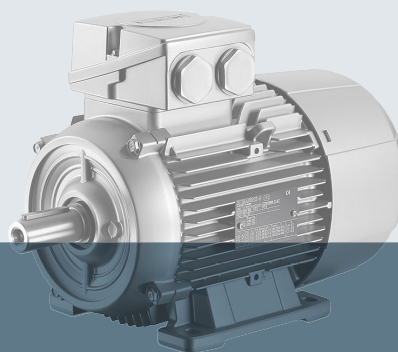


SIEMENS



SINAMICS

SINAMICS G120C

List Manual

Edition

04/2015

Answers for industry.

SIEMENS

SINAMICS

SINAMICS G120C

List Manual

Valid for

Drive

SINAMICS G120C

Firmware version

4.7 SP3

Fundamental safety
instructions

1

Parameters

2

Function diagrams

3

Faults and alarms

4

Appendix

A

Index




04/2015

A5E33840768

Legal information

Warning concept

This Manual contains information which you must observe to ensure your own personal safety as well as to avoid material damage. The notices referring to your personal safety are highlighted in the manual by a safety alert symbol, notices referring only to equipment damage have no safety alert symbol. Depending on the hazard level, warnings are indicated in a descending order as follows:

 DANGER
indicates that death or serious injury will result if proper precautions are not taken.
 WARNING
indicates that death or serious injury could result if proper precautions are not taken.
 CAUTION
indicates that minor personal injury can result if proper precautions are not taken.
NOTICE
indicates that property damage can result if proper precautions are not taken.


If more than one level of danger is simultaneously applicable, the warning notice for the highest level is 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 product/system described in this documentation may only be operated by **personnel qualified** for the specific task in accordance with the relevant documentation for the specific task, in particular its warning notices and safety instructions. Qualified personnel are those who, based on their training and experience, are capable of identifying risks and avoiding potential hazards when working with these products/systems.

Proper use of Siemens products

Note the following:

 WARNING
Siemens products are only permitted to be used for the applications envisaged in the catalog and in the associated technical documentation. If third-party products and components are to be used, they must be recommended or approved by Siemens. These products can only function correctly and safely if they are transported, stored, set up, mounted, installed, commissioned, operated and maintained correctly. The permissible ambient conditions must be adhered to. Information in the associated documentation must be observed.

Trademarks

All names identified with ® are registered trademarks of Siemens AG. Any other names used in this publication may be trademarks whose use by third parties for their own purposes could violate the rights of the owner.

Disclaimer of liability

We have verified that the contents of this document correspond to the hardware and software described. Since variance cannot be precluded entirely, we cannot guarantee full consistency. The information given in this document is reviewed at regular intervals and any corrections that might be necessary are made in the subsequent editions.

Table of contents

1	Fundamental safety instructions	7
1.1	General safety instructions	8
1.2	Industrial security	9
2	Parameters	11
2.1	Overview of parameters	12
2.1.1	Explanation of the parameter list	12
2.1.2	Number ranges of parameters	22
2.2	List of parameters	24
2.3	Parameters for data sets	336
2.3.1	Command Data Sets (CDS)	336
2.3.2	Drive Data Sets (DDS)	337
2.3.3	Motor data sets (MDS)	341
2.3.4	Power unit Data Sets (PDS)	343
2.3.5	Encoder Data Sets (EDS)	343
2.4	BICO parameters (connectors/binectors)	344
2.4.1	Binector inputs (BI)	344
2.4.2	Connector inputs (CI)	345
2.4.3	Binector outputs (BO)	345
2.4.4	Connector outputs (CO)	346
2.4.5	Connector/binector outputs (CO/BO)	349
2.5	Parameters for write protection and know-how protection	350
2.5.1	Parameters with "WRITE_NO_LOCK"	350
2.5.2	Parameters with "KHP_WRITE_NO_LOCK"	350
2.5.3	Parameters with "KHP_ACTIVE_READ"	351
2.6	Quick commissioning (p0010 = 1)	352
3	Function diagrams	355
3.1	Table of contents	356
3.2	Explanations on the function diagrams	361
3.3	Input/output terminals	366
3.4	PROFenergy	375
3.5	PROFIdrive communication (PROFIBUS/PROFINET)	378
3.6	CANopen communication	392
3.7	Communication, fieldbus interface (USS, MODBUS)	399
3.8	Internal control/status words	405
3.9	Brake control	423
3.10	Safety Integrated Basic Functions	425
3.11	Safety Integrated PROFIsafe	431

3.12	Setpoint channel	433
3.13	Vector control	442
3.14	Vector control, Standard Drive Control (p0096 = 1)	467
3.15	Vector control, Dynamic Drive Control (p0096 = 2)	473
3.16	Technology functions	490
3.17	Technology controller	492
3.18	Signals and monitoring functions	497
3.19	Diagnostics.	507
3.20	Data sets	513
4	Faults and alarms	517
4.1	Overview of faults and alarms	518
4.1.1	General	518
4.1.2	Explanation of the list of faults and alarms.	522
4.1.3	Number ranges of faults and alarms	527
4.2	List of faults and alarms	529
A	Appendix	617
A.1	ASCII table (characters that can be displayed)	618
A.2	List of abbreviations	621
	Index	631

Fundamental safety instructions

Content

1.1	General safety instructions	8
1.2	Industrial security	9

1.1 General safety instructions



WARNING

Risk of death if the safety instructions and remaining risks are not carefully observed

If the safety instructions and residual risks are not observed in the associated hardware documentation, accidents involving severe injuries or death can occur.

- Observe the safety instructions given in the hardware documentation.
- Consider the residual risks for the risk evaluation.



WARNING

Danger to life or malfunctions of the machine as a result of incorrect or changed parameterization

As a result of incorrect or changed parameterization, machines can malfunction, which in turn can lead to injuries or death.

- Protect the parameterization (parameter assignments) against unauthorized access.
- Respond to possible malfunctions by applying suitable measures (e.g. EMERGENCY-STOP or EMERGENCY-OFF).

1.2 Industrial security

Note

Industrial security

Siemens provides products and solutions with industrial security functions that support the secure operation of plants, solutions, machines, devices, and/or networks. They are important components of a holistic industrial security concept. With this in mind, Siemens' products and solutions undergo continuous development. Siemens recommends strongly that you regularly check for product updates.

To ensure that Siemens products and solutions are operated securely, suitable preventive measures (e.g. cell protection concept) and each component must be integrated into a state-of-the-art holistic industrial security concept. Third-party products that may be in use should also be considered. You will find more information about industrial security at:

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

To receive information about product updates on a regular basis, register for our product newsletter. You will find more information at:

<http://support.automation.siemens.com>



WARNING

Danger as a result of unsafe operating states resulting from software manipulation

Software manipulation (e.g. by viruses, Trojan horses, malware, worms) can cause unsafe operating states to develop in your installation which can result in death, severe injuries and/or material damage.

- Keep the software up to date.

Information and newsletters can be found at:

<http://support.automation.siemens.com>

- Incorporate the automation and drive components into a holistic, state-of-the-art industrial security concept for the installation or machine.

For more information, visit:

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

- Make sure that you include all installed products into the holistic industrial security concept.

Parameters

Content

2.1	Overview of parameters	12
2.2	List of parameters	24
2.3	Parameters for data sets	336
2.4	BICO parameters (connectors/binectors)	344
2.5	Parameters for write protection and know-how protection	350
2.6	Quick commissioning (p0010 = 1)	352

2.1 Overview of parameters




2.1.1 Explanation of the parameter list

Basic structure of the parameter descriptions

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

The "List of parameters" (Page 24) has the following structure:

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

pxxxx[0...n]	BICO: Full parameter name / abbreviated name				
CU/PM variants	Access level: 3	Calculated: p0340 = 1		Data type: FloatingPoint32	
	Can be changed: C(x), U, T	Scaling: p2002		Dyn. index: CDS, p0170	
	Unit group: 6_2	Unit selection: p0505		Func. diagram: 8070	
	Min	Max		Factory setting	
	0.00 [Nm]	10.00 [Nm]		0.00 [Nm]	
Description:	Text				
Value:	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 field:	Bit	Signal name	1 signal	0 signal	FP
	00	Name and meaning of bit 0	Yes	no	8060
	01	Name and meaning of bit 1	Yes	no	-
	02	Name and meaning of bit 2	Yes	no	8052
		etc.			
Dependency:	Text Refer to: pxxxx, rxxxx Refer to: Fxxxxx, Axxxxx				
Danger:	Warning:	Caution:	Safety notices with a warning triangle		
					
Notice:	Safety notice without a warning triangle				
Note:	Information that might be useful.				

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

The individual pieces of information are described in detail below.

pxxxx[0...n] Parameter number

The parameter number is made up of a "p" or "r", followed by the parameter number and the index or bit field (optional).

Examples of the representation in the parameter list:

- p... Adjustable parameters (read and write)
- r... Display parameters (read only)
- p0918 Adjustable parameter 918
- p2051[0...13] Adjustable parameter 2051, indices 0 to 13
- p1001[0...n] Adjustable parameter 1001, indices 0 to n (n = configurable)
- r0944 Display parameter 944
- r2129.0...15 Display parameter 2129 with bit field from bit 0 (smallest bit) to bit 15 (largest bit)

Other examples of notation in the documentation:

- p1070[1] Adjustable parameter 1070, index 1
- p2098[1].3 Adjustable parameter 2098, index 1 bit 3
- p0795.4 Adjustable parameter 795, bit 4

The following applies to adjustable parameters:

The parameter value as delivered is specified under "Factory setting" with the relevant unit in square brackets. 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 and parameters:

- Setting the PROFIBUS telegram (BICO interconnection)
p0922
- Setting component lists
p0230, p0300, p0301, p0400
- Automatically calculating and pre-assigning
p0340, p3900
- Restoring the factory settings
p0970

The following applies to display parameters:

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

Note

The parameter list can contain parameters that are not visible in the expert lists of the particular commissioning software (e.g. parameters for trace functions).

BICO: Full parameter name/Abbreviated name

The following abbreviations can appear in front of the BICO parameter 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.

Note

A BICO input (BI/CI) cannot be interconnected with just any BICO output (BO/CO, signal source).

When interconnecting a BICO input using the commissioning software, only the corresponding possible signal sources are listed.

Function diagrams 1020 ... 1030 explain the symbols for BICO parameters and how to deal with BICO technology.

G120C variants

Specifies for which G120C variants (communication) the parameter is valid is. If no G120C variant is listed, then the parameter is valid for all variants.

The following information relating to "G120C variants" can be displayed under the parameter number:

Table 2-1 Information in the "CU/PM variants" field

CU/PM variants	Meaning
	All G120C variants have this parameter.
G120C_CAN	G120C with CAN interface
G120C_DP	G120C with PROFIBUS interface
G120C_PN	G120C with PROFINET interface
G120C_USS	G120C with USS interface

Access level

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

The system uses the following access levels:

- 1: Standard (not adjustable, included in p0003 = 3)
- 2: Extended (not adjustable, included in p0003 = 3)
- 3: Expert
- 4: Service

Parameters with this access level are password protected.

Note

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

A higher access level will also include the functions of the lower levels.

Calculated

Specifies whether the parameter is influenced by automatic calculations.

p0340 determines which calculations are to be performed:

- p0340 = 1 includes the calculations from p0340 = 2, 3, 4, 5.
- p0340 = 2 calculates the motor parameters (p0350 ... p0360, p0625).
- p0340 = 3 includes the calculations from p0340 = 4, 5.
- p0340 = 4 only calculates the controller parameters.
- p0340 = 5 only calculates the controller limits.

Note

For p3900 > 0, p0340 = 1 is also called automatically.

After p1900 = 1, 2, p0340 = 3 is also called automatically.

Parameters with a reference to p0340 after "Calculated" depend on the Power Module being used and the motor. In this case, the values at "Factory setting" do not correspond to the actual values because these values are calculated during the commissioning. This also applies to the motor parameters.

Data type

The information on the data type can consist of the following two items (separated by a slash):

- First item
Data type of the parameter.
- Second item (for binector or connector input only)
Data type of the signal source to be interconnected (binector-/connector output).

Parameters can have the following data types:

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

Depending on the data type of the BICO input parameter (signal sink) and BICO output parameter (signal source), the following combinations are possible when creating BICO interconnections:

Table 2-2 Possible combinations of BICO interconnections

	BICO input parameter			
	CI parameter			BI parameter
BICO output parameter	Unsigned32 / Integer16	Unsigned32 / Integer32	Unsigned32 / FloatingPoint32	Unsigned32 / Binary
CO: Unsigned8	x	x	–	–
CO: Unsigned16	x	x	–	–
CO: Unsigned32	x	x	–	–
CO: Integer16	x	x	r2050	–
CO: Integer32	x	x	r2060	–
CO: FloatingPoint32	x	x	x	–
BO: Unsigned8	–	–	–	x
BO: Unsigned16	–	–	–	x
BO: Unsigned32	–	–	–	x
BO: Integer16	–	–	–	x
BO: Integer32	–	–	–	x
BO: FloatingPoint32	–	–	–	–
Legend: x : BICO interconnection permitted –: BICO interconnection not permitted rxxxx: BICO interconnection is only permitted for the specified CO parameters				

Can be changed

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

The information "C(x), T, U" ((x): optional) means that the parameter can be changed only in the specified drive unit state and that the change will not take effect until the unit switches to another state. This can be a single state or multiple states.

The following states are available:

- C(x) commissioning C: Commissioning
 Drive commissioning is in progress (p0010 > 0).
 Pulses cannot be enabled.
 The parameter can only be changed in the following drive commissioning settings (p0010 > 0):
 - C: Can be changed for all settings p0010 > 0.
 - C(x): Can only be changed for the settings 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 the status "C(x)" is not active.

Scaling

Specification of the reference variable with which a signal value is automatically converted for a BICO interconnection.

The following reference variables are available:

- p2000 ... p2007: Reference speed, reference voltage, etc.
- PERCENT: 1.0 = 100 %
- 4000H: 4000 hex = 100 % (word) or 4000 0000 hex = 100 % (double word)
- p0514: specific normalization

Refer to the description for p0514[0...9] and p0515[0...19] to p0524[0...19]

Dyn. index (dynamic index)

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

- Data set (if available).
- Parameter 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)

Data sets can only be created and deleted when p0010 = 15.

Note

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

Operating Instructions SINAMICS G120 Frequency Converter G120C.

Unit group and unit selection

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

For parameters where the unit can be switched over, the specifications for "Unit group" and "Unit selection" determine the group to which this parameter belongs and with which parameter the unit can be changed over.

Example:

Unit group: 7_1, unit selection: p0505

The parameter belongs to unit group 7_1 and the unit can be changed over using p0505.

All the potential unit groups and possible unit selections are listed below.

Table 2-3 Unit group (p0100)

Unit group	Unit selection for p0100 =			Reference variable for %
	0	1	2	
7_4	Nm	lbf ft	Nm	-
14_6	kW	hp	kW	-
25_1	kg m ²	lb ft ²	kg m ²	-
27_1	kg	lb	kg	-
28_1	Nm/A	lbf ft/A	Nm/A	-

Table 2-4 Unit group (p0505)

Unit group	Unit selection for p0505 =				Reference variable for %
	1	2	3	4	
2_1	Hz	%	Hz	%	p2000
3_1	1 rpm	%	1 rpm	%	p2000
5_1	Vrms	%	Vrms	%	p2001
5_2	V	%	V	%	p2001
5_3	V	%	V	%	p2001
6_2	Arms	%	Arms	%	p2002
6_5	A	%	A	%	p2002
7_1	Nm	%	lbf ft	%	p2003
7_2	Nm	Nm	lbf ft	lbf ft	-
14_5	kW	%	hp	%	r2004
14_10	kW	kW	hp	hp	-
21_1	°C	°C	°F	°F	-
21_2	K	K	°F	°F	-
39_1	1/s ²	%	1/s ²	%	p2007

Table 2-5 Unit group (p0595)

Unit group	Unit selection for p0595 =		Reference variable for %
	Value	Unit	
9_1	The values that can be set and the technological units are shown in p0595.		

Function diagram

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

Parameter values

Min.	Minimum value of the parameter [unit]
Max	Maximum value of the parameter [unit]
Factory setting	<p>Value when delivered [unit]</p> <p>In the case of a binector/connector input, the signal source of the default BICO interconnection is specified. A non-indexed connector output is assigned the index [0].</p> <p>A different value may be displayed for certain parameters (e.g. p1800) at the initial commissioning stage or when establishing the factory settings.</p> <p>Reason: The setting of these parameters is determined by the operating environment of the Control Unit (e.g. depending on converter type, power unit).</p>

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 adjustable parameters:

- Min, Max:
The adjustment range and unit apply to all indices.
- Factory setting:
When all indices have the same factory setting, index 0 is specified with the unit to represent all indices.
When the indices have different factory settings, they are all listed individually with the unit.

Bit field

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

- Bit number and signal name
- Meaning for signal states 0 and 1
- Function diagram (FP) (optional).

The signal is shown on this function diagram.

Dependency

Conditions that must be fulfilled in conjunction with this parameter. Also includes special effects that can occur between this parameter and others.

Where necessary, "Refer to:" indicates the following information:

- List of other relevant parameters to be considered.
- List of faults and alarms to be considered.

Safety guidelines

Important information that must be observed to avoid the risk of physical injury or material damage.

Information that must be observed to avoid any problems.

Information that the user may find useful.

Danger



The description of this safety notice can be found at the beginning of this manual (see "Legal information" (Page 4)).

Warning



The description of this safety notice can be found at the beginning of this manual (see "Legal information" (Page 4)).

Caution



The description of this safety notice can be found at the beginning of this manual (see "Legal information" (Page 4)).

Notice

The description of this safety notice can be found at the beginning of this manual (see "Legal information" (Page 4)).

Note

Information that the user may find useful.

2.1.2 Number ranges of parameters

Note

The following number ranges represent an overview for all the parameters available for the SINAMICS drive family.

The parameters for the product described in this List Manual are described in detail in "List of parameters" (Page 24).

Faults and alarms are organized into the following number ranges:

Table 2-6 Number ranges of faults and alarms

of	To	Area
1000	3999	Control Unit
4000	4999	Reserved
5000	5999	Power section
6000	6899	Infeed
6900	6999	Braking Module
7000	7999	Drive
8000	8999	Option Board
9000	12999	Reserved
13000	13020	Licensing
13021	13099	Reserved
13100	13102	Know-how protection
13103	19999	Reserved
20000	29999	OEM
30000	30999	DRIVE-CLiQ component power unit
31000	31999	DRIVE-CLiQ component encoder 1
32000	32999	DRIVE-CLiQ component encoder 2 Note Faults that occur are automatically output as an alarm if the encoder is parameterized as a direct measuring system and does not intervene in the motor control.
33000	33999	DRIVE-CLiQ component encoder 3 Note Faults that occur are automatically output as an alarm if the encoder is parameterized as a direct measuring system and does not intervene in the motor control.
34000	34999	Voltage Sensing Module (VSM)
35000	35199	Terminal Module 54F (TM54F)
35200	35999	Terminal Module 31 (TM31)
36000	36999	DRIVE-CLiQ Hub Module
37000	37999	HF Damping Module

Table 2-6 Number ranges of faults and alarms, continued

of	To	Area
40000	40999	Controller Extension 32 (CX32)
41000	48999	Reserved
49000	49999	SINAMICS GM/SM/GL
50000	50499	Communication Board (COMM BOARD)
50500	59999	OEM Siemens
60000	65535	SINAMICS DC MASTER (closed-loop DC current control)

2.2 List of parameters

Product: SINAMICS G120C, Version: 4705500, Language: eng
Objects: G120C_CAN, G120C_DP, G120C_PN, G120C_USS

r0002

Drive operating display / Drv op_display

Access level: 2	Calculated: -	Data type: Integer16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	200	-

Description:

Operating display for the drive.

Value:

0: Operation - everything enabled
10: Operation - set "enable setpoint" = "1"
12: Operation - RFG frozen, set "RFG start" = "1"
13: Operation - set "enable RFG" = "1"
14: Operation - MotID, excit. running
15: Operation - open brake (p1215)
16: Operation - withdraw braking with OFF1 using "ON/OFF1" = "1"
17: Operation - braking with OFF3 can only be interrupted with OFF2
18: Operation - brake on fault, remove fault, acknowledge
19: Operation - DC braking active (p1230, p1231)
21: Ready for operation - set "Operation enable" = "1" (p0852)
22: Ready for operation - de-magnetizing running (p0347)
31: Ready for switching on - set "ON/OFF1" = "0/1" (p0840)
35: Switching on inhibited - carry out first commissioning (p0010)
41: Switching on inhibited - set "ON/OFF1" = "0" (p0840)
42: Switching on inhibited - set "OC/OFF2" = "1" (p0844, p0845)
43: Switching on inhibited - set "OC/OFF3" = "1" (p0848, p0849)
44: Switching on inhibited - supply STO terminal w/ 24 V (hardware)
45: Switching on inhibited - rectify fault, acknowledge fault, STO
46: Switching on inhibited - exit comm mode (p0010)
70: Initialization
200: Wait for booting/partial booting

Dependency:

Refer to: r0046

Notice:

For several missing enable signals, the corresponding value with the highest number is displayed.

Note:

OC: Operating condition
RFG: Ramp-function generator
COMM: Commissioning
MotID: Motor data identification

p0003

Access level / Acc_level

Access level: 1	Calculated: -	Data type: Integer16
Can be changed: C, U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
3	4	3

Description:

Sets the access level to read and write parameters.

Value:

3: Expert
4: Service

Note:

A higher set access level also includes the lower one.
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).

p0010	Drive commissioning parameter filter / Drv comm. par_filt		
	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: C(1), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2800, 2818
	Min	Max	Factory setting
	0	95	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.		
Value:	0: Ready 1: Quick commissioning 2: Power unit commissioning 3: Motor commissioning 5: Technological application/units 15: Data sets 29: Only Siemens int 30: Parameter reset 39: Only Siemens int 49: Only Siemens int 95: Safety Integrated commissioning		
Dependency:	Refer to: r3996		
Notice:	When the parameter is reset to a value of 0, short-term communication interruptions may occur.		
Note:	The drive can only be powered up outside the drive commissioning (inverter enable). To realize this, this parameter must be set to 0. By setting p3900 to a value other than 0, the quick commissioning is completed, and this parameter is automatically reset to 0. Procedure for "Reset parameter": Set p0010 to 30 and p0970 to 1. Once the Control Unit has been booted up for the first time, the motor parameters suitable for the power unit have been defined, and the control parameters have been calculated accordingly, p0010 is automatically reset to 0. p0010 = 3 is used for the subsequent commissioning of additional drive data sets (creating data sets: see p0010 = 15). p0010 = 29, 39, 49: Only for internal Siemens use!		
p0015	Macro drive unit / Macro drv unit		
G120C_CAN	Access level: 1	Calculated: -	Data type: Unsigned32
G120C_USS	Can be changed: C, C(1)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	999999	12
Description:	Runs the corresponding macro files.		
Notice:	After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. When executing a specific macro, the corresponding programmed settings are made and become active.		
Note:	Macros available as standard are described in the technical documentation of the particular product.		
p0015	Macro drive unit / Macro drv unit		
G120C_DP	Access level: 1	Calculated: -	Data type: Unsigned32
G120C_PN	Can be changed: C, C(1)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	999999	7
Description:	Runs the corresponding macro files.		
Notice:	After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. When executing a specific macro, the corresponding programmed settings are made and become active.		
Note:	Macros available as standard are described in the technical documentation of the particular product.		

r0018	Control Unit firmware version / CU FW version		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	-
Description:	Displays the firmware version of the Control Unit.		
Dependency:	Refer to: r0197, r0198		
Note:	Example: The value 1010100 should be interpreted as V01.01.01.00.		
r0020	Speed setpoint smoothed / n_set smth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 5020, 6799
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the currently 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 a process quantity and may only be used as a display quantity. The speed setpoint is available smoothed (r0020) and unsmoothed (r0060).		
r0021	CO: Actual speed smoothed / n_act smooth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 6799
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Display of the calculated and smoothed rotor speed. Frequency components from the slip compensation (for induction motors) are not included.		
Dependency:	Refer to: r0022, r0063		
Note:	Smoothing time constant = 100 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The speed actual value is available smoothed (r0021, r0022) and unsmoothed (r0063).		
r0022	Speed actual value rpm smoothed / n_act rpm smooth		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6799
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Display of the calculated and smoothed rotor speed. Frequency components from the slip compensation (for induction motors) are not included. r0022 is identical to r0021, however, it always has units of rpm and contrary to r0021 cannot be changed over.		
Dependency:	Refer to: r0021, r0063		
Note:	Smoothing time constant = 100 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The speed actual value is available smoothed (r0021, r0022) and unsmoothed (r0063).		

r0024	Output frequency smoothed / f_outp smooth		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6799
	Min	Max	Factory setting
	- [Hz]	- [Hz]	- [Hz]
	Description: Display of the smoothed output frequency. Frequency components from the slip compensation (for induction motors) are included.		
	Dependency: Refer to: r0066		
	Note: Smoothing time constant = 100 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The output frequency is available smoothed (r0024) and unsmoothed (r0066).		
r0025	CO: Output voltage smoothed / U_outp smooth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 5730, 6300, 6799
	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
	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 a process quantity and may only be used as a display quantity. The output voltage is available smoothed (r0025) and unsmoothed (r0072).		
r0026	CO: DC link voltage smoothed / Vdc smooth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6799
	Min	Max	Factory setting
	- [V]	- [V]	- [V]
	Description: Displays the smoothed actual value of the DC link voltage.		
	Dependency: Refer to: r0070		
	Notice: When measuring a DC link voltage < 200 V, for the Power Module a valid measured value is not supplied. In this case, when an external 24 V power supply is connected, a value of approx. 24 V is displayed in the display parameter.		
	Note: Smoothing time constant = 100 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The DC link voltage is available smoothed (r0026) and unsmoothed (r0070). r0026 sets itself to the lower value of the pulsating DC link voltage.		
r0027	CO: Absolute actual current smoothed / I_act abs val smth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 5730, 6799, 8850, 8950
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
	Description: Displays the smoothed absolute actual current value.		
	Dependency: Refer to: r0068		
	Notice: This smoothed signal is not suitable for diagnostics or evaluation of dynamic operations. In this case, the unsmoothed value should be used.		

2 Parameters

2.2 List of parameters

Note: Smoothing time constant = 300 ms
The signal is not suitable as a process quantity and may only be used as a display quantity.
The absolute current actual value is available smoothed (r0027) and unsmoothed (r0068).

r0028	Modulation depth smoothed / Mod_depth smth		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 5730, 6799, 8950
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Displays the smoothed actual value of the modulation depth.		
Dependency:	Refer to: r0074		
Note:	Smoothing time constant = 100 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The modulation depth is available smoothed (r0028) and unsmoothed (r0074).		

r0029	Current actual value field-generating smoothed / Id_act smooth		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6799
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the smoothed field-generating actual current.		
Dependency:	Refer to: r0076		
Note:	Smoothing time constant = 300 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The field-generating current actual value is available smoothed (r0029) and unsmoothed (r0076).		

r0030	Current actual value torque-generating smoothed / Iq_act smooth		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6799
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the smoothed torque-generating actual current.		
Dependency:	Refer to: r0078		
Note:	Smoothing time constant = 300 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The torque-generating current actual value is available smoothed (r0030) and unsmoothed (r0078).		

r0031	Actual torque smoothed / M_act smooth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 5730, 6799
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Displays the smoothed torque actual value.		
Dependency:	Refer to: r0080		
Note:	Smoothing time constant = 100 ms The signal is not suitable as a process quantity and may only be used as a display quantity. The torque actual value is available smoothed (r0031) and unsmoothed (r0080).		

r0032	CO: Active power actual value smoothed / P_actv_act smth		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: r2004	Dyn. index: -
	Unit group: 14_10	Unit selection: p0505	Func. diagram: 5730, 6799, 8750, 8850, 8950
	Min	Max	Factory setting
	- [kW]	- [kW]	- [kW]
	Description: Displays the smoothed actual value of the active power.		
	Dependency: Refer to: r0082		
	Notice: This smoothed signal is not suitable for diagnostics or evaluation of dynamic operations. In this case, the unsmoothed value should be used.		
	Note: Power delivered at the motor shaft.		
	The active power is available smoothed (r0032 with 100 ms) and unsmoothed (r0082).		
r0033	Torque utilization smoothed / M_util smooth		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8012
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
	Description: Displays the smoothed torque utilization as a percentage.		
	Dependency: This parameter is only available for vector control. For U/f control r0033 = 0 %.		
	Note: Smoothing time constant = 100 ms		
	The signal is not suitable as a process quantity and may only be used as a display quantity.		
	The torque utilization is available smoothed (r0033) and unsmoothed (r0081).		
	For M_set total (r0079) > 0, the following applies:		
	- Required torque = M_set total		
	- Actual torque limit = M_max upper effective (r1538)		
	For M_set total (r0079) ≤ 0, the following applies:		
	- Required torque = - M_set total		
	- Actual torque limit = - 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 %		
r0034	CO: Motor utilization thermal / Mot_util therm		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8017
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
	Description: Displays the motor utilization from motor temperature model 1 (I2t).		
	Dependency: The thermal motor utilization is only determined for permanent-magnet synchronous motors when the motor temperature model 1 (I2t) is activated.		
	The following applies:		
	- r0034 = (motor model temperature - 40 K) / (p0605 - 40 K) * 100 %.		
	A motor utilization of 100% is displayed without temperature sensor (r0034 = 100 %), when the following conditions are fulfilled:		
	- the current corresponds to the rated current (p0305).		
	- the ambient temperature is 40 °C (p0625 = 40 °C).		
	Refer to: p0611, p0612, p0615		
	Notice: After the drive is switched on, the system starts to determine the motor temperature with an assumed model value.		
	This means that the value for the motor utilization is only valid after a stabilization time.		

2 Parameters

2.2 List of parameters

Note: Smoothing time constant = 100 ms
The signal is not suitable as a process quantity and may only be used as a display quantity.
For r0034 = -200.0 %, the following applies:
The value is invalid (e.g. the motor temperature model is not activated or has been incorrectly parameterized).

r0035	CO: Motor temperature / Mot temp		
	Access level: 2 Can be changed: - Unit group: 21_1 Min - [°C]	Calculated: - Scaling: p2006 Unit selection: p0505 Max - [°C]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 8016, 8017 Factory setting - [°C]
Description:	Display and connector output for the actual temperature in the motor.		
Note:	For r0035 not equal to -200.0 °C, the following applies: - this temperature display is valid. - a KTY sensor is connected. - the thermal model for the induction motor is activated (p0612 bit 1 = 1 and temperature sensor de-activated: p0600 = 0 or p0601 = 0). For r0035 equal to -200.0 °C, the following applies: - this temperature display is not valid (temperature sensor error). - A PTC sensor or bimetallic NC contact is connected. - the temperature sensor of the synchronous motor is de-activated (p0600 = 0 or p0601 = 0).		
r0036	CO: Power unit overload I2t / PU overload I2t		
	Access level: 3 Can be changed: - Unit group: - Min - [%]	Calculated: - Scaling: PERCENT Unit selection: - Max - [%]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 8019 Factory setting - [%]
Description:	Displays the power unit overload determined using the I2t calculation. 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.). If the I2t reference current of the power unit is not exceeded, then an overload (0 %) is not displayed. In the other case, the degree of thermal overload is calculated, whereby 100% results in a trip.		
Dependency:	Refer to: p0290 Refer to: F30005		
r0037[0...19]	CO: Power unit temperatures / PU temperatures		
	Access level: 4 Can be changed: - Unit group: 21_1 Min - [°C]	Calculated: - Scaling: p2006 Unit selection: p0505 Max - [°C]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 8019 Factory setting - [°C]
Description:	Display and connector output for the temperature in the power unit.		

Index:	[0] = Inverter maximum value
	[1] = Depletion layer maximum value
	[2] = Rectifier maximum value
	[3] = Air intake
	[4] = Interior of power unit
	[5] = Inverter 1
	[6] = Inverter 2
	[7...10] = Reserved
	[11] = Rectifier 1
	[12] = Reserved
	[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] = Reserved

Notice: Only for internal Siemens troubleshooting.

Note: The value of -200 indicates that there is no measuring signal.
r0037[0]: Maximum value of the inverter temperatures (r0037[5...10]).
r0037[1]: Maximum value of the depletion layer temperatures (r0037[13...18]).
r0037[2]: Maximum value of the rectifier temperatures (r0037[11...12]).
The maximum value is the temperature of the hottest inverter, depletion layer, or rectifier.
r0037[2, 3, 6, 11, 14...18] is only relevant for chassis power units.
In the case of a fault, the particular shutdown threshold depends on the power unit, and cannot be read out.

r0038 Power factor smoothed / Cos phi smooth

Access level: 4	Calculated: -	Data type: FloatingPoint32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 6799, 8850, 8950
Min	Max	Factory setting
-	-	-

Description: Displays the smoothed actual power factor. This refers to the electrical power of the basic fundamental signals at the converter output terminals.

Notice: For infeed units, the following applies:

For active powers < 25 % of the rated power, this does not provide any useful information.

Note: Smoothing time constant = 300 ms

The signal is not suitable as a process quantity and may only be used as a display quantity.

r0039[0...2] CO: Energy display / Energy displ

Access level: 2	Calculated: -	Data type: FloatingPoint32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
- [kWh]	- [kWh]	- [kWh]

Description: Displays the energy values at the output terminals of the power unit.

Index: [0] = Energy balance (sum)
[1] = Energy drawn
[2] = Energy fed back

Dependency: Refer to: p0040

Note: Re index 0:
Difference between the energy drawn and energy that is fed back.

p0040	Reset energy consumption display / Energy usage reset		
	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	0	1	0
	Setting to reset the display in r0039 and r0041.		
	Procedure: Set p0040 = 0 --> 1 The displays are reset and the parameter is automatically set to zero.		
Dependency:	Refer to: r0039		
Note:	When the energy usage display is reset, the process energy display r0042 is also reset.		
r0041	Energy consumption saved / Energy cons saved		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	- [kWh]	- [kWh]	- [kWh]
	Displays the saved energy referred to 100 operating hours.		
	Refer to: p0040		
Dependency:	This display is used for a fluid-flow machine.		
Note:	The flow characteristic is entered into p3320 ... p3329. For an operating time of below 100 hours, the display is interpolated up to 100 hours.		
r0042[0...2]	CO: Process energy display / Process energy		
	Access level: 2	Calculated: -	Data type: Integer32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	- [Wh]	- [Wh]	- [Wh]
	Displays the energy values at the output terminals of the power unit.		
	Index: [0] = Energy balance (sum) [1] = Energy drawn [2] = Energy fed back		
Dependency:	Refer to: p0043		
Note:	The signal can be displayed as process variable (scaling: 1 = 1 Wh). This is enabled in p0043. The display is also reset with p0040 = 1. If an enable is present in r0043 when the Control Unit powers up, then the value from r0039 is transferred into r0042. As r0039 serves as a reference signal for r0042, due to format reasons, the process energy display can only process values of r0039 up to 2147483 kWh. Further, r0039 should also be reset.		
p0043	BI: Enable energy usage display / Enab energy usage		
	Access level: 2	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	-	-	0
	Setting to enable and reset the process energy display in r0042.		
	The energy display starts when a one is connected to the Bico input.		
Dependency:	Refer to: r0042		

p0045				
Display values smoothing time constant / Disp_val T_smooth				
Access level: 3		Calculated: -	Data type: FloatingPoint32	
Can be changed: U, T		Scaling: -	Dyn. index: -	
Unit group: -		Unit selection: -	Func. diagram: 6714, 8012	
Min		Max	Factory setting	
0.00 [ms]		10000.00 [ms]	4.00 [ms]	
Description:	Sets the smoothing time constant for the following display values: r0063[1], r0068[1], r0080[1], r0082[1].			

r0046.0...31					
CO/BO: Missing enable sig / Missing enable sig					
Access level: 1		Calculated: -	Data type: Unsigned32		
Can be changed: -		Scaling: -	Dyn. index: -		
Unit group: -		Unit selection: -	Func. diagram: 2634		
Min		Max	Factory setting		
-		-	-		
Description:	Display and BICO output for missing enable signals that are preventing the closed-loop drive control from being commissioned.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	OFF1 enable missing	Yes	No	7954
	01	OFF2 enable missing	Yes	No	-
	02	OFF3 enable missing	Yes	No	-
	03	Operation enable missing	Yes	No	-
	04	DC braking enable missing	Yes	No	-
	08	Safety 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	DC braking internal enable missing	Yes	No	-
	21	Power unit enable missing	Yes	No	-
	26	Drive inactive or not operational	Yes	No	-
	27	De-magnetizing not completed	Yes	No	-
	28	Brake open 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 "switching on inhibited".				
	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 (DC brake active) when:				
	- the signal source in p1230 has a 1 signal.				
	Bit 08 = 1 (enable signal missing), if:				
	- safety functions have been enabled and STO is active.				
	- STO is selected via onboard terminals or PROFIsafe.				
	- a safety-relevant signal is present with STOP A response.				
	- the "STO via terminals at the Power Module" function is selected.				

- 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.
 - 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 enabled if the fault is removed and was acknowledged and the "switching on inhibited" withdrawn with OFF1 = 0.
- Bit 17 = 1 (enable signal missing), if:
- commissioning mode is selected (p0010 > 0).
 - there is an OFF2 fault response.
 - the drive is not operational.
- Bit 18 = 1 (enable signal missing), if:
- OFF3 has still not been completed or an OFF3 fault response is present.
- Bit 19 = 1 (internal pulse enable missing), if:
- sequence control does not have a finished message.
- Bit 20 = 1 (internal DC brake active), if:
- the drive is not in the state "Operation" or in "OFF1/3".
 - the internal pulse enable is missing (r0046.19 = 0).
- Bit 21 = 1 (enable signal missing), if:
- the power unit does not issue an enable signal (e.g. because DC link voltage is too low).
 - the holding brake opening time (p1216) has still not expired.
 - The hibernation mode is active.
- Bit 26 = 1 (enable signal missing), if:
- the drive is not operational.
- Bit 27 = 1 (enable signal missing), if:
- de-magnetization not completed.
- Bit 28 = 1 (enable signal missing), if:
- the holding brake is closed or has still not been opened.
- Bit 30 = 1 (speed controller inhibited), if one of the following reasons is present:
- the pole position identification is active.
 - motor data identification is active (only certain steps).
- Bit 31 = 1 (enable signal missing), if:
- the speed setpoint from jog 1 or 2 is entered.

r0047 Motor data identification and speed controller optimization / MotID and n_opt

Access level: 1	Calculated: -	Data type: Integer16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	300	-

Description: Displays the actual status for the motor data identification (stationary measurement) and the speed controller optimization (rotating measurement).

Value:

- 0: No measurement
- 115: Measurement q leakage inductance (part 2)
- 120: Speed controller optimization (vibration test)
- 140: Calculate speed controller setting
- 150: Measurement moment of inertia
- 170: Measurement magnetizing current and saturation characteristic
- 195: Measurement q leakage inductance (part 1)
- 200: Rotating measurement selected
- 220: identification leakage inductance

230: Identification rotor time constant
 240: Identification stator inductance
 250: Identification stator inductance LQLD
 260: Identification circuit
 270: Identification stator resistance
 290: Identification valve lockout time
 300: Stationary measurement selected

r0050.0...1**CO/BO: Command Data Set CDS effective / CDS effective**

Access level: 3	Calculated: -	Data type: Unsigned8
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8560
Min	Max	Factory setting
-	-	-

Description: Displays the effective Command Data Set (CDS).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	CDS eff bit 0	ON	OFF	-
	01	CDS eff bit 1	ON	OFF	-

Dependency: Refer to: p0810, r0836

Note: The Command Data Set selected using a binector input (e.g. p0810) is displayed using r0836.

r0051.0**CO/BO: Drive Data Set DDS effective / DDS effective**

Access level: 3	Calculated: -	Data type: Unsigned8
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8565
Min	Max	Factory setting
-	-	-

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	-

Dependency: Refer to: p0820, r0837

Note: When selecting the motor data identification routine and the rotating measurement, the drive data set changeover is suppressed.

r0052.0...15**CO/BO: Status word 1 / ZSW 1**

Access level: 2	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description: Display and connector output for status word 1.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Rdy for switch on	Yes	No	-
	01	Ready	Yes	No	-
	02	Operation enabled	Yes	No	-
	03	Fault present	Yes	No	-
	04	Coast down active (OFF2)	No	Yes	-
	05	Quick Stop active (OFF3)	No	Yes	-
	06	Switching on inhibited active	Yes	No	-
	07	Alarm present	Yes	No	-
	08	Deviation setpoint/actual speed	No	Yes	-
	09	Control request	Yes	No	-
	10	Maximum speed reached	Yes	No	-
	11	I, M, P limit reached	No	Yes	-
	12	Motor holding brake open	Yes	No	-

2 Parameters

2.2 List of parameters

13	Alarm motor overtemperature	No	Yes	-
14	Motor rotates forwards	Yes	No	-
15	Alarm drive converter overload	No	Yes	-

Note:

Re bit 03:

This signal is inverted if it is interconnected to a digital output.

Re r0052:

The status bits have the following sources:

Bit 00: r0899 Bit 0

Bit 01: r0899 Bit 1

Bit 02: r0899 Bit 2

Bit 03: r2139 Bit 3 (or r1214.10 for p1210 > 0)

Bit 04: r0899 Bit 4

Bit 05: r0899 Bit 5

Bit 06: r0899 Bit 6

Bit 07: r2139 Bit 7

Bit 08: r2197 Bit 7

Bit 09: r0899 Bit 7

Bit 10: r2197 Bit 6

Bit 11: r0056 Bit 13 (negated)

Bit 12: r0899 Bit 12

Bit 13: r2135 Bit 12 (negated)

Bit 14: r2197 Bit 3

Bit 15: r2135 Bit 15 (negated)

r0053.0...11

CO/BO: Status word 2 / ZSW 2

Access level: 2

Calculated: -

Data type: Unsigned16

Can be changed: -

Scaling: -

Dyn. index: -

Unit group: -

Unit selection: -

Func. diagram: -

Min

Max

Factory setting

-

-

-

Description:

Display and BICO output for status word 2.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	DC braking active	Yes	No	-
01	n_act > p1226 (n_standstill)	Yes	No	-
02	n_act > p1080 (n_min)	Yes	No	-
03	I_act >= p2170	Yes	No	-
04	n_act > p2155	Yes	No	-
05	n_act <= p2155	Yes	No	-
06	n_act >= r1119 (n_set)	Yes	No	-
07	Vdc <= p2172	Yes	No	-
08	Vdc > p2172	Yes	No	-
09	Reserved	Yes	No	-
10	Technology controller output at the lower limit	Yes	No	-
11	Technology controller output at the upper limit	Yes	No	-

Notice:

p2081 is used to define the signal sources of the PROFIdrive status word interconnection.

Note:

The following status bits are displayed in r0053:

Bit 00: r1239 Bit 8

Bit 02: r2197 Bit 0 (negated)

Bit 06: r2197 Bit 4

Bit 10: r2349 Bit 10

Bit 11: r2349 Bit 11

r0054.0...15**CO/BO: Control word 1 / STW 1**

Access level: 2	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description:

Displays control word 1.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	ON/OFF1	Yes	No	-
01	OC / OFF2	No	Yes	-
02	OC / OFF3	No	Yes	-
03	Operation enable	Yes	No	-
04	Ramp-function generator enable	Yes	No	-
05	Continue ramp-function generator	Yes	No	-
06	Speed setpoint enable	Yes	No	-
07	Acknowledge fault	Yes	No	-
08	Jog bit 0	Yes	No	3030
09	Jog bit 1	Yes	No	3030
10	Master control by PLC	Yes	No	-
11	Direction reversal (setpoint)	Yes	No	-
13	Motorized potentiometer raise	Yes	No	-
14	Motorized potentiometer lower	Yes	No	-
15	CDS bit 0	Yes	No	-

Note:

The following control bits are displayed in r0054:

Bit 00: r0898 Bit 0

Bit 01: r0898 Bit 1

Bit 02: r0898 Bit 2

Bit 03: r0898 Bit 3

Bit 04: r0898 Bit 4

Bit 05: r0898 Bit 5

Bit 06: r0898 Bit 6

Bit 07: r2138 Bit 7

Bit 08: r0898 Bit 8

Bit 09: r0898 Bit 9

Bit 10: r0898 Bit 10

Bit 11: r1198 Bit 11

Bit 13: r1198 Bit 13

Bit 14: r1198 Bit 14

Bit 15: r0836 Bit 0

r0055.0...15**CO/BO: Supplementary control word / Suppl STW**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2513
Min	Max	Factory setting
-	-	-

Description:

Display and BICO output for supplementary control word.

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	-
04	DDS select. bit 0	Yes	No	-
05	Reserved	Yes	No	-
08	Technology controller enable	Yes	No	-
09	DC braking enable	Yes	No	-
11	Reserved	Yes	No	-

2 Parameters

2.2 List of parameters

12	Reserved	Yes	No	-
13	External fault 1 (F07860)	No	Yes	-
15	CDS bit 1	Yes	No	-

Note: CDS: Command Data Set
The following control bits are displayed in r0055:
Bit 00: r1198.0
Bit 01: r1198.1
Bit 02: r1198.2
Bit 03: r1198.3
Bit 04: r0837.0
Bit 08: r2349.0 (negated)
Bit 09: r1239.11
Bit 13: r2138.13 (negated)
Bit 15: r0836.1

r0056.0...15	CO/BO: Status word, closed-loop control / ZSW cl-loop ctrl				
	Access level: 3		Calculated: -		Data type: Unsigned16
	Can be changed: -		Scaling: -		Dyn. index: -
	Unit group: -		Unit selection: -		Func. diagram: 2526
	Min		Max		Factory setting
	-		-		-
Description:	Display and BICO output for 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 available	Yes	No	-
	03	Soft starting present	Yes	No	-
	04	Magnetizing completed	Yes	No	-
	05	Voltage boost when starting	Active	Inactive	6301
	06	Acceleration voltage	Active	Inactive	6301
	07	Frequency negative	Yes	No	-
	08	Field weakening active	Yes	No	-
	09	Voltage limit active	Yes	No	6714
	10	Slip limit active	Yes	No	6310
	11	Frequency limit active	Yes	No	-
	12	Current limiting controller voltage output active	Yes	No	-
	13	Current/torque limiting	Active	Inactive	6060
	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.		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 2701, 6030, 6799
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
	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).		

r0062	CO: Speed setpoint after the filter / n_set after filter		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 6020, 6030, 6031
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Display and connector output for the speed setpoint after the setpoint filters.		
r0063[0...2]	CO: Speed actual value / n_act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 6020, 6799
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the speed actual value. Frequency components from the slip compensation (for induction motors) are not included.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045 [2] = Calculated from f_set - f_slip (unsmoothed)		
Dependency:	Refer to: r0021, r0022		
Note:	The speed actual value r0063[0] – smoothed with p0045 – is additionally displayed in r0063[1]. r0063[1] can be used as process variable for the appropriate smoothing time constant p0045. The speed (r0063[2]) calculated from the output frequency and slip can only be compared with the speed actual value (r0063[0]) in the steady-state. For U/f control, the mechanical speed calculated from the output frequency and the slip is shown in r0063[2] even if slip compensation is deactivated.		
r0064	CO: Speed controller system deviation / n_ctrl system dev		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 6040
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the actual system deviation of the speed controller.		
r0065	Slip frequency / f_slip		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 2_1	Unit selection: p0505	Func. diagram: 6310, 6700, 6727, 6730, 6732
	Min	Max	Factory setting
	- [Hz]	- [Hz]	- [Hz]
Description:	Displays the slip frequency for induction motors (ASM).		
r0066	CO: Output frequency / f_outp		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 2_1	Unit selection: p0505	Func. diagram: 6300, 6700, 6730, 6731, 6799
	Min	Max	Factory setting
	- [Hz]	- [Hz]	- [Hz]
Description:	Display and connector output for the unsmoothed output frequency of the power unit. Frequency components from the slip compensation (induction motor) are included.		

2 Parameters

2.2 List of parameters

Dependency: Refer to: r0024
Note: The output frequency is available smoothed (r0024) and unsmoothed (r0066).

r0067	CO: Output current maximum / I_outp max		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6300, 6640, 6724
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]

Description: Display and connector output for the maximum output current of the power unit.
Dependency: The maximum output current is determined by the parameterized current limit and the motor and converter thermal protection.
Refer to: p0290, p0640

r0068[0...1]	CO: Absolute current actual value / I_act abs val		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6300, 6714, 6799, 7017, 8017, 8018, 8019
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]

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: 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...8]	CO: Phase current actual value / I_phase act val		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_5	Unit selection: p0505	Func. diagram: 6730, 6731
	Min	Max	Factory setting
	- [A]	- [A]	- [A]

Description: Display and connector output for 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
[7] = Alpha component
[8] = Beta component
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 val		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_2	Unit selection: p0505	Func. diagram: 6723, 6724, 6730, 6731, 6799
	Min - [V]	Max - [V]	Factory setting - [V]
Description:	Display and connector output for the measured actual value of the DC link voltage.		
Dependency:	Refer to: r0026		
Notice:	When measuring a DC link voltage < 200 V, for the Power Module a valid measured value is not supplied. In this case, when an external 24 V power supply is connected, a value of approx. 24 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		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 6301, 6640, 6700, 6722, 6723, 6724, 6725, 6727
	Min - [Vrms]	Max - [Vrms]	Factory setting - [Vrms]
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: Output voltage / U_output		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 5700, 6730, 6731, 6799
	Min - [Vrms]	Max - [Vrms]	Factory setting - [Vrms]
Description:	Display and connector output for the actual output voltage of the power unit.		
Dependency:	Refer to: r0025		
Note:	The output voltage is available smoothed (r0025) and unsmoothed (r0072).		
r0073	Maximum modulation depth / Modulat_depth max		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6723, 6724
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Displays the maximum modulation depth.		
Dependency:	Refer to: p1803		

r0074	CO: Modulat_depth / Mod_depth		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 5730, 6730, 6731, 6799, 8940, 8950
	Min - [%]	Max - [%]	Factory setting - [%]
Description:	Display and connector output for 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: $(r0074 \times r0070) / (\sqrt{2} \times 100 \%)$. The modulation depth is available smoothed (r0028) and unsmoothed (r0074).		
r0075	CO: Current setpoint field-generating / Id_set		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6700, 6714, 6725
	Min - [Arms]	Max - [Arms]	Factory setting - [Arms]
Description:	Display and connector output for the field-generating current setpoint (Id_set).		
Note:	This value is irrelevant for the U/f control mode.		
r0076	CO: Current actual value field-generating / Id_act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 5700, 5714, 5730, 6700, 6714, 6799
	Min - [Arms]	Max - [Arms]	Factory setting - [Arms]
Description:	Display and connector output for the field-generating current actual voltage (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: Current setpoint torque-generating / Iq_set		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6700, 6710
	Min - [Arms]	Max - [Arms]	Factory setting - [Arms]
Description:	Display and connector output for the torque-generating current setpoint.		
Note:	This value is irrelevant for the U/f control mode.		

r0078	CO: Current actual value torque-generating / Iq_act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6310, 6700, 6714, 6799
	Min - [Arms]	Max - [Arms]	Factory setting - [Arms]
Description:	Display and connector output for the torque-generating current actual voltage (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).		
r0079	CO: Torque setpoint / M_set		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6020, 6060, 6710
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Display and connector output for the torque setpoint at the output of the speed controller.		
r0080[0...1]	CO: Torque actual value / M_act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6714, 6799
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Display and connector output for actual torque value.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045		
Dependency:	Refer to: r0031, p0045		
Note:	The value is available smoothed (r0031 with 100 ms, r0080[1] with p0045) and unsmoothed (r0080[0]).		
r0081	CO: Torque utilization / M_Utilization		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8012
	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:	This parameter is only available for vector control. For U/f control r0081 = 0 %. Refer to: r0033		
Note:	The torque utilization is available smoothed (r0033) and unsmoothed (r0081). The torque utilization is obtained from the required torque referred to the torque limit as follows: - Positive torque: $r0081 = (r0079 / r1538) * 100 \%$ - Negative torque: $r0081 = (-r0079 / -r1539) * 100 \%$		

r0082[0...2]	CO: Active power actual value / P_act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: r2004	Dyn. index: -
	Unit group: 14_5	Unit selection: p0505	Func. diagram: 6714, 6799
	Min	Max	Factory setting
	- [kW]	- [kW]	- [kW]
Description:	Displays the instantaneous active power.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045 [2] = Electric power		
Dependency:	Refer to: r0032		
Note:	The mechanical active power is available smoothed (r0032 with 100 ms, r0082[1] with p0045) and unsmoothed (r0082[0]).		
r0083	CO: Flux setpoint / Flex setp		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 5722
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Displays the flux setpoint.		
r0084[0...1]	CO: Flux actual value / Flux act val		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6730, 6731
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Displays the flux actual value.		
Index:	[0] = Unsmoothed [1] = Smoothed		
r0087	CO: Actual power factor / Cos phi act		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual active power factor. This value refers to the electrical power of the basic fundamental signals at the output terminals of the converter.		
r0089[0...2]	Actual phase voltage / U_phase act val		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_3	Unit selection: p0505	Func. diagram: 6719
	Min	Max	Factory setting
	- [V]	- [V]	- [V]
Description:	Displays the actual phase voltage.		
Index:	[0] = Phase U [1] = Phase V [2] = Phase W		
Note:	The values are determined from the transistor power-on duration.		

p0096	Application class / Appl_class		
	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: C(1)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6019
	Min	Max	Factory setting
	0	2	0
	Description: Setting the commissioning and control view for various application classes.		
	Value: 0: Expert 1: Standard drive control 2: Dynamic drive control		
	Dependency: The parameter is preset when commissioning the system for the first time and for the factory setting, depending on the power unit that is connected. Depending on the setting, the ability to see control parameters is restricted depending on the particular application. For p0096 > 0, the motor data identification is preset (p1900 = 12). With this setting, after the motor data identification, the system immediately goes into operation. p0096 = 1: motor type (p0300) synchronous or reluctance motor not possible.		
	Note: When changing p0096 to 1 or 2, when completing commissioning, fast parameterization should be executed (p3900 > 0). Depending on the setting, after quick commissioning and/or automatic parameterization, the procedure for motor data identification as well as the setting of the operating mode and parameterization of the closed-loop control must be appropriately adapted.		
p0100	IEC/NEMA mot stds / IEC/NEMA mot stds		
	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: C(1)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2	0
	Description: Defines whether the motor and drive converter power settings (e.g. rated motor power, p0307) are expressed in [kW] or [hp]. Depending on the selection, the rated motor frequency (p0310) is either set to 50 Hz or 60 Hz. For p0100 = 0, 2, the following applies: The power factor (p0308) should be parameterized. For p0100 = 1, the following applies: The efficiency (p0309) should be parameterized.		
	Value: 0: IEC-Motor (50 Hz, SI units) 1: NEMA motor (60 Hz, US units) 2: NEMA motor (60 Hz, SI units)		
	Dependency: If p0100 is changed, all of the rated motor parameters are reset. Only then are possible unit changeovers made. The units of all motor parameters are changed that are involved with the selection IEC or NEMA. Refer to: r0206, p0210, p0300, p0304, p0305, p0307, p0308, p0309, p0310, p0311, p0314, p0320, p0322, p0323, p0335, p1800		
	Note: The parameter value is not reset when the factory setting is restored (p0010 = 30, p0970).		
p0124[0...n]	CU detection via LED / CU detection LED		
	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: PDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
	Description: Identification of the Control Unit using an LED.		
	Note: While p0124 = 1, the READY LED flashes green/orange or red/orange with 2 Hz at the appropriate Control Unit.		

p0133[0...n]	Motor configuration / Motor config				
	Access level: 2		Calculated: -	Data type: Unsigned16	
	Can be changed: C(1, 3)		Scaling: -	Dyn. index: MDS	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Configuration of the motor when commissioning the motor.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Motor connection type	Delta	Star	-
	01	Motor 87 Hz operation	Yes	No	-
Dependency:	For standard induction motors (p0301 > 10000), bit 0 is automatically preassigned the connection type of the selected data set. For p0100 > 0 (60 Hz rated motor frequency), it is not possible to select bit 1. Refer to: p0304, p0305, p1082				
Note:	Re bit 00: When changing the bits, the rated motor voltage p0304 and the rated motor current p0305 are automatically converted to the selected connection type (star/delta). Re bit 01: 87 Hz operation is only possible in the delta connection type. When selected, the maximum speed p1082 is automatically preassigned for a maximum output frequency of 87 Hz.				

p0170	Number of Command Data Sets (CDS) / CDS count				
	Access level: 2		Calculated: -	Data type: Unsigned8	
	Can be changed: C(15)		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 8560	
	Min		Max	Factory setting	
	2		2	2	
Description:	Sets the number of Command Data Sets (CDS).				
Dependency:	Refer to: p0010, r3996				
Notice:	When the data sets are created, short-term communication interruptions may occur.				
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				
	Access level: 3		Calculated: -	Data type: Unsigned8	
	Can be changed: C(15)		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 8565	
	Min		Max	Factory setting	
	1		2	1	
Description:	Sets the number of Drive Data Sets (DDS).				
Dependency:	Refer to: p0010, r3996				
Notice:	When the data sets are created, short-term communication interruptions may occur.				

r0197[0...1]	Bootloader version / Bootloader vers				
	Access level: 4		Calculated: -	Data type: Unsigned32	
	Can be changed: -		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min		Max	Factory setting	
	-		-	-	
Description:	Displays the bootloader version. Index 0: Displays the bootloader version.				

Index 1:
Displays the bootloader version 3 (for CU320-2 and CU310-2)
Value 0 means that boot loader 3 is not available.

Dependency: Refer to: r0018, r0198

Note: Example:
The value 1010100 should be interpreted as V01.01.01.00.

r0198[0...2] BIOS/EEPROM data version / BIOS/EEPROM vers

Access level: 4	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description: Displays the BIOS and EEPROM data version.
r0198[0]: BIOS version
r0198[1]: EEPROM data version EEPROM 0
r0198[2]: EEPROM data version EEPROM 1

Dependency: Refer to: r0018, r0197

Note: Example:
The value 1010100 should be interpreted as V01.01.01.00.

p0201[0...n] Power unit code number / PU code no

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: C(2)	Scaling: -	Dyn. index: PDS
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	65535	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).
When the code number is changed, the connection voltage (p0210) is checked and, if necessary, adjusted.

r0204[0...n] Power unit hardware properties / PU HW property

Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: PDS
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description: Displays the properties supported by the power unit hardware.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	RFI filter available	Yes	No	-
	07	F3E regenerative feedback into the line supply	Yes	No	-
	08	Internal Braking Module	Yes	No	-
	12	Safe Brake Control (SBC) supported	No	Yes	-
	13	Safety Integrated supported	Yes	No	-
	14	Internal LC output filter	Yes	No	-
	15	Line voltage	1-phase	3-phase	-

p0205	Power unit application / PU application		
	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: C(1, 2)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	7	0
Description:	The duty cycles can be overloaded provided that the drive converter is operated with its base load current before and after the overload. This is based on a load duty cycle of 300 s.		
Value:	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 internal use) 7: S6 duty cycle (for internal use)		
Dependency:	Refer to: r3996		
Notice:	The parameter value is not reset when the factory setting is restored (see p0010 = 30, p0970). When the power unit use is changed, short-term communication interruptions may occur.		
Note:	When the parameter is changed, all of the motor parameters (p0305 ... p0311), the technological application (p0500) and the control mode (p1300) 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.		
r0206[0...4]	Rated power unit power / PU P_{rated}		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: 14_6	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	- [kW]	- [kW]	- [kW]
Description:	Displays the rated power unit power for various load duty cycles.		
Index:	[0] = Rated value [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 cont duty cyc [4] = S6 load duty cycle		
Dependency:	IECdrives (p0100 = 0): Units kW NEMA drives (p0100 = 1): Units hp Refer to: p0100, p0205		
r0207[0...4]	Rated power unit current / PU PI_{rated}		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8019
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the rated power unit power for various load duty cycles.		
Index:	[0] = Rated value [1] = Load duty cycle with low overload [2] = Load duty cycle with high overload [3] = S1 cont duty cyc [4] = S6 load duty cycle		
Dependency:	Refer to: p0205		

r0208	Rated power unit line supply voltage / PU U_{rated}		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
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 %		
<hr/>			
r0209[0...4]	Power unit maximum current / PU I_{max}		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8750, 8850, 8950
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the maximum output current of the power unit.		
Index:	[0] = Catalog [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		
<hr/>			
p0210	Drive unit line supply voltage / V_{connect}		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: C(2), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1 [V]	63000 [V]	400 [V]
Description:	Sets the drive unit supply voltage (rms value of the phase-to-phase line supply voltage).		
Dependency:	Set p1254, p1294 (automatic detection of the Vdc switch-on levels) = 0. The switch-in thresholds of the Vdc_max controller (r1242, r1282) are then directly determined using p0210.		
Notice:	If, in the switched-off state (pulse inhibit), the 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 the next time the system is switched on. In this case, an appropriate alarm A07401 is output.		
Note:	Setting ranges for p0210 as a function of the rated power unit voltage: U _{rated} = 230 V: - p0210 = 200 ... 240 V U _{rated} = 400 V: - p0210 = 380 ... 480 V U _{rated} = 690 V: - p0210 = 660 ... 690 V		
<hr/>			
p0219	Braking resistor braking power / R_{brake} P_{brake}		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 2), T	Scaling: -	Dyn. index: -
	Unit group: 14_6	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	0.00 [kW]	20000.00 [kW]	0.00 [kW]
Description:	Sets the braking power of the connected braking resistor.		
Dependency:	Refer to: p1127, p1240, p1280, p1531		

Note: When setting a value for the braking power, the following calculations are made:

- p1240, p1280: Vdc_max control is deactivated.
- p1531 = - p0219: the power limit when generating is set (limited to - p1530).
- The minimum ramp-down time is calculated (p1127) as a function of p0341, p0342 and p1082 (not for vector control with speed encoder).

If the parameter is reset again to zero, then the Vdc_max controller is reactivated and the power limit as well as the ramp-down time are recalculated.

p0230 Drive filter type motor side / Drv filt type mot			
Access level: 1		Calculated: -	Data type: Integer16
Can be changed: C(1, 2)		Scaling: -	Dyn. index: -
Unit group: -		Unit selection: -	Func. diagram: -
Min		Max	Factory setting
0		4	0
Description:	Sets the type of the filter at the motor side.		
Value:	0: No filter 1: Motor reactor 2: dv/dt filter 3: Sine-wave filter Siemens 4: Sine-wave 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 sine-wave 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 sine-wave filter and also the user must check whether they are permitted. --> p0233 (power unit, motor reactor) = filter inductance --> p0234 (power unit sine-wave 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:	The parameter cannot be changed if the power unit (e.g. PM260) is equipped with an internal sine-wave filter. For sine-wave filters, the test pulse evaluation to detect short-circuits is always deactivated. if a filter type cannot be selected, then this filter type is not permitted for the Motor Module. p0230 = 1: Power units with output reactor are limited to output frequencies of 150 Hz. p0230 = 3: Power units with sine-wave filter are limited to output frequencies of 200 Hz.		


p0233	Power unit motor reactor / PU mot reactor		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(2), U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [mH]	1000.000 [mH]	0.000 [mH]
	Description: Enter the inductance of a filter connected at the power unit output.		
	Dependency: This parameter is automatically pre-set when you select a filter via p0230 if a SIEMENS filter is defined for the power unit.		
	Refer to: p0230		
	Note: When exiting the quick commissioning using p3900 = 1, the parameter value is set to the value of the defined SIEMENS filter or to zero. For this reason, the parameter value of a third-party filter only has to be entered outside the commissioning phase (p0010 = 0) and then the controller calculation (p0340 = 3) is carried out.		
	The parameter cannot be changed if the power unit has an internal sine-wave filter.		
p0234	Power unit sine-wave filter capacitance / PU sine filter C		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(2), U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [µF]	1000.000 [µF]	0.000 [µF]
	Description: Enters the capacitance of a sine-wave filter connected at the power unit output.		
	Dependency: This parameter is automatically pre-set when you select a filter via p0230 if a SIEMENS filter is defined for the power unit.		
	Refer to: p0230		
	Note: The parameter value includes the sum of all of the capacitances of a phase connected in series (phase - ground).		
	When exiting the quick commissioning using p3900 = 1, the parameter value is set to the value of the defined SIEMENS filter or to zero. For this reason, the parameter value of a third-party filter only has to be entered outside the commissioning phase (p0010 = 0).		
	The parameter cannot be changed if the power unit has an internal sine-wave filter.		
r0238	Internal power unit resistance / PU R internal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [ohm]	- [ohm]	- [ohm]
	Description: Displays the internal resistance of the power unit (IGBT and line resistance).		
p0287[0...1]	Ground fault monitoring thresholds / Gnd flt threshold		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.0 [%]	100.0 [%]	[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 current of the power unit (r0209).		
	Index: [0] = Threshold at which pre-charging starts [1] = Threshold at which pre-charging stops		
	Dependency: Refer to: p1901 Refer to: F30021		
	Note: This parameter is only relevant for chassis power units.		

r0289	CO: Maximum power unit output current / PU I_outp max		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the actual maximum output current of the power unit taking into account derating factors.		
p0290	Power unit overload response / PU overld response		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8019
	Min	Max	Factory setting
	0	13	2
Description:	<p>Sets the response to a thermal overload condition of the power unit.</p> <p>The following quantities can result in a response to thermal overload:</p> <ul style="list-style-type: none"> - heat sink temperature (r0037.0). - chip temperature (r0037.1). - power unit overload I2t (r0036). <p>Possible measures to avoid thermal overload:</p> <ul style="list-style-type: none"> - reduce the output current limit r0289 and r0067 or the output frequency (for U/f control) indirectly via the output current limit and the intervention of the current limiting controller). - reduce the pulse frequency. <p>A reduction, if parameterized, is always realized after an appropriate alarm is output.</p>		
Value:	<p>0: Reduce output current or output frequency</p> <p>1: No reduction shutdown when overload threshold is reached</p> <p>2: Reduce I_output or f_output and f_pulse (not using I2t)</p> <p>3: Reduce the pulse frequency (not using I2t)</p> <p>12: I_output or f_output and automatic pulse frequency reduction</p> <p>13: Automatic pulse frequency reduction</p>		
Dependency:	<p>If a sine-wave filter is parameterized as output filter (p0230 = 3, 4), then only responses can be selected without pulse frequency reduction (p0290 = 0, 1).</p> <p>For a thermal power unit overload, an appropriate alarm or fault is output, and r2135.15 or r2135.13 set.</p> <p>Refer to: r0036, r0037, p0230, r2135</p> <p>Refer to: A05000, A05001, A07805</p>		
Notice:	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 irrespective of the setting of this parameter.		
Note:	<p>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).</p> <p>Under overload conditions, if the current and torque limits are reduced, and therefore the motor is braked, then forbidden speed ranges (e.g. minimum speed and suppression [skip] speeds) can also be passed through.</p> <p>For p0290 = 2, 3, 12, 13, the I2t overload detection of the power unit does not influence the response "Reduce pulse frequency".</p> <p>When the motor data identification routine is selected, p0290 cannot be changed.</p> <p>For short-circuit/ground fault detection, when the test pulse evaluation is active via p1901 "Test pulse evaluation configuration", the pulse frequency at the instant of switch on is briefly reduced.</p>		

p0292[0...1]	Power unit temperature alarm threshold / PU T_alm thresh		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [°C]	25 [°C]	[0] 5 [°C]
			[1] 15 [°C]
Description:	Sets the alarm threshold for power unit overtemperatures. The value is set as a difference to the tripping (shutdown) temperature.		
	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.		
Index:	[0] = Heat sink temperature		
	[1] = Power semiconductor (chip) temperature		
Dependency:	Refer to: r0037, p0290		
	Refer to: A05000		
p0295	Fan run-on time / Fan run-on time		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [s]	600 [s]	0 [s]
Description:	Sets the fan run-on time after the pulses for the power unit have been canceled.		
Note:	- Under certain circumstances, the fan can continue to run for longer than was set (e.g. as a result of the excessively high heat sink temperature).		
	- For values less than 1 s, a 1 s run on time for the fan is active.		
	- for a PM230 power unit, sizes D - F the parameter is ineffective.		
p0300[0...n]	Motor type selection / Mot type sel		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6310
	Min	Max	Factory setting
	0	277	0
Description:	Selecting the motor type.		
	The first digit of the parameter value always defines the general motor type and corresponds to the third-party motor belonging to a motor list:		
	1 = Rotating induction motor		
	2 = Rotating synchronous motor		
	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/IOP).		
Value:	0: No motor 1: Induction motor 2: Synchronous motor 10: 1LE1 induction motor 13: 1LG6 induction motor 17: 1LA7 induction motor 19: 1LA9 induction motor 100: 1LE1 induction motor 108: 1PH8 induction motor 271: 1FG1 synchronous geared motor without encoder 277: 1FK7 synchronous motor without encoder		

2 Parameters


2.2 List of parameters

Dependency:	When the motor type is changed, the code number in p0301 may be reset to 0. When selecting a motor type from the 1LA7 series, parameters of the thermal motor model are pre-assigned as a function of p0307 and p0311. For p0096 = 1 (Standard Drive Control) synchronous motor types cannot be selected.
Caution:	If a motor is selected, which is not contained in the motor lists (p0300 < 100), then the motor code number must be reset (p0301 = 0), if previously a motor was parameterized from the motor list.
	
Note:	Once the Control Unit has been powered up for the first time or if the factory settings have been defined accordingly, the motor type is pre-configured to induction motor (p0300 = 1). If a motor type has not been selected (p0300 = 0), then the drive commissioning routine cannot be exited.

p0301[0...n]	Motor code number selection / Mot code No. sel		
	Access level: 2	Calculated: -	Data type: Unsigned16
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	65535	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:	Code numbers can only be selected for motor types that correspond to the motor type selected in p0300. Refer to: p0300		
Note:	The motor code number can only be changed if the matching catalog motor was first selected in p0300. When selecting a catalog motor (p0300 >= 100), drive commissioning can only be exited if a code number is selected. If a change is made to a non-catalog motor, then the motor code number should be reset (p0301 = 0).		

p0304[0...n]	Rated motor voltage / Mot U_{rated}		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6301, 6724
	Min	Max	Factory setting
	0 [Vrms]	20000 [Vrms]	0 [Vrms]
Description:	Sets the rated motor voltage (rating plate).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	When the parameter value is entered the connection type of the motor (star-delta) must be taken into account. Once the Control Unit has booted for the first time or if the factory settings have been restored, the parameter is pre-assigned to match the power unit.		

p0305[0...n]	Rated motor current / Mot I_{rated}		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.00 [Arms]	10000.00 [Arms]	0.00 [Arms]
Description:	Sets the rated motor current (rating plate).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection. If p0305 is changed during quick commissioning (p0010 = 1), then the maximum current p0640 is pre-assigned accordingly.		
Note:	When the parameter value is entered the connection type of the motor (star-delta) must be taken into account. Once the Control Unit has booted for the first time or if the factory settings have been restored, the parameter is pre-assigned to match the power unit.		

p0306[0...n]	Number of motors connected in parallel / Motor qty		
	Access level: 1	Calculated: -	Data type: Unsigned8
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	50	1
Description:	Sets the number (count) of motors that can be operated in parallel using one motor data set. Depending on the motor number entered, internally an equivalent motor is calculated. The following should be observed in motors connected in parallel: Rating plate data should only be entered for one motor: p0305, p0307 The following parameters are also only valid for one motor: p0320, p0341, p0344, p0350 ... p0361 All other motor parameters take into account the replacement/equivalent motor (e.g. r0331, r0333).		
Recommendation:	For motors connected in parallel, external thermal protection should be provided for each individual motor.		
Dependency:	Refer to: r0331, r0382		
Caution:	The motors to be connected in parallel must be of the same type and size (same order no. (MLFB)). 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, p3900 > 0). For induction motors that are connected in parallel, but which are not mechanically coupled with one another, then the following applies: - an individual motor must not be loaded beyond its stall point.		
			
Notice:	If p0306 is changed during quick commissioning (p0010 = 1), then the maximum current p0640 is appropriately pre-assigned.		
Note:	Only operation with U/f characteristic makes sense if more than 10 identical motors are connected in parallel.		
p0307[0...n]	Rated motor power / Mot P_{rated}		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: 14_6	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	0.00 [kW]	100000.00 [kW]	0.00 [kW]
Description:	Sets the rated motor power (rating plate).		
Dependency:	IECdrives (p0100 = 0): Units kW NEMA drives (p0100 = 1): Units hp NEMA drives (p0100 = 2): Unit kW Refer to: p0100		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	Once the Control Unit has booted for the first time or if the factory settings have been restored, the parameter is pre-assigned to match the power unit.		
p0308[0...n]	Rated motor power factor / Mot cos phi rated		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000	1.000	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.		
Dependency:	This parameter is only available for p0100 = 0, 2. Refer to: p0100, p0309		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		

2 Parameters

2.2 List of parameters

Note: The parameter is not used for synchronous motors (p0300 = 2xx).
Once the Control Unit has booted for the first time or if the factory settings have been restored, the parameter is pre-assigned to match the power unit.

p0309[0...n]	Rated motor efficiency / Mot eta_{rated}		
	Access level: 1 Can be changed: C(1, 3) Unit group: - Min 0.0 [%]	Calculated: - Scaling: - Unit selection: - Max 99.9 [%]	Data type: FloatingPoint32 Dyn. index: MDS Func. diagram: - 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.		
Dependency:	This parameter is only visible for NEMA motors (p0100 = 1, 2). Refer to: p0100, p0308		
Note:	The parameter is not used for synchronous motors.		
p0310[0...n]	Rated motor frequency / Mot f_{rated}		
	Access level: 1 Can be changed: C(1, 3) Unit group: - Min 0.00 [Hz]	Calculated: - Scaling: - Unit selection: - Max 650.00 [Hz]	Data type: FloatingPoint32 Dyn. index: MDS Func. diagram: 6301 Factory setting 0.00 [Hz]
Description:	Sets the rated motor frequency (rating plate).		
Dependency:	The number of pole pairs is automatically re-calculated when the parameter is changed (together with p0311), if p0314 = 0. The rated frequency is restricted to values between 1.00 Hz and 650.00 Hz. Refer to: p0311, r0313, p0314		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection. If p0310 is changed during quick commissioning (p0010 = 1), the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned accordingly. The preassignment has been completed if the status display r3996 returns to zero.		
Note:	Once the Control Unit has been booted up for the first time or if the factory settings have been defined accordingly, the parameter is defined in accordance with the power unit.		
p0311[0...n]	Rated motor speed / Mot n_{rated}		
	Access level: 1 Can be changed: C(1, 3) Unit group: - Min 0.0 [rpm]	Calculated: - Scaling: - Unit selection: - Max 210000.0 [rpm]	Data type: FloatingPoint32 Dyn. index: MDS Func. diagram: - Factory setting 0.0 [rpm]
Description:	Sets the rated motor speed (rating plate). 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 vector control and slip compensation for U/f control.		
Dependency:	If p0311 is changed and for p0314 = 0, the pole pair is re-calculated automatically. Refer to: p0310, r0313, p0314		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection. If p0311 is changed during quick commissioning (p0010 = 1), the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned accordingly. The preassignment has been completed if the status display r3996 returns to zero.		
Note:	Once the Control Unit has been booted up for the first time or if the factory settings have been defined accordingly, the parameter is defined in accordance with the power unit.		

p0312[0...n]	Rated motor torque / Mot M_{rated}		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00 [Nm]	1000000.00 [Nm]	0.00 [Nm]
Description:	Sets the rated motor torque (rating plate).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
r0313[0...n]	Motor pole pair number, actual (or calculated) / Mot PolePairNo act		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 5300
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of motor pole pairs. The value is used for internal calculations. 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.		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	0
Description:	Sets the motor pole pair number. 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:	If p0314 is changed during quick commissioning (p0010 = 1), the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned accordingly. For induction motors, it is only necessary to enter the value if the rated motor slip is so high that the pole pair number r0313, obtained when making the calculation based on the rated frequency and rated speed, is too low.		
p0316[0...n]	Motor torque constant / Mot kT		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 28_1	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	0.00 [Nm/A]	400.00 [Nm/A]	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.		

2 Parameters

2.2 List of parameters

Notice: When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.


Note: This parameter is not used for induction motors (p0300 = 1xx).

p0318[0...n]	Motor stall current / Mot I_standstill		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 8017
	Min 0.00 [Arms]	Max 10000.00 [Arms]	Factory setting 0.00 [Arms]
Description:	Sets the stall current for synchronous motors (p0300 = 2xx).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	This parameter is not used for induction motors (p0300 = 1xx).		
p0320[0...n]	Motor rated magnetizing current/short-circuit current / Mot I_mag_rated		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 0.000 [Arms]	Max 5000.000 [Arms]	Factory setting 0.000 [Arms]
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.		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The magnetizing current p0320 for induction motors is reset when quick commissioning is exited with p3900 > 0. 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 remains constant.		
p0322[0...n]	Maximum motor speed / Mot n_max		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 0.0 [rpm]	Max 210000.0 [rpm]	Factory setting 0.0 [rpm]
Description:	Sets the maximum motor speed.		
Dependency:	Refer to: p1082		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection. If p0322 is changed during quick commissioning (p0010 = 1), the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned accordingly.		
Note:	The parameter has no significance for a value of p0322 = 0.		


p0323[0...n]	Maximum motor current / Mot I_max		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00 [Arms]	20000.00 [Arms]	0.00 [Arms]
Description:	Sets the maximum permissible motor current (e.g. de-magnetizing current for synchronous motors).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection. If p0323 is changed during quick commissioning (p0010 = 1), then the maximum current p0640 is pre-assigned accordingly.		
Note:	The parameter has no effect for induction motors. The parameter has not effect for synchronous motors if a value of 0.0 is entered. The user-selectable current limit is entered into p0640.		
p0325[0...n]	Motor pole position identification current 1st phase / Mot PolID I 1st ph		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [Arms]	10000.000 [Arms]	0.000 [Arms]
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. The two-stage technique is selected with p1980 = 4.		
Dependency:	Refer to: p0329, p1980 Refer to: F07969		
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).		
p0329[0...n]	Motor pole position identification current / Mot PolID current		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.0000 [Arms]	10000.0000 [Arms]	0.0000 [Arms]
Description:	Sets the current for the pole position identification routine (p1980 = 1). For a two-stage technique (p1980 = 4), the current is set for the 2nd phase. The current for the 1st phase is set in p0325.		
Dependency:	If a maximum current (p0323) was not parameterized, then p0329 is limited to the rated motor current. If p0329 is too small in order to determine the pole position (for p1980 = 1), then p0323 must be first parameterized and significantly greater than p0329. Refer to: p0325, p1980 Refer to: F07969		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		

r0330[0...n]	Rated motor slip / Mot slip_rated		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [Hz]	- [Hz]	- [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]	Actual motor magnetizing current/short-circuit current / Mot I_mag_rtd act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6722, 6724
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
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.		
r0333[0...n]	Rated motor torque / Mot M_rated		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: 7_4	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Displays the rated motor torque.		
Dependency:	IEC drives (p0100 = 0): unit Nm NEMA drives (p0100 = 1): unit lbf ft		
Note:	For induction motors, r0333 is calculated from p0307 and p0311. For synchronous motors, r0333 is calculated from p0305, p0316, p0327 and p0328.		
p0335[0...n]	Motor cooling type / Mot cool type		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(1, 3), T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	128	0
Description:	Sets the motor cooling system used.		
Value:	0: Non-ventilated 1: Forced cooling 2: Liquid cooling 128: No fan		
Dependency:	For 1LA7 motors (p0300), the parameter is pre-set as a function of p0307 and p0311.		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The parameter influences the thermal 3-mass motor model. 1LA7 motors, frame size 56 are operated without fan.		

p0340[0...n]	Automatic calculation motor/control parameters / Calc auto par		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(3), T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	5	0
Description:	Setting to automatically calculate motor parameters and U/f open-loop and closed-loop control parameters from the rating plate data.		
Value:	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:	After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. The following parameters are influenced using p0340: p0340 = 1: --> All of the parameters influenced for p0340 = 2, 3, 4, 5 --> p0341, p0342, p0344, p0640, p1082, p1231, p1232, p1349, p1611, p1726, p1909, p1959, p2000, p2001, p2002, p2003, p3927, p3928 p0340 = 2: --> p0350, p0354 ... p0360 --> p0625 (matching p0350) p0340 = 3: --> All of the parameters influenced for p0340 = 4, 5 --> p0346, p0347, p0622, p1320 ... p1327, p1582, p1755 p0340 = 4: --> p1290, p1292, p1338, p1340, p1341, p1345, p1346, p1470, p1472, p1764, p1767 p0340 = 5: --> p1037, p1038, p1520, p1521, p1530, p1531, p1802, p1803, p2390, p2392, p2393		
Note:	p0340 = 1 contains the calculations of p0340 = 2, 3, 4, 5. p0340 = 2 calculates the motor parameters (p0350 ... p0360). p0340 = 3 contains the calculations of p0340 = 4, 5. p0340 = 4 only calculates the controller parameters. p0340 = 5 only calculates the controller limits. When quick commissioning is exited using p3900 > 0, p0340 is automatically set to 1. At the end of the calculations, p0340 is automatically set to 0.		
p0341[0...n]	Motor moment of inertia / Mot M_mom of inert		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 25_1	Unit selection: p0100	Func. diagram: 6020, 6030, 6031
	Min	Max	Factory setting
	0.000000 [kgm ²]	100000.000000 [kgm ²]	0.000000 [kgm ²]
Description:	Sets the motor moment of inertia (without load).		
Dependency:	IEC drives (p0100 = 0): unit kg m ² NEMA drives (p0100 = 1): unit lb ft ² The parameter value is included, together with p0342, in the rated starting time of the motor. Refer to: p0342, r0345		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The product of p0341 * p0342 is used when the speed controller (p0340 = 4) is calculated automatically.		

p0342[0...n]	Ratio between the total and motor moment of inertia / Mot MomInert Ratio		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6020, 6030, 6031
	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:	The product of p0341 * p0342 is used when the speed controller (p0340 = 4) is calculated automatically.		
p0344[0...n]	Motor weight (for the thermal motor model) / Mot weight th mod		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), T	Scaling: -	Dyn. index: MDS
	Unit group: 27_1	Unit selection: p0100	Func. diagram: -
	Min 0.0 [kg]	Max 50000.0 [kg]	Factory setting 0.0 [kg]
Description:	Sets the motor weight.		
Dependency:	IEC drives (p0100 = 0): unit kg NEMA drives (p0100 = 1): unit lb		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The parameter influences the thermal 3 mass model of the induction motor. The parameter is not used for synchronous motors (p0300 = 2xx).		
r0345[0...n]	Nominal motor starting time / Mot t_start Rated		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	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.		
Dependency:	Refer to: r0313, r0333, p0341, p0342		
p0346[0...n]	Motor excitation build-up time / Mot t_excitation		
	Access level: 3	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	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.		
Caution:	If there is insufficient magnetization under load or if the acceleration rate is too high, then an induction motor can stall (refer to the note).		
			
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 magnetizing of the induction motor. This is the case if the current limit is reached while building up magnetizing. For induction motors, the parameter cannot be set to 0 s (internal limit: 0.1 * r0384).		

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 encoderless operation immediately after the pulses have been enabled.

p0347[0...n]	Motor de-excitation time / Mot t_de-excitat		
	Access level: 3	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [s]	20.000 [s]	0.000 [s]
Description:	Sets the de-magnetizing time (for induction motors) after the inverter pulses have been canceled. 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-magnetizing 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).		
p0350[0...n]	Motor stator resistance cold / Mot R_stator cold		
	Access level: 3	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00000 [ohm]	2000.00000 [ohm]	0.00000 [ohm]
Description:	Sets the stator resistance of the motor at ambient temperature p0625 (phase value).		
Dependency:	Refer to: p0625		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The motor identification routine determines the stator resistance from the total stator resistance minus the cable resistance (p0352).		
p0352[0...n]	Cable resistance / R_cable		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00000 [ohm]	120.00000 [ohm]	0.00000 [ohm]
Description:	Resistance of the power cable between the power unit and motor.		
Caution:			
Note:	The cable resistance should be entered prior to motor data identification. If it is used subsequently, the difference by which p0352 was changed must be subtracted from the stator resistance p0350 or motor data identification must be repeated. The parameter influences the temperature adaptation of the stator resistance. The motor identification sets the cable resistance to 20% of the measured total resistance if p0352 is zero at the time that the measurement is made. If p0352 is not zero, then the value is subtracted from the measured total stator resistance to calculate stator resistance p0350. In this case, p0350 is a minimum of 10% of the measured value. The cable resistance is reset when quick commissioning is exited with p3900 > 0.		

p0354[0...n]	Motor rotor resistance cold / Mot R_r cold		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6727
	Min	Max	Factory setting
	0.00000 [ohm]	300.00000 [ohm]	0.00000 [ohm]
Description:	Sets the rotor/secondary section resistance of the motor at the ambient temperature p0625. This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor data identification routine (p1910).		
Dependency:	Refer to: p0625		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The parameter is not used for synchronous motors (p0300 = 2).		
p0356[0...n]	Motor stator leakage inductance / Mot L_stator leak.		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00000 [mH]	1000.00000 [mH]	0.00000 [mH]
Description:	Induction machine: sets the stator 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).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	If the stator leakage inductance (p0356) for induction motors is changed outside the commissioning phase (p0010 > 0), the magnetizing inductance (p0360) is automatically adapted to the new EMF. You are then advised to repeat the measurement for the saturation characteristic (p1960). For permanent-magnet synchronous motors (p0300 = 2), this is the non-saturated value and is, therefore, ideal for a low current.		
p0357[0...n]	Motor stator inductance d axis / Mot L_stator d		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00000 [mH]	1000.00000 [mH]	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:	For permanent-magnet synchronous motors (p0300 = 2), this is the non-saturated value and is ideal for a low current.		
p0358[0...n]	Motor rotor leakage inductance / Mot L_rot leak		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6727
	Min	Max	Factory setting
	0.00000 [mH]	1000.00000 [mH]	0.00000 [mH]
Description:	Sets the rotor/secondary section leakage inductance of the motor. The value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		

Note: If the rotor leakage inductance (p0358) for induction motors is changed outside the commissioning phase (p0010 > 0), the magnetizing inductance (p0360) is automatically adapted to the new EMF. You are then advised to repeat the measurement for the saturation characteristic (p1960).

p0360[0...n]	Motor magnetizing inductance / Mot Lh		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6727
	Min	Max	Factory setting
	0.00000 [mH]	10000.00000 [mH]	0.00000 [mH]
Description:	Sets the magnetizing inductance of the motor. This parameter value is automatically calculated using the motor model (p0340 = 1, 2) or using the motor identification routine (p1910).		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The parameter is not used for synchronous motors (p0300 = 2).		

p0362[0...n]	Motor saturation characteristic flux 1 / Mot saturat.flux 1		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	Min	Max	Factory setting
	10.0 [%]	800.0 [%]	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. When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		

p0363[0...n]	Motor saturation characteristic flux 2 / Mot saturat.flux 2		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	Min	Max	Factory setting
	10.0 [%]	800.0 [%]	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. When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		

p0364[0...n]	Motor saturation characteristic flux 3 / Mot saturat.flux 3		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	Min	Max	Factory setting
	10.0 [%]	800.0 [%]	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. When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
p0365[0...n]	Motor saturation characteristic flux 4 / Mot saturat.flux 4		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	Min	Max	Factory setting
	10.0 [%]	800.0 [%]	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. When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
p0366[0...n]	Motor saturation characteristic I_mag 1 / Mot sat. I_mag 1		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	Min	Max	Factory setting
	5.0 [%]	800.0 [%]	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 magnetization current of the saturation characteristic in [%] with reference to the rated magnetization current (r0331).		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0362		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		

p0367[0...n]	Motor saturation characteristic I_mag 2 / Mot sat. I_mag 2		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	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 magnetization current of the saturation characteristic in [%] with reference to the rated magnetization current (r0331).		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0363		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
p0368[0...n]	Motor saturation characteristic I_mag 3 / Mot sat. I_mag 3		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	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 magnetization current of the saturation characteristic in [%] with reference to the rated magnetization current (r0331).		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0364		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
p0369[0...n]	Motor saturation characteristic I_mag 4 / Mot sat. I_mag 4		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6723
	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 magnetization current of the saturation characteristic in [%] with reference to the rated magnetization current (r0331).		
Dependency:	The following applies for the magnetizing currents: p0366 < p0367 < p0368 < p0369 Refer to: p0365		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		

r0382[0...n]	Motor magnetizing inductance transformed / Mot L_magn transf		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [mH]	- [mH]	- [mH]
Description:	Displays the magnetizing inductance of the motor.		
Note:	The parameter is not used for synchronous motors (p0300 = 2xx).		
r0384[0...n]	Motor rotor time constant / damping time constant d axis / Mot T_rotor/T_Dd		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 6722
	Min	Max	Factory setting
	- [ms]	- [ms]	- [ms]
Description:	Displays the rotor time constant.		
Note:	The parameter is not used for synchronous motors. The value is calculated from the total of the inductances on the rotor side (p0358, p0360) divided by the rotor resistance (p0354). The temperature adaptation of the rotor resistance for induction motors is not taken into account.		
r0386[0...n]	Motor stator leakage time constant / Mot T_stator leak		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [ms]	- [ms]	- [ms]
Description:	Displays the stator leakage time constant.		
Note:	The value is calculated from the total of all leakage inductances (p0233, p0356, p0358) divided by the total of all motor resistances (p0350, p0352, p0354). The temperature adaptation of the resistances is not taken into account.		
r0394[0...n]	Rated motor power / Mot P Rated		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: 14_6	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	- [kW]	- [kW]	- [kW]
Description:	Displays the rated motor power.		
Note:	The parameter displays p0307. For p0307 = 0, r0394 is calculated from p0304 and p0305 (only for induction motors). Depending on the actual motor type, deviations can occur from the actual rated motor power.		
r0395[0...n]	Actual stator resistance / R_stator act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [ohm]	- [ohm]	- [ohm]
Description:	Displays the actual stator resistance (phase value). The parameter value also contains the temperature-independent cable resistance.		
Dependency:	In the case of induction motors the parameter is also affected by the motor temperature model. Refer to: p0350, p0352, p0620		
Note:	In each case, only the stator resistance of the active Motor Data Set is included with the stator temperature of the thermal motor model.		

r0396[0...n]	Actual rotor resistance / R_rotor act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [ohm]	- [ohm]	- [ohm]
Description:	Displays the actual rotor resistance (phase value). The parameter is affected by the motor temperature model.		
Dependency:	Refer to: p0354, p0620		
Note:	In each case, only the rotor resistance of the active Motor Data Set is included with the rotor temperature of the thermal motor model. This parameter is not used for synchronous motors (p0300 = 2xx).		
p0422[0...n]	Absolute encoder linear measuring step resolution / Enc abs meas step		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(4)	Scaling: -	Dyn. index: EDS
	Unit group: -	Unit selection: -	Func. diagram: 4704
	Min	Max	Factory setting
	0 [nm]	4294967295 [nm]	100 [nm]
Description:	Sets the resolution of the absolute position for a linear absolute encoder.		
Notice:	This parameter is automatically pre-set for encoders from the encoder list (p0400). When selecting a catalog encoder, this parameter cannot be changed (write protection). Information in p0400 should be carefully observed when removing write protection.		
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.		
p0500	Technology application / Tec application		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(1, 5), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	3	0
Description:	Sets the technology application. The parameter influences the calculation of open-loop and closed-loop control parameters that is e.g. initiated using p0340 = 5.		
Value:	0: Standard drive 1: Pumps and fans 2: Sensorless closed-loop control down to f = 0 (passive loads) 3: Pumps and fans, efficiency optimization		
Dependency:	For p0096 = 1, 2 (Standard, Dynamic Drive Control) p0500 cannot be changed.		
Notice:	If the technological application is set to p0500 = 0 ... 3 during commissioning (p0010 = 1, 5, 30), the operating mode (p1300) is pre-set accordingly.		
Note:	The calculation of parameters dependent on the technology application can be called up as follows: - when exiting quick commissioning using p3900 > 0 - when writing p0340 = 1, 3, 5 For p0500 = 0 and when the calculation is initiated, the following parameters are set: - p1802 = 0 (automatic changeover SVM/FLB) - p1803 = 106 % For p0500 = 1 and when the calculation is initiated, the following parameters are set: - p1802 = 0 (automatic changeover SVM/FLB) - p1803 = 106 % For p0500 = 2 and when the calculation is initiated, the following parameters are set: - p1802 = 0 (automatic changeover SVM/FLB) - p1803 = 106 %		

For p0500 = 3 and when the calculation is initiated, the following parameters are set:

- p1802 = 0 (automatic changeover SVM/FLB)

- p1803 = 106 %


Re p1802 / p1803:

p1802 and p1803 are only changed, in all cases, if a sine-wave output filter (p0230 = 3, 4) has not been selected.

p0501	Technological application (standard drive control) / Techn appl SDC		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(1, 5), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the technology application. The parameter influences the calculation of open-loop and closed-loop control parameters that is e.g. initiated using p0340 = 5.		
Value:	0: Constant load (linear characteristic) 1: Speed-dependent load (parabolic characteristic)		
Dependency:	Refer to: p1300		
Notice:	If the technological application is set to p0501 = 0, 1 during commissioning (p0010 = 1, 5, 30), the operating mode (p1300) is pre-set accordingly.		
Note:	The calculation of parameters dependent on the technology application can be called up as follows: - when exiting quick commissioning using p3900 > 0 - when writing p0340 = 1, 3, 5 For p0501 = 0, 1 and when the calculation is initiated, the following parameters are set: - p1802 = 0 - p1803 = 106 % - p3855.0 = 1 (DC quantity control on) Re p1802 / p1803: These parameters are only changed, in all cases, if a sine-wave output filter (p0230 = 3, 4) has not been selected.		
p0502	Technological application (dynamic drive control) / Techn appl DDC		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(1, 5), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	5	0
Description:	Sets the technology application for dynamic applications (p0096 = 2). The parameter influences the calculation of open-loop and closed-loop control parameters that is e.g. initiated using p0340 or p3900.		
Value:	0: Standard drive (e.g. pumps, fans) 1: Dynamic starting or reversing 5: Heavy-duty starting (e.g. extruders, compressors)		
Dependency:	The calculation of parameters dependent on the technology application can be called up as follows: - when exiting quick commissioning using p3900 > 0 - when writing p0340 = 1, 3 or 5 Refer to: p1610, p1750		
Note:	When entering p0502 and initiating the calculation, the following parameters are set: p0502 = 0: - p1750.0/1/7 = 1 (start and reverse in open-loop control with rugged switchover limits) - p1610 = 50 %, p1611 = 30 % (low up to average starting torque) p0502 = 1: - p1750.0/1/7 = 0 (start and reverse in closed-loop control with shorter acceleration times) - p1610 = 50 %, p1611 = 30 % (only effective, if the drive is switched-on with a speed setpoint of zero)		

p0502 = 5:

- p1750.0/1/7 = 1 (start and reverse in open-loop control with rugged switchover limits)
- p1610 = 80 %, p1611 = 80 % (average up to higher starting torque)

p0505	Selecting the system of units / Unit sys select		
	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: C(5)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	4	1
Description:	Sets the actual system of units.		
Value:	1: SI system of units 2: System of units referred/SI 3: US system of units 4: System of units referred/US		
Dependency:	The parameter can only be changed in an offline project using the commissioning software.		
Caution:			
Note:			
	If a per unit representation is selected and if the reference parameters (e.g. p2000) are subsequently changed, then the physical significance of several control parameters is also adapted at the same time. The control behavior can change as a consequence.		
	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.		

p0514[0...9]	Scaling-specific reference values / Scal spec ref val		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000001	10000000.000000	1.000000
Description:	Sets the reference values for the specific scaling of BICO parameters. The specific scaling is active when interconnecting with other BICO parameters, and can be used in the following cases: 1. Parameter with the marking "Scaling: p0514". 2. Changing the standard scaling for parameters with the marking "Scaling: p2000" ... "Scaling: p2007". Relative values refer to the corresponding reference value. The reference value corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word). To specifically scale BICO parameters, proceed as follows: - set the reference value (p0514[0...9]). - set the numbers of the parameters, which should be active for the scaling, corresponding to the index of p0514 (p0515[0...19] ... p0524[0...19]). For parameters with the marking "Scaling: p0514", which are not entered in p0515[0...19] to p0524[0...19], the reference value 1.0 (factory setting) applies.		
Index:	[0] = Parameters in p0515[0...19] [1] = Parameters in p0516[0...19] [2] = Parameters in p0517[0...19] [3] = Parameters in p0518[0...19] [4] = Parameters in p0519[0...19] [5] = Parameters in p0520[0...19] [6] = Parameters in p0521[0...19] [7] = Parameters in p0522[0...19] [8] = Parameters in p0523[0...19] [9] = Parameters in p0524[0...19]		
Dependency:	Refer to: p0515, p0516, p0517, p0518, p0519, p0520, p0521, p0522, p0523, p0524		

p0515[0...19]	Scaling specific parameters referred to p0514[0] / Scal spec p514[0]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[0] for the specific scaling. p0515[0]: parameter number p0515[1]: parameter number p0515[2]: parameter number ... p0515[19]: parameter number		
Dependency:	Refer to: p0514		
p0516[0...19]	Scaling specific parameters referred to p0514[1] / Scal spec p514[1]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[1] for the specific scaling. p0516[0]: parameter number p0516[1]: parameter number p0516[2]: parameter number ... p0516[19]: parameter number		
Dependency:	Refer to: p0514		
p0517[0...19]	Scaling specific parameters referred to p0514[2] / Scal spec p514[2]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[2] for the specific scaling. p0517[0]: parameter number p0517[1]: parameter number p0517[2]: parameter number ... p0517[19]: parameter number		
Dependency:	Refer to: p0514		
p0518[0...19]	Scaling specific parameters referred to p0514[3] / Scal spec p514[3]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[3] for the specific scaling. p0518[0]: parameter number p0518[1]: parameter number		

p0518[2]: parameter number
 ...
 p0518[19]: parameter number
Dependency: Refer to: p0514

p0519[0...19] Scaling specific parameters referred to p0514[4] / Scal spec p514[4]			
Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32	
Can be changed: T	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: -	
Min	Max	Factory setting	
0	4294967295	0	

Description: Sets the parameters with reference value in p0514[4] for the specific scaling.

p0519[0]: parameter number
 p0519[1]: parameter number
 p0519[2]: parameter number
 ...

p0519[19]: parameter number
Dependency: Refer to: p0514

p0520[0...19] Scaling specific parameters referred to p0514[5] / Scal spec p514[5]			
Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32	
Can be changed: T	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: -	
Min	Max	Factory setting	
0	4294967295	0	

Description: Sets the parameters with reference value in p0514[5] for the specific scaling.

p0520[0]: parameter number
 p0520[1]: parameter number
 p0520[2]: parameter number
 ...

p0520[19]: parameter number
Dependency: Refer to: p0514

p0521[0...19] Scaling specific parameters referred to p0514[6] / Scal spec p514[6]			
Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32	
Can be changed: T	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: -	
Min	Max	Factory setting	
0	4294967295	0	

Description: Sets the parameters with reference value in p0514[6] for the specific scaling.

p0521[0]: parameter number
 p0521[1]: parameter number
 p0521[2]: parameter number
 ...

p0521[19]: parameter number
Dependency: Refer to: p0514

p0522[0...19]	Scaling specific parameters referred to p0514[7] / Scal spec p514[7]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[7] for the specific scaling. p0522[0]: parameter number p0522[1]: parameter number p0522[2]: parameter number ... p0522[19]: parameter number		
Dependency:	Refer to: p0514		
p0523[0...19]	Scaling specific parameters referred to p0514[8] / Scal spec p514[8]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[8] for the specific scaling. p0523[0]: parameter number p0523[1]: parameter number p0523[2]: parameter number ... p0523[19]: parameter number		
Dependency:	Refer to: p0514		
p0524[0...19]	Scaling specific parameters referred to p0514[9] / Scal spec p514[9]		
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the parameters with reference value in p0514[9] for the specific scaling. p0524[0]: parameter number p0524[1]: parameter number p0524[2]: parameter number ... p0524[19]: parameter number		
Dependency:	Refer to: p0514		
p0530[0...n]	Bearing version selection / Bearing vers sel		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	104	0
Description:	Sets the bearing version. Corresponding to the bearing version entered, its code number (p0531) is automatically set. 0 = No selection 1 = Manual entry		

101 = STANDARD
 102 = PERFORMANCE
 103 = HIGH PERFORMANCE
 104 = ADVANCED LIFETIME

Dependency: Refer to: p0301, p0531, p0532, p1082

Notice: For p0530 = 101, 102, 103, 104, the maximum bearing speed (p0532) is write protected. Write protection is withdrawn with p0530 = 1.

