational Stop
SPC	Sollwertkanal	Setpoint Channel
SPS	Speicherprogrammierbare Steuerung	Programmable Logic Controller (PLC)
SS1	Safe Stop 1	Safe Stop 1
SS2	Safe Stop 2	Safe Stop 2
SSI	Synchron Serielle Schnittstelle	Synchronous Serial Interface
SSM	Sichere Geschwindigkeitsanzeige $n < n_x$	Safe Speed Monitoring $n < n_x$
SSR	Sichere Bremsrampe	Safe Stop Ramp
STO	Sicherer Halt	Safe Torque Off
STW	PROFIBUS Steuerwort	PROFIBUS control word
T		
TB	Terminal Board	Terminal Board
TIA	Totally Integrated Automation	Totally Integrated Automation
TM	Terminal Module	Terminal Module
TN	Drehstromversorgungsnetz geerdet	Grounded three-phase supply network
Tn	Nachstellzeit	Integral time
TPDO	Transmit Process Data Object	Transmit Process Data Object
TT	Drehstromversorgungsnetz geerdet	Grounded three-phase supply network
TTL	Transistor-Transistor-Logik	Transistor-Transistor-Logic
U		
UL	Underwriters Laboratories Inc.	Underwriters Laboratories Inc.
USV	Unterbrechungsfreie Stromversorgung	Uninterruptible power supply
V		
VC	Vektorregelung	Vector Control
Vdc	Zwischenkreisspannung	DC link voltage
VdcN	Teilzwischenkreisspannung negativ	Partial DC link voltage negative
VdcP	Teilzwischenkreisspannung positiv	Partial DC link voltage positive
VDE	Verband Deutscher Elektrotechniker	Association of German Electrical Engineers
VDI	Verein Deutscher Ingenieure	Association of German Engineers
Vpp	Volt Spitze zu Spitze	Volt peak to peak

Abbreviation	German	English
VSM	Voltage Sensing Module	Voltage Sensing Module
W		
WEA	Wiedereinschaltautomatik	Automatic restart
WZM	Werkzeugmaschine	Machine tool
X		
XML	Erweiterbare Auszeichnungssprache (Standardsprache für Web-Publishing und Dokumentenmanagement)	Extensible Markup Language
Y		
Z		
ZK	Zwischenkreis	DC link
ZSW	PROFIBUS Zustandswort	PROFIBUS status word

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Installation and wiring recommendation for RS 485 Transmission
Order No. 2.111 (German) Version 1.0
2.112 (English)

Documentation for Safety Equipment

Note

For more information about technical documentation for Safety Integrated, visit the following address:

<http://www.siemens.com/safety>

The following list contains some of the safety-related documentation available.

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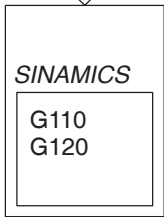
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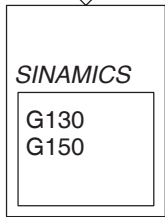
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Overview of SINAMICS Documentation (03/2006)

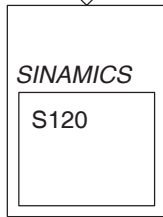
General Documentation/Catalogs



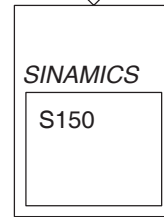
D11.1
Converter Chassis Units
0.12 – 3 kW



D11
Converter Chassis Units
Converter Cabinet Units

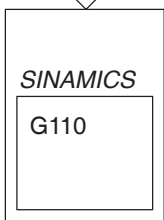


D21.1
Chassis Units

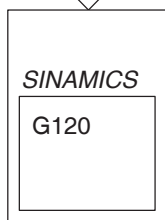


D21.3
Vector Control Cabinet Units
75 – 1200 kW

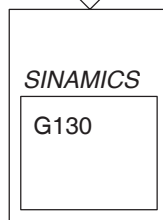
Manufacturer/Service Documentation



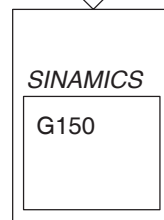
- Getting Started
- Operating Instructions
- List Manual



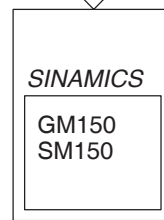
- Operating Instructions (Compact)
- Operating Instructions
- List Manual



- Operating Instructions
- List Manual

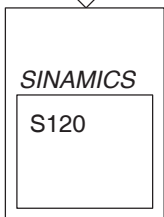


- Operating Instructions
- List Manual

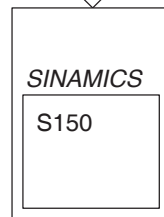


- Operating Instructions
- List Manual

Manufacturer/Service Documentation

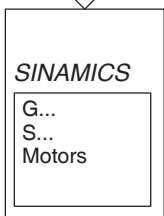


- Getting Started
- Equipment Manual for Control Units and Additional System Components
- Equipment Manual for Booksize Power Modules
- Equipment Manual Booksize Cold-Plate Power Sections
- Chassis Power Sections
- Equipment Manual AC DRIVE
- Commissioning Manual – Commissioning Manual CANopen
- Function Manual – Function Manual Free Function Blocks
- List Manual

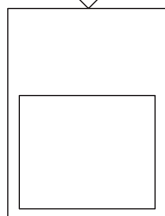


- Operating Instructions
- List Manual

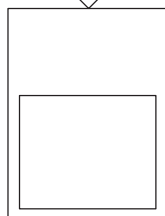
Manufacturer/Service Documentation



DOCONCD



Configuration Manual
Motors



EMC
Installation Guideline