If p0530 is changed during quick commissioning (p0010 = 1), then the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned appropriately. This is not the case when commissioning the motor (p0010 = 3). The maximum speed of the bearing is factored into the limit for the maximum speed p1082.

Note: For a motor with DRIVE-CLiQ, p0530 can only be set to 1.

p0531[0...n] Bearing code number selection / Bearing codeNo sel

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: C(3)	Scaling: -	Dyn. index: MDS
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	65535	0

Description: Display and setting the code number of the bearing.

When setting p0301 and p0530 the code number is automatically preassigned and is write protected. The information in p0530 should be observed when removing write protection.

Dependency: Refer to: p0301, p0530, p0532, p1082

Notice: If p0531 is changed during quick commissioning (p0010 = 1), then the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned appropriately. This is not the case when commissioning the motor (p0010 = 3). The maximum speed of the bearing is factored into the limit for the maximum speed p1082.

Note: p0531 cannot be changed on a motor with DRIVE-CLiQ.

p0532[0...n] Bearing maximum speed / Bearing n_max

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: C(1, 3)	Scaling: -	Dyn. index: MDS
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0.0 [rpm]	210000.0 [rpm]	0.0 [rpm]

Description: Sets the maximum speed of the bearing.

The following applies when calculating the maximum speed (p1082):

- for p0324 = 0 or p0532 = 0, p0322 is used.
- for p0324 > 0 and p0532 > 0, the minimum value from the two parameters is used.

Dependency: Refer to: p0301, p0322, p0530, p1082

Notice: This parameter is pre-assigned in the case of motors from the motor list (p0301) if a bearing version (p0530) is selected.

When selecting a catalog motor, this parameter cannot be changed (write protection). The information in p0530 should be observed when removing write protection.

If p0532 is changed during quick commissioning (p0010 = 1), then the maximum speed p1082, which is also associated with quick commissioning, is pre-assigned appropriately. This is not the case when commissioning the motor (p0010 = 3).

p0541[0...n] Load gearbox code number / Load grbx CodeNo


Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: T	Scaling: -	Dyn. index: MDS
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	4294967295	0

Description: Display and setting the code number of the load gearbox.

p0542[0...n]	Load gearbox maximum speed / Load grbx n_max		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [rpm]	340.28235E36 [rpm]	0 [rpm]
Description:	Maximum permissible input speed at the load gearbox. The following applies when calculating the maximum speed (p1082): - for p0324 = 0 or p0532 = 0 or p0542 = 0, p0322 is used. - for p0324 > 0, p0532 > 0 and p0542 > 0, the minimum value from the parameters is used.		
p0543[0...n]	Load gearbox maximum torque / Load grbx M_max		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: 7_1	Unit selection: p0505	Func. diagram: -
	Min	Max	Factory setting
	0 [Nm]	340.28235E36 [Nm]	0 [Nm]
Description:	Maximum permissible input torque at the load gearbox.		
p0544[0...n]	Load gearbox overall ratio (absolute value) numerator / Load grbx ratio N		
	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2147483647	0
Description:	Sets the numerator for the overall ratio of the load gearbox.		
p0545[0...n]	Load gearbox overall ratio (absolute value) denominator / Load grbx ratio D		
	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2147483647	0
Description:	Sets the denominator for the overall ratio of the load gearbox.		
p0546[0...n]	Load gearbox output direction of rotation inversion / Load grbx outp inv		
	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2147483647	0
Description:	Sets the inversion for the direction of rotation of the load gearbox.		
p0550[0...n]	Brake type / Brake type		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	65535	0
Description:	Sets the brake version.		

p0551[0...n]	Brake code number / Brake code no.		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	65535	0
Description:	Display and setting the code number of the brake.		
p0552[0...n]	Maximum brake speed / Brake n_max		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [rpm]	340.28235E36 [rpm]	0 [rpm]
Description:	Sets the maximum brake speed.		
p0553[0...n]	Brake holding torque / Brake M_hold		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: 7_1	Unit selection: p0505	Func. diagram: -
	Min	Max	Factory setting
	0 [Nm]	340.28235E36 [Nm]	0 [Nm]
Description:	Sets the brake holding torque.		
p0554[0...n]	Brake moment of inertia / Brake J		
	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [kgm ²]	2147483647 [kgm ²]	0 [kgm ²]
Description:	Sets the brake moment of inertia.		
p0573	Inhibit automatic reference value calculation / Inhibit calc		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Setting to inhibit the calculation of reference parameters (e.g. p2000) when automatically calculating the motor and closed-loop control parameters (p0340, p3900).		
Value:	0: No 1: Yes		
Notice:	The inhibit for the reference value calculation is canceled when new motor parameters (e.g. p0305) are entered and only one drive data set exists (p0180 = 1). This is the case during initial commissioning. Once the motor and control parameters have been calculated (p0340, p3900), the inhibit for the reference value calculation is automatically re-activated.		
Note:	If value = 0: The automatic calculation (p0340, p3900) overwrites the reference parameters. If value = 1: The automatic calculation (p0340, p3900) does not overwrite the reference parameters.		

p0595	Technological unit selection / Tech unit select		
	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: C(5)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	47	1
Description:	Selects the units for the parameters of the technology controller. For p0595 = 1, 2, the reference quantity set in p0596 is not active.		
Value:	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 33: K 34: 1 rpm 35: parts/min 36: m/s 37: ft³/s 38: ft³/min 39: BTU/min 40: BTU/h 41: mbar 42: inch wg 43: ft wg 44: m wg 45: % r.h. 46: g/kg 47: ppm		
Dependency:	Only the unit of the technology controller parameters are switched over (unit group 9_1). Refer to: p0596		
Note:	When switching over from % into another unit, the following sequence applies: - set p0596 - set p0595 to the required unit		

p0596	Technological unit reference quantity / Tech unit ref qty		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.01	340.28235E36	1.00
Description:	Sets the reference quantity for the technological units. When changing over using changeover parameter p0595 to absolute units, all of the parameters involved refer to the reference quantity.		
Dependency:	Refer to: p0595		
Notice:	When changing over from one technological unit into another, or when changing the reference parameter, a changeover is not made.		
p0601[0...n]	Motor temperature sensor type / Mot_temp_sens type		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 8016
	Min	Max	Factory setting
	0	4	0
Description:	Sets the sensor type for the motor temperature monitoring.		
Value:	0: No sensor 1: PTC alarm & timer 2: KTY84 4: Bimetallic NC contact alarm & timer		
Dependency:	A thermal motor model is calculated corresponding to p0612.		
Caution:	Re p0601 = 2: If the motor temperature sensor is not connected but another encoder, then the temperature adaptation of the motor resistances must be switched out (p0620 = 0). Otherwise, in controlled-loop operation, torque errors will occur that will mean that the motor will not be able to be stopped.		
			
Note:	Re p0601 = 1: Tripping resistance = 1650 Ohm. Wire breakage and short-circuit monitoring.		
p0604[0...n]	Mot_temp_mod 2/KTY alarm threshold / Mod 2/KTY A thresh		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8016
	Min	Max	Factory setting
	0.0 [°C]	240.0 [°C]	130.0 [°C]
Description:	Sets the alarm threshold for monitoring the motor temperature for motor temperature model 2 or KTY. After the alarm threshold is exceeded, alarm A07910 is output and timer (p0606) is started. If the delay time has expired and the alarm threshold has, in the meantime, not been fallen below, then fault F07011 is output.		
Dependency:	Refer to: p0606, p0612 Refer to: F07011, A07910		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The hysteresis is 2 K. When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		

p0605[0...n]	Mot_temp_mod 1/2 threshold / Mod 1/2 threshold		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8016, 8017
	Min	Max	Factory setting
	0.0 [°C]	240.0 [°C]	145.0 [°C]
Description:	Sets the threshold for monitoring the motor temperature for motor temperature model 1/2 or KTY. Motor temperature model 1 (p0612.0 = 1): alarm threshold - Alarm A07012 is output after the alarm threshold is exceeded. Motor temperature model 2 (p0612.1 = 1) or KTY: fault threshold - Fault F07011 is output after the fault threshold is exceeded.		
Dependency:	Refer to: p0606, p0611, p0612 Refer to: F07011, A07012		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection. Motor temperature model 1: p0605 also defines the target temperature of the model for r0034 = 100 %. Therefore, p0605 has no influence on the time up to alarm A07012 being issued. The time is only determined by time constant p0611, the actual current and the reference value p0305.		
Note:	The hysteresis is 2 K. When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
p0606[0...n]	Mot_temp_mod 2/KTY timer / Mod 2/KTY t_timer		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 8016
	Min	Max	Factory setting
	0.000 [s]	600.000 [s]	0.000 [s]
Description:	Sets the timer for monitoring the motor temperature for motor temperature model 2 or KTY. This timer is started when the temperature alarm threshold (p0604) is exceeded. If the timer has expired and the alarm threshold has, in the meantime, not been fallen below, then fault F07011 is output. If the temperature fault threshold (p0605) is prematurely exceeded before the timer has expired, then fault F07011 is immediately output.		
Dependency:	Refer to: p0604, p0605 Refer to: F07011, A07910		
Note:	With p0606 = 0 s, the timer 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, bimetallic NC contact: The timer minimum value has no special significance.		
p0607[0...n]	Temperature sensor fault timer / Sensor fault time		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 8016
	Min	Max	Factory setting
	0.000 [s]	600.000 [s]	0.100 [s]
Description:	Sets the timer between the output of alarm and fault for a temperature sensor fault. If there is a sensor fault, this timer is started. If the sensor fault is still present after the timer has expired, a corresponding fault is output.		
Notice:	The parameterized time is internally rounded-off to an integer multiple of 48 ms.		
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]	Motor overtemperature response / Mot temp response		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(3), T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 8016, 8017
	Min	Max	Factory setting
	0	12	12
Description:	Sets the system response when the motor temperature reaches the alarm threshold.		
Value:	0: No response only alarm no reduction of I_max 1: Messages, reduction of I_max 2: Messages, no reduction of I_max 12: Messages, no reduction of I_max, temperature storage		
Dependency:	Refer to: p0601, p0604, p0605, p0614, p0615 Refer to: F07011, A07012, A07910		
Note:	The I_max reduction is not executed for PTC (p0601 = 1) or bimetallic NC contact (p0601 = 4). The I_max reduction results in a lower output frequency. If value = 0: An alarm is output and I_max is not reduced. If value = 1: An alarm is output and a timer is started. A fault is output if the alarm is still active after this timer has expired. - for KTY84, the following applies: I_max. is reduced - for PTC, the following is valid: I_max. is not reduced If value = 2: An alarm is output and a timer is started. A fault is output if the alarm is still active after this timer has expired. If value = 12: Behavior is always the same as for value 2. For motor temperature monitoring without temperature sensor, when switching off, the model temperature is saved in a non-volatile fashion. When switching on, the same value (reduced by p0614) is taken into account in the model calculation. As a consequence, the UL508C specification is fulfilled.		
p0611[0...n]	I2t motor model thermal time constant / I2t mot_mod T		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1, 3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: 8017
	Min	Max	Factory setting
	0 [s]	20000 [s]	0 [s]
Description:	Sets the winding time constant. The time constant specifies the warm-up time of the cold stator winding when loaded with the motor standstill current (rated motor current, if the motor standstill current is not parameterized) up until a temperature rise of 63 % of the continuously permissible winding temperature has been reached.		
Dependency:	This parameter is only used for synchronous motors (p0300 = 2xx, 4). Refer to: r0034, p0612, p0615 Refer to: F07011, A07012, A07910		
Notice:	This parameter is automatically pre-set from the motor database for motors from the motor list (p0301). When selecting a catalog motor, this parameter cannot be changed (write protection). Information in p0300 should be carefully observed when removing write protection. When exiting commissioning, p0612 is checked, and where relevant, is preassigned to a value that matches the motor power, if a temperature sensor was not parameterized (see p0601).		
Note:	When parameter p0611 is reset to 0, then this switches out the thermal I2t motor model (refer to p0612). If no temperature sensor is parameterized, then the ambient temperature for the thermal motor model is referred to p0625.		

p0612[0...n]	Mot_temp_mod activation / Mot_temp_mod act				
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: MDS		
	Unit group: -	Unit selection: -	Func. diagram: 8017		
	Min	Max	Factory setting		
	-	-	0000 0010 0000 0010 bin		
Description:	Setting to activate the motor temperature model.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Activating motor temperature model 1 (I2t)	Yes	No	-
	01	Activate motor temperature model 2	Yes	No	-
	02	Activate motor temperature model 3	Yes	No	-
	09	Activate motor temperature model 2 expansions	Yes	No	-
Dependency:	For synchronous motors, when exiting commissioning, temperature model 1 is automatically activated if a time constant has been entered in p0611. Refer to: r0034, p0604, p0605, p0611, p0615, p0625, p0626, p0627, p0628 Refer to: F07011, A07012, A07910				
Note:	Mot_temp_mod: motor temperature model Re bit 00: This bit is used to activate/deactivate the motor temperature model for permanent-magnet synchronous motors. Re bit 01: This bit is used to activate/deactivate the motor temperature model for induction motors. Re bit 02: This bit is used to activate/deactivate the motor temperature model for 1FK7 motors without encoder. Motor temperature model 3 cannot be simultaneously activated with another motor temperature model.				

p0614[0...n]	Thermal resistance adaptation reduction factor / Therm R_adapt red		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [%]	100 [%]	30 [%]
Description:	Sets the reduction factor for the overtemperature of the thermal adaptation of the stator/rotor resistance. The value is a starting value when switching on. Internally, after switch-on, the reduction factor has no effect corresponding to the thermal time constant.		
Dependency:	Refer to: p0610		
Note:	The reduction factor is only effective for p0610 = 12, and refers to the overtemperature.		

p0615[0...n]	Mot_temp_mod 1 (I2t) fault threshold / I2t F thresh		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	0.0 [°C]	220.0 [°C]	180.0 [°C]
Description:	Sets the fault threshold for monitoring the motor temperature for motor temperature model 1 (I2t). - Fault F07011 is output after the fault threshold is exceeded. - fault threshold for r0034 = 100 % * (p0615 - 40) / (p0605 - 40).		
Dependency:	The parameter is only used for permanent-magnet synchronous motors (p0300 = 2xx). Refer to: r0034, p0611, p0612 Refer to: F07011, A07012		
Notice:	When selecting a catalog motor (p0301), this parameter is automatically pre-assigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	The hysteresis is 2 K.		

p0620[0...n]	Thermal adaptation, stator and rotor resistance / Mot therm_adapt R		
	Access level: 4	Calculated: p0340 = 1	Data type: Integer16
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2	1
Description:	Sets the thermal adaptation of the stator/primary section resistance and rotor/secondary section resistance according to r0395 and r0396.		
Value:	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. For p0620 = 2, the following applies: The stator resistance is adapted using the temperature in r0035.		
p0621[0...n]	Identification stator resistance after restart / Rst_ident Restart		
	Access level: 4	Calculated: -	Data type: Integer16
	Can be changed: C(3), T	Scaling: -	Dyn. index: MDS, p0130
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2	0
Description:	Selects the identification of the stator resistance after booting the Control Unit (only for vector control). The identification is used to measure the actual stator resistance and from the ratio of the result of motor data identification (p0350) to the matching ambient temperature (p0625) the actual mean temperature of the stator winding is calculated. The result is used to initialize the thermal motor model. p0621 = 1: Identification of the stator resistance only when the drive is powered up for the first time (pulse enable) after booting the Control Unit. p0621 = 2: Identification of the stator resistance every time the drive is powered up (pulse enable).		
Value:	0: No Rs identification 1: Rs identification after switching-on again 2: Rs identification after switching-on each time		
Dependency:	- perform motor data identification (see p1910) with cold motor. - enter ambient temperature at time of motor data identification in p0625. Refer to: p0622, r0623		
Notice:	The calculated stator temperature can only be compared with the measured value of a temperature sensor (KTY) to a certain extent, as the sensor is usually the warmest point of the stator winding, whereas the measured value of identification reflects the mean value of the stator winding. Furthermore this is a short-time measurement with limited accuracy that is performed during the magnetizing phase of the induction motor.		
Note:	The measurement is carried out: - For induction motors - When vector control is active (see p1300) - If a temperature sensor (KTY) has not been connected - When the motor is at a standstill when switched on When a flying restart is performed on a rotating motor, the temperatures of the thermal motor model are set to a third of the overtemperatures. This occurs only once, however, when the CU is booted (e.g. after a power failure). If identification is activated, the magnetizing time is determined via p0622 and not via p0346. The speed is enabled after completion of the measurement.		

p0622[0...n]	Motor excitation time for Rs_ident after powering up again / t_excit Rs_id		
	Access level: 4	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS, p0130
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [s]	20.000 [s]	0.000 [s]
Description:	Sets the excitation time of the motor for the stator resistance identification after powering up again (restart).		
Dependency:	Refer to: p0621, r0623		
Note:	<p>For p0622 < p0346 the following applies:</p> <p>If identification is activated, the magnetizing time is influenced by p0622. The speed is enabled after measurement is complete, but not before the time in p0346 has elapsed (see r0056 bit 4). The time taken for measurement also depends on the settling time of the measured current.</p> <p>For p0622 >= p0346 the following applies:</p> <p>Parameter p0622 is internally limited to the magnetizing time p0346, so that p0346 represents the maximum possible magnetizing time during identification. The entire measurement period (magnetizing plus measurement settling time plus measuring time) will always be greater than p0346.</p>		
r0623	Rs identification stator resistance after switch on again / Rs-id Rs aft sw-on		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [ohm]	- [ohm]	- [ohm]
Description:	Displays the stator resistance determined using the Rs identification after switching on again.		
Dependency:	Refer to: p0621, p0622		
p0625[0...n]	Motor ambient temperature during commissioning / Mot T_ambient		
	Access level: 3	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	-40 [°C]	80 [°C]	20 [°C]
Description:	Defines the ambient temperature of the motor for calculating the motor temperature model.		
Dependency:	Refer to: p0350, p0354		
Note:	<p>The parameters for stator and rotor resistance (p0350, p0354) refer to this temperature.</p> <p>If the thermal I2t motor model is activated for permanent-magnet synchronous motors (refer to p0611), p0625 is included in the model calculation if a temperature sensor is not being used (see p0601).</p>		
p0626[0...n]	Motor overtemperature, stator core / Mot T_over core		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_2	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	10 [K]	200 [K]	50 [K]
Description:	Defines the rated overtemperature of the stator core referred to the ambient temperature.		
Dependency:	<p>For 1LA7 motors (p0300), the parameter is pre-set as a function of p0307 and p0311.</p> <p>Refer to: p0625</p>		
Notice:	When selecting a standard induction motor listed in the catalog (p0300 > 100, p0301 > 10000), this parameter is automatically preassigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		

p0627[0...n]	Motor overtemperature, stator winding / Mot T_over stator		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_2	Unit selection: p0505	Func. diagram: 8017
	Min 15 [K]	Max 200 [K]	Factory setting 80 [K]
Description:	Defines the rated overtemperature of the stator winding referred to the ambient temperature.		
Dependency:	For 1LA7 motors (p0300), the parameter is pre-set as a function of p0307 and p0311. Refer to: p0625		
Notice:	When selecting a standard induction motor listed in the catalog (p0300 > 100, p0301 > 10000), this parameter is automatically preassigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
p0628[0...n]	Motor overtemperature rotor / Mot T_over rotor		
	Access level: 4	Calculated: p0340 = 1,2	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: 21_2	Unit selection: p0505	Func. diagram: 8017
	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:	For 1LA7 motors (p0300), the parameter is pre-set as a function of p0307 and p0311. Refer to: p0625		
Notice:	When selecting a standard induction motor listed in the catalog (p0300 > 100, p0301 > 10000), this parameter is automatically preassigned and is write protected. Information in p0300 should be carefully observed when removing write protection.		
Note:	When quick commissioning is exited with p3900 > 0, then the parameter is reset if a catalog motor has not been selected (p0300).		
r0630[0...n]	Mot_temp_mod ambient temperature / Mod T_ambient		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2006	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the ambient temperature of the motor temperature model (models 2 and 3).		
r0631[0...n]	Mot_temp_mod stator iron temperature / Mod T_stator		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2006	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min - [°C]	Max - [°C]	Factory setting - [°C]
Description:	Displays the stator iron temperature of the motor temperature model (models 2 and 3).		
Note:	For motor temperature model 1 (p0612.0 = 1), this parameter is not valid:		

r0632[0...n]	Mot_temp_mod stator winding temperature / Mod T_winding		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2006	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	- [°C]	- [°C]	- [°C]
Description:	Displays the stator winding temperature of the motor temperature model (models 2 and 3).		
Note:	For motor temperature model 1 (p0612.0 = 1), this parameter is not valid:		
r0633[0...n]	Mot_temp_mod rotor temperature / Mod rotor temp		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2006	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	- [°C]	- [°C]	- [°C]
Description:	Displays the rotor temperature of the motor temperature model (models 2 and 3).		
Note:	For motor temperature model 1 (p0612.0 = 1), this parameter is not valid:		
p0637[0...n]	Q flux flux gradient saturated / PSIQ Grad SAT		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00 [mH]	10000.00 [mH]	0.00 [mH]
Description:	The non-linear and cross-coupled quadrature axis flux functions are defined using 4 coefficients. This parameter describes the gradients of the saturated component over the quadrature axis current.		
p0640[0...n]	Current limit / Current limit		
	Access level: 2	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(1, 3), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6640
	Min	Max	Factory setting
	0.00 [Arms]	10000.00 [Arms]	0.00 [Arms]
Description:	Sets the current limit.		
Dependency:	Refer to: r0209, p0323		
Note:	<p>The parameter is part of the quick commissioning (p0010 = 1); this means that it is appropriately pre-assigned when changing p0305. The current limit p0640 is limited to r0209.</p> <p>The resulting current limit is displayed in r0067 and if required, r0067 is reduced by the thermal model of the power unit.</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. p0640 is limited to 4.0 x p0305.</p> <p>p0640 is pre-assigned for the automatic self commissioning routine (e.g. to 1.5 x p0305, with p0305 = r0207[1]).</p> <p>p0640 must be entered when commissioning the system. This is the reason that p0640 is not calculated by the automatic parameterization when exiting the quick commissioning (p3900 > 0).</p>		

p0650[0...n]	Actual motor operating hours / Mot t_oper act		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [h]	4294967295 [h]	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:	Refer to: p0651 Refer to: A01590		
Note:	The operating hours counter in p0650 can only be reset to 0. The operating hours counter only runs with drive data set 0 and 1 (DDS).		
p0651[0...n]	Motor operating hours maintenance interval / Mot t_op maint		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [h]	150000 [h]	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:	For p0651 = 0, the operating hours counter is disabled. When setting p0651 to 0, then p0650 is automatically set to 0. The operating hours counter only runs with drive data set 0 and 1 (DDS). If there is no temperature monitor, then interconnect to a fixed value. Re index 3: When the binector input is interconnected, pre-charging is switched-on independent of the magnitude of the pre-charging threshold.		
r0720[0...4]	CU number of inputs and outputs / CU I/O count		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2119
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of inputs and outputs.		
Index:	[0] = Number of digital inputs [1] = Number of digital outputs [2] = Number of digital input/outputs bidirectional [3] = Number of analog inputs [4] = Number of analog outputs		

r0722.0...11	CO/BO: CU digital inputs status / CU DI status				
	Access level: 2	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2201, 2221, 2255, 2810		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the status of the digital inputs.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (T. 5)	High	Low	-
	01	DI 1 (T. 6)	High	Low	-
	02	DI 2 (T. 7)	High	Low	-
	03	DI 3 (T. 8)	High	Low	-
	04	DI 4 (T. 16)	High	Low	-
	05	DI 5 (T. 17)	High	Low	-
	11	DI 11 (T. 3, 4) AI 0	High	Low	-
Dependency:	Refer to: r0723				
Note:	AI: Analog Input DI: Digital Input T: Terminal				

r0723.0...11	CO/BO: CU digital inputs status inverted / CU DI status inv				
	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2201, 2221, 2255		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the inverted status of the digital inputs.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DI 0 (T. 5)	High	Low	-
	01	DI 1 (T. 6)	High	Low	-
	02	DI 2 (T. 7)	High	Low	-
	03	DI 3 (T. 8)	High	Low	-
	04	DI 4 (T. 16)	High	Low	-
	05	DI 5 (T. 17)	High	Low	-
	11	DI 11 (T. 3, 4) AI 0	High	Low	-
Dependency:	Refer to: r0722				
Note:	AI: Analog Input DI: Digital Input T: Terminal				

p0724	CU digital inputs debounce time / CU DI t_debounce				
	Access level: 3	Calculated: -	Data type: FloatingPoint32		
	Can be changed: U, T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0.000 [ms]	20.000 [ms]	4.000 [ms]		
Description:	Sets the debounce time for digital inputs.				
Note:	The digital inputs are read in cyclically every 2 ms (DI 11, DI 12 every 4 ms). To debounce the signals, the set debounce time is converted into integer multiple debounce clock cycles Tp (Tp = p0724 / 2 ms). DI: Digital Input				

p0730	BI: CU signal source for terminal DO 0 / CU S_src DO 0		
	Access level: 2	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2119, 2030, 2130
	Min	Max	Factory setting
	-	-	52.3
Description:	Sets the signal source for terminal DO 0 (NO: T. 19 / NC: T. 18).		
Recommendation:	r0052.0 Ready for switching on r0052.1 Ready for operation r0052.2 Operation enabled r0052.3 Fault present r0052.4 Coast down active (OFF2) r0052.5 Quick stop active (OFF3) r0052.6 Switching on inhibited active r0052.7 Alarm present r0052.9 Control request r0052.14 Motor rotates forwards r0053.0 DC braking active r0053.1 n_act > p2167 (n_off) r0053.2 n_act <= p1080 (n_min) r0053.3 I_act > p2170 r0053.4 n_act > p2155 r0053.5 n_act <= p2155 r0053.6 n_act >= n_set r0053.10 Technology controller output at the lower limit r0053.11 Technology controller output at the upper limit		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
Note:	DO: Digital Output T: Terminal Relay output: NO = normally open, NC = normally closed		

p0731	BI: CU signal source for terminal DO 1 / CU S_src DO 1		
	Access level: 2	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2119, 2030, 2130
	Min	Max	Factory setting
	-	-	52.7
Description:	Sets the signal source for terminal DO 1 (NO: T. 21).		
Recommendation:	r0052.0 Ready for switching on r0052.1 Ready for operation r0052.2 Operation enabled r0052.3 Fault present r0052.4 Coast down active (OFF2) r0052.5 Quick stop active (OFF3) r0052.6 Switching on inhibited active r0052.7 Alarm present r0052.9 Control request r0052.14 Motor rotates forwards r0053.0 DC braking active r0053.1 n_act > p2167 (n_off) r0053.2 n_act <= p1080 (n_min) r0053.3 I_act > p2170 r0053.4 n_act > p2155		

2 Parameters

2.2 List of parameters

r0053.5 n_act <= p2155

r0053.6 n_act >= n_set

r0053.10 Technology controller output at the lower limit

r0053.11 Technology controller output at the upper limit

Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

Note: DO: Digital Output

T: Terminal

Relay output: NO = normally open, NC = normally closed

r0747

CU digital outputs status / CU DO status

Access level: 3

Calculated: -

Data type: Unsigned32

Can be changed: -

Scaling: -

Dyn. index: -

Unit group: -

Unit selection: -

Func. diagram: 2130, 2131, 2132, 2133

Min

Max

Factory setting

-

-

-

Description: Displays the status of digital outputs.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DO 0 (NO: T. 19 / NC: T. 18)	High	Low	-
	01	DO 1 (NO: T. 21)	High	Low	-

Note: DO: Digital Output

T: Terminal

Relay output: NO = normally open, NC = normally closed

Inversion using p0748 has been taken into account.

p0748

CU invert digital outputs / CU DO inv

Access level: 3

Calculated: -

Data type: Unsigned32

Can be changed: U, T

Scaling: -

Dyn. index: -

Unit group: -

Unit selection: -

Func. diagram: 2201, 2202, 2240, 2242

Min

Max

Factory setting

-

-

0000 bin

Description: Setting to invert the signals at the digital outputs.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DO 0 (NO: T. 19 / NC: T. 18)	Inverted	Not inverted	-
	01	DO 1 (NO: T. 21)	Inverted	Not inverted	-

Note: DO: Digital Output

T: Terminal

Relay output: NO = normally open, NC = normally closed

r0751.0...9

BO: CU analog inputs status word / CU AI status word

Access level: 3

Calculated: -

Data type: Unsigned16

Can be changed: -

Scaling: -

Dyn. index: -

Unit group: -

Unit selection: -

Func. diagram: 2250, 2251

Min

Max

Factory setting

-

-

-

Description: Display and binector output for the status of the analog inputs.


Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Analog input AI0 wire breakage	Yes	No	-
	01	Analog input AI1 wire breakage	Yes	No	-
	08	Analog input AI0 no wire breakage	Yes	No	-
	09	Analog input AI1 no wire breakage	Yes	No	-

Note: AI: Analog Input

r0752[0...1]	CO: CU analog inputs input voltage/current actual / CU AI U/I_inp act		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p0514	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	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] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Dependency:	The type of analog input AIx (voltage or current input) is set using p0756. Refer to: p0756		
Note:	AI: Analog Input T: Terminal		
p0753[0...1]	CU analog inputs smoothing time constant / CU AI T_smooth		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	0.0 [ms]	1000.0 [ms]	0.0 [ms]
Description:	Sets the smoothing time constant of the 1st-order low pass filter for the analog inputs.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	AI: Analog Input T: Terminal		
r0755[0...1]	CO: CU analog inputs actual value in percent / CU AI value in %		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Displays the currently referred input value of the analog inputs. When interconnected, the signals are referred to the reference quantities p200x and p205x.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	AI: Analog Input T: Terminal		
p0756[0...1]	CU analog inputs type / CU AI type		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	0	8	[0] 4 [1] 4
Description:	Sets the type of analog inputs. p0756[0...1] = 0, 1, 4 corresponds to a voltage input (r0752, p0757, p0759 are displayed in V). p0756[0...1] = 2, 3 corresponds to a current input (r0752, p0757, p0759 are displayed in mA). In addition, the associated DIP switch must be set. For the voltage input, DIP switch AI0/1 must be set to "U". For the current input, DIP switch AI0/1 or AI2 must be set to "I".		

2 Parameters

2.2 List of parameters

Value:	0: Unipolar voltage input (0 V ... +10 V) 1: Unipolar voltage input monitored (+2 V ... +10 V) 2: Unipolar current input (0 mA ... +20 mA) 3: Unipolar current input monitored (+4 mA to +20 mA) 4: Bipolar voltage input (-10 V ... +10 V) 8: No sensor connected
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)
Warning: 	The maximum voltage difference between analog input terminals AI+, AI-, and the ground must not exceed 35 V. If the system is operated when the load resistor is switched on (DIP switch set to "I"), the voltage between differential inputs AI+ and AI- must not exceed 10 V or the injected 80 mA current otherwise the input will be damaged.
Note:	When changing p0756, the parameters of the scaling characteristic (p0757, p0758, p0759, p0760) are overwritten with the following default values: For p0756 = 0, 4, p0757 is set to 0.0 V, p0758 = 0.0 %, p0759 = 10.0 V and p0760 = 100.0 %. For p0756 = 1, p0757 is set to 2.0 V, p0758 = 0.0 %, p0759 = 10.0 V and p0760 = 100.0 %. For p0756 = 2, p0757 is set to 0.0 mA, p0758 = 0.0 %, p0759 = 20.0 mA and p0760 = 100.0 %. For p0756 = 3, p0757 is set to 4.0 mA, p0758 = 0.0 %, p0759 = 20.0 mA and p0760 = 100.0 %.

p0757[0...1]	CU analog inputs characteristic value x1 / CU AI char x1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	-50.000	160.000	0.000
Description:	Sets the scaling characteristic for the analog inputs. The scaling characteristic for the analog inputs is defined using 2 points. This parameter specifies the x coordinate (V, mA) of the 1st value pair of the characteristic.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	The parameters for the characteristic do not have a limiting effect.		

p0758[0...1]	CU analog inputs characteristic value y1 / CU AI char y1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	-1000.00 [%]	1000.00 [%]	0.00 [%]
Description:	Sets the scaling characteristic for the analog inputs. The scaling characteristic for the analog inputs is defined using 2 points. This parameter specifies the y coordinate (percentage) of the 1st value pair of the characteristic.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	The parameters for the characteristic do not have a limiting effect.		

p0759[0...1]	CU analog inputs characteristic value x2 / CU AI char x2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	-50.000	160.000	10.000
Description:	Sets the scaling characteristic for the analog inputs. The scaling characteristic for the analog inputs is defined using 2 points. This parameter specifies the x coordinate (V, mA) of the 2nd value pair of the characteristic.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	The parameters for the characteristic do not have a limiting effect.		

p0760[0...1]	CU analog inputs characteristic value y2 / CU AI char y2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568, 9576
	Min	Max	Factory setting
	-1000.00 [%]	1000.00 [%]	100.00 [%]
Description:	Sets the scaling characteristic for the analog inputs.		
	The scaling characteristic for the analog inputs is defined using 2 points.		
	This parameter specifies the y coordinate (percentage) of the 2nd value pair of the characteristic.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	The parameters for the characteristic do not have a limiting effect.		

p0761[0...1]	CU analog inputs wire breakage monitoring response threshold / CU WireBrkThresh		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568
	Min	Max	Factory setting
	0.00	20.00	2.00
Description:	Sets the response threshold for the wire breakage monitoring of the analog inputs.		
	The unit for the parameter value depends on the set analog input type.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Dependency:	For the following analog input type, the wire breakage monitoring is active:		
	p0756[0...1] = 1 (unipolar voltage input monitored (+2 V ... +10 V)), unit [V]		
	p0756[0...1] = 3 (unipolar current input monitored (+4 mA ... +20 mA)), unit [mA]		
	Refer to: p0756		
Note:	AI: Analog Input		
	When p0761 = 0, wire breakage monitoring is not carried out.		

p0762[0...1]	CU analog inputs wire breakage monitoring delay time / CU wire brk t_del		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9566, 9568
	Min	Max	Factory setting
	0 [ms]	1000 [ms]	100 [ms]
Description:	Sets the delay time for the wire breakage monitoring of the analog inputs.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Note:	AI: Analog Input		

p0764[0...1]	CU analog inputs dead zone / CU AI dead zone		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2251
	Min	Max	Factory setting
	0.000	20.000	0.000
Description:	Determines the width of the dead zone at the analog input.		
	Analog input type unipolar (e.g. 0 ... +10 V):		
	The dead zone starts with the characteristic value x1/y1 (p0757/p0758).		
	Analog input type bipolar (e.g. -10 V ... +10 V):		
	The dead zone is located at the symmetrical center between characteristic value x1/y1 (p0757/p0758) and x2/y2 (p0759/p0760). The set value doubles the dead zone.		

2 Parameters

2.2 List of parameters

Index: [0] = AI0 (T. 3/4)
[1] = AI1 (T. 10/11)
Note: AI: Analog Input
T: Terminal

p0771[0...1]	CI: CU analog outputs signal source / CU AO S_src		
Access level: 2	Calculated: -	Data type: U32 / FloatingPoint32	
Can be changed: U, T	Scaling: PERCENT	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 2261	
Min	Max	Factory setting	
-	-	[0] 21[0]	
		[1] 27[0]	

Description: Sets the signal source for the analog outputs.

Index: [0] = AO0 (T 12/13)
[1] = AO1 (T 26/27)

Note: AO: Analog Output
T: Terminal

r0772[0...1]	CU analog outputs output value currently referred / CU AO outp act ref		
Access level: 3	Calculated: -	Data type: FloatingPoint32	
Can be changed: -	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 9572	
Min	Max	Factory setting	
- [%]	- [%]	- [%]	

Description: Displays the actual referred output value of the analog outputs.

Index: [0] = AO0 (T 12/13)
[1] = AO1 (T 26/27)

Note: AO: Analog Output
T: Terminal

p0773[0...1]	CU analog outputs smoothing time constant / CU AO T_smooth		
Access level: 2	Calculated: -	Data type: FloatingPoint32	
Can be changed: U, T	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 9572	
Min	Max	Factory setting	
0.0 [ms]	1000.0 [ms]	0.0 [ms]	

Description: Sets the smoothing time constant of the 1st-order low pass filter for the analog outputs.

Index: [0] = AO0 (T 12/13)
[1] = AO1 (T 26/27)

Note: AO: Analog Output
T: Terminal

r0774[0...1]	CU analog outputs output voltage/current actual / CU AO U/I_outp		
Access level: 2	Calculated: -	Data type: FloatingPoint32	
Can be changed: -	Scaling: p2001	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 9572	
Min	Max	Factory setting	
-	-	-	

Description: Displays the actual output voltage or output current at the analog outputs.

Index: [0] = AO0 (T 12/13)
[1] = AO1 (T 26/27)

Dependency: Refer to: p0776

Note: AO: Analog Output
T: Terminal

p0775[0...1]	CU analog outputs activate absolute value generation / CU AO absVal act		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9572
	Min	Max	Factory setting
	0	1	0
Description:	Activates the absolute value generation for the analog outputs.		
Value:	0: No absolute value generation 1: Absolute value generation switched in		
Index:	[0] = AO0 (T 12/13) [1] = AO1 (T 26/27)		
Note:	AO: Analog Output T: Terminal		
p0776[0...1]	CU analog outputs type / CU AO type		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9572
	Min	Max	Factory setting
	0	2	0
Description:	Sets the analog output type. p0776[x] = 1 corresponds to a voltage output (p0774, p0778, p0780 are displayed in V). p0776[x] = 0, 2 corresponds to a current output (p0774, p0778, p0780 are displayed in mA).		
Value:	0: Current output (0 mA ... +20 mA) 1: Voltage output (0 V ... +10 V) 2: Current output (+4 mA ... +20 mA)		
Index:	[0] = AO0 (T 12/13) [1] = AO1 (T 26/27)		
Note:	When changing p0776, the parameters of the scaling characteristic (p0777, p0778, p0779, p0780) are overwritten with the following default values: For p0776 = 0, p0777 is set to 0.0 %, p0778 = 0.0 mA, p0779 = 100.0 % and p0780 to 20.0 mA. For p0776 = 1, p0777 is set to 0.0 %, p0778 = 0.0 V, p0779 = 100.0 % and p0780 to 10.0 V. For p0776 = 2, p0777 is set to 0.0 %, p0778 = 4.0 mA, p0779 = 100.0 % and p0780 to 20.0 mA.		
p0777[0...1]	CU analog outputs characteristic value x1 / CU AO char x1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9572
	Min	Max	Factory setting
	-1000.00 [%]	1000.00 [%]	0.00 [%]
Description:	Sets the scaling characteristic for the analog outputs. The scaling 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] = AO0 (T 12/13) [1] = AO1 (T 26/27)		
Dependency:	Refer to: p0776		
Notice:	This parameter is automatically overwritten when changing p0776 (type of analog outputs).		
Note:	The parameters for the characteristic do not have a limiting effect.		

p0778[0...1]	CU analog outputs characteristic value y1 / CU AO char y1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9572
	Min	Max	Factory setting
	-20.000 [V]	20.000 [V]	0.000 [V]
Description:	Sets the scaling characteristic for the analog outputs. The scaling 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] = AO0 (T 12/13) [1] = AO1 (T 26/27)		
Dependency:	The unit of this parameter (V or mA) depends on the analog output type. Refer to: p0776		
Notice:	This parameter is automatically overwritten when changing p0776 (type of analog outputs).		
Note:	The parameters for the characteristic do not have a limiting effect.		
p0779[0...1]	CU analog outputs characteristic value x2 / CU AO char x2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9572
	Min	Max	Factory setting
	-1000.00 [%]	1000.00 [%]	100.00 [%]
Description:	Sets the scaling characteristic for the analog outputs. The scaling 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] = AO0 (T 12/13) [1] = AO1 (T 26/27)		
Dependency:	Refer to: p0776		
Notice:	This parameter is automatically overwritten when changing p0776 (type of analog outputs).		
Note:	The parameters for the characteristic do not have a limiting effect.		
p0780[0...1]	CU analog outputs characteristic value y2 / CU AO char y2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9572
	Min	Max	Factory setting
	-20.000 [V]	20.000 [V]	20.000 [V]
Description:	Sets the scaling characteristic for the analog outputs. The scaling 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] = AO0 (T 12/13) [1] = AO1 (T 26/27)		
Dependency:	The unit of this parameter (V or mA) depends on the analog output type. Refer to: p0776		
Notice:	This parameter is automatically overwritten when changing p0776 (type of analog outputs).		
Note:	The parameters for the characteristic do not have a limiting effect.		

p0782[0...1]						BI: CU analog outputs invert signal source / CU AO inv S_src									
			Access level: 3			Calculated: -			Data type: U32 / Binary						
			Can be changed: U, T			Scaling: -			Dyn. index: -						
			Unit group: -			Unit selection: -			Func. diagram: 9572						
			Min			Max			Factory setting						
			-			-			0						
Description:						Sets the signal source to invert the analog output signals.									
Index:						[0] = AO0 (T 12/13) [1] = AO1 (T 26/27)									
Note:						AO: Analog Output T: Terminal									
<hr/>															
r0785.0...1						BO: CU analog outputs status word / CU AO ZSW									
			Access level: 3			Calculated: -			Data type: Unsigned16						
			Can be changed: -			Scaling: -			Dyn. index: -						
			Unit group: -			Unit selection: -			Func. diagram: 9572						
			Min			Max			Factory setting						
			-			-			-						
Description:						Displays the status of analog outputs.									
Bit field:						Bit		Signal name		1 signal		0 signal		FP	
						00		AO 0 negative		Yes		No		-	
						01		AO 1 negative		Yes		No		-	
Note:						AO: Analog Output									
<hr/>															
p0791[0...1]						CO: Fieldbus analog outputs / Fieldbus AO									
G120C_USS			Access level: 3			Calculated: -			Data type: FloatingPoint32						
			Can be changed: U, T			Scaling: PERCENT			Dyn. index: -						
			Unit group: -			Unit selection: -			Func. diagram: -						
			Min			Max			Factory setting						
			-200.000 [%]			200.000 [%]			0.000 [%]						
Description:						Setting and connector output to control the analog outputs via fieldbus.									
Index:						[0] = AO0 (T 12/13) [1] = AO1 (T 26/27)									
Dependency:						Refer to: p0771									
Note:						AO: Analog Output The following interconnections must be established to control the analog outputs via fieldbus: - AO 0: p0771[0] with p0791[0] - AO 1: p0771[1] with p0791[1]									
<hr/>															
p0795						CU digital inputs simulation mode / CU DI simulation									
			Access level: 3			Calculated: -			Data type: Unsigned32						
			Can be changed: U, T			Scaling: -			Dyn. index: -						
			Unit group: -			Unit selection: -			Func. diagram: 2201, 2202, 2220, 2221, 2255, 2256						
			Min			Max			Factory setting						
			-			-			0000 0000 0000 0000 bin						
Description:						Sets the simulation mode for digital inputs.									
Bit field:						Bit		Signal name		1 signal		0 signal		FP	
						00		DI 0 (T. 5)		Simulation		Terminal eval		-	
						01		DI 1 (T. 6)		Simulation		Terminal eval		-	
						02		DI 2 (T. 7)		Simulation		Terminal eval		-	
						03		DI 3 (T. 8)		Simulation		Terminal eval		-	
						04		DI 4 (T. 16)		Simulation		Terminal eval		-	

2 Parameters

2.2 List of parameters

	05	DI 5 (T. 17)	Simulation	Terminal eval	-
	11	DI 11 (T. 3, 4) AI 0	Simulation	Terminal eval	-
	12	DI 12 (T. 10, 11) AI 1	Simulation	Terminal eval	-
Dependency:	The setpoint for the input signals is specified using p0796. Refer to: p0796				
Note:	This parameter is not saved when data is backed up (p0971). DI: Digital Input T: Terminal				

p0796	CU digital inputs simulation mode setpoint / CU DI simul setp				
	Access level: 3		Calculated: -	Data type: Unsigned32	
	Can be changed: U, T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 2201, 2202, 2220, 2221, 2255, 2256	
	Min		Max	Factory setting	
	-		-	0000 0000 0000 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	FP
	00	DI 0 (T. 5)	High	Low	-
	01	DI 1 (T. 6)	High	Low	-
	02	DI 2 (T. 7)	High	Low	-
	03	DI 3 (T. 8)	High	Low	-
	04	DI 4 (T. 16)	High	Low	-
	05	DI 5 (T. 17)	High	Low	-
	11	DI 11 (T. 3, 4) AI 0	High	Low	-
	12	DI 12 (T. 10, 11) AI 1	High	Low	-
Dependency:	The simulation of a digital input is selected using p0795. Refer to: p0795				
Note:	This parameter is not saved when data is backed up (p0971). AI: Analog Input DI: Digital Input T: Terminal				

p0797[0...1]	CU analog inputs simulation mode / CU AI sim_mode		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the simulation mode for the analog inputs.		
Value:	0: Terminal evaluation for analog input x 1: Simulation for analog input x		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Dependency:	The setpoint for the input voltage is specified via p0798. Refer to: p0798		
Note:	This parameter is not saved when data is backed up (p0971). AI: Analog Input		

p0798[0...1]	CU analog inputs simulation mode setpoint / CU AI sim setp		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-50.000	2000.000	0.000
Description:	Sets the setpoint for the input value in the simulation mode of the analog inputs.		
Index:	[0] = AI0 (T. 3/4) [1] = AI1 (T. 10/11)		
Dependency:	The simulation of an analog input is selected using p0797. If AI x is parameterized as a voltage input (p0756), the setpoint is a voltage in V. If AI x is parameterized as a current input (p0756), the setpoint is a current in mA. Refer to: p0756, p0797		
Note:	This parameter is not saved when data is backed up (p0971). AI: Analog Input		
p0802	Data transfer: memory card as source/target / mem_card src/targ		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	100	0
Description:	Sets the number for data transfer of a parameter backup from/to memory card. Transfer from memory card to device memory (p0804 = 1): - Sets the source of parameter backup (e.g. p0802 = 48 --> PS048xxx.ACX is the source). Transfer from non-volatile device memory to memory card (p0804 = 2): - Sets the target of parameter backup (e.g. p0802 = 23 --> PS023xxx.ACX is the target).		
Dependency:	Refer to: p0803, p0804		
Notice:	If the data between the volatile and non-volatile device memories differ, then it may be necessary to save the data on the memory card in a non-volatile fashion prior to the transfer (e.g. p0971 = 1).		
p0803	Data transfer: device memory as source/target / Dev_mem src/targ		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	12	0
Description:	Sets the number for data transfer of a parameter backup from/to device memory. Transfer from memory card to device memory (p0804 = 1): - Sets the target of the parameter backup (e.g. p0803 = 10 --> PS010xxx.ACX is the target). Transfer from non-volatile device memory to memory card (p0804 = 2): - Sets the source of the parameter backup (e.g. p0803 = 11 --> PS011xxx.ACX is the source).		
Value:	0: Source/target standard 10: Source/target with setting 10 11: Source/target with setting 11 12: Source/target with setting 12		
Dependency:	Refer to: p0802, p0804		
Notice:	If the data between the volatile and non-volatile device memories differ, then it may be necessary to save the data on the memory card in a non-volatile fashion prior to the transfer (e.g. p0971 = 1).		

p0804	Data transfer start / Data transf start		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1100	0
Description:	<p>Sets the transfer direction and start of data transfer between the memory card and non-volatile device memory.</p> <p>Example 1:</p> <p>The parameter backup is to be transferred from the device memory to the memory card with setting 0. The parameter backup is to be stored on the memory card with setting 22.</p> <p>p0802 = 22 (parameter backup stored on memory card as target with setting 22)</p> <p>p0803 = 0 (parameter backup stored in device memory as source with setting 0)</p> <p>p0804 = 2 (start data transfer from device memory to memory card)</p> <p>--> PS000xxx.ACX is transferred from device memory to memory card and stored as PS022xxx.ACX.</p> <p>Example 2:</p> <p>The parameter backup is to be transferred from the memory card to the device memory with setting 22. The parameter backup is to be stored in the device memory as setting 0.</p> <p>p0802 = 22 (parameter backup stored on memory card as source with setting 22)</p> <p>p0803 = 0 (parameter backup stored in device memory as target with setting 0)</p> <p>p0804 = 1 (start data transfer from memory card to device memory)</p> <p>--> PS022xxx.ACX is transferred from memory card to device memory and stored as PS000xxx.ACX.</p> <p>Example 3 (only supported for PROFIBUS/PROFINET):</p> <p>The PROFIBUS or PROFINET device master data (GSD) should be transferred from the device memory to the memory card.</p> <p>p0802 = (not relevant)</p> <p>p0803 = (not relevant)</p> <p>p0804 = 12 (start transferring the GSD files to the memory card)</p> <p>--> The GSD files are transferred from the device memory to the memory card and stored in the /SIEMENS/SINAMICS/DATA/CFG directory.</p>		
Value:	<p>0: Inactive</p> <p>1: Memory card to device memory</p> <p>2: Device memory to memory card</p> <p>1001: File on memory card cannot be opened</p> <p>1002: File in device memory cannot be opened</p> <p>1003: Memory card not found</p> <p>1100: File cannot be transferred</p>		
Dependency:	Refer to: p0802, p0803		
Notice:	<p>The memory card must not be removed while data is being transferred.</p> <p>For p0014 = 1, the following applies:</p> <p>After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.</p>		
Note:	<p>If a parameter backup with setting 0 is detected on the memory card when the Control Unit is switched on (PS000xxx.ACX), this is transferred automatically to the device memory.</p> <p>When the memory card is inserted, a parameter backup with setting 0 (PS000xxx.ACX) is automatically written to the memory card when the parameters are saved in a non-volatile memory (e.g. by means of "Copy RAM to ROM").</p> <p>Once the data has been successfully transferred, this parameter is automatically reset to 0. If an error occurs, the parameter is set to a value > 1000. Possible fault causes:</p> <p>p0804 = 1001:</p> <p>The parameter backup set in p0802 as the source on the memory card does not exist or there is not sufficient memory space available on the memory card.</p> <p>p0804 = 1002:</p> <p>The parameter backup set in p0803 as the source in the device memory does not exist or there is not sufficient memory space available in the device memory.</p> <p>p0804 = 1003:</p> <p>No memory card has been inserted.</p>		

p0804	Data transfer start / Data transf start		
G120C_DP	Access level: 3	Calculated: -	Data type: Integer16
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1100	0
Description:	<p>Sets the transfer direction and start of data transfer between the memory card and non-volatile device memory.</p> <p>Example 1:</p> <p>The parameter backup is to be transferred from the device memory to the memory card with setting 0. The parameter backup is to be stored on the memory card with setting 22.</p> <p>p0802 = 22 (parameter backup stored on memory card as target with setting 22)</p> <p>p0803 = 0 (parameter backup stored in device memory as source with setting 0)</p> <p>p0804 = 2 (start data transfer from device memory to memory card)</p> <p>--> PS000xxx.ACX is transferred from device memory to memory card and stored as PS022xxx.ACX.</p> <p>Example 2:</p> <p>The parameter backup is to be transferred from the memory card to the device memory with setting 22. The parameter backup is to be stored in the device memory as setting 0.</p> <p>p0802 = 22 (parameter backup stored on memory card as source with setting 22)</p> <p>p0803 = 0 (parameter backup stored in device memory as target with setting 0)</p> <p>p0804 = 1 (start data transfer from memory card to device memory)</p> <p>--> PS022xxx.ACX is transferred from memory card to device memory and stored as PS000xxx.ACX.</p> <p>Example 3 (only supported for PROFIBUS/PROFINET):</p> <p>The PROFIBUS or PROFINET device master data (GSD) should be transferred from the device memory to the memory card.</p> <p>p0802 = (not relevant)</p> <p>p0803 = (not relevant)</p> <p>p0804 = 12 (start transferring the GSD files to the memory card)</p> <p>--> The GSD files are transferred from the device memory to the memory card and stored in the /SIEMENS/SINAMICS/DATA/CFG directory.</p>		
Value:	<p>0: Inactive</p> <p>1: Memory card to device memory</p> <p>2: Device memory to memory card</p> <p>12: Device memory (GSD files) to memory card</p> <p>1001: File on memory card cannot be opened</p> <p>1002: File in device memory cannot be opened</p> <p>1003: Memory card not found</p> <p>1100: File cannot be transferred</p>		
Dependency:	Refer to: p0802, p0803		
Notice:	<p>The memory card must not be removed while data is being transferred.</p> <p>For p0014 = 1, the following applies:</p> <p>After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.</p>		
Note:	<p>If a parameter backup with setting 0 is detected on the memory card when the Control Unit is switched on (PS000xxx.ACX), this is transferred automatically to the device memory.</p> <p>When the memory card is inserted, a parameter backup with setting 0 (PS000xxx.ACX) is automatically written to the memory card when the parameters are saved in a non-volatile memory (e.g. by means of "Copy RAM to ROM").</p> <p>Once the data has been successfully transferred, this parameter is automatically reset to 0. If an error occurs, the parameter is set to a value > 1000. Possible fault causes:</p> <p>p0804 = 1001:</p> <p>The parameter backup set in p0802 as the source on the memory card does not exist or there is not sufficient memory space available on the memory card.</p> <p>p0804 = 1002:</p> <p>The parameter backup set in p0803 as the source in the device memory does not exist or there is not sufficient memory space available in the device memory.</p> <p>p0804 = 1003:</p> <p>No memory card has been inserted.</p>		

p0806	BI: Inhibit master control / PcCtrl inhibit				
	Access level: 3		Calculated: -	Data type: U32 / Binary	
	Can be changed: T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min		Max	Factory setting	
	-		-	0	
Description: Sets the signal source to block the master control.					
Dependency: Refer to: r0807					
Note: The commissioning software (drive control panel) uses the master control, for example.					

r0807.0	BO: Master control active / PcCtrl active				
	Access level: 3		Calculated: -	Data type: Unsigned8	
	Can be changed: -		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min		Max	Factory setting	
	-		-	-	
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	FP
	00	Master control active	Yes	No	3030, 6031
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 commissioning software (drive control panel) uses the master control, for example.					

p0809[0...2]	Copy Command Data Set CDS / Copy CDS				
	Access level: 2		Calculated: -	Data type: Unsigned8	
	Can be changed: T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 8560	
	Min		Max	Factory setting	
	0		3	0	
Description: Copies one Command Data Set (CDS) into another.					
Index: [0] = Source Command Data Set [1] = Target Command Data Set [2] = Start copying procedure					
Dependency: Refer to: r3996					
Notice: When the command data sets are copied, short-term communication interruptions may occur.					
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		
G120C_CAN	Access level: 2	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8560
	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, r0836		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
Note:	The 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.		
p0810	BI: Command data set selection CDS bit 0 / CDS select., bit 0		
G120C_DP	Access level: 2	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8560
	Min	Max	Factory setting
	-	-	722.3
Description:	Sets the signal source to select the Command Data Set bit 0 (CDS bit 0).		
Dependency:	Refer to: r0050, r0836		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
Note:	The 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		
	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: C(15)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8565
	Min	Max	Factory setting
	0	1	0
Description:	Copies one Drive Data Set (DDS) into another.		
Index:	[0] = Source Drive Data Set [1] = Target Drive Data Set [2] = Start copying procedure		
Dependency:	Refer to: r3996		
Notice:	When the drive data sets are copied, short-term communication interruptions may occur.		
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		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: C(15), T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 8565
	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, p0826, r0837		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		


p0826[0...n]	Motor changeover motor number / Mot_chng mot No.				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: C(3), T	Scaling: -	Dyn. index: MDS		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0	1	0		
Description:	Sets the freely-assignable motor number for the drive data set changeover. If the same motor is driven by different drive data sets, the same motor number must also be entered in these data sets. If the motor is also switched with the drive data set, different motor numbers must be used. In this case, the data set can only be switched when the pulse inhibit is set.				
Note:	If the motor numbers are identical, the same thermal motor model is used for calculation after data set changeover. If different motor numbers are used, different models are also used for calculating (the inactive motor cools down in each case).				

r0835.2...8	CO/BO: Data set changeover status word / DDS_ZSW				
	Access level: 2	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8575		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the status word for the drive data set changeover.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	02	Internal parameter calculation active	Yes	No	-
	04	Armature short circuit active	Yes	No	-
	05	Identification running	Yes	No	-
	07	Rotating measurement running	Yes	No	-
	08	Motor data identification running	Yes	No	-
Note:	Re bit 02: A data set changeover is delayed by the time required for the internal parameter calculation. Re bit 04: A data set changeover is only carried out when the armature short circuit is not activated. Re bit 05: A data set changeover is only carried out when pole position identification is not running. Re bit 07: A data set changeover is only carried out when rotating measurement is not running. Re bit 08: A data set changeover is only carried out when motor data identification is not running.				

r0836.0...1	CO/BO: Command Data Set CDS selected / CDS selected				
	Access level: 3	Calculated: -	Data type: Unsigned8		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8560		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the command data set (CDS) selected via the binector input.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	CDS select. bit 0	ON	OFF	-
	01	CDS select. bit 1	ON	OFF	-
Dependency:	Refer to: r0050, p0810				
Note:	Command data sets are selected via binector input p0810 and following. The currently effective command data set is displayed in r0050.				

r0837.0		CO/BO: Drive Data Set DDS selected / DDS selected			
	Access level: 3	Calculated: -	Data type: Unsigned8		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8565		
	Min	Max	Factory setting		
	-	-	-		
Description:		Displays the drive data set (DDS) selected via the binector input.			
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DDS select. bit 0	ON	OFF	-
Dependency:		Refer to: r0051, p0820			
Note:		Drive data sets are selected via binector input p0820 and following. The currently effective drive data set is displayed in r0051. If there is only one data set, then a value of 0 is displayed in this parameter and not the selection via binector inputs.			

p0840[0...n]		BI: ON / OFF (OFF1) / ON / OFF (OFF1)			
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary		
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170		
	Unit group: -	Unit selection: -	Func. diagram: 2501, 2512		
	Min	Max	Factory setting		
	-	-	[0] 722.0		
			[1] 0		
Description:		Sets the signal source for the command "ON/OFF (OFF1)". For the PROFIdrive profile, this command corresponds to control word 1 bit 0 (STW1.0).			
Recommendation:		When the setting for this binector input is changed, the motor can only be switched on by means of an appropriate signal change of the source.			
Dependency:		Refer to: p1055, p1056			
Caution:		When "master control from PC" is activated, this binector input is ineffective.			
					
Notice:		For binector input p0840 = 0 signal, the motor can be moved, jogging using binector input p1055 or p1056. The command "ON/OFF (OFF1)" can be issued using binector input p0840 or p1055/p1056. For binector input p0840 = 0 signal, the switch-on inhibit is acknowledged. Only the signal source that originally powered up can also power down again. The parameter may be protected as a result of p0922 or p2079 and cannot be changed.			
Note:		For drives with closed-loop speed control (p1300 = 20), the following applies: - BI: p0840 = 0 signal: OFF1 (braking with the ramp-function generator, then pulse suppression and switch-on inhibit) - BI: p0840 = 0/1 signal: ON (pulses can be enabled)			

p0840[0...n]		BI: ON / OFF (OFF1) / ON / OFF (OFF1)			
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary		
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170		
	Unit group: -	Unit selection: -	Func. diagram: 2501, 2512		
	Min	Max	Factory setting		
	-	-	[0] 2090.0		
			[1] 0		
Description:		Sets the signal source for the command "ON/OFF (OFF1)". For the PROFIdrive profile, this command corresponds to control word 1 bit 0 (STW1.0).			
Recommendation:		When the setting for this binector input is changed, the motor can only be switched on by means of an appropriate signal change of the source.			
Dependency:		Refer to: p1055, p1056			
Caution:		When "master control from PC" is activated, this binector input is ineffective.			
					

2 Parameters

2.2 List of parameters

- Notice:** For binector input p0840 = 0 signal, the motor can be moved, jogging using binector input p1055 or p1056.
The command "ON/OFF (OFF1)" can be issued using binector input p0840 or p1055/p1056.
For binector input p0840 = 0 signal, the switch-on inhibit is acknowledged.
Only the signal source that originally powered up can also power down again.
The parameter may be protected as a result of p0922 or p2079 and cannot be changed.
- Note:** For drives with closed-loop speed control (p1300 = 20), the following applies:
- BI: p0840 = 0 signal: OFF1 (braking with the ramp-function generator, then pulse suppression and switch-on inhibit)
- BI: p0840 = 0/1 signal: ON (pulses can be enabled)

p0844[0...n]	BI: No coast-down / coast-down (OFF2) signal source 1 / OFF2 S_src 1		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 8720, 8820, 8920
	Min	Max	Factory setting
	-	-	1

- Description:** Sets the first signal source for the command "No coast down/coast down (OFF2)".
The following signals are AND'ed:
- BI: p0844 "No coast-down / coast-down (OFF2) signal source 1"
- BI: p0845 "No coast-down / coast-down (OFF2) signal source 2"
For the PROFIdrive profile, the result of the AND logic operation corresponds to control word 1 bit 1 (STW1.1).
BI: p0844 = 0 signal or BI: p0845 = 0 signal
- OFF2 (immediate pulse suppression and switch on inhibit)
BI: p0844 = 1 signal and BI: p0845 = 1 signal
- No OFF2 (enable is possible)

Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.


p0844[0...n]	BI: No coast-down / coast-down (OFF2) signal source 1 / OFF2 S_src 1		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 8720, 8820, 8920
	Min	Max	Factory setting
	-	-	[0] 2090.1 [1] 1


- Description:** Sets the first signal source for the command "No coast down/coast down (OFF2)".
The following signals are AND'ed:
- BI: p0844 "No coast-down / coast-down (OFF2) signal source 1"
- BI: p0845 "No coast-down / coast-down (OFF2) signal source 2"
For the PROFIdrive profile, the result of the AND logic operation corresponds to control word 1 bit 1 (STW1.1).
BI: p0844 = 0 signal or BI: p0845 = 0 signal
- OFF2 (immediate pulse suppression and switch on inhibit)
BI: p0844 = 1 signal and BI: p0845 = 1 signal
- No OFF2 (enable is possible)

Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p0845[0...n]		BI: No coast-down / coast-down (OFF2) signal source 2 / OFF2 S_src 2	
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 8720, 8820, 8920
	Min	Max	Factory setting
	-	-	1
Description:		Sets the second signal source for the command "No coast down/coast down (OFF2)". The following signals are AND'ed: - BI: p0844 "No coast-down / coast-down (OFF2) signal source 1" - BI: p0845 "No coast-down / coast-down (OFF2) signal source 2" For the PROFIdrive profile, the result of the AND logic operation corresponds to control word 1 bit 1 (STW1.1). BI: p0844 = 0 signal or BI: p0845 = 0 signal - OFF2 (immediate pulse suppression and switch on inhibit) BI: p0844 = 1 signal and BI: p0845 = 1 signal - No OFF2 (enable is possible)	
Caution:		When "master control from PC" is activated, this binector input is effective.	
			

p0848[0...n]		BI: No Quick Stop / Quick Stop (OFF3) signal source 1 / OFF3 S_src 1	
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	1
Description:		Sets the first signal source for the command "No quick stop/quick stop (OFF3)". The following signals are AND'ed: - BI: p0848 "No quick stop / quick stop (OFF3) signal source 1" - BI: p0849 "No quick stop / quick stop (OFF3) signal source 2" For the PROFIdrive profile, the result of the AND logic operation corresponds to control word 1 bit 2 (STW1.2). BI: p0848 = 0 signal or BI: p0849 = 0 signal - OFF3 (braking along the OFF3 ramp (p1135), then pulse suppression and switch on inhibit) BI: p0848 = 1 signal and BI: p0849 = 1 signal - No OFF3 (enable is possible)	
Caution:		When "master control from PC" is activated, this binector input is ineffective.	
			
Notice:		The parameter may be protected as a result of p0922 or p2079 and cannot be changed.	
Note:		For drives with closed-loop torque control (activated using p1501), the following applies: BI: p0848 = 0 signal: - No dedicated braking response, but pulse suppression when standstill is detected (p1226, p1227).	

p0848[0...n]		BI: No Quick Stop / Quick Stop (OFF3) signal source 1 / OFF3 S_src 1	
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	[0] 2090.2
			[1] 1
Description:		Sets the first signal source for the command "No quick stop/quick stop (OFF3)". The following signals are AND'ed: - BI: p0848 "No quick stop / quick stop (OFF3) signal source 1" - BI: p0849 "No quick stop / quick stop (OFF3) signal source 2"	

For the PROFIdrive profile, the result of the AND logic operation corresponds to control word 1 bit 2 (STW1.2).

BI: p0848 = 0 signal or BI: p0849 = 0 signal

- OFF3 (braking along the OFF3 ramp (p1135), then pulse suppression and switch on inhibit)

BI: p0848 = 1 signal and BI: p0849 = 1 signal

- No OFF3 (enable is possible)

Caution:



Notice:

The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

Note:

For drives with closed-loop torque control (activated using p1501), the following applies:

BI: p0848 = 0 signal:

- No dedicated braking response, but pulse suppression when standstill is detected (p1226, p1227).

p0849[0...n]

BI: No Quick Stop / Quick Stop (OFF3) signal source 2 / OFF3 S_src 2

Access level: 3

Calculated: -

Data type: U32 / Binary

Can be changed: T

Scaling: -

Dyn. index: CDS, p0170

Unit group: -

Unit selection: -

Func. diagram: 2501

Min

Max

Factory setting

-

-

1

Description:

Sets the second signal source for the command "No quick stop/quick stop (OFF3)".

The following signals are AND'ed:

- BI: p0848 "No quick stop / quick stop (OFF3) signal source 1"

- BI: p0849 "No quick stop / quick stop (OFF3) signal source 2"

For the PROFIdrive profile, the result of the AND logic operation corresponds to control word 1 bit 2 (STW1.2).

BI: p0848 = 0 signal or BI: p0849 = 0 signal

- OFF3 (braking along the OFF3 ramp (p1135), then pulse suppression and switch on inhibit)

BI: p0848 = 1 signal and BI: p0849 = 1 signal

- No OFF3 (enable is possible)

Caution:



Note:

For drives with closed-loop torque control (activated using p1501), the following applies:

BI: p0849 = 0 signal:

- No dedicated braking response, but pulse suppression when standstill is detected (p1226, p1227).

p0852[0...n]

BI: Enable operation/inhibit operation / Operation enable

G120C_CAN

Access level: 3

Calculated: -

Data type: U32 / Binary

G120C_USS

Can be changed: T

Scaling: -

Dyn. index: CDS, p0170

Unit group: -

Unit selection: -

Func. diagram: 2501

Min

Max

Factory setting

-

-

1

Description:

Sets the signal source for the command "enable operation/inhibit operation".

For the PROFIdrive profile, this command corresponds to control word 1 bit 3 (STW1.3).

BI: p0852 = 0 signal

Inhibit operation (suppress pulses).

BI: p0852 = 1 signal




Enable operation (pulses can be enabled).

Caution:



Notice:

The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p0852[0...n]	BI: Enable operation/inhibit operation / Operation enable		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	[0] 2090.3
			[1] 1
Description:	Sets the signal source for the command "enable operation/inhibit operation". For the PROFIdrive profile, this command corresponds to control word 1 bit 3 (STW1.3). BI: p0852 = 0 signal Inhibit operation (suppress pulses). BI: p0852 = 1 signal Enable operation (pulses can be enabled).		
Caution:	When "master control from PC" is activated, this binector input is ineffective.		
			
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p0854[0...n]	BI: Control by PLC/no control by PLC / Master ctrl by PLC		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the command "control by PLC/no control by PLC". For the PROFIdrive profile, this command corresponds to control word 1 bit 10 (STW1.10). BI: p0854 = 0 signal No control by PLC BI: p0854 = 1 signal Master control by PLC.		
Caution:	When "master control from PC" is activated, this binector input is ineffective.		
			
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
Note:	This bit is used to initiate a response for the drives when the control fails (F07220). If there is no control available, then binector input p0854 should be set to 1. If a control is available, then STW1.10 must be set to 1 (PZD1) so that the received data is updated. This applies regardless of the setting in p0854 and even in the case of free telegram configuration (p0922 = 999).		
p0854[0...n]	BI: Control by PLC/no control by PLC / Master ctrl by PLC		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	[0] 2090.10
			[1] 1
Description:	Sets the signal source for the command "control by PLC/no control by PLC". For the PROFIdrive profile, this command corresponds to control word 1 bit 10 (STW1.10). BI: p0854 = 0 signal No control by PLC BI: p0854 = 1 signal Master control by PLC.		
Caution:	When "master control from PC" is activated, this binector input is ineffective.		
			

2 Parameters

2.2 List of parameters

Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

Note: This bit is used to initiate a response for the drives when the control fails (F07220). If there is no control available, then binector input p0854 should be set to 1.

If a control is available, then STW1.10 must be set to 1 (PZD1) so that the received data is updated. This applies regardless of the setting in p0854 and even in the case of free telegram configuration (p0922 = 999).

p0855[0...n]	BI: Unconditionally release holding brake / Uncond open brake		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 2701
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the command "unconditionally open holding brake".		
Dependency:	Refer to: p0858		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
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 / n_ctrl enable		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 2701
	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 an existing brake will be closed. If "enable speed controller" is withdrawn, the pulses are not suppressed.		

p0857	Power unit monitoring time / PU t_monit		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8760, 8864, 8964
	Min	Max	Factory setting
	100.0 [ms]	60000.0 [ms]	10000.0 [ms]
Description:	Sets the monitoring time for the power unit. 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, fault F07802 is output.		
Dependency:	Refer to: F07802, F30027		
Notice:	The maximum time to pre-charge the DC link is monitored in the power unit and cannot be changed. The maximum pre-charging duration depends on the power unit. The monitoring time for the pre-charging is started after the ON command (BI: p0840 = 0/1 signal). Fault F30027 is output when the maximum pre-charging duration is exceeded.		
Note:	The factory setting for p0857 depends on 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 the corresponding fault.		

p0858[0...n]	BI: Unconditionally close holding brake / Uncond close brake				
	Access level: 3		Calculated: -	Data type: U32 / Binary	
	Can be changed: T		Scaling: -	Dyn. index: CDS, p0170	
	Unit group: -		Unit selection: -	Func. diagram: 2501, 2701	
	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 contactor feedback signal / Line contact feedb				
	Access level: 3		Calculated: -	Data type: U32 / Binary	
	Can be changed: T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 2634	
	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					
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				
	Access level: 3		Calculated: -	Data type: FloatingPoint32	
	Can be changed: T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 2634	
	Min	Max	Factory setting		
0 [ms]	5000 [ms]	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					
Note: The monitoring function is disabled for the factory setting of p0860.					

r0863.0...1	CO/BO: Drive coupling status word/control word / CoupleZSW/STW				
	Access level: 3		Calculated: -	Data type: Unsigned16	
	Can be changed: -		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting		
-	-	-			
Description: Display and BICO output for the status word and control word of the drive coupling.					
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Closed-loop control operation	Yes	No	-
	01	Energize contactor	Yes	No	2634
Note: Re bit 01: Bit 1 is used to control an external line contactor.					

p0867	Power unit main contactor holding time after OFF1 / PU t_MC after OFF1				
	Access level: 3		Calculated: -	Data type: FloatingPoint32	
	Can be changed: T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min		Max	Factory setting	
	0.0 [ms]		500.0 [ms]	50.0 [ms]	
Description:	Sets the main contactor holding time after OFF1				
Dependency:	Refer to: p0869				
Note:	After withdrawing the OFF1 enable (source of p0840), the main contactor is opened after the main contactor holding time has elapsed.				
	For p0869 = 1 (keep main contactor closed for STO), after withdrawing STO, the switch-on inhibit must be acknowledged via the source of p0840 = 0 (OFF1) – and before the main contactor holding time expires, should go back to 1, otherwise the main contactor will open.				
	When operating a drive connected to SINUMERIK, which only closes the main contactor with the OFF1 command (blocksize, chassis), p0867 should be set as a minimum to 50 ms.				
p0869	Sequence control configuration / Seq_ctrl config				
	Access level: 3		Calculated: -	Data type: Unsigned16	
	Can be changed: T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: -	
	Min		Max	Factory setting	
	-		-	0000 bin	
Description:	Sets the configuration for the sequence control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Keep main contactor closed for STO	Yes	No	-
Dependency:	Refer to: p0867				
Note:	Re bit 00:				
	After withdrawing the OFF1 enable (source of p0840), the main contactor is opened after the main contactor holding time has elapsed.				
	For p0869.0 = 1, after withdrawing STO, the switch-on inhibit must be acknowledged via the source of p0840 = 0 (OFF1) – and before the main contactor holding time expires (p0867), should go back to 1, otherwise the main contactor will open.				
r0898.0...14	CO/BO: Control word sequence control / STW seq_ctrl				
	Access level: 2		Calculated: -	Data type: Unsigned16	
	Can be changed: -		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 2501	
	Min		Max	Factory setting	
	-		-	-	
Description:	Display and connector output for the control word of 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	Operation enable	Yes	No	-
	04	Ramp-function generator enable	Yes	No	-
	05	Continue ramp-function generator	Yes	No	-
	06	Speed setpoint enable	Yes	No	-
	07	Command open brake	Yes	No	-
	08	Jog 1	Yes	No	3001
	09	Jog 2	Yes	No	3001
	10	Master control by PLC	Yes	No	-
	12	Speed controller enable	Yes	No	-
	14	Command close brake	Yes	No	-
Note:	OC: Operating condition				

r0899.0...13	CO/BO: Status word sequence control / ZSW seq_ctrl				
	Access level: 2	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2503		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for the status word of the sequence control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Rdy for switch on	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 Quick Stop active	OFF3 inactive	OFF3 active	-
	06	Switching on inhibited active	Yes	No	-
	07	Drive ready	Yes	No	-
	08	Controller enable	Yes	No	-
	09	Control request	Yes	No	-
	11	Pulses enabled	Yes	No	-
	12	Open holding brake	Yes	No	-
	13	Command close holding brake	Yes	No	-
Note:	Re bits 00, 01, 02, 04, 05, 06, 09: For PROFIdrive, these signals are used for status word 1.				

p0918	PROFIBUS address / PB address				
G120C_DP	Access level: 2	Calculated: -	Data type: Unsigned16		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2401, 2410		
	Min	Max	Factory setting		
	1	126	126		
Description:	Displays or sets the PROFIBUS address for PROFIBUS interface on the Control Unit. The address can be set as follows: 1) Using the DIP switch on 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 are 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.				
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. For p0014 = 0, the following applies: Before a changed setting becomes permanently effective, a non-volatile RAM to ROM data save is required. To do this, set p0971 = 1 or p0014 = 1.				
Note:	Permissible PROFIBUS addresses: 1 ... 126 Address 126 is used for commissioning. Every PROFIBUS address change only becomes effective after a POWER ON.				

p0922	PROFIdrive PZD telegram selection / PZD telegr_sel		
G120C_DP	Access level: 1	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: C(1), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2401, 2420
	Min	Max	Factory setting
	1	999	1
Description:	Sets the send and receive telegram.		
Value:	1: Standard telegram 1, PZD-2/2 20: Standard telegram 20, PZD-2/6 352: SIEMENS telegram 352, PZD-6/6 353: SIEMENS telegram 353, PZD-2/2, PKW-4/4 354: SIEMENS telegram 354, PZD-6/6, PKW-4/4 999: Free telegram configuration with BICO		
Dependency:	Refer to: p2038 Refer to: F01505		
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 after setting value 999.		
r0944	CO: Counter for fault buffer changes / Fault buff change		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8060
	Min	Max	Factory setting
	-	-	-
Description:	Display and connector output for the counter for changes of the fault buffer. 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		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8060
	Min	Max	Factory setting
	-	-	-
Description:	Displays the numbers of faults that have occurred.		
Dependency:	Refer to: r0947, r0948, r0949, r2109, r2130, r2133, r2136, r3120, r3122		
Notice:	The properties of the fault buffer should be taken from the corresponding product documentation.		
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 ... r0945[15], r0949[15], r0948[15], r2109[15] --> 1st acknowledged fault case, fault 8 ... r0945[56], r0949[56], r0948[56], r2109[56] --> 7th acknowledged fault case, fault 1 ... r0945[63], r0949[63], r0948[63], r2109[63] --> 7th acknowledged fault case, fault 8		

r0946[0...65534] Fault code list / Fault code list

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8060
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.

r0947[0...63] Fault number / Fault number

Access level: 2	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8050, 8060
Min	Max	Factory setting
-	-	-

Description: This parameter is identical to r0945.

r0948[0...63] Fault time received in milliseconds / t_fault rcv ms

Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8050, 8060
Min	Max	Factory setting
- [ms]	- [ms]	- [ms]

Description: Displays the system runtime in milliseconds when the fault occurred.

Dependency: Refer to: r0945, r0947, r0949, r2109, r2130, r2133, r2136

Notice: The time comprises r2130 (days) and r0948 (milliseconds).

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

The structure of the fault buffer and the assignment of the indices is shown in r0945.

When the parameter is read via PROFIdrive, the TimeDifference data type applies.

r0949[0...63] Fault value / Fault value

Access level: 3	Calculated: -	Data type: Integer32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8050, 8060
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, r3120, r3122

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

The structure of the fault buffer and the assignment of the indices is shown in r0945.

p0952 Fault cases counter / Fault cases qty

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 6700, 8060
Min	Max	Factory setting
0	65535	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 / PB baud rate		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	Displays the corresponding value for the PROFIBUS baud rate.		
Value:	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		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	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] = device type, see below r0964[2] = 403 --> first part of the firmware version V04.03 (for second part, refer to index 6) r0964[3] = 2010 --> year 2010 r0964[4] = 1705 --> 17th of May r0964[5] = 2 --> 2 drive objects r0964[6] = 200 --> second part, firmware version (complete version: V04.03.02.00) Device type: r0964[1] = 6510 --> SINAMICS G120C_DP r0964[1] = 6511 --> SINAMICS G120C_PN r0964[1] = 6512 --> SINAMICS G120C_CAN r0964[1] = 6513 --> SINAMICS G120C_USS/MB		

r0965	PROFIdrive profile number / PD profile number		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the PROFIdrive profile number and profile version. Constant value = 0329 hex. Byte 1: Profile number = 03 hex = PROFIdrive profile Byte 2: Profile version = 29 hex = Version 4.1		
Note:	When the parameter is read via PROFIdrive, the Octet String 2 data type applies.		
p0969	System runtime relative / t_System relative		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8060
	Min	Max	Factory setting
	0 [ms]	4294967295 [ms]	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. When the parameter is read via PROFIdrive, the TimeDifference data type applies.		
p0970	Reset drive parameters / Drive par reset		
	Access level: 1	Calculated: -	Data type: Unsigned16
	Can be changed: C(1, 30)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	300	0
Description:	The parameter is used to initiate the reset of the drive parameters. Parameters p0100, p0205 are not reset. The following motor parameters are defined in accordance with the power unit: p0300 ... p0311. When downloading settings 10, 11, 12, the buffer memory mode is automatically deactivated (p0014 = 0).		
Value:	0: Inactive 1: Start a parameter reset 3: Start download of volatile parameters from RAM 5: Starts a safety parameter reset 10: Start loading the parameters saved with p0971=10 11: Start loading the parameters saved with p0971=11 12: Start loading the parameters saved with p0971=12 100: Start a BICO interconnection reset 300: Only Siemens int		
Dependency:	Refer to: F01659		
Notice:	After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. When the buffer memory is active (see p0014), the actual parameters are backed up from RAM to ROM when a parameter set is loaded (p0970 = 10, 11, 12). Peculiarities of communication via PROFIBUS DP: - Communication with Class 1 masters (e.g. S7 controllers) is interrupted. - Communication with Class 2 masters (e.g. STARTER) is retained.		
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. Parameter reset is completed with p0970 = 0 and r3996[0] = 0.		

For p0970 = 1 the following applies:

If a Safety Integrated function is parameterized (p9601), then the safety parameters are not reset. In this case, an error message (F01659) is output with fault value 2.

The following generally applies:

One index of parameters p2100, p2101, p2126, p2127 is not reset, if a parameterized message is precisely active in this index.

p0971**Save parameters / Save par**

Access level: 1	Calculated: -	Data type: Unsigned16
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	12	0

Description: Setting to save parameters in the non-volatile memory.

When saving, only the adjustable parameters intended to be saved are taken into account.

Value:

- 0: Inactive
- 1: Save drive object
- 10: Save in non-volatile memory as setting 10
- 11: Save in non-volatile memory as setting 11
- 12: Save in non-volatile memory as setting 12

Dependency: Refer to: p0970, p1960, p3845, r3996

Caution: If a memory card (optional) is inserted – and the USB interface is not used, the following applies:



The parameters are also saved on the card and therefore overwrite any existing data!

Notice: 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).

Writing to parameters is inhibited while saving.

The progress while saving is displayed in r3996.

Note: Parameters saved with p0971 = 10, 11, 12 can be loaded again with p0970 = 10, 11 or 12.

Identification and maintenance data (I&M data, p8806 and following) are only saved for p0971 = 1.

p0972**Drive unit reset / Drv_unit reset**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	3	0

Description: Sets the required procedure to execute a hardware reset for the drive unit.

Value:

- 0: Inactive
- 1: Hardware-Reset immediate
- 2: Hardware reset preparation
- 3: Hardware reset after cyclic communication has failed

Danger: It must be absolutely ensured that the system is in a safe condition.



The memory card/device memory of the Control Unit must not be accessed.

Note: If value = 1:

Reset is immediately executed and communications interrupted.

After communications have been established, check the reset operation (refer below).

If value = 2:

Help to check the reset operation.

Firstly, set p0972 = 2 and then read back. Secondly, set p0972 = 1 (it is possible that this request is possibly no longer acknowledged). The communication is then interrupted.

After communications have been established, check the reset operation (refer below).

If value = 3:

The reset is executed after interrupting cyclic communication. This setting is used to implement a synchronized reset by a control for several drive units.

If cyclic communication is not active, then the reset is immediately executed.

After communications have been established, check the reset operation (refer below).

To check the reset operation:

After the drive unit has been restarted and communications have been established, read p0972 and check the following:

p0972 = 0? --> The reset was successfully executed.

p0972 > 0? --> The reset was not executed.

r0980[0...299]	List of existing parameters 1 / List avail par 1		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the parameters that exist for this drive.		
Dependency:	Refer to: r0981, r0989		
Note:	<p>The existing parameters are displayed in indices 0 to 298. If an index contains the value 0, then the list ends here. In a long list, index 299 contains the parameter number at which position the list continues.</p> <p>This list consists solely of the following parameters: r0980[0...299], r0981[0...299] ... r0989[0...299]</p> <p>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).</p>		
r0981[0...299]	List of existing parameters 2 / List avail par 2		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the parameters that exist for this drive.		
Dependency:	Refer to: r0980, r0989		
Note:	<p>The existing parameters are displayed in indices 0 to 298. If an index contains the value 0, then the list ends here. In a long list, index 299 contains the parameter number at which position the list continues.</p> <p>This list consists solely of the following parameters: r0980[0...299], r0981[0...299] ... r0989[0...299]</p> <p>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).</p>		
r0989[0...299]	List of existing parameters 10 / List avail par 10		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the parameters that exist for this drive.		
Dependency:	Refer to: r0980, r0981		
Note:	<p>The existing parameters are displayed in indices 0 to 298. If an index contains the value 0, then the list ends here.</p> <p>This list consists solely of the following parameters: r0980[0...299], r0981[0...299] ... r0989[0...299]</p> <p>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).</p>		

r0990[0...99]	List of modified parameters 1 / List chang par 1		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays those parameters with a value other than the factory setting for this drive.		
Dependency:	Refer to: r0991, r0999		
Note:	<p>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.</p> <p>This list consists solely of the following parameters: r0990[0...99], r0991[0...99] ... r0999[0...99]</p> <p>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).</p>		
r0991[0...99]	List of modified parameters 2 / List chang par 2		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays those parameters with a value other than the factory setting for this drive.		
Dependency:	Refer to: r0990, r0999		
Note:	<p>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.</p> <p>This list consists solely of the following parameters: r0990[0...99], r0991[0...99] ... r0999[0...99]</p> <p>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).</p>		
r0999[0...99]	List of modified parameters 10 / List chang par 10		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays those parameters with a value other than the factory setting for this drive.		
Dependency:	Refer to: r0990, r0991		
Note:	<p>Modified parameters are displayed in indices 0 to 98. If an index contains the value 0, then the list ends here.</p> <p>This list consists solely of the following parameters: r0990[0...99], r0991[0...99] ... r0999[0...99]</p> <p>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).</p>		
p1000[0...n]	Speed setpoint selection / n_set sel		
G120C_CAN	Access level: 1	Calculated: -	Data type: Integer16
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	200	2
Description:	<p>Sets the source for the speed setpoint.</p> <p>For single-digit values, the following applies:</p> <p>The value specifies the main setpoint.</p>		

For double-digit values, the following applies:

The left-hand digit specifies the supplementary setpoint, the right-hand digit the main setpoint.

Example:

Value = 26

--> The analog setpoint (2) supplies the supplementary setpoint.

--> The fieldbus (6) supplies the main setpoint.

Value:	0:	No main setpoint
	1:	Motorized potentiometer
	2:	Analog setpoint
	3:	Fixed speed setpoint
	6:	Fieldbus
	10:	Motor potentiometer + no main setpoint
	11:	Motor potentiometer + motor potentiometer
	12:	Motor potentiometer + analog setpoint
	13:	Motor potentiometer + fixed speed setpoint
	16:	Motor potentiometer + fieldbus
	20:	Analog setpoint + no main setpoint
	21:	Analog setpoint + motor potentiometer
	22:	Analog setpoint + analog setpoint
	23:	Analog setpoint + fixed speed setpoint
	26:	Analog setpoint + fieldbus
	30:	Fixed speed setpoint + no main setpoint
	31:	Fixed speed setpoint + motor potentiometer
	32:	Fixed speed setpoint + analog setpoint
	33:	Fixed speed setpoint + fixed speed setpoint
	36:	Fixed speed setpoint + fieldbus
	60:	Fieldbus + no main setpoint
	61:	Fieldbus + motor potentiometer
	62:	Fieldbus + analog setpoint
	63:	Fieldbus + fixed speed setpoint
	66:	Fieldbus+fieldbus
	200:	Analog output connection

Dependency: When changing this parameter, the following settings are influenced:

Refer to: p1070, p1071, p1075, p1076

Caution:



If p1000 is selected as the main setpoint of the fieldbus, the following BICO interconnection is set automatically:
p2051[1] = r0063

Notice:

The parameter is possibly protected as a result of p0922.

For PROFIBUS/PROFINET Control Units, the following applies: The parameter can be freely set by setting p0922 = 999.

When executing a specific macro, the corresponding programmed settings are made and become active.

p1000[0...n]

Speed setpoint selection / n_set sel

G120C_DP	Access level: 1	Calculated: -	Data type: Integer16
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	200	6

Description:

Sets the source for the speed setpoint.

For single-digit values, the following applies:

The value specifies the main setpoint.

For double-digit values, the following applies:

The left-hand digit specifies the supplementary setpoint, the right-hand digit the main setpoint.

Example:

Value = 26

--> The analog setpoint (2) supplies the supplementary setpoint.

--> The fieldbus (6) supplies the main setpoint.

Value:

0:	No main setpoint
1:	Motorized potentiometer
2:	Analog setpoint

3:	Fixed speed setpoint
6:	Fieldbus
10:	Motor potentiometer + no main setpoint
11:	Motor potentiometer + motor potentiometer
12:	Motor potentiometer + analog setpoint
13:	Motor potentiometer + fixed speed setpoint
16:	Motor potentiometer + fieldbus
20:	Analog setpoint + no main setpoint
21:	Analog setpoint + motor potentiometer
22:	Analog setpoint + analog setpoint
23:	Analog setpoint + fixed speed setpoint
26:	Analog setpoint + fieldbus
30:	Fixed speed setpoint + no main setpoint
31:	Fixed speed setpoint + motor potentiometer
32:	Fixed speed setpoint + analog setpoint
33:	Fixed speed setpoint + fixed speed setpoint
36:	Fixed speed setpoint + fieldbus
60:	Fieldbus + no main setpoint
61:	Fieldbus + motor potentiometer
62:	Fieldbus + analog setpoint
63:	Fieldbus + fixed speed setpoint
66:	Fieldbus+fieldbus
200:	Analog output connection

Dependency:

When changing this parameter, the following settings are influenced:

Refer to: p1070, p1071, p1075, p1076

Caution:



If p1000 is selected as the main setpoint of the fieldbus, the following BICO interconnection is set automatically:
p2051[1] = r0063

Notice:

The parameter is possibly protected as a result of p0922.

For PROFIBUS/PROFINET Control Units, the following applies: The parameter can be freely set by setting p0922 = 999.

When executing a specific macro, the corresponding programmed settings are made and become active.

p1001[0...n]

CO: Fixed speed setpoint 1 / n_set_fixed 1

Access level: 2	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
Min	Max	Factory setting
-210000.000 [rpm]	210000.000 [rpm]	0.000 [rpm]

Description:

Setting and connector output for fixed speed setpoint 1.

Dependency:

Refer to: p1020, p1021, p1022, p1023, r1024

Notice:

A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.

p1002[0...n]

CO: Fixed speed setpoint 2 / n_set_fixed 2

Access level: 2	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
Min	Max	Factory setting
-210000.000 [rpm]	210000.000 [rpm]	0.000 [rpm]

Description:

Setting and connector output for fixed speed setpoint 2.

Dependency:

Refer to: p1020, p1021, p1022, p1023, r1024

Notice:

A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.

p1003[0...n]	CO: Fixed speed setpoint 3 / n_set_fixed 3		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 3.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1004[0...n]	CO: Fixed speed setpoint 4 / n_set_fixed 4		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 4.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1005[0...n]	CO: Fixed speed setpoint 5 / n_set_fixed 5		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 5.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1006[0...n]	CO: Fixed speed setpoint 6 / n_set_fixed 6		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 6.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1007[0...n]	CO: Fixed speed setpoint 7 / n_set_fixed 7		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 7.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		

p1008[0...n]	CO: Fixed speed setpoint 8 / n_set_fixed 8		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 8.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1009[0...n]	CO: Fixed speed setpoint 9 / n_set_fixed 9		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 9.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1010[0...n]	CO: Fixed speed setpoint 10 / n_set_fixed 10		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 10.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1011[0...n]	CO: Fixed speed setpoint 11 / n_set_fixed 11		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 11.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1012[0...n]	CO: Fixed speed setpoint 12 / n_set_fixed 12		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 12.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		

p1013[0...n]	CO: Fixed speed setpoint 13 / n_set_fixed 13		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 13.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1014[0...n]	CO: Fixed speed setpoint 14 / n_set_fixed 14		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 14.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1015[0...n]	CO: Fixed speed setpoint 15 / n_set_fixed 15		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3010
	Min -210000.000 [rpm]	Max 210000.000 [rpm]	Factory setting 0.000 [rpm]
Description:	Setting and connector output for fixed speed setpoint 15.		
Dependency:	Refer to: p1020, p1021, p1022, p1023, r1024		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
p1016	Fixed speed setpoint select mode / n_set_fix select		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 3010, 3011
	Min 1	Max 2	Factory setting 1
Description:	Sets the mode to select the fixed speed setpoint.		
Value:	1: Direct 2: Binary		
Note:	Re p1016 = 1:		
	In this mode, the setpoint is entered via the fixed speed setpoints p1001 ... p1004.		
	Up to 16 different setpoints are obtained by adding the individual fixed speed setpoints.		
	Re p1016 = 2:		
	In this mode, the setpoint is entered via the fixed speed setpoints p1001 ... p1015.		

p1020[0...n]	BI: Fixed speed setpoint selection Bit 0 / n_set_fixed Bit 0		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3010, 3011
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for selecting the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Sets the values for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1021, p1022, p1023		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0), then r1024 = 0 (setpoint = 0).		
p1021[0...n]	BI: Fixed speed setpoint selection Bit 1 / n_set_fixed Bit 1		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3010, 3011
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for selecting the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Sets the values for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1022, p1023		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0), then r1024 = 0 (setpoint = 0).		
p1022[0...n]	BI: Fixed speed setpoint selection Bit 2 / n_set_fixed Bit 2		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3010, 3011
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for selecting the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Sets the values for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1021, p1023		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0), then r1024 = 0 (setpoint = 0).		
p1023[0...n]	BI: Fixed speed setpoint selection Bit 3 / n_set_fixed Bit 3		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3010, 3011
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for selecting the fixed speed setpoint.		
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Sets the values for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1020, p1021, p1022		
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0), then r1024 = 0 (setpoint = 0).		

r1024	CO: Fixed speed setpoint effective / n_set_fixed eff				
	Access level: 3	Calculated: -	Data type: FloatingPoint32		
	Can be changed: -	Scaling: p2000	Dyn. index: -		
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3001, 3010, 3011		
	Min	Max	Factory setting		
	- [rpm]	- [rpm]	- [rpm]		
Description:	Display and connector output for the selected and active 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 the main setpoint (CI: p1070 = r1024).				
Dependency:	Selects the required fixed speed setpoint using p1020 ... p1023. Sets the values for the fixed speed setpoints 1 ... 15 using p1001 ... p1015. Refer to: p1070				
Note:	If a fixed speed setpoint has not been selected (p1020 ... p1023 = 0), then r1024 = 0 (setpoint = 0).				

r1025.0	BO: Fixed speed setpoint status / n_setp_fix status				
	Access level: 3	Calculated: -	Data type: Unsigned8		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and binector output for the status when selecting the fixed speed setpoints.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed speed setpoint selected	Yes	No	3011
Dependency:	Refer to: p1016				
Note:	Re bit 00: When the fixed speed setpoints are directly selected (p1016 = 1), this bit is set if at least 1 fixed speed setpoint is selected.				

p1030[0...n]	Motorized potentiometer configuration / Mop configuration				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: 3020		
	Min	Max	Factory setting		
	-	-	0000 0110 bin		
Description:	Sets the configuration for the motorized potentiometer.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Data save active	Yes	No	-
	01	Automatic mode ramp-function generator active	Yes	No	-
	02	Initial rounding-off active	Yes	No	-
	03	Save in NVRAM active	Yes	No	-
	04	Ramp-function generator always active	Yes	No	-
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.				
Note:	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, the ramp-function generator is always active.				

2 Parameters

2.2 List of parameters

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).

Re bit 04:

When the bit is set, the ramp-function generator is computed independent of the pulse enable. The actual output value of the motorized potentiometer is always in r1050.

p1035[0...n]	BI: Motorized potentiometer setpoint raise / Mop raise		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3020
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to continually increase the setpoint for the motorized potentiometer. The setpoint change (CO: r1050) depends on the set ramp-up time (p1047) and the duration of the signal that is present (BI: p1035).		
Dependency:	Refer to: p1036		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p1035[0...n]	BI: Motorized potentiometer setpoint raise / Mop raise		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3020
	Min	Max	Factory setting
	-	-	[0] 2090.13 [1] 0
Description:	Sets the signal source to continually increase the setpoint for the motorized potentiometer. The setpoint change (CO: r1050) depends on the set ramp-up time (p1047) and the duration of the signal that is present (BI: p1035).		
Dependency:	Refer to: p1036		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p1036[0...n]	BI: Motorized potentiometer lower setpoint / Mop lower		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3020
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to continuously lower the setpoint for the motorized potentiometer. The setpoint change (CO: r1050) depends on the set ramp-down time (p1048) and the duration of the signal that is present (BI: p1036).		
Dependency:	Refer to: p1035		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		

p1036[0...n]	BI: Motorized potentiometer lower setpoint / Mop lower		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3020
	Min	Max	Factory setting
	-	-	[0] 2090.14
			[1] 0
Description:	Sets the signal source to continuously lower the setpoint for the motorized potentiometer. The setpoint change (CO: r1050) depends on the set ramp-down time (p1048) and the duration of the signal that is present (BI: p1036).		
Dependency:	Refer to: p1035		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p1037[0...n]	Motorized potentiometer maximum speed / MotP n_max		
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3020
	Min	Max	Factory setting
	-210000.000 [rpm]	210000.000 [rpm]	0.000 [rpm]
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 (see function diagram 3020).		
p1038[0...n]	Motorized potentiometer minimum speed / MotP n_min		
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3020
	Min	Max	Factory setting
	-210000.000 [rpm]	210000.000 [rpm]	0.000 [rpm]
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 (see function diagram 3020).		
p1040[0...n]	Motorized potentiometer starting value / Mop start value		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3020
	Min	Max	Factory setting
	-210000.000 [rpm]	210000.000 [rpm]	0.000 [rpm]
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		
p1043[0...n]	BI: Motorized potentiometer accept setting value / MotP acc set val		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3020
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to accept the setting value for the motorized potentiometer.		
Dependency:	Refer to: p1044		

Note: The setting value (CI: p1044) becomes effective for a 0/1 edge of the setting command (BI: p1043).

p1044[0...n]	CI: Motorized potentiometer setting value / Mop set val		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2000	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3020
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the setting value for the motorized potentiometer.		
Dependency:	Refer to: p1043		
Note:	The setting value (CI: p1044) becomes effective for a 0/1 edge of the setting command (BI: p1043).		
r1045	CO: Mot. potentiometer speed setp. in front of ramp-fct. gen. / Mop n_set bef RFG		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3020
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3020
	Min	Max	Factory setting
	0.000 [s]	1000.000 [s]	10.000 [s]
Description:	Sets the ramp-up time for the internal ramp-function generator for the motorized potentiometer. The setpoint is changed from 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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3020
	Min	Max	Factory setting
	0.000 [s]	1000.000 [s]	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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3001, 3020
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
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, suppress 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		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 3030
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for jog 1.		
Recommendation:	When the setting for this binector input is changed, the motor can only be switched on by means of an appropriate 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.		
p1055[0...n]	BI: Jog bit 0 / Jog bit 0		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 3030
	Min	Max	Factory setting
	-	-	[0] 0 [1] 722.0
Description:	Sets the signal source for jog 1.		
Recommendation:	When the setting for this binector input is changed, the motor can only be switched on by means of an appropriate 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		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501, 3030
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for jog 2.		
Recommendation:	When the setting for this binector input is changed, the motor can only be switched on by means of an appropriate signal change of the source.		

2 Parameters

2.2 List of parameters

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.

p1056[0...n]

BI: Jog bit 1 / Jog bit 1

G120C_DP
G120C_PN

Access level: 3

Can be changed: T

Unit group: -

Min

-

Calculated: -

Scaling: -

Unit selection: -

Max

-

Data type: U32 / Binary

Dyn. index: CDS, p0170

Func. diagram: 2501, 3030

Factory setting

[0] 0

[1] 722.1

Description: Sets the signal source for jog 2.

Recommendation: When the setting for this binector input is changed, the motor can only be switched on by means of an appropriate 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

Access level: 2

Can be changed: T

Unit group: 3_1

Min

-210000.000 [rpm]

Calculated: -

Scaling: -

Unit selection: p0505

Max

210000.000 [rpm]

Data type: FloatingPoint32

Dyn. index: DDS, p0180

Func. diagram: 3001, 3030

Factory setting

150.000 [rpm]

Description: Sets the speed for jog 1.

Jogging (JOG) is level-triggered, and allows the motor to be incrementally traversed.

Dependency: Refer to: p1055, p1056

p1059[0...n]

Jog 2 speed setpoint / Jog 2 n_set

Access level: 2

Can be changed: T

Unit group: 3_1

Min

-210000.000 [rpm]

Calculated: -

Scaling: -

Unit selection: p0505

Max

210000.000 [rpm]

Data type: FloatingPoint32

Dyn. index: DDS, p0180

Func. diagram: 3001, 3030

Factory setting

-150.000 [rpm]

Description: Sets the speed for jog 2.

Jogging (JOG) is level-triggered, and allows the motor to be incrementally traversed.

Dependency: Refer to: p1055, p1056

p1070[0...n]

CI: Main setpoint / Main setpoint

G120C_CAN
G120C_USS

Access level: 3

Can be changed: T

Unit group: -

Min

-

Calculated: -

Scaling: p2000

Unit selection: -

Max

-

Data type: U32 / FloatingPoint32

Dyn. index: CDS, p0170

Func. diagram: 3001, 3030

Factory setting

[0] 755[0]

[1] 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

Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p1070[0...n]	CI: Main setpoint / Main setpoint		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
G120C_PN	Can be changed: T	Scaling: p2000	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3001, 3030
	Min	Max	Factory setting
	-	-	[0] 2050[1]
			[1] 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		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p1071[0...n]	CI: Main setpoint scaling / Main setp scal		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3001, 3030
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for scaling the main setpoint.		
r1073	CO: Main setpoint effective / Main setpoint eff		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3030
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the effective main setpoint. The value shown is the main setpoint after scaling.		
p1075[0...n]	CI: Suppl setp / Suppl setp		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2000	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3001, 3030
	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 setp scal		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3001, 3030
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for scaling the supplementary setpoint.		

r1077	CO: Supplementary setpoint effective / Suppl setpoint eff		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3030
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the effective supplementary setpoint. The value shown is the additional setpoint after scaling.		
r1078	CO: Total setpoint effective / Total setpoint eff		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3030
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the total effective setpoint. The value indicates the sum of the effective main setpoint and supplementary setpoint.		
p1080[0...n]	Minimum speed / n_min		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1), T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3050, 8020
	Min	Max	Factory setting
	0.000 [rpm]	19500.000 [rpm]	0.000 [rpm]
Description:	Sets the lowest possible motor speed. This value is not undershot in operation.		
Dependency:	Refer to: p1106		
Notice:	The effective minimum speed is formed from p1080 and p1106.		
Note:	The parameter value applies for both motor directions. In exceptional cases, the motor can operate below this value (e.g. when reversing).		
p1081	Maximum speed scaling / n_max scal		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 3050, 3095
	Min	Max	Factory setting
	100.00 [%]	105.00 [%]	100.00 [%]
Description:	Sets the scaling for the maximum speed (p1082). For a higher-level speed control, this scaling allows the maximum speed to be briefly exceeded.		
Dependency:	Refer to: p1082		
Notice:	Continuous operation above a scaling of 100 % is not permitted.		
p1082[0...n]	Maximum speed / n_max		
	Access level: 1	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(1), T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3020, 3050, 3070
	Min	Max	Factory setting
	0.000 [rpm]	210000.000 [rpm]	1500.000 [rpm]
Description:	Sets the highest possible speed. Example: Induction motor p0310 = 50 / 60 Hz without output filter and Blocksize power unit p1082 <= 60 x 240 Hz / r0313 (vector control) p1082 <= 60 x 550 Hz / r0313 (U/f control)		

Dependency:	<p>For vector control, the maximum speed is restricted to $60.0 / (8.333 \times 500 \mu s \times r0313)$. This can be identified by a reduction in r1084. p1082 is not changed in this process due to the fact that the operating mode p1300 can be changed over.</p> <p>If a sine-wave 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). When using sine-wave filters (p0230 = 3, 4), the maximum speed r1084 is limited to 70% of the resonant frequency of the filter capacitance and the motor leakage inductance.</p> <p>For reactors and dU/dt filters, it is limited to 120 Hz / r0313.</p> <p>Refer to: p0230, r0313, p0322</p>
Notice:	After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.
Note:	<p>The parameter applies for both motor directions.</p> <p>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 quick commissioning (p0010 = 1); this means that it is appropriately pre-assigned when changing p0310, p0311 and p0322.</p> <p>The following limits are always effective for p1082:</p> <p>$p1082 \leq 60 \times \text{minimum} (15 \times r0310, 550 \text{ Hz}) / \text{pole pair number}$</p> <p>$p1082 \leq 60 \times \text{maximum power unit pulse frequency} / (k \times \text{pole pair number})$, with $k = 12$ (vector control), $k = 6.5$ (U/f control)</p> <p>If a sine-wave 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 120 Hz / pole pair number.</p> <p>During automatic calculation (p0340 = 1, p3900 > 0), the parameter value is assigned the maximum motor speed (p0322). For p0322 = 0 the rated motor speed (p0311) is used as default (pre-assignment) value. For induction motors, the synchronous no-load speed is used as the default value (p0310 x 60 / pole pair number).</p> <p>For synchronous motors, the following additionally applies:</p> <p>During automatic calculation (p0340, p3900), p1082 is limited to speeds where the EMF does not exceed the DC link voltage.</p> <p>p1082 is also available in the quick commissioning (p0010 = 1); this means that when exiting via p3900 > 0, the value is not changed.</p> <p>For vector control, the maximum speed is restricted to $60.0 / (8.333 \times 500 \mu s \times \text{pole pair number})$. This can be identified by a reduction in r1084. p1082 is not changed in this process due to the fact that the operating mode p1300 can be changed over.</p> <p>When using sine-wave filters (p0230 = 3, 4), the maximum speed r1084 is limited to 70% of the resonant frequency of the filter capacitance and the motor leakage inductance.</p>

p1083[0...n]	CO: Speed limit in positive direction of rotation / n_limit pos		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2000	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3050
	Min	Max	Factory setting
	0.000 [rpm]	210000.000 [rpm]	210000.000 [rpm]
Description:	Sets the maximum speed for the positive direction.		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
r1084	CO: Speed limit positive effective / n_limit pos eff		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3050, 7958
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Display and connector output for the active positive speed limit.		
Dependency:	Refer to: p1082, p1083		

p1086[0...n]	CO: Speed limit in negative direction of rotation / n_limit neg		
	Access level: 3 Can be changed: U, T Unit group: 3_1 Min -210000.000 [rpm]	Calculated: - Scaling: p2000 Unit selection: p0505 Max 0.000 [rpm]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 3050 Factory setting -210000.000 [rpm]
Description: Sets the speed limit for the negative direction. Notice: A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.			
r1087	CO: Speed limit negative effective / n_limit neg eff		
	Access level: 3 Can be changed: - Unit group: 3_1 Min - [rpm]	Calculated: - Scaling: p2000 Unit selection: p0505 Max - [rpm]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 3050, 7958 Factory setting - [rpm]
Description: Display and connector output for the active negative speed limit. Dependency: Refer to: p1082, p1086			
p1091[0...n]	Skip speed 1 / n_skip 1		
	Access level: 3 Can be changed: U, T Unit group: 3_1 Min 0.000 [rpm]	Calculated: - Scaling: p2000 Unit selection: p0505 Max 210000.000 [rpm]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 3050 Factory setting 0.000 [rpm]
Description: Sets skip speed 1. Dependency: Refer to: p1092, p1101 Notice: Skip bandwidths can also become ineffective as a result of the downstream limits in the setpoint channel. Note: The skip (suppression) speeds can be used to prevent the effects of mechanical resonance.			
p1092[0...n]	Skip speed 2 / n_skip 2		
	Access level: 3 Can be changed: U, T Unit group: 3_1 Min 0.000 [rpm]	Calculated: - Scaling: p2000 Unit selection: p0505 Max 210000.000 [rpm]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 3050 Factory setting 0.000 [rpm]
Description: Sets skip speed 2. Dependency: Refer to: p1091, p1101 Notice: Skip bandwidths can also become ineffective as a result of the downstream limits in the setpoint channel.			
p1101[0...n]	Skip speed bandwidth / n_skip bandwidth		
	Access level: 3 Can be changed: U, T Unit group: 3_1 Min 0.000 [rpm]	Calculated: - Scaling: p2000 Unit selection: p0505 Max 210000.000 [rpm]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 3050 Factory setting 0.000 [rpm]
Description: Sets the bandwidth for the skip speeds/velocities 1 to 4. Dependency: Refer to: p1091, p1092 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 between 580 and 620 [rpm] are skipped.

For the skip bandwidths, the following hysteresis behavior applies:



For a setpoint speed coming from below, the following applies:

$r1170 < 580 \text{ [rpm]}$ and $580 \text{ [rpm]} \leq r1114 \leq 620 \text{ [rpm]}$ --> $r1119 = 580 \text{ [rpm]}$

For a setpoint speed coming from above, the following applies:

$r1170 > 620 \text{ [rpm]}$ and $580 \text{ [rpm]} \leq r1114 \leq 620 \text{ [rpm]}$ --> $r1119 = 620 \text{ [rpm]}$

p1106[0...n]	CI: Minimum speed signal source / n_min s_src		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2000	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3050
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for lowest possible motor speed.		
Dependency:	Refer to: p1080		
Notice:	The effective minimum speed is formed from p1080 and p1106.		
p1110[0...n]	BI: Inhibit negative direction / Inhib neg dir		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3040
	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		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2505, 3040
	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 aft min_lim		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3050
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the speed setpoint after the minimum limiting.		
Dependency:	Refer to: p1091, p1092, p1101		

p1113[0...n]	BI: Setpoint inversion / Setp inv		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2441, 2442, 2505, 3040
	Min	Max	Factory setting
	-	-	[0] 722.1 [1] 0
Description:	Sets the signal source to invert the setpoint.		
Dependency:	Refer to: r1198		
Caution:	If the technology controller is being used as the speed main setpoint (p2251 = 0), do not invert the setpoint using p1113 when the technology controller is enabled because this can cause the speed to change suddenly and lead to positive couplings in the control loop.		
			
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p1113[0...n]	BI: Setpoint inversion / Setp inv		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2441, 2442, 2505, 3040
	Min	Max	Factory setting
	-	-	[0] 2090.11 [1] 0
Description:	Sets the signal source to invert the setpoint.		
Dependency:	Refer to: r1198		
Caution:	If the technology controller is being used as the speed main setpoint (p2251 = 0), do not invert the setpoint using p1113 when the technology controller is enabled because this can cause the speed to change suddenly and lead to positive couplings in the control loop.		
			
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
r1114	CO: Setpoint after the direction limiting / Setp after limit		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3001, 3040, 3050
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the speed/velocity setpoint after the changeover and limiting the direction.		
r1119	CO: Ramp-function generator setpoint at the input / RFG setp at inp		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 3001, 3050, 3070, 6300
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the setpoint at the input of the ramp-function generator.		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
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		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	0.000 [s]	999999.000 [s]	10.000 [s]
Description:	The ramp-function generator ramps-up the speed setpoint from standstill (setpoint = 0) up to the maximum speed (p1082) in this time.		
Dependency:	Refer to: p1082, p1123		
Note:	<p>The ramp-up time can be scaled via connector input p1138.</p> <p>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.</p> <p>For U/f control and sensorless vector control (see p1300), a ramp-up time of 0 s does not make sense. The setting should be based on the startup times (r0345) of the motor.</p>		
p1121[0...n]	Ramp-function generator ramp-down time / RFG ramp-down time		
	Access level: 1	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3060, 3070
	Min	Max	Factory setting
	0.000 [s]	999999.000 [s]	10.000 [s]
Description:	<p>Sets the ramp-down time for the ramp-function generator.</p> <p>The ramp-function generator ramps-down the speed setpoint from the maximum speed (p1082) down to standstill (setpoint = 0) in this time.</p> <p>Further, the ramp-down time is always effective for OFF1.</p>		
Dependency:	Refer to: p1082, p1123		
Note:	For U/f control and sensorless vector control (see p1300), a ramp-down time of 0 s does not make sense. The setting should be based on the startup times (r0345) of the motor.		
p1123[0...n]	Ramp-function generator minimum ramp-up time / RFG t_{RU} min		
	Access level: 4	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [s]	999999.000 [s]	0.000 [s]
Description:	<p>Sets the minimum ramp-up time.</p> <p>The ramp-up time (p1120) is limited internally to this minimum value.</p>		
Dependency:	Refer to: p1082		
Note:	<p>The setting should be based on the startup times (r0345) of the motor.</p> <p>If the maximum speed p1082 changes, p1123 is re-calculated.</p>		
p1127[0...n]	Ramp-function generator minimum ramp-down time / RFG t_{RD} min		
	Access level: 4	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [s]	999999.000 [s]	0.000 [s]
Description:	<p>Sets the minimum ramp-down time.</p> <p>The ramp-down time (p1121) is limited internally to this minimum value.</p>		
Dependency:	Refer to: p1082		

2 Parameters

2.2 List of parameters

Note: For U/f control and sensorless vector control (see p1300), a ramp-down time of 0 s does not make sense. The setting should be based on the startup times (r0345) of the motor.
If the maximum speed p1082 changes, p1127 is re-calculated.
If a braking resistor is connected to the DC link (p0219 > 0), then the minimum ramp-down time is automatically adapted using p1127.

p1130[0...n]	Ramp-function generator initial rounding-off time / RFG t_start_round		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	0.000 [s]	30.000 [s]	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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	0.000 [s]	30.000 [s]	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		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	0	1	0
Description:	Sets the smoothed response to the OFF1 command or the reduced setpoint for the extended ramp-function generator.		
Value:	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 / OFF3 t_RD		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(1), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3060, 3070
	Min	Max	Factory setting
	0.000 [s]	5400.000 [s]	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.		

p1136[0...n]	OFF3 initial rounding-off time / RFGOFF3 t_strt_rnd		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	0.000 [s]	30.000 [s]	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		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	0.000 [s]	30.000 [s]	0.000 [s]
Description:	Sets the final rounding-off time for OFF3 for the extended ramp generator.		
p1138[0...n]	CI: Ramp-function generator ramp-up time scaling / RFG t_RU scal		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for scaling the ramp-up time of the ramp-function generator.		
Dependency:	Refer to: p1120		
Note:	The ramp-up time is set in p1120.		
p1139[0...n]	CI: Ramp-function generator ramp-down time scaling / RFG t_RD scal		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 3070
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for scaling the ramp-down time of the ramp-function generator.		
Dependency:	Refer to: p1121		
Note:	The ramp-down time is set in p1121.		
p1140[0...n]	BI: Enable ramp-function generator/inhibit ramp-function generator / RFG enable		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source for the command "enable ramp-function generator/inhibit ramp-function generator". For the PROFIdrive profile, this command corresponds to control word 1 bit 4 (STW1.4). BI: p1140 = 0 signal: Inhibits the ramp-function generator (the ramp-function generator output is set to zero). BI: p1140 = 1 signal: Ramp-function generator enable.		
Dependency:	Refer to: r0054, p1141, p1142		
Caution:	When "master control from PC" is activated, this binector input is ineffective.		



Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p1140[0...n] BI: Enable ramp-function generator/inhibit ramp-function generator / RFG enable

G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	[0] 2090.4
			[1] 1

Description: Sets the signal source for the command "enable ramp-function generator/inhibit ramp-function generator".
For the PROFIdrive profile, this command corresponds to control word 1 bit 4 (STW1.4).

BI: p1140 = 0 signal:

Inhibits the ramp-function generator (the ramp-function generator output is set to zero).

BI: p1140 = 1 signal:

Ramp-function generator enable.

Dependency: Refer to: r0054, p1141, p1142

Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p1141[0...n] BI: Continue ramp-function generator/freeze ramp-function generator / Continue RFG

G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	1

Description: Sets the signal source for the command "continue ramp-function generator/freeze ramp-function generator".
For the PROFIdrive profile, this command corresponds to control word 1 bit 5 (STW1.5).

BI: p1141 = 0 signal:

Freezes the ramp-function generator.

BI: p1141 = 1 signal:

Continue ramp-function generator.

Dependency: Refer to: r0054, p1140, p1142

Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The ramp-function generator is, independent of the state 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.

p1141[0...n] BI: Continue ramp-function generator/freeze ramp-function generator / Continue RFG

G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2501
	Min	Max	Factory setting
	-	-	[0] 2090.5
			[1] 1

Description: Sets the signal source for the command "continue ramp-function generator/freeze ramp-function generator".
For the PROFIdrive profile, this command corresponds to control word 1 bit 5 (STW1.5).

BI: p1141 = 0 signal:

Freezes the ramp-function generator.

BI: p1141 = 1 signal:

Continue ramp-function generator.

Dependency: Refer to: r0054, p1140, p1142
Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The ramp-function generator is, independent of the state 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.

p1142[0...n]		BI: Enable setpoint/inhibit setpoint / Setpoint enable		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary	
G120C_USS	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170	
	Unit group: -	Unit selection: -	Func. diagram: 2501	
	Min	Max	Factory setting	
	-	-	1	

Description: Sets the signal source for the command "enable setpoint/inhibit setpoint".
 For the PROFIdrive profile, this command corresponds to control word 1 bit 6 (STW1.6).
 BI: p1142 = 0 signal
 Inhibits the setpoint (the ramp-function generator input is set to zero).
 BI: p1142 = 1 signal
 Setpoint enable.

Dependency: Refer to: p1140, p1141
Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.
Note: When the function module "position control" (r0108.3 = 1) is activated, this binector input is interconnected as follows as standard:
 BI: p1142 = 0 signal

p1142[0...n]		BI: Enable setpoint/inhibit setpoint / Setpoint enable		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary	
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170	
	Unit group: -	Unit selection: -	Func. diagram: 2501	
	Min	Max	Factory setting	
	-	-	[0] 2090.6	
			[1] 1	

Description: Sets the signal source for the command "enable setpoint/inhibit setpoint".
 For the PROFIdrive profile, this command corresponds to control word 1 bit 6 (STW1.6).
 BI: p1142 = 0 signal
 Inhibits the setpoint (the ramp-function generator input is set to zero).
 BI: p1142 = 1 signal
 Setpoint enable.

Dependency: Refer to: p1140, p1141
Caution: When "master control from PC" is activated, this binector input is ineffective.



Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.
Note: When the function module "position control" (r0108.3 = 1) is activated, this binector input is interconnected as follows as standard:
 BI: p1142 = 0 signal

r1149	CO: Ramp-function generator acceleration / RFG acceleration				
	Access level: 3		Calculated: -	Data type: FloatingPoint32	
	Can be changed: -		Scaling: p2007	Dyn. index: -	
	Unit group: 39_1		Unit selection: p0505	Func. diagram: 3070	
	Min - [rev/s²]		Max - [rev/s²]	Factory setting - [rev/s²]	
Description:	Displays the acceleration of the ramp-function generator.				

r1150	CO: Ramp-function generator speed setpoint at the output / RFG n_set at outp				
	Access level: 4		Calculated: -	Data type: FloatingPoint32	
	Can be changed: -		Scaling: p2000	Dyn. index: -	
	Unit group: 3_1		Unit selection: p0505	Func. diagram: -	
	Min - [rpm]		Max - [rpm]	Factory setting - [rpm]	
Description:	Displays the setpoint at the output of the ramp-function generator.				

r1170	CO: Speed controller setpoint sum / n_ctrl setp sum				
	Access level: 3		Calculated: -	Data type: FloatingPoint32	
	Can be changed: -		Scaling: p2000	Dyn. index: -	
	Unit group: 3_1		Unit selection: p0505	Func. diagram: 3001, 3070, 6300	
	Min - [rpm]		Max - [rpm]	Factory setting - [rpm]	
Description:	Display and connector output for the speed setpoint.				
Dependency:	Refer to: r1150				


r1198.0...15	CO/BO: Control word setpoint channel / STW setpoint chan				
	Access level: 3		Calculated: -	Data type: Unsigned16	
	Can be changed: -		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 2505	
	Min -		Max -	Factory setting -	
Description:	Display and BICO output for the control word of the setpoint channel.				



Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed setp bit 0	Yes	No	3010
	01	Fixed setp bit 1	Yes	No	3010
	02	Fixed setp bit 2	Yes	No	3010
	03	Fixed setp bit 3	Yes	No	3010
	05	Inhibit negative direction	Yes	No	3040
	06	Inhibit positive direction	Yes	No	3040
	11	Setpoint inversion	Yes	No	3040
	13	Motorized potentiometer raise	Yes	No	3020
	14	Motorized potentiometer lower	Yes	No	3020
	15	Bypass ramp-function generator	Yes	No	3070

p1200[0...n]	Flying restart operating mode / FlyRest op_mode				
	Access level: 2		Calculated: -	Data type: Integer16	
	Can be changed: U, T		Scaling: -	Dyn. index: DDS, p0180	
	Unit group: -		Unit selection: -	Func. diagram: 6300	
	Min 0		Max 4	Factory setting 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-function generator setting.				

Value:	0: Flying restart inactive 1: Flying restart always active (start in setpoint direction) 4: Flying restart always active (start only in setpoint direction)
Dependency:	For synchronous motors, flying restart cannot be activated. Refer to: p1201 Refer to: F07330, F07331
Notice:	The "flying restart" function must be used in cases where the motor may still be 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.
Note:	For p1200 = 1, 4, the following applies: Flying restart is active after faults, OFF1, OFF2, OFF3. For p1200 = 1, the following applies: The search is made in both directions. For p1200 = 4, the following applies: The search is only made in the setpoint direction. 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. For lower speeds, it is assumed that the motor is at a standstill. If p1200 is changed during commissioning (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).

p1201[0...n]	BI: Flying restart enable signal source / Fly_res enab S_src		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source to enable the "flying restart" function.		
Dependency:	Refer to: p1200		
Note:	Withdrawing the enable signal has the same effect as setting p1200 = 0.		


p1202[0...n]	Flying restart search current / FlyRest I_srch		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	10 [%]	400 [%]	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:	In U/f control mode, the parameter serves as a threshold value for establishing the current at the beginning of the flying restart function. When the threshold value is reached, the prevailing search current is set dependent upon the frequency on the basis of voltage inputs. Reducing the search current can also improve flying restart performance (if the system moment of inertia is not very high, for example). For a reluctance motor, the parameter is only changed after the motor data identification has been carried out.		

p1203[0...n]	Flying restart search rate factor / FlyRst v_Srch Fact		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	10 [%]	4000 [%]	100 [%]
Description:	Sets the factor for the search speed for flying restart. 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.		
Recommendation:	For encoderless vector control and motor cables longer than 200 m, set the factor p1203 >= 300 %.		
Caution:	An unfavorable parameter value can result in the motor behaving in an uncontrollable fashion.		
	For vector control, a value that is too low or too high can cause flying restart to become unstable.		
Note:	The parameter factory setting is selected so that standard induction motors that are rotating can be found and restarted as quickly as possible (fast flying restart). With this pre-setting, if the motor is not found (e.g. for motors that are accelerated as a result of active loads or with U/f control and low speeds), we recommend that the search rate is reduced (by increasing p1203). For the flying restart of a reluctance motor, the minimum search velocity is limited (p1203 >= 50 %).		
p1206[0...9]	Faults without automatic restart / F w/out auto AR		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	65535	0
Description:	Sets faults for which automatic restart should not be effective.		
Dependency:	The setting is only effective for p1210 = 6, 16, 26. Refer to: p1210		
p1210	Automatic restart mode / AR mode		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	26	0
Description:	Sets the automatic restart mode (AR). The parameters must be saved in the non-volatile memory p0971 = 1 in order that the setting becomes effective.		
Value:	0: Inhibit automatic restart 1: Acknowledge all faults without restarting 4: Restart after line supply failure w/o additional start attempts 6: Restart after fault with additional start attempts 14: Restart after line supply failure following man. acknowledgment 16: Restart after fault following manual acknowledgment 26: Acknowledging all faults and reclosing for an ON command		
Recommendation:	For brief line supply failures, the motor shaft may still be rotating when restarting. The "flying restart" function (p1200) might need to be activated to restart while the motor shaft is still rotating.		
Dependency:	The automatic restart requires an active ON command (e.g., via a digital input). If, for p1210 > 1, there is no active ON command, then the automatic restart is interrupted. When using an Operator Panel in the LOCAL mode, then there is no automatic start. For p1210 = 14, 16, a manual acknowledgement is required for an automatic restart. Refer to: p0840, p0857 Refer to: F30003		
Danger:	If the automatic restart is activated (p1210 > 1) if there is an ON command (refer to p0840), the drive is powered up as soon as any fault messages that are present can be acknowledged. This also occurs after the line supply returns or the Control Unit boots if the DC link voltage is present again. This automatic power-up sequence can only be interrupted by withdrawing the ON command.		
			

- Notice:** A change is only accepted and made in the state "initialization" and "wait for alarm". When faults are present, therefore, the parameter cannot be changed.
- For $p1210 > 1$, the motor is automatically started.
- Note:** Re $p1210 = 1$:
 Faults that are present are automatically acknowledged. If new faults occur after a successful fault acknowledgment, then these are also automatically acknowledged again. $p1211$ has no influence on the number of acknowledgment attempts.
- Re $p1210 = 4$:
 An automatic restart is only performed if fault F30003 has occurred on the power unit. If additional faults are present, then these faults are also acknowledged and when successful, starting continues. If, for external 24 V power supplies of the Control Unit, additional faults subsequently occur, these are no longer interpreted as line faults and are therefore also not acknowledged.
- Re $p1210 = 6$:
 An automatic restart is carried out if any fault has occurred.
- Re $p1210 = 14$:
 As for $p1210 = 4$. However, faults that are present must be manually acknowledged.
- Re $p1210 = 16$:
 As for $p1210 = 6$. However, faults that are present must be manually acknowledged.
- Re $p1210 = 26$:
 The same as for $p1210 = 6$. For this mode, the switch-on command can be entered with a delay. The restart is interrupted with either OFF2 or OFF3. Alarm A07321 is only displayed if the cause of the fault has been removed and the drive is restarted by setting the switch-on command.


p1211	Automatic restart start attempts / AR start attempts		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	10	3
Description:	Sets the start attempts of the automatic restart function for p1210 = 4, 6, 14, 16, 26.		
Dependency:	A change is only accepted and made in the state "initialization" and "wait for alarm". Refer to: p1210 Refer to: F07320		
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. After a complete power failure the start counter always starts with the counter value that applied before the power failure, and decrements this start attempt by 1. If a further attempt to acknowledge is started by the automatic restart function prior to power failure, e.g. when the CU remains active on power failure longer than the time p1212 / 2, the fault counter will already have been decremented once. In this case, the start counter is thus decreased by the value 2.		
Note:	A start 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. 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 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. 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. Re p1210 = 26: The start counter is decremented if after a successful fault acknowledgement, the on command is present.		

p1212	Automatic restart delay time start attempts / AR t_wait start		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.1 [s]	1000.0 [s]	1.0 [s]
Description:	Sets the delay time up to restart.		
Dependency:	This parameter setting is active for p1210 = 4, 6, 26. For p1210 = 1, the following applies: Faults are only automatically acknowledged in half of the waiting time, no restart. Refer to: p1210		
Notice:	A change is only accepted and made in the state "initialization" and "wait for alarm".		
Note:	The faults are automatically acknowledged after half of the delay time has expired and the full delay time. If the cause of a fault is not removed in the first half of the delay time, then it is no longer possible to acknowledge in the delay time.		
p1213[0...1]	Automatic restart monitoring time / AR t_monit		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.0 [s]	10000.0 [s]	[0] 60.0 [s] [1] 0.0 [s]
Description:	Sets the monitoring time of the automatic restart (AR).		
Index:	[0] = Restart [1] = Reset start counter		
Dependency:	Refer to: p1210		
Notice:	A change is only accepted and made in the state "initialization" and "wait for alarm". 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:	Re index 0: 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 magnetizing 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 be extended if the faults that occur cannot be immediately and successfully acknowledged (e.g. for faults that are permanently present). In the case of p1210 = 14, 16, the faults which are present must be acknowledged manually within the time in p1213[0]. Otherwise, fault F07320 is generated after the set time. Re index 1: The start counter is only reset to the starting value p1211 if, after successful restart, the time in p1213[1]. The delay time is not effective for fault acknowledgement without automatic restart (p1210 = 1). After a power failure (blackout) the delay time only starts after the line supply returns and the Control Unit boots. The start counter is set to p1211, if F07320 occurred, the power-on command is withdrawn and the fault is acknowledged. The start counter is immediately updated if the starting value p1211 or the mode p1210 is changed. For p1210 = 26, the fault must have been successfully acknowledged and the switch-on command issued within the time in p1213[0]. Otherwise, fault F07320 is generated after the set time.		

p1215	Motor holding brake configuration / Brake config		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2701
	Min	Max	Factory setting
	0	3	0
Description:	Sets the holding brake configuration.		
Value:	0: No motor holding brake available 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 suppressed, the brake is closed even if the motor is still rotating. Pulse suppression 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 a holding brake integrated in the motor is used, then it is not permissible that p1215 is set to 3. 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. The parameter can only be set to zero when the pulses are inhibited.		

p1216	Motor holding brake opening time / Brake t _{open}		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2701
	Min	Max	Factory setting
	0 [ms]	10000 [ms]	100 [ms]
Description:	Sets the time to open the motor holding brake. After the holding brake has been controlled (opened), the speed setpoint remains at zero for this time. After this, the speed 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		
Note:	For a motor with DRIVE-CLiQ and integrated brake, for p0300 = 10000, this time is pre-assigned the value saved in the motor.		

p1217	Motor holding brake closing time / Brake t _{close}		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2701
	Min	Max	Factory setting
	0 [ms]	10000 [ms]	100 [ms]
Description:	Sets the time to apply the motor holding brake. After OFF1 or OFF3 and the controlling (closing) of the holding brake, the drive remains stationary under closed-loop control for this time with a speed setpoint of zero. The pulses are suppressed 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 suppressed 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.		
Note:	For a motor with DRIVE-CLiQ and integrated brake, for p0300 = 10000, this time is pre-assigned the value saved in the motor.		

p1226[0...n]	Threshold for zero speed detection / n_standst n_thresh		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 2701, 8020
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	20.00 [rpm]
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 undershot, standstill is identified.		
Dependency:	Refer to: p1227		
Caution:			
	For closed-loop speed and torque control without encoder, the following applies: If p1226 is set to values under approx. 1 % of the rated motor speed, then the model switchover limits of the vector control must be increased in order to guarantee reliable shutdown (see p1755).		
Note:	Standstill is identified in the following cases: - the speed actual value falls below the speed threshold in p1226 and the time started after this in p1228 has expired. - the speed setpoint falls below the speed threshold in p1226 and the time started after this in p1227 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.		
p1227	Zero speed detection monitoring time / n_standst t_monit		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2701
	Min	Max	Factory setting
	0.000 [s]	300.000 [s]	300.000 [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).		
Dependency:	The parameter is pre-assigned depending on the size of the power unit. Refer to: p1226		
Notice:	For p1145 > 0.0 (RFG tracking) the setpoint is not equal to zero dependent on the selected value. This can therefore cause the monitoring time in p1227 to be exceeded. In this case, for a driven motor, the pulses are not suppressed.		
Note:	Standstill is identified in the following cases: - the speed actual value falls below the speed threshold in p1226 and the time started after this in p1228 has expired. - the speed setpoint falls below the speed threshold in p1226 and the time started after this in p1227 has expired. For p1227 = 300.000 s the following applies: Monitoring is de-activated. For p1227 = 0.000 s, the following applies: With OFF1 or OFF3 and a ramp-down time = 0, the pulses are immediately suppressed and the motor "coasts" down. Once the Control Unit has been booted up for the first time or if the factory settings have been defined accordingly, the parameter is defined in accordance with the power unit.		
p1228	Pulse suppression delay time / Pulse suppr t_del		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2701, 8020
	Min	Max	Factory setting
	0.000 [s]	299.000 [s]	0.010 [s]
Description:	Sets the delay time for pulse suppression. After OFF1 or OFF3, the pulses are canceled, if at least one of the following conditions is fulfilled: - the speed actual value falls below the threshold in p1226 and the time started after this in p1228 has expired. - the speed setpoint falls below the threshold in p1226 and the time started after this in p1227 has expired.		
Dependency:	Refer to: p1226, p1227		

Notice: When the motor holding brake is activated, pulse cancellation is additionally delayed by the brake closing time (p1217).

p1230[0...n]	BI: DC braking activation / DC brake act		
	Access level: 2	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7017
	Min	Max	Factory setting
	-	-	0

Description: Sets the signal source to activate DC braking.

Dependency: Refer to: p1231, p1232, p1233, p1234, r1239

Note: 1 signal: DC braking activated.

0 signal: DC braking de-activated.

p1231[0...n]	DC braking configuration / DCBRK config		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: MDS, p0130
	Unit group: -	Unit selection: -	Func. diagram: 7014, 7016, 7017
	Min	Max	Factory setting
	0	14	0

Description: Setting to activate DC braking.

Value:

- 0: No function
- 4: DC braking
- 5: DC braking for OFF1/OFF3
- 14: DC braking below starting speed

Dependency: Refer to: p0300, p1232, p1233, p1234, r1239

Note: The function can only be used for induction motors (p0300 = 1).

Re p1231 = 4:

The function is activated as soon as the activation criterion is fulfilled.

- the function can be superseded by an OFF2 response.

Activation criterion (one of the following criteria is fulfilled):

- binector input p1230 = 1 signal (DC braking activation, depending on the operating mode).
- the drive is not in the state "S4: Operation" or in "S5x".
- the internal pulse enable is missing (r0046.19 = 0).

DC braking can only be withdrawn (p1231 = 0) if it is not being used as a fault response in p2101.

Re p1231 = 5:

DC braking is activated if the OFF1 or OFF3 command is present. Binector input p1230 is ineffective. If the drive speed still lies above the speed threshold p1234, then initially, the drive is ramped-down to this threshold, demagnetized (see p0347) and is then switched into DC braking for the time set in p1233. After this, the drive is switched-off. If, at OFF1, the drive speed is below p1234, then it is immediately demagnetized and switched into DC braking. A change is made into normal operation if the OFF1 command is withdrawn prematurely (the system waits for demagnetization). Flying restart must be activated if the motor is still rotating.

DC braking by means of fault response continues to be possible.

Re p1231 = 14:

In addition to the function for p1231 = 5, binector input p1230 is evaluated.

DC braking is only automatically activated when the speed threshold p1234 is fallen below if binector input p1230 = 1 signal. This is also the case, if no OFF command is present.

After demagnetization and after the time in p1233 has expired, the drive changes back into normal operation or is switched-off (for OFF1/OFF3).

If a 0 signal is applied to binector input p1230, for OFF1 and OFF3 no DC braking is executed.

Note:

DCBRK: DC Braking


p1232[0...n]	DC braking braking current / DCBRK I_brake				
	Access level: 2		Calculated: p0340 = 1		Data type: FloatingPoint32
	Can be changed: U, T		Scaling: -		Dyn. index: MDS, p0130
	Unit group: -		Unit selection: -		Func. diagram: 7017
	Min		Max		Factory setting
	0.00 [Arms]		10000.00 [Arms]		0.00 [Arms]
Description:	Sets the braking current for DC braking.				
Dependency:	Refer to: p1230, p1231, p1233, p1234, r1239, p1345, p1346				
Note:	A change to the braking current becomes effective the next time that DC braking is switched on. The value for p1232 is specified as an rms value in the 3-phase system. The magnitude of the braking current is the same as that of an identical output current at frequency zero (see r0067, r0068, p0640). The braking current is internally limited to r0067. For the current controller, the settings of parameters p1345 and p1346 (I_max limiting controller) are used.				

p1233[0...n]	DC braking time / DCBRK time				
	Access level: 2		Calculated: -		Data type: FloatingPoint32
	Can be changed: U, T		Scaling: -		Dyn. index: MDS, p0130
	Unit group: -		Unit selection: -		Func. diagram: 7017
	Min		Max		Factory setting
	0.0 [s]		3600.0 [s]		1.0 [s]
Description:	Sets the DC braking time (as fault response).				
Dependency:	Refer to: p1230, p1231, p1232, p1234, r1239				

p1234[0...n]	Speed at the start of DC braking / DCBRK n_start				
	Access level: 2		Calculated: -		Data type: FloatingPoint32
	Can be changed: U, T		Scaling: -		Dyn. index: MDS, p0130
	Unit group: -		Unit selection: -		Func. diagram: 7017
	Min		Max		Factory setting
	0.00 [rpm]		210000.00 [rpm]		210000.00 [rpm]
Description:	Sets the starting speed for DC braking. If the actual speed falls below this threshold, then DC braking is activated.				
Dependency:	Refer to: p1230, p1231, p1232, p1233, r1239				

r1239.8...13	CO/BO: DC braking status word / DCBRK ZSW				
	Access level: 2		Calculated: -		Data type: Unsigned32
	Can be changed: -		Scaling: -		Dyn. index: -
	Unit group: -		Unit selection: -		Func. diagram: -
	Min		Max		Factory setting
	-		-		-
Description:	Status word of the DC braking.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	08	DC braking active	Yes	No	7017
	10	DC braking ready	Yes	No	7017
	11	DC braking selected	Yes	No	-
	12	DC braking selection internally inhibited	Yes	No	-
	13	DC braking for OFF1/OFF3	Yes	No	-
Dependency:	Refer to: p1231, p1232, p1233, p1234				
Note:	Re bit 12, 13: Only effective for p1231 = 14.				

p1240[0...n]	Vdc controller configuration (vector control) / Vdc ctr config vec		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6220
	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. For U/f control: see p1280.		
Value:	0: Inhib Vdc ctrl 1: Enable Vdc_max controller 2: Enable Vdc_min controller (kinetic buffering) 3: Enable Vdc_min controller and Vdc_max controller		
Dependency:	Refer to: p1245 Refer to: A07400, A07401, A07402, F07405, F07406		
Notice:	An excessively high value in p1245 can possibly negatively influence the normal operation of the drive.		
Note:	If a braking resistor is connected to the DC link (p0219 > 0), then the Vdc_max control is automatically deactivated. p1240 = 1, 3: When the DC link voltage limit specified for the power unit 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_max controller switch-in level / Vdc_max on_level		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6220
	Min	Max	Factory setting
	- [V]	- [V]	- [V]
Description:	Displays the switch-in level for the Vdc_max controller. If p1254 = 0 (automatic sensing of the switch-in level = off), then the following applies: $r1242 = 1.15 * \sqrt{2} * V_{\text{mains}} = 1.15 * \sqrt{2} * p0210$ (supply voltage) If p1254 = 1 (automatic sensing of the switch-in level = on), then the following applies: $r1242 = V_{\text{dc_max}} - 50.0 \text{ V}$ (Vdc_max: Overvoltage threshold of the power unit)		
Notice:	If the activation level of the Vdc_max controller is already exceeded in the deactivated state (pulse inhibit) by the DC link voltage, then the controller can be automatically deactivated (see F07401), so that the drive is not accelerated the next time that it is activated.		
Note:	The Vdc_max controller is not switched back off until the DC-link voltage falls below the threshold $0.95 * r1242$ and the controller output is zero.		

p1243[0...n]	Vdc_max controller dynamic factor / Vdc_max dyn_factor		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6220
	Min	Max	Factory setting
	1 [%]	10000 [%]	100 [%]
Description:	Sets the dynamic factor for the DC link voltage controller (Vdc_max controller). 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, this can be carried out using the dynamic factor. In this case p1250, p1251, p1252 are weighted with the dynamic factor p1243.		
p1245[0...n]	Vdc_min controller switch-in level (kinetic buffering) / Vdc_min on_level		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	65 [%]	150 [%]	76 [%]
Description:	Sets the switch-in level for the Vdc-min controller (kinetic buffering). The value is obtained as follows: $r1246[V] = p1245[\%] * \sqrt{2} * p0210$		
Dependency:	Refer to: p0210		
Warning:	An excessively high value possibly negatively influences normal drive operation, and can mean that after the line supply returns, the Vdc minimum control can no longer be exited.		
			
r1246	Vdc_min controller switch-in level (kinetic buffering) / Vdc_min on_level		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6220
	Min	Max	Factory setting
	- [V]	- [V]	- [V]
Description:	Displays the switch-in level for the Vdc_min controller (kinetic buffering).		
Note:	The Vdc_min controller is not switched back off until the DC-link voltage rises above the threshold $1.05 * p1246$ and the controller output is zero.		
p1247[0...n]	Vdc_min controller dynamic factor (kinetic buffering) / Vdc_min dyn_factor		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6220
	Min	Max	Factory setting
	1 [%]	10000 [%]	300 [%]
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, this can be carried out using the dynamic factor. In this case p1250, p1251, p1252 are weighted with the dynamic factor p1247.		

p1249[0...n]	Vdc_max controller speed threshold / Vdc_max n_thresh		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: -
	Min 0.00 [rpm]	Max 210000.00 [rpm]	Factory setting 10.00 [rpm]
Description:	Sets the lower speed threshold for the Vdc_max controller. When this speed threshold is undershot, the Vdc_max control is switched out and the speed is controlled using the ramp-function generator.		
Note:	For fast braking where the ramp-function generator tracking was active, it is possible to prevent the drive rotating in the opposite direction by increasing the speed threshold and setting a final rounding-off time in the ramp-function generator (p1131). This is supported using a dynamic setting of the speed controller.		
p1250[0...n]	Vdc controller proportional gain / Vdc_ctrl Kp		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 0.00	Max 100.00	Factory setting 1.00
Description:	Sets the proportional gain for the DC-link voltage controller (Vdc_min controller, Vdc_max controller).		
Dependency:	The effective proportional gain is obtained taking into account p1243 (Vdc_max controller dynamic factor) and the DC link capacitance of the power unit.		
p1251[0...n]	Vdc controller integral time / Vdc_ctrl Tn		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6220
	Min 0 [ms]	Max 10000 [ms]	Factory setting 0 [ms]
Description:	Sets the integral time for the DC-link voltage controller (Vdc_min controller, Vdc_max controller).		
Dependency:	The effective integral time is obtained taking into account p1243 (Vdc_max controller dynamic factor).		
Note:	p1251 = 0: The integral component is de-activated.		
p1252[0...n]	Vdc controller rate time / Vdc_ctrl t_rate		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6220
	Min 0 [ms]	Max 1000 [ms]	Factory setting 0 [ms]
Description:	Sets the rate time constant for the DC-link voltage controller (Vdc_min controller, Vdc_max controller).		
Dependency:	The effective rate time is obtained taking into account p1243 (Vdc_max controller dynamic factor).		
p1254	Vdc_max controller automatic ON level detection / Vdc_max SenseOnLev		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 0	Max 1	Factory setting 1
Description:	Activates/de-activates the automatic sensing of the switch-in level for the Vdc_max controller.		
Value:	0: Automatic detection inhibited 1: Automatic detection enabled		

p1255[0...n]	Vdc_min controller time threshold / Vdc_min t_thresh		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [s]	1800.000 [s]	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		
Notice:	If a time threshold has been parameterized, the Vdc_max controller should also be activated (p1240 = 3) so that the drive does not shut down with overvoltage when Vdc_min control is exited (due to the time violation) and in the event of fault response OFF3. It is also possible to increase the OFF3 ramp-down time p1135.		
p1256[0...n]	Vdc_min controller response (kinetic buffering) / Vdc_min response		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the response for the Vdc_min controller (kinetic buffering).		
Value:	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		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: -
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	50.00 [rpm]
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 . Kinetic buffering is not started below the speed threshold.		
Note:	Exiting the Vdc_min control before reaching motor standstill prevents the regenerative braking current from increasing significantly at low speeds, and after a pulse inhibit, means that the motor coasts down. However, the maximum braking torque can be set via the appropriate torque limiting.		
r1258	CO: Vdc controller output / Vdc_ctrl output		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6220
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the actual output of the Vdc controller (DC link voltage controller)		
Note:	The regenerative power limit p1531 is used for 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.		

p1271[0...n]	Flying restart maximum frequency for the inhibited direction / FlyRes f_max dir				
	Access level: 3	Calculated: -	Data type: FloatingPoint32		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0 [Hz]	650 [Hz]	0 [Hz]		
Description:	Sets the maximum search frequency for a flying restart in an inhibited setpoint direction (p1110, p1111).				
Note:	The parameter has no effect for an operating mode, which only searches in the setpoint direction (p1200 > 3).				

p1280[0...n]	Vdc controller configuration (U/f) / Vdc_ctr config U/f				
	Access level: 3	Calculated: -	Data type: Integer16		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6320		
	Min	Max	Factory setting		
	0	1	1		
Description:	Sets the configuration of the controller for the DC link voltage (Vdc controller) in the U/f operating mode.				
Value:	0: Inhib Vdc ctrl 1: Enable Vdc_max controller				
Note:	For high input voltages (p0210), the following settings can improve the degree of ruggedness of the Vdc_max controller: - Set the input voltage as low as possible, and in so doing, avoid A07401 (p0210). - set the rounding times (p1130, p1136). - Increase the ramp-down times (p1121). - Reduce the integral time of the controller (p1291), factor 0.5. - Reduce the rate time of the controller (p1292, factor 0.5). In this case, we generally recommend to use vector control (p1300 = 20) (Vdc controller, see p1240). The following measures are suitable to improve the Vdc_min controller: - Optimize the Vdc_min controller (see p1287). If a braking resistor is connected to the DC link (p0219 > 0), then the Vdc_max control is automatically deactivated.				

p1281[0...n]	Vdc controller configuration / Vdc ctrl config.				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the configuration of the DC link voltage controller.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Vdc min controller (U/f) without up ramp	Yes	No	-
	02	Vdc min shorter wait time when the line returns	Yes	No	-
Note:	Re bit 00: Deactivates the up ramp for Vdc min control. For drives with a mechanical system that can oscillate and high moment of inertia, the speed can be more quickly tracked. Re bit 02: When the line supply returns, normal operation is resumed earlier, and the system does not wait until the Vdc min controller reaches the setpoint speed.				

r1282	Vdc_max controller switch-in level (U/f) / Vdc_max on_level		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6320
Description:	Min	Max	Factory setting
	- [V]	- [V]	- [V]
	Displays the switch-in level for the Vdc_max controller.		
	If p1294 = 0 (automatic sensing of the switch-in level = off), then the following applies: $r1282 = 1.15 * \sqrt{2} * p0210$ (supply voltage) If p1294 = 1 (automatic sensing of the switch-in level = on), then the following applies: $r1282 = Vdc_max - 50.0 \text{ V}$ (Vdc_max: Overvoltage threshold of the power unit) $r1282 = Vdc_max - 25.0 \text{ V}$ (for 230 V power units)		
Notice:	If the activation level of the Vdc_max controller is already exceeded in the deactivated state (pulse inhibit) by the DC link voltage, then the controller can be automatically deactivated (see F07401), so that the drive is not accelerated the next time that it is activated.		
Note:	The Vdc_max controller is not switched back off until the DC-link voltage falls below the threshold $0.95 * r1282$ and the controller output is zero.		
p1283[0...n]	Vdc_max controller dynamic factor (U/f) / Vdc_max dyn_factor		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6320
Description:	Min	Max	Factory setting
	1 [%]	10000 [%]	100 [%]
	Sets the dynamic factor for the DC link voltage controller (Vdc_max controller).		
	100% means that p1290, p1291, and p1292 (gain, integral time, and rate time) are used in accordance with their basic settings and on the basis of a theoretical controller optimization. If subsequent optimization is required, this can be carried out using the dynamic factor. In this case, p1290, p1291, and p1292 are weighted with the dynamic factor p1283.		
p1284[0...n]	Vdc_max controller time threshold (U/f) / Vdc_max t_thresh		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	0.000 [s]	300.000 [s]	4.000 [s]
	Sets the monitoring time for the Vdc_max controller.		
	If the down ramp of the speed setpoint is held for longer than the time set in p1284, then fault F07404 is output.		
p1288[0...n]	Vdc_max controller feedback coupling factor ramp-fct. gen. (U/f) / Vdc_max factor RFG		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	0.000	100.000	0.500
	Sets the feedback factor for the ramp-function generator.		
	Its ramp times are decelerated relative to the output signal of the Vdc_max controller.		
Note:	For values p1288 = 0.0 to 0.5, the controller dynamics are automatically adapted internally.		

p1290[0...n]	Vdc controller proportional gain (U/f) / Vdc_ctrl Kp		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6320
	Min	Max	Factory setting
	0.00	100.00	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 pre-set to a value that is optimally adapted to the capacitance of the power unit.		
p1291[0...n]	Vdc controller integral time (U/f) / Vdc_ctrl Tn		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6320
	Min	Max	Factory setting
	0 [ms]	10000 [ms]	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		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6320
	Min	Max	Factory setting
	0 [ms]	1000 [ms]	10 [ms]
Description:	Sets the rate time constant for the Vdc controller (DC link voltage controller).		
p1293[0...n]	Vdc min controller output limit (U/f) / Vdc_min outp_lim		
	Access level: 4	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6320
	Min	Max	Factory setting
	0.00 [Hz]	600.00 [Hz]	600.00 [Hz]
Description:	Sets the output limit for the Vdc min controller (DC link undervoltage controller).		
p1294	Vdc_max controller automatic detection ON signal level (U/f) / Vdc_max SenseOnLev		
	Access level: 4	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Activates/de-activates the automatic sensing of the switch-in level for the Vdc_max controller. When the sensing function is de-activated, the activation threshold r1282 for the Vdc_max controller is determined from the parameterized connection voltage p0210.		
Value:	0: Automatic detection inhibited 1: Automatic detection enabled		

p1295[0...n]	Vdc_min controller time threshold (U/f) / Vdc_min t_thresh		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000 [s]	10000.000 [s]	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		
Notice:	If a time threshold has been parameterized, the Vdc_max controller should also be activated (p1280 = 3) so that the drive does not shut down with overvoltage when Vdc_min control is exited (due to the time violation) and in the event of fault response OFF3. It is also possible to increase the OFF3 ramp-down time p1135.		
p1297[0...n]	Vdc_min controller speed threshold (U/f) / Vdc_min n_thresh		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: -
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	50.00 [rpm]
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 .		
Note:	Exiting the Vdc_min control before reaching motor standstill prevents the regenerative braking current from increasing significantly at low speeds, and after a pulse inhibit, means that the motor coasts down.		
r1298	CO: Vdc controller output (U/f) / Vdc_ctrl output		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 6320
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the actual output of the Vdc controller (DC link voltage controller)		
p1300[0...n]	Open-loop/closed-loop control operating mode / Op/cl-lp ctrl_mode		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C(1), T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6301, 8012
	Min	Max	Factory setting
	0	20	0
Description:	Sets the open and closed-loop control mode of a drive.		
Value:	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 4: U/f control with linear characteristic and ECO 5: U/f control for drives requiring a precise freq. (e.g. textiles) 6: U/f control for drives requiring a precise frequency and FCC 7: U/f control for a parabolic characteristic and ECO 19: U/f control with independent voltage setpoint 20: Speed control (encoderless)		
Dependency:	For Standard Drive Control (p0096 = 1), settings p1300 = 0, 2 are possible, for Dynamic Drive Control (p0096 = 2) only p1300 = 20 can be set. Only operation with U/f characteristic is possible if the rated motor speed is not entered (p0311). Operation with a U/f characteristic is not supported for 1LE4 synchronous motors. Refer to: p0300, p0311, p0500		

- Notice:** Active slip compensation is required in the U/f control types with Eco mode (p1300 = 4, 7). The scaling of the slip compensation (p1335) should be set so that the slip is completely compensated (generally 100%).
The Eco mode is only effective in steady-state operation and when the ramp-function generator is not bypassed.
- Note:** For the open-loop control modes p1300 = 5 and 6 (textile sector), slip compensation p1335, resonance damping p1338, and the I_{max} frequency controller are switched off internally so that the output frequency can be set precisely. The I_{max} voltage controller remains active.
During operation (pulses enabled) the open-loop/closed-loop control mode cannot be changed by changing over drive data sets.

p1302[0...n]					
U/f control configuration / U/f config					
Access level: 3		Calculated: -		Data type: Unsigned16	
Can be changed: T		Scaling: -		Dyn. index: DDS, p0180	
Unit group: -		Unit selection: -		Func. diagram: -	
Min		Max		Factory setting	
-		-		0000 0000 bin	
Description: Sets the configuration for the U/f control.					
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	03	Motor holding brake with constant stop frequency	Yes	No	-
	04	Field orientation	Yes	No	-
	05	Starting current when accelerating without flux boost	Yes	No	-
	07	Inhibit I _{q,max} controller	Yes	No	-
Note:					
Re bit 03: When the bit is set, when the drive stops, the starting frequency of the motor holding brake is also not fallen below when the actual slip frequency is less than the starting frequency.					
Re bit 04: Field orientation for the closed-loop control of the basis application. The field orientation is activated with the automatic calculation if p0096 is set = 1.					
Re bit 05 (only effective for p1302.4 = 1): The starting current when accelerating (p1311) generally results in an increase in the absolute current and flux. With p1302.5 = 1 the current is only increased in the direction of the load. This setting is recommended for drives with higher power ratings or drives with extremely fast rates of acceleration.					
Re bit 07: For field orientation (bit04 = 1), the I _{q,max} controller supports the current limiting controller (see p1341). For diagnostic purposes, the I _{q,max} controller can be deactivated using this bit.					

p1310[0...n]	Starting current (voltage boost) permanent / I_start (Ua) perm		
	Access level: 2	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6301, 6851
	Min	Max	Factory setting
	0.0 [%]	250.0 [%]	50.0 [%]
Description:	<p>Defines the voltage boost as a [%] referred to the rated motor current (p0305).</p> <p>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.</p> <p>The magnitude of the boost in Volt at a frequency of zero is defined as follows:</p> <p>Voltage boost [V] = 1.732 x p0305 (rated motor current [A]) x r0395 (stator/primary section resistance [ohm]) x p1310 (permanent voltage boost [%]) / 100 %</p> <p>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.</p> <p>The voltage boost can be used for both linear as well as square-law U/f characteristics.</p>		

For field orientation (p1302.4 = 1, default setting for p0096 = 1), in the vicinity of low output frequencies, a minimum current is impressed with the magnitude of the rated magnetizing current.

For p1310 = 0%, a current setpoint is calculated that corresponds to the no-load case. For p1610 = 100 %, a current setpoint is calculated that corresponds to the rated motor current.

Dependency:

The starting current (voltage boost) is limited by the current limit p0640.

The accuracy of the starting current depends on the setting of the stator and feeder cable resistance (p0350, p0352).

For vector control, the starting current is realized using p1610.

Refer to: p1300, p1311, p1312, r1315

Notice:

The starting current (voltage boost) increases the motor temperature (particularly at zero speed).

Note:

The starting current as a result of 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), voltage boost for starting (p1312)).

However, these parameters are assigned the following priorities: p1310 > p1311, p1312

For field orientation (p1302.4 = 1, not PM230, PM250, PM260), p1311 and p1312 of the voltage boost is also added in the direction of the load current (non linear).

p1311[0...n]

Starting current (voltage boost) when accelerating / I_start accel

Access level: 2

Calculated: -

Data type: FloatingPoint32

Can be changed: U, T

Scaling: -

Dyn. index: DDS, p0180

Unit group: -

Unit selection: -

Func. diagram: 6300, 6301, 6851

Min

Max

Factory setting

0.0 [%]

250.0 [%]

0.0 [%]

Description:

p1311 only results in a voltage boost when accelerating and generates a supplementary torque 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 build-up and withdrawal of the voltage boost are smoothed.

The magnitude of the boost in Volt at a frequency of zero is defined as follows (not for field orientation):

Voltage boost [V] = $1.732 \cdot p0305$ (rated motor current [A]) $\times r0395$ (stator/primary section resistance [ohm]) $\times p1311$ (voltage boost when accelerating [%]) / 100 %

Dependency:

The current limit p0640 limits the boost.

For field orientation (p1302 bit 4 = 1, not PM230, PM250, PM260), p1311 is preassigned by the automatic calculation.

For vector control, the starting current is realized using p1611.

Refer to: p1300, p1310, p1312, r1315

Notice:

The voltage boost results in a higher motor temperature increase.

Note:

The voltage boost when accelerating can improve the response to small, positive setpoint changes.

Assigning priorities for the voltage boosts: refer to p1310

For field orientation (p1302 bit 4 = 1, not PM230, PM250, PM260), p1311 of the voltage boost is also added in the direction of the load current (non-linear).

p1312[0...n]

Starting current (voltage boost) when starting / I_start start

Access level: 2

Calculated: -

Data type: FloatingPoint32

Can be changed: U, T

Scaling: -

Dyn. index: DDS, p0180

Unit group: -

Unit selection: -

Func. diagram: 6300, 6301, 6851

Min

Max

Factory setting

0.0 [%]

250.0 [%]

0.0 [%]

Description:

Setting for an additional voltage boost when powering-up, however, only for the first acceleration phase.

The voltage boost becomes effective for a positive setpoint increase and disappears as soon as the setpoint has been reached. The build-up and withdrawal of the voltage boost are smoothed.

Dependency:

The current limit p0640 limits the boost.

Refer to: p1300, p1310, p1311, r1315

Notice:

The voltage boost results in a higher motor temperature increase.

Note:

The voltage boost when accelerating can improve the response to small, positive setpoint changes.

Assigning priorities for the voltage boosts: refer to p1310

For field orientation (p1302.4 = 1, not PM230, PM250, PM260), p1312 of the voltage boost is also added in the direction of the load current (non-linear).


r1315	Voltage boost total / U_boost total		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6301, 6851
	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
Description:	Displays the total resulting voltage boost in volt. For field orientation (p1302.4 = 1, not for PM230, PM250, PM260), at low speeds, as a minimum the magnetizing current is set, so that the voltage depends on r0331.		
Dependency:	Refer to: p1310, p1311, p1312		
p1320[0...n]	U/f control programmable characteristic frequency 1 / Uf char f1		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.00 [Hz]	3000.00 [Hz]	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 U/f characteristic.		
p1321[0...n]	U/f control programmable characteristic voltage 1 / Uf char U1		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.0 [Vrms]	10000.0 [Vrms]	0.0 [Vrms]
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 U/f characteristic.		
p1322[0...n]	U/f control programmable characteristic frequency 2 / Uf char f2		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.00 [Hz]	3000.00 [Hz]	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		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.0 [Vrms]	10000.0 [Vrms]	0.0 [Vrms]
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		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.00 [Hz]	3000.00 [Hz]	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		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.0 [Vrms]	10000.0 [Vrms]	0.0 [Vrms]
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		
	Access level: 3	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.00 [Hz]	10000.00 [Hz]	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 frequency of the fourth point along the characteristic.		
Dependency:	Selects the freely programmable characteristic using p1300 = 3. The following applies for 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, p1324, p1325, p1327		
Note:	Linear interpolation is carried out between the points 0 Hz/p1310, p1320/p1321 ... p1326/p1327. For output frequencies above p1326, the characteristic is extrapolated with the gradient between the characteristic points p1324/p1325 and p1326/p1327. The voltage boost when accelerating (p1311) is also applied to the freely programmable U/f characteristic.		

p1327[0...n]	U/f control programmable characteristic voltage 4 / Uf char U4		
	Access level: 3	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.0 [Vrms]	10000.0 [Vrms]	0.0 [Vrms]
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 fourth point along the characteristic.		
Dependency:	Selects the freely programmable characteristic using p1300 = 3. Refer to: p1310, p1311, p1320, p1321, p1322, p1323, p1324, p1325, p1326		
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 U/f characteristic.		

p1330[0...n]	CI: U/f control independent voltage setpoint / Uf U_set independ.		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2001	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 6301
	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:	Selects the U/f control with independent voltage setpoint via p1300 = 19. Refer to: p1300		

p1331[0...n]	Voltage limiting / U_lim		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 6300
	Min	Max	Factory setting
	50.00 [Vrms]	2000.00 [Vrms]	1000.00 [Vrms]
Description:	Limiting the voltage setpoint. This means that the output voltage can be reduced with respect to the calculated maximum voltage r0071 and the start of field weakening.		
Note:	The output voltage is only limited if, as a result of p1331, the maximum output voltage (r0071) is fallen below.		

p1333[0...n]	U/f control FCC starting frequency / U/f FCC f_start		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6301
	Min	Max	Factory setting
	0.00 [Hz]	3000.00 [Hz]	0.00 [Hz]
Description:	Sets the starting frequency at which FCC (Flux Current Control) is activated.		
Dependency:	The correct operating mode must be set (p1300 = 1, 6).		
Warning:	An excessively low value can result in instability.		
			
Note:	For p1333 = 0 Hz, the FCC starting frequency is automatically set to 6 % of the rated motor frequency.		

p1334[0...n]	U/f control slip compensation starting frequency / Slip comp start		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6310
	Min 0.00 [Hz]	Max 3000.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Sets the starting frequency of the slip compensation.		
Note:	For p1334 = 0, the starting frequency of the slip compensation is automatically set to 6 % of the rated motor frequency.		
p1335[0...n]	Slip compensation scaling / Slip comp scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6310
	Min 0.0 [%]	Max 600.0 [%]	Factory setting 0.0 [%]
Description:	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.		
Dependency:	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. For U/f control types with Eco optimization (4 and 7), the slip compensation must be activated in order to guarantee correct operation.		
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 during commissioning (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		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6310
	Min 0.00 [%]	Max 600.00 [%]	Factory setting 250.00 [%]
Description:	Sets the limit value for slip compensation in [%] referred to r0330 (motor rated slip).		
r1337	CO: Actual slip compensation / Slip comp act val		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6310
	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		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6310
	Min	Max	Factory setting
	0.00	100.00	0.00
Description:	Sets the gain for resonance damping for U/f control.		
Dependency:	Refer to: p1300, p1349		
Note:	<p>The resonance damping function dampens active current oscillations that frequency occur under no-load conditions. The resonance damping is active in a range from approximately 6 % of the rated motor frequency (p0310). The shutoff frequency is determined by p1349.</p> <p>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.</p>		
p1340[0...n]	I_max frequency controller proportional gain / I_max_ctrl Kp		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300
	Min	Max	Factory setting
	0.000	0.500	0.000
Description:	<p>Sets the proportional gain of the I_max frequency controller.</p> <p>The I_max controller reduces the drive converter output current if the maximum current (r0067) is exceeded. In the U/f operating modes (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).</p>		
Dependency:	In the U/f modes (p1300) for textile applications and for external voltage setpoints, only the I_max voltage controller is used.		
Notice:	<p>When de-activating the I_max controller, the following must be carefully observed:</p> <p>When the maximum current (r0067) is exceeded, the output current is no longer reduced. The drive is switched off when the overcurrent limits are exceeded.</p>		
Note:	<p>p1341 = 0: I_max frequency controller de-activated and I_max voltage controller activated over the complete speed range.</p>		
p1341[0...n]	I_max frequency controller integral time / I_max_ctrl Tn		
	Access level: 4	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300
	Min	Max	Factory setting
	0.000 [s]	50.000 [s]	0.300 [s]
Description:	Sets the integral time for the I_max frequency controller.		
Dependency:	Refer to: p1340		
Note:	<p>When p1341 = 0, the current limiting controller influencing the frequency is de-activated and only the current limiting controller influencing the output voltage remains active (p1345, p1346).</p> <p>This current limiting function is de-activated with p1340 = p1341 = 0.</p>		

r1343	CO: I_max controller frequency output / I_max_ctrl f_outp		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 6300
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Displays the effective frequency limit.		
Dependency:	Refer to: p1340		
r1344	I_max controller voltage output / I_max_ctrl U_outp		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 6300
	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
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		
	Access level: 4	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300
	Min	Max	Factory setting
	0.000	100000.000	0.000
Description:	Sets the proportional gain for the I_max voltage controller.		
Dependency:	Refer to: p1340		
Note:	The controller settings are also used in the current controller of the DC braking (refer to p1232).		
p1346[0...n]	I_max voltage controller integral time / I_max_U_ctrl Tn		
	Access level: 4	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6300
	Min	Max	Factory setting
	0.000 [s]	50.000 [s]	0.030 [s]
Description:	Sets the integral time for the I_max voltage controller.		
Dependency:	Refer to: p1340		
Note:	The controller settings are also used in the current controller of the DC braking (refer to p1232). For p1346 = 0, the following applies: The integral time of the I_max voltage controller is de-activated.		
r1348	CO: U/f control Eco factor actual value / U/f Eco fac act v		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6300, 6301
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Displays the economic factor determined for optimizing motor consumption.		
Dependency:	Refer to: p1335		
Note:	The value is only determined for operating modes with Economic (p1300 = 4, 7).		

p1349[0...n]	U/f mode resonance damping maximum frequency / Uf res_damp f_max			
	Access level: 3		Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T		Scaling: -	Dyn. index: DDS, p0180
	Unit group: -		Unit selection: -	Func. diagram: 6310
	Min	Max	Factory setting	
	0.00 [Hz]	3000.00 [Hz]	0.00 [Hz]	
Description:	Sets the maximum output frequency for resonance damping for U/f control. Resonance damping is inactive above this output frequency.			
Dependency:	Refer to: p1338			
Note:	For p1349 = 0, the changeover limit is automatically set to 95 % of the rated motor frequency - however, to a max. of 45 Hz.			

p1351[0...n]	CO: Motor holding brake starting frequency / Brake f_start			
	Access level: 3		Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T		Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: -		Unit selection: -	Func. diagram: 6310
	Min	Max	Factory setting	
	-300.00 [%]	300.00 [%]	0.00 [%]	
Description:	Sets the frequency setting value at the slip compensation output for starting up with motor holding brake.			
Dependency:	When setting p1351 > 0, then slip compensation is automatically activated (p1335 = 100 %). Refer to: p1302, p1352			
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.			
Note:	Connected with p1352 a value of 100% corresponds to the motor rated slip (r0330).			

p1352[0...n]	CI: Motor holding brake starting frequency signal source / Brake f_start			
	Access level: 3		Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T		Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -		Unit selection: -	Func. diagram: 6310
	Min	Max	Factory setting	
	-	-	1351[0]	
Description:	Sets the signal source for the frequency setting value at the slip compensation output for starting up with motor holding brake.			
Dependency:	Refer to: p1216			
Note:	A value of 100% corresponds to the motor rated slip (r0330). The setting of the starting frequency begins after magnetizing (see p0346, r0056.4) and ends once the brake opening time (p1216) has elapsed and the starting frequency (p1334) has been reached. A setting value of zero means that no setting procedure will take place.			

p1400[0...n]	Speed control configuration / n_ctrl config				
	Access level: 3		Calculated: -	Data type: Unsigned32	
	Can be changed: U, T		Scaling: -	Dyn. index: DDS, p0180	
	Unit group: -		Unit selection: -	Func. diagram: 6490	
	Min	Max	Factory setting		
	-	-	0000 0000 0000 0000 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	6040
	01	Sensorless vector control freeze I comp	Yes	No	6040
	05	Kp/Tn adaptation active	Yes	No	6040
	06	Free Tn adaptation active	Yes	No	6050
	14	Torque pre-control	Always active	For n_ctrl enab	6060
	15	Sensorless vector control speed pre-control	Yes	No	6030
	16	I component for limiting	Enable	Hold	6030

2 Parameters

2.2 List of parameters

18	Moment of inertia estimator active	Yes	No	6030
20	Acceleration model	ON	OFF	6031
22	Obtain moment of inertia estimator value for pulse inhibit	Yes	No	6030
24	Accelerated moment of inertia estimator active	Yes	No	6030

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.

Re bit 20:

The acceleration model for the speed setpoint is only active if p1496 is not zero.

r1406.4...15

CO/BO: Control word speed controller / STW n_ctrl

Access level: 4	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description:

Display and BICO output for the control word of the speed controller.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
04	Hold speed controller I component	Yes	No	6040
05	Set speed controller I component	Yes	No	6040
11	Reserved	-	-	-
15	Set speed adaptation controller I component	Yes	No	-

r1407.0...27

CO/BO: Status word speed controller / ZSW n_ctrl

Access level: 4	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2522
Min	Max	Factory setting
-	-	-

Description:


Display and BICO output for 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	Encoderless operation active	Yes	No	-
02	Torque control active	Yes	No	6030, 6060, 8011
03	Speed control active	Yes	No	6040
05	Speed controller I component frozen	Yes	No	6040
06	Speed controller I component set	Yes	No	6040
07	Torque limit reached	Yes	No	6060
08	Upper torque limit active	Yes	No	6060
09	Lower torque limit active	Yes	No	6060
10	Reserved	-	-	-
11	Speed setpoint limited	Yes	No	6030
12	Ramp-function generator set	Yes	No	-
13	Encoderless operation due to a fault	Yes	No	-
14	I/f control active	Yes	No	-
15	Torque limit reached (without pre-control)	Yes	No	6060
17	Speed limiting control active	Yes	No	6640
23	Acceleration model activated	Yes	No	-
24	Moment of inertia estimator active	Yes	No	-
25	Load estimate active	Yes	No	-
26	Moment of inertia estimator stabilized	Yes	No	-
27	Accelerated moment of inertia estimator active	Yes	No	-

SINAMICS G120C
List Manual (LH13), 04/2015, A5E33840768

p1470[0...n]	Speed controller encoderless operation P-gain / n_ctrl SL Kp		
	Access level: 2	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6040, 6050
	Min 0.000	Max 999999.000	Factory setting 0.300
Description:	Sets the P gain for encoderless operation for the speed controller.		
Note:	The product p0341 x p0342 is taken into account when automatically calculating the speed controller (p0340 = 1, 3, 4).		
p1472[0...n]	Speed controller encoderless operation integral time / n_ctrl SL Tn		
	Access level: 2	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6040, 6050
	Min 0.0 [ms]	Max 100000.0 [ms]	Factory setting 20.0 [ms]
Description:	Set the integral time for encoderless operation for the speed controller.		
Note:	The integral component is stopped if the complete controller output or the sum of controller output and torque pre-control reach the torque limit.		
p1475[0...n]	CI: Speed controller torque setting value for motor holding brake / n_ctrl M_sv MHB		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2003	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 6040
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the torque setting value when starting up with motor holding brake.		
Dependency:	.		
Note:	The setting of the integral output of the speed controller begins after magnetizing (see p0346, r0056 bit 4) and ends at the end of the brake control opening time p1216. A setting value of zero means that no setting procedure will take place. If p1351 is used as a signal source for the torque setting value, the percentage value is interpreted in relation to the rated torque (p2003).		
r1482	CO: Speed controller I torque output / n_ctrl I-M_outp		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 5040, 5042, 5210, 6030, 6040
	Min - [Nm]	Max - [Nm]	Factory setting - [Nm]
Description:	Display and connector output for the torque setpoint at the output of the I speed controller.		
r1493	CO: Moment of inertia total, scaled / M_inert tot scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: 25_1	Unit selection: p0100	Func. diagram: 6031
	Min - [kgm²]	Max - [kgm²]	Factory setting - [kgm²]
Description:	Display and connector output for the parameterized total moment of inertia. The value is calculated as follows: (p0341 * p0342) + p1496		


p1496[0...n]	Acceleration pre-control scaling / a_prectrl scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6020, 6031
	Min	Max	Factory setting
	0.0 [%]	10000.0 [%]	0.0 [%]
	Description: Sets the scaling for the acceleration pre-control of the speed/velocity controller.		
	Dependency: Refer to: p0341, p0342		
	Warning: The acceleration precontrol is kept at the old value if the ramp-function generator tracking (r1199.5) is active or the ramp-function generator output is set (r1199.3). This is used to avoid torque peaks. Depending on the application, it may therefore be necessary to disable the ramp-function generator tracking (p1145 = 0) or the acceleration precontrol (p1496 = 0).		
	The acceleration precontrol is set to zero, if the Vdc control is active (r0056.14/15).		
	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 M_inertia		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 25_1	Unit selection: p0100	Func. diagram: 6031
	Min	Max	Factory setting
	0.00000 [kgm²]	100000.00000 [kgm²]	0.00000 [kgm²]
	Description: Sets the load moment of inertia.		
	Note: (p0341 * p0342) + p1498 influence the speed/torque pre-control in encoderless operation.		
p1502[0...n]	BI: Freeze moment of inertia estimator / J_estim freeze		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	0
	Description: Sets the signal source to freeze the estimated moment of inertia.		
	0 signal: Moment of inertia estimator active 1 signal: Determined moment of inertia frozen.		
	Dependency: Refer to: p1300		
	Note: Only active when the "moment of inertia estimator" function module is active (r0108.10 = 1) and p1400.18 = 1.		
	For operation with encoder, in addition, p1402.4 must be set to 1.		
r1508	CO: Torque setpoint before supplementary torque / M_set bef. M_suppl		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6030, 6060, 6722
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
	Description: Displays the torque setpoint before entering the supplementary torque.		
	For closed-loop speed control, r1508 corresponds to the speed controller output.		

p1511[0...n]	CI: Supplementary torque 1 / M_suppl 1		
	Access level: 3 Can be changed: T Unit group: - Min -	Calculated: - Scaling: p2003 Unit selection: - Max -	Data type: U32 / FloatingPoint32 Dyn. index: CDS, p0170 Func. diagram: 6020, 6060 Factory setting 0
Description: Sets the signal source for supplementary torque 1.			
r1515	Supplementary torque total / M_suppl total		
	Access level: 4 Can be changed: - Unit group: 7_1 Min - [Nm]	Calculated: - Scaling: p2003 Unit selection: p0505 Max - [Nm]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 6020, 6060 Factory setting - [Nm]
Description: Displays the total supplementary torque. The displayed value is the total of supplementary torque values 1 and 2.			
r1516	CO: Supplementary torque and acceleration torque / M_suppl + M_accel		
	Access level: 2 Can be changed: - Unit group: 7_1 Min - [Nm]	Calculated: - Scaling: p2003 Unit selection: p0505 Max - [Nm]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 6060 Factory setting - [Nm]
Description: Displays the total supplementary torque and the accelerating torque. The displayed value is the total of the smoothed supplementary torque and the accelerating torque.			
p1517[0...n]	Accelerating torque smoothing time constant / M_accel T_smooth		
	Access level: 4 Can be changed: U, T Unit group: - Min 0.00 [ms]	Calculated: - Scaling: - Unit selection: - Max 100.00 [ms]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6060 Factory setting 4.00 [ms]
Description: Sets the smoothing time constant of the accelerating torque.			
Note: The acceleration pre-control is inhibited if the smoothing is set to the maximum value.			
p1520[0...n]	CO: Torque limit upper / M_max upper		
	Access level: 2 Can be changed: U, T Unit group: 7_1 Min -1000000.00 [Nm]	Calculated: p0340 = 1,3,5 Scaling: p2003 Unit selection: p0505 Max 20000000.00 [Nm]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6020, 6630 Factory setting 0.00 [Nm]
Description: Sets the fixed, upper torque limit.			
Dependency: Refer to: p1521, p1522, p1523, r1538, r1539			
Danger: 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 data set always acts on the effective data set.			
Note: The torque limit is limited to 400% of the rated motor torque. When automatically calculating the motor/closed-loop control parameters (p0340), the torque limit is set to match the current limit (p0640).			

p1521[0...n]	CO: Torque limit lower / M_max lower		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2003	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6020, 6630
	Min -20000000.00 [Nm]	Max 1000000.00 [Nm]	Factory setting 0.00 [Nm]
Description:	Sets the fixed, lower torque limit.		
Dependency:	Refer to: p1520, p1522, p1523		
Danger:	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 data set always acts on the effective data set.		
Note:	The torque limit is limited to 400% of the rated motor torque. When automatically calculating the motor/closed-loop control parameters (p0340), the torque limit is set to match the current limit (p0640).		
p1522[0...n]	CI: Torque limit upper / M_max upper		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2003	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 6630
	Min -	Max -	Factory setting 1520[0]
Description:	Sets the signal source for the upper torque limit.		
Dependency:	Refer to: p1520, p1521, p1523		
Danger:	Negative values resulting from the signal source and scaling can cause the motor to accelerate in an uncontrolled manner.		
			
p1523[0...n]	CI: Torque limit lower / M_max lower		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2003	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 6020, 6630
	Min -	Max -	Factory setting 1521[0]
Description:	Sets the signal source for the lower torque limit.		
Dependency:	Refer to: p1520, p1521, p1522		
Danger:	Positive values resulting from the signal source and scaling can cause the motor to accelerate in an uncontrolled manner.		
			
p1524[0...n]	CO: Torque limit upper scaling / M_max upper scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6630
	Min -2000.0 [%]	Max 2000.0 [%]	Factory setting 100.0 [%]
Description:	Sets the scaling for the upper torque limit.		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
Note:	This parameter can be freely interconnected.		

p1525[0...n]	CO: Torque limit lower scaling / M_max lower scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6630
	Min	Max	Factory setting
	-2000.0 [%]	2000.0 [%]	100.0 [%]
Description:	Sets the scaling for the lower torque limit.		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
Note:	This parameter can be freely interconnected.		
r1526	CO: Torque limit upper without offset / M_max up w/o offs		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6060, 6630, 6640
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Display and connector output for the upper torque limit of all torque limits without offset.		
Dependency:	Refer to: p1520, p1521, p1522, p1523		
r1527	CO: Torque limit lower without offset / M_max low w/o offs		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6060, 6630, 6640
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Display and connector output for the lower torque limit of all torque limits without offset.		
Dependency:	Refer to: p1520, p1521, p1522, p1523		
p1530[0...n]	Power limit motoring / P_max mot		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 14_5	Unit selection: p0505	Func. diagram: 6640
	Min	Max	Factory setting
	0.00 [kW]	100000.00 [kW]	0.00 [kW]
Description:	Sets the power limit when motoring.		
Dependency:	Refer to: p0500, p1531		
Note:	The power limit is limited to 300% of the rated motor power.		
p1531[0...n]	Power limit regenerative / P_max gen		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 14_5	Unit selection: p0505	Func. diagram: 6640
	Min	Max	Factory setting
	-100000.00 [kW]	-0.01 [kW]	-0.01 [kW]
Description:	Sets the regenerative power limit.		
Dependency:	Refer to: r0206, p0500, p1530		
Note:	The power limit is limited to 300% of the rated motor power. For power units without energy recovery capability, the regenerative power limit is preset to 30 % of the power r0206[0]. For a braking resistor connected to the DC link (p0219 > 0), the power limit when generating is automatically adapted. For power units with energy recovery, the parameter is limited to the negative value of r0206[2].		

r1533	Current limit torque-generating total / Iq_max total		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2002	Dyn. index: -
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 6640
	Min	Max	Factory setting
	- [Arms]	- [Arms]	- [Arms]
Description:	Displays the maximum torque/force generating current as a result if all current limits.		
r1538	CO: Upper effective torque limit / M_max upper eff		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6020, 6640
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Display and connector output for the actual effective upper torque limit.		
Note:	The effective upper torque limit is reduced with respect to the selected upper torque limit p1520, if the current limit p0640 is reduced or the rated magnetizing current of the induction motor p0320 is increased. This may be the case for rotating measurements (see p1960). The torque limit p1520 can be re-calculated using p0340 = 1, 3 or 5.		
r1539	CO: Lower effective torque limit / M_max lower eff		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6020, 6640
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Display and connector output for the actual 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. This may be the case for rotating measurements (see p1960). The torque limit p1520 can be re-calculated using p0340 = 1, 3 or 5.		
r1547[0...1]	CO: Torque limit for speed controller output / M_max outp n_ctrl		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2003	Dyn. index: -
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 6060
	Min	Max	Factory setting
	- [Nm]	- [Nm]	- [Nm]
Description:	Displays the torque limit to limit the speed controller output.		
Index:	[0] = Upper limit [1] = Lower limit		
p1552[0...n]	CI: Torque limit upper scaling without offset / M_max up w/o offs		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 6060
	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.		

p1553[0...n]	Stall limit scaling / Stall limit scal		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
Description: Danger: 	Min	Max	Factory setting
	80.0 [%]	130.0 [%]	100.0 [%]
	Sets the scaling of the stall limit for the start of field weakening.		
	If the stall current limit is increased, then the q current setpoint can exceed the stall limit; as a consequence, a hysteresis effect can occur when loading and unloading.		
p1554[0...n]	CI: Torque limit lower scaling without offset / M_max low w/o offs		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 6060
Description:	Min	Max	Factory setting
	-	-	1
	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.		
p1560[0...n]	Moment of inertia estimator accelerating torque threshold value / J_est M thresh		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	0.10 [%]	100.00 [%]	10.00 [%]
	Sets the threshold for the accelerating torque for the moment of inertia estimator.		
	The moment of inertia estimator is active above this threshold.		
Dependency:	The value is referred to the rated torque (r0333).		
	Refer to: p1400, p1561, p1562		
Note:	The moment of inertia estimation is inaccurate at very low accelerating torques. As a consequence, below this threshold, the estimator does not provide any new values.		
p1561[0...n]	Moment of inertia estimator change time moment of inertia / J_est t J		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	10.00 [ms]	5000.00 [ms]	500.00 [ms]
	Sets the change time for the moment of inertia for the moment of inertia estimator.		
	Lower values mean that faster changes are possible.		
Dependency:	For a higher value, this estimated value is smoothed more significantly.		
	Refer to: p1400, p1560, p1562		
p1562[0...n]	Moment of inertia estimator change time load / J_est t load		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
Description:	Min	Max	Factory setting
	5.00 [ms]	5000.00 [ms]	10.00 [ms]
	Sets the change time for the load torque for the moment of inertia estimator.		
	Lower values mean that faster changes are possible.		
Dependency:	For a higher value, this estimated value is smoothed more significantly.		

Dependency: Refer to: p1400, p1560, p1561

p1563[0...n] CO: Mom. of inertia estimator load torque direction of rotation pos. / J_est M pos

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: p2003	Dyn. index: DDS, p0180
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-340.28235E36 [Nm]	340.28235E36 [Nm]	0.00 [Nm]

Description: Display and connector output for the monitored load torque in the positive direction of rotation.
The moment of inertia estimator estimates the load torque drawn while the speed is constant.

Dependency: Refer to: p1400, p1560, p1561

p1564[0...n] CO: Mom. of inertia estimator load torque direction of rotation neg. / J_est M neg

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: p2003	Dyn. index: DDS, p0180
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-340.28235E36 [Nm]	340.28235E36 [Nm]	0.00 [Nm]

Description: Display and connector output for the monitored load torque in the negative direction of rotation.
The moment of inertia estimator estimates the load torque drawn while the speed is constant.

Dependency: Refer to: p1400, p1560, p1561

p1570[0...n] CO: Flux setpoint / Flex setp

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
Unit group: -	Unit selection: -	Func. diagram: 6722
Min	Max	Factory setting
50.0 [%]	200.0 [%]	100.0 [%]

Description: Sets the flux setpoint referred to rated motor flux.

Notice: A BICO interconnection to a parameter that belongs to a drive data set 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), if p1580 > 0% has been set.

p1575[0...n] Voltage target value limit / U_tgt val lim

Access level: 4	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
Unit group: -	Unit selection: -	Func. diagram: 6725
Min	Max	Factory setting
50.00 [%]	200.00 [%]	200.00 [%]


Description: Sets the limit of the voltage target value.
In steady-state field weakening operation this corresponds to the required output voltage.
The value of 100% refers to p0304.

Note: The output voltage is only limited if the maximum output voltage (r0071) minus the voltage reserve (p1574) corresponds to a value higher than p1575.

Limiting via p1575 allows the influence of the voltage ripple of the line supply voltage to be eliminated at the operating point.

p1580[0...n]	Efficiency optimization / Efficiency opt.		
	Access level: 3 Can be changed: U, T Unit group: - Min 0 [%]	Calculated: - Scaling: - Unit selection: - Max 100 [%]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6722 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 Tn, 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		
	Access level: 4 Can be changed: U, T Unit group: - Min 4 [ms]	Calculated: p0340 = 1,3 Scaling: - Unit selection: - Max 5000 [ms]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6722, 6724 Factory setting 15 [ms]
Description:	Sets the smoothing time for the flux setpoint.		
p1586[0...n]	Field weakening characteristic scaling / Field weak scal		
	Access level: 4 Can be changed: U, T Unit group: - Min 80.0 [%]	Calculated: - Scaling: - Unit selection: - Max 120.0 [%]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: - Factory setting 100.0 [%]
Description:	Sets the scaling of the pre-control characteristic for the start of field weakening. For values above 100 % and for partial load situations, the field weakening starts at higher speeds.		
Note:	If the start of field weakening is shifted to lower speeds, then the voltage reserve is increased for partial load situations. If the start of field weakening is shifted to higher speeds, the voltage reserve is appropriately reduced so that for fast load changes, it can be expected that this will have a negative impact on the dynamic performance.		
p1590[0...n]	Flux controller P gain / Flux controller Kp		
	Access level: 4 Can be changed: U, T Unit group: - Min 0.0	Calculated: p0340 = 1,3,4 Scaling: - Unit selection: - Max 999999.0	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6723 Factory setting 10.0
Description:	Sets the proportional gain for the flux controller.		
Note:	The value is automatically pre-assigned dependent on the motor when the drive system is first commissioned. When calculating controller parameters (p0340 = 4), this value is re-calculated.		

r1598	CO: Total flux setpoint / Flux setp total		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6714, 6723, 6724, 6725, 6726, 8018
Description:	Min	Max	Factory setting
	- [%]	- [%]	- [%]
	Displays the effective flux setpoint.		
	The value is referred to the rated motor flux.		
p1610[0...n]	Torque setpoint static (sensorless) / M_set static		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6700, 6721, 6722, 6726
Description:	Min	Max	Factory setting
	-200.0 [%]	200.0 [%]	50.0 [%]
	Sets the static torque setpoint for sensorless vector control (SLVC).		
	This parameter is entered as a percentage referred to the rated motor torque.		
Notice:	For sensorless 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.		
	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 (ASM: rated magnetizing current, RESM: no-load magnetizing current).		
	For p1610 = 100 %, a current setpoint is calculated that corresponds to the rated motor torque.		
p1611[0...n]	Additional acceleration torque (sensorless) / M_suppl_accel		
	Access level: 2	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6700, 6721, 6722, 6726
Description:	Min	Max	Factory setting
	0.0 [%]	200.0 [%]	30.0 [%]
	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.		
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 pre-control of the speed controller (p1496).		
r1614	EMF maximum / EMF max		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 6725
Description:	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
	Displays the actual maximum possible electromotive force (EMF) of the separately-excited synchronous motor.		
	Dependency: The value is the basis for the flux setpoint.		
	The maximum possible EMF depends on the following factors:		
	- Actual DC link voltage (r0070).		
	- Maximum modulation depth (p1803).		
	- Field-generating and torque-generating current setpoint.		

p1616[0...n]	Current setpoint smoothing time / I_set T_smooth		
	Access level: 3 Can be changed: U, T Unit group: - Min 4 [ms]	Calculated: p0340 = 1,3 Scaling: - Unit selection: - Max 10000 [ms]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6721, 6722 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 injected for sensorless vector control.		
r1624	Field-generating current setpoint total / Id_setp total		
	Access level: 4 Can be changed: - Unit group: 6_2 Min - [Arms]	Calculated: - Scaling: p2002 Unit selection: p0505 Max - [Arms]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: 6640, 6721, 6723, 6727 Factory setting - [Arms]
Description:	Displays the limited field-generating current setpoint (Id_setp). This value comprises the steady-state field-generating current setpoint and a dynamic component that is only set when changes are made to the flux setpoint.		
p1715[0...n]	Current controller P gain / I_ctrl Kp		
	Access level: 4 Can be changed: U, T Unit group: - Min 0.000	Calculated: p0340 = 1,3,4 Scaling: - Unit selection: - Max 100000.000	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6714 Factory setting 0.000
Description:	Sets the proportional gain of the current controller. This value is automatically pre-set using p3900 or p0340 when commissioning has been completed.		
p1717[0...n]	Current controller integral-action time / I_ctrl Tn		
	Access level: 4 Can be changed: U, T Unit group: - Min 0.00 [ms]	Calculated: p0340 = 1,3,4 Scaling: - Unit selection: - Max 1000.00 [ms]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 5714, 6700, 6714, 7017 Factory setting 2.00 [ms]
Description:	Sets the integral-action time of the current controller.		
Dependency:	Refer to: p1715		
p1730[0...n]	Isd controller integral component shutdown threshold / Isd ctrl Tn shutd		
	Access level: 4 Can be changed: U, T Unit group: - Min 30 [%]	Calculated: p0340 = 1,3,4 Scaling: - Unit selection: - Max 150 [%]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: - Factory setting 30 [%]
Description:	Sets the speed activation threshold (referred to the synchronous speed) for pure quadrature branch operation of the closed-loop current control. The d current controller is only effective as P controller for speeds greater than the threshold value.		
Warning:	For settings above 80%, the d current controller is active up to the field weakening limit. When operated at the voltage limit, this can result in an unstable behavior.		
			
Note:	The parameter value is referred to the synchronous rated motor speed.		


r1732[0...1]	CO: Direct-axis voltage setpoint / Direct U set		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 5700, 5714, 6714, 5718
	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
Description:	Display and connector output for the direct axis voltage setpoint Ud.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045		

r1733[0...1]	CO: Quadrature-axis voltage setpoint / Quad U set		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2001	Dyn. index: -
	Unit group: 5_1	Unit selection: p0505	Func. diagram: 5700, 5714, 5718, 6714, 6719
	Min	Max	Factory setting
	- [Vrms]	- [Vrms]	- [Vrms]
Description:	Display and connector output for the quadrature axis voltage setpoint Uq.		
Index:	[0] = Unsmoothed [1] = Smoothed with p0045		

p1740[0...n]	Gain resonance damping for encoderless closed-loop control / Gain res_damp		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.000	10.000	0.025
Description:	Defines the gain of the controller for resonance damping for operation with sensorless vector control in the range that current is injected.		

p1745[0...n]	Motor model error threshold stall detection / MotMod ThreshStall		
	Access level: 3	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.0 [%]	1000.0 [%]	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 status signal r1408.12 is set to 1.		
Dependency:	If a stalled drive is detected (r1408.12 = 1), fault F07902 is output after the delay time.		
Note:	Monitoring is only effective in the low speed range.		

r1746	Motor model error signal stall detection / MotMod sig stall		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Signal to initiate stall detection		
Note:	The signal is not calculated while magnetizing and only calculated in the low speed range.		

p1749[0...n]	Motor model increase changeover speed encoderless operation / Incr n_chng no enc				
	Access level: 4	Calculated: p0340 = 1,3	Data type: FloatingPoint32		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0.0 [%]	99.0 [%]	50.0 [%]		
Description:	Minimum operating frequency for rugged operation. If the minimum value is greater than the lower changeover limit parameterized with p1755 * (1 - 2 * p1756), then the difference is displayed using p1749 * p1755. The parameter value cannot be changed.				
Dependency:	Refer to: p1755, p1756				
p1750[0...n]	Motor model configuration / MotMod config				
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: Unsigned8		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 0000 bin		
Description:	Sets the configuration for the motor model. Bit 0 = 1: Forces open-loop speed-controlled starting (ASM). Bit 1 = 1: Forces the system to pass through frequency zero, open-loop-controlled (ASM). Bit 2 = 1: Drive remains in full closed-loop control mode, even at zero frequency (ASM). Bit 3 = 1: Motor model evaluates the saturation characteristic (ASM). Bit 6 = 1: If the motor is blocked, sensorless vector control remains speed-controlled (ASM). Bit 7 = 1: Use rugged switchover limits to switchover the model (open-loop/closed-loop controlled) for regenerative operation (ASM).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Controlled start	Yes	No	-
	01	Controlled through 0 Hz	Yes	No	-
	02	Closed-loop ctrl oper. down to zero freq. for passive loads	Yes	No	-
	03	Motor model Lh_pre = f(PsiEst)	Yes	No	-
	06	Closed-loop/open-loop controlled (PMSM) for a blocked motor	Yes	No	-
	07	Use rugged changeover limits	Yes	No	-
Dependency:	Refer to: p0500				
Caution:	Do not use bit 6 = 1 if the motor can be slowly reversed by the load at the torque limit. Long delay times due to blocking (p2177 > p1758) can cause the motor to stall. In this case you should de-activate the function or use closed-loop control throughout the speed range (note the information re bit 2 = 1).				
					
Note:	Bits 0 ... 2 only have an influence for encoderless vector control, bit 2 is pre-assigned depending on p0500. Re bit 2 = 1: The sensorless vector control is effective down to zero frequency. A change is not made into the open-loop speed controlled mode. This operating mode is possible for passive loads. These include applications where the load itself does not generate any active torque and therefore only acts reactively to the drive torque of the induction motor. If bit 2 = 1, then bit 3 is automatically set to 1. Manual de-selection is possible and may be sensible if the saturation characteristic (p1960) was not measured for third-party motors. Generally, for standard SIEMENS motors, the already pre-assigned (default value) saturation characteristic is adequate. When the bit is set, the selection of bits 0 and 1 is ignored. Re bit 2 = 0: Bit 3 is also automatically deactivated. Re bit 6 = 1: The following applies for encoderless vector control of induction motors: For a blocked motor (see p2175, p2177) the time condition in p1758 is bypassed and a change is not made into open-loop controlled operation.				

The following applies for encoderless vector control of synchronous motors:

For a blocked motor (see p2175, p2177), the speed ramp-function generator is held in open-loop speed controlled operation, and a change is not made into closed-loop controlled operation.

Re bit 7 = 1:

The following applies for encoderless vector control of induction motors:

If the changeover limits are parameterized too low (p1755, p1756), then they are automatically increased to rugged values by the absolute amount $p1749 * p1755$.

The effective time condition for changing over into open-controlled operation is obtained from the minimum value of p1758 and $0.5 * r0384$.

Is recommended that bit 7 is activated for applications that demand a high torque at low frequencies, and at the same time require low speed gradients..

Adequate parameterization of the current setpoint must be ensured (p1610, p1611).

p1755[0...n]	Motor model changeover speed encoderless operation / MotMod n_chgSnsorI		
	Access level: 3	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: -
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	210000.00 [rpm]
Description:	Sets the speed to change over the motor model to encoderless operation.		
Dependency:	Refer to: p1749, p1756		
Notice:	The changeover speed represents the steady-state minimum speed up to which the motor model can be used in sensorless steady-state operation. If the stability is not adequate close to the changeover speed, it may make sense to increase the parameter value. On the other hand, very low changeover speeds can negatively impact the stability.		
Note:	The changeover speed applies for the changeover between open-loop and closed-loop control mode.		
p1756	Motor model changeover speed hysteresis encoderless operation / MotMod n_chgov hys		
	Access level: 4	Calculated: p0340 = 1,3	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 6730, 6731
	Min	Max	Factory setting
	0.0 [%]	95.0 [%]	50.0 [%]
Description:	Sets the hysteresis for the changeover speed of the motor model for encoderless operation.		
Dependency:	Refer to: p1755		
Note:	The parameter value refers to p1755. Extremely small hystereses can have a negative impact on the stability in the changeover speed range, and very high hystereses in the standstill range.		
p1764[0...n]	Motor model without encoder speed adaptation Kp / MotMod woE n_adaKp		
	Access level: 4	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 6730
	Min	Max	Factory setting
	0.000	100000.000	1000.000
Description:	Sets the proportional gain of the controller for speed adaptation without encoder.		

p1767[0...n]	Motor model without encoder speed adaptation Tn / MotMod woE n_adaTn			
	Access level: 4	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32	
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180	
	Unit group: -	Unit selection: -	Func. diagram: 6730	
	Min	Max	Factory setting	
	1 [ms]	200 [ms]	4 [ms]	
Description:	Sets the integral time of the controller for speed adaptation without encoder			

p1780[0...n]	Motor model adaptation configuration / MotMod adapt conf				
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 0000 0101 1100 bin		
Description:	Sets the configuration for the adaptation circuit of the motor model. Induction motor (ASM): Rs, Lh, and offset compensation. Permanent-magnet synchronous motor (PMSM): 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 PMSM kT adaptation	Yes	No	-
	04	Select motor model offset adaptation	Yes	No	-
	06	Select pole position identification PMSM encoderless	Yes	No	-
	07	Select T(valve) with Rs adaptation	Yes	No	-
	10	Filter time combination current like current ctrl integral time	Yes	No	-
	12	Start PMSM sensorless with last angle	Yes	No	-
	13	Fast pulsed pole position identification	Yes	No	-
	14	Delay of the precontrol speed to the motor model	Yes	No	-
	15	RESM Q flux model linear active	Yes	No	-
Dependency:	In U/f characteristic operating mode only bit 7 is relevant. For active motor model feedback (see p1784), the Lh adaptation is internally deactivated automatically.				
Note:	ASM: Induction motor PMSM: permanent-magnet synchronous motor 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. In order that the correction values of the Rs, Lh and kT adaptation (selected using Bit 0 ... Bit 2) are correctly accepted when changing over the drive data set, a dedicated motor number must be entered into p0826 for each different motor. Re bit 12 (only for synchronous motors and bit 6 = 1): The pole position identification is only carried out after power on and after the motor has coasted down. The switch-off speed p1226 should be as low as possible. If the power unit is switched off when the motor is stationary, then the next time that the power unit is switched on, the old angle is used as starting value. The precondition applies that while the power unit is switched off the motor does not rotate. The duration of the pole position identification is shortened using bit 13. As a consequence, the pole wheel angle error can be slightly greater.				

p1784[0...n]	Motor model feedback scaling / MotMod fdbk scal		
	Access level: 4 Can be changed: U, T Unit group: - Min 0.0 [%]	Calculated: p0340 = 1,3,4 Scaling: - Unit selection: - Max 1000.0 [%]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: - Factory setting 0.0 [%]
Description:	Sets the scaling for model fault feedback.		
Note:	Feeding back the measured model fault to the model states increases the control stability and makes the motor model rugged against parameter errors. When feedback is selected (p1784 > 0), Lh adaptation is not effective.		
r1787[0...n]	Motor model Lh adaptation corrective value / MotMod Lh corr		
	Access level: 4 Can be changed: - Unit group: - Min - [mH]	Calculated: - Scaling: - Unit selection: - Max - [mH]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: - Factory setting - [mH]
Description:	Displays the corrective value for the Lh adaptation of the motor model for an induction motor (ASM).		
Dependency:	Refer to: p0826, p1780		
Note:	The adaptation result is reset if the magnetizing inductance of the induction motor is changed (p0360, r0382).		
p1800[0...n]	Pulse frequency setpoint / Pulse freq setp		
	Access level: 2 Can be changed: U, T Unit group: - Min 2.000 [kHz]	Calculated: - Scaling: - Unit selection: - Max 16.000 [kHz]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 8019 Factory setting 4.000 [kHz]
Description:	Sets the pulse frequency for the converter. This parameter is pre-set to the rated converter value when the drive is first commissioned.		
Dependency:	Refer to: p0230		
Note:	The maximum and minimum possible pulse frequency is also determined by the power unit being used (minimum pulse frequency: 2 kHz or 4 kHz). When the pulse frequency is increased, depending on the particular power unit, the maximum output current can be reduced (derating, refer to r0067). If a sine-wave filter is parameterized as output filter (p0230 = 3), then the pulse frequency cannot be set below the minimum value required for the filter. For operation with output reactors, the pulse frequency is limited to 4 kHz (see p0230). If p1800 is changed during commissioning (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[0...1]	CO: Pulse frequency / Pulse frequency		
	Access level: 2 Can be changed: - Unit group: - Min - [kHz]	Calculated: - Scaling: p2000 Unit selection: - Max - [kHz]	Data type: FloatingPoint32 Dyn. index: - Func. diagram: - Factory setting - [kHz]
Description:	Display and connector output for the actual converter switching frequency.		
Index:	[0] = Actual [1] = Modulator minimum value		
Note:	The selected pulse frequency (p1800) may be reduced if the drive converter has an overload condition (p0290).		

p1802[0...n]	Modulator mode / Modulator mode		
	Access level: 4 Can be changed: T Unit group: - Min 0	Calculated: p0340 = 1,3,5 Scaling: - Unit selection: - Max 10	Data type: Integer16 Dyn. index: DDS, p0180 Func. diagram: - Factory setting 0
Description:	Sets the modulator mode.		
Value:	0: Automatic changeover SVM/FLB 2: Space vector modulation (SVM) 3: SVM without overcontrol 4: SVM/FLB without overcontrol 10: SVM/FLB with modulation depth reduction		
Dependency:	If a sine-wave filter is parameterized as output filter (p0230 = 3, 4), then only space vector modulation without overcontrol can be selected as modulation type (p1802 = 3). Refer to: p0230, p0500		
Note:	When modulation modes are enabled that could lead to overmodulation (p1802 = 0, 2, 10), the modulation depth must be limited using p1803 (default, p1803 < 100 %). 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.		
p1803[0...n]	Maximum modulation depth / Modulat depth max		
	Access level: 4 Can be changed: U, T Unit group: - Min 20.0 [%]	Calculated: p0340 = 1,3,5 Scaling: - Unit selection: - Max 150.0 [%]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: 6723 Factory setting 106.0 [%]
Description:	Defines the maximum modulation depth.		
Dependency:	Refer to: p0500		
Note:	p1803 = 100% is the overcontrol limit for space vector modulation (for an ideal drive converter without any switching delay).		
p1806[0...n]	Filter time constant Vdc correction / T_filt Vdc_corr		
	Access level: 3 Can be changed: U, T Unit group: - Min 0.0 [ms]	Calculated: p0340 = 1,3 Scaling: - Unit selection: - Max 10000.0 [ms]	Data type: FloatingPoint32 Dyn. index: DDS, p0180 Func. diagram: - Factory setting 0.0 [ms]
Description:	Sets the filter time constant for the DC link voltage. This time constant is used to calculate the modulation depth.		
p1820[0...n]	Reverse the output phase sequence / Outp_ph_seq rev		
	Access level: 2 Can be changed: C(2), T Unit group: - Min 0	Calculated: - Scaling: - Unit selection: - Max 1	Data type: Integer16 Dyn. index: DDS, p0180 Func. diagram: - Factory setting 0
Description:	Sets the phase sequence reversal for the motor without setpoint change. If the motor does not rotate in the required direction, then the output phase sequence can be reversed using this parameter. This means that the direction of the motor is reversed without the setpoint being changed.		
Value:	0: OFF 1: ON		
Note:	This setting can only be changed when the pulses are inhibited.		

SINAMICS G120C
List Manual (LH13), 04/2015, A5E33840768

With the following power-on command, a rotating motor data identification routine is carried out - and in addition, a speed controller optimization by making measurements at different motor speeds.

p1900 = 2:

Sets p1910 = 1 and p1960 = 0

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.

p1900 = 3:

Sets p1960 = 0, 1 depending on p1300

This setting should only be selected if the motor data identification was already carried out at standstill.

When the drive enable signals are present, with the next power-on command, a rotating motor data identification routine is carried out - and in addition, speed controller optimization by taking measurements at different motor speeds.

p1900 = 11, 12:

The same as p1900 = 1, 2 with the difference, that after the measurement, the system immediately goes into operation. For this purpose, p1909.18 is set = p1959.13 is set = 1 .

Value:

- 0: Inhibited
- 1: Identifying motor data and optimizing the speed controller
- 2: Identifying motor data (at standstill)
- 3: Optimizing the speed controller (in rotating operation)
- 11: Identify motor data and optimize speed controller, operation
- 12: Identifying motor data (at standstill), operation

Dependency: Refer to: p1300, p1910, p1960
Refer to: A07980, A07981, F07983, F07984, F07985, F07986, F07988, F07990, A07991

Notice: p1900 = 3:
This setting should only be selected if the motor data identification was already carried out at standstill.
If there is a motor holding brake, it must be open (p1215 = 2).
To permanently accept the determined settings they must be saved in a non-volatile fashion (p0971).
During the rotating measurement it is not possible to save the parameter (p0971).
For p0014 = 1, the following applies:

After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.

Note: The motor and control parameters of the vector control are only optimally set when both measurements are carried out (initially at standstill, and then with the motor rotating). The measurement with rotating motor is not performed for p1300 < 20 (U/f controls).

An appropriate alarm is output when the parameter is set.

The power-on command must remain set during a measurement and after the measurement has been completed, the drive automatically resets it.

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.

p1900 is automatically set to 0 after the motor data identification routine has been completed.

If a reluctance motor has been parameterized, a pole position identification is carried out during the stationary measurement. As a consequence, faults that occur can also be assigned to the pole position identification.

p1901 Test pulse evaluation configuration / Test puls config

Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	0000 bin

Description: Sets the configuration for the test pulse evaluation.

Bit 00: Check for conductor-to-conductor short circuit once/always when the pulses are enabled.

Bit 01: Check for ground fault once/always when the pulses are enabled.

Bit 02: Activation of the tests selected using bit 00 and/or bit 01 each time the pulses are enabled

Recommendation: If the ground fault test is incorrectly initiated because the motor is not at a standstill, then the pulse cancellation delay time (p1228) should be increased.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Phase short-circuit test pulse active	Yes	No	-
	01	Ground fault detection test pulse active	Yes	No	-
	02	Test pulse at each pulse enable	Yes	No	-
Dependency:	The ground fault test is only possible when the motor is stationary, and is therefore only realized when flying restart is deactivated (p1200 = 0). Refer to: p0287				
Note:	If a conductor-to-conductor short-circuit is detected during the test, this is displayed in r1902.1. If a ground fault is detected during the test, this is displayed in r1902.2. Re bit 02 = 0: If the test was successful once after POWER ON (see r1902.0), it is not repeated. Re bit 02 = 1: The test is not only performed after POWER ON, but also each time the pulses are enabled.				

p1909[0...n]	Motor data identification control word / MotID STW				
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32		
	Can be changed: T	Scaling: -	Dyn. index: MDS		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 0000 0000 0000 0000 0000 0000 0000 0000 bin		

Description: Sets the configuration for the motor data identification.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Stator inductance estimate no measurement	Yes	No	-
	02	Rotor time constant estimate no measurement	Yes	No	-
	03	Leakage inductance estimate no measurement	Yes	No	-
	05	Determine Tr and Lsig evaluation in the time range	Yes	No	-
	06	Activate vibration damping	Yes	No	-
	07	De-activate vibration detection	Yes	No	-
	11	De-activate pulse measurement Lq Ld	Yes	No	-
	12	De-activate rotor resistance Rr measurement	Yes	No	-
	14	De-activate valve interlocking time measurement	Yes	No	-
	15	Determine only stator resistance, valve voltage fault, dead time	Yes	No	-
	16	Short motor identification (lower quality)	Yes	No	-
	17	Measurement without control parameter calculation	Yes	No	-
	18	After motID direct transition into operation	Yes	No	-
	19	After MotID automatically save results	Yes	No	-
	20	Estimate cable resistance	Yes	No	-

Note: The following applies to permanent-magnet synchronous motors:
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.
When de-selecting with bit 11 or in the U/f mode, the stator inductance is measured at half the rated motor current.
If the stator inductance is not measured but is to be estimated, then bit 0 should be set and bit 11 should be de-selected.
Bit 19 = 1:
All parameters are automatically saved after a successful motor data identification.
If a speed controller optimization run is then selected, the parameters are only saved after this measurement has been completed.

Bit 22 = 1:
Only that measurement is carried out that is required for the flying restart of a reluctance motor. The bit is reset after a successful measurement

p1910	Motor data identification selection / MotID selection		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	28	0
Description:	<p>Sets the motor data identification routine.</p> <p>The motor data identification routine is carried out after the next power-on command.</p> <p>p1910 = 1:</p> <p>All motor data and the drive converter characteristics are identified and then transferred to the following parameters: p0350, p0354, p0356, p0357, p0358, p0360.</p> <p>After this, the control parameter p0340 = 3 is automatically calculated.</p> <p>p1910 = 20:</p> <p>Only for internal SIEMENS use.</p>		
Value:	<p>0: Inhibited</p> <p>1: Complete identification (ID) and acceptance of motor data</p> <p>2: Complete identification (ID) of motor data without acceptance</p> <p>20: Voltage vector input</p> <p>21: Voltage vector input without filter</p> <p>22: Rectangular voltage vector input without filter</p> <p>23: Triangular voltage vector input without filter</p> <p>24: Rectangular voltage vector input with filter</p> <p>25: Triangular voltage vector input with filter</p> <p>26: Enter voltage vector with DTC correction</p> <p>27: Enter voltage vector with AVC</p> <p>28: Enter voltage vector with DTC + AVC correction</p>		
Dependency:	<p>"Quick commissioning" must be carried out (p0010 = 1, p3900 > 0) before executing the motor data identification routine!</p> <p>When selecting the motor data identification routine, the drive data set changeover is suppressed.</p> <p>Refer to: p1900</p> <p>Refer to: F07990, A07991</p>		
Notice:	<p>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:</p> <ul style="list-style-type: none"> - 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. 		
Note:	<p>If there is a motor holding brake, it must be open (p1215 = 2).</p> <p>To permanently accept the determined settings they must be saved in a non-volatile fashion (p0971).</p> <p>When setting p1910, the following should be observed:</p> <ol style="list-style-type: none"> 1. "With acceptance" means: The parameters specified in the description are overwritten with the identified values and therefore have an influence on the controller setting. 2. "Without acceptance" means: The identified parameters are only displayed in the range r1912 ... r1926 (service parameters). The controller settings remain unchanged. 3. For settings 27 and 28, the AVC configuration set using p1840 is active. <p>The power-on command must remain set during a measurement and after the measurement has been completed, the drive automatically resets it. The duration of the measurements can lie between 0.3 s and several minutes. This time is mainly influenced by the motor size. At the end of the motor data identification, p1910 is automatically set to 0, if only the stationary measurement is selected, then p1900 is also reset to 0, otherwise, the rotating measurement is activated.</p>		

p1959[0...n]	Rotating measurement configuration / Rot meas config				
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned16		
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 0000 0001 1110 bin		
Description:	Sets the configuration of the rotating measurement.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Saturation characteristic identification	Yes	No	-
	02	Moment of inertia identification	Yes	No	-
	03	Re-calculates the speed controller parameters	Yes	No	-
	04	Speed controller optimization (vibration test)	Yes	No	-
	11	Do not change the controller parameters during the measurement	Yes	No	-
	12	Measurement shortened	Yes	No	-
	13	After measurement direct transition into operation	Yes	No	-
Dependency:	Refer to: F07988				
Note:	The following parameters are influenced for the individual optimization steps:				
	Bit 01: p0320, p0360, p0362 ... p0369				
	Bit 02: p0341, p0342				
	Bit 03: p1470, p1472, p1496				
	Bit 04: Dependent on p1960				
	p1960 = 1, 3: p1400, p1470, p1472, p1496				
	Re bit 12 = 1:				
	The selection only has an effect on the measurement p1960 = 1, 2. For the shortened measurement, the magnetizing current and moment of inertia are determined with a somewhat lower accuracy, the oscillation test is completely eliminated.				
	Re bit 13 = 1:				
	After the measurement has been completed, the system immediately goes into closed-loop speed controlled operation.				

p1960	Rotating measurement selection / Rot meas sel		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	3	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 open-loop control):		
	It is not possible to select rotating measurement or speed controller optimization.		
	p1300 = 20, 22 (encoderless operation):		
	Only rotating measurement or speed controller optimization can be selected in the encoderless mode.		
Value:	0: Inhibited		
	1: Rotating measurement in encoderless operation		
	3: Speed controller optimization in encoderless operation		
Dependency:	Before the rotating measurement is carried out, the motor data identification routine (p1900, p1910, r3925) should have already been done.		
	When selecting the rotating measurement, the drive data set changeover is suppressed.		
	Refer to: p1300, p1900, p1959, p1967, r1968		

Danger:



For drives with a mechanical system that limits the distance moved, it must be ensured that this is not reached during the rotating measurement. If this is not the case, then it is not permissible that the measurement is carried out.

Notice:

If there is a motor holding brake, it must be open (p1215 = 2).

To permanently accept the determined settings they must be saved in a non-volatile fashion (p0971).

During the rotating measurement it is not possible to save the parameter (p0971).

Note:

When the rotating measurement is activated, it is not possible to save the parameters (p0971).

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 900 s.

p1961

Saturation characteristic speed to determine / Sat_char n determ

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
26 [%]	75 [%]	40 [%]

Description:

Sets the speed to determine the saturation characteristic.

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.

p1965

Speed_ctrl_opt speed / n_opt speed

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
10 [%]	75 [%]	40 [%]

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 20 % for the upper speed value.

The q leakage inductance (refer to p1959.5) is determined at zero speed and at 50 % of p1965 - however, with a maximum output frequency of 15 Hz and at a minimum of 10% of the rated motor speed.

p1967

Speed_ctrl_opt dynamic factor / n_opt dyn_factor

Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
1 [%]	400 [%]	100 [%]

Description:

Sets the dynamic response factor for speed controller optimization.

After optimization, the dynamic response achieved is displayed in r1968.

Dependency:

Refer to: p1959, r1968

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).

If the actual dynamic response (see r1968) is significantly reduced with respect to the required dynamic response (p1967), then this can be as a result of mechanical load oscillations. If, in spite of this load behavior, a higher dynamic response is required, then the oscillation test (p1959.4 = 0) should be deactivated and the measurement repeated.

r1968	Speed_ctrl_opt dynamic factor actual / n_opt dyn_fact act		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	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 dynamic factor only refers to the control mode of the speed controller set in p1960.		
p1980[0...n]	PoIID technique / PoIID technique		
	Access level: 3	Calculated: p0340 = 1,3	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: MDS
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	10	4
Description:	Sets the pole position identification technique. p1980 = 1, 8: The current magnitude is set using p0329. p1980 = 4, 6: The current magnitude of the first measurement section is set using p0325, the second using p0329. p1980 = 10: The rated motor current is impressed to align. The current magnitudes are limited to the rated power unit values.		
Value:	1: Voltage pulsing 1st harmonics 4: Voltage pulsing 2-stage 6: Voltage pulsing 2-stage inverse 8: Voltage pulsing 2nd harmonic, inverse 10: DC current injection		
Dependency:	When commissioning a catalog motor, the technique is automatically selected depending on the motor type being used. Refer to: p0325, p0329, p1780 Refer to: F07969		
Note:	Voltage pulse technique (p1980 = 1, 4) cannot be applied to operation with sine-wave output filters (p0230).		
p2000	Reference speed reference frequency / n_ref f_ref		
	Access level: 2	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	6.00 [rpm]	210000.00 [rpm]	1500.00 [rpm]
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 corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word). The following applies: Reference frequency (in Hz) = reference speed (in ((rpm) / 60) x pole pair number)		
Dependency:	This parameter is only updated during the automatic calculation (p0340 = 1, p3900 > 0) if motor commissioning was carried out beforehand for drive data set zero. This means that the parameter is not locked against overwriting using p0573 = 1. Refer to: p2001, p2002, p2003, r2004, r3996		
Notice:	When the reference speed / reference frequency is changed, short-term communication interruptions may occur.		
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. r0755[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 actual input value is cyclically converted into a percentage value via the pre-specified scaling 4000 hex. This percentage value is converted to the absolute speed setpoint via reference speed (p2000).

p2001	Reference voltage / Reference voltage		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	10 [Vrms]	100000 [Vrms]	1000 [Vrms]
Description:	<p>Sets the reference quantity for voltages.</p> <p>All voltages specified as relative value are referred to this reference quantity. This also applies for direct voltage values (= rms value) like the DC-link voltage.</p> <p>The reference quantity corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word).</p> <p>Note:</p> <p>This reference quantity also applies to direct voltage values. It is not interpreted as rms value, but as DC voltage value.</p>		
Dependency:	<p>p2001 is only updated during automatic calculation (p0340 = 1, p3900 > 0) if motor commissioning has been carried out first for drive data set zero and as a result overwriting of the parameter has not been blocked by setting p0573 = 1.</p> <p>Refer to: r3996</p>		
Notice:	When the reference voltage is changed, short-term communication interruptions may occur.		
Note:	<p>If a BICO interconnection is established between different physical quantities, then the particular reference quantities are used as internal conversion factor.</p> <p>For infeed units, the parameterized device supply voltage (p0210) is pre-assigned as the reference quantity.</p> <p>Example:</p> <p>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.</p>		
p2002	Reference current / I_ref		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.10 [Arms]	100000.00 [Arms]	100.00 [Arms]
Description:	<p>Sets the reference quantity for currents.</p> <p>All currents specified as relative value are referred to this reference quantity.</p> <p>The reference quantity corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word).</p>		
Dependency:	<p>This parameter is only updated during the automatic calculation (p0340 = 1, p3900 > 0) if motor commissioning was carried out beforehand for drive data set zero. This means that the parameter is not locked against overwriting using p0573 = 1.</p> <p>Refer to: r3996</p>		
Notice:	<p>If various DDS are used with different motor data, then the reference quantities remain the same as these are not changed over with the DDS. The resulting conversion factor must be taken into account.</p> <p>Example:</p> <p>p2002 = 100 A</p> <p>Reference quantity 100 A corresponds to 100 %</p> <p>p0305[0] = 100 A</p> <p>Rated motor current 100 A for MDS0 in DDS0 --> 100 % corresponds to 100 % of the rated motor current</p>		

p0305[1] = 50 A

Rated motor current 50 A for MDS1 in DDS1 --> 100 % corresponds to 200 % of the rated motor current

When the reference current is changed, short-term communication interruptions may occur.

Note:

Preassigned value is p0640.

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, which 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 / M_ref**

Access level: 3

Calculated: p0340 = 1

Data type: FloatingPoint32

Can be changed: T

Scaling: -

Dyn. index: -

Unit group: 7_2

Unit selection: p0505

Func. diagram: -

Min

Max

Factory setting

0.01 [Nm]

20000000.00 [Nm]

1.00 [Nm]

Description:

Sets the reference quantity for torque.

All torques specified as relative value are referred to this reference quantity.

The reference quantity corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word).

Dependency:

This parameter is only updated during the automatic calculation ($p0340 = 1$, $p3900 > 0$) if motor commissioning was carried out beforehand for drive data set zero. This means that the parameter is not locked against overwriting using $p0573 = 1$.

Refer to: r3996

Notice:

When the reference torque is changed, short-term communication interruptions may occur.

Note:

Preassigned value is $2 * p0333$.

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 (r0079) 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.

r2004**Reference power / P_ref**

Access level: 3

Calculated: -

Data type: FloatingPoint32

Can be changed: -

Scaling: -

Dyn. index: -

Unit group: 14_10

Unit selection: p0505

Func. diagram: -

Min

Max

Factory setting

- [kW]

- [kW]

- [kW]

Description:

Displays the reference quantity for power.

All power ratings specified as relative value are referred to this reference quantity.

The reference quantity corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word).

Dependency:

This value is calculated as follows:

Infeed: Calculated from voltage times current.

Closed-loop control: Calculated from torque times speed.

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:

- $2 * \pi * \text{reference speed} / 60 * \text{reference torque (motor)}$

- $\text{reference voltage} * \text{reference current} * \text{root}(3)$ (infeed)

p2006	Reference temp / Ref temp		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 50.00 [°C]	Max 300.00 [°C]	Factory setting 100.00 [°C]
Description:	Sets the reference quantity for temperature. All temperatures specified as relative value are referred to this reference quantity. The reference quantity corresponds to 100% or 4000 hex (word) or 4000 0000 hex (double word).		
p2010	Comm IF baud rate / Comm baud		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 6	Max 12	Factory setting 12
Description:	Sets the baud rate for the commissioning interface (USS, RS232).		
Value:	6: 9600 baud 7: 19200 baud 8: 38400 baud 9: 57600 baud 10: 76800 baud 11: 93750 baud 12: 115200 baud		
Note:	COMM-IF: Commissioning interface The parameter is not influenced by setting the factory setting.		
p2011	Comm IF address / Comm add		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min 0	Max 31	Factory setting 2
Description:	Sets the address for the commissioning interface (USS, RS232).		
Note:	The parameter is not influenced by setting the factory setting.		
p2016[0...3]	CI: Comm IF USS PZD send word / Comm USS send word		
	Access level: 3	Calculated: -	Data type: U32 / Integer16
	Can be changed: U, T	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min -	Max -	Factory setting 0
Description:	Selects the PZD (actual values) to be sent via the commissioning interface USS. The actual values are displayed on an intelligent operator panel (IOP).		
Index:	[0] = PZD 1 [1] = PZD 2 [2] = PZD 3 [3] = PZD 4		

p2020	Field bus interface baud rate / Field bus baud		
G120C_USS	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	4	13	8
Description:	Sets the baud rate for the field bus interface (RS485).		
Value:	4: 2400 baud 5: 4800 baud 6: 9600 baud 7: 19200 baud 8: 38400 baud 9: 57600 baud 10: 76800 baud 11: 93750 baud 12: 115200 baud 13: 187500 baud		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. For p0014 = 0, the following applies: Before a changed setting becomes permanently effective, a non-volatile RAM to ROM data save is required. To do this, set p0971 = 1 or p0014 = 1.		
Note:	Fieldbus IF: Fieldbus interface Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting. The parameter is set to the factory setting when the protocol is reselected. When p2030 = 1 (USS), the following applies: Min./max./factory setting: 4/13/8 When p2030 = 2 (MODBUS), the following applies: Min./max./factory setting: 5/13/7		

p2021	Field bus interface address / Field bus address		
G120C_USS	Access level: 2	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	0	247	0
Description:	Displays or sets the address for the fieldbus interface (RS485). The address can be set as follows: 1) Using the address switch on the Control Unit. --> p2021 displays the address setting. --> A change only becomes effective after a POWER ON. 2) Using p2021 --> Only if an address of 0 or an address that is invalid for the fieldbus selected in p2030 has been set using the address switch. --> 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.		
Dependency:	Refer to: p2030		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. For p0014 = 0, the following applies: Before a changed setting becomes permanently effective, a non-volatile RAM to ROM data save is required. To do this, set p0971 = 1 or p0014 = 1.		

2 Parameters

2.2 List of parameters

Note: Changes only become effective after POWER ON.
The parameter is not influenced by setting the factory setting.
The parameter is set to the factory setting when the protocol is reselected.
When p2030 = 1 (USS), the following applies:
Min./max./factory setting: 0/30/0
When p2030 = 2 (MODBUS), the following applies:
Min./max./factory setting: 1/247/1

p2022		Field bus int USS PZD no. / Field bus USS PZD	
G120C_USS	Access level: 2	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min 0	Max 8	Factory setting 2
Description:	Sets the number of 16-bit words in the PZD part of the USS telegram for the field bus interface.		
Dependency:	Refer to: p2030		
Note:	The parameter is not influenced by setting the factory setting.		

p2023		Field bus int USS PKW no. / Field bus USS PKW	
G120C_USS	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min 0	Max 127	Factory setting 127
Description:	Sets the number of 16-bit words in the PKW part of the USS telegram for the field bus interface.		
Value:	0: PKW 0 words 3: PKW 3 words 4: PKW 4 words 127: PKW variable		
Dependency:	Refer to: p2030		
Note:	The parameter is not influenced by setting the factory setting.		

p2024[0...2]		Fieldbus interface times / Fieldbus times	
G120C_USS	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min 0 [ms]	Max 10000 [ms]	Factory setting [0] 1000 [ms] [1] 0 [ms] [2] 0 [ms]
Description:	Sets the time values for the fieldbus interface. The following applies for MODBUS: p2024[0]: Maximum permissible telegram processing time of the MODBUS slave in which a reply is sent back to the MODBUS master. p2024[1]: Not relevant. p2024[2]: Telegram pause time (pause time between two telegrams).		
Index:	[0] = Max. processing time [1] = Character delay time [2] = Telegram pause time		
Dependency:	Refer to: p2020, p2030		
Note:	Re p2024[2] (MODBUS): If the field bus baud rate is changed (p2020), the default time setting is restored. The default setting corresponds to a time of 3.5 characters (dependent on the baud rate that has been set).		

r2029[0...7]	Field bus int error statistics / Field bus error		
G120C_USS	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	-	-	-
Description:	Displays the receive errors on the field bus interface (RS485).		
Index:	[0] = Number of error-free telegrams [1] = Number of rejected telegrams [2] = Number of framing errors [3] = Number of overrun errors [4] = Number of parity errors [5] = Number of starting character errors [6] = Number of checksum errors [7] = Number of length errors		
p2030	Field bus int protocol selection / Field bus protocol		
G120C_CAN	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	0	4	4
Description:	Sets the communication protocol for the field bus interface.		
Value:	0: No protocol 4: CAN		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting.		
p2030	Field bus int protocol selection / Field bus protocol		
G120C_DP	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	0	3	3
Description:	Sets the communication protocol for the field bus interface.		
Value:	0: No protocol 3: PROFIBUS		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting.		

p2030	Field bus int protocol selection / Field bus protocol		
G120C_PN	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	0	10	7
Description:	Sets the communication protocol for the field bus interface.		
Value:	0: No protocol 7: PROFINET 10: Ethernet/IP		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting.		
p2030	Field bus int protocol selection / Field bus protocol		
G120C_USS	Access level: 1	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	0	2	0
Description:	Sets the communication protocol for the field bus interface.		
Value:	0: No protocol 1: USS 2: MODBUS		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting.		
p2031	Fieldbus interface MODBUS parity / Modbus parity		
G120C_USS	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9310
	Min	Max	Factory setting
	0	2	2
Description:	Sets the parity for the MODBUS protocol (p2030 = 2).		
Value:	0: No parity 1: Odd parity 2: Even parity		
Note:	Fieldbus IF: Fieldbus interface Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting. The parameter is set to the factory setting when the protocol is reselected (p2030 = 2).		

r2032	Master control control word effective / PcCtrl STW eff				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the effective control word 1 (STW1) of the drive for the master 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	Operation enable	Yes	No	-
	04	Ramp-function generator enable	Yes	No	-
	05	Start ramp-function generator	Yes	No	-
	06	Speed setpoint enable	Yes	No	-
	07	Acknowledge fault	Yes	No	-
	08	Jog bit 0	Yes	No	3030
	09	Jog bit 1	Yes	No	3030
	10	Master control 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:	OC: Operating condition				

p2037	PROFIdrive STW1.10 = 0 mode / PD STW1.10=0				
G120C_DP	Access level: 3	Calculated: -	Data type: Integer16		
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0	2	0		
Description:	Sets the processing mode for PROFIdrive STW1.10 "master control by PLC". Generally, control word 1 is received with the first 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.				
Value:	0: Freeze setpoints and continue to process sign-of-life 1: Freeze setpoints and sign-of-life 2: Do not freeze setpoints				
Recommendation:	Do not change the setting p2037 = 0.				
Note:	If the STW1 is not transferred according to the PROFIdrive with PZD1 (with bit 10 "master control by PLC"), then p2037 should be set to 2.				

p2038	PROFIdrive STW/ZSW interface mode / PD STW/ZSW IF mode				
G120C_DP	Access level: 3	Calculated: -	Data type: Integer16		
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0	2	0		
Description:	Sets the interface mode of the PROFIdrive control words and status words. When selecting a telegram via p0922 (p2079), this parameter influences the device-specific assignment of the bits in the control and status words.				
Value:	0: SINAMICS 2: VIK-NAMUR				
Dependency:	Refer to: p0922, p2079				
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.				
Note:	- For p0922 (p2079) = 1, 350 ... 999, p2038 is automatically set to 0. - For p0922 (p2079) = 20, p2038 is automatically set to 2. It is not then possible to change p2038.				

p2039	Select debug monitor interface / Debug monit select				
	Access level: 4	Calculated: -	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0	3	0		
Description:	The serial interface for the debug monitor is COM1 (commissioning interface, RS232) or COM2 (fieldbus interface, RS485). Value = 0: De-activated Value = 1: COM1, commissioning protocol is de-activated Value = 2: COM2, field bus is de-activated Value = 3: Reserved				
Note:	Value = 2 is only possible for Control Units with RS485 as a field bus interface.				
p2040	Fieldbus interface monitoring time / Fieldbus t_monit				
G120C_CAN	Access level: 3	Calculated: -	Data type: FloatingPoint32		
G120C_USS	Can be changed: U, T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 9310		
	Min	Max	Factory setting		
	0 [ms]	1999999 [ms]	100 [ms]		
Description:	Sets the monitoring time to monitor the process data received via the fieldbus interface. If no process data is received within this time, then an appropriate message is output.				
Dependency:	Refer to: F01910				
Note:	p2040 = 0: Monitoring is de-activated.				
p2042	PROFIBUS Ident Number / PB Ident No.				
G120C_DP	Access level: 3	Calculated: -	Data type: Integer16		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0	1	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).				
Value:	0: SINAMICS 1: VIK-NAMUR				
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.				
Note:	Every change only becomes effective after a POWER ON.				
r2043.0...2	BO: PROFIdrive PZD state / PD PZD state				
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned8		
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2410		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the PROFIdrive PZD state.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Setpoint failure	Yes	No	-
	02	Fieldbus oper	Yes	No	-
Dependency:	Refer to: p2044				

Note: When using the "setpoint failure" signal, the bus can be monitored and an application-specific response triggered when the setpoint fails.

p2044	PROFIdrive fault delay / PD fault delay		
G120C_DP	Access level: 3	Calculated: -	Data type: FloatingPoint32
G120C_PN	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2410
	Min	Max	Factory setting
	0 [s]	100 [s]	0 [s]
Description:	Sets the delay time to initiate fault F01910 after a 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		
p2047	PROFIBUS additional monitoring time / PB suppl t_monit		
G120C_DP	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2410
	Min	Max	Factory setting
	0 [ms]	20000 [ms]	0 [ms]
Description:	Sets the additional monitoring time to monitor the process data received via PROFIBUS. Enables short bus faults to be compensated. If no process data is received within this time, then an appropriate message is output.		
Dependency:	Refer to: F01910		
Note:	For controller STOP, the additional monitoring time is not effective.		
r2050[0...11]	CO: PROFIBUS PZD receive word / PZD rcv word		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2440, 2468, 9360
	Min	Max	Factory setting
	-	-	-
Description:	Connector output to interconnect PZD (setpoints) with word format received from the fieldbus controller.		
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		
Notice:	Where there is a multiple interconnection of a connector output, all the connector inputs must either have Integer or FloatingPoint data types. A BICO interconnection for a single PZD can only take place either on r2050 or r2060.		

p2051[0...16]	CI: PROFIdrive PZD send word / PZD send word		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Integer16
G120C_USS	Can be changed: U, T	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2450, 2470, 9370
	Min	Max	Factory setting
	-	-	0
Description:	Selects the PZD (actual values) with word format to be sent to the fieldbus controller.		
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		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
p2051[0...16]	CI: PROFIdrive PZD send word / PZD send word		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Integer16
G120C_PN	Can be changed: U, T	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2450, 2470, 9370
	Min	Max	Factory setting
	-	-	[0] 2089[0] [1] 63[0] [2...16] 0
Description:	Selects the PZD (actual values) with word format to be sent to the fieldbus controller.		
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		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		

r2053[0...16]		PROFIdrive diagnostics send PZD word / Diag send word				
Access level: 3		Calculated: -		Data type: Unsigned16		
Can be changed: -		Scaling: -		Dyn. index: -		
Unit group: -		Unit selection: -		Func. diagram: 2450, 2470, 9370		
Min		Max		Factory setting		
-		-		-		
Description:		Displays the PZD (actual values) with word format sent to the fieldbus controller.				
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				
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	-

r2054 PROFIBUS status / PB status				
G120C_DP	Access level: 3		Calculated: -	Data type: Integer16
	Can be changed: -		Scaling: -	Dyn. index: -
	Unit group: -		Unit selection: -	Func. diagram: 2410
	Min	Max	Factory setting	
	0	4	-	
Description:	Status display for the PROFIBUS interface.			
Value:	0: OFF			
	1: No connection (search for baud rate)			
	2: Connection OK (baud rate found)			
	3: Cyclic connection with master (data exchange)			
	4: Cyclic data OK			

r2055[0...2]	PROFIBUS diagnostics standard / PB diag standard		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2410
	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		
r2057	PROFIBUS address switch diagnostics / PB addr_sw diag		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2410
	Min	Max	Factory setting
	-	-	-
Description:	Displays the setting of the PROFIBUS address switch "DP ADDRESS" on the Control Unit.		
Dependency:	Refer to: p0918		
Notice:	The display is updated after switching on, and not cyclically.		
r2060[0...10]	CO: PROFIdrive PZD receive double word / PZD recv DW		
	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: -	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2440, 2468
	Min	Max	Factory setting
	-	-	-
Description:	Connector output to interconnect PZD (setpoints) with double word format received from the fieldbus controller.		
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		
Dependency:	Refer to: r2050		
Notice:	Where there is a multiple interconnection of a connector output, all the connector inputs must either have Integer or FloatingPoint data types. A BICO interconnection for a single PZD can only take place either on r2050 or r2060.		
p2061[0...15]	CI: PROFIBUS PZD send double word / PZD send DW		
	Access level: 3	Calculated: -	Data type: U32 / Integer32
	Can be changed: U, T	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2470
	Min	Max	Factory setting
	-	-	0
Description:	Selects the PZD (actual values) with double word format to be sent to the fieldbus controller.		
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

Dependency:

Refer to: p2051

Notice:

A BICO interconnection for a single PZD can only take place either on p2051 or p2061.

The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

r2063[0...15]**PROFIdrive diagnostics PZD send double word / Diag send DW**

Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2470
Min	Max	Factory setting
-	-	-

Description:

Displays the PZD (actual values) with double word format sent to the fieldbus controller.

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

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	-

2 Parameters

2.2 List of parameters

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	-

Notice: A maximum of 4 indices of the "trace" function can be used.

r2067[0...1] PZD maximum interconnected / PZDmaxIntercon

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description: Display for the maximum interconnected PZD in the receive/send direction
Index 0: receive (r2050, r2060)
Index 1: send (p2051, p2061)

p2072 Response receive value after PZD failure / Resp aft PZD fail

Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	0000 bin

Description: Sets the response for the receive value (r2090) after PZD failure.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Unconditionally open holding brake (p0855)	Freeze value	Zero the value	-

r2074[0...11] PROFIdrive diagnostics bus address PZD receive / Diag addr rcv

G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the PROFIBUS address of the sender from which the process data (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

Note: Value range:
0 - 125: Bus address of the sender
65535: Not assigned

r2075[0...11]		PROFIdrive diagnostics telegram offset PZD receive / Diag offs recv		
G120C_DP	Access level:	3	Calculated:	-
	Can be changed:	-	Scaling:	-
	Unit group:	-	Unit selection:	-
	Min		Max	
		-	-	-
Description:	Displays the PZD byte offset in the PROFIdrive receive telegram (controller 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			
Note:	Value range: 0 - 242: Byte offset 65535: Not assigned			

r2076[0...16]		PROFIdrive diagnostics telegram offset PZD send / Diag offs send		
G120C_DP	Access level:	3	Calculated:	-
	Can be changed:	-	Scaling:	-
	Unit group:	-	Unit selection:	-
	Min		Max	
		-	-	-
Description:	Displays the PZD byte offset in the PROFIdrive send telegram (controller 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			
Note:	Value range: 0 - 242: Byte offset 65535: Not assigned			

r2077[0...15]	PROFIBUS diagnostics peer-to-peer data transfer addresses / PB diag peer addr		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned8
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the addresses of the slaves (peers) where peer-to-peer data transfer has been configured via PROFIBUS.		
p2079	PROFIdrive PZD telegram selection extended / PZD telegr ext		
G120C_DP	Access level: 3	Calculated: -	Data type: Integer16
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	999	1
Description:	Sets the send and receive telegram. Contrary to p0922, a telegram can be selected using p2079 and subsequently expanded.		
Value:	1: Standard telegram 1, PZD-2/2 20: Standard telegram 20, PZD-2/6 352: SIEMENS telegram 352, PZD-6/6 353: SIEMENS telegram 353, PZD-2/2, PKW-4/4 354: SIEMENS telegram 354, PZD-6/6, PKW-4/4 999: Free telegram configuration with BICO		
Dependency:	Refer to: p0922		
Note:	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.		
p2080[0...15]	BI: Binector-connector converter status word 1 / Bin/con ZSW1		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2472
	Min	Max	Factory setting
	-	-	0
Description:	Selects bits to be sent to the PROFIdrive controller. 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		

Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p2080[0...15]		BI: Binector-connector converter status word 1 / Bin/con ZSW1		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary	
G120C_PN	Can be changed: U, T	Scaling: -	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: 2472	
	Min	Max	Factory setting	
	-	-	[0] 899.0	
			[1] 899.1	
			[2] 899.2	
			[3] 2139.3	
			[4] 899.4	
			[5] 899.5	
			[6] 899.6	
			[7] 2139.7	
			[8] 2197.7	
			[9] 899.9	
			[10] 2199.1	
			[11] 1407.7	
			[12] 899.12	
			[13] 2135.14	
			[14] 2197.3	
			[15] 2135.15	

Description: Selects bits to be sent to the PROFIdrive controller.
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

Notice: The parameter may be protected as a result of p0922 or p2079 and cannot be changed.

p2088[0...4]		Invert binector-connector converter status word / Bin/con ZSW inv		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16	
G120C_USS	Can be changed: U, T	Scaling: -	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: 2472	
	Min	Max	Factory setting	
	-	-	0000 0000 0000 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
[4] = Free status word 5

2 Parameters

2.2 List of parameters

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, r2089

p2088[0...4] Invert binector-connector converter status word / Bin/con ZSW inv

G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2472
	Min	Max	Factory setting
	-	-	[0] 1010 1000 0000 0000 bin [1...4] 0000 0000 0000 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
[4] = Free status word 5

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, r2089

r2089[0...4] CO: Send binector-connector converter status word / Bin/con ZSW send

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2472
Min	Max	Factory setting
-	-	-

Description: Connector output to interconnect the status words to a PZD send word.

Index:
[0] = Status word 1
[1] = Status word 2

[2] = Free status word 3

[3] = Free status word 4

[4] = Free status word 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	-

Dependency: Refer to: p2051, p2080

r2090.0...15 BO: PROFIdrive PZD1 receive bit-serial / PZD1 recv bitw

Access level: 3

Calculated: -

Data type: Unsigned16

Can be changed: -

Scaling: -

Dyn. index: -

Unit group: -

Unit selection: -

Func. diagram: 2468, 9204, 9206, 9360

Min

Max

Factory setting

-

-

-

Description:

Binector output for bit-serial interconnection of PZD1 (normally control word 1) received from the PROFIdrive controller.

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	-

r2091.0...15 BO: PROFIdrive PZD2 receive bit-serial / PZD2 recv bitw

G120C_CAN

Access level: 3

Calculated: -

Data type: Unsigned16

Can be changed: -

Scaling: -

Dyn. index: -

Unit group: -

Unit selection: -

Func. diagram: 2468, 9204, 9206

Min

Max

Factory setting

-

-

-

Description:

Binector output for bit-serial interconnection of PZD2 received from the PROFIdrive controller.

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	-

2 Parameters

2.2 List of parameters

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	-

r2091.0...15

BO: PROFIdrive PZD2 receive bit-serial / PZD2 recv bitw

G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
G120C_USS	Unit group: -	Unit selection: -	Func. diagram: 2468
	Min	Max	Factory setting
	-	-	-

Description:

Binector output for bit-serial interconnection of PZD2 received from the PROFIdrive controller.

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	-

r2092.0...15

BO: PROFIdrive PZD3 receive bit-serial / PZD3 recv bitw

G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2468, 9204, 9206
	Min	Max	Factory setting
	-	-	-

Description:

Binector output for bit-serial interconnection of PZD3 received from the PROFIdrive controller.

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	-

r2092.0...15 BO: PROFIdrive PZD3 receive bit-serial / PZD3 recv bitw

G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
G120C_USS	Unit group: -	Unit selection: -	Func. diagram: 2468
	Min	Max	Factory setting
	-	-	-

Description: Binector output for bit-serial interconnection of PZD3 received from the PROFIdrive controller.

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	-

r2093.0...15 BO: PROFIdrive PZD4 receive bit-serial / PZD4 recv bitw

G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2468, 9204, 9206
	Min	Max	Factory setting
	-	-	-

Description: Binector output for bit-serial interconnection of PZD4 (normally control word 2) received from the PROFIdrive controller.

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	-

r2093.0...15**BO: PROFIdrive PZD4 receive bit-serial / PZD4 recv bitw**

G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
G120C_USS	Unit group: -	Unit selection: -	Func. diagram: 2468
	Min	Max	Factory setting
	-	-	-

Description: Binector output for bit-serial interconnection of PZD4 (normally control word 2) received from the PROFIdrive controller.

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	-

r2094.0...15**BO: Connector-binector converter binector output / Con/bin outp**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2468, 9360
Min	Max	Factory setting
-	-	-

Description: Binector output for bit-serial onward interconnection of a PZD word received from the PROFIdrive controller. 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

r2095.0...15	BO: Connector-binector converter binector output / Con/bin outp		
Access level: 3	Calculated: -	Data type: Unsigned16	
Can be changed: -	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 2468, 9360	
Min	Max	Factory setting	
-	-	-	

Description: Binector output for bit-serial interconnection of a PZD word received from the PROFIdrive controller.
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]	Inverter connector-binector converter binector output / Con/bin outp inv		
Access level: 3	Calculated: -	Data type: Unsigned16	
Can be changed: U, T	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 2468, 9360	
Min	Max	Factory setting	
-	-	0000 0000 0000 0000 bin	

Description: Setting to invert the individual binector outputs of the connector-binector converter.
Using p2098[0], the signals of connector input p2099[0] are influenced.
Using p2098[1], the signals of connector input 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

p2099[0...1]	CI: Connector-binector converter signal source / Con/bin S_src		
	Access level: 3	Calculated: -	Data type: U32 / Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2468, 9360
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the connector-binector converter. A PZD receive word can be selected as signal source. The signals are available to be serially passed-on (interconnection).		
Dependency:	Refer to: r2094, r2095		
Note:	From the signal source set via the connector input, the corresponding lower 16 bits are converted. p2099[0...1] together with r2094.0...15 and r2095.0...15 forms two connector-binector converters: Connector input p2099[0] to binector output in r2094.0...15 Connector input p2099[1] to binector output in r2095.0...15		

p2100[0...19]	Change fault response fault number / Chng resp F_no		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8075
	Min	Max	Factory setting
	0	65535	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		
Note:	Re-parameterization is also possible if a fault is present. The change only becomes effective after the fault has been resolved.		

p2101[0...19]	Change fault response response / Chng resp resp		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8075
	Min	Max	Factory setting
	0	6	0
Description:	Sets the fault response for the selected fault.		
Value:	0: NONE 1: OFF1 2: OFF2 3: OFF3 5: STOP2 6: Internal armature short-circuit / DC braking		
Dependency:	The fault is selected and the required response is set under the same index.		
	Refer to: p2100		
Notice:	For the following cases, it is not possible to re-parameterize the fault response to a fault: - Fault number does not exist (exception value = 0). - Message type is not "fault" (F). - Fault response is not permissible for the set fault number.		
Note:	Re-parameterization is also possible if a fault is present. The change only becomes effective after the fault has been resolved. The fault response can only be changed for faults with the appropriate identification. Example: F12345 and fault response = NONE (OFF1, OFF2) --> The fault response NONE can be changed to OFF1 or OFF2. Re value = 1 (OFF1): Braking along the ramp-function generator down ramp followed by a pulse inhibit.		

Re value = 2 (OFF2):
Internal/external pulse inhibit.
Re value = 3 (OFF3):
Braking along the OFF3 down ramp followed by a pulse inhibit.
Re value = 5 (STOP2):
n_set = 0
Re value = 6 (armature short-circuit, internal/DC braking):
This value can only be set for all drive data sets when p1231 = 4.
a) DC braking is not possible for synchronous motors.
b) DC braking is possible for induction motors.

p2103[0...n]	BI: 1. Acknowledge faults / 1. Acknowledge		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2441, 2442, 2443, 2447, 2475, 2546, 9220, 9677, 9678
	Min	Max	Factory setting
	-	-	[0] 722.2
			[1] 0
Description:	Sets the first signal source to acknowledge faults.		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
Note:	A fault acknowledgement is triggered with a 0/1 signal.		
p2103[0...n]	BI: 1. Acknowledge faults / 1. Acknowledge		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2441, 2442, 2443, 2447, 2475, 2546, 9220, 9677, 9678
	Min	Max	Factory setting
	-	-	[0] 2090.7
			[1] 722.2
Description:	Sets the first signal source to acknowledge faults.		
Notice:	The parameter may be protected as a result of p0922 or p2079 and cannot be changed.		
Note:	A fault acknowledgement is triggered with a 0/1 signal.		
p2104[0...n]	BI: 2. Acknowledge faults / 2. Acknowledge		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_USS	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2546, 8060
	Min	Max	Factory setting
	-	-	0
Description:	Sets the second signal source to acknowledge faults.		
Note:	A fault acknowledgement is triggered with a 0/1 signal.		
p2104[0...n]	BI: 2. Acknowledge faults / 2. Acknowledge		
G120C_DP	Access level: 3	Calculated: -	Data type: U32 / Binary
G120C_PN	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2546, 8060
	Min	Max	Factory setting
	-	-	[0] 722.2
			[1] 0
Description:	Sets the second signal source to acknowledge faults.		
Note:	A fault acknowledgement is triggered with a 0/1 signal.		

p2106[0...n]	BI: External fault 1 / External fault 1		
	Access level: 3 Can be changed: U, T Unit group: - Min -	Calculated: - Scaling: - Unit selection: - Max -	Data type: U32 / Binary Dyn. index: CDS, p0170 Func. diagram: 2546 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.			
r2109[0...63]	Fault time removed in milliseconds / tflt resolved ms		
	Access level: 4 Can be changed: - Unit group: - Min - [ms]	Calculated: - Scaling: - Unit selection: - Max - [ms]	Data type: Unsigned32 Dyn. index: - Func. diagram: 8050, 8060 Factory setting - [ms]
Description: Displays the system runtime in milliseconds when the fault was removed. Dependency: Refer to: r0945, r0947, r0948, r0949, r2130, r2133, r2136 Notice: The time comprises r2136 (days) and r2109 (milliseconds). Note: The buffer parameters are cyclically updated in the background (refer to status signal in r2139). The structure of the fault buffer and the assignment of the indices is shown in r0945.			
r2110[0...63]	Alarm number / Alarm number		
	Access level: 2 Can be changed: - Unit group: - Min -	Calculated: - Scaling: - Unit selection: - Max -	Data type: Unsigned16 Dyn. index: - Func. diagram: 8065 Factory setting -
Description: This parameter is identical to r2122.			
p2111	Alarm counter / Alarm counter		
	Access level: 3 Can be changed: U, T Unit group: - Min 0	Calculated: - Scaling: - Unit selection: - Max 65535	Data type: Unsigned16 Dyn. index: - Func. diagram: 8050, 8065 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[0...n]	BI: External alarm 1 / External alarm 1		
	Access level: 3 Can be changed: U, T Unit group: - Min -	Calculated: - Scaling: - Unit selection: - Max -	Data type: U32 / Binary Dyn. index: CDS, p0170 Func. diagram: 2546 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.			

p2118[0...19]	Change message type message number / Chng type msg_no		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8075
	Min	Max	Factory setting
	0	65535	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		
Note:	Re-parameterization is also possible if a message is present. The change only becomes effective after the message has gone.		
p2119[0...19]	Change message type type / Change type type		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8075
	Min	Max	Factory setting
	1	3	1
Description:	Sets the message type for the selected fault or alarm.		
Value:	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		
Note:	Re-parameterization is also possible if a message is present. The change only becomes effective after the message has gone.		
	The message type can only be changed for messages with the appropriate identification (exception, value = 0).		
	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	CO: Sum of fault and alarm buffer changes / Sum buffer changed		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8065
	Min	Max	Factory setting
	-	-	-
Description:	Displays the sum of all of the fault and alarm buffer changes in the drive unit.		
Dependency:	Refer to: r0944		
r2122[0...63]	Alarm code / Alarm code		
	Access level: 2	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8065
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of alarms that have occurred.		
Dependency:	Refer to: r2110, r2123, r2124, r2125, r2134, r3121, r3123		
Notice:	The properties of the alarm buffer should be taken from the corresponding product documentation.		

2 Parameters

2.2 List of parameters

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		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8065
	Min	Max	Factory setting
	- [ms]	- [ms]	- [ms]
Description:	Displays the system runtime in milliseconds when the alarm occurred.		
Dependency:	Refer to: r2110, r2122, r2124, r2125, r2134		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139). The structure of the alarm buffer and the assignment of the indices is shown in r2122.		

r2124[0...63]	Alarm value / Alarm value		
	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8065
	Min	Max	Factory setting
	-	-	-
Description:	Displays additional information about the active alarm (as integer number).		
Dependency:	Refer to: r2110, r2122, r2123, r2125, r2134, r3121, r3123		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139). The structure of the alarm buffer and the assignment of the indices is shown in r2122.		

r2125[0...63]	Alarm time removed in milliseconds / t_alarm res ms		
Access level: 3	Calculated: -	Data type: Unsigned32	
Can be changed: -	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 8050, 8065	
Min	Max	Factory setting	
- [ms]	- [ms]	- [ms]	
Description:	Displays the system runtime in milliseconds when the alarm was cleared.		
Dependency:	Refer to: r2110, r2122, r2123, r2124, r2134		
Note:	The buffer parameters are cyclicly updated in the background (refer to status signal in r2139). The structure of the alarm buffer and the assionment of the indices is shown in r2122.		

p2126[0...19]	Change acknowledge mode fault number / Chng ackn F_no		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8075
	Min	Max	Factory setting
	0	65535	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		

Note: Re-parameterization is also possible if a fault is present. The change only becomes effective after the fault has been resolved.

p2127[0...19]	Change acknowledge mode mode / Chng ackn mode		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8075
	Min	Max	Factory setting
	1	2	1
Description:	Sets the acknowledge mode for selected fault.		
Value:	1: Acknowledgment only using POWER ON 2: Ack IMMEDIATELY after the fault cause has been removed		
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 for a fault in the following cases: - Fault number does not exist (exception value = 0). - Message type is not "fault" (F). - Acknowledge mode is not permissible for the set fault number.		
Note:	Re-parameterization is also possible if a fault is present. The change only becomes effective after the fault has been resolved. The acknowledge mode can only be changed for faults with the appropriate identification. Example: F12345 and acknowledge mode = IMMEDIATELY (POWER ON) --> The acknowledge mode can be changed from IMMEDIATELY to POWER ON.		

p2128[0...15]	Faults/alarms trigger selection / F/A trigger sel		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8050, 8070
	Min	Max	Factory setting
	0	65535	0
Description:	Sets the faults/alarms for which a trigger signal should be generated in r2129.0...15.		
Dependency:	If the fault/alarm set in p2128[0...15] occurs, then the particular binector output r2129.0...15 is set. Refer to: r2129		

r2129.0...15	CO/BO: Faults/alarms trigger word / F/A trigger word				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8070		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for the trigger signals of the faults/alarms set in p2128[0...15].				
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	-

2 Parameters

2.2 List of parameters

13	Trigger signal p2128[13]	ON	OFF	-
14	Trigger signal p2128[14]	ON	OFF	-
15	Trigger signal p2128[15]	ON	OFF	-

Dependency: If the fault/alarm set in p2128[0...15] occurs, then the particular binector output r2129.0...15 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 rcv days		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8060
	Min	Max	Factory setting
	-	-	-
Description:	Displays the system runtime in days when the fault occurred.		
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2133, r2136		
Notice:	The time comprises r2130 (days) and r0948 (milliseconds). The value displayed in p2130 refers to 01.01.1970.		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).		

r2131	CO: Actual fault code / Act fault code		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8060
	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		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8065
	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		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8060
	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				
	Access level: 3	Calculated: -	Data type: FloatingPoint32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8065		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays additional information about the active alarm for float values.				
Dependency:	Refer to: r2110, r2122, r2123, r2124, r2125, r3121, r3123				
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).				

r2135.12...15	CO/BO: Status word faults/alarms 2 / ZSW fault/alarm 2				
	Access level: 2	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2548		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for the second status word of faults and alarms.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	12	Fault motor overtemperature	Yes	No	8016
	13	Fault power unit thermal overload	Yes	No	8019
	14	Alarm motor overtemperature	Yes	No	8016
	15	Alarm power unit thermal overload	Yes	No	8019

r2136[0...63]	Fault time removed in days / t_fit resolv days				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8060		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the system runtime in days when the fault was removed.				
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2130, r2133				
Notice:	The time comprises r2136 (days) and r2109 (milliseconds).				
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139).				

r2138.7...15	CO/BO: Control word faults/alarms / STW fault/alarm				
	Access level: 2	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2546		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for the control word of faults and alarms.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	07	Acknowledge fault	Yes	No	8060
	10	External alarm 1 (A07850) effective	Yes	No	8065
	11	External alarm 2 (A07851) effective	Yes	No	8065
	12	External alarm 3 (A07852) effective	Yes	No	8065
	13	External fault 1 (F07860) effective	Yes	No	8060
	14	External fault 2 (F07861) effective	Yes	No	8060
	15	External fault 3 (F07862) effective	Yes	No	8060
Dependency:	Refer to: p2103, p2104, p2106, p2112				

r2139.0...15	CO/BO: Status word faults/alarms 1 / ZSW fault/alarm 1				
	Access level: 2	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2548		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for status word 1 of faults and alarms.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Being acknowledged	Yes	No	-
	01	Acknowledgment required	Yes	No	-
	03	Fault present	Yes	No	8060
	06	Internal message 1 present	Yes	No	-
	07	Alarm present	Yes	No	8065
	08	Internal message 2 present	Yes	No	-
	11	Alarm class bit 0	High	Low	-
	12	Alarm class bit 1	High	Low	-
	13	Maintenance required	Yes	No	-
	14	Maintenance urgently required	Yes	No	-
	15	Fault gone/can be acknowledged	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" or "alarm present" has occurred, a change in the buffer was also detected (r0944, r9744, r2121). Re bit 06, 08: These status bits are used for internal diagnostic purposes only. Re bit 11, 12: These status bits are used for the classification of internal alarm classes and are intended for diagnostic purposes only on certain automation systems with integrated SINAMICS functionality.				

p2141[0...n]	Speed threshold 1 / n_thresh val 1				
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 8010		
	Min	Max	Factory setting		
	0.00 [rpm]	210000.00 [rpm]	5.00 [rpm]		
Description:	Sets the speed threshold value for the signal "f or n comparison value reached or exceeded" (BO: r2199.1).				
Dependency:	Refer to: r2199				

p2153[0...n]	Speed actual value filter time constant / n_act_filt T				
	Access level: 3	Calculated: -	Data type: FloatingPoint32		
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: 8010		
	Min	Max	Factory setting		
	0 [ms]	1000000 [ms]	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				

p2155[0...n]	Speed threshold 2 / n_thresh val 2		
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 8010
	Min 0.00 [rpm]	Max 210000.00 [rpm]	Factory setting 900.00 [rpm]
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: r2197		
p2156[0...n]	On delay comparison value reached / t_on cmprr val rchd		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 8010
	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, r2199		
p2165[0...n]	Load monitoring stall monitoring upper threshold / Stall_mon up thr		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 8013
	Min 0.00 [rpm]	Max 210000.00 [rpm]	Factory setting 0.00 [rpm]
Description:	Sets the upper speed threshold of the stall monitoring of the pump or fan. The lower limit is formed by the speed threshold 1 of the load monitoring (p2182). The stall monitoring is active between p2182 and p2165.		
Dependency:	The following applies: p2182 < p2165 Refer to: A07891, F07894		
Note:	For p2165 = 0 or p2165 < p2182, the following applies: There is no special stall monitoring for the pump/fan, but only the remaining load monitoring functions (e.g. leakage monitoring for a pump) for the pump or fan are active.		
p2168[0...n]	Load monitoring stall monitoring torque threshold / Stall_mon M_thresh		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 8013
	Min 0.00 [Nm]	Max 20000000.00 [Nm]	Factory setting 10000000.00 [Nm]
Description:	Sets the torque threshold of the stall monitoring of the pump or fan. If, in the monitored speed range from p2182 to p2165, the torque exceeds this threshold, then this is evaluated as either the motor having stalled or heavy-duty starting.		
Dependency:	For pumps, the following applies (p2193 = 4): - the leakage characteristic must lie below the torque threshold for the stall monitoring - the torque threshold for dry running operation must lie below the torque threshold for stall monitoring For fans, the following applies (p2193 = 5): - the torque threshold for the stall monitoring must lie above the torque threshold to identify belt breakage (p2191). Refer to: p2165, p2191 Refer to: A07891, F07894		

2 Parameters

2.2 List of parameters

Note: The following applies for p2168 = 0:
The special stall monitoring for pump/fan is deactivated.
Then, only the remaining load monitoring functions (e.g. the leakage monitoring for a pump) for pump or fan are realized.

r2169	CO: Actual speed smoothed signals / n_act smth message		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: p2000	Dyn. index: -
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 8010
	Min	Max	Factory setting
	- [rpm]	- [rpm]	- [rpm]
Description:	Display and connector output of the smoothed speed actual value for messages.		
Dependency:	Refer to: p2153		
p2170[0...n]	Current threshold value / I_thres		
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2002	Dyn. index: DDS, p0180
	Unit group: 6_2	Unit selection: p0505	Func. diagram: 8020
	Min	Max	Factory setting
	0.00 [Arms]	10000.00 [Arms]	0.00 [Arms]
Description:	Sets the absolute current threshold for the messages. "I_act >= I_threshold p2170" (BO: r2197.8) "I_act < I_threshold p2170" (BO: r2198.8)		
Dependency:	Refer to: p2171		
p2171[0...n]	Current threshold value reached delay time / I_thresh rch t_del		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 8020
	Min	Max	Factory setting
	0 [ms]	10000 [ms]	10 [ms]
Description:	Sets the delay time for the comparison of the current actual value (r0068) with the current threshold value (p2170).		
Dependency:	Refer to: p2170		
p2172[0...n]	DC link voltage threshold value / Vdc thresh val		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2001	Dyn. index: DDS, p0180
	Unit group: 5_2	Unit selection: p0505	Func. diagram: -
	Min	Max	Factory setting
	0 [V]	2000 [V]	800 [V]
Description:	Sets the DC link voltage threshold value for the following messages: "Vdc_act <= Vdc_threshold p2172" (BO: r2197.9) "Vdc_act > Vdc_threshold p2172" (BO: r2197.10)		

p2174[0...n]	Torque threshold value 1 / M_thresh val 1		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 8012
	Min	Max	Factory setting
	0.00 [Nm]	20000000.00 [Nm]	5.13 [Nm]
Description:	Sets the torque threshold value for the messages: "Torque setpoint < torque threshold value 1 and n_set reached" (BO: r2198.9) "Torque setpoint < torque threshold value 1" (BO: r2198.10) "Torque setpoint > torque threshold value 1" (BO: r2198.13)		
Dependency:	Refer to: p2195, r2198		
p2191[0...n]	Load monitoring torque threshold no load / M_thresh no load		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 8013
	Min	Max	Factory setting
	0.00 [Nm]	20000000.00 [Nm]	0.00 [Nm]
Description:	Setting of the torque threshold to identify dry running operation for pumps or belt breakage for fans.		
Dependency:	The following applies: p2191 < p2168 if p2168 <> 0 Refer to: A07892, F07895		
Note:	For the setting p2191 = 0, the monitoring for dry running operation or belt breakage is deactivated. Preassignment: p2191 = 5 % of the rated motor torque (p0333).		
p2194[0...n]	Torque threshold value 2 / M_thresh val 2		
	Access level: 3	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 8012
	Min	Max	Factory setting
	0.00 [%]	100.00 [%]	90.00 [%]
Description:	Sets the torque threshold value for the message "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		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 8012
	Min	Max	Factory setting
	0.0 [ms]	1000.0 [ms]	800.0 [ms]
Description:	Sets the switch-off 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		

r2197.0...13

CO/BO: Status word monitoring 1 / ZSW monitor 1

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2534
Min	Max	Factory setting
-	-	-

Description:

Display and BICO output for the first status word of the monitoring functions.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	n_act <= n_min p1080	Yes	No	8020
01	n_act <= speed threshold value 2 p2155	Yes	No	8010
02	n_act > speed threshold value 2 p2155	Yes	No	8010
03	n_act >= 0	Yes	No	8011
04	n_act >= n_set	Yes	No	8020
05	n_act <= n_standstill p1226	Yes	No	8020
06	n_act > n_max	Yes	No	8010
07	Speed setp - act val deviation in tolerance t_off	Yes	No	8011
08	l_act >= l_threshold value p2170	Yes	No	8020
09	Vdc_act <= Vdc_threshold value p2172	Yes	No	8020
10	Vdc_act > Vdc_threshold value p2172	Yes	No	8020
11	Output load is not present	Yes	No	8020
12	n_act > n_max (delayed)	Yes	No	8021
13	n_act > n_max (F07901)	Yes	No	-

Notice:

Re bit 06:

When the overspeed is reached, this bit is set and F07901 output immediately following this. The bit is canceled again as soon as the next pulse inhibit is present.

Note:

Re bit 00:

The threshold value is set in p1080 and the hysteresis in p2150.

Re bit 01, 02:

The threshold value is set in p2155 and the hysteresis in p2140.

Re bit 03:

1 signal direction of rotation positive.

0 signal: direction of rotation negative.

The hysteresis is set in p2150.

Re bit 04:

The threshold value is set in r1119 and the hysteresis in p2150.

Re bit 05:

The threshold value is set in p1226 and the delay time in p1228.

Re bit 06:

The hysteresis is set in p2162.

Re bit 07:

The threshold value is set in p2163 and the hysteresis is set in p2164.

Re bit 08:

The threshold value is set in p2170 and the delay time in p2171.

Re bit 09, 10:

The threshold value is set in p2172 and the delay time in p2173.

Re bit 11:

The threshold value is set in p2179 and the delay time in p2180.

Re bit 12:

The threshold value is set in p2182, the hysteresis in p2162, and the delay time (for canceling the signal) in p2152.

Re bit 13:

Only for internal Siemens use.

r2198.0...13**CO/BO: Status word monitoring 2 / ZSW monitor 2**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2536
Min	Max	Factory setting
-	-	-

Description:

Display and BICO output for the second status word of the monitoring functions.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	n_act <= speed threshold value 5	Yes	No	8021
01	n_act > speed threshold value 5	Yes	No	8021
02	n_act <= speed threshold value 6	Yes	No	8021
03	n_act > speed threshold value 6	Yes	No	8021
04	n_set < p2161	Yes	No	8011
05	n_set > 0	Yes	No	8011
06	Motor blocked	Yes	No	8012
07	Motor stalled	Yes	No	8012
08	l_act < l_threshold value p2170	Yes	No	8020
09	M_act > torque threshold value 1 and n_set reached	Yes	No	8021
10	M_set < torque threshold value 1	Yes	No	8012
11	Load in the alarm range	Yes	No	8013
12	Load in the fault range	Yes	No	8013
13	M_act > torque threshold value 1	Yes	No	8021

Note:

Re bit 10:

The torque threshold value 1 is set in p2174.

Re bit 12:

This bit is reset after the fault cause disappears, even if the fault itself is still present.

r2199.0...11**CO/BO: Status word monitoring 3 / ZSW monitor 3**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2537
Min	Max	Factory setting
-	-	-

Description:

Display and BICO output for the third status word of the 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	8011
05	Ramp-up/ramp-down completed	Yes	No	8011
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. We recommend setting the hysteresis (p2142) for canceling the bit to a value lower than that in p2141. Otherwise, the bit is not reset.

Re bit 11:

The torque threshold value 2 is set in p2194.

p2200[0...n]	BI: Technology controller enable / Tec_ctrl enable		
	Access level: 2	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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_ctrl fix val1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2202[0...n]	CO: Technology controller fixed value 2 / Tec_ctr fix val 2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2203[0...n]	CO: Technology controller fixed value 3 / Tec_ctr fix val 3		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2204[0...n]	CO: Technology controller fixed value 4 / Tec_ctr fix val 4		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		

p2205[0...n]	CO: Technology controller fixed value 5 / Tec_ctr fix val 5		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	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 data set always acts on the effective data set.		
p2206[0...n]	CO: Technology controller fixed value 6 / Tec_ctr fix val 6		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	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 data set always acts on the effective data set.		
p2207[0...n]	CO: Technology controller fixed value 7 / Tec_ctr fix val 7		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	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 data set always acts on the effective data set.		
p2208[0...n]	CO: Technology controller fixed value 8 / Tec_ctr fix val 8		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	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 data set always acts on the effective data set.		
p2209[0...n]	CO: Technology controller fixed value 9 / Tec_ctr fix val 9		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	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 data set always acts on the effective data set.		

p2210[0...n]	CO: Technology controller fixed value 10 / Tec_ctr fix val 10		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2211[0...n]	CO: Technology controller fixed value 11 / Tec_ctr fix val 11		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2212[0...n]	CO: Technology controller fixed value 12 / Tec_ctr fix val 12		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2213[0...n]	CO: Technology controller fixed value 13 / Tec_ctr fix val 13		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2214[0...n]	CO: Technology controller fixed value 14 / Tec_ctr fix val 14		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		

p2215[0...n]	CO: Technology controller fixed value 15 / Tec_ctr fix val 15		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7950
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 data set always acts on the effective data set.		
p2216[0...n]	Technology controller fixed value selection method / Tec_ctr FixVal sel		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	1	2	1
Description:	Sets the method to select the fixed setpoints.		
Value:	1: Direct selection 2: Binary selection		
p2220[0...n]	BI: Technology controller fixed value selection bit 0 / Tec_ctrl sel bit 0		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select a fixed value of the technology controller.		
Dependency:	Refer to: p2221, p2222, p2223		
p2221[0...n]	BI: Technology controller fixed value selection bit 1 / Tec_ctrl sel bit 1		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select a fixed value of the technology controller.		
Dependency:	Refer to: p2220, p2222, p2223		
p2222[0...n]	BI: Technology controller fixed value selection bit 2 / Tec_ctrl sel bit 2		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7950, 7951
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to select a fixed value of the technology controller.		
Dependency:	Refer to: p2220, p2221, p2223		

p2223[0...n]	BI: Technology controller fixed value selection bit 3 / Tec_ctrl sel bit 3				
	Access level: 3		Calculated: -		Data type: U32 / Binary
	Can be changed: T		Scaling: -		Dyn. index: CDS, p0170
	Unit group: -		Unit selection: -		Func. diagram: 7950, 7951
	Min		Max		Factory setting
	-		-		0
Description: Sets the signal source to select a fixed value of the technology controller.					
Dependency: Refer to: p2220, p2221, p2222					

r2224	CO: Technology controller fixed value effective / Tec_ctr FixVal eff				
	Access level: 3		Calculated: -		Data type: FloatingPoint32
	Can be changed: -		Scaling: PERCENT		Dyn. index: -
	Unit group: 9_1		Unit selection: p0595		Func. diagram: 7950, 7951
	Min		Max		Factory setting
	- [%]		- [%]		- [%]
Description: Display and connector output for the selected and active fixed value of the technology controller.					
Dependency: Refer to: r2229					

r2225.0	CO/BO: Technology controller fixed value selection status word / Tec_ctr FixVal ZSW				
	Access level: 3		Calculated: -		Data type: Unsigned16
	Can be changed: -		Scaling: -		Dyn. index: -
	Unit group: -		Unit selection: -		Func. diagram: -
	Min		Max		Factory setting
	-		-		-
Description: Display and BICO output for the status word of the fixed value selection of the technology controller.					
Bit field:					
	Bit	Signal name	1 signal	0 signal	FP
	00	Technology controller fixed value selected	Yes	No	7950, 7951

r2229	Technology controller number actual / Tec_ctrl No. act				
	Access level: 3		Calculated: -		Data type: Unsigned32
	Can be changed: -		Scaling: -		Dyn. index: -
	Unit group: -		Unit selection: -		Func. diagram: 7950
	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				
	Access level: 3		Calculated: -		Data type: Unsigned32
	Can be changed: U, T		Scaling: -		Dyn. index: DDS, p0180
	Unit group: -		Unit selection: -		Func. diagram: 7954
	Min		Max		Factory setting
	-		-		0000 0100 bin
Description: Sets the configuration for the motorized potentiometer of the technology controller.					
Bit field:					
	Bit	Signal name	1 signal	0 signal	FP
	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	-
	04	Ramp-function generator always active	Yes	No	-
Dependency: Refer to: r2231, p2240					

Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.
Note:	<p>Re bit 00:</p> <p>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.</p> <p>Re bit 02:</p> <p>0: Without initial rounding-off 1: With initial rounding-off.</p> <p>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 initial rounding is independent of the ramp-up time and only depends on the selected maximum value (p2237). It is calculated as follows: $r = 0.0001 \times \max(p2237, p2238) \text{ [%]} / 0.13^2 \text{ [s}^2\text{]}$ The jerk is effective until the maximum acceleration is reached ($a_{\max} = p2237 \text{ [%]} / p2247 \text{ [s]}$ or $a_{\max} = p2238 \text{ [%]} / p2248 \text{ [s]}$), after which the drive continues to run linearly with constant acceleration. The higher the maximum acceleration (the lower that p2247 is), the longer the ramp-up time increases with respect to the set ramp-up time.</p> <p>Re bit 03:</p> <p>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).</p> <p>Re bit 04:</p> <p>When the bit is set, the ramp-function generator is computed independent of the pulse enable. The actual output value of the motorized potentiometer is always in r2250.</p>

r2231 Technology controller motorized potentiometer setpoint memory / Tec_ctrl mop mem

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: 9_1	Unit selection: p0595	Func. diagram: 7954
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_ctrl mop raise


Access level: 3	Calculated: -	Data type: U32 / Binary
Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
Unit group: -	Unit selection: -	Func. diagram: 7954
Min	Max	Factory setting
-	-	0

Description: Sets the signal source to continually increase the setpoint for the motorized potentiometer of the technology controller.
The setpoint change (CO: r2250) depends on the set ramp-up time (p2247) and the duration of the signal that is present (BI: p2235).

Dependency: Refer to: p2236

p2236[0...n]	BI: Technology controller motorized potentiometer lower setpoint / Tec_ctrl mop lower		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7954
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to continually reduce the setpoint for the motorized potentiometer of the technology controller. The setpoint change (CO: r2250) depends on the set ramp-down time (p2248) and the duration of the signal that is present (BI: p2236).		
Dependency:	Refer to: p2235		
p2237[0...n]	Technology controller motorized potentiometer maximum value / Tec_ctrl mop max		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7954
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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_ctrl mop min		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7954
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	-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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7954
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	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 befRFG		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7954
	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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 7954
	Min	Max	Factory setting
	0.0 [s]	1000.0 [s]	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		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 7954
	Min	Max	Factory setting
	0.0 [s]	1000.0 [s]	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 aftRFG		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7954
	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		
p2251	Technology controller mode / Tec_ctrl mode		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 3070, 7958
	Min	Max	Factory setting
	0	1	0
Description:	Sets the mode for using the technology controller output.		
Value:	0: Technology controller as main speed setpoint 1: Technology controller as supplementary speed setpoint		
Dependency:	p2251 = 0, 1 is only effective if the enable signal of the technology controller is interconnected (p2200 > 0).		


p2252	Technology controller configuration / Tec_ctrl config				
	Access level: 3	Calculated: p0340 = 1	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 0000 bin		
Description:	Sets the configuration of the technology controller.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	04	Ramp-up/ramp-down function generator bypass	Deactivated	Activated	-
	05	Integrator active for skip speeds	Yes	no	-
	06	Internal controller limit not displayed	Yes	No	-
Dependency:	Re bit 04 = 0: The setting is only effective when the PID controller is deactivated. Refer to: p2280, p2285 Re bit 04 = 1 (p2251 = 0): The PID controller can oscillate if the ramp-up and ramp-down times of the speed setpoint channel are not taken into account when setting controller parameters p2280 and p2285.				
Caution:					
Note:	Re bit 04 = 0 (only for p2251 = 0): The ramp-function generator in the speed setpoint channel is bypassed when the technology controller is operational. As a consequence, ramp times p1120, p1121 are not taken into consideration when configuring the controller. Re bit 04 = 1 (only for p2251 = 0): The ramp-function generator in the speed setpoint channel is not bypassed when the technology controller is operational. As a consequence, the ramp-up and ramp-down times (p1120, p1121) remain effective, and must be taken into account as controlled system variables when setting the PID controller parameters (p2280, p2285). The enable ramps of the PID controller are ensured in this setting by p1120, p1121 as well as rounding functions p1130 and p1131. The ramp-up/ramp-down time of the PID controller limiting p2293 must be set appropriately shorter, as otherwise this has an impact on the speed setpoint channel. Re bit 05 = 0: The integral component of the PID controller is held if a skip band or the minimum speed range is passed through in the speed set point channel. This prevents the speed from oscillating between the edges of the skip band. Re bit 05 = 1: The setting is only effective if a skip band is no longer active. The integral component of the PID controller is not held in the range of the skip speeds. The skip band is passed through even for small system deviations and low controller gain factors. In so doing, the controller integral time must be selected large enough so that no undesirable speed oscillations occur between the skip band edges. The influence of a minimum speed p1080 on the integration behavior can be reduced by raising the lower PID controller limit to p1080 / p2000 * 100%. Re bit 06 = 1: In r2349, bit 10 and bit 11 are not displayed when reaching internal limits (e.g. for OFF1/3).				

p2253[0...n]	CI: Technology controller setpoint 1 / Tec_ctrl setp 1				
	Access level: 2	Calculated: -	Data type: U32 / FloatingPoint32		
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170		
	Unit group: -	Unit selection: -	Func. diagram: 7958		
	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_ctrl setp 2		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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_ctrl set1 scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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_ctrl set2 scal		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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_ctrl t_ramp-up		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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_ctrl t_ramp-dn		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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 aftRFG		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	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_ctrl set T		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.000 [s]	60.000 [s]	0.000 [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 aftFit		
	Access level: 4	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Display and connector output for the smoothed setpoint after the setpoint filter (PT1) of the technology controller.		
p2263	Technology controller type / Tec_ctrl type		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0	1	0
Description:	Sets the type of technology controller.		
Value:	0: D component in the actual value signal 1: D component in system deviation		
p2264[0...n]	CI: Technology controller actual value / Tec_ctrl act val		
	Access level: 2	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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_ctrl act T		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.000 [s]	60.000 [s]	0.000 [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 aftFlt		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Display and connector output for the smoothed actual value after the filter (PT1) of the technology controller.		
p2267	Technology controller upper limit actual value / Tec_ctrl u_lim act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	100.00 [%]
Description:	Sets the upper limit for the actual value signal of the technology controller.		
Dependency:	Refer to: p2264, p2265, p2271		
	Refer to: F07426		
Notice:	If the actual value exceeds this upper limit, this results in fault F07426.		
p2268	Technology controller lower limit actual value / Tec_ctrl l_lim act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	-100.00 [%]
Description:	Sets the lower limit for the actual value signal of the technology controller.		
Dependency:	Refer to: p2264, p2265, p2271		
	Refer to: F07426		
Notice:	If the actual value falls below this lower limit, this results in fault F07426.		
p2269	Technology controller gain actual value / Tech_ctrl gain act		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.00 [%]	500.00 [%]	100.00 [%]
Description:	Sets the scaling factor for the actual value of the technology controller.		
Dependency:	Refer to: p2264, p2265, p2267, p2268, p2271		
Note:	For 100%, the actual value is not changed.		
p2270	Technology controller actual value function / Tec_ctr ActVal fct		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0	3	0
Description:	Setting to use an arithmetic function for the actual value signal of the technology controller.		
Value:	0: Output (y) = input (x) 1: Root function (root from x) 2: Square function (x * x) 3: Cube function (x * x * x)		
Dependency:	Refer to: p2264, p2265, p2267, p2268, p2269, p2271		

p2271	Technology controller actual value inversion (sensor type) / Tech_ctrl act inv		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0	1	0
Description:	Setting to invert the actual value signal of the technology controller. The inversion depends on the sensor type for the actual value signal.		
Value:	0: No inversion 1: Inversion actual value signal		
Caution:	If the actual value inversion is incorrectly selected, then the closed-loop control with the technology controller can become unstable and can oscillate!		
			
Note:	The correct setting can be determined as follows: - inhibit the technology controller (p2200 = 0). - increase the motor speed and in so doing, measure the actual value signal of the technology controller. --> If the actual value increases as the motor speed increases, then p2271 should be set to 0 (no inversion). --> If the actual value decreases as the motor speed increases, then p2271 should be set to 1 (the actual value signal is inverted).		
r2272	CO: Technology controller actual value scaled / Tech_ctrl act scal		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Display and connector output for the scaled actual value signal of the technology controller.		
Dependency:	Refer to: p2264, p2265, r2266, p2267, p2268, p2269, p2270, p2271		
r2273	CO: Technology controller system deviation / Tec_ctrl sys_dev		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: 7958
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Displays the system deviation between the setpoint and actual value of the technology controller.		
Dependency:	Refer to: p2263		
p2274	Technology controller differentiation time constant / Tec_ctrl D comp T		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.000 [s]	60.000 [s]	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_ctrl Kp		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.000	1000.000	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_ctrl Tn		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.000 [s]	10000.000 [s]	30.000 [s]
Description:	Sets the integral time (I component, integrating time constant) of the technology controller.		
Notice:	The following applies for p2251 = 0: If the output of the technology controller lies within the range of a suppression (skip) bandwidth (p1091 ... p1092, p1101) or below the minimum speed (p1080), the integral component of the controller is held so that the controller temporarily works as a P controller. This is necessary in order to prevent the controller from behaving in an unstable manner, as the ramp-function generator switches to the parameterized up and down ramps (p1120, p1121) at the same time in order to avoid setpoint steps. This state can be exited or avoided by changing the controller setpoint or by using the start speed (= minimum speed).		
Note:	When the controller output reaches the limit, the I component of the controller is held. p2285 = 0: The integral time is disabled and the I component of the controller is reset.		
p2286[0...n]	BI: Hold technology controller integrator / Tec_ctr integ hold		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	-	-	56.13
Description:	Sets the signal source to hold the integrator for the technology controller.		
p2289[0...n]	CI: Technology controller pre-control signal / Tec_ctr prectr_sig		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the pre-control signal of the technology controller.		
p2290[0...n]	BI: Technology controller limiting enable / Tec_ctrl lim enab		
	Access level: 2	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	-	-	1
Description:	Sets the signal source to enable the technology controller output. The technology controller output is enabled with a 1 signal. The technology controller output is held with a 0 signal.		

p2291	CO: Technology controller maximum limiting / Tec_ctrl max_lim		
Access level: 3	Calculated: -	Data type: FloatingPoint32	
Can be changed: U, T	Scaling: PERCENT	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 7958	
Min	Max	Factory setting	
-200.00 [%]	200.00 [%]	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_ctrl min_lim		
Access level: 3	Calculated: -	Data type: FloatingPoint32	
Can be changed: U, T	Scaling: PERCENT	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 7958	
Min	Max	Factory setting	
-200.00 [%]	200.00 [%]	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 t_RU/RD		
Access level: 3	Calculated: -	Data type: FloatingPoint32	
Can be changed: U, T	Scaling: -	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 7958	
Min	Max	Factory setting	
0.00 [s]	100.00 [s]	1.00 [s]	

Description: Sets the ramping time for the output signal of the technology controller.

Dependency: Refer to: p2291, p2292

Note: The time refers to the set maximum and minimum limits (p2291, p2292).

r2294	CO: Technology controller output signal / Tec_ctrl outp_sig		
Access level: 2	Calculated: -	Data type: FloatingPoint32	
Can be changed: -	Scaling: PERCENT	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 7958	
Min	Max	Factory setting	
- [%]	- [%]	- [%]	

Description: Display and connector output for the output signal of the technology controller.

Dependency: Refer to: p2295


p2295	CO: Technology controller output scaling / Tec_ctrl outp_scal		
Access level: 3	Calculated: -	Data type: FloatingPoint32	
Can be changed: U, T	Scaling: PERCENT	Dyn. index: -	
Unit group: -	Unit selection: -	Func. diagram: 7958	
Min	Max	Factory setting	
-100.00 [%]	100.00 [%]	100.00 [%]	

Description: Sets the scaling for the output signal of the technology controller.

p2296[0...n]	CI: Technology controller output scaling / Tec_ctrl outp scal		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	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 limit signal source / Tec_ctrMaxLimS_src		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	-	-	1084[0]
Description:	Sets the signal source for the maximum limiting of the technology controller.		
Dependency:	Refer to: p2291		
Note:	In order that the output of the technology controller does not exceed the maximum speed limit, its upper limit p2297 should be connected to the actual maximum speed r1084. In mode p2251 = 1, p2299 must also be connected to the output of the ramp-function generator r1150.		
p2298[0...n]	CI: Technology controller minimum limit signal source / Tec_ctrl min_l s_s		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	-	-	1087[0]
Description:	Sets the signal source for the minimum limiting of the technology controller.		
Dependency:	Refer to: p2292		
Note:	If the technology controller is rotated in a negative direction in mode p2251 = 0, its lower limit p2298 should be connected to the actual minimum speed r1087. In mode p2251 = 1, p2299 must also be connected to the output of the ramp-function generator r1150.		
p2299[0...n]	CI: Technology controller limit offset / Tech_ctrl lim offs		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the offset of the output limiting of the technology controller.		
Note:	In mode p2251 = 1, p2299 must be connected to the output of ramp-function generator r1150 so that the technology controller stops when the speed limits are reached (see also p2297, p2298).		
p2302	Technology controller output signal starting value / Tec_ctr start val		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0.00 [%]	200.00 [%]	0.00 [%]
Description:	Sets the start value for the output of the technology controller. If the drive is switched on and the technology controller is already enabled (see p2200, r0056.3), then its output signal r2294 first goes to the start value p2302, before the controller starts to operate.		

Dependency: The starting value is only effective in the mode "technology controller as main speed setpoint" (p2251 = 0).
If the technology controller is first enabled when the drive is switched on, a start speed remains ineffective, and the controller output starts with the actual setpoint speed of the ramp-function generator.

Note: If the technology controller operates on the speed/setpoint channel (p2251 = 0), then the starting value is interpreted as the starting speed and when operation is enabled, is connected to the output of the technology controller (r2294).
If fault F07426 "technology controller actual value limited" occurs while ramping up to the starting value and if the associated reaction has been set to "NONE" (see p2100, p2101), the starting value is kept as the speed setpoint instead of a switch to closed-loop control operation.

p2306	Technology controller system deviation inversion / Tec_ctr SysDev inv		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7958
	Min	Max	Factory setting
	0	1	0
Description:	Setting to invert the system deviation of the technology controller. The setting depends on the type of control loop.		
Value:	0: No inversion 1: Inversion		
Caution:	If the actual value inversion is incorrectly selected, then the closed-loop control with the technology controller can become unstable and can oscillate!		
			
Note:	The correct setting can be determined as follows: - inhibit the technology controller (p2200 = 0). - increase the motor speed and in so doing, measure the actual value signal (of the technology controller). - if the actual value increases with increasing motor speed, then the inversion should be switched out. - if the actual value decreases with increasing motor speed, then the inversion should be set. If value = 0: The drive reduces the output speed when the actual value rises (e.g. for heating fans, intake pump, compressor). If value = 1: The drive increases the output speed when the actual value increases (e.g. for cooling fans, discharge pumps).		

p2339	Techn. controller threshold value f. I comp. hold for skip speed / Tec_ctrl thr_skip		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: -
	Unit group: 9_1	Unit selection: p0595	Func. diagram: -
	Min	Max	Factory setting
	0.00 [%]	200.00 [%]	2.00 [%]
Description:	Sets the threshold value for the system deviation of the technology controller, which controls holding the controller integral component in the range of the skip speeds of the ramp-function generator.		
Recommendation:	To avoid speed setpoint steps in the range of the skip speeds, we recommend setting p2252 bit 4 = 1 (ramp-function generator bypass deactivated).		
Dependency:	The parameter has no effect for p2252 bit 5 = 1 (integrator hold deactivated). Refer to: r2273		
Note:	Only p2251 = 0: If the output signal of the technology controller reaches a skip band in the speed setpoint channel, then the integral component of the controller is held, if at the same time, the system deviation is lower than the threshold value set here. By holding the integral component, it can be avoided that the controller oscillates in the range of the skip bands.		

r2344	CO: Technology controller last speed setpoint (smoothed) / Tec_ctrl n_setp_sm				
	Access level: 3		Calculated: -	Data type: FloatingPoint32	
	Can be changed: -		Scaling: PERCENT	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 7958	
	Min		Max	Factory setting	
	- [%]		- [%]	- [%]	
Description:	Displays the smoothed speed setpoint of the technology controller prior to switching to operation with fault response (see p2345).				
Dependency:	Refer to: p2345				
Note:	Smoothing time = 10 s				
p2345	Technology controller fault response / Tech_ctrl flt resp				
	Access level: 3		Calculated: -	Data type: Integer16	
	Can be changed: U, T		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 7958	
	Min		Max	Factory setting	
	0		2	0	
Description:	Sets the response of the technology controller to the occurrence of fault F07426 (technology controller actual value limited).				
	The fault response is executed if status bit 8 or 9 in the technology controller status word r2349 is set. If both status bits are zero, a switch back to technology controller operation will follow.				
Value:	0: Function inhibited				
	1: On fault: Changeover to r2344 (or p2302)				
	2: On fault: Changeover to p2215				
Dependency:	The parameterized fault response is only effective if the technology controller mode is set to p2251 = 0 (technology controller as main setpoint).				
	Refer to: p2267, p2268, r2344				
	Refer to: F07426				
Notice:	Dependent upon the application, the changing over of the setpoint when fault F07426 occurs can lead to the fault condition disappearing and the re-activation of the technology controller. This can repeat itself and cause limit oscillations. In this case, a different fault response or a different fixed setpoint 15 for the fault response p2345 = 2 should be selected.				
Note:	The parameterized fault response can only be achieved if the default fault response of the technology controller fault F07426 is set to "NONE" (see p2100, p2101). If a fault response other than "NONE" is entered in p2101 for F07426, p2345 must be set to zero.				
	If the fault occurs during ramping up to the starting setpoint p2302, this starting setpoint is retained as the final value (there is no changeover to the fault response setpoint).				
r2349.0...13	CO/BO: Technology controller status word / Tec_ctrl status				
	Access level: 3		Calculated: -	Data type: Unsigned32	
	Can be changed: -		Scaling: -	Dyn. index: -	
	Unit group: -		Unit selection: -	Func. diagram: 7958	
	Min		Max	Factory setting	
	-		-	-	
Description:	Display and BICO output for 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	Yes	No	-
		potentiometer limited max			
	03	Technology controller motorized	Yes	No	-
		potentiometer limited min			
	04	Technology controller speed setpoint total in setpoint channel	Yes	No	-
	05	Technology controller RFG bypassed in the setpoint channel	Yes	No	-

2 Parameters

2.2 List of parameters

06	Technology controller starting value at the current limit	No	Yes	-
08	Technology controller actual value at the minimum	Yes	No	-
09	Technology controller actual value at the maximum	Yes	No	-
10	Technology controller output at the minimum	Yes	No	-
11	Technology controller output at the maximum	Yes	No	-
12	Fault response active	Yes	No	-
13	Technology controller limiting enable	Yes	No	-

Note:

While the technology controller is enabled, the following applies:

When switching off with OFF1, OFF3 and for pulse inhibit, bits 10 and 11 are simultaneously set to 1 as the controller output is defined by the internal limiting.

p2350

PID autotune enable / PID auto en

Access level: 2	Calculated: -	Data type: Integer16
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	4	0

Value:

0:	No function
1:	Ziegler Nichols
2:	Some overshoot
3:	No overshoot
4:	PI only

p2354

PID tuning timeout length / PID auto to

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
60 [s]	65000 [s]	240 [s]

p2355

PID tuning offset / PID auto o/s

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0 [%]	20 [%]	5 [%]

p2900[0...n]

CO: Fixed value 1 [%] / Fixed value 1 [%]

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
Unit group: -	Unit selection: -	Func. diagram: 1021
Min	Max	Factory setting
-10000.00 [%]	10000.00 [%]	0.00 [%]

Description:

Setting and connector output for a fixed percentage value.

Dependency:

Refer to: p2901, r2902, p2930

Notice:

A BICO interconnection to a parameter that belongs to a drive data set 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 [%]		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 1021
	Min	Max	Factory setting
	-10000.00 [%]	10000.00 [%]	0.00 [%]
Description:	Setting and connector output for a fixed percentage value.		
Dependency:	Refer to: p2900, p2930		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set 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)		
r2902[0...14]	CO: Fixed values [%] / Fixed values [%]		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: PERCENT	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 1021
	Min	Max	Factory setting
	- [%]	- [%]	- [%]
Description:	Display and connector output for frequently used percentage values.		
Index:	[0] = Fixed value +0 % [1] = Fixed value +5 % [2] = Fixed value +10 % [3] = Fixed value +20 % [4] = Fixed value +50 % [5] = Fixed value +100 % [6] = Fixed value +150 % [7] = Fixed value +200 % [8] = Fixed value -5 % [9] = Fixed value -10 % [10] = Fixed value -20 % [11] = Fixed value -50 % [12] = Fixed value -100 % [13] = Fixed value -150 % [14] = Fixed value -200 %		
Dependency:	Refer to: p2900, p2901, p2930		
Note:	The signal sources can, for example, be used to interconnect scalings.		
p2930[0...n]	CO: Fixed value M [Nm] / Fixed value M [Nm]		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: p2003	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 1021
	Min	Max	Factory setting
	-100000.00 [Nm]	100000.00 [Nm]	0.00 [Nm]
Description:	Setting and connector output for a fixed torque value.		
Dependency:	Refer to: p2900, p2901, r2902		
Notice:	A BICO interconnection to a parameter that belongs to a drive data set always acts on the effective data set.		
Note:	The value can, for example, be used to interconnect a supplementary torque.		

r2969[0...6]	Flux model value display / Psi_mod val displ			
	Access level: 3	Calculated: -	Data type: FloatingPoint32	
	Can be changed: -	Scaling: -	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Displays the values of the direct access flux model for the synchronous reluctance motor (RESM) for diagnostic purposes. Valid values are only displayed when the pulses are inhibited. Re index 0: Display of the entered direct axis current id in Arms: Re index 1, 2, 3: Display of the saturation curves of the direct axis flux psid(id, iq): - r2969[1]: flux in Vsrms with respect to the direct axis current for iq = 0 - r2969[2]: flux in Vsrms with respect to the direct axis current for iq = 0.5 * p2950 - r2969[3]: flux in Vsrms with respect to the direct axis current for iq = p2950 Re index 4, 5, 6: Displays the relative error of the current inversion(id(psid, iq) - id) / p2950: - r2969[4]: error with respect to direct axis current for iq = 0 - r2969[5]: error with respect to direct axis current for iq = 0.5 * p2950 - r2969[6]: error with respect to direct axis current for iq = p2950			
Index:	[0] = d-current [1] = d-flux iq0 [2] = d-flux iq1 [3] = d-flux iq2 [4] = d-current error iq0 [5] = d-current error iq1 [6] = d-current error iq2			
Note:	RESM: reluctance synchronous motor (synchronous reluctance motor)			

r3113.0...15	CO/BO: NAMUR message bit bar / NAMUR bit bar				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for the status of the NAMUR message bit bar. The faults and 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 converter information electronics/software error	Yes	No	-
	01	Network 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	-
	10	Error communication internal	Yes	No	-
	11	Fault infeed	Yes	No	-
	15	Other faults	Yes	No	-

Note:

Re bit 00:

Hardware or software malfunction was identified. Carry out a POWER ON of the component involved. If it occurs again, contact the hotline.

Re bit 01:

A line supply fault has occurred (phase failure, voltage level, ...). Check the line supply / fuses. Check the supply voltage. Check the wiring.

Re bit 02:

The DC link voltage has assumed an inadmissibly high value. Check the dimensioning of the system (line supply, reactor, voltages). Check the infeed settings.

Re bit 03:

An inadmissible operating state of the power electronics was identified (overcurrent, overtemperature, IGBT failure, ...). Check that the permissible load cycles are maintained. Check the ambient temperatures (fan).

Re bit 04:

The temperature in the component has exceeded the highest permissible limit. Check the ambient temperature / control cabinet cooling.

Re bit 05:

A ground fault / inter-phase short-circuit was detected in the power cables or in the motor windings. Check the power cable (connection). Check the motor.

Re bit 06:

The motor was operated outside the permissible limits (temperature, current, torque, ...). Check the load cycles and limits that have been set. Check the ambient temperature / motor cooling.

Re bit 07:

The communication to the higher-level control system (internal coupling, PROFIBUS, PROFINET, ...) is faulted or interrupted. Check the state of the higher-level control system. Check the communication connection/wiring. Check the bus configuration / clock cycles.

Re bit 08:

A safety operation monitoring function (Safety) has detected an error.

Re bit 09:

When evaluating the encoder signals (track signals, zero marks, absolute values, ...) an illegal signal state was detected. Check the encoder / state of the encoder signals. Observe the maximum frequencies.

Re bit 10:

The internal communication between the SINAMICS components is faulted or interrupted. Check the DRIVE-CLiQ wiring. Ensure an EMC-compliant design. Observe the maximum permissible quantity structure / clock cycles.

Re bit 11:

The infeed is faulted or has failed. Check the infeed and the surroundings (line supply, filter, reactors, fuses, ...). Check the closed-loop infeed control.

Re bit 15:

Group fault. Determine the precise cause of the fault using the commissioning tool.

p3117**Change safety message type / Ch. SI mess type****Access level:** 3**Calculated:** -**Data type:** Unsigned32**Can be changed:** -**Scaling:** -**Dyn. index:** -**Unit group:** -**Unit selection:** -**Func. diagram:** -**Min****Max****Factory setting**

0

1

0

Description:

Sets the re-parameterization of all safety messages for faults and alarms.

The relevant message type during changeover is selected by the firmware.

0: Safety messages are not re-parameterized

1: Safety messages are re-parameterized

Note:

A change only becomes effective after a POWER ON.

r3120[0...63]	Component fault / Comp fault		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8060
	Min	Max	Factory setting
	0	3	-
Description:	Displays the component of the fault which has occurred.		
Value:	0: No assignment 1: Control Unit 2: Power Module 3: Motor		
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2130, r2133, r2136, r3122		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139). The structure of the fault buffer and the assignment of the indices is shown in r0945.		

r3121[0...63]	Component alarm / Comp alarm		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 8065
	Min	Max	Factory setting
	0	3	-
Description:	Displays the component of the alarm which has occurred.		
Value:	0: No assignment 1: Control Unit 2: Power Module 3: Motor		
Dependency:	Refer to: r2110, r2122, r2123, r2124, r2125, r2134, r3123		
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139). The structure of the alarm buffer and the assignment of the indices is shown in r2122.		

r3122[0...63]	Diagnostic attribute fault / Diag_attr fault				
	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 8060		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the diagnostic attribute of the fault which has occurred.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Hardware replacement recommended	Yes	No	-
	15	Message has gone	Yes	No	-
	16	PROFIdrive fault class bit 0	High	Low	-
	17	PROFIdrive fault class bit 1	High	Low	-
	18	PROFIdrive fault class bit 2	High	Low	-
	19	PROFIdrive fault class bit 3	High	Low	-
	20	PROFIdrive fault class bit 4	High	Low	-
Dependency:	Refer to: r0945, r0947, r0948, r0949, r2109, r2130, r2133, r2136, r3120				
Note:	The buffer parameters are cyclically updated in the background (refer to status signal in r2139). The structure of the fault buffer and the assignment of the indices is shown in r0945. Re bits 20 ... 16: Bits 20, 19, 18, 17, 16 = 0, 0, 0, 0, 0 --> PROFIdrive message class 0: not assigned Bits 20, 19, 18, 17, 16 = 0, 0, 0, 0, 1 --> PROFIdrive message class 1: hardware fault/software error Bits 20, 19, 18, 17, 16 = 0, 0, 0, 1, 0 --> PROFIdrive message class 2: line fault Bits 20, 19, 18, 17, 16 = 0, 0, 0, 1, 1 --> PROFIdrive message class 3: supply voltage fault Bits 20, 19, 18, 17, 16 = 0, 0, 1, 0, 0 --> PROFIdrive message class 4: DC link fault Bits 20, 19, 18, 17, 16 = 0, 0, 1, 0, 1 --> PROFIdrive message class 5: power electronics faulted				

Bits 20, 19, 18, 17, 16 = 0, 0, 1, 1, 0 --> PROFIdrive message class 6: overtemperature electronic components
 Bits 20, 19, 18, 17, 16 = 0, 0, 1, 1, 1 --> PROFIdrive message class 7: ground fault/phase fault detected
 Bits 20, 19, 18, 17, 16 = 0, 1, 0, 0, 0 --> PROFIdrive message class 8: motor overload
 Bits 20, 19, 18, 17, 16 = 0, 1, 0, 0, 1 --> PROFIdrive message class 9: communication error to the higher-level control
 Bits 20, 19, 18, 17, 16 = 0, 1, 0, 1, 0 --> PROFIdrive message class 10: safe monitoring channel has identified an error
 Bits 20, 19, 18, 17, 16 = 0, 1, 0, 1, 1 --> PROFIdrive message class 11: incorrect position actual value/speed actual value or not available
 Bits 20, 19, 18, 17, 16 = 0, 1, 1, 0, 0 --> PROFIdrive message class 12: internal (DRIVE-CLiQ) communication error
 Bits 20, 19, 18, 17, 16 = 0, 1, 1, 0, 1 --> PROFIdrive message class 13: infeed unit faulted
 Bits 20, 19, 18, 17, 16 = 0, 1, 1, 1, 0 --> PROFIdrive message class 14: braking controller/Braking Module faulted
 Bits 20, 19, 18, 17, 16 = 0, 1, 1, 1, 1 --> PROFIdrive message class 15: line filter faulted
 Bits 20, 19, 18, 17, 16 = 1, 0, 0, 0, 0 --> PROFIdrive message class 16: external measured value/signal state outside the permissible range
 Bits 20, 19, 18, 17, 16 = 1, 0, 0, 0, 1 --> PROFIdrive message class 17: application/technology function faulted
 Bits 20, 19, 18, 17, 16 = 1, 0, 0, 1, 0 --> PROFIdrive message class 18: error in the parameterization/configuration/commissioning sequence
 Bits 20, 19, 18, 17, 16 = 1, 0, 0, 1, 1 --> PROFIdrive message class 19: general drive fault
 Bits 20, 19, 18, 17, 16 = 0, 1, 1, 0, 0 --> PROFIdrive message class 20: auxiliary unit faulted

r3123[0...63]**Diagnostic attribute alarm / Diag_attr alarm**

Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8065
Min	Max	Factory setting
-	-	-

Description:

Displays the diagnostic attribute of the alarm which has occurred.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Hardware replacement recommended	Yes	No	-
11	Alarm class bit 0	High	Low	-
12	Alarm class bit 1	High	Low	-
13	Maintenance required	Yes	No	-
14	Maintenance urgently required	Yes	No	-
15	Message has gone	Yes	No	-
16	PROFIdrive fault class bit 0	High	Low	-
17	PROFIdrive fault class bit 1	High	Low	-
18	PROFIdrive fault class bit 2	High	Low	-
19	PROFIdrive fault class bit 3	High	Low	-
20	PROFIdrive fault class bit 4	High	Low	-

Dependency:

Refer to: r2110, r2122, r2123, r2124, r2125, r2134, r3121

Note:

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

The structure of the alarm buffer and the assignment of the indices is shown in r2122.

Re bit 12, 11:

These status bits are used for the classification of internal alarm classes and are intended for diagnostic purposes only on certain automation systems with integrated SINAMICS functionality.

Re bits 20 ... 16:

Bits 20, 19, 18, 17, 16 = 0, 0, 0, 0, 0 --> PROFIdrive message class 0: not assigned
 Bits 20, 19, 18, 17, 16 = 0, 0, 0, 0, 1 --> PROFIdrive message class 1: hardware fault/software error
 Bits 20, 19, 18, 17, 16 = 0, 0, 0, 1, 0 --> PROFIdrive message class 2: line fault
 Bits 20, 19, 18, 17, 16 = 0, 0, 0, 1, 1 --> PROFIdrive message class 3: supply voltage fault
 Bits 20, 19, 18, 17, 16 = 0, 0, 1, 0, 0 --> PROFIdrive message class 4: DC link fault
 Bits 20, 19, 18, 17, 16 = 0, 0, 1, 0, 1 --> PROFIdrive message class 5: power electronics faulted
 Bits 20, 19, 18, 17, 16 = 0, 0, 1, 1, 0 --> PROFIdrive message class 6: overtemperature electronic components
 Bits 20, 19, 18, 17, 16 = 0, 0, 1, 1, 1 --> PROFIdrive message class 7: ground fault/phase fault detected
 Bits 20, 19, 18, 17, 16 = 0, 1, 0, 0, 0 --> PROFIdrive message class 8: motor overload
 Bits 20, 19, 18, 17, 16 = 0, 1, 0, 0, 1 --> PROFIdrive message class 9: communication error to the higher-level control

2 Parameters

2.2 List of parameters

Bits 20, 19, 18, 17, 16 = 0, 1, 0, 1, 0 --> PROFIdrive message class 10: safe monitoring channel has identified an error
Bits 20, 19, 18, 17, 16 = 0, 1, 0, 1, 1 --> PROFIdrive message class 11: incorrect position actual value/speed actual value or not available
Bits 20, 19, 18, 17, 16 = 0, 1, 1, 0, 0 --> PROFIdrive message class 12: internal (DRIVE-CLiQ) communication error
Bits 20, 19, 18, 17, 16 = 0, 1, 1, 0, 1 --> PROFIdrive message class 13: infeed unit faulted
Bits 20, 19, 18, 17, 16 = 0, 1, 1, 1, 0 --> PROFIdrive message class 14: braking controller/Braking Module faulted
Bits 20, 19, 18, 17, 16 = 0, 1, 1, 1, 1 --> PROFIdrive message class 15: line filter faulted
Bits 20, 19, 18, 17, 16 = 1, 0, 0, 0, 0 --> PROFIdrive message class 16: external measured value/signal state outside the permissible range
Bits 20, 19, 18, 17, 16 = 1, 0, 0, 0, 1 --> PROFIdrive message class 17: application/technology function faulted
Bits 20, 19, 18, 17, 16 = 1, 0, 0, 1, 0 --> PROFIdrive message class 18: error in the parameterization/configuration/commissioning sequence
Bits 20, 19, 18, 17, 16 = 1, 0, 0, 1, 1 --> PROFIdrive message class 19: general drive fault
Bits 20, 19, 18, 17, 16 = 0, 1, 1, 0, 0 --> PROFIdrive message class 20: auxiliary unit faulted

p3233[0...n]	Torque actual value filter time constant / M_act_filt T		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 8013
	Min	Max	Factory setting
	0 [ms]	1000000 [ms]	100 [ms]
Description:	Sets the time constant for the PT1 element to smooth the torque actual value. The smoothed torque actual value is compared with the threshold values and is only used for messages and signals.		

p3320[0...n]	Fluid flow machine power point 1 / Fluid_mach P1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	25.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the power (P) of point 1 as a [%]. The characteristic comprises the following value pairs: Power (P) / speed (n) p3320 / p3321 --> point 1 (P1 / n1) p3322 / p3323 --> point 2 (P2 / n2) p3324 / p3325 --> point 3 (P3 / n3) p3326 / p3327 --> point 4 (P4 / n4) p3328 / p3329 --> point 5 (P5 / n5)		
Dependency:	Refer to: r0041, p3321, p3322, p3323, p3324, p3325, p3326, p3327, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed. The energy saved is displayed in r0041.		

p3321[0...n]	Fluid flow machine speed point 1 / Fluid_mach n1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	0.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the speed (n) of point 1 as a [%].		

The characteristic comprises the following value pairs:

Power (P) / speed (n)

p3320 / p3321 → point 1 (P1 / n1)

p3322 / p3323 → point 2 (P2 / n2)

p3324 / p3325 → point 3 (P3 / n3)

p3326 / p3327 → point 4 (P4 / n4)

p3328 / p3329 → point 5 (P5 / n5)

Dependency:

Refer to: r0041, p3320, p3322, p3323, p3324, p3325, p3326, p3327, p3328, p3329

Note:

The reference value for power and speed is the rated power/rated speed.

The energy saved is displayed in r0041.

p3322[0...n]	Fluid flow machine power point 2 / Fluid_mach P2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	50.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required.		
	This parameter specifies the power (P) of point 2 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3323, p3324, p3325, p3326, p3327, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed.		
	The energy saved is displayed in r0041.		
p3323[0...n]	Fluid flow machine speed point 2 / Fluid_mach n2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	25.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required.		
	This parameter specifies the speed (n) of point 2 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3324, p3325, p3326, p3327, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed.		
	The energy saved is displayed in r0041.		
p3324[0...n]	Fluid flow machine power point 3 / Fluid_mach P3		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	77.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required.		
	This parameter specifies the power (P) of point 3 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3323, p3325, p3326, p3327, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed.		
	The energy saved is displayed in r0041.		

p3325[0...n]	Fluid flow machine speed point 3 / Fluid_mach n3		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	50.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the speed (n) of point 3 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3323, p3324, p3326, p3327, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed. The energy saved is displayed in r0041.		
p3326[0...n]	Fluid flow machine power point 4 / Fluid_mach P4		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	92.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the power (P) of point 4 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3323, p3324, p3325, p3327, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed. The energy saved is displayed in r0041.		
p3327[0...n]	Fluid flow machine speed point 4 / Fluid_mach n4		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	75.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the speed (n) of point 4 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3323, p3324, p3325, p3326, p3328, p3329		
Note:	The reference value for power and speed is the rated power/rated speed. The energy saved is displayed in r0041.		
p3328[0...n]	Fluid flow machine power point 5 / Fluid_mach P5		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	100.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the power (P) of point 5 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3323, p3324, p3325, p3326, p3327, p3329		
Note:	The reference value for power and speed is the rated power/rated speed. The energy saved is displayed in r0041.		

p3329[0...n]	Fluid flow machine speed point 5 / Fluid_mach n5		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00	100.00	100.00
Description:	For the energy-saving display of a fluid-flow machine, a typical flow characteristic $P = f(n)$ with 5 points along the characteristic is required. This parameter specifies the speed (n) of point 5 as a [%].		
Dependency:	Refer to: r0041, p3320, p3321, p3322, p3323, p3324, p3325, p3326, p3327, p3328		
Note:	The reference value for power and speed is the rated power/rated speed. The energy saved is displayed in r0041.		
p3330[0...n]	BI: 2/3 wire control command 1 / 2/3 wire cmd 1		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2272, 2273
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for command 1 for the two-wire control/three-wire control.		
Dependency:	Refer to: p0015, p3331, p3332, r3333, p3334		
Note:	The mode of operation of this binector input is dependent on the wire control set in p0015.		
p3331[0...n]	BI: 2/3 wire control command 2 / 2/3 wire cmd 2		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2272, 2273
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for command 2 for the two-wire control/three-wire control.		
Dependency:	Refer to: p0015, p3330, p3332, r3333, p3334		
Note:	The mode of operation of this binector input is dependent on the wire control set in p0015.		
p3332[0...n]	BI: 2/3 wire control command 3 / 2/3 wire cmd 3		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: CDS, p0170
	Unit group: -	Unit selection: -	Func. diagram: 2273
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for command 3 for the two-wire control/three-wire control.		
Dependency:	Refer to: p0015, p3330, p3331, r3333, p3334		
Note:	The mode of operation of this binector input is dependent on the wire control set in p0015.		
r3333.0...3	CO/BO: 2/3 wire control control word / 2/3 wire STW		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2272, 2273
	Min	Max	Factory setting
	-	-	-
Description:	Displays the control word for the two wire control/three wire control. The control signals are dependent on the wire control set in p0015 and the signal states at the digital inputs.		

2 Parameters

2.2 List of parameters

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON	Yes	No	-
	01	Reversing	Yes	No	-
	02	ON inverted	Yes	No	-
	03	Reversing inverted	Yes	No	-

Dependency: Refer to: p0015, p3330, p3331, p3332, p3334

p3334 2/3 wire control selection / 2/3 wire select

Access level: 4	Calculated: -	Data type: Integer16
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2272, 2273
Min	Max	Factory setting
0	4	0

Description: Sets the two wire control/three wire control.

Value:

- 0: No wire control
- 1: Two wire control clockwise/counterclockwise 1
- 2: Two wire control clockwise/counterclockwise 2
- 3: Three wire control enable clockwise/counterclockwise
- 4: Three wire control enable ON/reversing

Dependency: Refer to: p0015, p3330, p3331, p3332, r3333

Note: This value depends on the wire control set in p0015.

p3820[0...n] Friction characteristic value n0 / Friction n0

Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
Min	Max	Factory setting
0.00 [rpm]	210000.00 [rpm]	15.00 [rpm]

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

p3821[0...n] Friction characteristic value n1 / Friction n1

Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
Min	Max	Factory setting
0.00 [rpm]	210000.00 [rpm]	30.00 [rpm]

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

p3822[0...n] Friction characteristic value n2 / Friction n2

Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
Min	Max	Factory setting
0.00 [rpm]	210000.00 [rpm]	60.00 [rpm]

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

p3823[0...n]	Friction characteristic value n3 / Friction n3		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	120.00 [rpm]
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		
p3824[0...n]	Friction characteristic value n4 / Friction n4		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	150.00 [rpm]
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		
p3825[0...n]	Friction characteristic value n5 / Friction n5		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	300.00 [rpm]
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		
p3826[0...n]	Friction characteristic value n6 / Friction n6		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	600.00 [rpm]
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		
p3827[0...n]	Friction characteristic value n7 / Friction n7		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	0.00 [rpm]	210000.00 [rpm]	1200.00 [rpm]
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		

p3828[0...n]	Friction characteristic value n8 / Friction n8		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min 0.00 [rpm]	Max 210000.00 [rpm]	Factory setting 1500.00 [rpm]
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		
p3829[0...n]	Friction characteristic value n9 / Friction n9		
	Access level: 2	Calculated: p0340 = 1,3,5	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 3_1	Unit selection: p0505	Func. diagram: 7010
	Min 0.00 [rpm]	Max 210000.00 [rpm]	Factory setting 3000.00 [rpm]
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		
p3830[0...n]	Friction characteristic value M0 / Friction M0		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	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		
p3831[0...n]	Friction characteristic value M1 / Friction M1		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	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		
p3832[0...n]	Friction characteristic value M2 / Friction M2		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	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		

p3833[0...n]	Friction characteristic value M3 / Friction M3		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	-1000000.00 [Nm]	1000000.00 [Nm]	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		
p3834[0...n]	Friction characteristic value M4 / Friction M4		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	-1000000.00 [Nm]	1000000.00 [Nm]	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		
p3835[0...n]	Friction characteristic value M5 / Friction M5		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	-1000000.00 [Nm]	1000000.00 [Nm]	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		
p3836[0...n]	Friction characteristic value M6 / Friction M6		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	-1000000.00 [Nm]	1000000.00 [Nm]	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		
p3837[0...n]	Friction characteristic value M7 / Friction M7		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010
	Min	Max	Factory setting
	-1000000.00 [Nm]	1000000.00 [Nm]	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		

p3838[0...n]	Friction characteristic value M8 / Friction M8				
	Access level: 2	Calculated: -	Data type: FloatingPoint32		
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010		
	Min	Max	Factory setting		
	-1000000.00 [Nm]	1000000.00 [Nm]	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				
p3839[0...n]	Friction characteristic value M9 / Friction M9				
	Access level: 2	Calculated: -	Data type: FloatingPoint32		
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010		
	Min	Max	Factory setting		
	-1000000.00 [Nm]	1000000.00 [Nm]	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				
r3840.0...8	CO/BO: Friction characteristic status word / Friction ZSW				
	Access level: 2	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 7010		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and BICO output for the status word of the friction characteristic.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Friction characteristic OK	Yes	No	-
	01	Friction characteristic record activated	Yes	No	-
	02	Friction characteristic record completed	Yes	No	-
	03	Friction characteristic record aborted	Yes	No	-
	08	Friction characteristic positive direction	Yes	No	-
r3841	CO: Friction characteristic output / Frict outp				
	Access level: 2	Calculated: -	Data type: FloatingPoint32		
	Can be changed: -	Scaling: p2003	Dyn. index: -		
	Unit group: 7_1	Unit selection: p0505	Func. diagram: 7010		
	Min	Max	Factory setting		
	- [Nm]	- [Nm]	- [Nm]		
Description:	Display and connector output for the torque of the friction characteristic dependent on the speed.				
Dependency:	Refer to: p3842				
p3842	Friction characteristic activation / Frict act				
	Access level: 2	Calculated: -	Data type: Integer16		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 7010		
	Min	Max	Factory setting		
	0	1	0		
Description:	Setting to activate and de-activate the friction characteristic.				
Value:	0: Friction characteristic de-activated				
	1: Friction characteristic activated				
Dependency:	Refer to: r3841, p3845				

p3845	Friction characteristic record activation / Frict rec act		
	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 7010
	Min	Max	Factory setting
	0	3	0
Description:	Setting for the friction characteristic record. After the next power-on command, the friction characteristic is automatically recorded.		
Value:	0: Friction characteristic record de-activated 1: Friction char record activated for all directions 2: Friction char record activated for positive direction 3: Friction char record activated for negative direction		
Dependency:	When selecting the friction characteristic measurement, the drive data set changeover is suppressed. For linear drives (refer to r0108 bit 12) it is not permissible to carry out the friction characteristic measurement for mechanical systems that limit travel.		
Danger:			
Notice:	For drives with a mechanical system that limit the distance moved, it must be ensured that during recording, the friction characteristic is not reached. If this is not the case, then it is not permissible that the measurement is carried out.		
Note:	To permanently accept the determined settings they must be saved in a non-volatile fashion (p0971, p0977). When the friction characteristic record is active, it is not possible to save the parameters (p0971, p0977). When the friction characteristic record is active (p3845 > 0), it is not possible to change p3820 ... p3829, p3830 ... p3839 and p3842. When recording the friction characteristic, in addition to the friction, the motor losses are also determined (e.g. iron losses, eddy current losses and re-magnetizing 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 record ramp-up/ramp-down time / Frict rec t_RU/RD		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 7010
	Min	Max	Factory setting
	0.000 [s]	999999.000 [s]	10.000 [s]
Description:	Sets the ramp-up/ramp-down time of the ramp-up/ramp-down function generator to automatically record 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 record warm-up time / Frict rec t_warm		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 7010
	Min	Max	Factory setting
	0.000 [s]	3600.000 [s]	0.000 [s]
Description:	Sets the warm-up time. For an automatic trace (record) 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		

p3856[0...n]	Compound braking current / Compound I_brake				
	Access level: 3	Calculated: -	Data type: FloatingPoint32		
	Can be changed: U, T	Scaling: PERCENT	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0.00 [%]	250.00 [%]	0.00 [%]		
Description:	Compound braking current is used to define the amount of DC current that is produced on stopping the motor during U/f operation to further increase the DC brake function. Compound braking is a superimposition of the DC brake function with regenerative braking (net braking along the ramp) after OFF1 or OFF3. This permits braking with controlled motor frequency and minimum power input into the motor. Effective braking without using additional hardware components is obtained by optimizing the ramp down time and compound braking.				
Dependency:	The compound braking current is only activated if the DC link voltage exceeds the threshold value in r1282. Compound braking does not operate in the following cases: - DC braking activated (p1230, r1239). - motor is still not magnetized (e.g. for flying restart). - vector control parameterized (p1300 >= 20). - synchronous motor used (p0300 = 2xx).				
Notice:	Generally, increasing the braking current improves the braking effect when stopping the motor. However, if the value is set too high, then the drive can be tripped (shut down) as a result of overcurrent or ground fault. Recommendation: $p3856 < 100 \% \times (r0209 - r0331) / p0305 / 2$ Compound braking generates a current in the motor with a ripple manifesting the rotational frequency. The higher the braking current is set, the higher the resulting ripple, especially when the Vdc_max control is simultaneously active (refer to p1280).				
Note:	The parameter value is entered relative to the rated motor current (p0305). Compound braking is deactivated with p3856 = 0%.				

r3859.0	CO/BO: Compound braking/DC quantity control status word / Comp-br/DC_ctr ZSW				
	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 6797		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and connector output for the status word of the compound braking and DC quantity control.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Compound braking active	Yes	No	-
Dependency:	Refer to: p3856				

p3900	Completion of quick commissioning / Compl quick_comm				
	Access level: 1	Calculated: -	Data type: Integer16		
	Can be changed: C(1)	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	0	3	0		
Description:	Exits quick commissioning (p0010 = 1) with automatic calculation of all parameters of all existing drive data sets that depend on the entries made during quick commissioning. 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 p15 and p1500 are re-established and all of the dependent motor, open-loop and control-loop control parameters are calculated (corresponding to p0340 = 1).				

p3900 = 2 includes the restoration of the interconnections of PROFIBUS PZD telegram selection (p0922) and the interconnections via p15 and p1500 and the calculations corresponding to p0340 = 1.

p3900 = 3 only includes the calculations associated with the motor, open-loop and closed-loop control parameters corresponding to p0340 = 1.

Value:

- 0: No quick parameterization
- 1: Quick parameterization after parameter reset
- 2: Quick parameterization (only) for BICO and motor parameters
- 3: Quick parameterization for motor parameters (only)

Notice: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.

Note: When the calculations have been completed, p3900 and p0010 are automatically reset to a value of zero.
When calculating motor, open-loop and closed-loop control parameters (such as for p0340 = 1) parameters associated with a selected Siemens catalog motor are not overwritten.
If a catalog motor has not been selected (p0300), then the following parameters are reset with p3900 > 0 in order to restore the situation that applied when commissioning the drive for the first time:
induction motor: p0320, p0352, p0362 ... p0369, p0604, p0605
synchronous motor: p0352, p0604, p0605

r3925[0...n]		Identification final display / Ident final_disp		
		Access level: 3	Calculated: p0340 = 1	Data type: Unsigned32
		Can be changed: -	Scaling: -	Dyn. index: DDS, p0180
		Unit group: -	Unit selection: -	Func. diagram: -
		Min	Max	Factory setting
		-	-	-
Description:		Displays the commissioning steps that have been carried out.		
Bit field:		Bit	Signal name	1 signal
		00	Motor/control parameters calculated (p0340 = 1, p3900 > 0)	Yes
		02	Motor data identification carried out at standstill (p1910 = 1)	Yes
		03	Rotating measurement carried out (p1960 = 1, 2)	Yes
		08	Motor identification data have been automatically backed up	Yes
		11	Automatic parameterization as standard drive control	Yes
		12	Automatic parameterization as dynamic drive control	Yes
		15	Motor equivalent circuit diagram parameters changed	Yes
Note:		The individual bits are only set if the appropriate action has been initiated and successfully completed. When motor rating plate parameters are changed, the final display is reset.		

r3926[0...n]		Voltage generation alternating base voltage amplitude / U_gen altern base		
		Access level: 4	Calculated: -	Data type: FloatingPoint32
		Can be changed: -	Scaling: -	Dyn. index: MDS
		Unit group: -	Unit selection: -	Func. diagram: -
		Min	Max	Factory setting
		- [V]	- [V]	- [V]
Description:		Displays the base voltage for the alternating voltage in the context of motor data identification.		
		0: No alternating voltages. The function is de-activated.		
		<0: Automatic determination of the base voltage and wobulation / self-setting based on the converter and the connected motor.		
		Otherwise: Base voltage for alternating current generation in volts (wobulation active).		

r3927[0...n]	Motor data identification control word / MotID STW				
	Access level: 4	Calculated: p0340 = 1	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Successfully completed component of the last motor data identification carried out.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Stator inductance estimate no measurement	Yes	No	-
	02	Rotor time constant estimate no measurement	Yes	No	-
	03	Leakage inductance estimate no measurement	Yes	No	-
	05	Determine Tr and Lsig evaluation in the time range	Yes	No	-
	06	Activate vibration damping	Yes	No	-
	07	De-activate vibration detection	Yes	No	-
	11	De-activate pulse measurement Lq Ld	Yes	No	-
	12	De-activate rotor resistance Rr measurement	Yes	No	-
	14	De-activate valve interlocking time measurement	Yes	No	-
	15	Determine only stator resistance, valve voltage fault, dead time	Yes	No	-
	16	Short motor identification (lower quality)	Yes	No	-
	17	Measurement without control parameter calculation	Yes	No	-
	18	After motID direct transition into operation	Yes	No	-
	19	After MotID automatically save results	Yes	No	-
	20	Estimate cable resistance	Yes	No	-
	21	Calibrating the output voltage measurement	Yes	No	-
	22	Only identify circle	Yes	No	-
	23	Deactivate circle identification	Yes	No	-
	24	Circle identification with 0.90degrees	Yes	No	-
Dependency:	Refer to: r3925				
Note:	The parameter is a copy of p1909.				

r3928[0...n]	Rotating measurement configuration / Rot meas config				
	Access level: 4	Calculated: p0340 = 1	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Successfully completed component of the last rotating measurement carried out.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Saturation characteristic identification	Yes	No	-
	02	Moment of inertia identification	Yes	No	-
	03	Re-calculates the speed controller parameters	Yes	No	-
	04	Speed controller optimization (vibration test)	Yes	No	-
	05	q leakage inductance ident. (for current controller adaptation)	Yes	No	-
	11	Do not change the controller parameters during the measurement	Yes	No	-

12	Measurement shortened	Yes	No	-
13	After measurement direct transition into operation	Yes	No	-
14	Calculate speed actual value smoothing time	Yes	No	-

Dependency:

Refer to: r3925

Note:

The parameter is a copy of p1959.

r3929[0...n]**Motor data identification modulated voltage generation / MotID U_gen mod**

Access level: 4	Calculated: p0340 = 1	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: DDS, p0180
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description:

Configuration of voltage generation for the various MotID sections in the case of the most recent successful MotID.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Wobble U_generate to determine dead-time correction	Yes	No	-
01	Wobble U_generate to determine stator resistance	Yes	No	-
02	Wobble U_generation to determine rotor time constant	Yes	No	-
03	Wobble U_generation to determine leakage inductance	Yes	No	-
04	Wobble U_generation to determine dynamic leakage inductance	Yes	No	-
05	Wobble U_generation to determine magnetizing inductance	Yes	No	-
08	Alternating U_generate to determine dead-time correction	Yes	No	-
09	Alternating U_generate to determine stator resistance	Yes	No	-
10	Alternating U_generate to determine rotor time constant	Yes	No	-
11	Alternating U_generate to determine leakage inductance	Yes	No	-
12	Alternating U_generate to determine dyn. leakage inductance	Yes	No	-
13	Alternating U_generate to determine magnetizing inductance	Yes	No	-

p3950**Service parameter / Serv par**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: C, U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description:

For service personnel only.

p3981**Faults acknowledge drive object / Faults ackn DO**

Access level: 3	Calculated: -	Data type: Unsigned8
Can be changed: U, T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 8060
Min	Max	Factory setting
0	1	0


Description:

Setting to acknowledge all active faults of a drive object.

Notice:

Safety messages cannot be acknowledged using this parameter.

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			
Access level: 3		Calculated: -		Data type: Integer16			
Can be changed: U, T		Scaling: -		Dyn. index: -			
Unit group: -		Unit selection: -		Func. diagram: -			
Min		Max		Factory setting			
0		1		0			
Description:		Sets the mode to change over the master control / LOCAL mode.					
Value:		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.					
							

r3996[0...1]	Parameter write inhibit status / Par_write inhib st		
	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays whether writing to parameters is inhibited. r3996[0] = 0: Parameter write not inhibited. 0 < r3996[0] < 100: Parameter write inhibited. The value shows how the calculations are progressing.		
Index:	[0] = Progress calculations [1] = Cause		
Note:	Re index 1: Only for internal Siemens troubleshooting.		

p5271[0...n]	Online tuning configuration controller / Ot config ctrl		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: 5045
	Min	Max	Factory setting
	-	-	0000 0000 bin
Description:	Sets the configuration for the online tuning.		
Bit field:	Bit	Signal name	1 signal
	02	Load adaptation Kp	Yes
	06	Do not change Kp	Yes
Note:	Re bit 00: For significant differences between the motor and load moment of inertia, or for low dynamic performance of the controller, then the P controller becomes a PD controller in the position control loop. As a consequence, the dynamic performance of the position controller is increased. This function should only be set when the speed pre-control (bit 3 = 1) or the torque pre-control (bit 4 = 1) is active. Re bit 01: At low speeds, the controller gain factors are automatically reduced in order to avoid noise and oscillation at standstill. Re bit 02: The estimated load moment of inertia is taken into account for the speed controller gain (see p5273). Re bit 03: Activates the speed pre-control for the basic positioner (EPOS).		
		0 signal	FP
		No	-
		No	-

Re bit 04:

Activates the torque pre-control for the basic positioner (EPOS).

Re bit 05:

The maximum setpoint acceleration for the basic positioner (EPOS) is determined based on the estimated moment of inertia. This is realized by activating the bit once.

The prerequisite is that the drive pulses are inhibited, and the moment of inertia was previously determined.

Re bit 06:

The speed controller gain set in p1460 is not changed when calculating the controller data.

p5310[0...n]	Moment of inertia precontrol configuration / J_est config				
	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: DDS, p0180		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Configuration of the moment of inertia precontrol when the moment of inertia estimator is active.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Activating calculations	Yes	No	-
	01	Activating the moment of inertia precontrol	Yes	No	-
Dependency:	The function module "Moment of inertia estimator" (r0108.10) must be activated for the "Moment of inertia precontrol" function.				
Note:	Refer to: r5311, p5312, p5313, p5314, p5315				
	Possible bit combinations:				
	Bit 1, 0				
	= 0, 0 --> function not active				
	= 0, 1 --> cyclic calculation of the coefficients without moment of inertia precontrol (commissioning)				
	= 1, 0 --> moment of inertia precontrol activated (without cyclic calculation of the coefficients)				
	= 1, 1 --> moment of inertia precontrol activated (with cyclic calculation of the coefficients)				
	Re bit 00:				
	Calculation for the constant and linear coefficients of the moment of inertia precontrol is activated. The results are written to parameters (p5312, p5313, p5314, p5315).				
	Re bit 01:				
	The moment of inertia precontrol is activated.				
	The moment of inertia is calculated from the currently measured load torque and the saved coefficients (p5312, p5313, p5314, p5315).				

r5311[0...n]	Moment of inertia precontrol status word / J_estimate ZSW				
	Access level: 3		Calculated: -		Data type: Unsigned32
	Can be changed: -		Scaling: -		Dyn. index: DDS, p0180
	Unit group: -		Unit selection: -		Func. diagram: -
	Min		Max		Factory setting
	-		-		-
Description:	Display for the status word of the moment of inertia precontrol.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	New measuring points are available	Yes	No	-
	01	New parameters being calculated	Yes	No	-
	02	Moment of inertia precontrol active	Yes	No	-
	03	Calculation of the positive coefficients completed	Yes	No	-
	04	Calculation of the negative coefficients completed	Yes	No	-
	05	Results are being written to parameter	Yes	No	-
Dependency:	The function module "Moment of inertia estimator" (r0108.10) must be activated for the "Moment of inertia precontrol" function.				
	Refer to: p5310, p5312, p5313, p5314, p5315				

p5312[0...n]	Moment of inertia precontrol linear positive / J_est lin pos		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-340.28235E36 [s^2]	340.28235E36 [s^2]	0.000000 [s^2]
Description:	Setting of the linear coefficients for moment of inertia precontrol in the positive direction when the moment of inertia estimator is active. The estimated moment of inertia is obtained according to the following formula: Moment of inertia (J) = linear coefficient (p5312) * load torque + constant coefficient (p5313)		
Dependency:	The function module "Moment of inertia estimator" (r0108.10) must be activated for the "Moment of inertia precontrol" function. Refer to: p5310, r5311, p5313, p5314, p5315		
p5313[0...n]	Moment of inertia precontrol constant positive / J_est const pos		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 25_1	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	-340.28235E36 [kgm^2]	340.28235E36 [kgm^2]	0.000000 [kgm^2]
Description:	Setting of the constant coefficients for moment of inertia precontrol in the positive direction when the moment of inertia estimator is active. The estimated moment of inertia is obtained according to the following formula: Moment of inertia (J) = linear coefficient (p5312) * load torque + constant coefficient (p5313)		
Dependency:	The function module "Moment of inertia estimator" (r0108.10) must be activated for the "Moment of inertia precontrol" function. Refer to: p5310, r5311, p5312, p5314, p5315		
p5314[0...n]	Moment of inertia precontrol linear negative / J_est lin neg		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-340.28235E36 [s^2]	340.28235E36 [s^2]	0.000000 [s^2]
Description:	Setting of the linear coefficients for moment of inertia precontrol in the negative direction when the moment of inertia estimator is active. The estimated moment of inertia is obtained according to the following formula: Moment of inertia (J) = linear coefficient (p5314) * load torque + constant coefficient (p5315)		
Dependency:	The function module "Moment of inertia estimator" (r0108.10) must be activated for the "Moment of inertia precontrol" function. Refer to: p5310, r5311, p5312, p5313, p5315		
p5315[0...n]	Moment of inertia precontrol constant negative / J_est const neg		
	Access level: 3	Calculated: p0340 = 1	Data type: FloatingPoint32
	Can be changed: C(3), U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: 25_1	Unit selection: p0100	Func. diagram: -
	Min	Max	Factory setting
	-340.28235E36 [kgm^2]	340.28235E36 [kgm^2]	0.000000 [kgm^2]
Description:	Setting of the constant coefficients for moment of inertia precontrol in the negative direction when the moment of inertia estimator is active. The estimated moment of inertia is obtained according to the following formula: Moment of inertia (J) = linear coefficient (p5314) * load torque + constant coefficient (p5315)		

Dependency: The function module "Moment of inertia estimator" (r0108.10) must be activated for the "Moment of inertia precontrol" function.
Refer to: p5310, r5311, p5312, p5313, p5314

p5316[0...n]	Moment of inertia precontrol change time moment of inertia / J_prectrl t J		
	Access level: 3	Calculated: p0340 = 1,3,4	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: DDS, p0180
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	10.00 [ms]	5000.00 [ms]	500.00 [ms]
Description:	Sets the change time for the moment of inertia for the moment of inertia precontrol. Lower values mean that faster changes are possible. For a higher value, this estimated value is smoothed more significantly.		
Dependency:	Refer to: p1400, p1560, p1562		
r5397	Mot_temp_mod 3 ambient temperature image p0613 / AmbTmp image p0613		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	- [°C]	- [°C]	- [°C]
Description:	Displays the ambient temperature for motor temperature model 3. This value is used to calculate the utilization display (p0034). The parameter value is an image of p0613.		
Dependency:	Refer to: r0034		
Note:	Users cannot see and change parameter p0613 (only Siemens internal).		
r5398[0...n]	Mot_temp_mod 3 alarm threshold image p5390 / A thr image p5390		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	- [°C]	- [°C]	- [°C]
Description:	Displays the alarm threshold for monitoring the motor temperature for motor temperature model 3. This value is used to calculate the utilization display (p0034). The parameter value is an image of p5390.		
Dependency:	Refer to: F07011, A07012, A07014		
Note:	Users cannot see and change parameter p5390 (only Siemens internal).		
r5399[0...n]	Mot_temp_mod 3 fault threshold image p5391 / F thr image p5391		
	Access level: 2	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: MDS
	Unit group: 21_1	Unit selection: p0505	Func. diagram: 8017
	Min	Max	Factory setting
	- [°C]	- [°C]	- [°C]
Description:	Sets the fault threshold for monitoring the motor temperature for motor temperature model 3. Fault F07011 is output after the fault threshold is exceeded. The parameter value is an image of p5391.		
Dependency:	Refer to: F07011, A07012, A07014		
Note:	Users cannot see and change parameter p5391 (only Siemens internal).		

r5600	Pe energy-saving mode ID / Pe mode ID		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2381, 2382
	Min	Max	Factory setting
	0	255	-
Description:	Displays the PROFlenergy mode ID of the effective energy-saving mode.		
Value:	0: POWER OFF 2: Energy-saving mode 2 240: Operation 255: Ready		
Note:	Pe: PROFlenergy profiles		
p5602[0...1]	Pe energy-saving mode pause time minimal / Pe mod t_pause min		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2381
	Min	Max	Factory setting
	300000 [ms]	4294967295 [ms]	[0] 300000 [ms] [1] 480000 [ms]
Description:	Sets the minimum possible pause time for the energy-saving mode. The value is the sum of the following times: - Energy-saving mode transition time - Operating state transition time regular - Energy-saving mode, dwell time minimal		
Index:	[0] = Reserved [1] = Mode 2		
Note:	It is not permissible that the value is less than the sum of the "energy-saving mode transition time" and the "operating state transition time" (system properties). Pe: PROFlenergy profiles		
p5606[0...1]	Pe energy-saving mode time of maximum stay / Pe t_max_stay		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2381
	Min	Max	Factory setting
	0 [ms]	4294967295 [ms]	4294967295 [ms]
Description:	Sets the maximum dwell time for the energy-saving mode.		
Index:	[0] = Reserved [1] = Mode 2		
Note:	Pe: PROFlenergy profiles		

p5611		Pe energy-saving properties general / Pe properties gen			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2381, 2382		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:		Sets the general properties for energy-saving.			
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Inhibit PROFenergy control commands	Yes	No	-
	01	Drive initiates OFF1 when transitioning to energy-saving mode	Yes	No	-
	02	Trans to energy-saving mode from PROFIdrive state S3/S4 poss	Yes	No	-
Note:		Pe: PROFenergy profiles PROFIdrive state S4: operation			

p5612[0...1]		Pe energy-saving properties mode-dependent / Pe properties mod			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	[0] 0110 bin [1] 0000 bin		
Description:		Sets the mode-dependent properties for energy-saving.			
Index:		[0] = Reserved [1] = Mode 2			
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Reserved	Yes	No	-
Note:		Pe: PROFenergy profiles			

r5613.0...1		CO/BO: Pe energy-saving active/inactive / Pe save act/inact			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2382		
	Min	Max	Factory setting		
	-	-	-		
Description:		Display and binector output for the state display PROFenergy energy saving active or inactive.			
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Pe active	Yes	No	-
	01	Pe inactive	Yes	No	-
Note:		Bit 0 and bit 1 are inverse of one another. Pe: PROFenergy profiles			

p5614		BI: Pe set switching-on inhibited signal source / Pe sw on_inh s_src			
G120C_PN	Access level: 3	Calculated: -	Data type: U32 / Binary		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2382		
	Min	Max	Factory setting		
	-	-	0		
Description:		Sets the signal source to set in the PROFIdrive state S1 "switching-on inhibit".			
Dependency:		Refer to: r5613			
Note:		Pe: PROFenergy profiles			

r7758[0...19]	KHP Control Unit serial number / KHP CU ser_no				
	Access level: 3	Calculated: -	Data type: Unsigned8		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the actual serial number of the Control Unit. The individual characters of the serial number are displayed in the ASCII code in the indices. For the commissioning software, the ASCII characters are displayed uncoded.				
Dependency:	Refer to: p7765, p7766, p7767, p7768				
Notice:	An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual.				
Note:	KHP: Know-How Protection				

p7759[0...19]	KHP Control Unit reference serial number / KHP CU ref ser_no				
	Access level: 3	Calculated: -	Data type: Unsigned8		
	Can be changed: T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Sets the reference serial number for the Control Unit. Using this parameter, if a Control Unit and/or a memory card is replaced at the end customer, the OEM can again adapt the project to the modified hardware.				
Dependency:	Refer to: p7765, p7766, p7767, p7768				
Note:	KHP: Know-How Protection - The OEM may only change this parameter for the use case "Sending encrypted SINAMICS data". - SINAMICS only evaluates this parameter when powering up from the encrypted "Load into file system..." output or when powering up from the encrypted PS files. The evaluation is only made when know-how protection and memory card copy protection have been activated.				

r7760	Write protection/know-how protection status / Wr_prot/KHP stat				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the status for the write protection and know-how protection.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Write protection active	Yes	No	-
	01	Know-how protection active	Yes	No	-
	02	Know-how protection temporarily withdrawn	Yes	No	-
	03	Know-how protection cannot be deactivated	Yes	No	-
	04	Extended copy protection is active	Yes	No	-
	05	Basic copy protection is active	Yes	No	-
	06	Trace and measuring functions for diagnostic purposes active	Yes	No	-
Dependency:	Refer to: p7761, p7765, p7766, p7767, p7768				
Note:	KHP: Know-How Protection Re bit 00: Write protection can be activated/deactivated via p7761 on the Control Unit. Re bit 01: The know-how protection can be activated by entering a password (p7766 ... p7768). Re bit 02: If it has already been activated, know-how protection can be temporarily deactivated by entering the valid password in p7766. In this case, bit 1 = 0 and bit 2 = 1 offset.				

Re bit 03:

Know-how protection cannot be deactivated, as p7766 is not entered in the OEM exception list (only the factory setting is possible). This bit is only set if know-how protection is active (bit 1 = 1) and p7766 has not been entered in the OEM exception list.

Re bit 04:

When know-how protection has been activated, the contents of the memory card (parameter and DCC data) can be additionally protected against being used with other memory cards/Control Units. This bit is only set if know-how protection is active and p7765 bit 00 is set.

Re bit 05:

When know-how protection has been activated, the contents of the memory card (parameter and DCC data) can be additionally protected against being used with other memory cards. This bit is only set if know-how protection is active and in p7765 bit 01 is set and not bit 00.

Re bit 06:

When know-how protection is activated, the drive data can be traced using the device trace function. This bit is only set if know-how protection is active and in p7765.2 is set.

p7761	Write protection / Write protection		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Setting for activating/de-activating the write protection for adjustable parameters.		
Value:	0: Deactivate write protection 1: Activate write protection		
Dependency:	Refer to: r7760		
Note:	Parameters with the "WRITE_NO_LOCK" attributes are excluded from the write protection. A product-specific list of these parameters is also available in the corresponding List Manual.		

p7762	Write protection multi-master fieldbus system access behavior / Fieldbus acc_behav		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the behavior for write protection when accessing via multi-master fieldbus systems (e.g. CAN, BACnet).		
Value:	0: Write access independent of p7761 1: Write access dependent on p7761		
Dependency:	Refer to: r7760, p7761		

p7763	KHP OEM exception list number of indices for p7764 / KHP OEM qty p7764		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	500	1
Description:	Sets the number of parameters for the OEM exception list (p7764[0...n]). p7764[0...n], with n = p7763 - 1		
Dependency:	Refer to: p7764		
Note:	KHP: Know-How Protection Even if know-how protection is set, parameters in this list can be read and written to.		

p7764[0...n]	KHP OEM exception list / KHP OEM excep list			
	Access level: 3	Calculated: -	Data type: Unsigned16	
	Can be changed: U, T	Scaling: -	Dyn. index: p7763	
	Unit group: -	Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting	
	0	65535	[0] 7766 [1...499] 0	
Description:	OEM exception list (p7764[0...n] for setting parameters that should be excluded from know-how protection. p7764[0...n], with n = p7763 - 1			
Dependency:	The number of indices depends on p7763. Refer to: p7763			
Note:	KHP: Know-How Protection Even if know-how protection is set, parameters in this list can be read and written to.			

p7765	KHP configuration / KHP config				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: U, T	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Configuration settings for know-how protection. Re bit 00, 01: When KHP is activated, this means that the OEM can define whether the parameters and DCC data encrypted on the memory card should be protected before using on other memory cards/Control Units. Re bit 02: This means that the OEM can define whether it is possible or not to trace the drive data using the device trace function although KHP is activated.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Extended copy protection - linked to the memory card and CU	Yes	No	-
	01	Basic copy protection - linked to the memory card	Yes	No	-
	02	Permit trace and measuring functions for diagnostic purposes	Yes	No	-
Dependency:	Refer to: p7766, p7767, p7768				
Note:	KHP: Know-How Protection For copy protection, the serial numbers of the memory card and/or Control Unit are checked. The memory card copy protection and preventing data to be traced are only effective when the know-how protection has been activated. Re bit 00, 01: If both bits are inadvertently set to 1 (e.g. at the BOP), then the setting of bit 0 applies. There is no copy protection if both bits are set to 0.				

p7766[0...29]	KHP password input / KHP passw input		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Sets the password for know-how protection. Example of a password: 123aBc = 49 50 51 97 66 99 dec (ASCII characters) [0] = character 1 (e.g. 49 dec) [1] = character 2 (e.g. 50 dec) ... [5] = character 6 (e.g. 99 dec) [29] = 0 dec (completes the entry)		
Dependency:	Refer to: p7767, p7768		
Notice:	An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual. When using the STARTER commissioning software, the password should be entered using the associated dialogs. The following rules apply when entering the password: - Password entry must start with p7766[0]. - No gaps are permissible in the password. - Entering a password is completed when writing to p7766[29] (p7766[29] = 0 for passwords less than 30 characters).		
Note:	KHP: Know-How Protection When reading, p7766[0...29] = 42 dec (ASCII character = "***") is displayed. Parameters with the "KHP_WRITE_NO_LOCK" attribute are not involved in the know-how protection. Parameters with the "KHP_ACTIVE_READ" attribute can be read even when know-how protection is activated. A product-specific list of these parameters is also available in the corresponding List Manual.		
p7767[0...29]	KHP password new / KHP passw new		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Sets the new password for know-how protection.		
Dependency:	Refer to: p7766, p7768		
Note:	KHP: Know-How Protection When reading, p7767[0...29] = 42 dec (ASCII character = "***") is displayed.		
p7768[0...29]	KHP password confirmation / KHP passw confirm		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Confirms the new password for know-how protection.		
Dependency:	Refer to: p7766, p7767		
Note:	KHP: Know-How Protection When reading, p7768[0...29] = 42 dec (ASCII character = "***") is displayed.		

p7769[0...20]	KHP memory card reference serial number / KHP mem ref ser_no		
	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Sets the reference serial number for the memory card. Using this parameter, if a Control Unit and/or a memory card is replaced at the end customer, the OEM can again adapt the project to the modified hardware.		
Dependency:	Refer to: p7765, p7766, p7767, p7768		
Note:	KHP: Know-How Protection - The OEM may only change this parameter for the use case "Sending encrypted SINAMICS data". - SINAMICS only evaluates this parameter when powering up from the encrypted "Load into file system..." output or when powering up from the encrypted PS files. The evaluation is only made when know-how protection and memory card copy protection have been activated.		
p7775	NVRAM data backup/import/delete / NVRAM backup		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: C, U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	17	0
Description:	Setting to backup/import/delete NVRAM data. NVRAM data are non-volatile data in the device (e.g. fault buffer). For NVRAM data actions, the following data are excluded: - Crash diagnostics - CU operating hours counter - CU temperature - Safety logbook		
Value:	0: Inactive 1: NVRAM data backup to memory card 2: Import NVRAM data from the memory card 3: Delete NVRAM data in the device 10: Error when clearing 11: Error when backing up, memory card not available 12: Error when backing up, insufficient memory space 13: Error when backing up 14: Error when importing, memory card not available 15: Error when importing, checksum error 16: Error when importing, no NVRAM data available 17: Error when importing		
Notice:	Re value = 2, 3: These actions are only possible when pulses are inhibited.		
Note:	After the action has been successfully completed, the parameter is automatically set to zero. The actions importing and deleting NVRAM data immediately initiate a warm restart. If the procedure was not successfully completed, then an appropriate fault value is displayed (p7775 >= 10).		
r7843[0...20]	Memory card serial number / Mem_card ser.no		
	Access level: 1	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual serial number of the memory card. The individual characters of the serial number are displayed in the ASCII code in the indices.		

Notice: An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual.

Note: Example: displaying the serial number for a memory card:
 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
 r7843[20] = 0 dec
 Serial number = 111923E

r8540.0...15**BO: STW1 from BOP/IOP in the manual mode / STW1 OP**

Access level: 3	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description: For the manual mode: Display of STW1 (control word 1) entered at the BOP/ IOP.

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	Reserved	Yes	No	-
	04	Reserved	Yes	No	-
	05	Reserved	Yes	No	-
	06	Reserved	Yes	No	-
	07	Acknowledge fault	Yes	No	-
	08	Jog bit 0	Yes	No	3030
	09	Jog bit 1	Yes	No	3030
	10	Reserved	Yes	No	-
	11	Direction reversal (setpoint)	Yes	No	-
	12	Reserved	Yes	No	-
	13	Reserved	Yes	No	-
	14	Reserved	Yes	No	-
	15	Reserved	Yes	No	-

r8541**CO: Speed setpoint from BOP/IOP in the manual mode / N_set OP**

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: -	Scaling: p2000	Dyn. index: -
Unit group: 3_1	Unit selection: p0505	Func. diagram: -
Min	Max	Factory setting
- [rpm]	- [rpm]	- [rpm]

Description: For the manual mode: Display of the speed setpoint entered at the BOP/ IOP.

p8542[0...15]	BI: Active STW1 in the BOP/IOP manual mode / STW1 act OP		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	[0] 8540.0
			[1] 8540.1
			[2] 8540.2
			[3] 8540.3
			[4] 8540.4
			[5] 8540.5
			[6] 8540.6
			[7] 8540.7
			[8] 8540.8
			[9] 8540.9
			[10] 8540.10
			[11] 8540.11
			[12] 8540.12
			[13] 8540.13
			[14] 8540.14
			[15] 8540.15
Description:	For the manual mode: Setting of the signal sources for STW1 (control word 1).		
Index:	[0] = ON/OFF1 [1] = OC / OFF2 [2] = OC / OFF3 [3] = Operation enable [4] = Ramp-function generator enable [5] = Continue ramp-function generator [6] = Speed setpoint enable [7] = Acknowledge fault [8] = Jog bit 0 [9] = Jog bit 1 [10] = Master control by PLC [11] = Direction reversal (setpoint) [12] = Enable speed controller [13] = Motorized potentiometer raise [14] = Motorized potentiometer lower [15] = CDS bit 0		
p8543	CI: Active speed setpoint in the BOP/IOP manual mode / N_act act OP		
	Access level: 3	Calculated: -	Data type: U32 / FloatingPoint32
	Can be changed: T	Scaling: p2000	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	8541[0]
Description:	For the manual mode: Sets the signal source for the speed setpoint.		

p8558	BI: Select IOP manual mode / Sel IOP man mode		
	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min -	Max -	Factory setting 0
r8570[0...39]	Macro drive object / Macro DO		
	Access level: 1	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min -	Max -	Factory setting -
Description: Displays the macro file saved in the appropriate directory on the memory card/device memory.			
Dependency: Refer to: p0015			
Note: For a value = 9999999, the following applies: The read operation is still running.			
r8600 G120C_CAN	CAN device type / Device type		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min -	Max -	Factory setting -
Description: Displays all of the devices connected to the CAN bus after run-up. r8600 = 00000000 hex: No drive recognized. = 02010192 hex: 1 Vector drive			
Note: Corresponds to the CANopen object 1000 hex. For each detected drive, the device type is displayed in object 67FF hex.			
r8601 G120C_CAN	CAN error register / Error register		
	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min -	Max -	Factory setting -
Description: Displays the error register for CANopen. Bit 0: Generic error. 0 signal: No error present. 1 signal: Generic error present. Bit 1 ... 3: Not supported (always a 0 signal). Bit 4: Communications error. 0 signal: There is no message in the range 8700 ... 8799. 1 signal: There is at least one message (fault or alarm) in the range 8700 ... 8799. Bit 5 ... 6: Not supported (always a 0 signal). Bit 7: Fault outside the range 8700 ... 8799. 0 signal: There is no fault outside the range 8700 ... 8799. 1 signal: There is at least one fault outside the range 8700 ... 8799.			
Note: Corresponds to the CANopen object 1001 hex.			

p8602			
CAN SYNC object / SYNC object			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0080 hex
Description:	Sets the SYNC object parameter for the following CANopen objects: - 1005 hex: COB-ID		
Note:	SINAMICS operates as SYNC load. COB-ID: CAN object identification		

p8603			
CAN COB-ID Emergency Message / COB-ID EMCY Msg			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex
Description:	Sets the COB-ID for the emergency message (error telegram). It corresponds to the CANopen objects: - 1014 hex: COB-ID		
Note:	If, when downloading, the pre-set value 0 is downloaded, then the CANopen pre-set value 80 hex + Node-ID is automatically set. Online, the value 0 is rejected as, according to the CANopen Standard, COB-ID 0 is not permitted here. The changeover of the node ID using the hardware switch at the Control Unit or per software has no effect on the COB-ID EMCY. The saved value remains effective.		

p8604[0...1]			
CAN life guarding / Life guarding			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	65535	0
Description:	Sets the life 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 the life time [1] = Factor for the lifetime		
Dependency:	Refer to: p8606 Refer to: F08700		
Note:	For p8604[0] = 0 and/or p8604[1] = 0, the life guarding event service (monitoring the node guarding, fault F08700 with fault value = 2) is deactivated. The node guarding protocol is active without the life guarding event service, if the heartbeat protocol is deactivated (p8606 = 0).		

p8606	CAN Producer Heartbeat Time / Prod Heartb Time		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [ms]	65535 [ms]	0 [ms]
Description:	Sets the time [ms] to cyclically send heartbeat telegrams. The smallest cycle is 100 ms. For p8606 = 0, heartbeat telegrams are not sent.		
Dependency:	Refer to: p8604		
Note:	Corresponds to the CANopen object 1017 hex. Activating the heartbeat protocol automatically deactivates the node guarding.		
r8607[0...3]	CAN Identity Object / Identity object		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	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. Re index 3: The SINAMICS serial number comprises 60 bits. Of these bits, the following are displayed in this index: Bits 0 ... 19: Consecutive number Bits 20 ... 23: Production ID - 0 hex: Development - 1 hex: P1 unique number - 2 hex: P2 unique number - 3 hex: WA unique number - 9 hex: Pattern - F hex: All others Bits 24 ... 27: Month of manufacture (0 means January, B means December) Bits 28 ... 31: Year of manufacture (0 means 2002)		
p8608[0...1]	CAN Clear Bus Off Error / Clear bus off err		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	As a result of a Bus Off error, the CAN controller is set into the initialization state. Index 0: The CAN controller is manually started after resolving the cause of the error with p8608[0] = 1. Index 1: The automatic CAN bus start function is activated using p8608[1] = 1. At 2 second intervals, the CAN controller is automatically restarted until the cause of the error has been resolved and a CAN connection has been established.		
Value:	0: Inactive 1: Start CAN controller		

2 Parameters

2.2 List of parameters

Index: [0] = Manual controller start function
[1] = Activating the automatic controller start function

Note: Re index 0:
This parameter is automatically reset to 0 after start.

p8609[0...1]	CAN Error Behavior / Error behavior		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	2	1
Description:	Sets the behavior of the CAN node referred to the communications error or equipment fault.		
Value:	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]	CAN First Server SDO / First server SDO		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the identifier (client/server and server/client) of the SDO channel.		
Index:	[0] = COB-ID from the client to the server [1] = COB-ID from the server to the client		
Note:	Corresponds to the CANopen object 1200 hex. SDO: Service Data Object		
p8611[0...82]	CAN Pre-defined Error Field / Pre_def err field		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	FFFF 1000 hex	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 drive object ID 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) All drive objects are acknowledged by writing the value 0 to index 0. As soon as a fault has been acknowledged or an alarm cleared, then it is also cleared from the fault list.		

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
Note:	Corresponds to the CANopen object 1003 hex.

p8620	CAN Node-ID / Node ID		
G120C_CAN	Access level: 2	Calculated: -	Data type: Unsigned8
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	127	126
Description:	Display or setting of the CANopen Node ID. The Node ID can be set as follows: 1) Using the address switch on 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 address 0 is set using the address switch. --> the Node ID is set as standard to 126. --> A change only becomes effective after save and POWER ON.		
Dependency:	Refer to: r8621		
Notice:	For p0014 = 1, the following applies: After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0. For p0014 = 0, the following applies: Before a changed setting becomes permanently effective, a non-volatile RAM to ROM data save is required. To do this, set p0971 = 1 or p0014 = 1.		
Note:	Every node ID change only becomes effective after a POWER ON. The active node ID is displayed in r8621. The parameter is not influenced by setting the factory setting. It is only possible to independently set CANopen node ID and the PROFIBUS address using p0918 and p8620 (prerequisite: the address 0 is set for the address switch).		

r8621	CAN Node-ID active / Node ID active		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the active CANopen Node ID.		
Dependency:	Refer to: p8620		

p8622	CAN bit rate / Bit rate		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	7	6
Description:	<p>Setting the bit rate for the CAN bus.</p> <p>The appropriate bit timings are selected that are defined in p8623 in the associated sub-index.</p> <p>Example:</p> <p>Bit rate = 20 kbit/s --> p8622 = 6 --> associated bit timing is in p8623[6].</p>		
Value:	<p>0: 1 Mbit/s</p> <p>1: 800 kbit/s</p> <p>2: 500 kbit/s</p> <p>3: 250 kbit/s</p> <p>4: 125 kbit/s</p> <p>5: 50 kbit/s</p> <p>6: 20 kbit/s</p> <p>7: 10 kbit/s</p>		
Dependency:	Refer to: p8623		
Notice:	<p>For p0014 = 1, the following applies:</p> <p>After the value has been modified, no further parameter modifications can be made and the status is shown in r3996. Modifications can be made again when r3996 = 0.</p> <p>For p0014 = 0, the following applies:</p> <p>Before a changed setting becomes permanently effective, a non-volatile RAM to ROM data save is required. To do this, set p0971 = 1 or p0014 = 1.</p>		
Note:	The parameter is not influenced by setting the factory setting.		
p8623[0...7]	CAN Bit Timing selection / Bit timing select		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	000F 7FFF hex	<p>[0] 1405 hex</p> <p>[1] 1605 hex</p> <p>[2] 1C05 hex</p> <p>[3] 1C0B hex</p> <p>[4] 1C17 hex</p> <p>[5] 1C3B hex</p> <p>[6] 0002 1C15 hex</p> <p>[7] 0004 1C2B hex</p>
Description:	<p>Sets the bit timing for the C_CAN controller to the associated and selected bit rate (p8622).</p> <p>Bits are distributed to the following parameters of the C_CAN controller in p8623[0...7]:</p> <p>Bit 0 ... 5: BRP (Baud Rate Prescaler)</p> <p>Bit 6 ... 7: SJW (Synchronization Jump Width)</p> <p>Bit 8 ... 11: TSEG1 (Time Segment 1, before the sampling point)</p> <p>Bit 12 ... 14: TSEG2 (Time Segment 2, after the sampling point)</p> <p>Bit 15: Reserved</p> <p>Bit 16 ... 19: BRPE (Baud Rate Prescaler Extension)</p> <p>Bit 20 ... 31: Reserved</p> <p>Example:</p> <p>Bit rate = 20 kbit/s --> p8622 = 6 --> associated bit timing is in p8623[6] --> 0001 2FB6</p>		
Recommendation:	Use the factory setting when setting the bit timing.		
Index:	<p>[0] = 1 Mbit/s</p> <p>[1] = 800 kbit/s</p> <p>[2] = 500 kbit/s</p>		

[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: The parameter is not influenced by setting the factory setting.

p8630[0...2] CAN virtual objects / Virtual objects			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	65535	0
Description: Activating access to parameters via manufacturer-specific CANopen objects and setting for the subindex 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: 0: Not possible to access virtual CANopen objects 1: Possible to access virtual CANopen objects 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 number [1] = Sub-index range [2] = Parameter range			

p8641 CAN Abort Connection Option Code / Abort con opt code			
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	3	3
Description: Sets the drive behavior if a CAN communication error occurs.			
Value: 0: No response 1: OFF1 2: OFF2 3: OFF3			
Dependency: Refer to: F08700			

r8680[0...36] CAN Diagnosis Hardware / Diagnostics HW			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	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.			

2.2 List of parameters

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
Note:	A description of the individual registers of the C_CAN controller can be taken from "C_CAN User's Manual".

p8684	CAN NMT state after booting / NMT state aft boot		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	4	127	127
Description:	Sets the CANopen NMT state that is effective after booting.		
Value:	4: Stopped 5: Operational 127: Pre-operational		
Dependency:	Refer to: p8685		
Note:	Bootling in the NMT state pre-operational corresponds to the CANopen standard		

p8685	CAN NMT states / NMT states		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	129	127
Description:	Sets and displays the CANopen NMT state.		
Value:	0: Initialization 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.		

p8699	CAN: RPDO monitoring time / RPDO t_monit		
G120C_CAN	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0 [ms]	65535000 [ms]	0 [ms]
Description:	Sets the monitoring time for the process data received via the CAN bus. A value that is not a multiple integer of the CANopen sampling time is rounded-off. If no process data is received within this time, then fault F08702 is output.		
Dependency:	Refer to: F08702		
Note:	Value = 0: Monitoring is de-activated. p2048: CANopen sampling time		

p8700[0...1]	CAN Receive PDO 1 / Receive PDO 1		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1400 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8701[0...1]	CAN Receive PDO 2 / Receive PDO 2		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1401 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8702[0...1]	CAN Receive PDO 3 / Receive PDO 3		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1402 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		

p8703[0...1]	CAN Receive PDO 4 / Receive PDO 4		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1403 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8704[0...1]	CAN Receive PDO 5 / Receive PDO 5		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1404 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		
p8705[0...1]	CAN Receive PDO 6 / Receive PDO 6		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1405 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		

p8706[0...1]			
CAN Receive PDO 7 / Receive PDO 7			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1406 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		

p8707[0...1]			
CAN Receive PDO 8 / Receive PDO 8			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204
	Min	Max	Factory setting
	0000 hex	8000 06DF hex	[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.		
Note:	Corresponds to the CANopen object 1407 hex. Transmission types 0, 1, FE and FF can be set. PDO: Process Data Object		

p8710[0...3]			
CAN Receive Mapping for RPDO 1 / Mapping RPDO 1			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. Dummy mapping not supported. The parameter can only be written online when the associated COB ID in p870x is set as invalid.		

p8711[0...3]	CAN Receive Mapping for RPDO 2 / Mapping RPDO 2		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. Dummy mapping not supported. The parameter can only be written online when the associated COB ID in p870x is set as invalid.		
p8712[0...3]	CAN Receive Mapping for RPDO 3 / Mapping RPDO 3		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. Dummy mapping not supported. The parameter can only be written online when the associated COB ID in p870x is set as invalid.		
p8713[0...3]	CAN Receive Mapping for RPDO 4 / Mapping RPDO 4		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. Dummy mapping not supported. The parameter can only be written online when the associated COB ID in p870x is set as invalid.		
p8714[0...3]	CAN Receive Mapping for RPDO 5 / Mapping RPDO 5		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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.

Dummy mapping not supported.

The parameter can only be written online when the associated COB ID in p870x is set as invalid.

p8715[0...3]**CAN Receive Mapping for RPDO 6 / Mapping RPDO 6**

G120C_CAN

Access level: 3**Calculated:** -**Data type:** Unsigned32**Can be changed:** C(3), T**Scaling:** -**Dyn. index:** -**Unit group:** -**Unit selection:** -**Func. diagram:** 9204**Min****Max****Factory setting**

0000 hex

FFFF FFFF hex

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.

Dummy mapping not supported.

The parameter can only be written online when the associated COB ID in p870x is set as invalid.

p8716[0...3]**CAN Receive Mapping for RPDO 7 / Mapping RPDO 7**

G120C_CAN

Access level: 3**Calculated:** -**Data type:** Unsigned32**Can be changed:** C(3), T**Scaling:** -**Dyn. index:** -**Unit group:** -**Unit selection:** -**Func. diagram:** 9204**Min****Max****Factory setting**

0000 hex

FFFF FFFF hex

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.

Dummy mapping not supported.

The parameter can only be written online when the associated COB ID in p870x is set as invalid.

p8717[0...3]**CAN Receive Mapping for RPDO 8 / Mapping RPDO 8**

G120C_CAN

Access level: 3**Calculated:** -**Data type:** Unsigned32**Can be changed:** C(3), T**Scaling:** -**Dyn. index:** -**Unit group:** -**Unit selection:** -**Func. diagram:** 9204**Min****Max****Factory setting**

0000 hex

FFFF FFFF hex

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.

Dummy mapping not supported.

The parameter can only be written online when the associated COB ID in p870x is set as invalid.

p8720[0...4]	CAN Transmit PDO 1 / Transmit PDO 1		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time is rounded-off.		
Note:	Corresponds to the CANopen object 1800 hex. Transmission types 0, 1 ... F0, FE and FF can be set. p2048: CANopen sampling time PDO: Process Data Object		

p8721[0...4]	CAN Transmit PDO 2 / Transmit PDO 2		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time is rounded-off.		
Note:	Corresponds to the CANopen object 1801 hex. Transmission types 0, 1 ... F0, FE and FF can be set. p2048: CANopen sampling time PDO: Process Data Object		

p8722[0...4]		CAN Transmit PDO 3 / Transmit PDO 3	
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time is rounded-off.		
Note:	Corresponds to the CANopen object 1802 hex. Transmission types 0, 1 ... F0, FE and FF can be set. p2048: CANopen sampling time PDO: Process Data Object		

p8723[0...4]		CAN Transmit PDO 4 / Transmit PDO 4	
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time is rounded-off.		
Note:	Corresponds to the CANopen object 1803 hex. Transmission types 0, 1 ... F0, FE and FF can be set. p2048: CANopen sampling time PDO: Process Data Object		

p8724[0...4]	CAN Transmit PDO 5 / Transmit PDO 5		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time is rounded-off.		
Note:	Corresponds to the CANopen object 1804 hex. Transmission types 0, 1 ... F0, FE and FF can be set. p2048: CANopen sampling time PDO: Process Data Object		
p8725[0...4]	CAN Transmit PDO 6 / Transmit PDO 6		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time 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. p8848: CANopen sampling time PDO: Process Data Object		

p8726[0...4]	CAN Transmit PDO 7 / Transmit PDO 7		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time 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. p8848: CANopen sampling time PDO: Process Data Object		
p8727[0...4]	CAN Transmit PDO 8 / Transmit PDO 8		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	Min	Max	Factory setting
	0000 hex	C000 06DF hex	[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.		
Notice:	For inhibit time and event timer, the following apply: A value that is not a multiple integer of the CANopen sampling time is rounded-off.		
Note:	Corresponds to the CANopen object 1807 hex. Transmission types 0, 1 ... F0, FE and FF can be set. p2048: CANopen sampling time PDO: Process Data Object		

p8730[0...3]	CAN Transmit Mapping for TPDO 1 / Mapping TPDO 1		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. The parameter can only be written online when the associated COB ID in p872x is set as invalid.		
p8731[0...3]	CAN Transmit Mapping for TPDO 2 / Mapping TPDO 2		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. The parameter can only be written online when the associated COB ID in p872x is set as invalid.		
p8732[0...3]	CAN Transmit Mapping for TPDO 3 / Mapping TPDO 3		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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. The parameter can only be written online when the associated COB ID in p872x is set as invalid.		
p8733[0...3]	CAN Transmit Mapping for TPDO 4 / Mapping TPDO 4		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208, 9210
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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.
The parameter can only be written online when the associated COB ID in p872x is set as invalid.

p8734[0...3] CAN Transmit Mapping for TPDO 5 / Mapping TPDO 5			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	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. The parameter can only be written online when the associated COB ID in p872x is set as invalid.		

p8735[0...3] CAN Transmit Mapping for TPDO 6 / Mapping TPDO 6			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	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. The parameter can only be written online when the associated COB ID in p872x is set as invalid.		

p8736[0...3] CAN Transmit Mapping for TPDO 7 / Mapping TPDO 7			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	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. The parameter can only be written online when the associated COB ID in p872x is set as invalid.		

p8737[0...3] CAN Transmit Mapping for TPDO 8 / Mapping TPDO 8			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9208
	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 Parameters

2.2 List of parameters

[2] = Mapped object 3

[3] = Mapped object 4

Note:

Corresponds to the CANopen object 1A07 hex.

The parameter can only be written online when the associated COB ID in p872x is set as invalid.

p8744	CAN PDO mapping configuration / PDO Mapping config		
G120C_CAN	Access level: 2	Calculated: -	Data type: Integer16
	Can be changed: C, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9204, 9206, 9208, 9210
	Min	Max	Factory setting
	1	2	2
Description:	Selector switch for the PDO mapping.		
Value:	1: Predefined Connection Set 2: Free PDO Mapping		
r8745[0...15]	CO: CAN free PZD receive objects 16 bit / Free PZD recv 16		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Access to free PZD receive objects 16 bit using the SDO transfer. An index can only be used, if the corresponding object has not been mapped in a PDO.		
Index:	[0] = PZD object 0 [1] = PZD object 1 [2] = PZD object 2 [3] = PZD object 3 [4] = PZD object 4 [5] = PZD object 5 [6] = PZD object 6 [7] = PZD object 7 [8] = PZD object 8 [9] = PZD object 9 [10] = PZD object 10 [11] = PZD object 11 [12] = PZD object 12 [13] = PZD object 13 [14] = PZD object 14 [15] = PZD object 15		
Note:	Index 0 corresponds to the CANopen object 5800 hex Index 1 corresponds to the CANopen object 5801 hex Index 2 corresponds to the CANopen object 5802 hex Index 3 corresponds to the CANopen object 5803 hex Index 4 corresponds to the CANopen object 5804 hex Index 5 corresponds to the CANopen object 5805 hex Index 6 corresponds to the CANopen object 5806 hex Index 7 corresponds to the CANopen object 5807 hex Index 8 corresponds to the CANopen object 5808 hex Index 9 corresponds to the CANopen object 5809 hex Index 10 corresponds to the CANopen object 580A hex Index 11 corresponds to the CANopen object 580B hex Index 12 corresponds to the CANopen object 580C hex Index 13 corresponds to the CANopen object 580D hex Index 14 corresponds to the CANopen object 580E hex Index 15 corresponds to the CANopen object 580F hex		

p8746[0...15]	CI: CAN free PZD send objects 16 bit / Free PZD send 16		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Integer16
	Can be changed: U, T	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for free PZD send objects 16 bit for SDO transfer. An index can only be used, if the corresponding object has not been mapped in a PDO.		
Index:	[0] = PZD object 0 [1] = PZD object 1 [2] = PZD object 2 [3] = PZD object 3 [4] = PZD object 4 [5] = PZD object 5 [6] = PZD object 6 [7] = PZD object 7 [8] = PZD object 8 [9] = PZD object 9 [10] = PZD object 10 [11] = PZD object 11 [12] = PZD object 12 [13] = PZD object 13 [14] = PZD object 14 [15] = PZD object 15		
Note:	Index 0 corresponds to the CANopen object 5810 hex Index 1 corresponds to the CANopen object 5811 hex Index 2 corresponds to the CANopen object 5812 hex Index 3 corresponds to the CANopen object 5813 hex Index 4 corresponds to the CANopen object 5814 hex Index 5 corresponds to the CANopen object 5815 hex Index 6 corresponds to the CANopen object 5816 hex Index 7 corresponds to the CANopen object 5817 hex Index 8 corresponds to the CANopen object 5818 hex Index 9 corresponds to the CANopen object 5819 hex Index 10 corresponds to the CANopen object 581A hex Index 11 corresponds to the CANopen object 581B hex Index 12 corresponds to the CANopen object 581C hex Index 13 corresponds to the CANopen object 581D hex Index 14 corresponds to the CANopen object 581E hex Index 15 corresponds to the CANopen object 581F hex		
r8747[0...7]	CO: CAN free PZD receive objects 32 bit / Free PZD recv 32		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer32
	Can be changed: -	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Access to free PZD receive objects 32 bit using the SDO transfer. An index can only be used, if the corresponding object has not been mapped in a PDO.		
Index:	[0] = PZD object 0 [1] = PZD object 1 [2] = PZD object 2 [3] = PZD object 3 [4] = PZD object 4 [5] = PZD object 5 [6] = PZD object 6 [7] = PZD object 7		

2 Parameters

2.2 List of parameters

Note: Index 0 corresponds to the CANopen object 5820 hex
Index 1 corresponds to the CANopen object 5821 hex
Index 2 corresponds to the CANopen object 5822 hex
Index 3 corresponds to the CANopen object 5823 hex
Index 4 corresponds to the CANopen object 5824 hex
Index 5 corresponds to the CANopen object 5825 hex
Index 6 corresponds to the CANopen object 5826 hex
Index 7 corresponds to the CANopen object 5827 hex

p8748[0...7]	CI: CAN free PZD send objects 32 bit / Free PZD send 32		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Integer32
	Can be changed: U, T	Scaling: 4000H	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	0

Description: Sets the signal source for free PZD send objects 32 bit for SDO transfer.
An index can only be used, if the corresponding object has not been mapped in a PDO.

Index: [0] = PZD object 0
[1] = PZD object 1
[2] = PZD object 2
[3] = PZD object 3
[4] = PZD object 4
[5] = PZD object 5
[6] = PZD object 6
[7] = PZD object 7

Note: Index 0 corresponds to the CANopen object 5830 hex
Index 1 corresponds to the CANopen object 5831 hex
Index 2 corresponds to the CANopen object 5832 hex
Index 3 corresponds to the CANopen object 5833 hex
Index 4 corresponds to the CANopen object 5834 hex
Index 5 corresponds to the CANopen object 5835 hex
Index 6 corresponds to the CANopen object 5836 hex
Index 7 corresponds to the CANopen object 5837 hex

r8750[0...15]	CAN mapped 16-bit receive objects / RPDO 16 mapped		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the mapped 16-bit receive CANopen objects in the process data buffer.
Example:
If, e.g. the control word is mapped in an RPDO, then r8750 indicates the position of the control word 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...15] = Reserved

r8751[0...15]			
CAN mapped 16-bit transmit objects / TPDO 16 mapped			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
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...15] = Reserved		
Dependency:	Refer to: r8750		

r8760[0...14]			
CAN mapped 32-bit receive objects / RPDO 32 mapped			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the mapped 32-bit receive 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...14] = Reserved		

r8761[0...14]			
CAN mapped 32-bit transmit objects / TPDO 32 mapped			
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	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		

2 Parameters

2.2 List of parameters

[9] = PZD 10 + 11
[10] = PZD 11 + 12
[11...14] = Reserved

r8762	CO: CAN operating mode display / Op mode display		
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the currently effective CANopen operating mode.
To send the CANopen object 0x6061 mapped in a TPDO, this parameter can be correspondingly interconnected in the PZD interface.

r8784	CO: CAN status word / Status word		
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9226
	Min	Max	Factory setting
	-	-	-

Description: Display and connector output for the CANopen status word

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Rdy for switch on	Yes	No	-
	01	Ready	Yes	No	-
	02	Operation enabled	Yes	No	-
	03	Fault present	Yes	No	-
	04	No coasting active	Yes	No	-
	05	No Quick Stop active	Yes	No	-
	06	Switching on inhibited active	Yes	No	-
	07	Alarm present	Yes	No	-
	08	Can be freely interconnected (BI: p8785)	Yes	No	-
	09	Control request	Yes	No	-
	10	Target reached	Yes	No	-
	11	Torque limit reached	Yes	No	-
	12	Velocity equal to zero	Yes	No	-
	14	Can be freely interconnected (BI: p8786)	Yes	No	-
	15	Can be freely interconnected (BI: p8787)	Yes	No	-

Note: Corresponds to CANopen object 6041 hex.
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: CAN status word bit 8 / Status word bit 8		
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9226
	Min	Max	Factory setting
	-	-	0

Description: Sets the signal source for bit 8 of the CANopen status word.

Dependency: Refer to: r8784

p8786			
BI: CAN status word bit 14 / Status word bit 14			
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9226
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for bit 14 of the CANopen status word.		
Dependency:	Refer to: r8784		
<hr/>			
p8787			
BI: CAN status word bit 15 / Status word bit 15			
G120C_CAN	Access level: 3	Calculated: -	Data type: U32 / Binary
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 9226
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for bit 15 of the CANopen status word.		
Dependency:	Refer to: r8784		
<hr/>			
p8790			
CAN control word - auto interconnection / STW interc auto			
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the automatic BICO interconnection of the CANopen control word.		
Value:	0: No interconn 1: Interconnection		
Dependency:	Refer to: r2050, r2090, r2091, r2092, r2093, r8750, r8795		
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 = r209x.0 BI: p0844.0 = r209x.1 BI: p0848.0 = r209x.2 BI: p0852.0 = r209x.3 BI: p2103.0 = r209x.7 The write access is rejected if a CANopen control word is not mapped at one of these locations. This also causes the project download of the commissioning software to be canceled.		
<hr/>			
p8791			
CAN stop option code / Stop opt_code			
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: C(3), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-1	3	-1
Description:	Setting for the CANopen control word bit 8 "Stop" (CANopen STW.8).		
Value:	-1: No interconn 1: Interconnection CANopen STW.8 with p1142 3: Interconnection CANopen STW.8 with p1140		
Dependency:	Refer to: r2050, r8750, r8795		
Note:	Corresponds to CANopen object 605D hex. The BICO interconnection is established, if the CANopen control word is mapped at one of the locations x = 0 ... 3 in the receive process data buffer.		

r8792[0]	CO: CAN velocity mode I16 setpoint / Vel mod I16 set				
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16		
	Can be changed: -	Scaling: 4000H	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and connector output to interconnect standardized I16 setpoint CANopen objects of the velocity mode for SDO transfer. An index can only be used, if the corresponding object has not been mapped in a PDO.				
Index:	[0] = VL Target Velocity				
Note:	Re index 0: Corresponds to the CANopen object 6042 hex. The displayed parameter value is scaled via the reference speed p2000: 4000 hex corresponds to p2000				
r8795.0...15	CO/BO: CAN control word / Control word				
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
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 Quick Stop	Yes	No	-
	03	Operation enable	Yes	No	-
	04	Ramp-function generator enable	Yes	No	-
	05	Continue ramp-function generator	Yes	No (freeze)	-
	06	Speed setpoint enable	Yes	No	-
	07	Acknowledge fault	Yes	No	-
	08	Stop	Yes	No	-
	11	Freely interconn	Yes	No	-
	12	Freely interconn	Yes	No	-
	13	Freely interconn	Yes	No	-
	14	Freely interconn	Yes	No	-
	15	Freely interconn	Yes	No	-
Dependency:	Refer to: p8790				
Note:	Corresponds to the CANopen object 6040 hex.				
r8796[0]	CO: CAN profile velocity mode I32 setpoints / Pr vel mo I32 set				
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer32		
	Can be changed: -	Scaling: 4000H	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Display and connector output to interconnect standardized I32 setpoint CANopen objects of the profile velocity mode for SDO transfer. An index can only be used, if the corresponding object has not been mapped in a PDO.				
Index:	[0] = Target velocity				
Note:	Re index 0: Corresponds to the CANopen object 60FF hex. The displayed parameter value is scaled via the reference speed p2000: 4000 0000 hex corresponds to p2000				

r8797[0]				
CO: CAN profile torque mode I16 setpoints / Pr Tq mod I16 set				
G120C_CAN	Access level: 3	Calculated: -	Data type: Integer16	
	Can be changed: -	Scaling: 4000H	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Display and connector output to interconnect standardized I16 setpoint CANopen objects of the profile torque mode for SDO transfer. An index can only be used, if the corresponding object has not been mapped in a PDO.			
Index:	[0] = Target torque			
Note:	Re index 0: Corresponds to the CANopen object 6071 hex. The displayed parameter value is scaled via the reference torque p2003: 4000 hex corresponds to p2003			
<hr/>				
p8798[0...1]				
CAN speed conversion factor / n_conv_factor				
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32	
	Can be changed: T	Scaling: -	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting	
	1	4294967295	1	
Description:	The factor converts the required velocity units into the internal velocity units (U/s). With the factory 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			
<hr/>				
p8805				
Identification and maintenance 4 configuration / I&M 4 config				
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16	
	Can be changed: U, T	Scaling: -	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting	
	0	1	0	
Description:	Sets the configuration for the content of identification and maintenance 4 (I&M 4, p8809).			
Value:	0: Standard value for I&M 4 (p8809) 1: User value for I&M 4 (p8809)			
Dependency:	For p8805 = 0, if the user writes at least one value in p8809[0...53], then p8805 is automatically set to = 1. When p8805 is reset = 0, then the content of the factory setting is set in p8809.			
Note:	Re p8805 = 0: PROFINET I&M 4 (p8809) contains the information for the SI change tracking. Re p8805 = 1: PROFINET I&M 4 (p8809) contains the values written by the user.			
<hr/>				
p8806[0...53]				
Identification and Maintenance 1 / I&M 1				
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8	
	Can be changed: U, T	Scaling: -	Dyn. index: -	
	Unit group: -	Unit selection: -	Func. diagram: -	
	Min	Max	Factory setting	
	-	-	-	
Description:	Parameters for the PROFINET data set "Identification and Maintenance 1" (I&M 1). This information is known as "System identifier" and "Location identifier".			

2 Parameters

2.2 List of parameters

Dependency: Refer to: p8807, p8808
Notice: Only characters belonging to the standard ASCII character set may be used (32 dec to 126 dec).
Note: An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual.
Re p8806[0...31]:
System identifier.
Re p8806[32...53]:
Location identifier.

p8807[0...15] Identification and Maintenance 2 / I&M 2			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	
Description: Parameters for the PROFINET data set "Identification and Maintenance 2" (I&M 2). This information is known as "Installation date".			
Dependency: Refer to: p8806, p8808			
Note: An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual. Re p8807[0...15]: Dates of installation or first commissioning of the device with the following format options (ASCII): YYYY-MM-DD or YYYY-MM-DD hh:mm - YYYY: year - MM: month 01 ... 12 - DD: day 01 ... 31 - hh: hours 00 ... 23 - mm: minutes 00 ... 59 Separators must be placed between the individual data, i.e. a hyphen '-', space ' ' and colon ':'.			

p8808[0...53] Identification and Maintenance 3 / I&M 3			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	
Description: Parameters for the PROFINET data set "Identification and Maintenance 3" (I&M 3). This information is known as "Supplementary information".			
Dependency: Refer to: p8806, p8807			
Notice: Only characters belonging to the standard ASCII character set may be used (32 dec to 126 dec).			
Note: An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual. Re p8808[0...53]: Any supplementary information and comments (ASCII).			

p8809[0...53] Identification and Maintenance 4 / I&M 4			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 bin	1111 1111 bin	0000 bin
Description: Parameters for the PROFINET data set "Identification and Maintenance 4" (I&M 4). This information is known as "Signature".			

Dependency:	This parameter is preassigned as standard (see note). After writing information to p8809, p8805 is automatically set to = 1. Refer to: p8805
Note:	For p8805 = 0 (factory setting) the following applies: Parameter p8809 contains the information described below. Re p8809[0...3]: Contains the value from r9781[0] "SI change tracking checksum functional". Re p8809[4...7]: Contains the value from r9782[0] "SI change tracking time stamp checksum functional". Re p8809[8...53]: Reserved.

r8854	PROFINET state / PN state		
G120C_PN	Access level: 4	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	State display for PROFINET.		
Value:	0: No initialization 1: Fatal fault 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]	PROFINET read diagnostics channel / PN diag_chan read		
G120C_PN	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the PROFINET diagnostics data.		
Note:	Only for internal Siemens diagnostics.		

r8859[0...7]	PROFINET identification data / PN ident data		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the PROFINET identification data		
Index:	[0] = Version interface structure [1] = Version interface driver [2] = Company (Siemens = 42) [3] = CB type [4] = Firmware version [5] = Firmware date (year) [6] = Firmware date (day/month) [7] = Firmware patch/hot fix		
Note:	Example: r8859[0] = 100 --> version of the interface structure V1.00 r8859[1] = 111 --> version of the interface driver V1.11 r8859[2] = 42 --> SIEMENS		

2 Parameters

2.2 List of parameters

r8859[3] = 0
r8859[4] = 1300 --> first part, firmware version V13.00 (second part, see index 7)
r8859[5] = 2011 --> year 2011
r8859[6] = 2306 --> 23rd June
r8859[7] = 1700 --> second part, firmware version (complete version: V13.00.17.00)

r8909	PN device ID / PN device ID		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-

Description: Displays the PROFINET Device ID.
Every SINAMICS device type has its own PROFINET Device ID and its own PROFINET GSD.

Note: List of the SINAMICS Device IDs:
0501 hex: S120/S150
0504 hex: G130/G150
050A hex: DC MASTER
050C hex: MV
050F hex: G120P
0510 hex: G120C
0511 hex: G120 CU240E-2
0512 hex: G120D
0513 hex: G120 CU250S-2 Vector
0514 hex: G110M

p8920[0...239]	PN Name of Station / PN Name Stat		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-

Description: Sets the station name for the onboard PROFINET interface on the Control Unit.
The actual station name is displayed in r8930.

Dependency: Refer to: p8925, r8930

Note: An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual.
The interface configuration (p8920 and following) is activated with p8925.
The parameter is not influenced by setting the factory setting.
PN: PROFINET

p8921[0...3]	PN IP address / PN IP addr		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	0

Description: Sets the IP address for the onboard PROFINET interface on the Control Unit.
The actual IP address is displayed in r8931.

Dependency: Refer to: p8925, r8931

Note: The interface configuration (p8920 and following) is activated with p8925.
The parameter is not influenced by setting the factory setting.

p8922[0...3]	PN Def Gateway / PN Def Gateway		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	0
Description:	Sets the default gateway for the onboard PROFINET interface on the Control Unit. The actual standard gateway is displayed in r8932.		
Dependency:	Refer to: p8925, r8932		
Note:	The interface configuration (p8920 and following) is activated with p8925. The parameter is not influenced by setting the factory setting.		
p8923[0...3]	PN Subnet Mask / PN Subnet Mask		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	0
Description:	Sets the subnet mask for the onboard PROFINET interface on the Control Unit. The actual subnet mask is displayed in r8933.		
Dependency:	Refer to: p8925, r8933		
Note:	The interface configuration (p8920 and following) is activated with p8925. The parameter is not influenced by setting the factory setting.		
p8924	PN DHCP Mode / PN DHCP Mode		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	3	0
Description:	Sets the DHCP mode for the onboard PROFINET interface on the Control Unit. The actual DHCP mode is displayed in r8934.		
Value:	0: DHCP off 2: DHCP on, identification using MAC address 3: DHCP on, identification via name of station		
Dependency:	Refer to: p8925, r8934		
Notice:	When the DHCP mode is active (p8924 not equal to 0), then PROFINET communication via this interface is no longer possible! However, the interface can be used by the STARTER/SCOUT commissioning tool.		
Note:	The interface configuration (p8920 and following) is activated with p8925. The active DHCP mode is displayed in parameter r8934. The parameter is not influenced by setting the factory setting.		
p8925	PN interface configuration / PN IF config		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	3	0
Description:	Setting to activate the interface configuration for the onboard PROFINET interface on the Control Unit. p8925 is automatically set to 0 at the end of the operation.		
Value:	0: No function 1: Reserved		

2 Parameters

2.2 List of parameters

	2: Save and activate configuration
	3: Delete configuration
Dependency:	Refer to: p8920, p8921, p8922, p8923, p8924
Notice:	When the DHCP mode is active (p8924 > 0), then PROFINET communication via this interface is no longer possible! However, the interface can be used by the STARTER/SCOUT commissioning tool.
Note:	Re p8925 = 2: The interface configuration (p8920 and following) is saved and activated after the next POWER ON. Re p8925 = 3: The factory setting of the interface configuration is loaded after the next POWER ON.

p8929 PN remote controller number / PN rem ctrl num			
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: C	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	2	1
Description:	Sets the number of remote controllers expected for PROFINET onboard. The "Shared Device" functionality is activated with a value = 2. The drive is being accessed by two PROFINET controllers simultaneously: - automation controller (SIMOTION or SIMATIC A-CPU). - safety controller (SIMATIC F-CPU).		
Value:	1: Automation or Safety 2: Automation and Safety		
Notice:	The F CPU may only use PROFIsafe telegrams.		
Note:	A change only becomes effective after POWER ON, reset or download.		

r8930[0...239] PN Name of Station actual / PN Name Stat act			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the actual station name for the onboard PROFINET interface on the Control Unit.		

r8931[0...3] PN IP address actual / PN IP addr act			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	Displays the actual IP address for the onboard PROFINET interface on the Control Unit.		

r8932[0...3] PN Default Gateway actual / PN Def Gateway act			
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	Displays the actual default gateway for the onboard PROFINET interface on the Control Unit.		

r8933[0...3]	PN Subnet Mask actual / PN Subnet Mask act		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	Displays the actual subnet mask for the onboard PROFINET interface on the Control Unit.		
r8934	PN DHCP Mode actual / PN DHCP Mode act		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	3	-
Description:	Displays the actual DHCP mode for the onboard PROFINET interface on the Control Unit.		
Value:	0: DHCP off 2: DHCP on, identification using MAC address 3: DHCP on, identification via name of station		
Notice:	When the DHCP mode is active (parameter value not equal to 0), PROFINET communication via this interface is no longer possible! However, the interface can be used for commissioning tool such as STARTER or SCOUT.		
r8935[0...5]	PN MAC address / PN MAC addr		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	00FF hex	-
Description:	Displays the MAC address for the onboard PROFINET interface on the Control Unit.		
r8939	PN DAP ID / PN DAP ID		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the PROFINET Device Access Point ID (DAP ID) for the onboard PROFINET interface. The combination of device ID (r8909) and DAP ID uniquely identifies a PROFINET access point.		
Note:	List of the SINAMICS DAP IDs: 20007 hex: CBE20 V4.5 20008 hex: CBE20 V4.6 20107 hex: CU310-2 PN V4.5 20108 hex: CU310-2 PN V4.6 20307 hex: CU320-2 PN V4.5 20308 hex: CU320-2 PN V4.6 20407 hex: CU230P-2 PN /CU240x-2 PN V4.5 20408 hex: CU230P-2 PN /CU240x-2 PN /CU250S-2 PN /G110M PN V4.6 20507 hex: CU250D-2 PN V4.5 20508 hex: CU250D-2 PN V4.6		

r8960[0...2]	PN subslot controller assignment / PN subslot assign		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	8	-
Description:	Displays the controller assignment of a PROFINET subslot on the actual drive object.		
Index:	[0] = Subslot 2 PROFIsafe [1] = Subslot 3 PZD telegram [2] = Subslot 4 PZD supplementary data		
Dependency:	Refer to: r8961, r8962		
Note:	Example: If the parameter contains the value 2 in index [1], then this means that subslot 3 is assigned to controller 2.		
r8961[0...3]	PN IP Address Remote Controller 1 / IP Addr Rem Ctrl1		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	Displays the IP address of the first PROFINET controller connected with the device via PN onboard.		
r8962[0...3]	PN IP Address Remote Controller 2 / IP Addr Rem Ctrl2		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	255	-
Description:	Displays the IP address of the second PROFINET controller connected with the device via PN onboard.		
p8980	Ethernet/IPprofile / Eth/IP profile		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the profile for Ethernet/IP.		
Value:	0: SINAMICS 1: ODVA AC/DC		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting. ODVA: Open DeviceNet Vendor Association		
p8981	Ethernet/IP ODVA STOP mode / Eth/IP ODVA STOP		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	1	0
Description:	Sets the STOP mode for the Ethernet/IP ODVA profile (p8980 = 1).		
Value:	0: OFF1 1: OFF2		
Dependency:	Refer to: p8980		

Note: Changes only become effective after POWER ON.
The parameter is not influenced by setting the factory setting.

p8982	Ethernet/IP ODVA speed scaling / Eth/IP ODVA n scal		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	123	133	128
Description:	Sets the scaling for the speed for Ethernet/IP ODVA profile (p8980 = 1).		
Value:	123: 32 124: 16 125: 8 126: 4 127: 2 128: 1 129: 0.5 130: 0.25 131: 0.125 132: 0.0625 133: 0.03125		
Dependency:	Refer to: p8980		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting.		

p8983	Ethernet/IP ODVA torque scaling / Eth/IP ODVA M scal		
G120C_PN	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	123	133	128
Description:	Sets the scaling for the torque for Ethernet/IP ODVA profile (p8980 = 1).		
Value:	123: 32 124: 16 125: 8 126: 4 127: 2 128: 1 129: 0.5 130: 0.25 131: 0.125 132: 0.0625 133: 0.03125		
Dependency:	Refer to: p8980		
Note:	Changes only become effective after POWER ON. The parameter is not influenced by setting the factory setting.		

p8991	USB memory access / USB mem acc		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	1	2	1
Description:	Selects the storage medium for access via the USB mass storage.		
Value:	1: Memory card 2: Flash r/w internal		

2 Parameters

2.2 List of parameters

Note: A change only becomes effective after a POWER ON.
The parameter is not influenced by setting the factory setting.

p8999

USB functionality / USB Fct

Access level: 4	Calculated: -	Data type: Integer16
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
1	3	3

Description:

Setting the USB functionality.

Value:

1: USS commissioning via the virtual COM port
2: Only memory access
3: USB commissioning and memory access

Note:

COMM: Commissioning.

A change only becomes effective after a POWER ON.

The parameter is not influenced by setting the factory setting.

p9400

Safely remove memory card / Mem_card rem

Access level: 2	Calculated: -	Data type: Integer16
Can be changed: T	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
0	100	0

Description:

Setting and display when memory card is "removed safely".

Procedure:

Setting p9400 = 2 results in a value of 3

--> The memory card can be removed safely. After removal the value sets itself to 0 automatically.

Setting p9400 = 2 results in a value of 100

--> The memory card cannot be removed safely. Removal may destroy the file system on the memory card. It may be necessary to set p9400 = 2 again.

Value:

0: No memory card inserted
1: Memory card inserted
2: Request "safe removal" of the memory card
3: "Safe removal" possible
100: "Safe removal" not possible due to access

Dependency:

Refer to: r9401

Notice:

Removing the memory card without a request (p9400 = 2) and confirmation (p9400 = 3) may destroy the file system on the memory card. The memory card will then no longer work properly and must be replaced.

Note:

The status when the memory card is being "removed safely" is shown in r9401.

Re value = 0, 1, 3, 100:

These values can only be displayed, not set.

r9401

Safely remove memory card status / Mem_card rem stat

Access level: 2	Calculated: -	Data type: Unsigned16
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description:

Displays the status of the memory card.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Memory card inserted	Yes	No	-
01	Memory card activated	Yes	No	-
02	SIEMENS memory card	Yes	No	-
03	Memory card as USB data storage medium from the PC used	Yes	No	-

Dependency:

Refer to: p9400

Note:

Re bit 01, 00:
 Bit 1/0 = 0/0: No memory card inserted (corresponds to p9400 = 0).
 Bit 1/0 = 0/1: "Safe removal" possible (corresponds to p9400 = 3).
 Bit 1/0 = 1/0: Status not possible.
 Bit 1/0 = 1/1: Memory card inserted (corresponds to p9400 = 1, 2, 100).
 Re bit 02, 00:
 Bit 2/0 = 0/0: No memory card inserted.
 Bit 2/0 = 0/1: Memory card inserted, but not a SIEMENS memory card.
 Bit 2/0 = 1/0: Status not possible.
 Bit 2/0 = 1/1: SIEMENS memory card inserted.

r9406[0...19]		PS file parameter number not transferred / PS par_no n transf			
Access level:	4	Calculated:	-	Data type:	Unsigned16
Can be changed:	-	Scaling:	-	Dyn. index:	-
Unit group:	-	Unit selection:	-	Func. diagram:	-
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 non-volatile memory (e.g. memory card).			
		r9406[0] = 0			
		--> All of the parameter values were able to be transferred error-free.			
		r9406[0...x] > 0			
		--> indicates the parameter number in the following cases:			
		- parameter, whose value was not able to be completely accepted.			
		- indexed parameter, where at least 1 index was not able to be accepted. 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.			
		r9406[x] parameter number, parameter not accepted			
		r9407[x] parameter index, parameter not accepted			
		r9408[x] fault code, parameter not accepted			

r9407[0...19]		PS file parameter index parameter not transferred / PS parameter index			
Access level:	4	Calculated:	-	Data type:	Unsigned16
Can be changed:	-	Scaling:	-	Dyn. index:	-
Unit group:	-	Unit selection:	-	Func. diagram:	-
Min		Max		Factory setting	
-		-		-	
Description:					
Displays the first index of the parameters that could not be transferred when the parameter backup files (PS files) were read from the non-volatile memory (e.g. memory 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.					
r9406[x] parameter number, parameter not accepted					
r9407[x] parameter index, parameter not accepted					
r9408[x] fault code, parameter not accepted					

r9408[0...19]	PS file fault code parameter not transferred / PS fault code		
	Access level: 4	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Only for internal Siemens service purposes.		
Dependency:	Refer to: r9406, r9407		
Note:	All indices from r9406 to r9408 designate the same parameter. r9406[x] parameter number, parameter not accepted r9407[x] parameter index, parameter not accepted r9408[x] fault code, parameter not accepted		
r9463	Actual macro / Actual macro		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	999999	-
Description:	Displays the set valid macro.		
Note:	A value of 0 is displayed if a parameter set by a macro is changed.		
p9484	BICO interconnections search signal source / BICO S_src srch		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	Sets the signal source (BO/CO parameter, BICO coded) to search in the signal sinks. The signal source to be searched for is set in p9484 (BICO-coded) and the search result is specified using the number (r9485) and the first index (r9486).		
Dependency:	Refer to: r9485, r9486		
r9485	BICO interconnections signal source search count / BICO S_src srchQty		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of BICO interconnections to the signal sink being searched for.		
Dependency:	Refer to: p9484, r9486		
Note:	The signal source to be searched is set in p9484 (BICO-coded). The search result is contained in r9482 and r9483 and is specified by the count (r9485) and the first index (r9486).		

r9486	BICO interconnections signal source search first index / BICO S_src srchldx				
	Access level: 3	Calculated: -	Data type: Unsigned16		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the first index of the signal source being searched for. The signal source to be searched for is set in p9484 (BICO-coded) and the search result is specified using the number (r9485) and the first index (r9486).				
Dependency:	Refer to: p9484, r9485				
Note:	The signal source to be searched is set in p9484 (BICO-coded). The search result is contained in r9482 and r9483 and is specified by the count (r9485) and the first index (r9486).				

p9601	SI enable functions integrated in the drive (processor 1) / SI enable fct P1				
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32		
G120C_USS	Can be changed: C(95)	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the enable signals for the safety functions integrated in the drive and the type of selection on processor 1. Not all of the settings listed below will be permissible, depending on the Control Unit and Power Module being used 0000 hex: Safety functions integrated in the drive inhibited (no safety function). 0001 hex: Basic functions are enabled via onboard terminals (permissible for r9771.0 = 1).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable STO via terminals (processor 1)	Enable	Inhibit	2810
Dependency:	Refer to: r9771, p9801				
Note:	A change only becomes effective after a POWER ON. STO: Safe Torque Off				

p9601	SI enable functions integrated in the drive (processor 1) / SI enable fct P1				
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned32		
G120C_PN	Can be changed: C(95)	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the enable signals for the safety functions integrated in the drive and the type of selection on processor 1. Not all of the settings listed below will be permissible, depending on the Control Unit and Power Module being used 0000 hex: Safety functions integrated in the drive inhibited (no safety function). 0001 hex: Basic functions are enabled via onboard terminals (permissible for r9771.0 = 1). 0008 hex: Basic functions are enabled via PROFIsafe (permissible for r9771.6 = 1). 0009 hex: Basic functions are enabled via PROFIsafe onboard terminals (permissible for r9771.6 = 1).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable STO via terminals (processor 1)	Enable	Inhibit	2810
	03	Enable PROFIsafe (processor 1)	Enable	Inhibit	-
Dependency:	Refer to: r9771, p9801				
Note:	A change only becomes effective after a POWER ON. STO: Safe Torque Off				

p9610	SI PROFIsafe address (processor 1) / SI PROFIsafe P1		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	FFFE hex	0000 hex
Description:	Sets the PROFIsafe address for processor 1.		
Dependency:	Refer to: p9810		
p9650	SI F-DI changeover discrepancy time (processor 1) / SI F-DI chg t P1		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2810
	Min	Max	Factory setting
	0.00 [ms]	2000.00 [ms]	500.00 [ms]
Description:	Sets the discrepancy time for the changeover of the failsafe digital input for STO on processor 1. An F-DI changeover is not effective simultaneously due to the different runtimes in the two monitoring channels. After an F-DI changeover, dynamic data is not subject to a crosswise data comparison during this discrepancy 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 set time is rounded internally to an integer multiple of the monitoring clock cycle. F-DI: Failsafe Digital Input		
p9651	SI STO debounce time (processor 1) / SI STO t_debou P1		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00 [ms]	100.00 [ms]	1.00 [ms]
Description:	Sets the debounce time for the failsafe digital inputs used to control the "STO" function. The debounce time is rounded to whole milliseconds.		
Note:	The debounce time is rounded to whole milliseconds. It specifies the maximum duration of a fault pulse at the fail-safe digital inputs with no reaction/influence on the selection or deselection of the Safety Basic Functions. Example: Debounce time = 1 ms: Fault pulses of 1 ms are filtered; only pulses longer than 2 ms are processed. Debounce time = 3 ms: Fault pulses of 3 ms are filtered; only pulses longer than 4 ms are processed.		
p9659	SI forced checking procedure timer / SI FCP Timer		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2810
	Min	Max	Factory setting
	0.00 [h]	9000.00 [h]	8.00 [h]
Description:	Sets the time interval for carrying out the forced checking procedure and testing the Safety shutdown paths. Within the parameterized time, STO must have been de-selected at least once. The monitoring time is reset each time that STO is de-selected.		
Dependency:	Refer to: A01699		
Note:	STO: Safe Torque Off		

r9660	SI forced checking procedure remaining time / SI frc chk remain		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [h]	- [h]	- [h]
Description:	Displays the time remaining before dynamization and testing of the safety shutdown paths (forced checking procedure).		
Dependency:	Refer to: A01699		
p9670	SI module identification Control Unit / Module ID CU		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	CRC via Node Identifier of the Control Unit.		
Note:	CU: Control Unit		
p9672	SI module identifier Power Module / Module ID PM		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(95), T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	4294967295	0
Description:	CRC via the Node Identifier of a Power Module.		
Note:	PM: Power Module		
p9700	SI copy function / SI copy function		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: C(95), U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	00D0 hex	0000 hex
Description:	Setting to start the required copy function. After starting, the corresponding parameters are copied from processor 1 to processor 2. Once copying is complete, the parameter is automatically reset to zero.		
Value:	0: [00 hex] Copy function ended 29: [1D hex] Start copy function node identifier 87: [57 hex] Start copy function SI parameters 208: [D0 hex] Start copy function SI basic parameters		
Dependency:	Refer to: r3996		
Notice:	When the parameters are copied, short-term communication interruptions may occur.		
Note:	Re value = 57 hex and D0 hex: The value can only be set if the safety commissioning mode is set and the Safety Integrated password was entered. Re value = D0 hex: The following parameters are copied after starting the copy function: p9601 --> p9801, p9610 --> 9810, p9650 --> p9850, p9651 --> p9851		

p9701	Acknowledge SI data change / Ackn SI data		
	Access level: 3	Calculated: -	Data type: Integer16
	Can be changed: C(95), U, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	00EC hex	0000 hex
Description:	Setting to transfer the reference checksums from the associated actual checksums after changes (SI parameters, hardware). After transferring the reference checksums, parameters are automatically reset to zero.		
Value:	0: [00 hex] Data unchanged 172: [AC hex] Acknowledge data change complete 220: [DC hex] Acknowledge SI basic parameter change 236: [EC hex] Acknowledge hardware CRC		
Dependency:	Refer to: r9798, p9799, r9898, p9899		
Note:	Re value = AC and DC hex: These values can only be set if the safety commissioning mode is set and the Safety Integrated password was entered.		
p9761	SI password input / SI password inp		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C, T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2800
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex
Description:	Enters the Safety Integrated password.		
Dependency:	Refer to: F01659		
Note:	It is not possible to change Safety Integrated parameters until the Safety Integrated password has been entered.		
p9762	SI password new / SI password new		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2800
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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 acknowledgement / SI ackn password		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2800
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	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.		

r9768[0...7]	SI PROFIsafe receive control words (processor 1) / SI Ps PZD recv P1		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the received PROFIsafe telegram on processor 1.		
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		
Dependency:	Refer to: r9769		
Note:	The PROFIsafe trailer at the end of the telegram is also displayed (2 words).		
r9769[0...7]	SI PROFIsafe send status words (processor 1) / SI Ps PZD send P1		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the PROFIsafe telegram to be sent on processor 1.		
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		
Dependency:	Refer to: r9768		
Note:	The PROFIsafe trailer at the end of the telegram is also displayed (2 words).		
r9770[0...3]	SI version drive-integrated safety function (processor 1) / SI version Drv P1		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2802
	Min	Max	Factory setting
	-	-	-
Description:	Displays the Safety Integrated version for the drive-integrated safety functions on processor 1.		
Index:	[0] = Safety Version (major release) [1] = Safety Version (minor release) [2] = Safety Version (baselevel or patch) [3] = Safety Version (hotfix)		
Note:	Example: r9770[0] = 2, r9770[1] = 60, r9770[2] = 1, r9770[3] = 0 --> Safety version V02.60.01.00		

2 Parameters

2.2 List of parameters

r9771	SI common functions (processor 1) / SI general fct P1				
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32		
G120C_USS	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2804		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the supported Safety Integrated monitoring functions. Processor 1 determines this display.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	STO supported via terminals	Yes	No	2804
Dependency:	Refer to: r9871				
Note:	STO: Safe Torque Off				

r9771	SI common functions (processor 1) / SI general fct P1				
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned32		
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2804		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the supported Safety Integrated monitoring functions. Processor 1 determines this display.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	STO supported via terminals	Yes	No	2804
	06	Basic Functions PROFIsafe supported	Yes	No	-
Dependency:	Refer to: r9871				
Note:	STO: Safe Torque Off				

r9772.0...21	CO/BO: SI status (processor 1) / SI status P1				
	Access level: 2	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2804		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the Safety Integrated status on processor 1.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	STO selected on processor 1	Yes	No	2810
	01	STO active on processor 1	Yes	No	2810
	07	STO terminal state on processor 1 (Basic Functions)	High	Low	-
	09	STOP A cannot be acknowledged active	Yes	No	2802
	10	STOP A active	Yes	No	2802
	15	STOP F active	Yes	No	2802
	16	STO cause: Safety comm. mode	Yes	No	-
	17	STO cause selection via terminal (Basic Functions)	Yes	No	-
	18	STO cause: Selection via motion monitoring functions	Yes	No	-
	19	STO cause actual value missing	Yes	No	-
	20	STO cause selection PROFIsafe (Basic Functions)	Yes	No	-
	21	STO cause selection on the other monitoring channel	Yes	No	-
Dependency:	Refer to: r9872				
Note:	Re bit 00: When STO is selected, the cause is displayed in bits 16 ... 21.				

Re bit 18:

When the bit is set, STO is selected via PROFIsafe.

Re bit 19:

For the drive-integrated motion monitoring functions, due to OFF2, no actual value sensing possible.

r9773.0...31**CO/BO: SI status (processor 1 + processor 2) / SI status P1+P2**

Access level: 2	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2804
Min	Max	Factory setting
-	-	-

Description:

Display and BICO output for the Safety Integrated status on the drive (processor 1 + processor 2).

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	STO selected in drive	Yes	No	2804
01	STO active in drive	Yes	No	2804
31	Shutdown paths must be tested	Yes	No	2810

Note:

This status is formed from the AND operation of the relevant status of the two monitoring channels.

r9776**SI diagnostics / SI diag**

Access level: 3	Calculated: -	Data type: Unsigned32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: -
Min	Max	Factory setting
-	-	-

Description:

The parameter is used for diagnostics.

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Safety parameter changed POWER ON required	Yes	No	-
01	Safety functions enabled	Yes	No	-
02	Safety component replaced and data save required	Yes	No	-

Note:

Re bit 00 = 1:

At least one Safety parameter has been changed that will only take effect after a POWER ON.

Re bit 01 = 1:

Safety functions (basic functions or extended functions) have been enabled and are active.

Re bit 02 = 1:

A safety-relevant component has been replaced. Data save required (p0977 = 1 or p0971 = 1 or "copy RAM to ROM").

r9780**SI monitoring clock cycle (processor 1) / SI mon_clk cyc P1**

Access level: 3	Calculated: -	Data type: FloatingPoint32
Can be changed: -	Scaling: -	Dyn. index: -
Unit group: -	Unit selection: -	Func. diagram: 2802
Min	Max	Factory setting
- [ms]	- [ms]	- [ms]

Description:

Displays the clock cycle time for the Safety Integrated Basic Functions on processor 1.

Note:

Information regarding the relationship between monitoring clock cycle and response times can be found in the following references:

- SINAMICS G120 Function Manual Safety Integrated
- technical documentation for the particular product

r9781[0...1]	SI checksum to check changes (processor 1) / SI chg chksm P1		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	-	-	-
Description:	Displays the checksum for tracking changes for Safety Integrated. These are additional checksums that are created to track changes (fingerprint for the "safety logbook" functionality) to safety parameters (that are relevant for checksums).		
Index:	[0] = SI checksum to track functional changes [1] = SI checksum to track hardware-specific changes		
Dependency:	Refer to: p9601, p9799		
r9782[0...1]	SI time stamp to check changes (processor 1) / SI chg t P1		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [h]	- [h]	- [h]
Description:	Displays the time stamps for the checksums for tracking changes for Safety Integrated. The time stamps for the checksums for tracking changes (fingerprint for the "safety logbook" functionality) made to safety parameters are saved in parameters p9781[0] and p9781[1].		
Index:	[0] = SI time stamp for checksum to track functional changes [1] = SI time stamp for checksum to track hardware-specific changes		
Dependency:	Refer to: p9601, p9799		
r9794[0...19]	SI crosswise comparison list (processor 1) / SI CDC_list P1		
	Access level: 3	Calculated: -	Data type: Unsigned16
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2802
	Min	Max	Factory setting
	-	-	-
Description:	Displays the numbers of the data items that are currently being compared crosswise on processor 1. The content of the list of crosswise-compared data is dependent upon the particular application.		
Note:	Example: r9794[0] = 1 (monitoring clock cycle) r9794[1] = 2 (enable safety functions) r9794[2] = 3 (F-DI changeover, tolerance time) ... A complete list of numbers for crosswise-compared data items appears in fault F01611.		
r9795	SI diagnostics STOP F (processor 1) / SI diag STOP F P1		
	Access level: 2	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2802
	Min	Max	Factory setting
	-	-	-
Description:	Displays the number of the cross-compared data item which caused STOP F on processor 1.		
Dependency:	Refer to: F01611		
Note:	A complete list of numbers for crosswise-compared data items appears in fault F01611.		

r9798	SI actual checksum SI parameters (processor 1) / SI act chksm P1				
	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2800		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the checksum for the Safety Integrated parameters checked using checksums on processor 1 (actual checksum).				
Dependency:	Refer to: p9799, r9898				
p9799	SI setpoint checksum SI parameters (processor 1) / SI setp_chksm P1				
	Access level: 3	Calculated: -	Data type: Unsigned32		
	Can be changed: C(95)	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2800		
	Min	Max	Factory setting		
	0000 hex	FFFF FFFF hex	0000 hex		
Description:	Sets the checksum for the Safety Integrated parameters checked using checksums on processor 1 (setpoint checksum).				
Dependency:	Refer to: r9798, p9899				
p9801	SI enable functions integrated in the drive (processor 2) / SI enable fct P2				
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned16		
G120C_USS	Can be changed: C(95)	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the enable signals for the safety functions integrated in the drive and the type of selection on processor 1. Not all of the settings listed below will be permissible, depending on the Control Unit and Power Module being used: 0000 hex: Safety functions integrated in the drive inhibited (no safety function). 0001 hex: Basic functions are enabled via onboard terminals (permissible for r9771.0 = 1).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable STO via terminals (processor 2)	Enable	Inhibit	2810
Dependency:	Refer to: p9601, r9871				
Notice:	This parameter is overwritten by the copy function of the safety functions integrated in the drive.				
Note:	A change only becomes effective after a POWER ON. STO: Safe Torque Off				
p9801	SI enable functions integrated in the drive (processor 2) / SI enable fct P2				
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16		
G120C_PN	Can be changed: C(95)	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: -		
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Sets the enable signals for the safety functions integrated in the drive and the type of selection on processor 1. Not all of the settings listed below will be permissible, depending on the Control Unit and Power Module being used: 0000 hex: Safety functions integrated in the drive inhibited (no safety function). 0001 hex: Basic functions are enabled via onboard terminals (permissible for r9771.0 = 1).				

2 Parameters

2.2 List of parameters

0008 hex:

Basic functions are enabled via PROFIsafe (permissible for r9771.6 = 1).

0009 hex:

Basic functions are enabled via PROFIsafe onboard terminals (permissible for r9771.6 = 1).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable STO via terminals (processor 2)	Enable	Inhibit	2810
	03	Enable PROFIsafe (processor 2)	Enable	Inhibit	-
Dependency:	Refer to: p9601, r9871				
Notice:	This parameter is overwritten by the copy function of the safety functions integrated in the drive.				
Note:	A change only becomes effective after a POWER ON. STO: Safe Torque Off				

p9810	SI PROFIsafe address (processor 2) / SI PROFIsafe P2		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0000 hex	FFFE hex	0000 hex
Description:	Sets the PROFIsafe address on processor 2.		
Notice:	This parameter is overwritten by the copy function of the safety functions integrated in the drive.		

p9850	SI F-DI changeover discrepancy time (processor 2) / SI F-DI chg t P2		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2810
	Min	Max	Factory setting
	0.00 [µs]	2000000.00 [µs]	500000.00 [µs]
Description:	Sets the discrepancy time for the changeover of the failsafe digital input for STO on processor 2. An F-DI changeover is not effective simultaneously due to the different runtimes in the two monitoring channels. After an F-DI changeover, dynamic data is not subject to a crosswise data comparison during this discrepancy time.		
Dependency:	Refer to: p9650		
Notice:	This parameter is overwritten by the copy function of the safety functions integrated in the drive.		
Note:	For a crosswise data comparison between p9650 and p9850, a difference of one Safety monitoring clock cycle is tolerated. The set time is rounded internally to an integer multiple of the monitoring clock cycle. F-DI: Failsafe Digital Input		

p9851	SI STO debounce time (processor 2) / SI STO t_debou P2		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0.00 [µs]	100000.00 [µs]	0.00 [µs]
Description:	Sets the debounce time for the failsafe digital inputs used to control the "STO" function. The debounce time is rounded to whole milliseconds.		
Dependency:	Refer to: p9651		
Notice:	This parameter is overwritten by the copy function of the safety functions integrated in the drive.		
Note:	Rounding effects can occur in the last decimal place of the parameterized time. The debounce time is rounded to whole milliseconds. It specifies the maximum duration of a fault pulse at the fail-safe digital inputs with no reaction/influence on the selection or deselection of the Safety Basic Functions. Example: Debounce time = 1 ms: Fault pulses of 1 ms are filtered; only pulses longer than 2 ms are processed. Debounce time = 3 ms: Fault pulses of 3 ms are filtered; only pulses longer than 4 ms are processed.		

r9871	SI common functions (processor 2) / SI common fct P2				
G120C_CAN	Access level: 3	Calculated: -	Data type: Unsigned32		
G120C_USS	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2804		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the supported Safety Integrated monitoring functions. Processor 2 determines this display.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	STO supported via terminals	Yes	No	2804
Dependency:	Refer to: r9771				
Note:	STO: Safe Torque Off				

r9871	SI common functions (processor 2) / SI common fct P2				
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned32		
G120C_PN	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2804		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the supported Safety Integrated monitoring functions. Processor 2 determines this display.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	STO supported via terminals	Yes	No	2804
	06	Basic Functions PROFIsafe supported	Yes	No	-
Dependency:	Refer to: r9771				
Note:	STO: Safe Torque Off				

r9872.0...21	CO/BO: SI status (processor 2) / SI Status P2				
	Access level: 2	Calculated: -	Data type: Unsigned32		
	Can be changed: -	Scaling: -	Dyn. index: -		
	Unit group: -	Unit selection: -	Func. diagram: 2804		
	Min	Max	Factory setting		
	-	-	-		
Description:	Displays the Safety Integrated status on processor 2.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	STO selected on processor 2	Yes	No	2810
	01	STO active on processor 2	Yes	No	2810
	07	STO terminal state on processor 2 (Basic Functions)	High	Low	-
	09	STOP A cannot be acknowledged active	Yes	No	2802
	10	STOP A active	Yes	No	2802
	15	STOP F active	Yes	No	2802
	16	STO cause: Safety comm. mode	Yes	No	-
	17	STO cause selection via terminal (Basic Functions)	Yes	No	-
	18	STO cause: Selection via motion monitoring functions	Yes	No	-
	20	STO cause selection PROFIsafe (Basic Functions)	Yes	No	-
	21	STO cause selection on the other monitoring channel	Yes	No	-
Dependency:	Refer to: r9772				

2 Parameters

2.2 List of parameters

Note: Re bit 00:
When STO is selected, the cause is displayed in bits 16 ... 21.
Re bit 18:
When the bit is set, STO is selected via PROFIsafe.

r9898	SI actual checksum SI parameters (processor 2) / SI act_chksm P2		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2800
	Min	Max	Factory setting
	-	-	-

Description: Displays the checksum for the Safety Integrated parameters checked using checksums on processor 2 (actual checksum).

Dependency: Refer to: r9798, p9899

p9899	SI setpoint checksum SI parameters (processor 2) / SI setp_chksm P2		
	Access level: 3	Calculated: -	Data type: Unsigned32
	Can be changed: C(95)	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2800
	Min	Max	Factory setting
	0000 hex	FFFF FFFF hex	0000 hex

Description: Sets the checksum for the Safety Integrated parameters checked using checksums on processor 2 (setpoint checksum).

Dependency: Refer to: p9799, r9898

r9976[0...7]	System utilization / Sys util		
	Access level: 3	Calculated: -	Data type: FloatingPoint32
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	- [%]	- [%]	- [%]

Description: Displays the system utilization.
If the utilization is greater than 100%, fault F01054 is output.

Index: [0] = Reserved
[1] = Computing time utilization
[2] = Reserved
[3] = Reserved
[4] = Reserved
[5] = Largest total utilization
[6] = Reserved
[7] = Reserved

Dependency: Refer to: F01054, F01205

Note: Re index 1:
The value shows the total computing time load of the system.
Re index 5:
The total utilization is determined using all sampling times used. The largest total utilization is mapped here. The sampling time with the largest total utilization is displayed in r9979.
Total utilization:
Computing time load of sampling time involved including load from higher-priority sampling times (interrupts).

p60022	PROFIsafe telegram selection / Ps telegram_sel		
G120C_DP	Access level: 3	Calculated: -	Data type: Unsigned16
G120C_PN	Can be changed: T	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: -
	Min	Max	Factory setting
	0	998	998
Description:	Sets the telegram number for PROFIsafe.		
Value:	0: No PROFIsafe telegram selected 30: PROFIsafe standard telegram 30, PZD-1/1 998: Compatibility mode (as for firmware version < 4.6)		
Note:	For p9601.3 = p9801.3 = 1 (PROFIsafe enabled), the following variants exist when parameterizing PROFIsafe telegram 30: - p9611 = p9811 = 998 and p60022 = 0 - p9611 = p9811 = 998 and p60022 = 30 - p9611 = p9811 = 30 and p60022 = 30		
r61000[0...239]	PROFINET Name of Station / PN Name of Station		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2410
	Min	Max	Factory setting
	-	-	-
Description:	Displays PROFINET Name of Station.		
Notice:	An ASCII table (excerpt) can be found, for example, in the appendix to the List Manual.		
r61001[0...3]	PROFINET IP of Station / PN IP of Station		
G120C_PN	Access level: 3	Calculated: -	Data type: Unsigned8
	Can be changed: -	Scaling: -	Dyn. index: -
	Unit group: -	Unit selection: -	Func. diagram: 2410
	Min	Max	Factory setting
	-	-	-
Description:	Displays PROFINET IP of Station.		

2.3 Parameters for data sets

2.3.1 Command Data Sets (CDS)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: CDS

p0820[0...n]	Bl: Drive Data Set selection DDS bit 0 / DDS select., bit 0
p0840[0...n]	Bl: ON / OFF (OFF1) / ON / OFF (OFF1)
p0844[0...n]	Bl: No coast-down / coast-down (OFF2) signal source 1 / OFF2 S_src 1
p0845[0...n]	Bl: No coast-down / coast-down (OFF2) signal source 2 / OFF2 S_src 2
p0848[0...n]	Bl: No Quick Stop / Quick Stop (OFF3) signal source 1 / OFF3 S_src 1
p0849[0...n]	Bl: No Quick Stop / Quick Stop (OFF3) signal source 2 / OFF3 S_src 2
p0852[0...n]	Bl: Enable operation/inhibit operation / Operation enable
p0854[0...n]	Bl: Control by PLC/no control by PLC / Master ctrl by PLC
p0855[0...n]	Bl: Unconditionally release holding brake / Uncond open brake
p0856[0...n]	Bl: Enable speed controller / n_ctrl enable
p0858[0...n]	Bl: Unconditionally close holding brake / Uncond close brake
p1000[0...n]	Speed setpoint selection / n_set sel
p1020[0...n]	Bl: Fixed speed setpoint selection Bit 0 / n_set_fixed Bit 0
p1021[0...n]	Bl: Fixed speed setpoint selection Bit 1 / n_set_fixed Bit 1
p1022[0...n]	Bl: Fixed speed setpoint selection Bit 2 / n_set_fixed Bit 2
p1023[0...n]	Bl: Fixed speed setpoint selection Bit 3 / n_set_fixed Bit 3
p1035[0...n]	Bl: Motorized potentiometer setpoint raise / Mop raise
p1036[0...n]	Bl: Motorized potentiometer lower setpoint / Mop lower
p1043[0...n]	Bl: Motorized potentiometer accept setting value / MotP acc set val
p1044[0...n]	Cl: Motorized potentiometer setting value / Mop set val
p1055[0...n]	Bl: Jog bit 0 / Jog bit 0
p1056[0...n]	Bl: Jog bit 1 / Jog bit 1
p1070[0...n]	Cl: Main setpoint / Main setpoint
p1071[0...n]	Cl: Main setpoint scaling / Main setp scal
p1075[0...n]	Cl: Suppl setp / Suppl setp
p1076[0...n]	Cl: Supplementary setpoint scaling / Suppl setp scal
p1106[0...n]	Cl: Minimum speed signal source / n_min s_src
p1110[0...n]	Bl: Inhibit negative direction / Inhib neg dir
p1111[0...n]	Bl: Inhibit positive direction / Inhib pos dir
p1113[0...n]	Bl: Setpoint inversion / Setp inv
p1138[0...n]	Cl: Ramp-function generator ramp-up time scaling / RFG t_RU scal
p1139[0...n]	Cl: Ramp-function generator ramp-down time scaling / RFG t_RD scal
p1140[0...n]	Bl: Enable ramp-function generator/inhibit ramp-function generator / RFG enable
p1141[0...n]	Bl: Continue ramp-function generator/freeze ramp-function generator / Continue RFG
p1142[0...n]	Bl: Enable setpoint/inhibit setpoint / Setpoint enable
p1201[0...n]	Bl: Flying restart enable signal source / Fly_res enab S_src
p1230[0...n]	Bl: DC braking activation / DC brake act
p1330[0...n]	Cl: U/f control independent voltage setpoint / Uf U_set independ.
p1352[0...n]	Cl: Motor holding brake starting frequency signal source / Brake f_start
p1475[0...n]	Cl: Speed controller torque setting value for motor holding brake / n_ctrl M_sv MHB
p1502[0...n]	Bl: Freeze moment of inertia estimator / J_estim freeze
p1511[0...n]	Cl: Supplementary torque 1 / M_suppl 1
p1522[0...n]	Cl: Torque limit upper / M_max upper
p1523[0...n]	Cl: Torque limit lower / M_max lower
p1552[0...n]	Cl: Torque limit upper scaling without offset / M_max up w/o offs
p1554[0...n]	Cl: Torque limit lower scaling without offset / M_max low w/o offs
p2103[0...n]	Bl: 1. Acknowledge faults / 1. Acknowledge
p2104[0...n]	Bl: 2. Acknowledge faults / 2. Acknowledge

p2106[0...n]	BI: External fault 1 / External fault 1
p2112[0...n]	BI: External alarm 1 / External alarm 1
p2200[0...n]	BI: Technology controller enable / Tec_ctrl enable
p2220[0...n]	BI: Technology controller fixed value selection bit 0 / Tec_ctrl sel bit 0
p2221[0...n]	BI: Technology controller fixed value selection bit 1 / Tec_ctrl sel bit 1
p2222[0...n]	BI: Technology controller fixed value selection bit 2 / Tec_ctrl sel bit 2
p2223[0...n]	BI: Technology controller fixed value selection bit 3 / Tec_ctrl sel bit 3
p2235[0...n]	BI: Technology controller motorized potentiometer raise setpoint / Tec_ctrl mop raise
p2236[0...n]	BI: Technology controller motorized potentiometer lower setpoint / Tec_ctrl mop lower
p2253[0...n]	CI: Technology controller setpoint 1 / Tec_ctrl setp 1
p2254[0...n]	CI: Technology controller setpoint 2 / Tec_ctrl setp 2
p2264[0...n]	CI: Technology controller actual value / Tec_ctrl act val
p2286[0...n]	BI: Hold technology controller integrator / Tec_ctr integ hold
p2289[0...n]	CI: Technology controller pre-control signal / Tec_ctr prectr_sig
p2290[0...n]	BI: Technology controller limiting enable / Tec_ctrl lim enab
p2296[0...n]	CI: Technology controller output scaling / Tec_ctrl outp scal
p2297[0...n]	CI: Technology controller maximum limit signal source / Tec_ctrMaxLimS_src
p2298[0...n]	CI: Technology controller minimum limit signal source / Tec_ctrl min_l s_s
p2299[0...n]	CI: Technology controller limit offset / Tec_ctrl lim offs
p3330[0...n]	BI: 2/3 wire control command 1 / 2/3 wire cmd 1
p3331[0...n]	BI: 2/3 wire control command 2 / 2/3 wire cmd 2
p3332[0...n]	BI: 2/3 wire control command 3 / 2/3 wire cmd 3

2.3.2 Drive Data Sets (DDS)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: DDS

p0340[0...n]	Automatic calculation motor/control parameters / Calc auto par
p0640[0...n]	Current limit / Current limit
p1001[0...n]	CO: Fixed speed setpoint 1 / n_set_fixed 1
p1002[0...n]	CO: Fixed speed setpoint 2 / n_set_fixed 2
p1003[0...n]	CO: Fixed speed setpoint 3 / n_set_fixed 3
p1004[0...n]	CO: Fixed speed setpoint 4 / n_set_fixed 4
p1005[0...n]	CO: Fixed speed setpoint 5 / n_set_fixed 5
p1006[0...n]	CO: Fixed speed setpoint 6 / n_set_fixed 6
p1007[0...n]	CO: Fixed speed setpoint 7 / n_set_fixed 7
p1008[0...n]	CO: Fixed speed setpoint 8 / n_set_fixed 8
p1009[0...n]	CO: Fixed speed setpoint 9 / n_set_fixed 9
p1010[0...n]	CO: Fixed speed setpoint 10 / n_set_fixed 10
p1011[0...n]	CO: Fixed speed setpoint 11 / n_set_fixed 11
p1012[0...n]	CO: Fixed speed setpoint 12 / n_set_fixed 12
p1013[0...n]	CO: Fixed speed setpoint 13 / n_set_fixed 13
p1014[0...n]	CO: Fixed speed setpoint 14 / n_set_fixed 14
p1015[0...n]	CO: Fixed speed setpoint 15 / n_set_fixed 15
p1030[0...n]	Motorized potentiometer configuration / Mop configuration
p1037[0...n]	Motorized potentiometer maximum speed / MotP n_max
p1038[0...n]	Motorized potentiometer minimum speed / MotP n_min
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
p1059[0...n]	Jog 2 speed setpoint / Jog 2 n_set
p1080[0...n]	Minimum speed / n_min
p1082[0...n]	Maximum speed / n_max
p1083[0...n]	CO: Speed limit in positive direction of rotation / n_limit pos

p1086[0...n]	CO: Speed limit in negative direction of rotation / n_limit neg
p1091[0...n]	Skip speed 1 / n_skip 1
p1092[0...n]	Skip speed 2 / n_skip 2
p1101[0...n]	Skip speed bandwidth / n_skip bandwidth
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
p1123[0...n]	Ramp-function generator minimum ramp-up time / RFG t_RU min
p1127[0...n]	Ramp-function generator minimum ramp-down time / RFG t_RD min
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 / OFF3 t_RD
p1136[0...n]	OFF3 initial rounding-off time / RFGOFF3 t_strt_rnd
p1137[0...n]	OFF3 final rounding-off time / RFG OFF3 t_end_del
p1200[0...n]	Flying restart operating mode / FlyRest op_mode
p1202[0...n]	Flying restart search current / FlyRest I_srch
p1203[0...n]	Flying restart search rate factor / FlyRst v_Srch Fact
p1226[0...n]	Threshold for zero speed detection / n_standst n_thresh
p1240[0...n]	Vdc controller configuration (vector control) / Vdc ctr config vec
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
p1249[0...n]	Vdc_max controller speed threshold / Vdc_max n_thresh
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
p1271[0...n]	Flying restart maximum frequency for the inhibited direction / FlyRes f_max dir
p1280[0...n]	Vdc controller configuration (U/f) / Vdc_ctr config U/f
p1281[0...n]	Vdc controller configuration / Vdc ctrl config.
p1283[0...n]	Vdc_max controller dynamic factor (U/f) / Vdc_max dyn_factor
p1284[0...n]	Vdc_max controller time threshold (U/f) / Vdc_max t_thresh
p1288[0...n]	Vdc_max controller feedback coupling factor ramp-fct. gen. (U/f) / Vdc_max factor RFG
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 min controller output limit (U/f) / Vdc_min outp_lim
p1295[0...n]	Vdc_min controller time threshold (U/f) / Vdc_min t_thresh
p1297[0...n]	Vdc_min controller speed threshold (U/f) / Vdc_min n_thresh
p1300[0...n]	Open-loop/closed-loop control operating mode / Op/cl-lp ctrl_mode
p1302[0...n]	U/f control configuration / U/f config
p1310[0...n]	Starting current (voltage boost) permanent / I_start (Ua) perm
p1311[0...n]	Starting current (voltage boost) when accelerating / I_start accel
p1312[0...n]	Starting current (voltage boost) when starting / I_start start
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
p1331[0...n]	Voltage limiting / U_lim

p1333[0...n]	U/f control FCC starting frequency / U/f FCC f_start
p1334[0...n]	U/f control slip compensation starting frequency / Slip comp start
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
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
p1351[0...n]	CO: Motor holding brake starting frequency / Brake f_start
p1400[0...n]	Speed control configuration / n_ctrl config
p1452[0...n]	Speed controller speed actual value smoothing time (sensorless) / n_C n_act T_s SL
p1470[0...n]	Speed controller encoderless operation P-gain / n_ctrl SL Kp
p1472[0...n]	Speed controller encoderless operation integral time / n_ctrl SL Tn
p1496[0...n]	Acceleration pre-control scaling / a_prectrl scal
p1498[0...n]	Load moment of inertia / Load M_inertia
p1517[0...n]	Accelerating torque smoothing time constant / M_accel T_smooth
p1520[0...n]	CO: Torque limit upper / M_max upper
p1521[0...n]	CO: Torque limit lower / M_max lower
p1524[0...n]	CO: Torque limit upper scaling / M_max upper scal
p1525[0...n]	CO: Torque limit lower scaling / M_max lower scal
p1530[0...n]	Power limit motoring / P_max mot
p1531[0...n]	Power limit regenerative / P_max gen
p1553[0...n]	Stall limit scaling / Stall limit scal
p1560[0...n]	Moment of inertia estimator accelerating torque threshold value / J_est M thresh
p1561[0...n]	Moment of inertia estimator change time moment of inertia / J_est t J
p1562[0...n]	Moment of inertia estimator change time load / J_est t load
p1563[0...n]	CO: Mom. of inertia estimator load torque direction of rotation pos. / J_est M pos
p1564[0...n]	CO: Mom. of inertia estimator load torque direction of rotation neg. / J_est M neg
p1570[0...n]	CO: Flux setpoint / Flex setp
p1575[0...n]	Voltage target value limit / U_tgt val lim
p1580[0...n]	Efficiency optimization / Efficiency opt.
p1582[0...n]	Flux setpoint smoothing time / Flux setp T_smth
p1586[0...n]	Field weakening characteristic scaling / Field weak scal
p1590[0...n]	Flux controller P gain / Flux controller Kp
p1610[0...n]	Torque setpoint static (sensorless) / M_set static
p1611[0...n]	Additional acceleration torque (sensorless) / M_suppl_accel
p1616[0...n]	Current setpoint smoothing time / I_set T_smooth
p1715[0...n]	Current controller P gain / I_ctrl Kp
p1717[0...n]	Current controller integral-action time / I_ctrl Tn
p1730[0...n]	Isd controller integral component shutdown threshold / Isd ctrl Tn shutd
p1740[0...n]	Gain resonance damping for encoderless closed-loop control / Gain res_damp
p1745[0...n]	Motor model error threshold stall detection / MotMod ThreshStall
p1749[0...n]	Motor model increase changeover speed encoderless operation / Incr n_chng no enc
p1750[0...n]	Motor model configuration / MotMod config
p1755[0...n]	Motor model changeover speed encoderless operation / MotMod n_chgSnsorl
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
p1780[0...n]	Motor model adaptation configuration / MotMod adapt conf
p1784[0...n]	Motor model feedback scaling / MotMod fdbk scal
r1787[0...n]	Motor model Lh adaptation corrective value / MotMod Lh corr
p1800[0...n]	Pulse frequency setpoint / Pulse freq setp
p1802[0...n]	Modulator mode / Modulator mode
p1803[0...n]	Maximum modulation depth / Modulat depth max

p1806[0...n]	Filter time constant Vdc correction / T_filt Vdc_corr
p1820[0...n]	Reverse the output phase sequence / Outp_ph_seq rev
p1959[0...n]	Rotating measurement configuration / Rot meas config
p2141[0...n]	Speed threshold 1 / n_thresh val 1
p2153[0...n]	Speed actual value filter time constant / n_act_filt T
p2155[0...n]	Speed threshold 2 / n_thresh val 2
p2156[0...n]	On delay comparison value reached / t_on cmpr val rchd
p2165[0...n]	Load monitoring stall monitoring upper threshold / Stall_mon up thr
p2168[0...n]	Load monitoring stall monitoring torque threshold / Stall_mon M_thresh
p2170[0...n]	Current threshold value / I_thres
p2171[0...n]	Current threshold value reached delay time / I_thresh rch t_del
p2172[0...n]	DC link voltage threshold value / Vdc thresh val
p2174[0...n]	Torque threshold value 1 / M_thresh val 1
p2191[0...n]	Load monitoring torque threshold no load / M_thresh no load
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_ctrl fix val1
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
p2216[0...n]	Technology controller fixed value selection method / Tec_ctr FixVal sel
p2230[0...n]	Technology controller motorized potentiometer configuration / Tec_ctr mop config
p2237[0...n]	Technology controller motorized potentiometer maximum value / Tec_ctrl mop max
p2238[0...n]	Technology controller motorized potentiometer minimum value / Tec_ctrl mop min
p2240[0...n]	Technology controller motorized potentiometer starting value / Tec_ctrl 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
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]
p3233[0...n]	Torque actual value filter time constant / M_act_filt T
p3320[0...n]	Fluid flow machine power point 1 / Fluid_mach P1
p3321[0...n]	Fluid flow machine speed point 1 / Fluid_mach n1
p3322[0...n]	Fluid flow machine power point 2 / Fluid_mach P2
p3323[0...n]	Fluid flow machine speed point 2 / Fluid_mach n2
p3324[0...n]	Fluid flow machine power point 3 / Fluid_mach P3
p3325[0...n]	Fluid flow machine speed point 3 / Fluid_mach n3
p3326[0...n]	Fluid flow machine power point 4 / Fluid_mach P4
p3327[0...n]	Fluid flow machine speed point 4 / Fluid_mach n4
p3328[0...n]	Fluid flow machine power point 5 / Fluid_mach P5
p3329[0...n]	Fluid flow machine speed point 5 / Fluid_mach n5
p3820[0...n]	Friction characteristic value n0 / Friction n0
p3821[0...n]	Friction characteristic value n1 / Friction n1
p3822[0...n]	Friction characteristic value n2 / Friction n2

p3823[0...n]	Friction characteristic value n3 / Friction n3
p3824[0...n]	Friction characteristic value n4 / Friction n4
p3825[0...n]	Friction characteristic value n5 / Friction n5
p3826[0...n]	Friction characteristic value n6 / Friction n6
p3827[0...n]	Friction characteristic value n7 / Friction n7
p3828[0...n]	Friction characteristic value n8 / Friction n8
p3829[0...n]	Friction characteristic value n9 / Friction n9
p3830[0...n]	Friction characteristic value M0 / Friction M0
p3831[0...n]	Friction characteristic value M1 / Friction M1
p3832[0...n]	Friction characteristic value M2 / Friction M2
p3833[0...n]	Friction characteristic value M3 / Friction M3
p3834[0...n]	Friction characteristic value M4 / Friction M4
p3835[0...n]	Friction characteristic value M5 / Friction M5
p3836[0...n]	Friction characteristic value M6 / Friction M6
p3837[0...n]	Friction characteristic value M7 / Friction M7
p3838[0...n]	Friction characteristic value M8 / Friction M8
p3839[0...n]	Friction characteristic value M9 / Friction M9
p3846[0...n]	Friction characteristic record ramp-up/ramp-down time / Frict rec t _{RU/RD}
p3847[0...n]	Friction characteristic record warm-up time / Frict rec t _{warm}
p3856[0...n]	Compound braking current / Compound I _{brake}
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
r3929[0...n]	Motor data identification modulated voltage generation / MotID U _{gen} mod
p5271[0...n]	Online tuning configuration controller / Ot config ctrl
p5310[0...n]	Moment of inertia precontrol configuration / J _{est} config
r5311[0...n]	Moment of inertia precontrol status word / J _{estimate} ZSW
p5312[0...n]	Moment of inertia precontrol linear positive / J _{est} lin pos
p5313[0...n]	Moment of inertia precontrol constant positive / J _{est} const pos
p5314[0...n]	Moment of inertia precontrol linear negative / J _{est} lin neg
p5315[0...n]	Moment of inertia precontrol constant negative / J _{est} const neg
p5316[0...n]	Moment of inertia precontrol change time moment of inertia / J _{prectrl} t _J

2.3.3 Motor data sets (MDS)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: MDS

p0133[0...n]	Motor configuration / Motor config
p0300[0...n]	Motor type selection / Mot type sel
p0301[0...n]	Motor code number selection / Mot code No. sel
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}
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}
p0312[0...n]	Rated motor torque / Mot M _{rated}
r0313[0...n]	Motor pole pair number, actual (or calculated) / Mot PolePairNo act
p0314[0...n]	Motor pole pair number / Mot pole pair No.
p0316[0...n]	Motor torque constant / Mot kT
p0318[0...n]	Motor stall current / Mot I _{standstill}
p0320[0...n]	Motor rated magnetizing current/short-circuit current / Mot I _{mag_rated}
p0322[0...n]	Maximum motor speed / Mot n _{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
p0329[0...n]	Motor pole position identification current / Mot PolID current
r0330[0...n]	Rated motor slip / Mot slip Rated
r0331[0...n]	Actual motor magnetizing current/short-circuit current / Mot I_mag_rtd act
r0333[0...n]	Rated motor torque / Mot M_Rated
p0335[0...n]	Motor cooling type / Mot cool type
p0341[0...n]	Motor moment of inertia / Mot M_mom of inert
p0342[0...n]	Ratio between the total and motor moment of inertia / Mot MomInert Ratio
p0344[0...n]	Motor weight (for the thermal motor model) / Mot weight th mod
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
p0350[0...n]	Motor stator resistance cold / Mot R_stator cold
p0352[0...n]	Cable resistance / R_cable
p0354[0...n]	Motor rotor resistance cold / Mot R_r cold
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 / Mot L_rot leak
p0360[0...n]	Motor magnetizing inductance / Mot Lh
p0362[0...n]	Motor saturation characteristic flux 1 / Mot saturat.flux 1
p0363[0...n]	Motor saturation characteristic flux 2 / Mot saturat.flux 2
p0364[0...n]	Motor saturation characteristic flux 3 / Mot saturat.flux 3
p0365[0...n]	Motor saturation characteristic flux 4 / Mot saturat.flux 4
p0366[0...n]	Motor saturation characteristic I_mag 1 / Mot sat. I_mag 1
p0367[0...n]	Motor saturation characteristic I_mag 2 / Mot sat. I_mag 2
p0368[0...n]	Motor saturation characteristic I_mag 3 / Mot sat. I_mag 3
p0369[0...n]	Motor saturation characteristic I_mag 4 / Mot sat. I_mag 4
r0382[0...n]	Motor magnetizing inductance transformed / Mot L_magn transf
r0384[0...n]	Motor rotor time constant / damping time constant d axis / Mot T_rotor/T_Dd
r0386[0...n]	Motor stator leakage time constant / Mot T_stator leak
r0394[0...n]	Rated motor power / Mot P_Rated
r0395[0...n]	Actual stator resistance / R_stator act
r0396[0...n]	Actual rotor resistance / R_rotor act
p0530[0...n]	Bearing version selection / Bearing vers sel
p0531[0...n]	Bearing code number selection / Bearing codeNo sel
p0532[0...n]	Bearing maximum speed / Bearing n_max
p0541[0...n]	Load gearbox code number / Load grbx CodeNo
p0542[0...n]	Load gearbox maximum speed / Load grbx n_max
p0543[0...n]	Load gearbox maximum torque / Load grbx M_max
p0544[0...n]	Load gearbox overall ratio (absolute value) numerator / Load grbx ratio N
p0545[0...n]	Load gearbox overall ratio (absolute value) denominator / Load grbx ratio D
p0546[0...n]	Load gearbox output direction of rotation inversion / Load grbx outp inv
p0550[0...n]	Brake type / Brake type
p0551[0...n]	Brake code number / Brake code no.
p0552[0...n]	Maximum brake speed / Brake n_max
p0553[0...n]	Brake holding torque / Brake M_hold
p0554[0...n]	Brake moment of inertia / Brake J
p0601[0...n]	Motor temperature sensor type / Mot_temp_sens type
p0604[0...n]	Mot_temp_mod 2/KTY alarm threshold / Mod 2/KTY A thresh
p0605[0...n]	Mot_temp_mod 1/2 threshold / Mod 1/2 threshold
p0606[0...n]	Mot_temp_mod 2/KTY timer / Mod 2/KTY t_timer
p0607[0...n]	Temperature sensor fault timer / Sensor fault time
p0610[0...n]	Motor overtemperature response / Mot temp response
p0611[0...n]	I2t motor model thermal time constant / I2t mot_mod T

p0612[0...n]	Mot_temp_mod activation / Mot_temp_mod act
p0614[0...n]	Thermal resistance adaptation reduction factor / Therm R_adapt red
p0615[0...n]	Mot_temp_mod 1 (I2t) fault threshold / I2t F thresh
p0620[0...n]	Thermal adaptation, stator and rotor resistance / Mot therm_adapt R
p0621[0...n]	Identification stator resistance after restart / Rst_ident Restart
p0622[0...n]	Motor excitation time for Rs_ident after powering up again / t_excit Rs_id
p0625[0...n]	Motor ambient temperature during commissioning / 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]	Motor overtemperature rotor / Mot T_over rotor
r0630[0...n]	Mot_temp_mod ambient temperature / Mod T_ambient
r0631[0...n]	Mot_temp_mod stator iron temperature / Mod T_stator
r0632[0...n]	Mot_temp_mod stator winding temperature / Mod T_winding
r0633[0...n]	Mot_temp_mod rotor temperature / Mod rotor temp
p0637[0...n]	Q flux flux gradient saturated / PSIQ Grad SAT
p0650[0...n]	Actual motor operating hours / Mot t_oper act
p0651[0...n]	Motor operating hours maintenance interval / Mot t_op maint
p0826[0...n]	Motor changeover motor number / Mot_chng mot No.
p1231[0...n]	DC braking configuration / DCBRK config
p1232[0...n]	DC braking braking current / DCBRK I_brake
p1233[0...n]	DC braking time / DCBRK time
p1234[0...n]	Speed at the start of DC braking / DCBRK n_start
p1909[0...n]	Motor data identification control word / MotID STW
p1980[0...n]	PolID technique / PolID technique
r3926[0...n]	Voltage generation alternating base voltage amplitude / U_gen altern base
r5398[0...n]	Mot_temp_mod 3 alarm threshold image p5390 / A thr image p5390
r5399[0...n]	Mot_temp_mod 3 fault threshold image p5391 / F thr image p5391

2.3.4

Power unit Data Sets (PDS)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: PDS

p0124[0...n]	CU detection via LED / CU detection LED
p0201[0...n]	Power unit code number / PU code no
r0204[0...n]	Power unit hardware properties / PU HW property

2.3.5

Encoder Data Sets (EDS)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: EDS

p0422[0...n]	Absolute encoder linear measuring step resolution / Enc abs meas step
--------------	---

2.4 BICO parameters (connectors/binectors)

2.4.1 Binector inputs (BI)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: BI

p0043	BI: Enable energy usage display / Enab energy usage
p0730	BI: CU signal source for terminal DO 0 / CU S_src DO 0
p0731	BI: CU signal source for terminal DO 1 / CU S_src DO 1
p0782[0...1]	BI: CU analog outputs invert signal source / CU AO inv S_src
p0806	BI: Inhibit master control / PcCtrl inhibit
p0810	BI: Command data set selection CDS bit 0 / CDS select., bit 0
p0820[0...n]	BI: Drive Data Set selection DDS bit 0 / DDS select., bit 0
p0840[0...n]	BI: ON / OFF (OFF1) / ON / OFF (OFF1)
p0844[0...n]	BI: No coast-down / coast-down (OFF2) signal source 1 / OFF2 S_src 1
p0845[0...n]	BI: No coast-down / coast-down (OFF2) signal source 2 / OFF2 S_src 2
p0848[0...n]	BI: No Quick Stop / Quick Stop (OFF3) signal source 1 / OFF3 S_src 1
p0849[0...n]	BI: No Quick Stop / Quick Stop (OFF3) signal source 2 / OFF3 S_src 2
p0852[0...n]	BI: Enable operation/inhibit operation / Operation enable
p0854[0...n]	BI: Control by PLC/no control by PLC / Master ctrl by PLC
p0855[0...n]	BI: Unconditionally release holding brake / Uncond open brake
p0856[0...n]	BI: Enable speed controller / n_ctrl enable
p0858[0...n]	BI: Unconditionally close holding brake / Uncond close brake
p0860	BI: Line contactor feedback signal / Line contact feedb
p1020[0...n]	BI: Fixed speed setpoint selection Bit 0 / n_set_fixed Bit 0
p1021[0...n]	BI: Fixed speed setpoint selection Bit 1 / n_set_fixed Bit 1
p1022[0...n]	BI: Fixed speed setpoint selection Bit 2 / n_set_fixed Bit 2
p1023[0...n]	BI: Fixed speed setpoint selection Bit 3 / n_set_fixed Bit 3
p1035[0...n]	BI: Motorized potentiometer setpoint raise / Mop raise
p1036[0...n]	BI: Motorized potentiometer lower setpoint / Mop lower
p1043[0...n]	BI: Motorized potentiometer accept setting value / MotP acc set val
p1055[0...n]	BI: Jog bit 0 / Jog bit 0
p1056[0...n]	BI: Jog bit 1 / Jog bit 1
p1110[0...n]	BI: Inhibit negative direction / Inhib neg dir
p1111[0...n]	BI: Inhibit positive direction / Inhib pos dir
p1113[0...n]	BI: Setpoint inversion / Setp inv
p1140[0...n]	BI: Enable ramp-function generator/inhibit ramp-function generator / RFG enable
p1141[0...n]	BI: Continue ramp-function generator/freeze ramp-function generator / Continue RFG
p1142[0...n]	BI: Enable setpoint/inhibit setpoint / Setpoint enable
p1201[0...n]	BI: Flying restart enable signal source / Fly_res enab S_src
p1230[0...n]	BI: DC braking activation / DC brake act
p1502[0...n]	BI: Freeze moment of inertia estimator / J_estim freeze
p2080[0...15]	BI: Binector-connector converter status word 1 / Bin/con ZSW1
p2103[0...n]	BI: 1. Acknowledge faults / 1. Acknowledge
p2104[0...n]	BI: 2. Acknowledge faults / 2. Acknowledge
p2106[0...n]	BI: External fault 1 / External fault 1
p2112[0...n]	BI: External alarm 1 / External alarm 1
p2200[0...n]	BI: Technology controller enable / Tec_ctrl enable
p2220[0...n]	BI: Technology controller fixed value selection bit 0 / Tec_ctrl sel bit 0
p2221[0...n]	BI: Technology controller fixed value selection bit 1 / Tec_ctrl sel bit 1
p2222[0...n]	BI: Technology controller fixed value selection bit 2 / Tec_ctrl sel bit 2
p2223[0...n]	BI: Technology controller fixed value selection bit 3 / Tec_ctrl sel bit 3
p2235[0...n]	BI: Technology controller motorized potentiometer raise setpoint / Tec_ctrl mop raise
p2236[0...n]	BI: Technology controller motorized potentiometer lower setpoint / Tec_ctrl mop lower

p2286[0...n]	BI: Hold technology controller integrator / Tec_ctr integ hold
p2290[0...n]	BI: Technology controller limiting enable / Tec_ctrl lim enab
p3330[0...n]	BI: 2/3 wire control command 1 / 2/3 wire cmd 1
p3331[0...n]	BI: 2/3 wire control command 2 / 2/3 wire cmd 2
p3332[0...n]	BI: 2/3 wire control command 3 / 2/3 wire cmd 3
p5614	BI: Pe set switching-on inhibited signal source / Pe sw on_inh s_src
p8542[0...15]	BI: Active STW1 in the BOP/IOP manual mode / STW1 act OP
p8558	BI: Select IOP manual mode / Sel IOP man mode
p8785	BI: CAN status word bit 8 / Status word bit 8
p8786	BI: CAN status word bit 14 / Status word bit 14
p8787	BI: CAN status word bit 15 / Status word bit 15

2.4.2 Connector inputs (CI)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: CI

p0771[0...1]	CI: CU analog outputs signal source / CU AO S_src
p1044[0...n]	CI: Motorized potentiometer setting value / Mop set val
p1070[0...n]	CI: Main setpoint / Main setpoint
p1071[0...n]	CI: Main setpoint scaling / Main setp scal
p1075[0...n]	CI: Suppl setp / Suppl setp
p1076[0...n]	CI: Supplementary setpoint scaling / Suppl setp scal
p1106[0...n]	CI: Minimum speed signal source / n_min s_src
p1138[0...n]	CI: Ramp-function generator ramp-up time scaling / RFG t_RU scal
p1139[0...n]	CI: Ramp-function generator ramp-down time scaling / RFG t_RD scal
p1330[0...n]	CI: U/f control independent voltage setpoint / Uf U_set independ.
p1352[0...n]	CI: Motor holding brake starting frequency signal source / Brake f_start
p1475[0...n]	CI: Speed controller torque setting value for motor holding brake / n_ctrl M_sv MHB
p1511[0...n]	CI: Supplementary torque 1 / M_suppl 1
p1522[0...n]	CI: Torque limit upper / M_max upper
p1523[0...n]	CI: Torque limit lower / M_max lower
p1552[0...n]	CI: Torque limit upper scaling without offset / M_max up w/o offs
p1554[0...n]	CI: Torque limit lower scaling without offset / M_max low w/o offs
p2016[0...3]	CI: Comm IF USS PZD send word / Comm USS send word
p2051[0...16]	CI: PROFIdrive PZD send word / PZD send word
p2061[0...15]	CI: PROFIBUS PZD send double word / PZD send DW
p2099[0...1]	CI: Connector-binector converter signal source / Con/bin S_src
p2253[0...n]	CI: Technology controller setpoint 1 / Tec_ctrl setp 1
p2254[0...n]	CI: Technology controller setpoint 2 / Tec_ctrl setp 2
p2264[0...n]	CI: Technology controller actual value / Tec_ctrl act val
p2289[0...n]	CI: Technology controller pre-control signal / Tec_ctr prectr_sig
p2296[0...n]	CI: Technology controller output scaling / Tec_ctrl outp scal
p2297[0...n]	CI: Technology controller maximum limit signal source / Tec_ctrMaxLimS_src
p2298[0...n]	CI: Technology controller minimum limit signal source / Tec_ctrl min_l s_s
p2299[0...n]	CI: Technology controller limit offset / Tech_ctrl lim offs
p8543	CI: Active speed setpoint in the BOP/IOP manual mode / N_act act OP
p8746[0...15]	CI: CAN free PZD send objects 16 bit / Free PZD send 16
p8748[0...7]	CI: CAN free PZD send objects 32 bit / Free PZD send 32

2.4.3 Binector outputs (BO)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: BO

r0751.0...9	BO: CU analog inputs status word / CU AI status word
-------------	--

r0785.0...1	BO: CU analog outputs status word / CU AO ZSW
r0807.0	BO: Master control active / PcCtrl active
r1025.0	BO: Fixed speed setpoint status / n_setp_fix status
r2043.0...2	BO: PROFIdrive PZD state / PD PZD state
r2090.0...15	BO: PROFIdrive PZD1 receive bit-serial / PZD1 recv bitw
r2091.0...15	BO: PROFIdrive PZD2 receive bit-serial / PZD2 recv bitw
r2092.0...15	BO: PROFIdrive PZD3 receive bit-serial / PZD3 recv bitw
r2093.0...15	BO: PROFIdrive PZD4 receive bit-serial / PZD4 recv bitw
r2094.0...15	BO: Connector-binector converter binector output / Con/bin outp
r2095.0...15	BO: Connector-binector converter binector output / Con/bin outp
r8540.0...15	BO: STW1 from BOP/IOP in the manual mode / STW1 OP

2.4.4 Connector outputs (CO)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: CO

r0021	CO: Actual speed smoothed / n_act smooth
r0025	CO: Output voltage smoothed / U_outp smooth
r0026	CO: DC link voltage smoothed / Vdc smooth
r0027	CO: Absolute actual current smoothed / I_act abs val smth
r0032	CO: Active power actual value smoothed / P_actv_act smth
r0034	CO: Motor utilization thermal / Mot_util therm
r0035	CO: Motor temperature / Mot temp
r0036	CO: Power unit overload I2t / PU overload I2t
r0037[0...19]	CO: Power unit temperatures / PU temperatures
r0039[0...2]	CO: Energy display / Energy displ
r0042[0...2]	CO: Process energy display / Process energy
r0060	CO: Speed setpoint before the setpoint filter / n_set before filt.
r0062	CO: Speed setpoint after the filter / n_set after filter
r0063[0...2]	CO: Speed actual value / n_act
r0064	CO: Speed controller system deviation / n_ctrl system dev
r0066	CO: Output frequency / f_outp
r0067	CO: Output current maximum / I_outp max
r0068[0...1]	CO: Absolute current actual value / I_act abs val
r0069[0...8]	CO: Phase current actual value / I_phase act val
r0070	CO: Actual DC link voltage / Vdc act val
r0072	CO: Output voltage / U_output
r0074	CO: Modulat_depth / Mod_depth
r0075	CO: Current setpoint field-generating / Id_set
r0076	CO: Current actual value field-generating / Id_act
r0077	CO: Current setpoint torque-generating / Iq_set
r0078	CO: Current actual value torque-generating / Iq_act
r0079	CO: Torque setpoint / M_set
r0080[0...1]	CO: Torque actual value / M_act
r0081	CO: Torque utilization / M_Utilization
r0082[0...2]	CO: Active power actual value / P_act
r0083	CO: Flux setpoint / Flex setp
r0084[0...1]	CO: Flux actual value / Flux act val
r0087	CO: Actual power factor / Cos phi act
r0289	CO: Maximum power unit output current / PU I_outp max
r0752[0...1]	CO: CU analog inputs input voltage/current actual / CU AI U/I_inp act
r0755[0...1]	CO: CU analog inputs actual value in percent / CU AI value in %
p0791[0...1]	CO: Fieldbus analog outputs / Fieldbus AO
r0944	CO: Counter for fault buffer changes / Fault buff change
p1001[0...n]	CO: Fixed speed setpoint 1 / n_set_fixed 1

p1002[0...n]	CO: Fixed speed setpoint 2 / n_set_fixed 2
p1003[0...n]	CO: Fixed speed setpoint 3 / n_set_fixed 3
p1004[0...n]	CO: Fixed speed setpoint 4 / n_set_fixed 4
p1005[0...n]	CO: Fixed speed setpoint 5 / n_set_fixed 5
p1006[0...n]	CO: Fixed speed setpoint 6 / n_set_fixed 6
p1007[0...n]	CO: Fixed speed setpoint 7 / n_set_fixed 7
p1008[0...n]	CO: Fixed speed setpoint 8 / n_set_fixed 8
p1009[0...n]	CO: Fixed speed setpoint 9 / n_set_fixed 9
p1010[0...n]	CO: Fixed speed setpoint 10 / n_set_fixed 10
p1011[0...n]	CO: Fixed speed setpoint 11 / n_set_fixed 11
p1012[0...n]	CO: Fixed speed setpoint 12 / n_set_fixed 12
p1013[0...n]	CO: Fixed speed setpoint 13 / n_set_fixed 13
p1014[0...n]	CO: Fixed speed setpoint 14 / n_set_fixed 14
p1015[0...n]	CO: Fixed speed setpoint 15 / n_set_fixed 15
r1024	CO: Fixed speed setpoint effective / n_set_fixed eff
r1045	CO: Mot. potentiometer speed setp. in front of ramp-fct. gen. / Mop n_set bef RFG
r1050	CO: Motor. potentiometer setpoint after the ramp-function generator / Mop setp after RFG
r1073	CO: Main setpoint effective / Main setpoint eff
r1077	CO: Supplementary setpoint effective / Suppl setpoint eff
r1078	CO: Total setpoint effective / Total setpoint eff
p1083[0...n]	CO: Speed limit in positive direction of rotation / n_limit pos
r1084	CO: Speed limit positive effective / n_limit pos eff
p1086[0...n]	CO: Speed limit in negative direction of rotation / n_limit neg
r1087	CO: Speed limit negative effective / n_limit neg eff
r1112	CO: Speed setpoint after minimum limiting / n_set aft min_lim
r1114	CO: Setpoint after the direction limiting / Setp after limit
r1119	CO: Ramp-function generator setpoint at the input / RFG setp at inp
r1149	CO: Ramp-function generator acceleration / RFG acceleration
r1150	CO: Ramp-function generator speed setpoint at the output / RFG n_set at outp
r1170	CO: Speed controller setpoint sum / n_ctrl setp sum
r1258	CO: Vdc controller output / Vdc_ctrl output
r1298	CO: Vdc controller output (U/f) / Vdc_ctrl output
r1337	CO: Actual slip compensation / Slip comp act val
r1343	CO: I_max controller frequency output / I_max_ctrl f_outp
r1348	CO: U/f control Eco factor actual value / U/f Eco fac act v
p1351[0...n]	CO: Motor holding brake starting frequency / Brake f_start
r1438	CO: Speed controller speed setpoint / n_ctrl n_set
r1445	CO: Actual speed smoothed / n_act smooth
r1482	CO: Speed controller I torque output / n_ctrl I-M_outp
r1493	CO: Moment of inertia total, scaled / M_inert tot scal
r1508	CO: Torque setpoint before supplementary torque / M_set bef. M_suppl
r1516	CO: Supplementary torque and acceleration torque / M_suppl + M_accel
p1520[0...n]	CO: Torque limit upper / M_max upper
p1521[0...n]	CO: Torque limit lower / M_max lower
p1524[0...n]	CO: Torque limit upper scaling / M_max upper scal
p1525[0...n]	CO: Torque limit lower scaling / M_max lower scal
r1526	CO: Torque limit upper without offset / M_max up w/o offs
r1527	CO: Torque limit lower without offset / M_max low w/o offs
r1538	CO: Upper effective torque limit / M_max upper eff
r1539	CO: Lower effective torque limit / M_max lower eff
r1547[0...1]	CO: Torque limit for speed controller output / M_max outp n_ctrl
p1563[0...n]	CO: Mom. of inertia estimator load torque direction of rotation pos. / J_est M pos
p1564[0...n]	CO: Mom. of inertia estimator load torque direction of rotation neg. / J_est M neg
p1570[0...n]	CO: Flux setpoint / Flex setp
r1598	CO: Total flux setpoint / Flux setp total

r1732[0...1]	CO: Direct-axis voltage setpoint / Direct U set
r1733[0...1]	CO: Quadrature-axis voltage setpoint / Quad U set
r1801[0...1]	CO: Pulse frequency / Pulse frequency
r2050[0...11]	CO: PROFIBUS PZD receive word / PZD recv word
r2060[0...10]	CO: PROFIdrive PZD receive double word / PZD recv DW
r2089[0...4]	CO: Send binector-connector converter status word / Bin/con ZSW send
r2120	CO: Sum of fault and alarm buffer changes / Sum buffer changed
r2131	CO: Actual fault code / Act fault code
r2132	CO: Actual alarm code / Actual alarm code
r2169	CO: Actual speed smoothed signals / n_act smth message
p2201[0...n]	CO: Technology controller fixed value 1 / Tec_ctrl fix val1
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
r2224	CO: Technology controller fixed value effective / Tec_ctr FixVal eff
r2245	CO: Technology controller mot. potentiometer setpoint before RFG / Tec_ctr mop befRFG
r2250	CO: Technology controller motorized potentiometer setpoint after RFG / Tec_ctr mop aftRFG
r2260	CO: Technology controller setpoint after ramp-function generator / Tec_ctr set aftRFG
r2262	CO: Technology controller setpoint after filter / Tec_ctr set aftFlt
r2266	CO: Technology controller actual value after filter / Tec_ctr act aftFlt
r2272	CO: Technology controller actual value scaled / Tech_ctrl act scal
r2273	CO: Technology controller system deviation / Tec_ctrl sys_dev
p2291	CO: Technology controller maximum limiting / Tec_ctrl max_lim
p2292	CO: Technology controller minimum limiting / Tec_ctrl min_lim
r2294	CO: Technology controller output signal / Tec_ctrl outp_sig
p2295	CO: Technology controller output scaling / Tec_ctrl outp scal
r2344	CO: Technology controller last speed setpoint (smoothed) / Tec_ctrl n_setp_sm
p2900[0...n]	CO: Fixed value 1 [%] / Fixed value 1 [%]
p2901[0...n]	CO: Fixed value 2 [%] / Fixed value 2 [%]
r2902[0...14]	CO: Fixed values [%] / Fixed values [%]
p2930[0...n]	CO: Fixed value M [Nm] / Fixed value M [Nm]
r3841	CO: Friction characteristic output / Frict outp
r8541	CO: Speed setpoint from BOP/IOP in the manual mode / N_set OP
r8745[0...15]	CO: CAN free PZD receive objects 16 bit / Free PZD recv 16
r8747[0...7]	CO: CAN free PZD receive objects 32 bit / Free PZD recv 32
r8762	CO: CAN operating mode display / Op mode display
r8784	CO: CAN status word / Status word
r8792[0]	CO: CAN velocity mode I16 setpoint / Vel mod I16 set
r8796[0]	CO: CAN profile velocity mode I32 setpoints / Pr vel mo I32 set
r8797[0]	CO: CAN profile torque mode I16 setpoints / Pr Tq mod I16 set

2.4.5 Connector/binector outputs (CO/BO)

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: CO/BO

r0046.0...31	CO/BO: Missing enable sig / Missing enable sig
r0050.0...1	CO/BO: Command Data Set CDS effective / CDS effective
r0051.0	CO/BO: Drive Data Set DDS effective / DDS effective
r0052.0...15	CO/BO: Status word 1 / ZSW 1
r0053.0...11	CO/BO: Status word 2 / ZSW 2
r0054.0...15	CO/BO: Control word 1 / STW 1
r0055.0...15	CO/BO: Supplementary control word / Suppl STW
r0056.0...15	CO/BO: Status word, closed-loop control / ZSW cl-loop ctrl
r0722.0...11	CO/BO: CU digital inputs status / CU DI status
r0723.0...11	CO/BO: CU digital inputs status inverted / CU DI status inv
r0835.2...8	CO/BO: Data set changeover status word / DDS_ZSW
r0836.0...1	CO/BO: Command Data Set CDS selected / CDS selected
r0837.0	CO/BO: Drive Data Set DDS selected / DDS selected
r0863.0...1	CO/BO: Drive coupling status word/control word / CoupleZSW/STW
r0898.0...14	CO/BO: Control word sequence control / STW seq_ctrl
r0899.0...13	CO/BO: Status word sequence control / ZSW seq_ctrl
r1198.0...15	CO/BO: Control word setpoint channel / STW setpoint chan
r1239.8...13	CO/BO: DC braking status word / DCBRK ZSW
r1406.4...15	CO/BO: Control word speed controller / STW n_ctrl
r1407.0...27	CO/BO: Status word speed controller / ZSW n_ctrl
r1408.0...14	CO/BO: Status word current controller / ZSW I_ctrl
r1838.0...15	CO/BO: Gating unit status word 1 / Gating unit ZSW1
r2129.0...15	CO/BO: Faults/alarms trigger word / F/A trigger word
r2135.12...15	CO/BO: Status word faults/alarms 2 / ZSW fault/alarm 2
r2138.7...15	CO/BO: Control word faults/alarms / STW fault/alarm
r2139.0...15	CO/BO: Status word faults/alarms 1 / ZSW fault/alarm 1
r2197.0...13	CO/BO: Status word monitoring 1 / ZSW monitor 1
r2198.0...13	CO/BO: Status word monitoring 2 / ZSW monitor 2
r2199.0...11	CO/BO: Status word monitoring 3 / ZSW monitor 3
r2225.0	CO/BO: Technology controller fixed value selection status word / Tec_ctr FixVal ZSW
r2349.0...13	CO/BO: Technology controller status word / Tec_ctrl status
r3113.0...15	CO/BO: NAMUR message bit bar / NAMUR bit bar
r3333.0...3	CO/BO: 2/3 wire control control word / 2/3 wire STW
r3840.0...8	CO/BO: Friction characteristic status word / Friction ZSW
r3859.0	CO/BO: Compound braking/DC quantity control status word / Comp-br/DC_ctr ZSW
r5613.0...1	CO/BO: Pe energy-saving active/inactive / Pe save act/inact
r8795.0...15	CO/BO: CAN control word / Control word
r9772.0...21	CO/BO: SI status (processor 1) / SI status P1
r9773.0...31	CO/BO: SI status (processor 1 + processor 2) / SI status P1+P2
r9872.0...21	CO/BO: SI status (processor 2) / SI Status P2

2.5 Parameters for write protection and know-how protection

2.5.1 Parameters with "WRITE_NO_LOCK"

The following list contains the parameters with the "WRITE_NO_LOCK" attribute.

These parameters are not affected by the write protection.

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: WRITE_NO_LOCK

p0003	Access level / Acc_level
p0010	Drive commissioning parameter filter / Drv comm. par_filt
p0124[0...n]	CU detection via LED / CU detection LED
p0791[0...1]	CO: Fieldbus analog outputs / Fieldbus AO
p0970	Reset drive parameters / Drive par reset
p0971	Save parameters / Save par
p0972	Drive unit reset / Drv_unit reset
p2111	Alarm counter / Alarm counter
p3950	Service parameter / Serv par
p3981	Faults acknowledge drive object / Faults ackn DO
p3985	Master control mode selection / PcCtrl mode select
p7761	Write protection / Write protection
p8805	Identification and maintenance 4 configuration / I&M 4 config
p8806[0...53]	Identification and Maintenance 1 / I&M 1
p8807[0...15]	Identification and Maintenance 2 / I&M 2
p8808[0...53]	Identification and Maintenance 3 / I&M 3
p8809[0...53]	Identification and Maintenance 4 / I&M 4
p9400	Safely remove memory card / Mem_card rem
p9484	BICO interconnections search signal source / BICO S_src srch

2.5.2 Parameters with "KHP_WRITE_NO_LOCK"

The following list contains the parameters with the "KHP_WRITE_NO_LOCK" attribute.

These parameters are not affected by the know-how protection.

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: KHP_WRITE_NO_LOCK

p0003	Access level / Acc_level
p0010	Drive commissioning parameter filter / Drv comm. par_filt
p0124[0...n]	CU detection via LED / CU detection LED
p0791[0...1]	CO: Fieldbus analog outputs / Fieldbus AO
p0970	Reset drive parameters / Drive par reset
p0971	Save parameters / Save par
p0972	Drive unit reset / Drv_unit reset
p2040	Fieldbus interface monitoring time / Fieldbus t_monit
p2111	Alarm counter / Alarm counter
p3950	Service parameter / Serv par
p3981	Faults acknowledge drive object / Faults ackn DO
p3985	Master control mode selection / PcCtrl mode select
p7761	Write protection / Write protection
p8805	Identification and maintenance 4 configuration / I&M 4 config
p8806[0...53]	Identification and Maintenance 1 / I&M 1
p8807[0...15]	Identification and Maintenance 2 / I&M 2
p8808[0...53]	Identification and Maintenance 3 / I&M 3
p8809[0...53]	Identification and Maintenance 4 / I&M 4

p8980	Ethernet/IPprofile / Eth/IP profile
p8981	Ethernet/IP ODVA STOP mode / Eth/IP ODVA STOP
p8982	Ethernet/IP ODVA speed scaling / Eth/IP ODVA n scal
p8983	Ethernet/IP ODVA torque scaling / Eth/IP ODVA M scal
p9400	Safely remove memory card / Mem_card rem
p9484	BICO interconnections search signal source / BICO S_src srch

2.5.3

Parameters with "KHP_ACTIVE_READ"

The following list contains the parameters with the "KHP_ACTIVE_READ" attribute.

These parameters can also be read with activated know-how protection.

Product: SINAMICS G120C, Version: 4705500, Language: eng, Type: KHP_ACTIVE_READ

p0015	Macro drive unit / Macro drv unit
p0100	IEC/NEMA mot stds / IEC/NEMA mot stds
p0170	Number of Command Data Sets (CDS) / CDS count
p0180	Number of Drive Data Sets (DDS) / DDS count
p0300[0...n]	Motor type selection / Mot type sel
p0304[0...n]	Rated motor voltage / Mot U _{rated}
p0305[0...n]	Rated motor current / Mot I _{rated}
p0505	Selecting the system of units / Unit sys select
p0595	Technological unit selection / Tech unit select
p0730	BI: CU signal source for terminal DO 0 / CU S _{src} DO 0
p0731	BI: CU signal source for terminal DO 1 / CU S _{src} DO 1
p0806	BI: Inhibit master control / PcCtrl inhibit
p0922	PROFIdrive PZD telegram selection / PZD telegr_sel
p1080[0...n]	Minimum speed / n _{min}
p1082[0...n]	Maximum speed / n _{max}
p1520[0...n]	CO: Torque limit upper / M _{max} upper
p2000	Reference speed reference frequency / n _{ref} f _{ref}
p2001	Reference voltage / Reference voltage
p2002	Reference current / I _{ref}
p2003	Reference torque / M _{ref}
p2006	Reference temp / Ref temp
p2030	Field bus int protocol selection / Field bus protocol
p2038	PROFIdrive STW/ZSW interface mode / PD STW/ZSW IF mode
p2079	PROFIdrive PZD telegram selection extended / PZD telegr_ext
p7763	KHP OEM exception list number of indices for p7764 / KHP OEM qty p7764
p7764[0...n]	KHP OEM exception list / KHP OEM excep list
p9601	SI enable functions integrated in the drive (processor 1) / SI enable fct P1
p9810	SI PROFIsafe address (processor 2) / SI PROFIsafe P2

2.6 Quick commissioning (p0010 = 1)

The parameters required for the quick commissioning (p0010 = 1) are shown in the following table:

Table 2-7 Quick commissioning (p0010 = 1)

Par. no.	Name	Access level		Can be changed
p0010	Drive, commissioning parameter filter	1		C(1)T
p0015	Macro drive unit	1		C(1)
p0096	Application class	1		C(1)
p0100	IEC/NEMA mot stds	1		C(1)
p0205	Power unit application	1		C(1,2)
p0230	Drive filter type, motor side	1		C(1,2)
p0300	Motor type selection	2		C(1,3)
p0301	Motor code number selection	2		C(1,3)
p0304	Rated motor voltage	1		C(1,3)
p0305	Rated motor current	1		C(1,3)
p0306	Number of motors connected in parallel	1		C(1,3)
p0307	Rated motor power	1		C(1,3)
p0308	Rated motor power factor	1		C(1,3)
p0309	Rated motor efficiency	1		C(1,3)
p0310	Rated motor frequency	1		C(1,3)
p0311	Rated motor speed	1		C(1,3)
p0316	Motor torque constant	4		C(1,3)UT
p0322	Maximum motor speed	1		C(1,3)
p0323	Maximum motor current	1		C(1,3)
p0335	Motor cooling type	2		C(1,3)T
p0500	Technology application	2	G120C CAN G120C DP G120C USS/MB G120C PN	C(1,5)T
p0500	Technology application	4	G120C PN	C(1,5)T
p0640	Current limit	2		C(1,3)UT
p0922	PROFIdrive telegram selection	1		C(1)T
p0970	Reset drive parameters	1		C(1,30)
p1080	Minimum speed	1		C(1)T
p1082	Maximum rotation speed	1		C(1)T
p1120	Ramp-function generator ramp-up time	1		C(1)UT
p1121	Ramp-function generator ramp-down time	1		C(1)UT
p1135	OFF3 ramp-down time	2		C(1)UT

Table 2-7 Quick commissioning (p0010 = 1), continued

Par. no.	Name	Access level		Can be changed
p1300	Open-loop/closed-loop control operating mode	2		C(1)T
p1900	Motor data identification and rotating measurement	2		C(1)T
p1905	Parameter tuning selection	1		C(1)T
p3900	Completion of quick commissioning	1		C(1)

If p0010 = 1 is selected, p0003 (user access level) can be used to select the parameters that are to be accessed.

At the end of the quick commissioning, set p3900 = 1 to perform the required motor calculations and reset all other parameters (not included in p0010 = 1) to their default settings.

Note

This only applies for the quick commissioning.

Function diagrams

Content

3.1	Table of contents	356
3.2	Explanations on the function diagrams	361
3.3	Input/output terminals	366
3.4	PROFInergy	375
3.5	PROFIdrive communication (PROFIBUS/PROFINET)	378
3.6	CANopen communication	392
3.7	Communication, fieldbus interface (USS, MODBUS)	399
3.8	Internal control/status words	405
3.9	Brake control	423
3.10	Safety Integrated Basic Functions	425
3.11	Safety Integrated PROFIsafe	431
3.12	Setpoint channel	433
3.13	Vector control	442
3.14	Vector control, Standard Drive Control (p0096 = 1)	467
3.15	Vector control, Dynamic Drive Control (p0096 = 2)	473
3.16	Technology functions	490
3.17	Technology controller	492
3.18	Signals and monitoring functions	497
3.19	Diagnostics	507
3.20	Data sets	513

3.1 Table of contents

3.2 Explanations on the function diagrams	361
1020 – Explanation of the symbols (part 1)	362
1021 – Explanation of the symbols (part 2)	363
1022 – Explanation of the symbols (part 3)	364
1030 – Handling BICO technology	365
3.3 Input/output terminals	366
2201 – Connection overview	367
2221 – Digital inputs, electrically isolated (DI 0 ... DI 5)	368
2241 – Digital outputs (DO 0 ... DO 1)	369
2250 – Analog input 0 (AI 0)	370
2255 – Analog inputs as digital inputs (DI 11)	371
2260 – Analog output 0 (AO 0)	372
2272 – Two-wire control	373
2273 – Three-wire control	374
3.4 PROFIenergy	375
2381 – Control commands and interrogation commands	376
2382 – States	377
3.5 PROFIdrive communication (PROFIBUS/PROFINET)	378
2401 – Overview	379
2410 – PROFIBUS (PB) / PROFINET (PN), addresses and diagnostics	380
2420 – Telegrams and process data (PZD)	381
2440 – PZD receive signals interconnection	382
2441 – STW1 control word interconnection (p2038 = 2)	383
2442 – STW1 control word interconnection (p2038 = 0)	384
2446 – STW3 control word interconnection	385
2450 – PZD send signals interconnection	386
2451 – ZSW1 status word interconnection (p2038 = 2)	387
2452 – ZSW1 status word interconnection (p2038 = 0)	388
2456 – ZSW3 status word interconnection	389
2468 – Receive telegram, free interconnection via BICO (p0922 = 999)	390
2470 – Send telegram, free interconnection via BICO (p0922 = 999)	391

3.6 CANopen communication	392
9204 – Receive telegram, free PDO mapping (p8744 = 2)	393
9206 – Receive telegram, Predefined Connection Set (p8744 = 1)	394
9208 – Send telegram, free PDO mapping (p8744 = 2)	395
9210 – Send telegram, Predefined Connection Set (p8744 = 1)	396
9220 – Control word, CANopen	397
9226 – Status word, CANopen	398
3.7 Communication, fieldbus interface (USS, MODBUS)	399
9310 – Configuration, addresses and diagnostics	400
9342 – STW1 control word interconnection	401
9352 – ZSW1 status word interconnection	402
9360 – Receive telegram, free interconnection via BICO (p0922 = 999)	403
9370 – Send telegram, free interconnection via BICO (p0922 = 999)	404
3.8 Internal control/status words	405
2501 – Control word, sequence control	406
2503 – Status word, sequence control	407
2505 – Control word, setpoint channel	408
2510 – Status word 1 (r0052)	409
2511 – Status word 2 (r0053)	410
2512 – Control word 1 (r0054)	411
2513 – Control word 2 (r0055)	412
2522 – Status word, speed controller	413
2526 – Status word, closed-loop control	414
2530 – Status word, closed-loop current control	415
2534 – Status word, monitoring functions 1	416
2536 – Status word, monitoring functions 2	417
2537 – Status word, monitoring functions 3	418
2546 – Control word, faults/alarms	419
2548 – Status word, faults/alarms 1 and 2	420
2610 – Sequence control - Sequencer	421
2634 – Sequence control - missing enable signals	422
3.9 Brake control	423
2701 – Basic brake control	424

3.10 Safety Integrated Basic Functions	425
2800 – Parameter manager	426
2802 – Monitoring functions and faults/alarms	427
2804 – Status words	428
2810 – STO: Safe Torque Off	429
2813 – F-DI: Fail-safe Digital Input	430
3.11 Safety Integrated PROFIsafe	431
2915 – Standard telegrams	432
3.12 Setpoint channel	433
3001 – Overview	434
3010 – Fixed speed setpoints, binary selection (p1016 = 2)	435
3011 – Fixed speed setpoints, direct selection (p1016 = 1)	436
3020 – Motorized potentiometer	437
3030 – Main/supplementary setpoint, setpoint scaling, jogging	438
3040 – Direction limitation and direction reversal	439
3050 – Skip frequency bands and speed limitations	440
3070 – Extended ramp-function generator	441
3.13 Vector control	442
6019 – Application classes (p0096), overview	443
6020 – Speed control and generation of the torque limits, overview	444
6030 – Speed setpoint, acceleration model	445
6035 – Moment of inertia estimator	446
6040 – Speed controller	447
6060 – Torque setpoint	448
6220 – Vdc_max controller and Vdc_min controller	449
6300 – U/f control, overview	450
6301 – U/f characteristic and voltage boost	451
6310 – Resonance damping and slip compensation (U/f)	452
6320 – Vdc_max controller	453
6490 – Speed control configuration	454
6630 – Upper/lower torque limit	455
6640 – Current/power/torque limits	456
6700 – Current control, overview	457
6710 – Current setpoint filter	458
6714 – Iq and Id controllers	459

6721 – Id setpoint (PMSM, p0300 = 2)	460
6722 – Field weakening characteristic, flux setpoint (ASM, p0300 = 1)	461
6723 – Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1)	462
6724 – Field weakening controller (PMSM, p0300 = 2)	463
6730 – Interface to the Power Module (ASM, p0300 = 1)	464
6731 – Interface to the Power Module (PMSM, p0300 = 2)	465
6799 – Display signals	466
3.14 Vector control, Standard Drive Control (p0096 = 1)	467
6850 – U/f control, overview (p0096 = 1)	468
6851 – U/f characteristic and voltage boost (p0096 = 1)	469
6853 – Resonance damping and slip compensation (U/f) (p0096 = 1)	470
6854 – Vdc_max controller (p0096 = 1)	471
6856 – Interface to the Power Module (p0096 = 1)	472
3.15 Vector control, Dynamic Drive Control (p0096 = 2)	473
6820 – Speed control and generation of the torque limits, overview (p0096 = 2)	474
6821 – Current control, overview (p0096 = 2)	475
6822 – Speed setpoint, precontrol symmetrization, acceleration model (p0096 = 2)	476
6823 – Moment of inertia estimator (p0096 = 2)	477
6824 – Speed controller with Kp_n/Tn_n adaptation) (p0096 = 2)	478
6826 – Torque setpoint (p0096 = 2)	479
6827 – Vdc_max controller and Vdc_min controller (p0096 = 2)	480
6828 – Current/power/torque limits (p0096 = 2)	481
6832 – Current setpoint filter (p0096 = 2)	482
6833 – Iq and Id controller (p0096 = 2)	483
6836 – Id setpoint (PMSM, p0300 = 2xx, p0096 = 2)	484
6837 – Field weakening characteristic, Id setpoint (ASM, p0300 = 1, p0096 = 2)	485
6838 – Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1, p0096 = 2)	486
6839 – Field weakening controller (PMSM, p0300 = 2xx, p0096 = 2)	487
6841 – Interface to the Power Module (ASM, p0300 = 1, p0096 = 2)	488
6842 – Interface to the Power Module (PMSM, p0300 = 2xx, p0096 = 2)	489
3.16 Technology functions	490
7017 – DC brake (p0300 = 1)	491

3.17 Technology controller	492
7950 – Fixed value selection binary (p2216 = 2)	493
7951 – Fixed value selection direct (p2216 = 1)	494
7954 – Motorized potentiometer	495
7958 – Closed-loop control	496
 3.18 Signals and monitoring functions	 497
8005 – Overview	498
8010 – Speed messages 1	499
8011 – Speed messages 2	500
8012 – Torque signals, motor blocked/stalled	501
8016 – Thermal monitoring, motor	502
8017 – Thermal motor models	503
8019 – Thermal monitoring, power unit	504
8020 – Monitoring functions 1	505
8021 – Monitoring functions 2	506
 3.19 Diagnostics	 507
8050 – Overview	508
8060 – Fault buffer	509
8065 – Alarm buffer	510
8070 – Faults/alarms trigger word (r2129)	511
8075 – Faults/alarms configuration	512
 3.20 Data sets	 513
8560 – Command Data Sets (CDS)	514
8565 – Drive Data Sets (DDS)	515

3.2 Explanations on the function diagrams

Function block diagrams

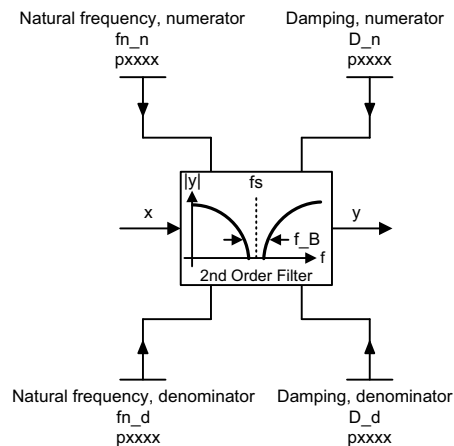
1020 – Explanation of the symbols (part 1)	362
1021 – Explanation of the symbols (part 2)	363
1022 – Explanation of the symbols (part 3)	364
1030 – Handling BICO technology	365

Parameters		Connectors		Binectors		Data sets	
Symbol	Meaning	Symbol	Meaning	Symbol	Meaning	Symbol	Meaning
Parameter name [Unit] rxxx[y..z] ↑	Monitoring parameter with unit [Unit] and index range [y..z] or data set [C/D]	Parameter name pxxx[y..z] ⌋ (Def)	Connector input CI with index range [y..z] or data set [C/D] and factory setting (Def) *)	Parameter name pxxxx[y..z] ⌋ (Def.y)	Binector input BI with with index range [y..z] or data set [C/D] and factory setting.bit number (Def)	pxxxx[C] ↓	Parameter belongs to the Command Data Set (CDS).
Parameter name from ... to [Unit] pxxxx[C/D] (Def) ↓	Setting parameter with min/max value and unit [Unit] data set [C/D] and factory setting (Def) *)	Parameter name [Unit] rxxx[y..z] ⌋	Connector output CO with unit [Unit] and with index range [y..z]	Parameter name rxxx ⌋	Binector output BO	pxxxx[D] ↓	Parameter belongs to the Drive Data Set (DDS).
		Connectors/binectors		Pre-assigned connectors and binectors		pxxxx[E] ↓	Parameter belongs to the Encoder Data Set (EDS).
		Symbol	Meaning	Symbol	Meaning	pxxxx[M] ↓	Parameter belongs to the Motor Data Set (MDS).
		Parameter name rxxx ⌋ rxxx ⌋	Connector/binector output CO/BO	Parameter name from ... to [Unit] pxxxx[D] (Def) ⌋	Setting parameter with min/max value and unit [Unit] data set [D] and factory setting (Def)	pxxxx[P] ↓	Parameter belongs to the Power unit Data Set (PDS).
Information on parameters, binectors, connectors				Cross references between diagrams			
Symbol	Meaning			Symbol	Meaning		
Parameter name	Parameter name (up to 18 characters)			Signal path	The function diagrams are sub-divided into signal paths 1...8 in order to facilitate orientation.		
[Unit]	[dimension unit]			Text → [aaaa.b]	Text = Unique signal designation aaaa = Signal to target diagram aaa b = Signal to signal path b		
rxxx[y] or rxxx[y...z] or rxxx[y].ww or rxxx.ww	"r" = monitoring parameter. These parameters are read-only "xxxx" stands for the parameter number "[y]" specifies the applicable index, "[y...z]" specifies the index range ".ww" specifies the bit number (e.g. 0...15).			[cccc.d] → Text	Text = Unique signal designation cccc = Signal from source diagram cccc d = Signal from signal path d		
pxxxx[y] or pxxxx[y...z] or pxxxx[y].ww or pxxxx.ww				To "function diagram name" [aaaa.b] = binectors.			
from ... to	Value range.			Cross references for control bits			
(xxxx[y].ww)	Parameter number (xxxx) with Index number [y] and bit number .ww.			Symbol	Meaning		
(Def)	Factory setting.			pxxxx	pxxxx= Original parameter of signal		
(Def.w)	Factory setting with bit number as prefix.			[aaaa.b]	aaaa = Signal from source diagram aaaa b = Signal from signal path b		
[aaaa.b]	Diagram references for setting parameters that occur a multiple number of times. [Function diagram number, signal path]						
*) For some parameters the value for the factory setting is calculated during commissioning for they are dependent on Power Module and motor (see Section 2.1.1 "Calculated").							
1	2	3	4	5	6	7	8
Explanations on the function diagrams					fp_1020_97_61.vsd	Function diagram	
Explanation of the symbols (part 1)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 1020 -

Fig. 3-1 1020 – Explanation of the symbols (part 1)

Pre-assigned connectors and binectors		Symbols for logic functions		Symbols for computational and closed-loop control functions			
Fixed percentage values <div><div><div>Fixed value 1 [%] -10000.00 ... 10000.00 [%] p2900 [D] (0.00)</div><div>Fixed value 1 [%] -10 000.00...10 000.00 [%] p2900[D] (0.00)</div></div>or<div><div>Fixed value 2 [%] -10 000.00...10 000.00 [%] p2901[D] (0.00)</div><div>Fixed values [%] p2902[0...14] (0.00)</div></div><div><div>p2902[0] = +0 % p2902[1] = +5 % p2902[2] = +10 % p2902[3] = +20 % p2902[4] = +50 %</div><div>p2902[5] = +100 % p2902[6] = +150 % p2902[7] = +200 % p2902[8] = -5 % p2902[9] = -10 %</div><div>p2902[10] = -20 % p2902[11] = -50 % p2902[12] = -100 % p2902[13] = -150 % p2902[14] = -200 %</div></div></div>		<div><div><div><div>1</div></div></div><div>Logical inversion</div></div> <div><div><div>&</div></div></div> <div>AND element</div> <div>with logical inversion of an input signal</div> <div><div><div>≥1</div></div></div> <div>OR element</div> <div><div><div><div>x₁</div><div>=1</div><div>y</div></div><div>x₂</div></div><div>Exclusiv-OR/XOR</div><div>y = 1 when x₁ ≠ x₂ is.</div></div> <div><div><div><div>x₁</div><div>=</div><div>y</div></div><div>x₂</div></div><div>Comparator</div><div>y = 1 when x₁ = x₂ is.</div></div> <div><div><div><div>S</div><div>Q</div></div><div><div>R</div><div>Q̄</div></div></div><div>R/S flip-flop</div><div>S = setting input R = reset input Q = non-inverted output Q̄ = inverted output</div></div>		<div><div><div><div>S</div><div>1</div><div>0</div></div><div>y</div></div><div>Threshold value switch 1/0</div><div>Outputs at y a logical "1" if x < S.</div></div> <div><div><div><div>S</div><div>1</div><div>0</div></div><div>y</div></div><div>Threshold value switch 0/1</div><div>Outputs at y a logical "1" if x > S.</div></div> <div><div><div><div>S</div><div>1</div><div>0</div></div><div>y</div></div><div>Threshold value 1/0 with hysteresis</div><div>Outputs a logical "1" at y if x < S. If x ≥ S + H then y returns to 0.</div></div> <div><div><div><div>S</div><div>1</div><div>0</div></div><div>y</div></div><div>Threshold value 0/1 with hysteresis</div><div>Outputs a logical "1" at y if x > S. If x ≤ S - H then y returns to 0.</div></div> <div><div><div><div>LU</div><div>MLU</div><div>LL</div><div>MLL</div></div><div>y</div></div><div>Limiter</div><div>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.</div></div> <div><div><div><div>SET</div><div>S & H</div></div><div>y</div></div><div>Sample & Hold element</div><div>Sample and hold element. y = x if SET = 1 (not retentively saved at POWER OFF)</div></div>			
Fixed speed values <div><div><div>n_set_fixed 1 -210000.000 ... 210000.000 [rpm] p1001 [D] (0.000)</div><div>n_set_fixed 1 -210 000.000...210 000.000 [1/min] p1001[D] (0.000)</div></div>or<div><div>n_set_fixed 15 -210 000.000...210 000.000 [1/min] p1015[D] (0.000)</div></div></div>		Symbols for computational and closed-loop control functions <div><div><div><div>-1</div></div><div>y</div></div><div>Sign reversal</div><div>y = -x</div></div> <div><div><div><div>x</div><div>y</div></div></div><div>Absolute value generator</div><div>y = x </div></div> <div><div><div><div>x₁</div><div>÷</div><div>y</div></div><div>x₂</div></div><div>Divider</div><div>$y = \frac{x_1}{x_2}$</div></div> <div><div><div><div>x₁</div><div>×</div><div>y</div></div><div>x₂</div></div><div>Multiplier</div><div>y = x₁ • x₂</div></div> <div><div><div><div>x</div><div>>0</div><div>y</div></div></div><div>Comparator greater than 0</div><div>y = 1, if the analog signal x > 0, i.e. is positive.</div></div> <div><div><div><div><div>d</div><div>dt</div></div><div>y</div></div><div>x</div></div><div>Differentiator</div><div>$y = \frac{dx}{dt}$</div></div>		<div><div><div><div>LU</div><div>MLU</div><div>LL</div><div>MLL</div></div><div>y</div></div><div>Limiter</div><div>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.</div></div> <div><div><div><div>SET</div><div>S & H</div></div><div>y</div></div><div>Sample & Hold element</div><div>Sample and hold element. y = x if SET = 1 (not retentively saved at POWER OFF)</div></div>			
Fixed torque value <div><div><div>Fixed value M [Nm] -100000.00 ... 100000.00 [Nm] p2930 [D] (0.00)</div><div>Fixed value M [Nm] -100 000.00...100 000.00 [Nm] p2930[D] (0.00)</div></div>or<div><div>Fixed value M [Nm] -100 000.00...100 000.00 [Nm] p2930[D] (0.00)</div></div></div>		Symbol for monitoring <div><div><div>Monitoring</div></div><div>Axxxxx or Fxxxxx</div><div>Monitoring</div><div>In the bottom right-hand corner of the diagram.</div></div>					
1	2	3	4	5	6	7	8
Explanations on the function diagrams					fp_1021_97_61.vsd	Function diagram	
Explanation of the symbols (part 2)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 1021 -

2nd-order filter (bandstop/general filter)



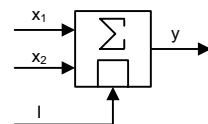
Used as bandstop filter

- center frequency f_s :
 $f_{n_n} = f_s$
 $f_{n_d} = f_s$
- bandwidth f_B :
 $D_{n_n} = 0$
 $D_{d_d} = \frac{f_B}{2 \cdot f_s}$

Transfer function when used as general filter

$$H(s) = \frac{\left(\frac{s}{2\pi f_{n_n}}\right)^2 + \frac{2 \cdot D_{n_n}}{2\pi f_{n_n}} \cdot s + 1}{\left(\frac{s}{2\pi f_{n_d}}\right)^2 + \frac{2 \cdot D_{d_d}}{2\pi f_{n_d}} \cdot s + 1}$$

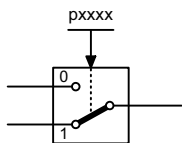
Analog adder can be activated



The following applies to $l = 1$ signal: $y = x_1 + x_2$

The following applies to $l = 0$ signal: $y = x_1$

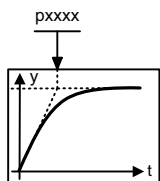
Switch symbol



Simple changeover switch

The switch position is shown according to the factory setting (in this case, switch position 1 in the default state on delivery).

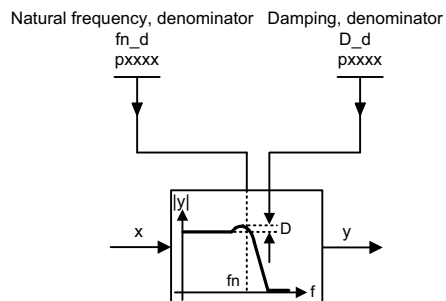
PT1 element



Delay element, first order.

pxxxx = time constant

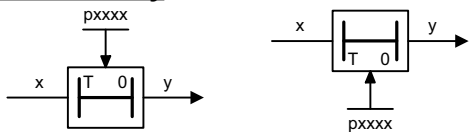
PT2 low pass



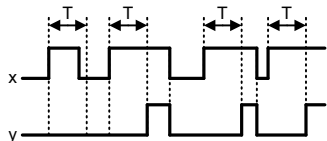
Transfer function

$$H(s) = \frac{1}{\left(\frac{s}{2\pi f_{n_d}}\right)^2 + \frac{2 \cdot D_{d_d}}{2\pi f_{n_d}} \cdot s + 1}$$

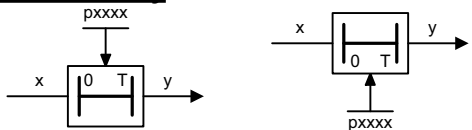
Switch-on delay



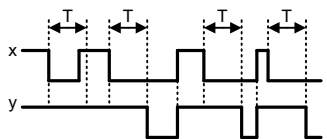
The digital signal x must have the value "1" without any interruption during the time T before output y changes to "1".



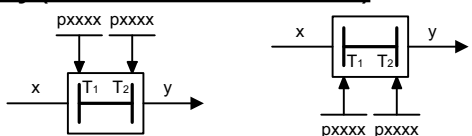
Switch-off delay



The digital signal x must have the value "0" without interruption during the time T before output y changes to "0".



Delay (switch-on and switch-off)



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.

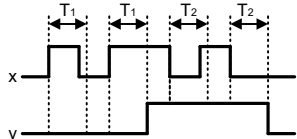


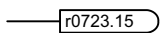
Fig. 3-3

1022 – Explanation of the symbols (part 3)

1	2	3	4	5	6	7	8	
Explanations on the function diagrams					fp_1022_97_61.vsd	Function diagram		- 1022 -
Explanation of the symbols (part 3)					11.03.2015 V4.7.3	SINAMICS G120C		

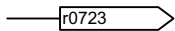
Handling BICO technology

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 variables, speeds or torques). Connectors are also "CO:" display parameters (CO = Connector Output).

Parameterization:

At the signal destination, the required binector or connector is selected using appropriate parameters:

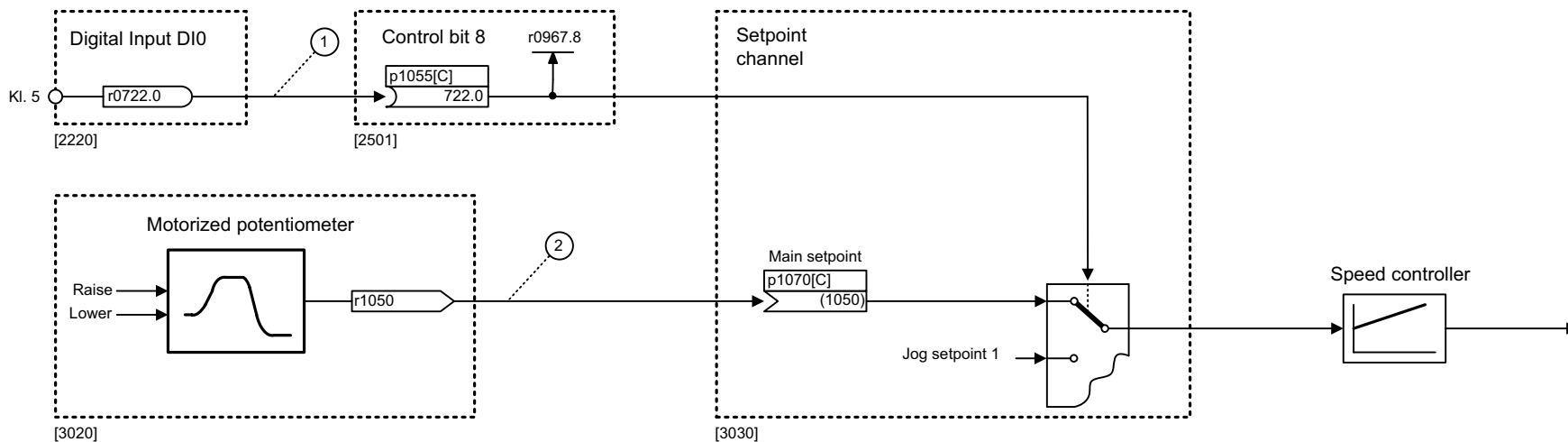
"BI:" parameter for binectors (BI = Binector Input)

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 "jog" command (BI: p1055) from Digital Input DI0 (BO: r0722.0, Terminal 5 (KI. 5)) on the CU.



Parameterizing steps:

- ① p1055[0] = 722.0 Terminal 5 (KI. 5) acts as "Jog bit 0".
- ② p1070[0] = 1050 The output of the motorized potentiometer acts as main setpoint for the speed controller.

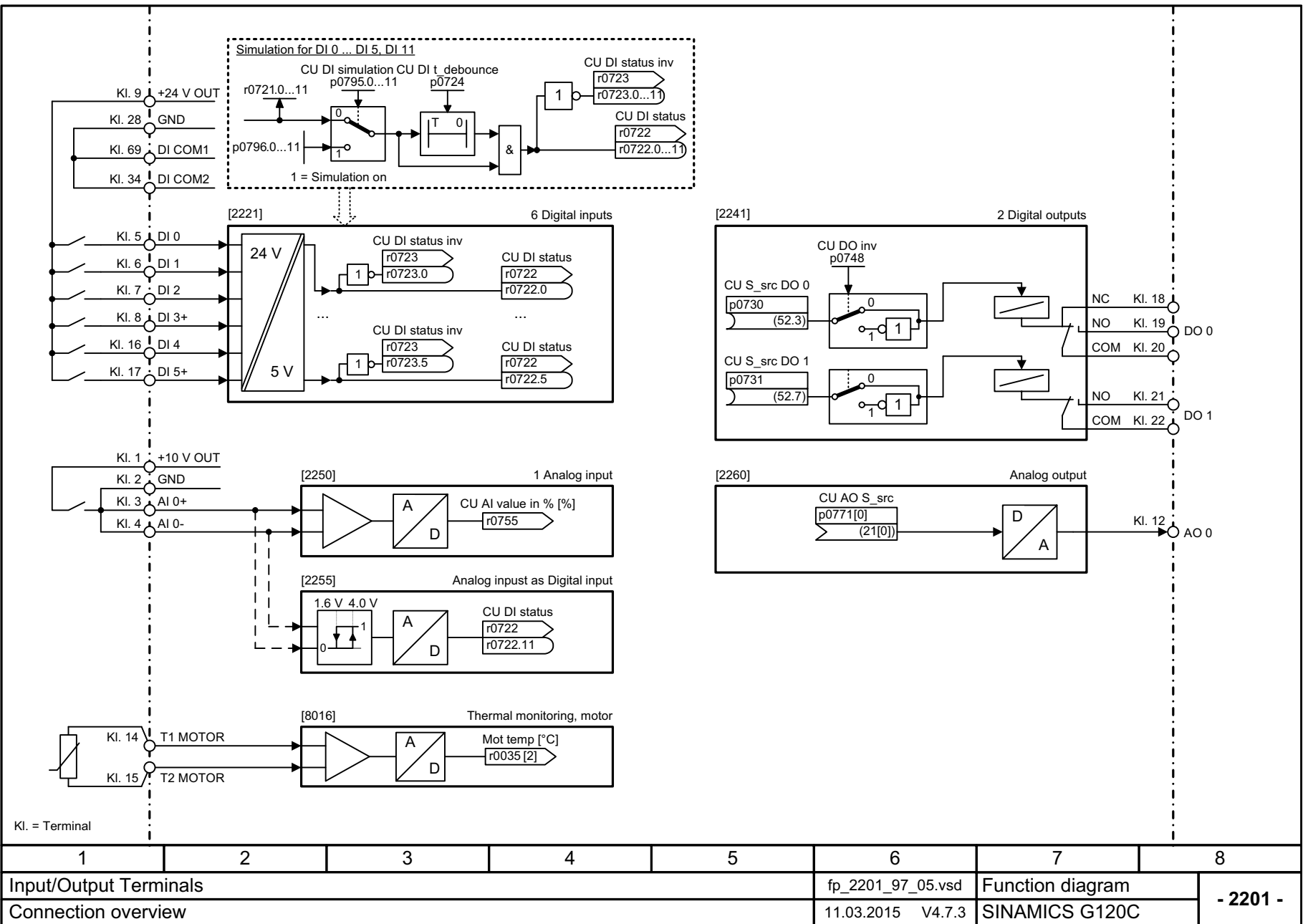
1	2	3	4	5	6	7	8
Explanations on the function diagrams					fp_1030_97_61.vsd	Function diagram	- 1030 -
Handling BICO technology					11.03.2015 V4.7.3	SINAMICS G120C	

Fig. 3-4 1030 – Handling BICO technology

3.3 Input/output terminals

Function block diagrams

2201 – Connection overview	367
2221 – Digital inputs, electrically isolated (DI 0 ... DI 5)	368
2241 – Digital outputs (DO 0 ... DO 1)	369
2250 – Analog input 0 (AI 0)	370
2255 – Analog inputs as digital inputs (DI 11)	371
2260 – Analog output 0 (AO 0)	372
2272 – Two-wire control	373
2273 – Three-wire control	374



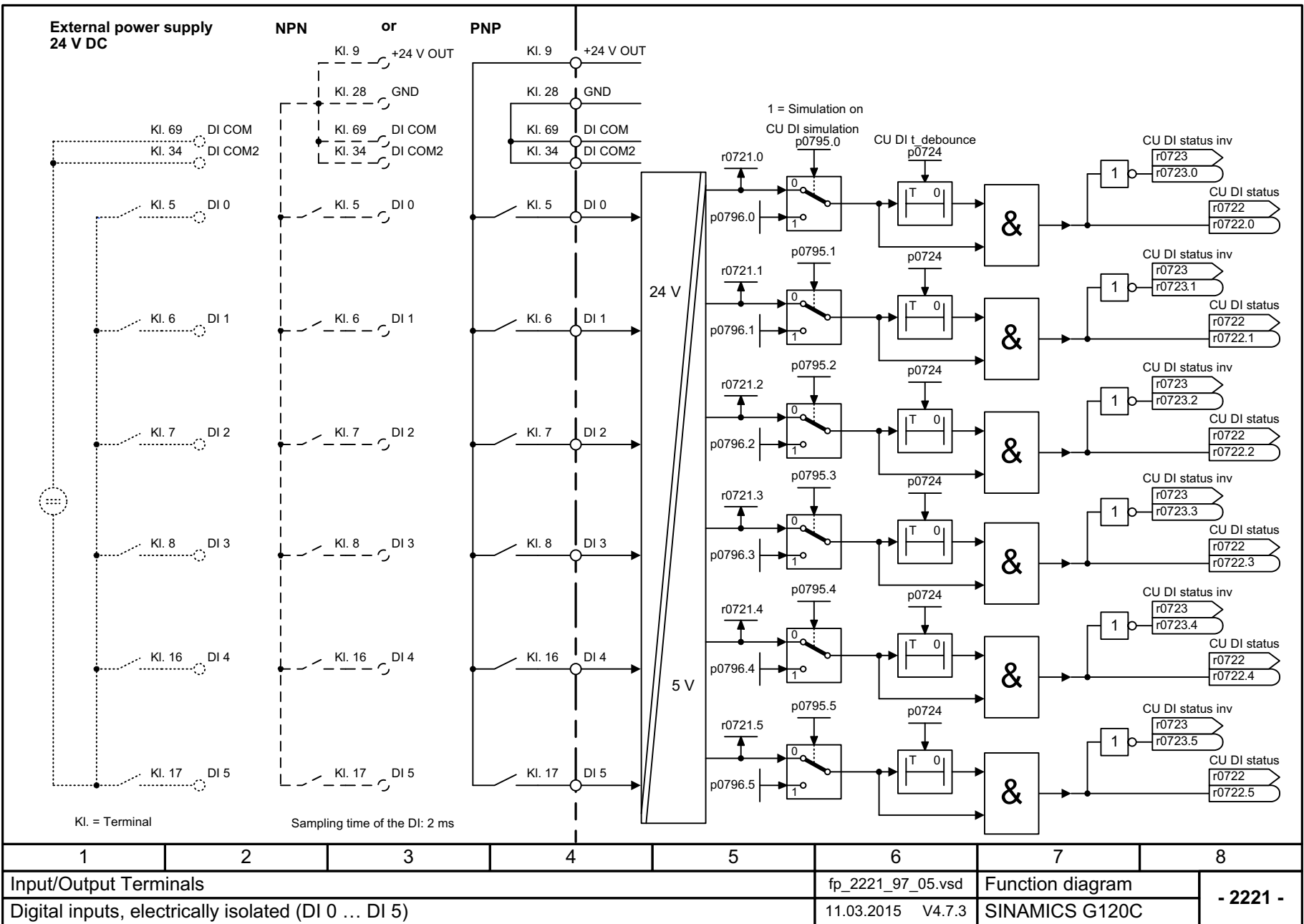
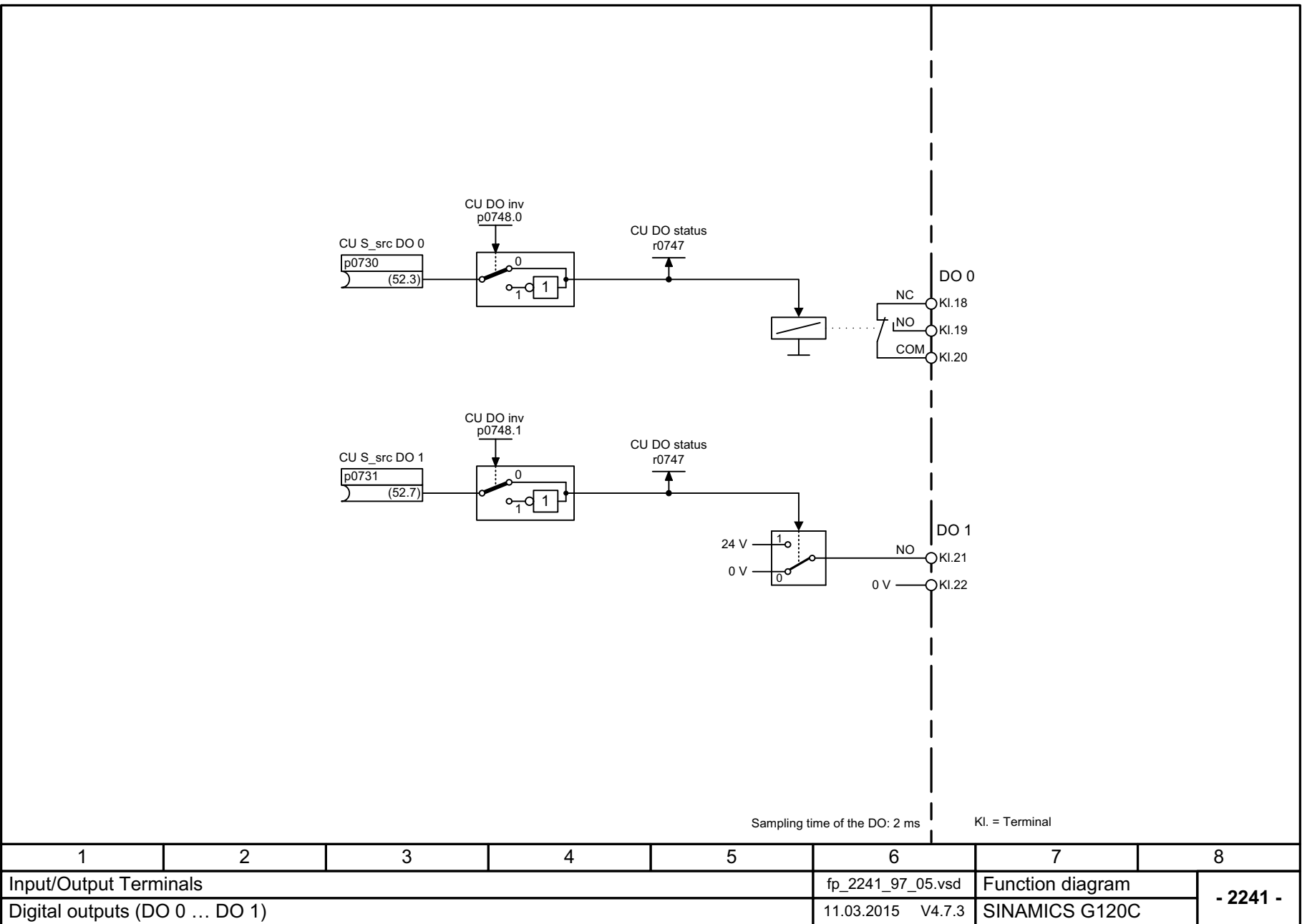
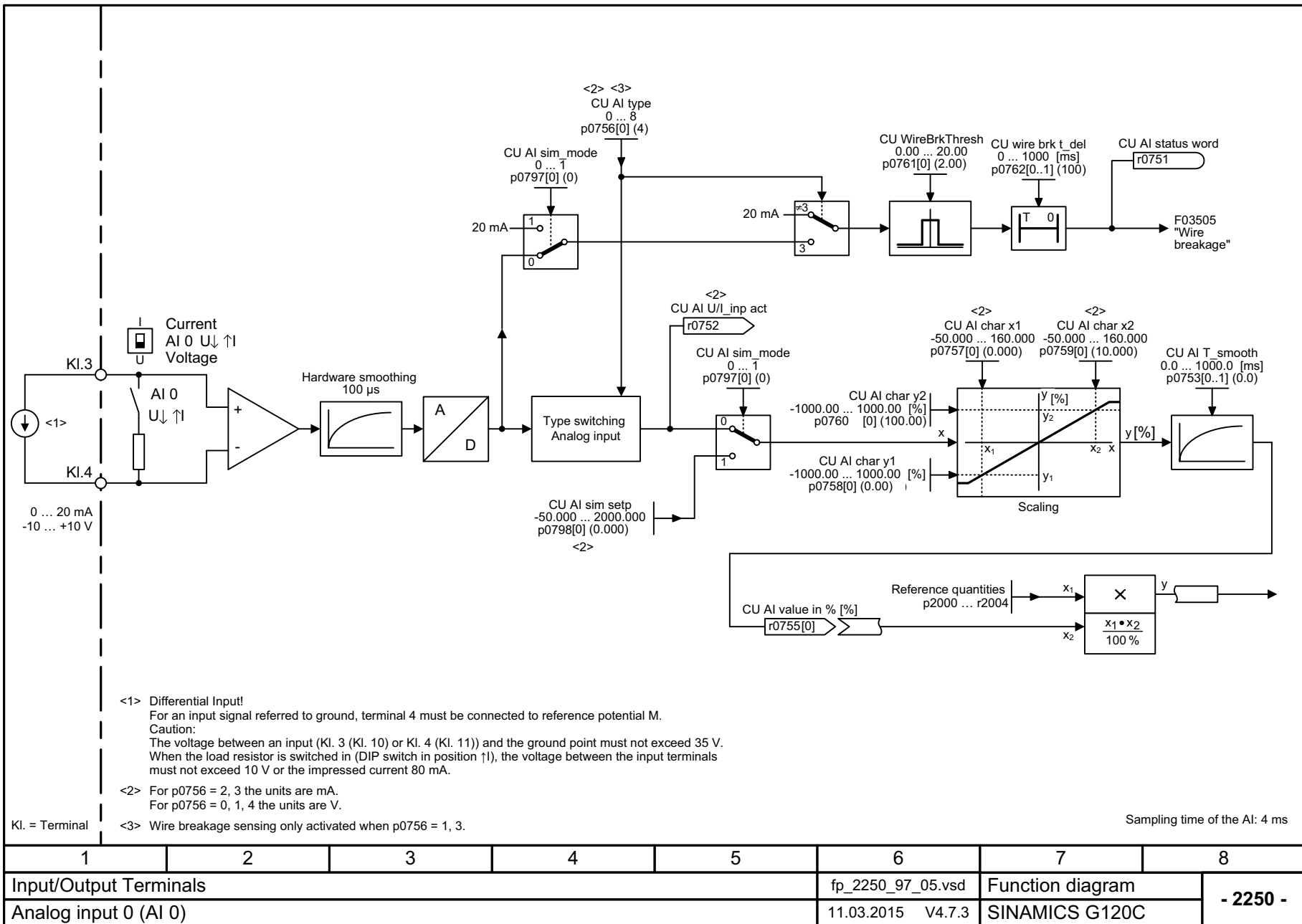
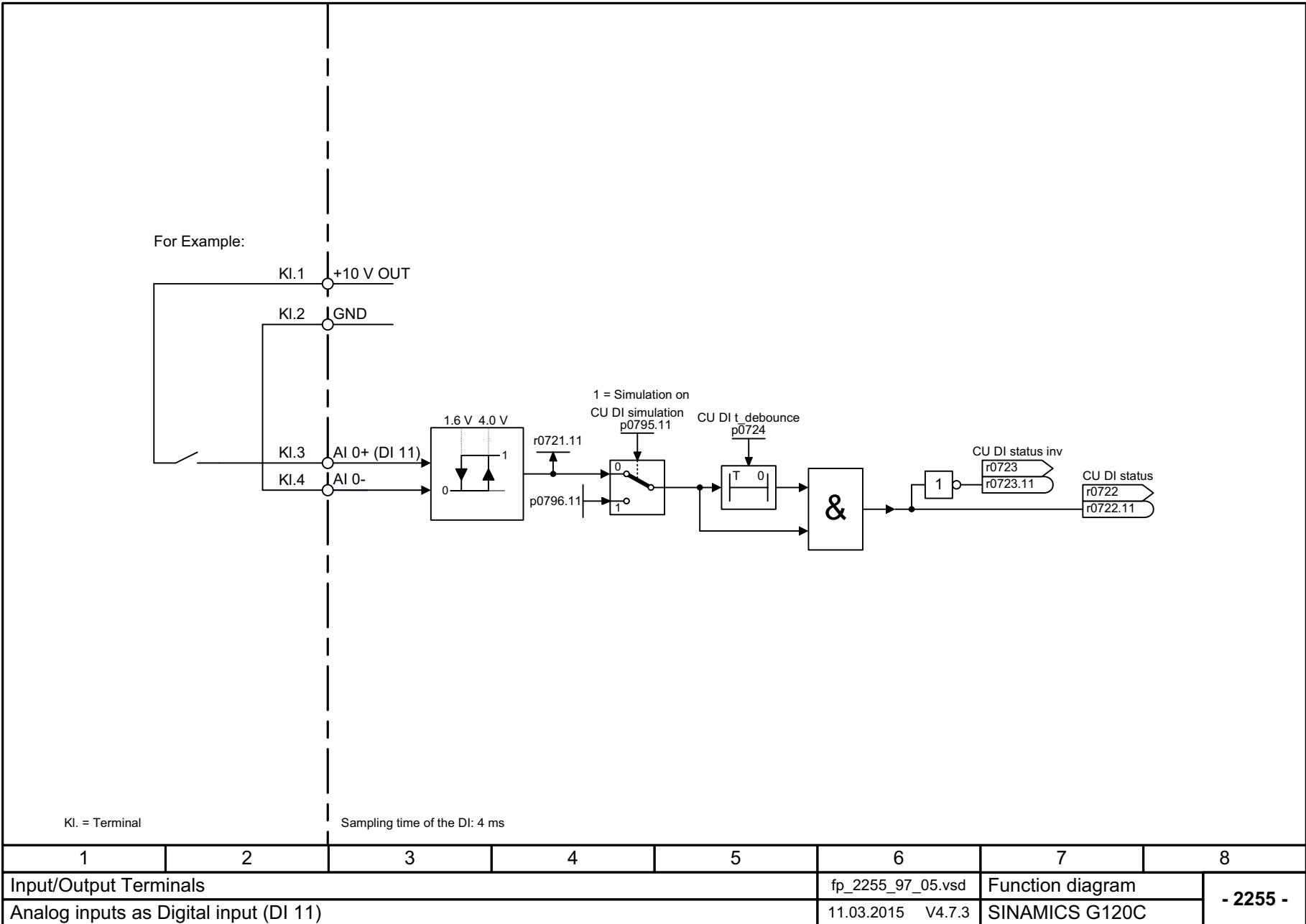


Fig. 3-6

2221 – Digital inputs, electrically isolated (DI 0 ... DI 5)







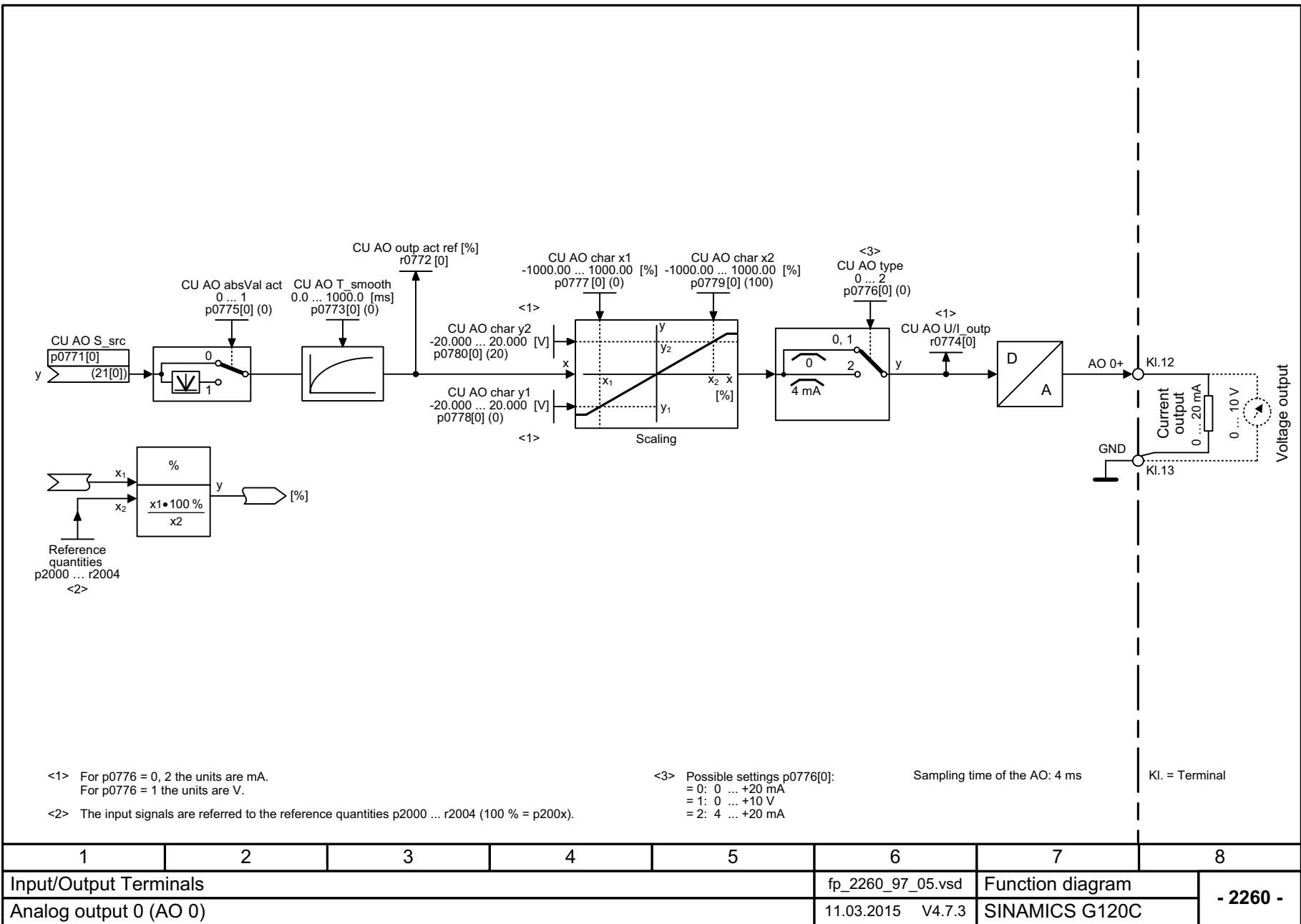
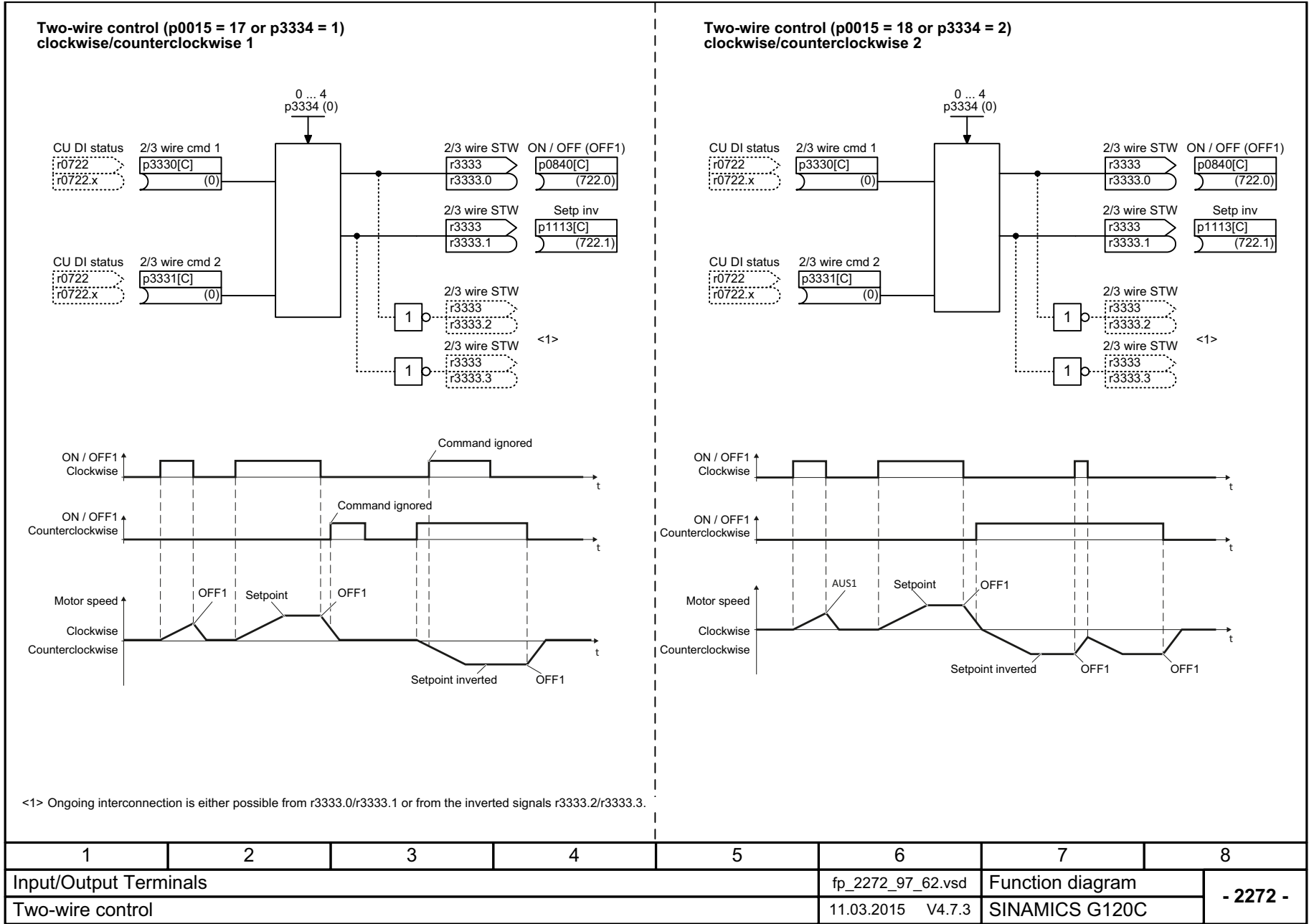
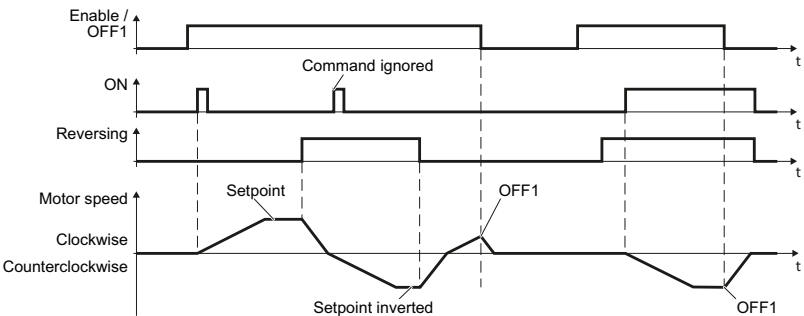
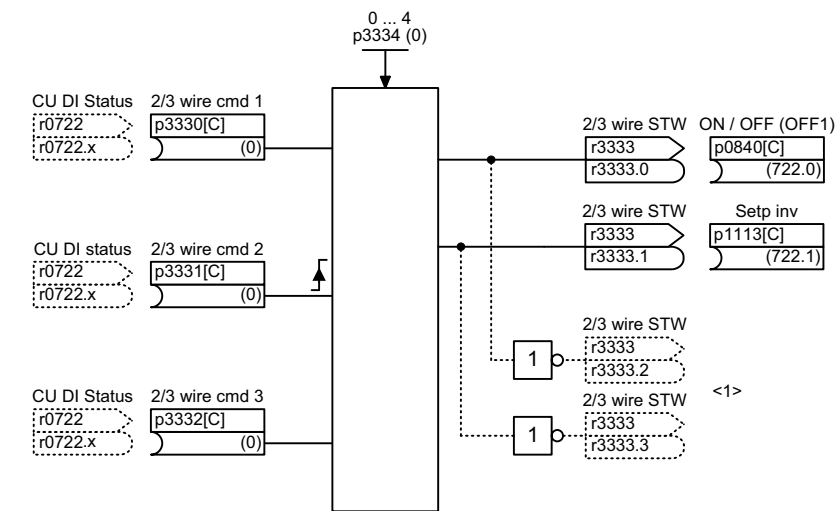


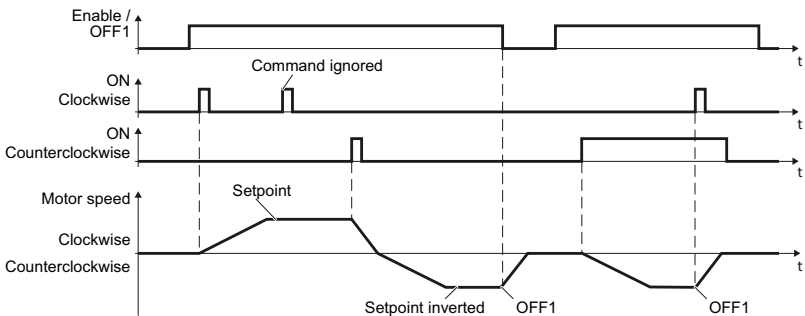
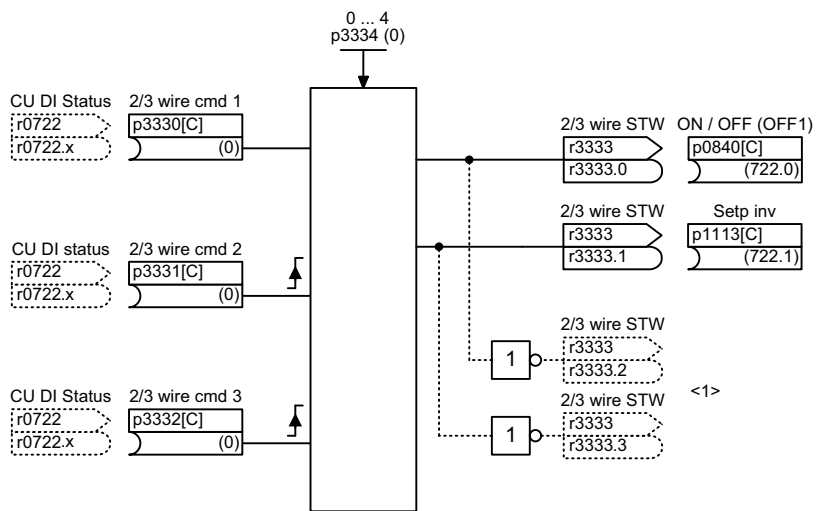
Fig. 3-11 2272 – Two-wire control



Three-wire control (p0015 = 20 or p3334 = 4)
enable ON/reversing



Three-wire control (p0015 = 19 or p3334 = 3)
enable clockwise/counterclockwise



<1> Ongoing interconnection is either possible from r3333.0/r3333.1 or from the inverted signals r3333.2/r3333.3.

1	2	3	4	5	6	7	8
Input/Output Terminals					fp_2273_97_62.vsd	Function diagram	
Three-wire control					11.03.2015 V4.7.3	SINAMICS G120C	

- 2273 -

Fig. 3-12 2273 – Three-wire control

3.4 PROFlenergy

Function block diagrams

2381 – Control commands and interrogation commands	376
2382 – States	377

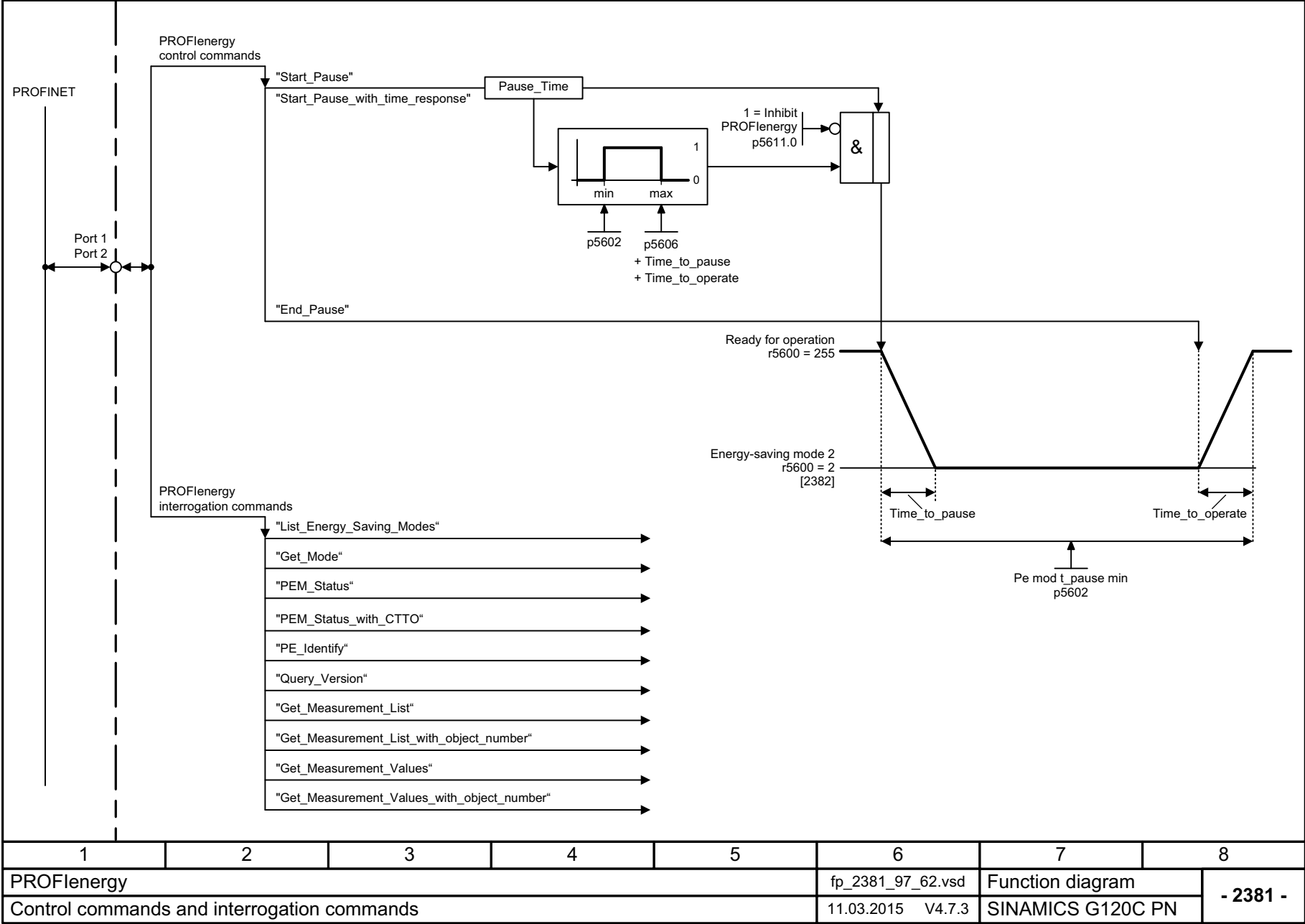
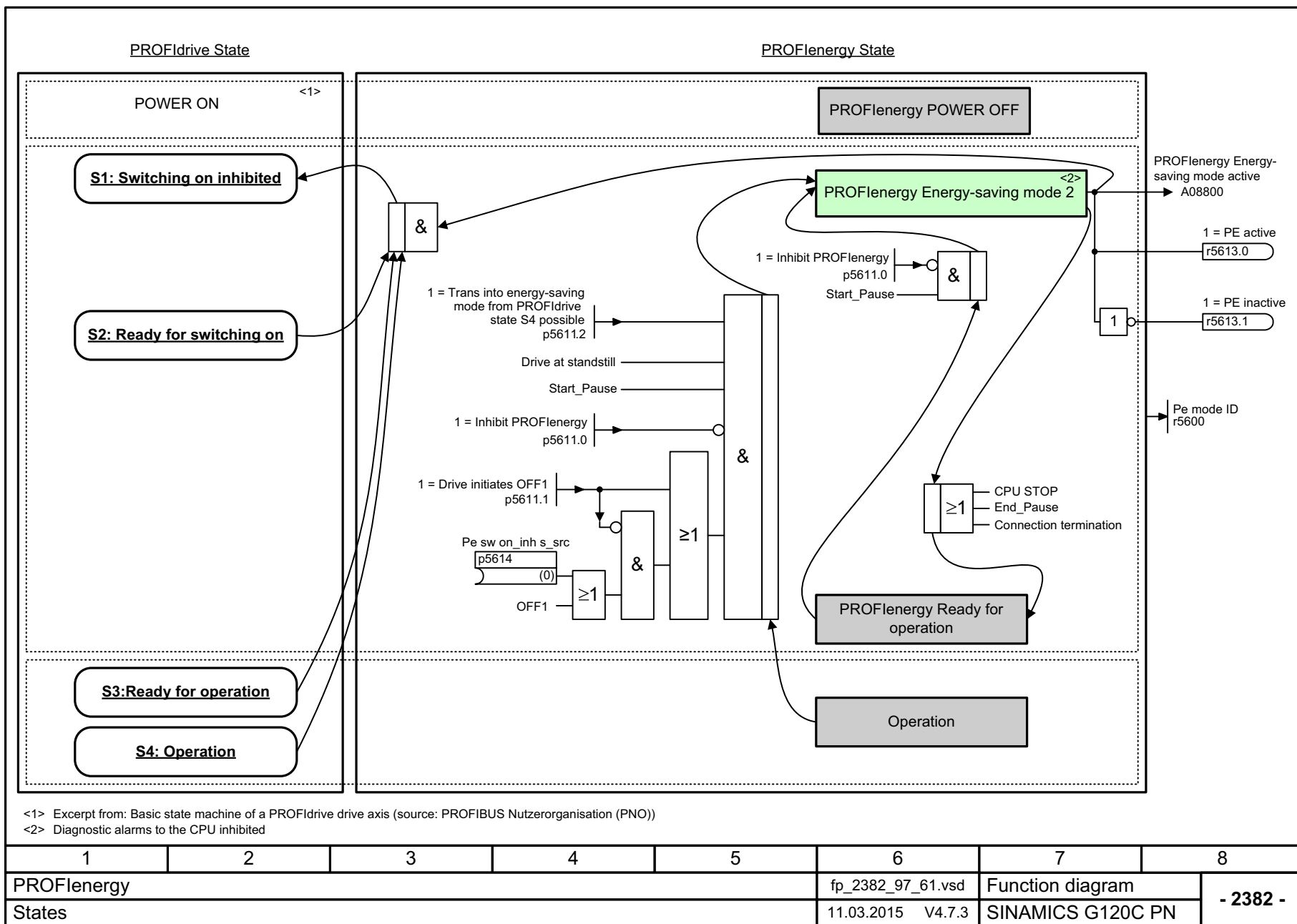


Fig. 3-13 2381 – Control commands and interrogation commands

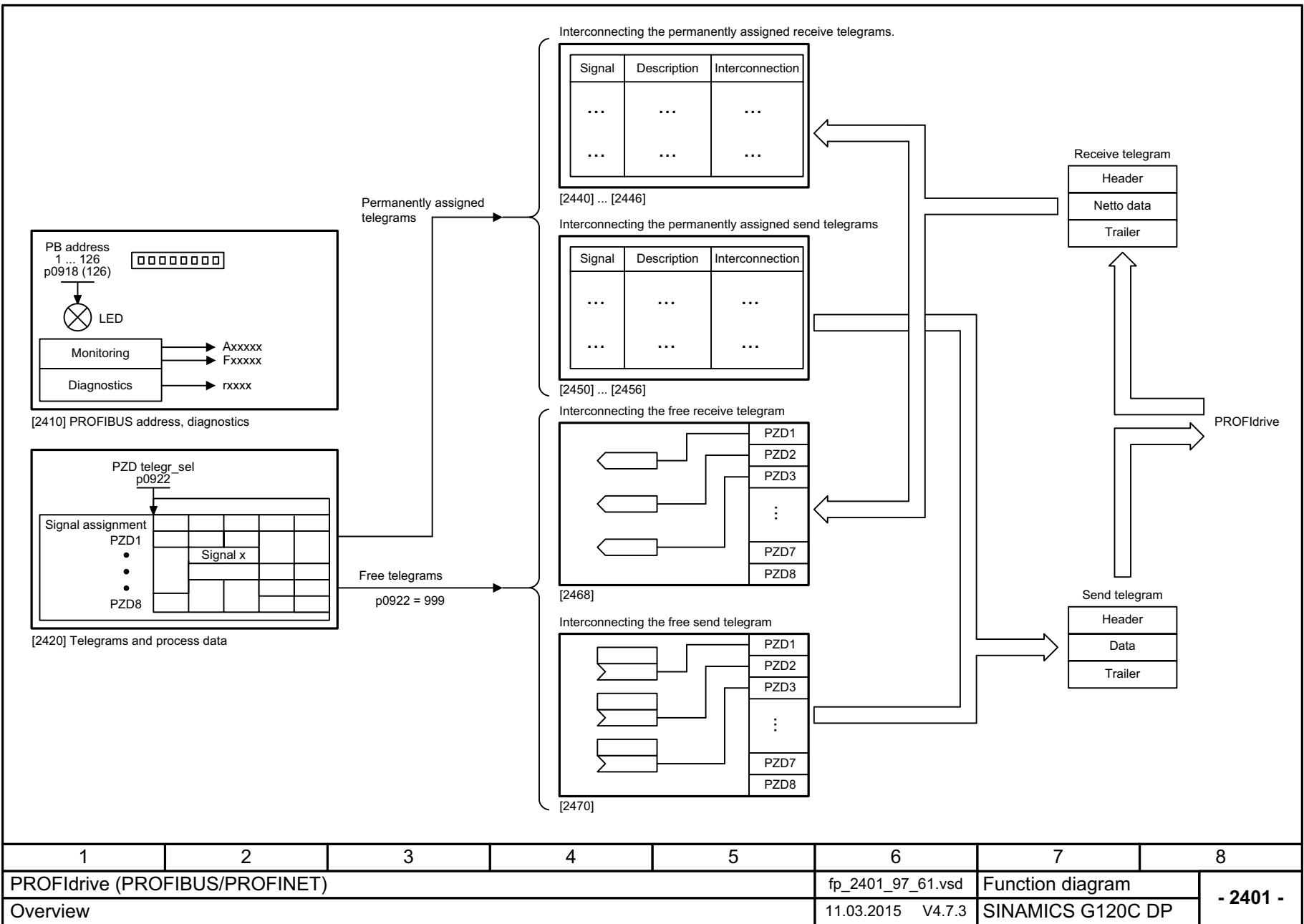
377



3.5 PROFIdrive communication (PROFIBUS/PROFINET)

Function block diagrams

2401 – Overview	379
2410 – PROFIBUS (PB) / PROFINET (PN), addresses and diagnostics	380
2420 – Telegrams and process data (PZD)	381
2440 – PZD receive signals interconnection	382
2441 – STW1 control word interconnection (p2038 = 2)	383
2442 – STW1 control word interconnection (p2038 = 0)	384
2446 – STW3 control word interconnection	385
2450 – PZD send signals interconnection	386
2451 – ZSW1 status word interconnection (p2038 = 2)	387
2452 – ZSW1 status word interconnection (p2038 = 0)	388
2456 – ZSW3 status word interconnection	389
2468 – Receive telegram, free interconnection via BICO (p0922 = 999)	390
2470 – Send telegram, free interconnection via BICO (p0922 = 999)	391



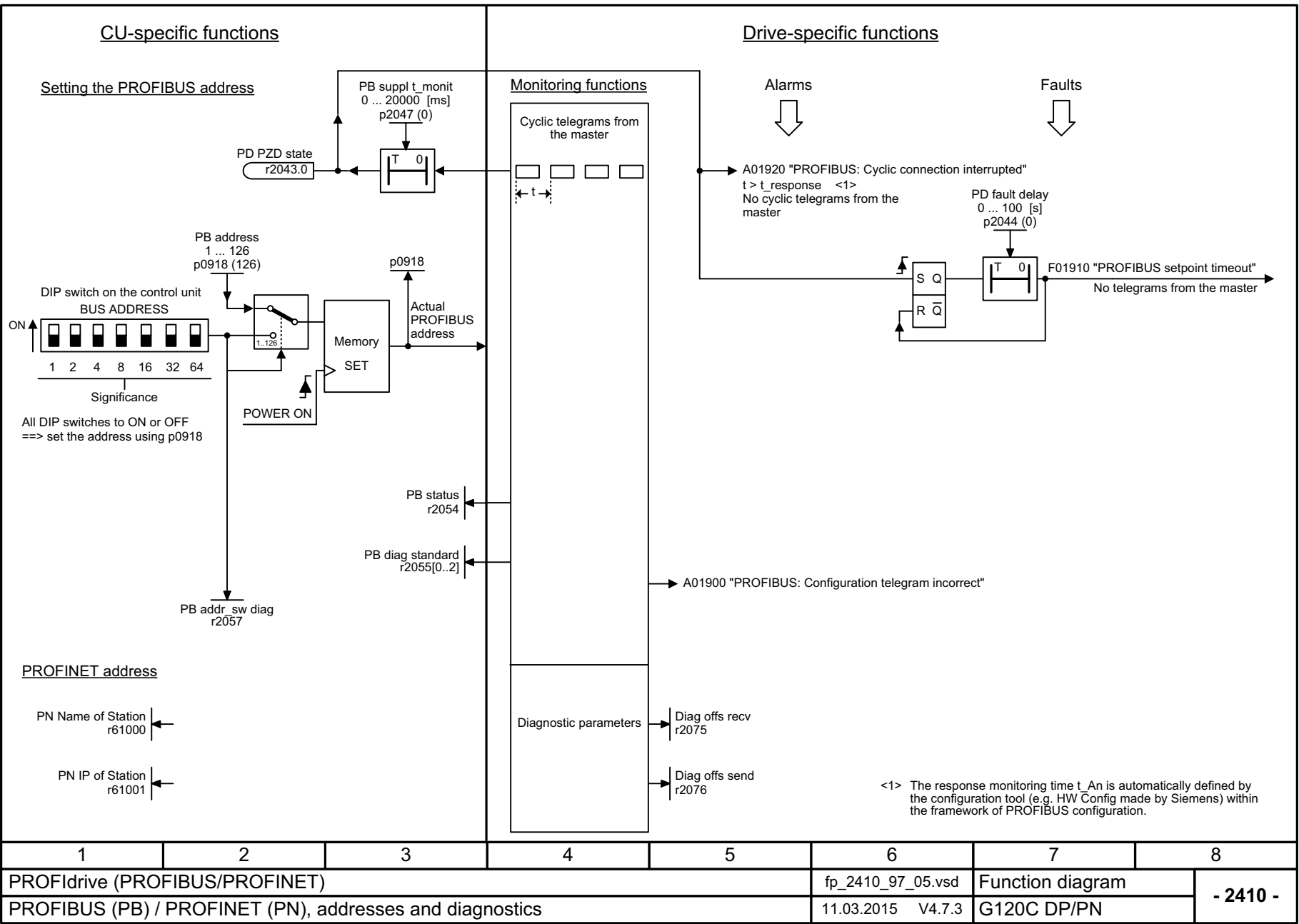
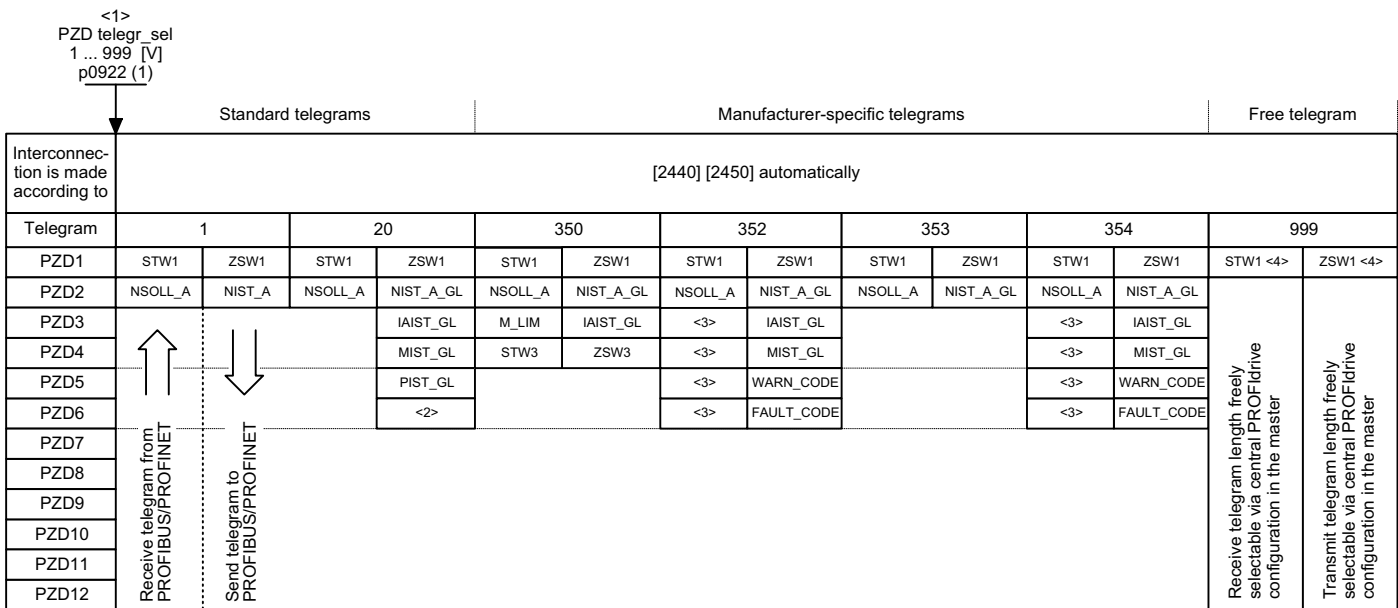


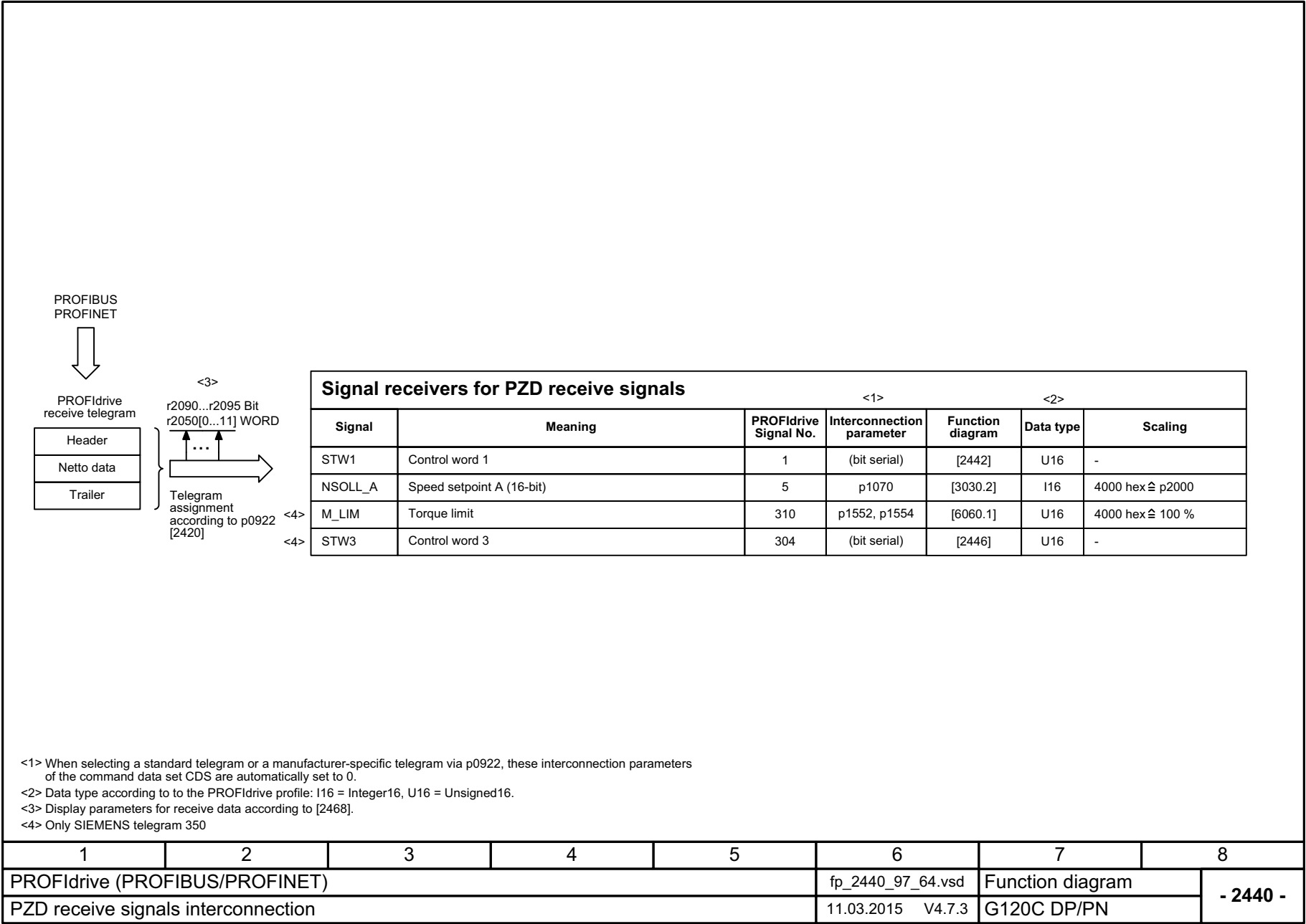
Fig. 3-16 2410 – PROFIBUS (PB) / PROFINET (PN), addresses and diagnostics

Fig. 3-17 2420 – Telegrams and process data (PZD)



- <1> If p0922 = 999 is changed to another value, the telegram is automatically assigned.
If p0922 unequal 999 is changed to p0922 = 999, the "old" telegram assignment is maintained!
- <2> Freely interconnectable (pre-setting: MELD_NAMUR).
- <3> Can be freely connected.
- <4> In order to comply with the PROFIdrive profile, PZD1 must be used as control word 1 (STW1) or status word 1 (ZSW1).
p2037 = 2 should be set if STW1 is not transferred with PZD1 as specified in the PROFIdrive profile.

1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2420_97_67.vsd	Function diagram	
Telegrams and Process Data (PZD)					11.03.2015 V4.7.3	G120C DP/PN	
							- 2420 -







Signal targets for STW1 in Interface Mode VIK-NAMUR (p2038 = 2)						<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 suppression & ready for switching on)	p0840[0] = r2090.0	[2501.3]	Sequence control	-		
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse suppression and switching on inhibited)	p0844[0] = r2090.1	[2501.3]	Sequence control	-		
STW1.2	1 = No OFF3 (enable is possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse suppression and switching on inhibited)	p0848[0] = r2090.2	[2501.3]	Sequence control	-		
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (suppress pulses)	p0852[0] = r2090.3	[2501.3]	Sequence control	-		
STW1.4	1 = Ramp-function generator enable 0 = Inhibit ramp-function generator (set the ramp-function generator output to zero)	p1140[0] = r2090.4	[2501.3]	[3070]	-		
STW1.5	1 = Continue ramp-function generator 0 = Freezes the ramp-function generator	p1141[0] = r2090.5	[2501.3]	[3070]	-		
STW1.6	1 = Setpoint enable 0 = Inhibits the setpoint (the ramp-function generator input is set to zero)	p1142[0] = r2090.6	[2501.3]	[3070]	-		
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 <4>	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 <3>	-	[8560]	-		
<1> Used in telegram 20. <2> Bit 10 in STW1 must be set to ensure that the drive accepts the process data. <3> Interconnection is not inhibited.						<4> The direction reversal can be locked. See p1110 and p1111.	
1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2441_97_61.vsd	Function diagram	- 2441 -
STW1 control word interconnection (p2038 = 2)					11.03.2015 V4.7.3	G120C DP/PN	

Fig. 3-19 2441 – STW1 control word interconnection (p2038 = 2)

Signal targets for STW1 in Interface Mode SINAMICS (p2038 = 0)					
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 suppression & ready for switching on)	p0840[0] = r2090.0	[2501.3]	Sequence control	-
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse suppression and switching on inhibited)	p0844[0] = r2090.1	[2501.3]	Sequence control	-
STW1.2	1 = No OFF3 (enable is possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse suppression and switching on inhibited)	p0848[0] = r2090.2	[2501.3]	Sequence control	-
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (suppress pulses)	p0852[0] = r2090.3	[2501.3]	Sequence control	-
STW1.4	1 = Ramp-function generator enable 0 = Inhibit ramp-function generator (set the ramp-function generator output to zero)	p1140[0] = r2090.4	[2501.3]	[3070]	-
STW1.5	1 = Continue ramp-function generator 0 = Freezes the ramp-function generator	p1141[0] = r2090.5	[2501.3]	[3070]	-
STW1.6	1 = Setpoint enable 0 = Inhibits the setpoint (the ramp-function generator input is set to zero)	p1142[0] = r2090.6	[2501.3]	[3070]	-
STW1.7	 = Acknowledge faults	p2103[0] = r2090.7	[2546.1]	[8060]	-
STW1.8	Reserved	-	-	-	-
STW1.9	Reserved	-	-	-	-
STW1.10	1 = Control via PLC <1>	p0854[0] = r2090.10	[2501.3]	[2501]	-
STW1.11	1 = Dir of rot reversal <2>	p1113[0] = r2090.11	[2505.3]	[3040]	-
STW1.12	Reserved	-	-	-	-
STW1.13	1 = Motorized potentiometer, setpoint, raise	p1035[0] = r2090.13	[2505.3]	[3020]	-
STW1.14	1 = Motorized potentiometer, setpoint, lower	p1036[0] = r2090.14	[2505.3]	[3020]	-
STW1.15	Reserved	-	-	-	-

<1> Bit 10 in STW1 must be set to ensure that the drive accepts the process data.

<2> The direction reversal can be locked. See p1110 and p1111.

1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2442_97_61.vsd	Function diagram	- 2442 -
STW1 control word interconnection (p2038 = 0)					11.03.2015 V4.7.3	G120C DP/PN	

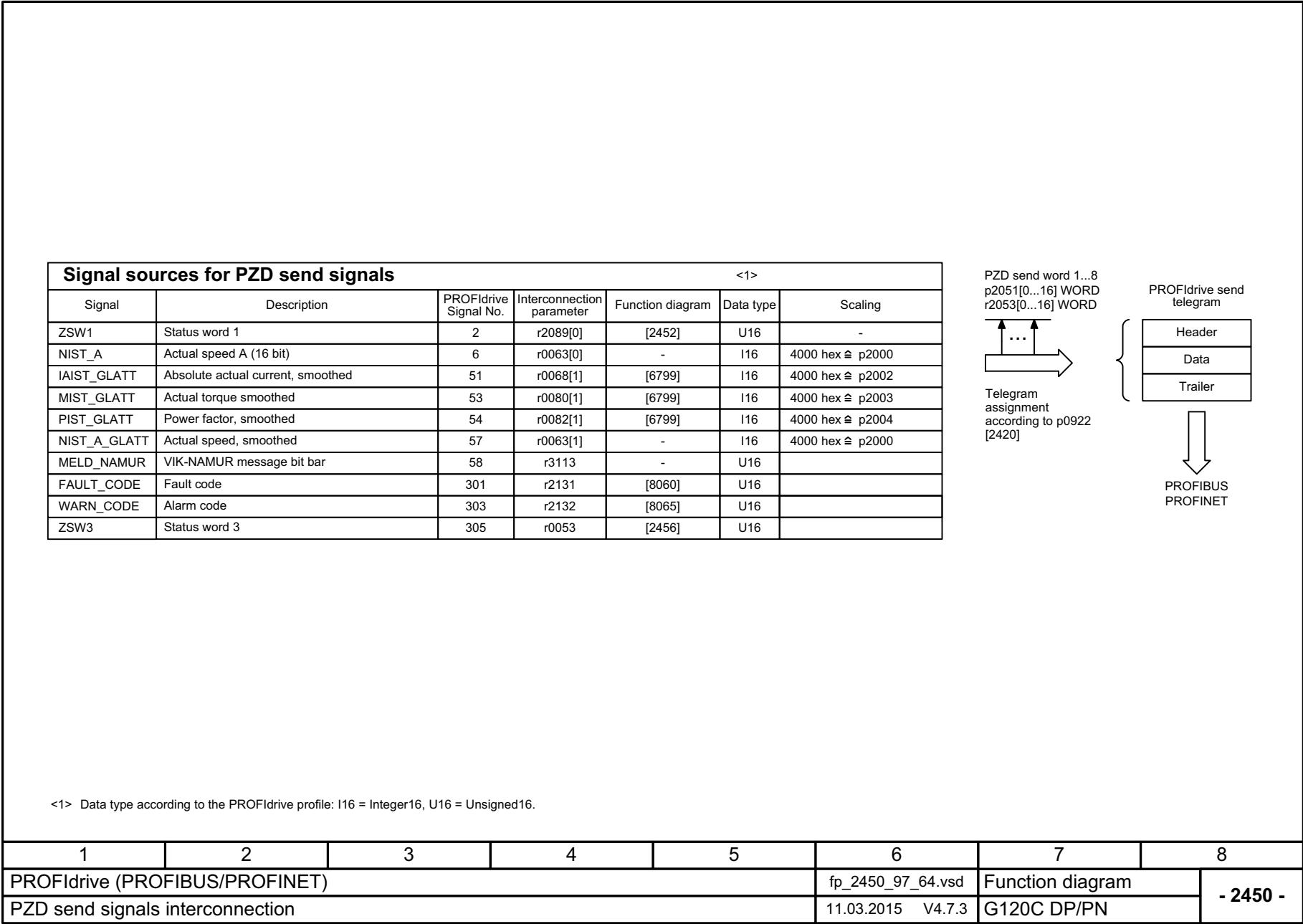
Fig. 3-20 2442 – STW1 control word interconnection (p2038 = 0)

Signal targets for STW3 in Interface Mode SINAMICS					<1>
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted
STW3.0	1 = Fixed setp bit 0	p1020[0] = r2093.0	[3010.2]	[3010.2]	-
STW3.1	1 = Fixed setp bit 1	p1021[0] = r2093.1	[2513.2]	[3010.2]	-
STW3.2	1 = Fixed setp bit 2	p1022[0] = r2093.2	[2513.2]	[3010.2]	-
STW3.3	1 = Fixed setp bit 3	p1023[0] = r2093.3	[2513.2]	[3010.2]	-
STW3.4	Reserved	-	-	-	-
STW3.5	Reserved	-	-	-	-
STW3.6	Reserved	-	-	-	-
STW3.7	Reserved	-	-	-	-
STW3.8	1 = Technology controller enable	p2200[0] = r2093.8	[2513.2]	[7958.4]	-
STW3.9	1 = DC brake enable	p1230[0] = r2093.9	[2513.2]	[7017.1]	-
STW3.10	Reserved	-	-	-	-
STW3.11	Reserved	-	-	-	-
STW3.12	Reserved	-	-	-	-
STW3.13	0 = External fault 1 (F07860)	p2106[0] = r2093.13	[2513.2]	[8060.1]	-
STW3.14	Reserved	-	-	-	-
STW3.15	Reserved	-	-	-	-

<1> Used in telegram 350.

1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2446_97_05.vsd	Function diagram	
STW3 control word interconnection					11.03.2015 V4.7.3	G120C DP/PN	
							- 2446 -

Fig. 3-21 2446 – STW3 control word interconnection



Signal sources for ZSW1 in Interface Mode VIK-NAMUR (p2038 = 2)					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted <1>
ZSW1.0	1 = Ready for switching on	p2080[0] = r0899.0	[2503.7]	Sequence control	-
ZSW1.1	1 = Ready for operation (DC link loaded, pulses inhibited)	p2080[1] = r0899.1	[2503.7]	Sequence control	-
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	Sequence control	-
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]	Sequence control	-
ZSW1.5	1 = No quick stop active (OFF3 inactive)	p2080[5] = r0899.5	[2503.7]	Sequence control	-
ZSW1.6	1 = Switching on inhibited active	p2080[6] = r0899.6	[2503.7]	Sequence control	-
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]	[8011]	-
ZSW1.9	1 = Control requested	p2080[9] = r0899.9	[2503.7]	[2503]	-
ZSW1.10	1 = f or n comparison value reached/exceeded	p2080[10] = r2199.1	[2537.7]	[8010]	-
ZSW1.11	1 = I, M, or P limit not reached	p2080[11] = r0056.13	[2522.7]	[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)	p2080[14] = r2197.3	[2534.7]	[8011]	-
ZSW1.15	1 = Display CDS	p2080[15] = r0836.0 <2>	-	-	-

<1> The ZSW1 is generated using the binector-connector converter (BI: p2080[0...15], inversion: p2088[0].0...p2088[0].15).

<2> Interconnection is not inhibited.

1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2451_97_61.vsd	Function diagram	
ZSW1 status word interconnection (p2038 = 2)					11.03.2015 V4.7.3	G120C DP/PN	

- 2451 -

Fig. 3-23 2451 – ZSW1 status word interconnection (p2038 = 2)

Signal sources for ZSW1 im Interface Mode SINAMICS (p2038 = 0)					
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted <1>
ZSW1.0	1 = Ready for switching on	p2080[0] = r0899.0	[2503.7]	Sequence control	-
ZSW1.1	1 = Ready for operation (DC link loaded, pulses inhibited)	p2080[1] = r0899.1	[2503.7]	Sequence control	-
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	Sequence control	-
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]	Sequence control	-
ZSW1.5	1 = No Quick stop active (OFF3 inactive)	p2080[5] = r0899.5	[2503.7]	Sequence control	-
ZSW1.6	1 = Switching on inhibited active	p2080[6] = r0899.6	[2503.7]	Sequence control	-
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]	[8011]	-
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	1 = I, M, or P limit not reached	p2080[11] = r1407.7	[2522.7]	[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)	p2080[14] = r2197.3	[2534.7]	[8011]	-
ZSW1.15	1 = No alarm, thermal overload, power unit	p2080[15] = r2135.15	[2548.7]	[8019]	✓

<1> The ZSW1 is generated using the binector-connector converter (BI: p2080[0...15], inversion: p2088[0]...p2088[0].15).

<2> The drive is ready to accept data.

1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2452_97_61.vsd	Function diagram	- 2452 -
ZSW1 status word interconnection (p2038 = 0)					11.03.2015 V4.7.3	G120C DP/PN	

Fig. 3-24 2452 – ZSW1 status word interconnection (p2038 = 0)

Signal sources for ZSW3 im Interface Mode SINAMICS						<1>
Signal	Meaning	Interconnection parameters	[Function diagram] internal status word	[Function diagram] signal source	Inverted	
ZSW3.0	1 = DC braking active	p2051[3] = r0053	[2511.7]	[7017.5]	-	
ZSW3.1	1 = n_act > p1226 (n_standstill)		[2511.7]	[2534.7]	-	
ZSW3.2	1 = n_act > p1080 (n_min)		[2511.7]	[2534.7]	-	
ZSW3.3	1 = l_act >= p2170		[2511.7]	[2534.7]	-	
ZSW3.4	1 = n_act > p2155		[2511.7]	[2534.7]	-	
ZSW3.5	1 = n_act <= p2155		[2511.7]	[2534.7]	-	
ZSW3.6	1 = n_act >= r1119 (n_set)		[2511.7]	[2534.7]	-	
ZSW3.7	1 = Vdc <= p2172		[2511.7]	[2534.7]	-	
ZSW3.8	1 = Vdc > p2172		[2511.7]	[2534.7]	-	
ZSW3.9	1 = Ramping finished		[2511.7]	[3080.7]	-	
ZSW3.10	1 = Technology controller output at the lower limit		[2511.7]	[7958.7]	-	
ZSW3.11	1 = Technology controller output at the upper limit		[2511.7]	[7958.7]	-	
ZSW3.12	Reserved		-	-	-	
ZSW3.13	Reserved		-	-	-	
ZSW3.14	Reserved		-	-	-	
ZSW3.15	Reserved	-	-	-		
<1> Used in telegrams 350.						

1	2	3	4	5	6	7	8
PROFIdrive (PROFIBUS/PROFINET)					fp_2456_97_61.vsd	Function diagram	
ZSW3 status word interconnection					11.03.2015 V4.7.3	G120C DP/PN	

- 2456 -

Fig. 3-25 2456 – ZSW3 status word interconnection

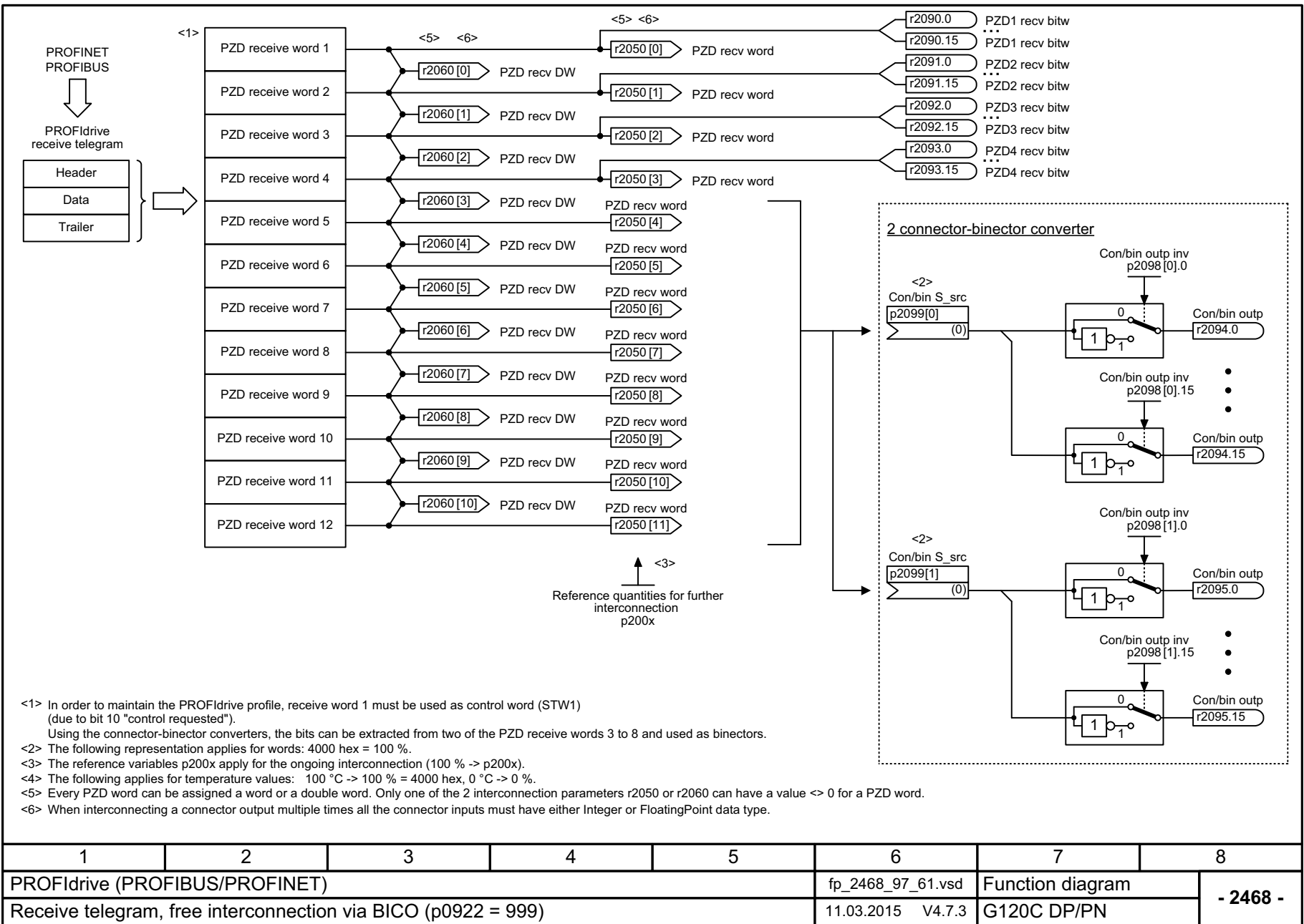
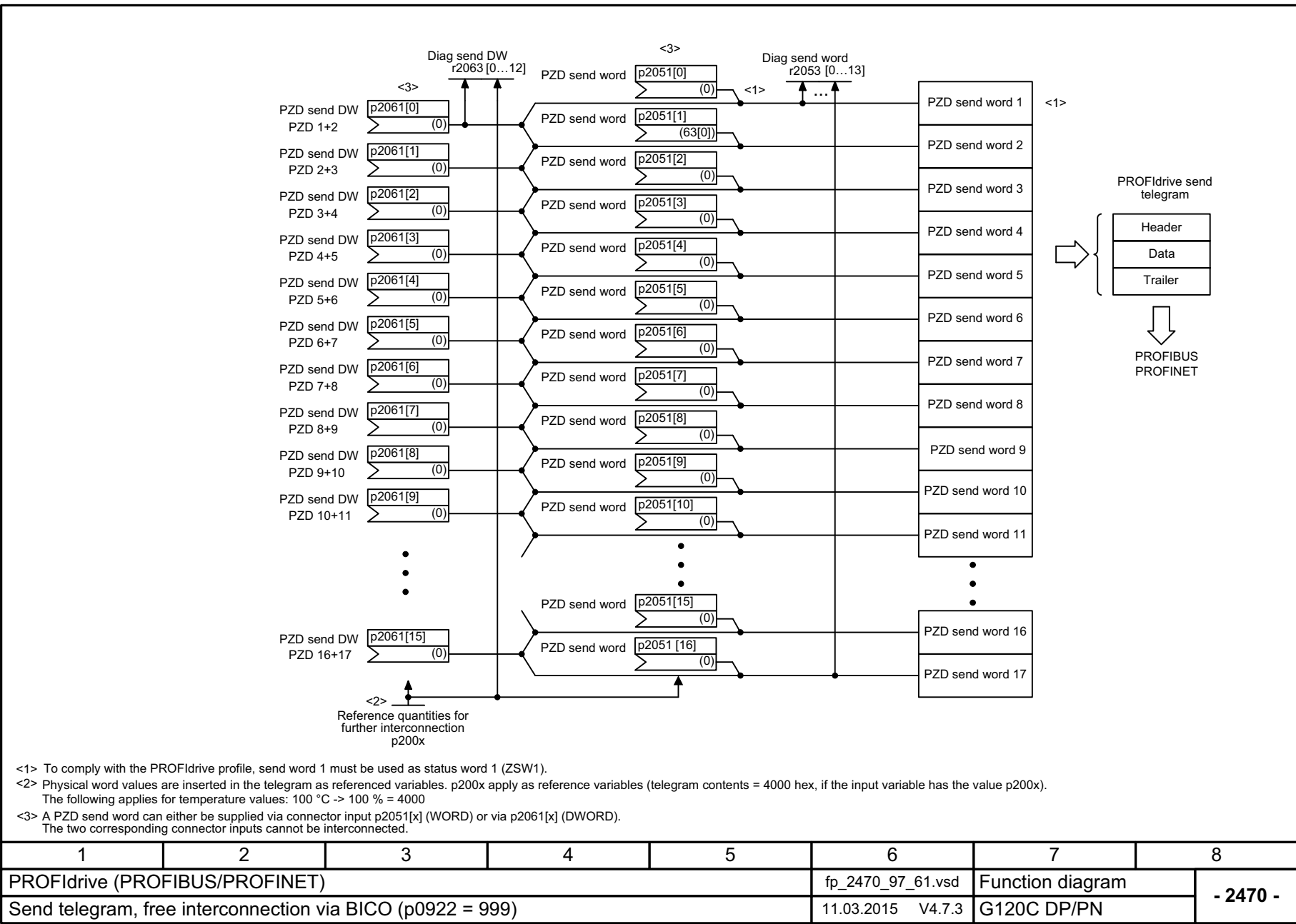


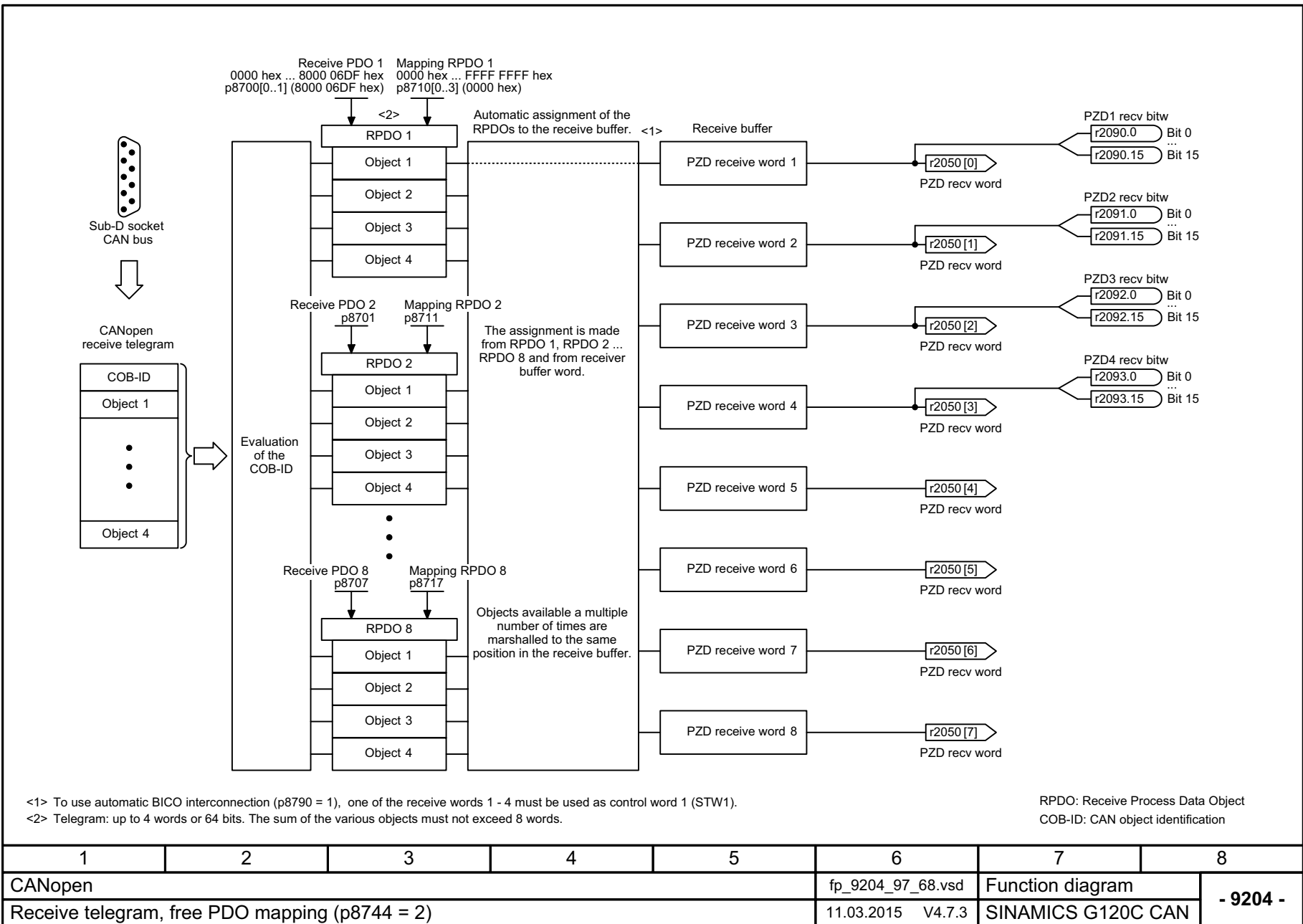
Fig. 3-26 2468 – Receive telegram, free interconnection via BICO (p0922 = 999)

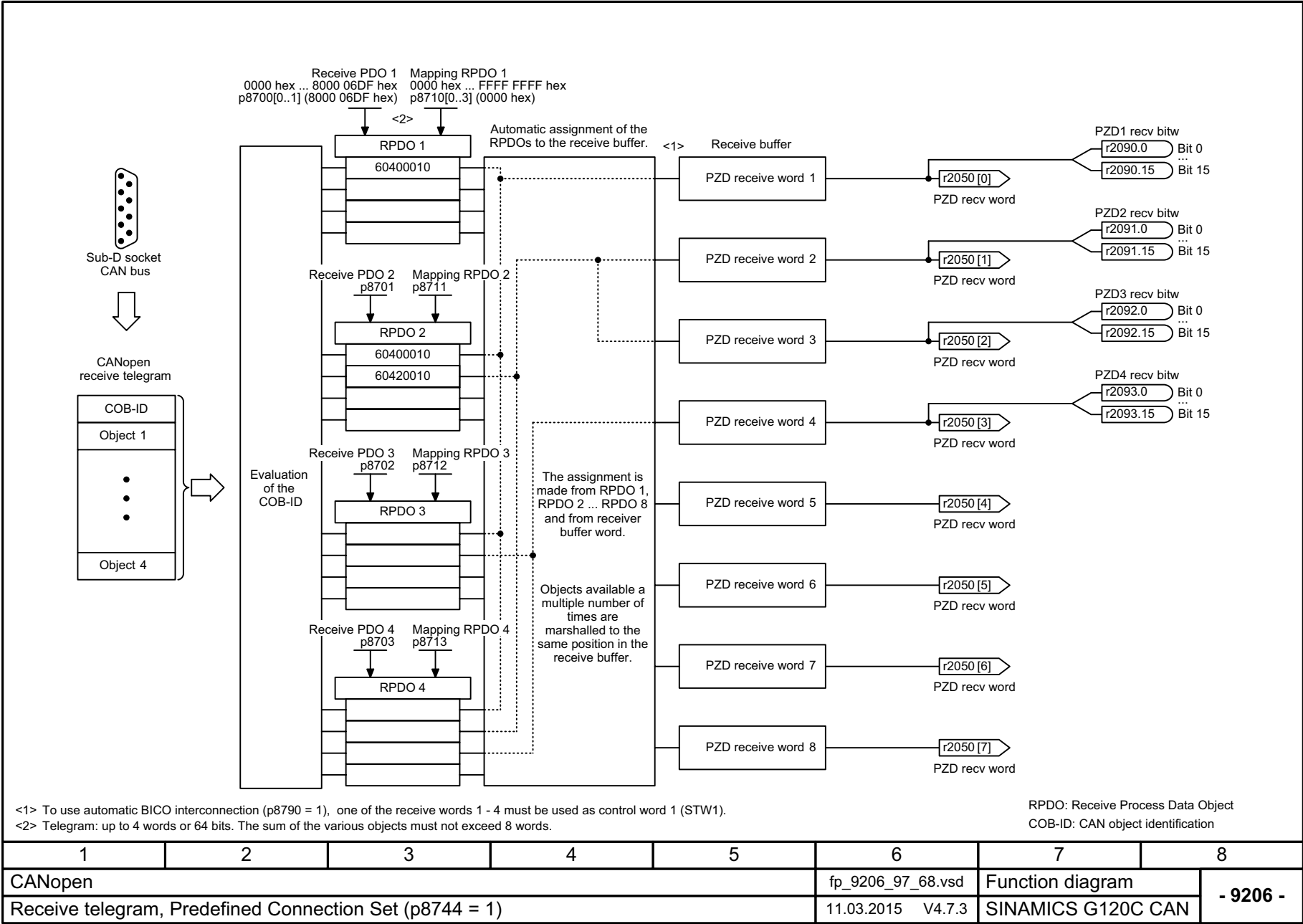


3.6 CANopen communication

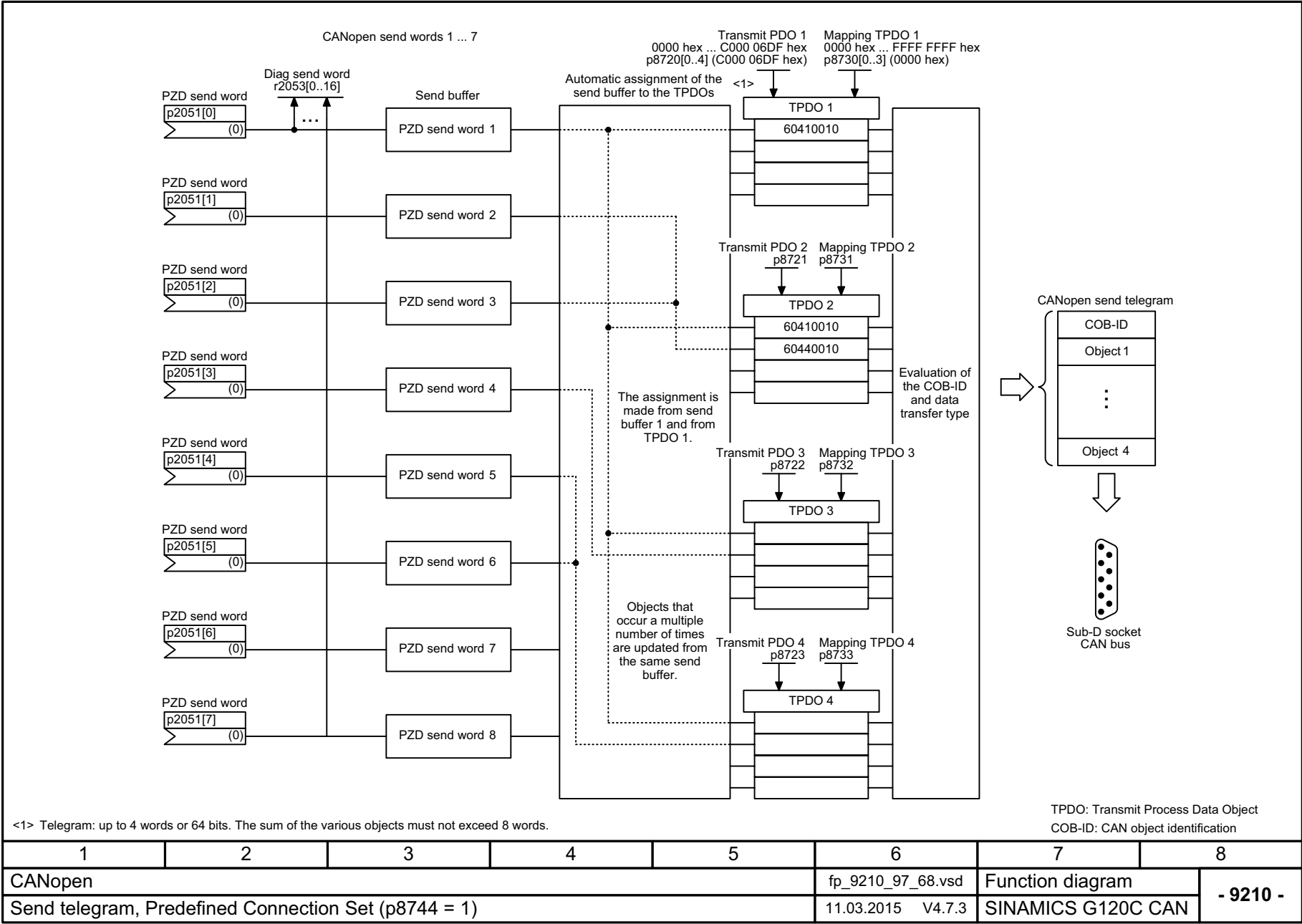
Function block diagrams



9204 – Receive telegram, free PDO mapping (p8744 = 2)	393
9206 – Receive telegram, Predefined Connection Set (p8744 = 1)	394
9208 – Send telegram, free PDO mapping (p8744 = 2)	395
9210 – Send telegram, Predefined Connection Set (p8744 = 1)	396
9220 – Control word, CANopen	397
9226 – Status word, CANopen	398









Signal targets for control word CANopen (r8795)				
Signal	Meaning	Interconnection parameters <1>	[Function diagram] internal control word	[Function diagram] signal target
STW.0	 = ON (pulses can be enabled) 0 = OFF1 (braking with RFG, then pulse suppression and ready for switching on)	p0840[0] = r2090.0	[2501.3]	Sequence control
STW.1	1 = No coast-down activated (enable possible) 0 = Activate coast-down (immediate pulse suppression and switching on inhibited)	p0844[0] = r2090.1	[2501.3]	Sequence control
STW.2	1 = No Quick stop activated (enable possible) 0 = Activate Quick stop (OFF3 ramp p1135, then pulse suppression and switching on inhibited)	p0848[0] = r2090.2	[2501.3]	Sequence control
STW.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (suppress pulses)	p0852[0] = r2090.3	[2501.3]	Sequence control
STW.4	1 = Enable ramp-function generator 0 = Inhibit ramp-function generator	p1140[0] = r2090.4<2>	[2501.3]	[3070]
STW.5	1 = Continue ramp-function generator 0 = function generator	p1141[0] = r2090.5<2>	[2501.3]	[3070]
STW.6	1 = Enable setpoint 0 = Inhibit setpoint (set the ramp-function generator input to zero)	p1142[0] = r2090.6<2>	[2501.3]	[3070]
STW.7	 = Acknowledge fault	p2103[0] = r2090.7	[2546.1]	[8060]
STW.8	1 = Stop	<2> <3>	-	[3070]
STW.9	Reserved	-	-	-
STW.10	Reserved	-	-	-
STW.11	Can be freely connected	pxxxx[y] = r2090.11	-	-
STW.12	Can be freely connected	pxxxx[y] = r2090.12	-	-
STW.13	Can be freely connected	pxxxx[y] = r2090.13	-	-
STW.14	Can be freely connected	pxxxx[y] = r2090.14	-	-
STW.15	Can be freely connected	pxxxx[y] = r2090.15	-	-

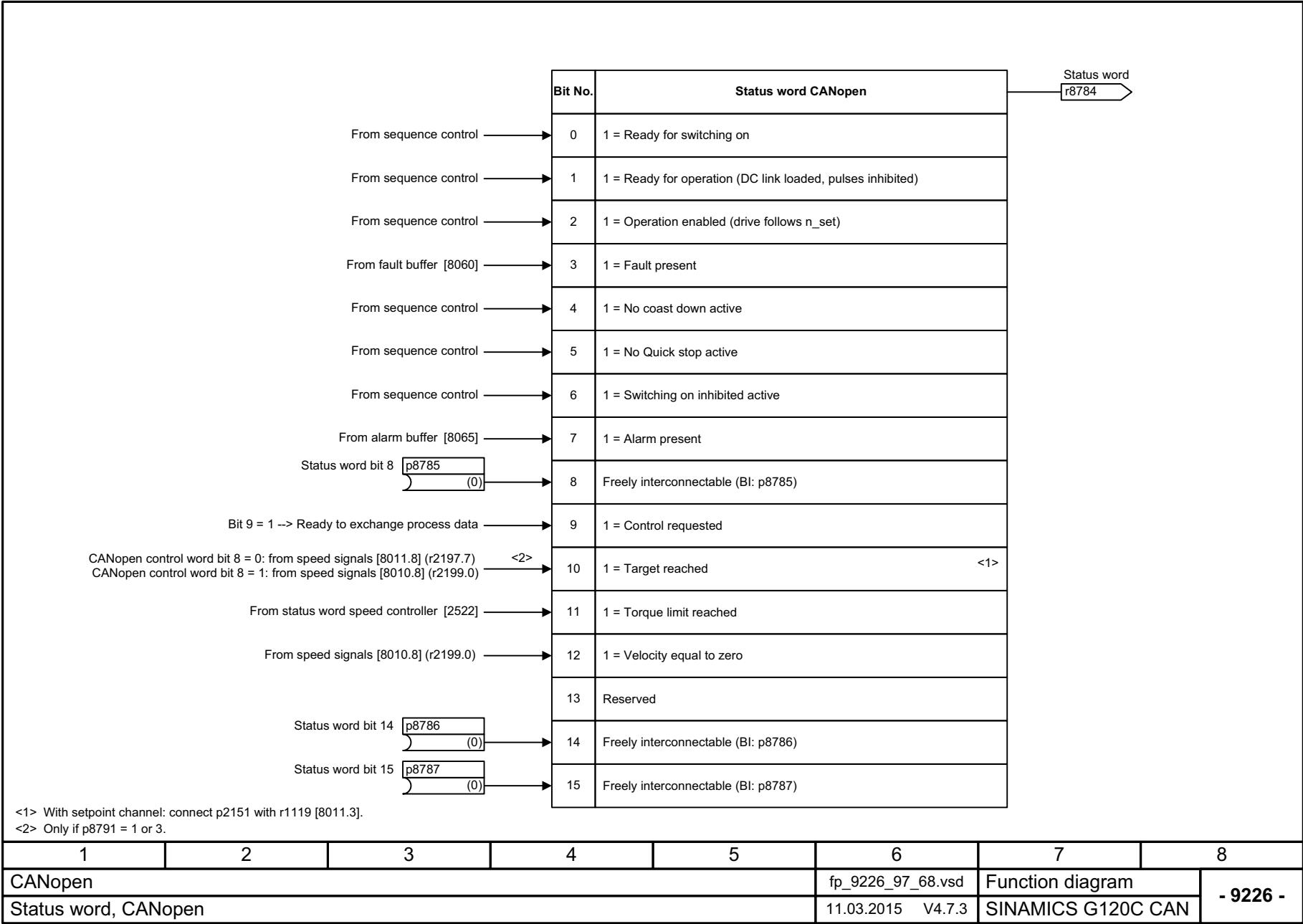
<1> Depending on the position of the CANopen control word in p8750, the number of the binector to be connected changes.

<2> Not taken into account for the automatic control word interconnection (p8790).

<3> Interconnection via p8791.

1	2	3	4	5	6	7	8
CANopen					fp_9220_97_68.vsd	Function diagram	
Control word, CANopen					11.03.2015 V4.7.3	SINAMICS G120C CAN	
							- 9220 -

Fig. 3-32 9220 – Control word, CANopen



3.7 Communication, fieldbus interface (USS, MODBUS)

Function block diagrams

9310 – Configuration, addresses and diagnostics	400
9342 – STW1 control word interconnection	401
9352 – ZSW1 status word interconnection	402
9360 – Receive telegram, free interconnection via BICO (p0922 = 999)	403
9370 – Send telegram, free interconnection via BICO (p0922 = 999)	404

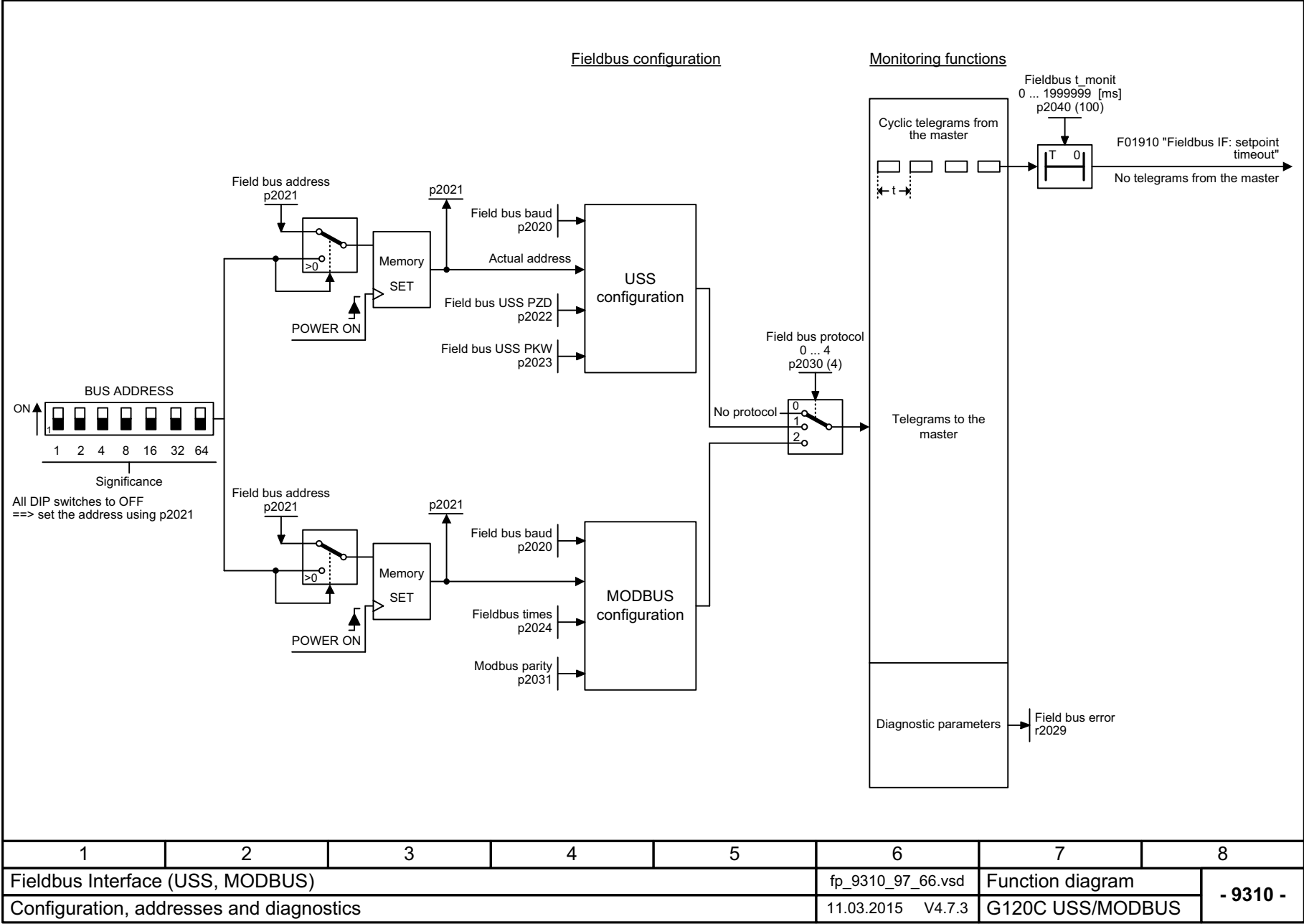




Fig. 3-34

9310 – Configuration, addresses and diagnostics

Signal targets for fieldbus STW1					
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 suppression & ready for switching on)	p0840[0] = r2090.0	[2501.3]	Sequence control	-
STW1.1	1 = No OFF2 (enable is possible) 0 = OFF2 (immediate pulse suppression and switching on inhibited)	p0844[0] = r2090.1	[2501.3]	Sequence control	-
STW1.2	1 = No OFF3 (enable is possible) 0 = OFF3 (braking with the OFF3 ramp p1135, then pulse suppression and switching on inhibited)	p0848[0] = r2090.2	[2501.3]	Sequence control	-
STW1.3	1 = Enable operation (pulses can be enabled) 0 = Inhibit operation (suppress pulses)	p0852[0] = r2090.3	[2501.3]	Sequence control	-
STW1.4	1 = Ramp-function generator enable 0 = Inhibit ramp-function generator (set the ramp-function generator output to zero)	p1140[0] = r2090.4	[2501.3]	[3070]	-
STW1.5	1 = Continue ramp-function generator 0 = Freezes the ramp-function generator	p1141[0] = r2090.5	[2501.3]	[3070]	-
STW1.6	1 = Setpoint enable 0 = Inhibits the setpoint (the ramp-function generator input is set to zero)	p1142[0] = r2090.6	[2501.3]	[3070]	-
STW1.7	 = Acknowledge faults	p2103[0] = r2090.7	[2546.1]	[8060]	-
STW1.8	Reserved	-	-	-	-
STW1.9	Reserved	-	-	-	-
STW1.10	1 = Control via PLC <1>	p0854[0] = r2090.10	[2501.3]	[2501]	-
STW1.11	1 = Dir of rot reversal <2>	p1113[0] = r2090.11	[2505.3]	[3040]	-
STW1.12	Reserved	-	-	-	-
STW1.13	1 = Motorized potentiometer, setpoint, raise	p1035[0] = r2090.13	[2505.3]	[3020]	-
STW1.14	1 = Motorized potentiometer, setpoint, lower	p1036[0] = r2090.14	[2505.3]	[3020]	-
STW1.15	Reserved	-	-	-	-

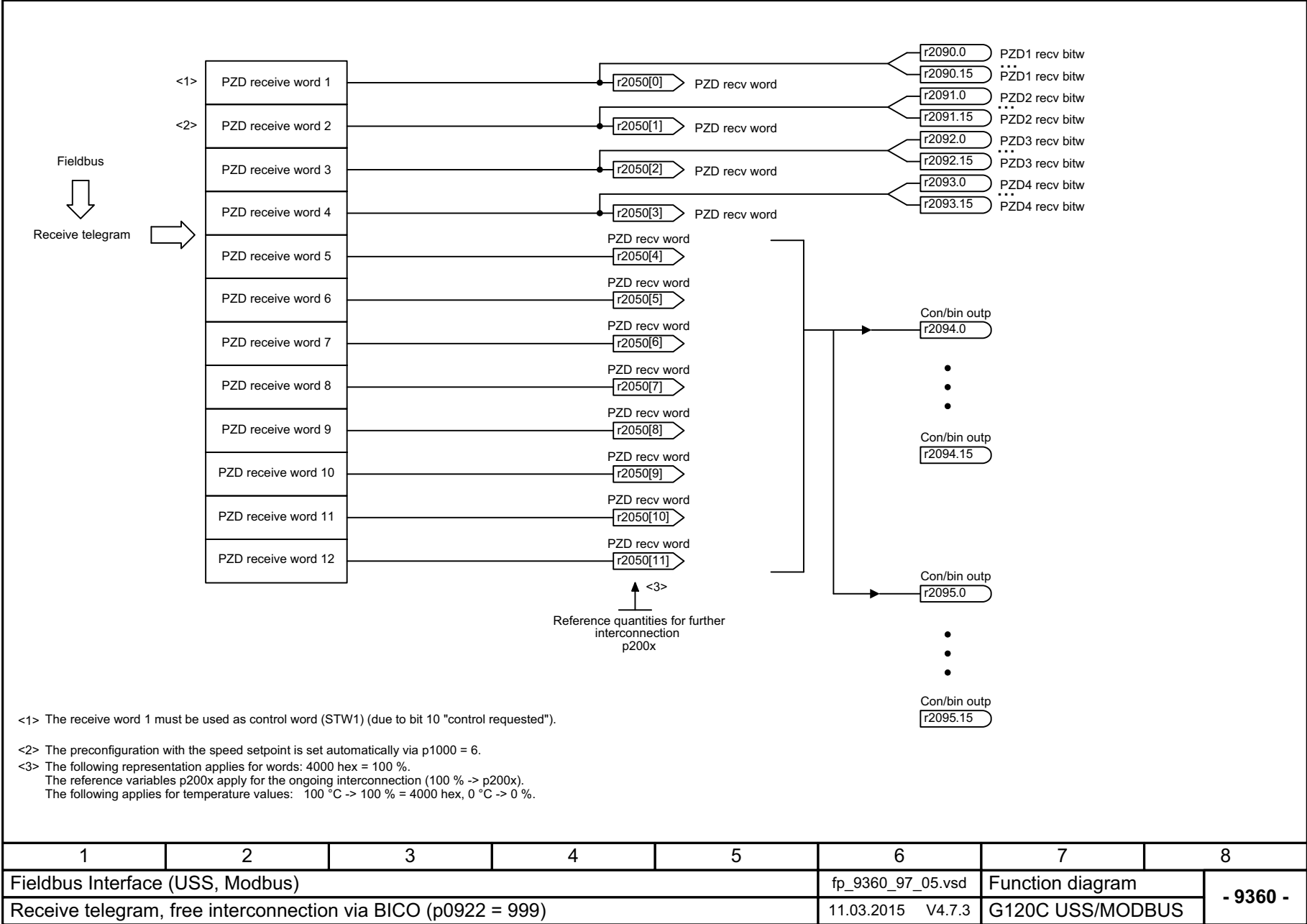
<1> Bit 10 in STW1 must be set to ensure that the drive accepts the process data.
<2> The direction reversal can be locked. See p1110 and p1111.

1	2	3	4	5	6	7	8
Fieldbus Interface (USS, Modbus)					fp_9342_97_62.vsd	Function diagram	
STW1 control word interconnection					11.03.2015 V4.7.3	G120C USS/MODBUS	
							- 9342 -

Fig. 3-35 9342 – STW1 control word interconnection

Signal sources for fieldbus ZSW1							
Signal	Meaning	Interconnection parameters	[Function diagram] internal control word	[Function diagram] signal target	Inverted <1>		
ZSW1.0	1 = Ready for switching on	p2080[0] = r0899.0	[2503.7]	Sequence control	-		
ZSW1.1	1 = Ready for operation (DC link loaded, pulses inhibited)	p2080[1] = r0899.1	[2503.7]	Sequence control	-		
ZSW1.2	1 = Operation enabled (drive follows n_set)	p2080[2] = r0899.2	[2503.7]	Sequence control	-		
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]	Sequence control	-		
ZSW1.5	1 = No Quick stop active (OFF3 inactive)	p2080[5] = r0899.5	[2503.7]	Sequence control	-		
ZSW1.6	1 = Switching on inhibited active	p2080[6] = r0899.6	[2503.7]	Sequence control	-		
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]	[8011]	-		
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	1 = I, M, or P limit not reached	p2080[11] = r1407.7	[2522.7]	[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)	p2080[14] = r2197.3	[2534.7]	[8011]	-		
ZSW1.15	1 = No alarm, thermal overload, power unit	p2080[15] = r2135.15	[2548.7]	[8019]	✓		
<div><1> The ZSW1 is generated using the binector-connector converter (BI: p2080[0...15], inversion: p2088[0].0...p2088[0].15).</div> <div><2> The drive is ready to accept data.</div>							
1	2	3	4	5	6	7	8
Fieldbus Interface (USS, MODBUS)				fp_9352_97_62.vsd	Function diagram		- 9352 -
ZSW1 status word interconnection				11.03.2015 V4.7.3	G120C USS/MODBUS		

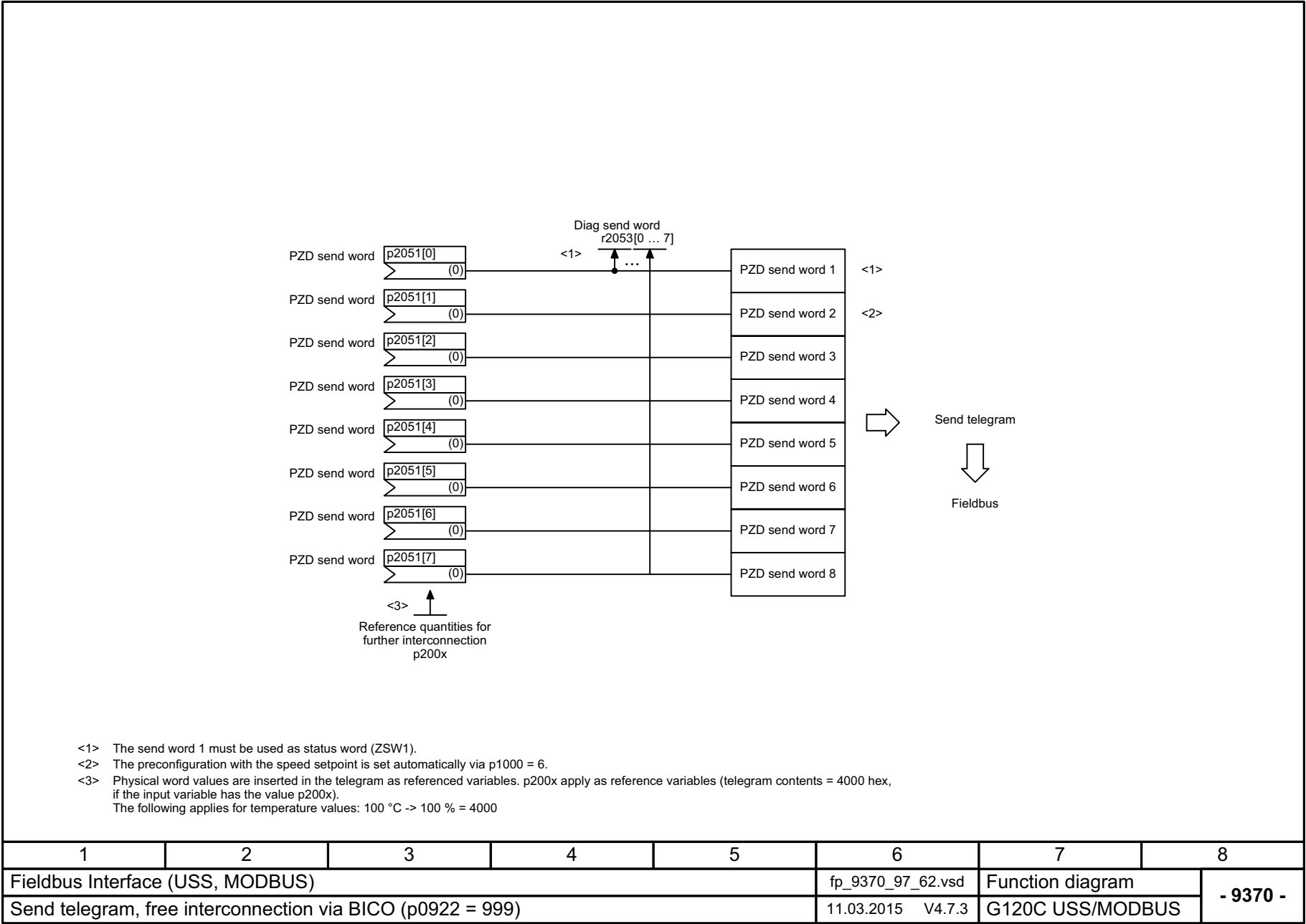
Fig. 3-36 9352 – ZSW1 status word interconnection



1	2	3	4	5	6	7	8
Fieldbus Interface (USS, Modbus)					fp_9360_97_05.vsd	Function diagram	
Receive telegram, free interconnection via BICO (p0922 = 999)					11.03.2015 V4.7.3	G120C USS/MODBUS	
					- 9360 -		

Fig. 3-37

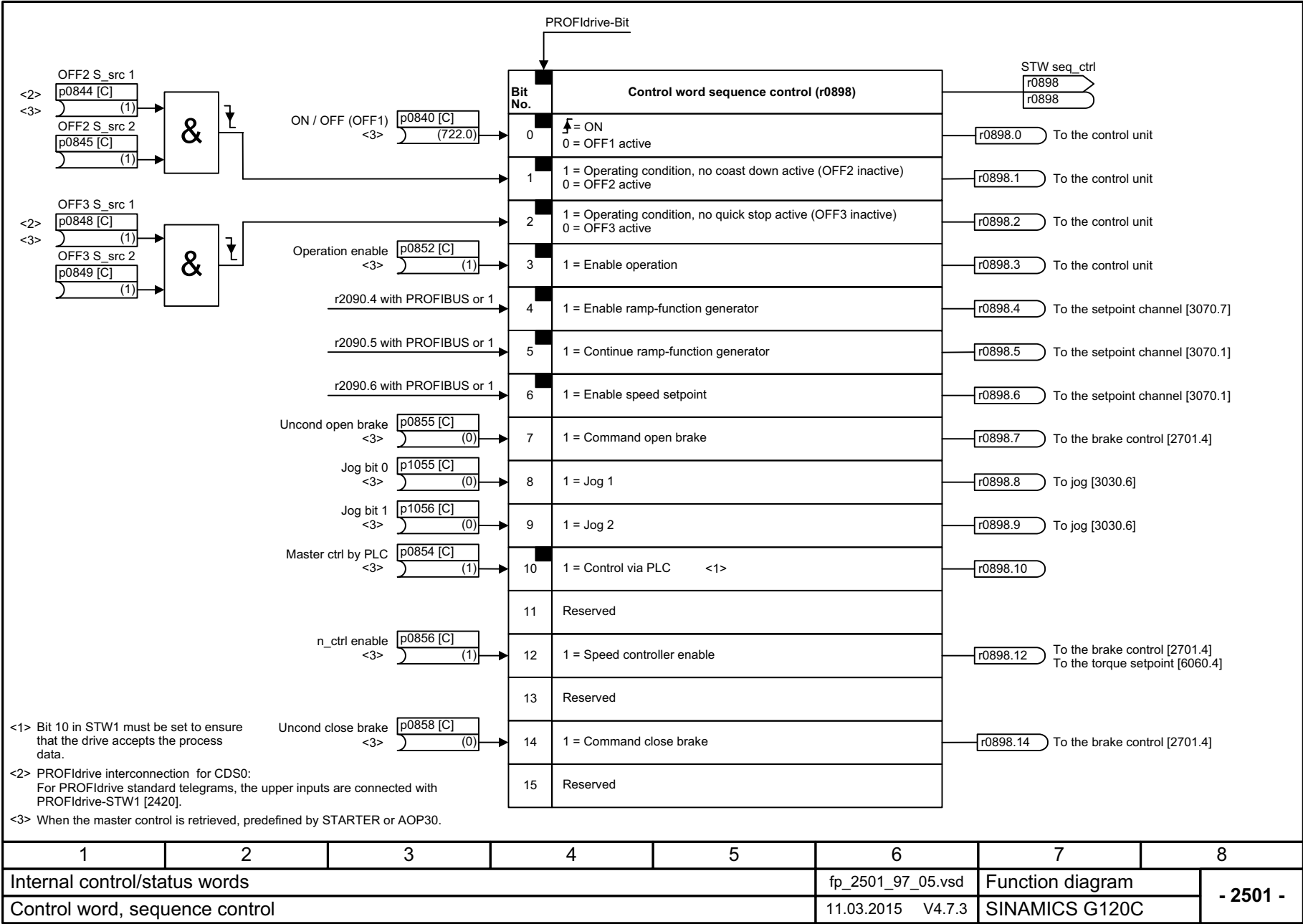
9360 – Receive telegram, free interconnection via BICO (p0922 = 999)

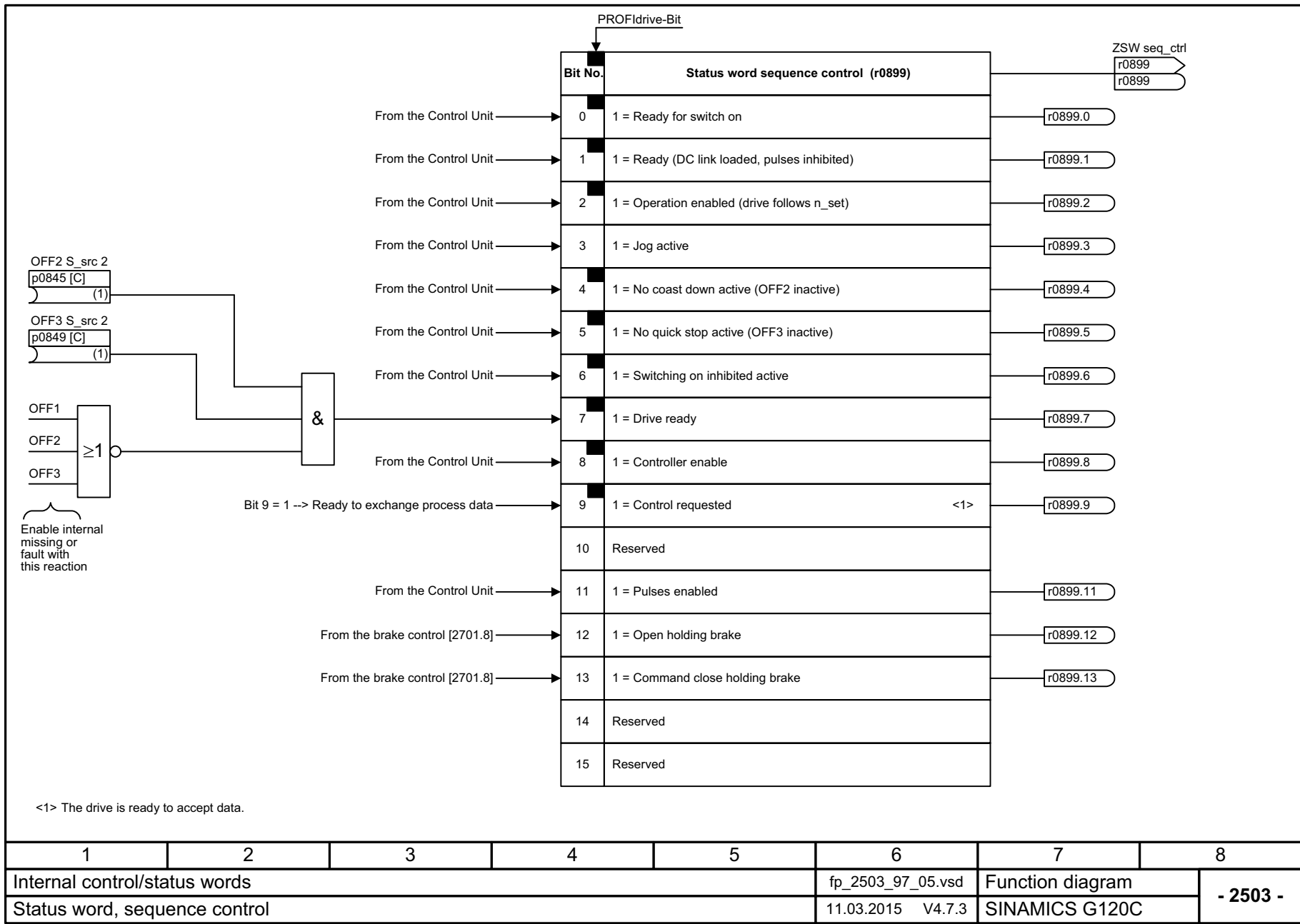


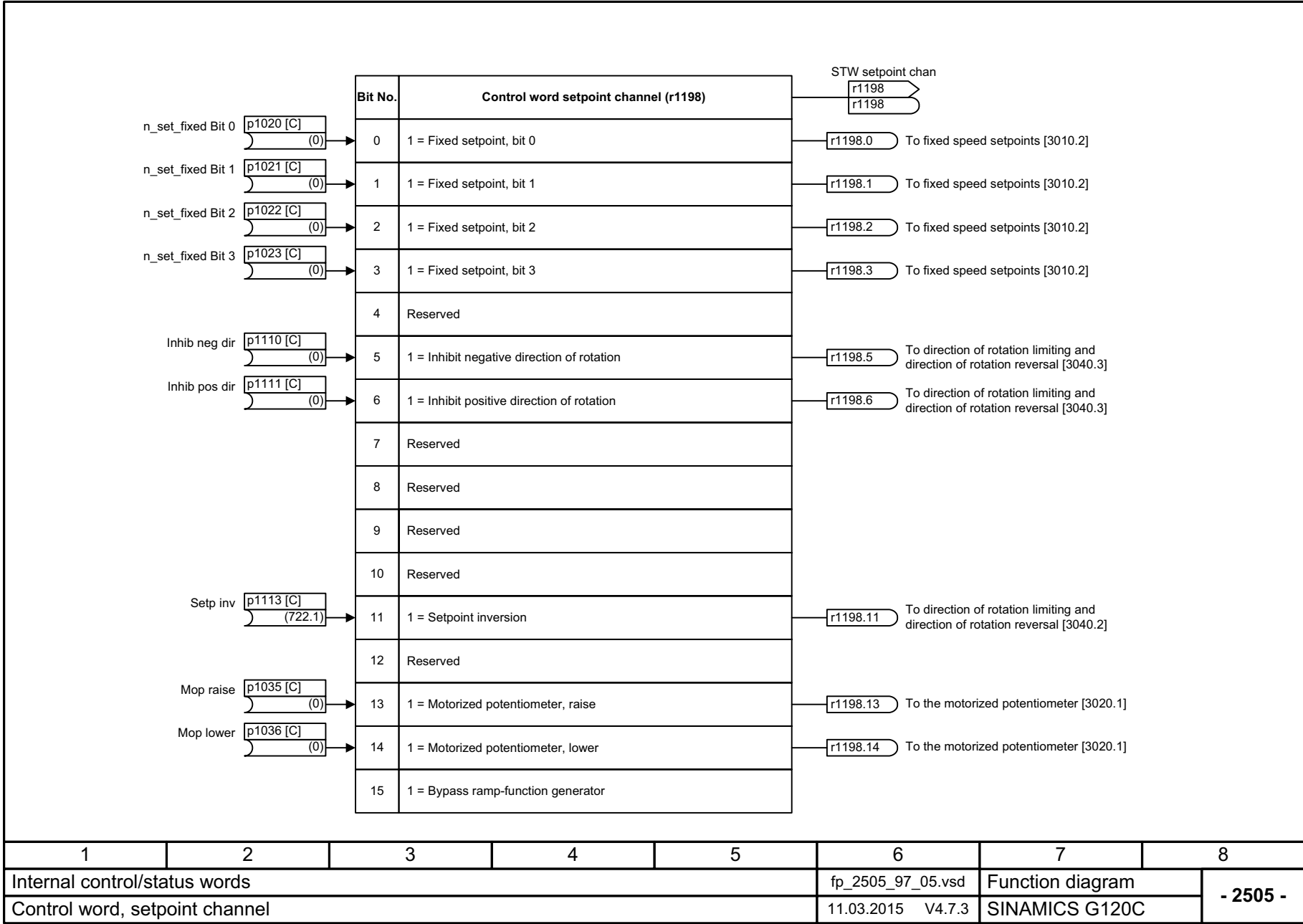
3.8 Internal control/status words

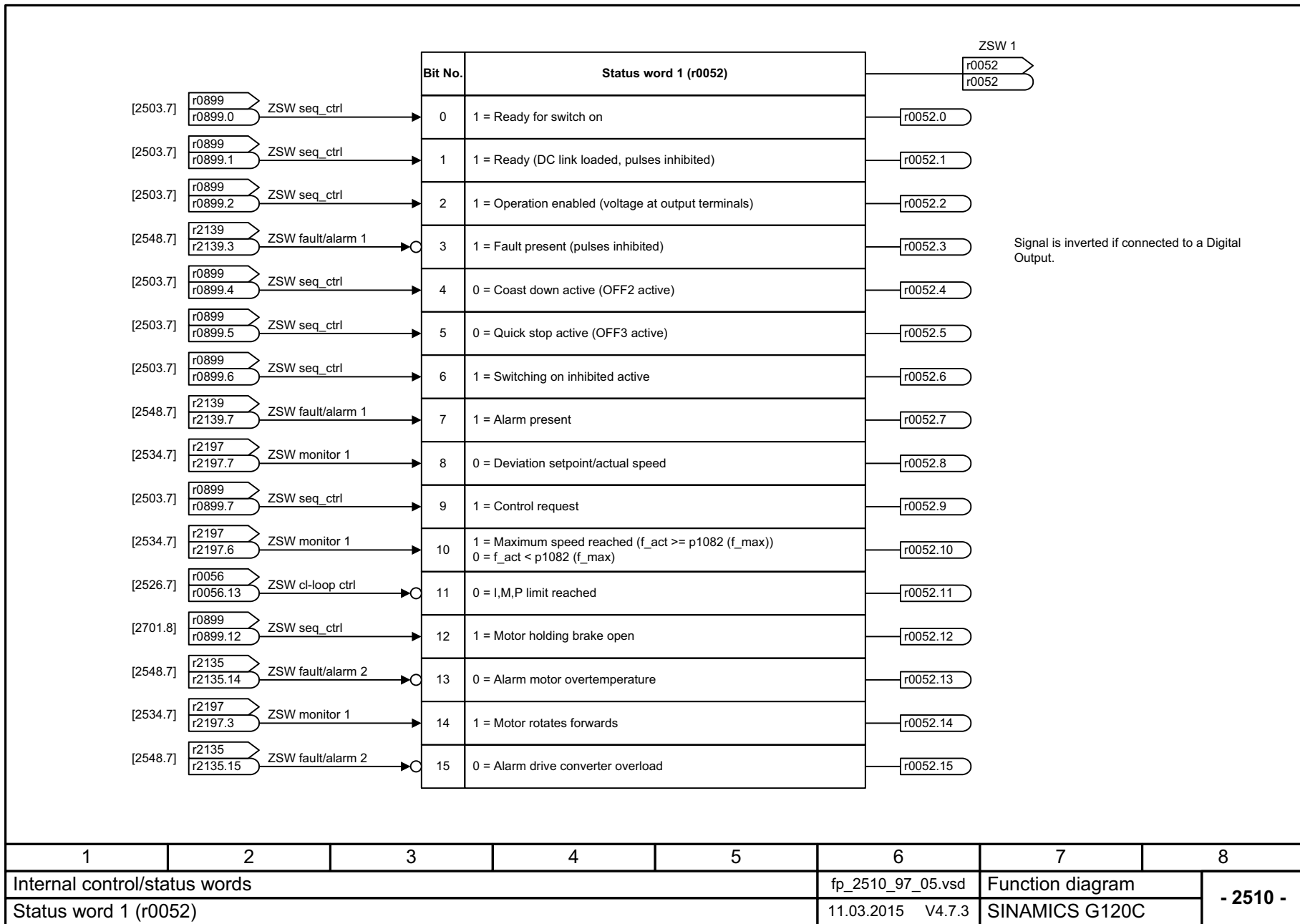
Function block diagrams

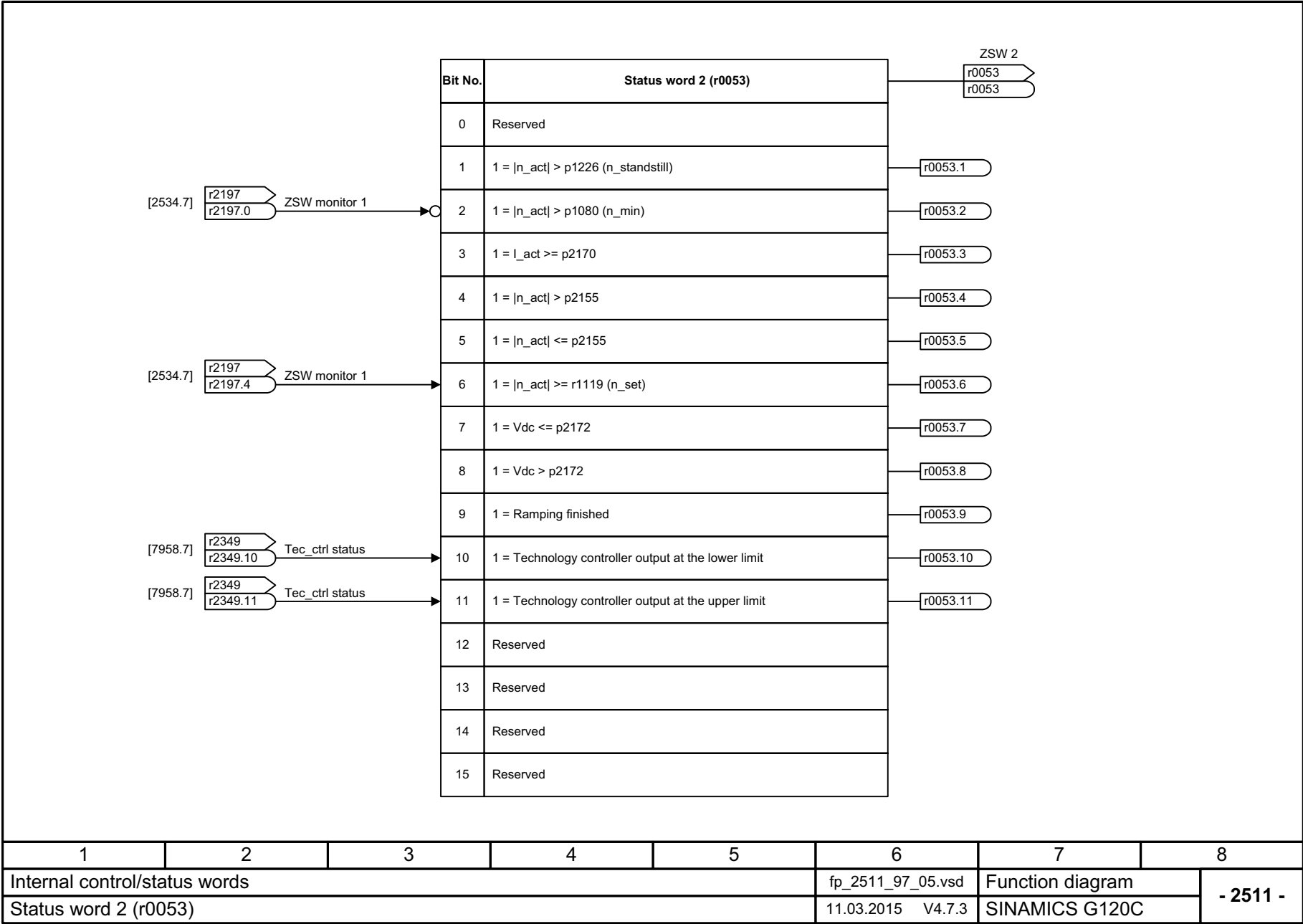
2501 – Control word, sequence control	406
2503 – Status word, sequence control	407
2505 – Control word, setpoint channel	408
2510 – Status word 1 (r0052)	409
2511 – Status word 2 (r0053)	410
2512 – Control word 1 (r0054)	411
2513 – Control word 2 (r0055)	412
2522 – Status word, speed controller	413
2526 – Status word, closed-loop control	414
2530 – Status word, closed-loop current control	415
2534 – Status word, monitoring functions 1	416
2536 – Status word, monitoring functions 2	417
2537 – Status word, monitoring functions 3	418
2546 – Control word, faults/alarms	419
2548 – Status word, faults/alarms 1 and 2	420
2610 – Sequence control - Sequencer	421
2634 – Sequence control - missing enable signals	422

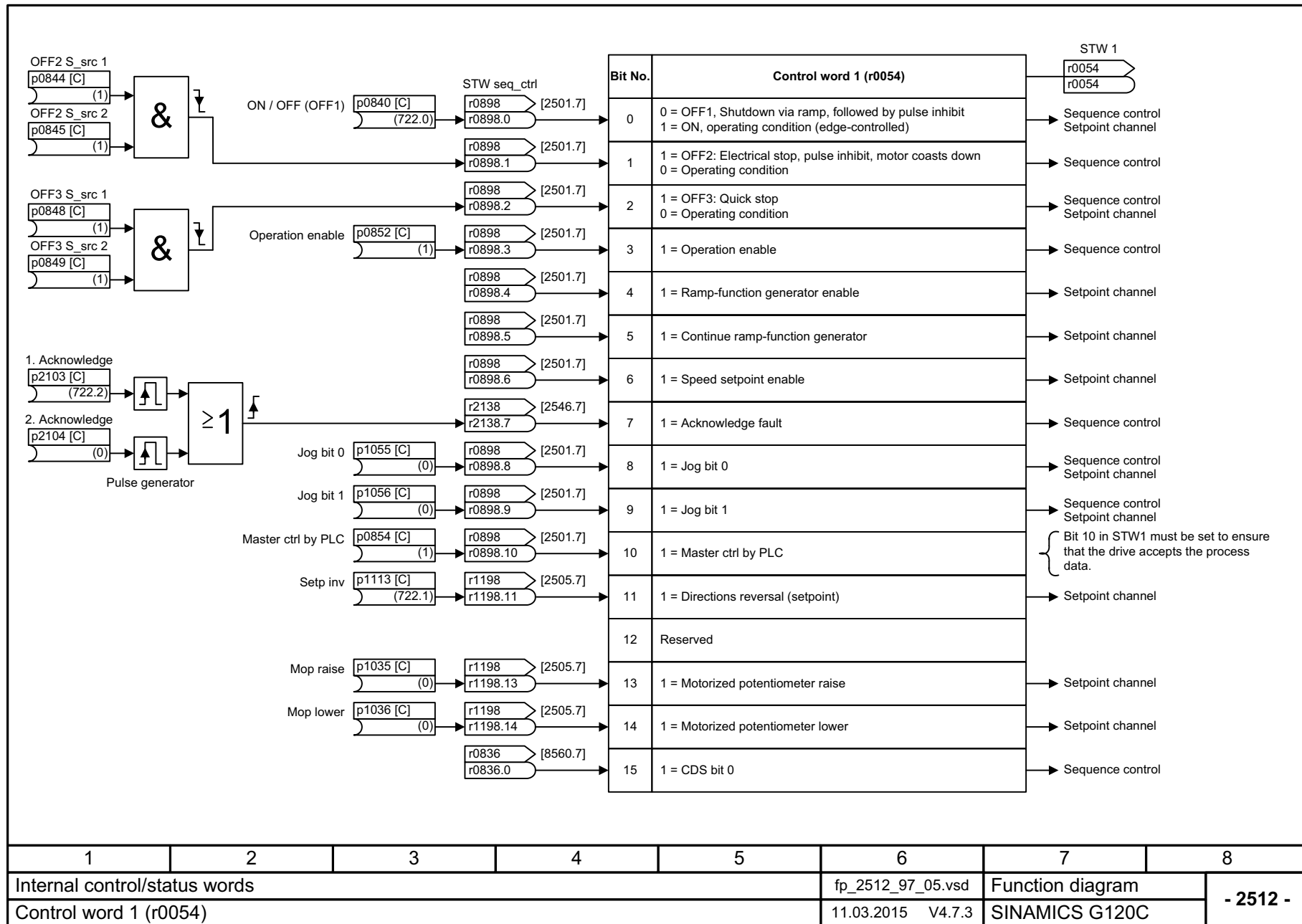


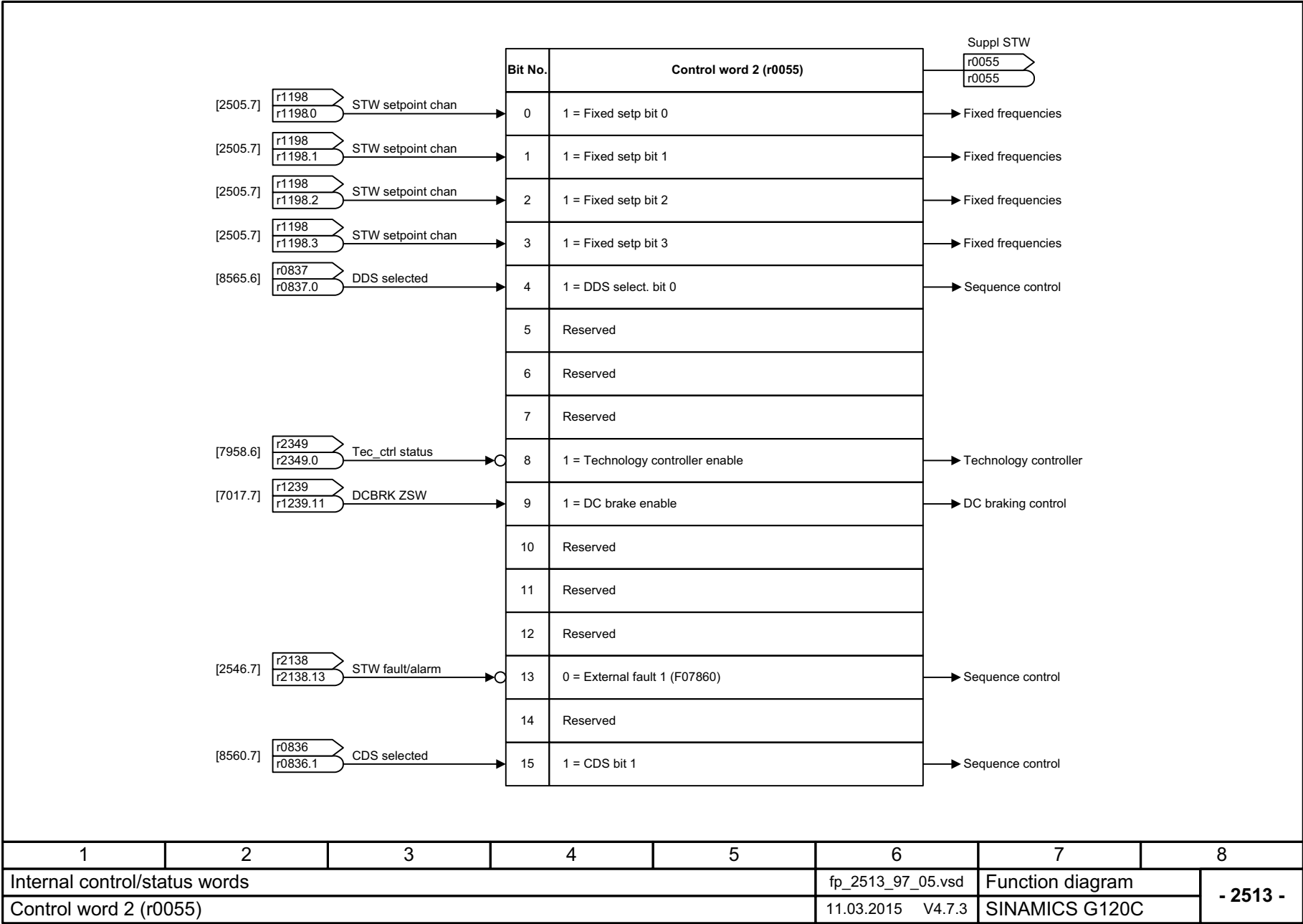












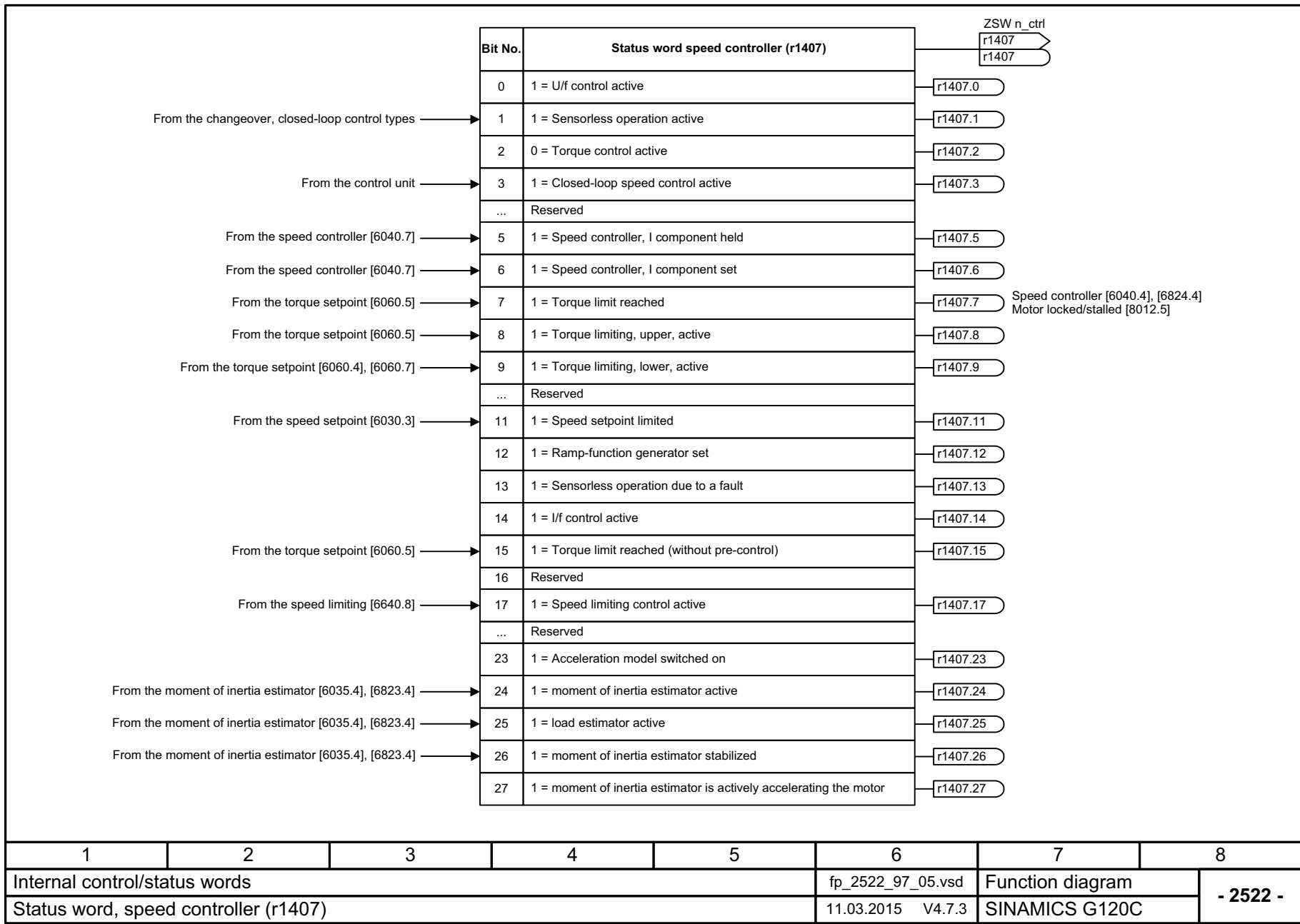
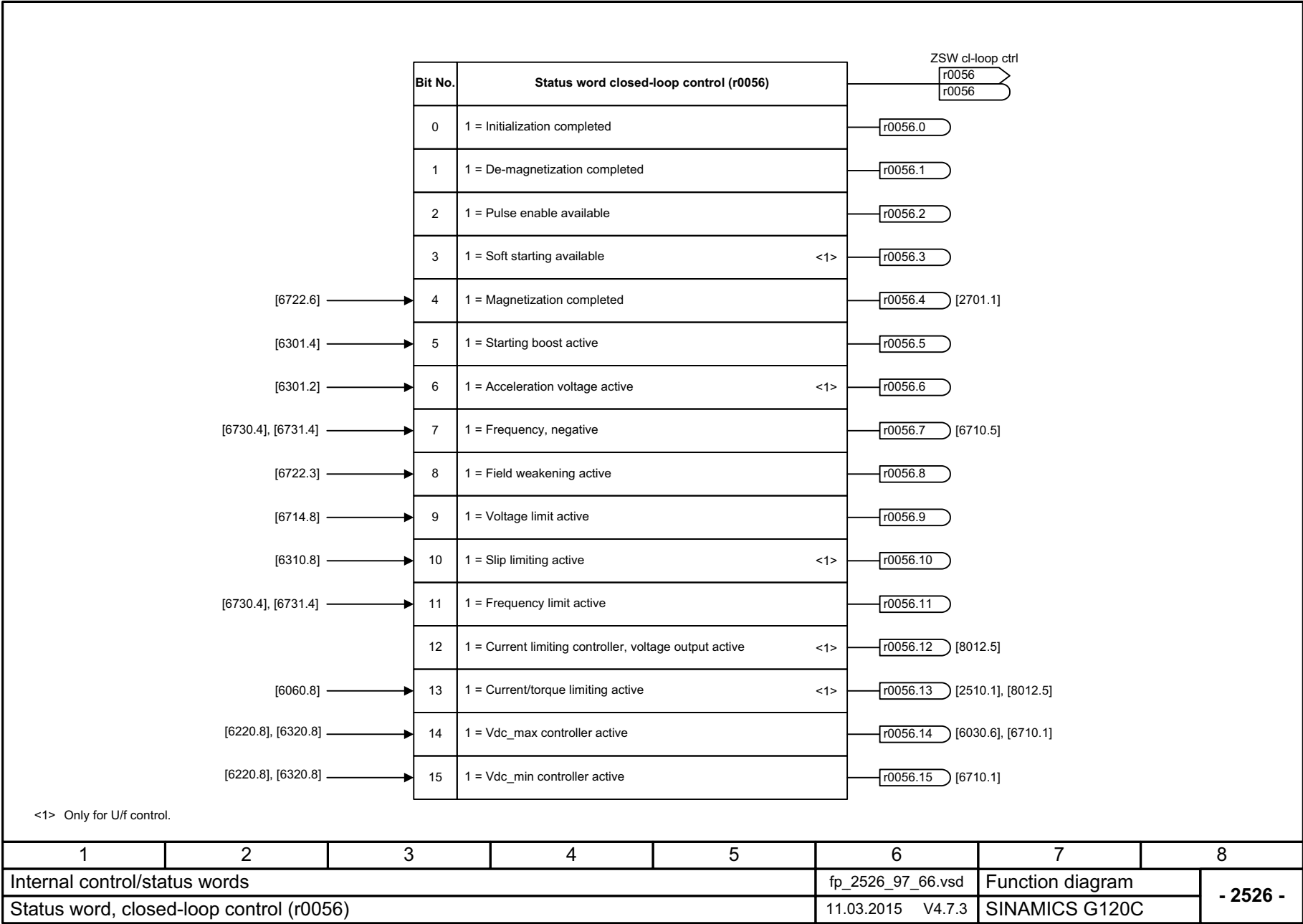


Fig. 3-46 2522 – Status word, speed controller



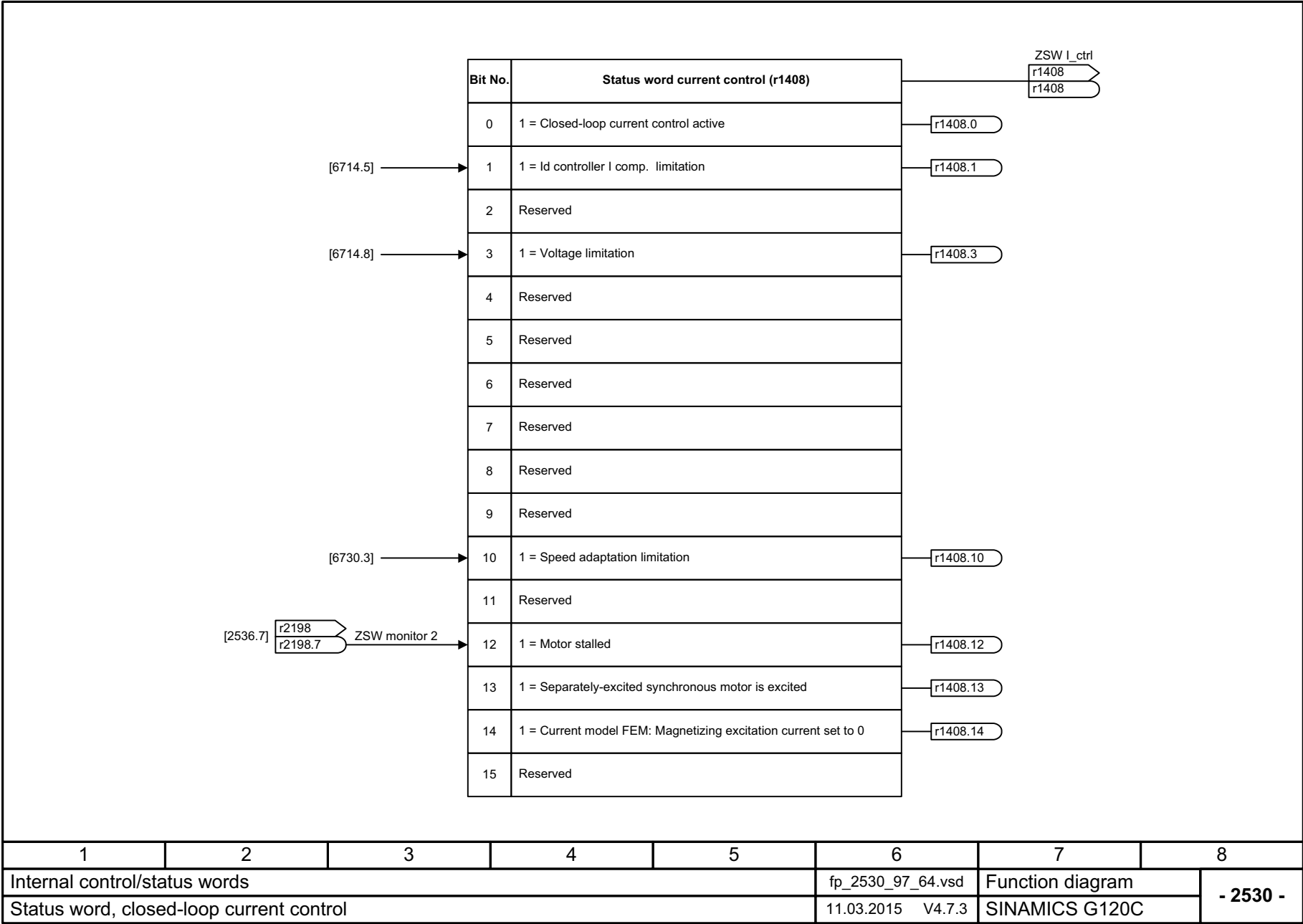
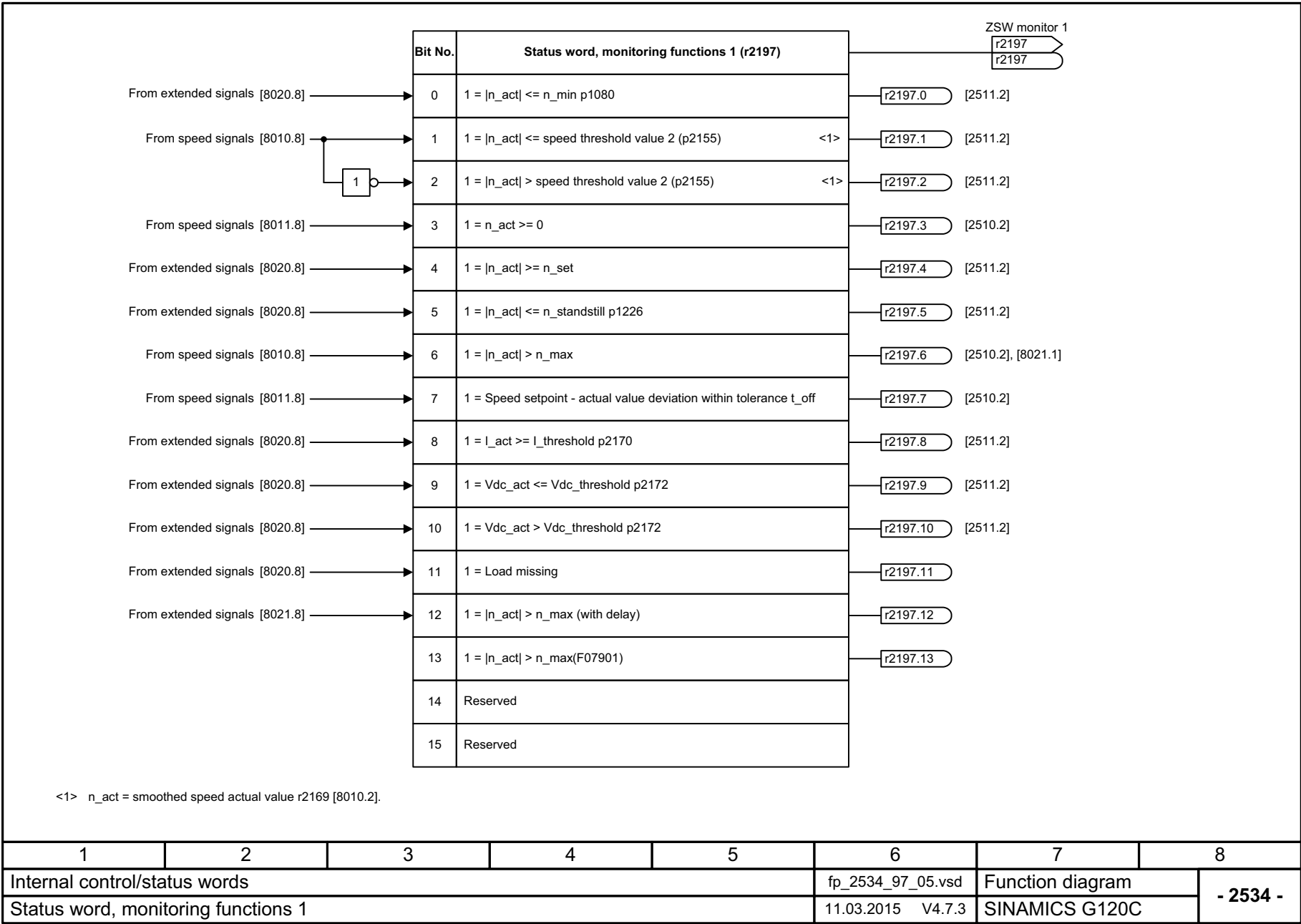


Fig. 3-48 2530 – Status word, closed-loop current control



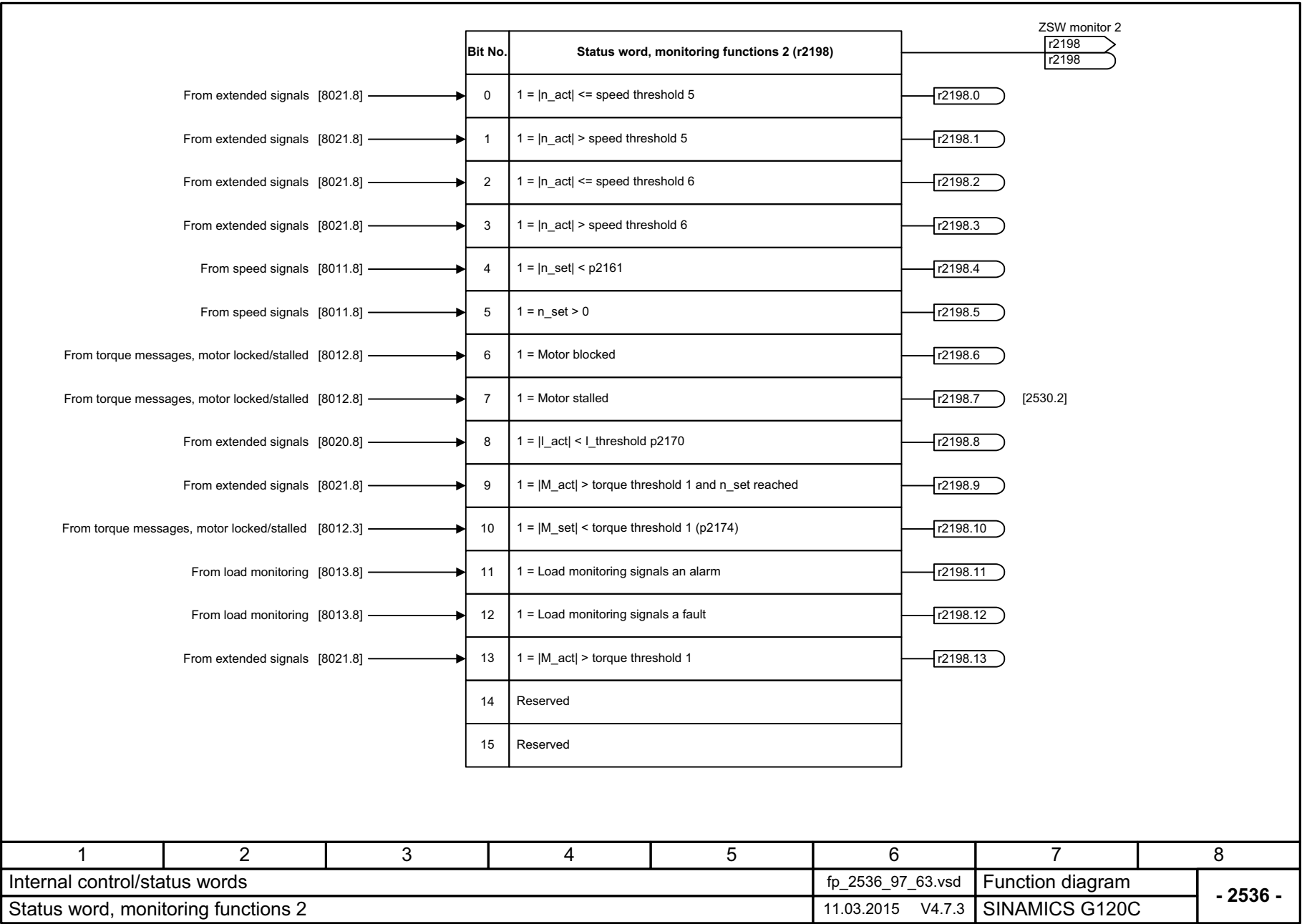


Fig. 3-50 2536 – Status word, monitoring functions 2

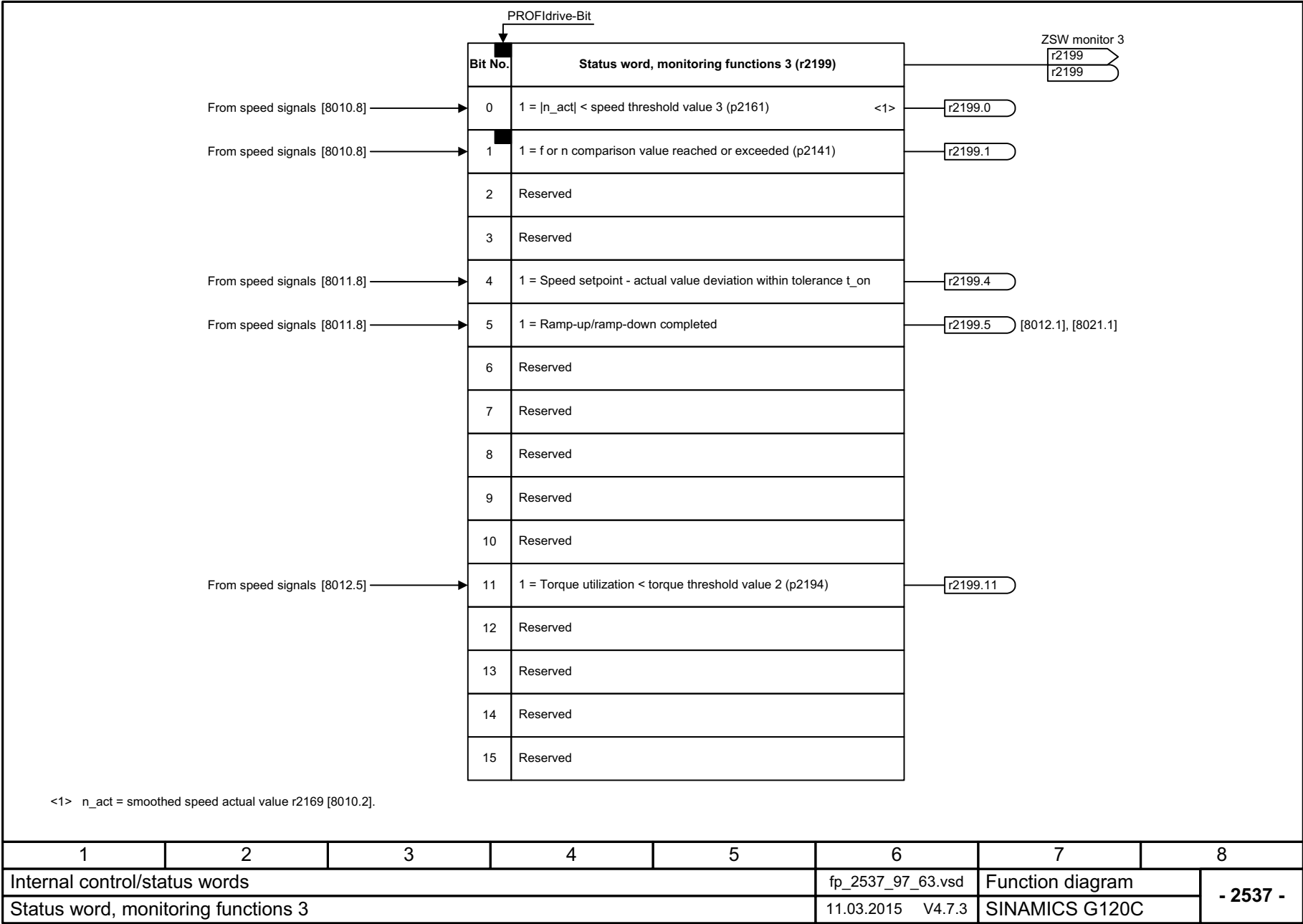
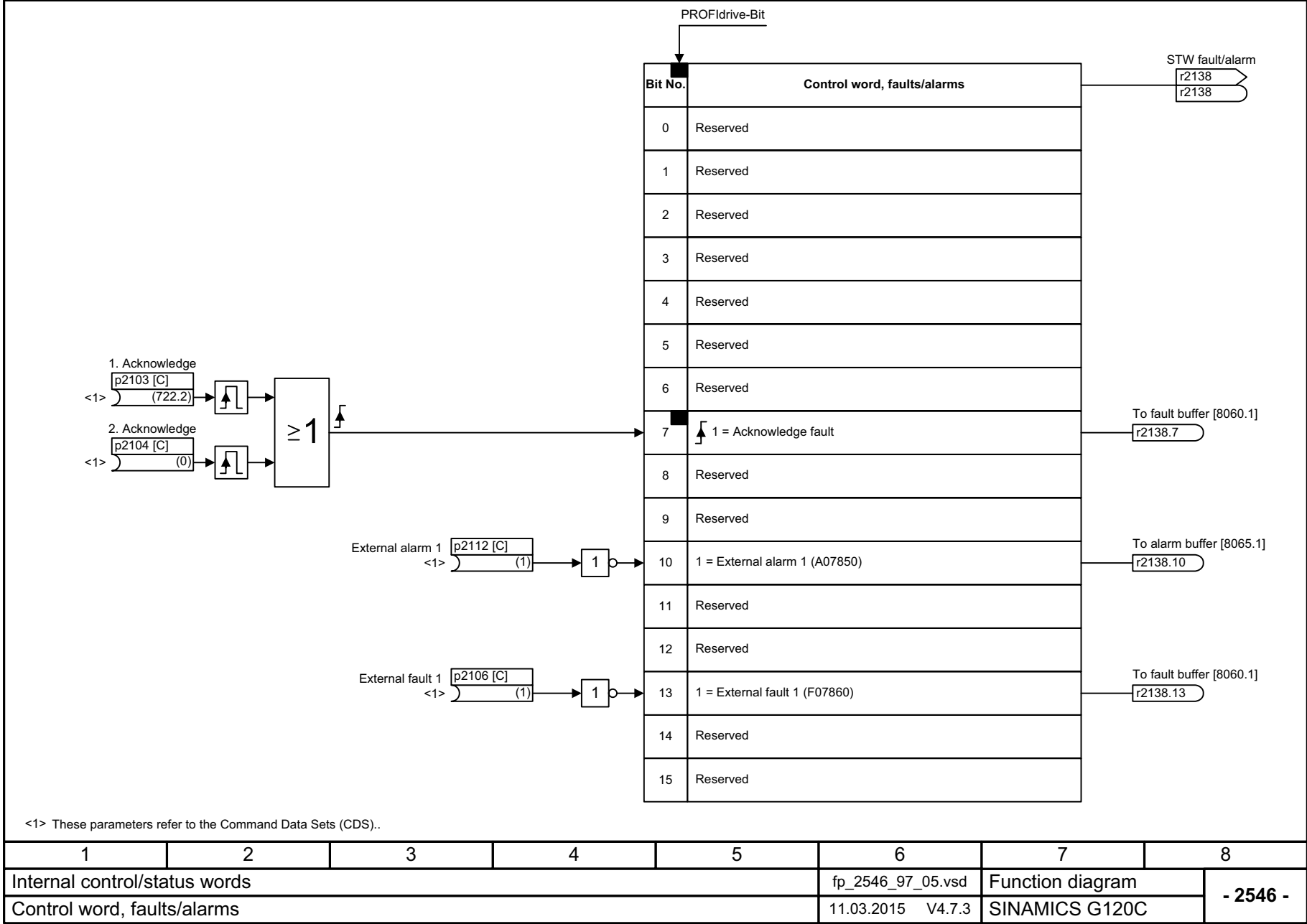


Fig. 3-51 2537 – Status word, monitoring functions 3



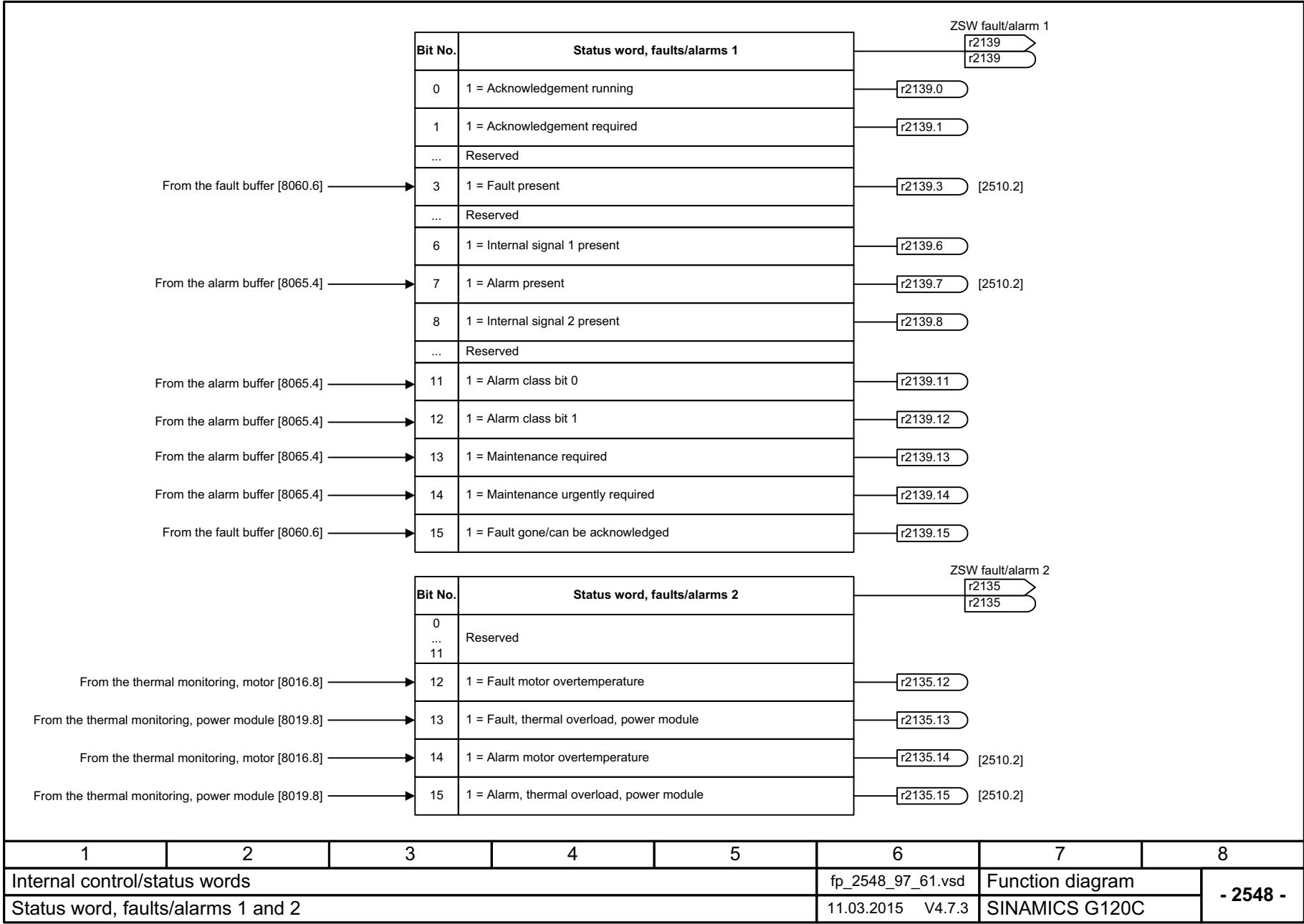
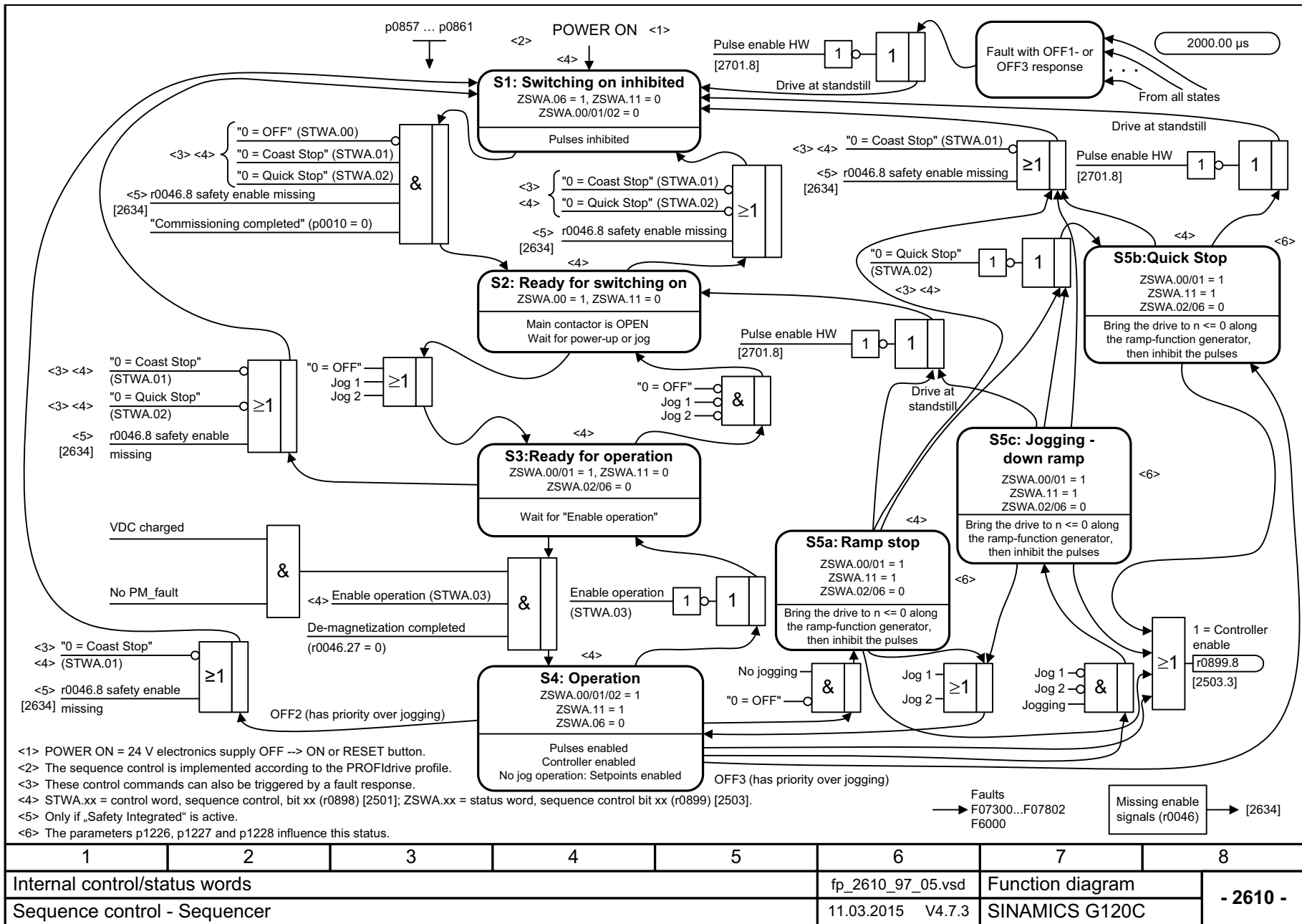


Fig. 3-53 2548 – Status word, faults/alarms 1 and 2



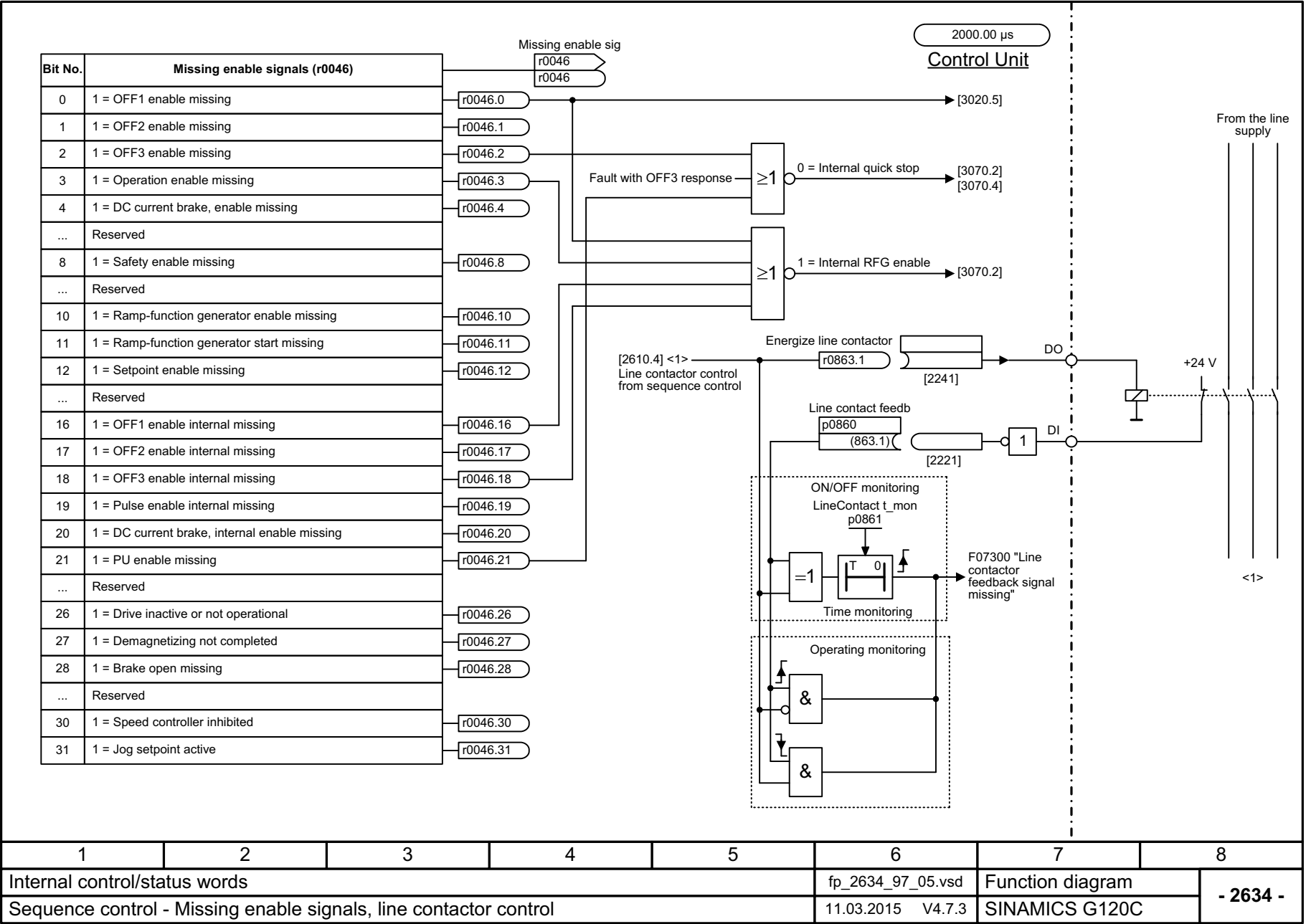


Fig. 3-55 2634 – Sequence control - missing enable signals

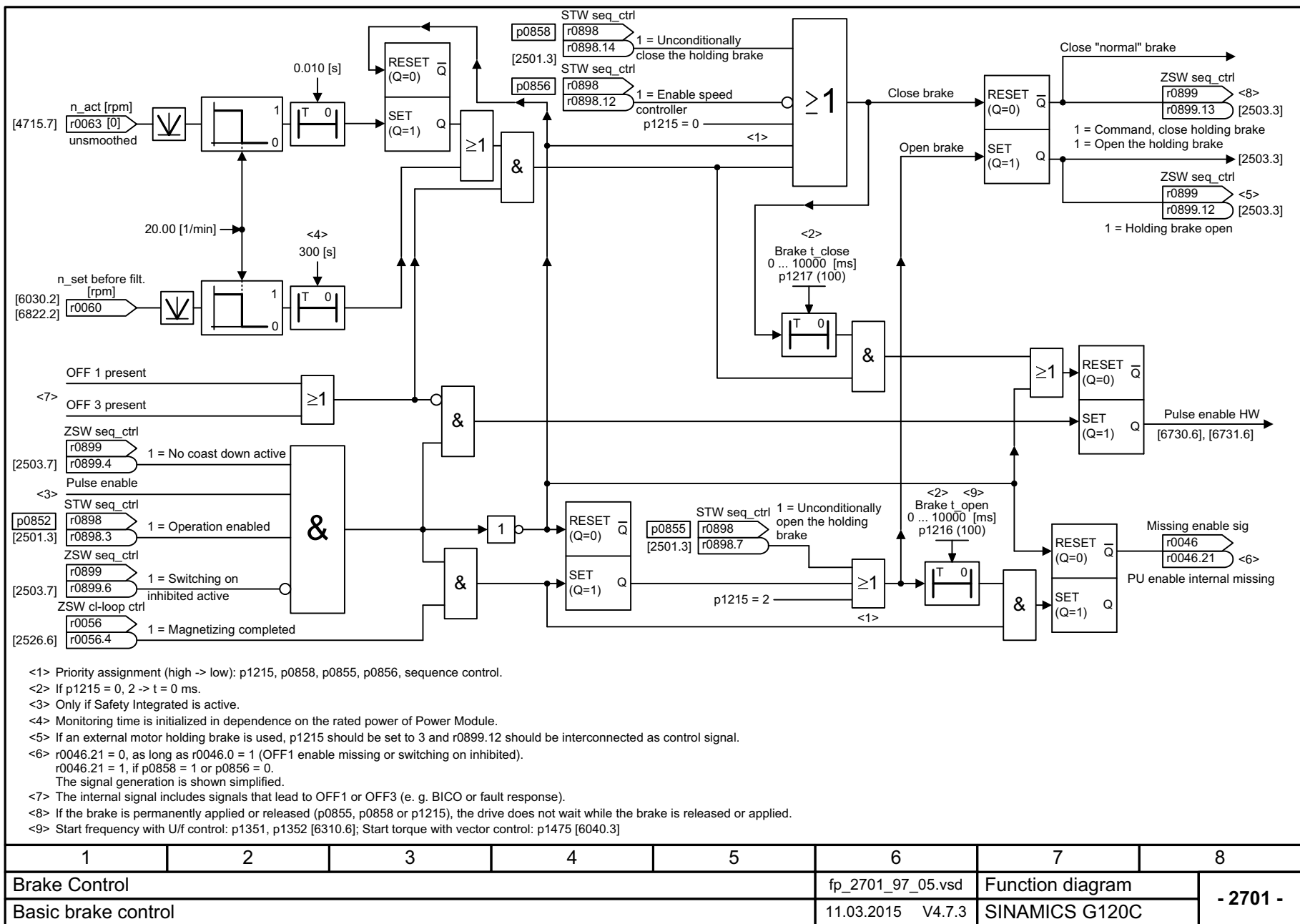
3.9 Brake control

Function block diagrams

2701 – Basic brake control

424

SINAMICS G120C
List Manual (LH13), 04/2015, A5E33840768



3.10 Safety Integrated Basic Functions

Function block diagrams

2800 – Parameter manager	426
2802 – Monitoring functions and faults/alarms	427
2804 – Status words	428
2810 – STO: Safe Torque Off	429
2813 – F-DI: Fail-safe Digital Input	430

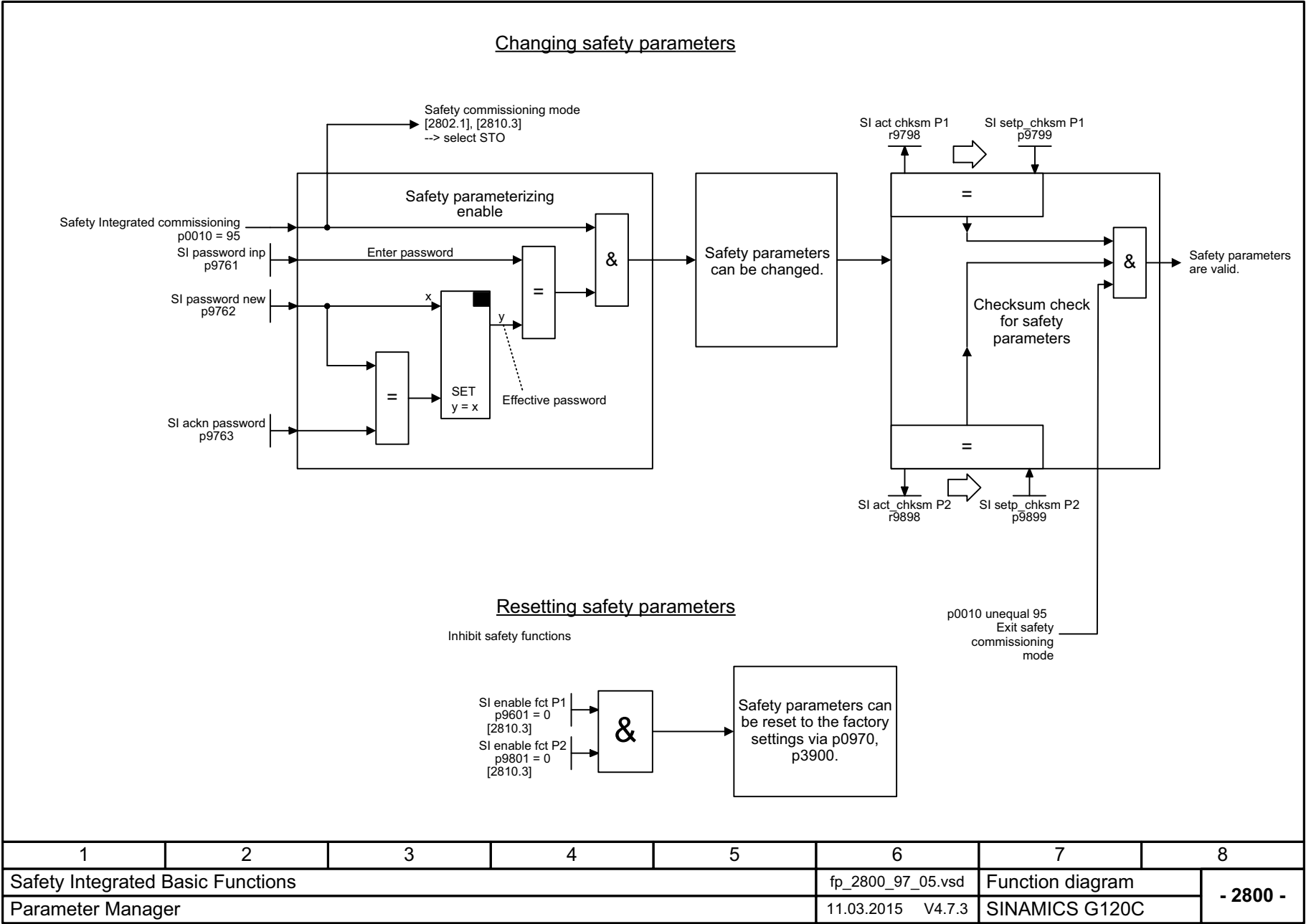
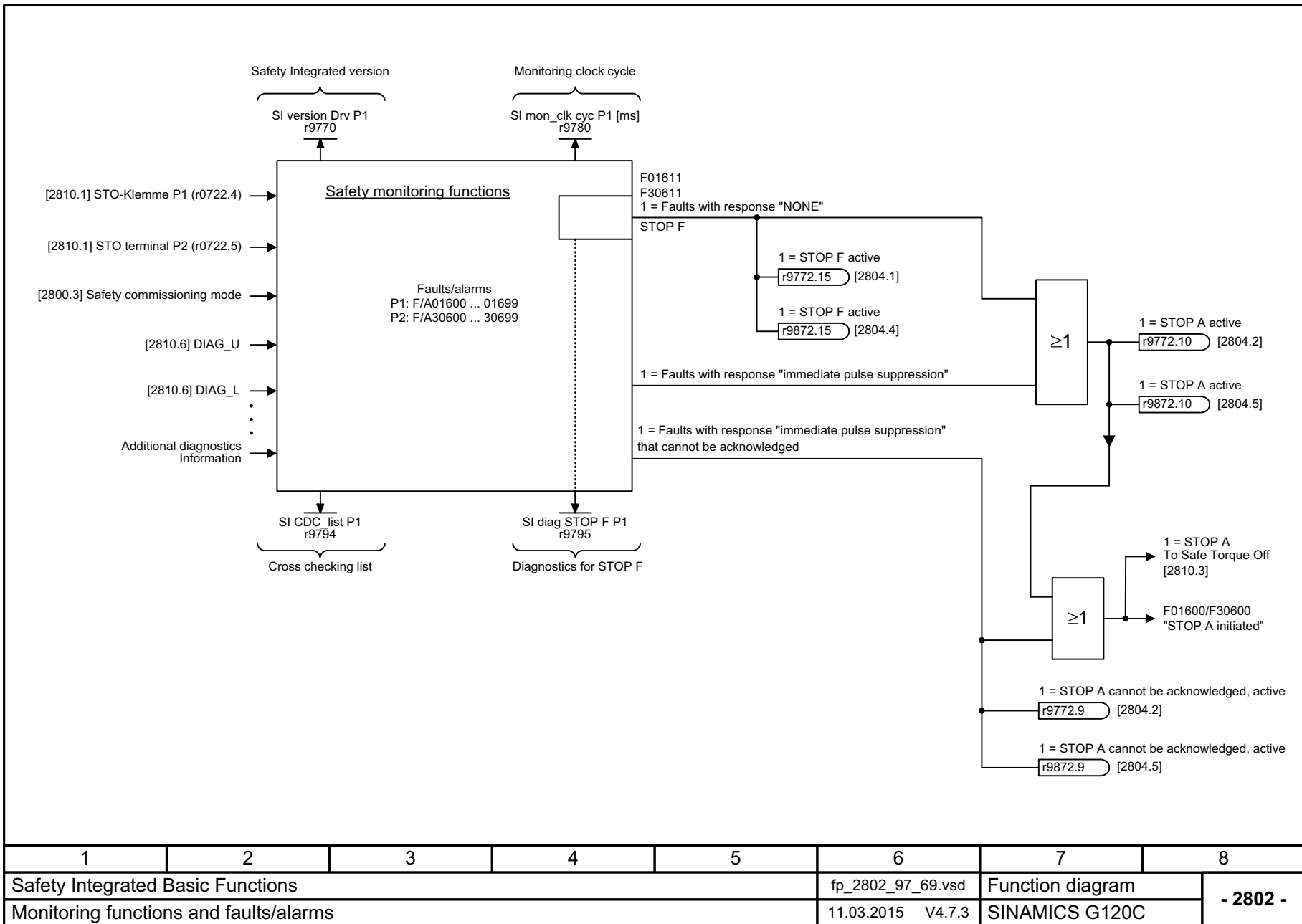
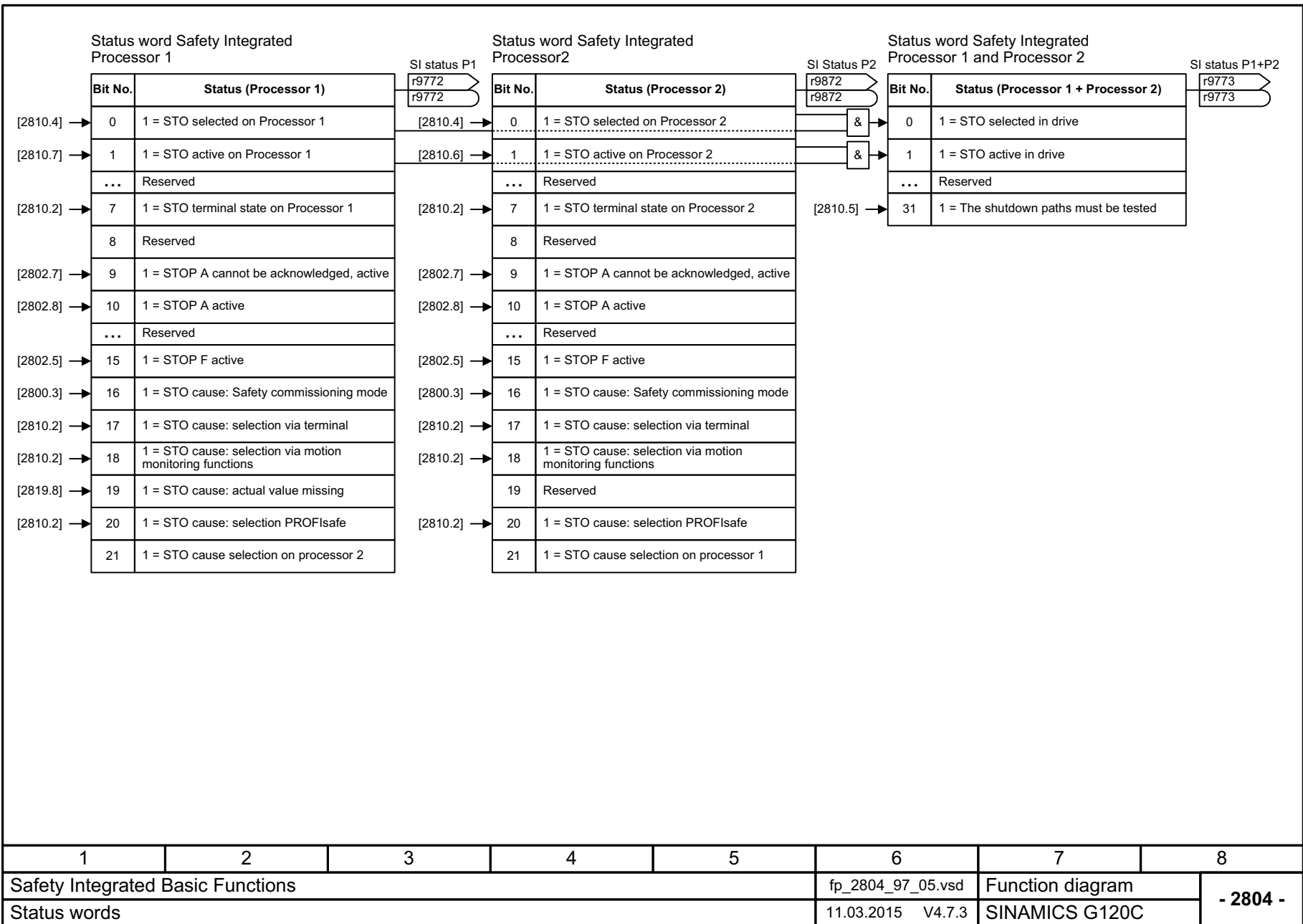
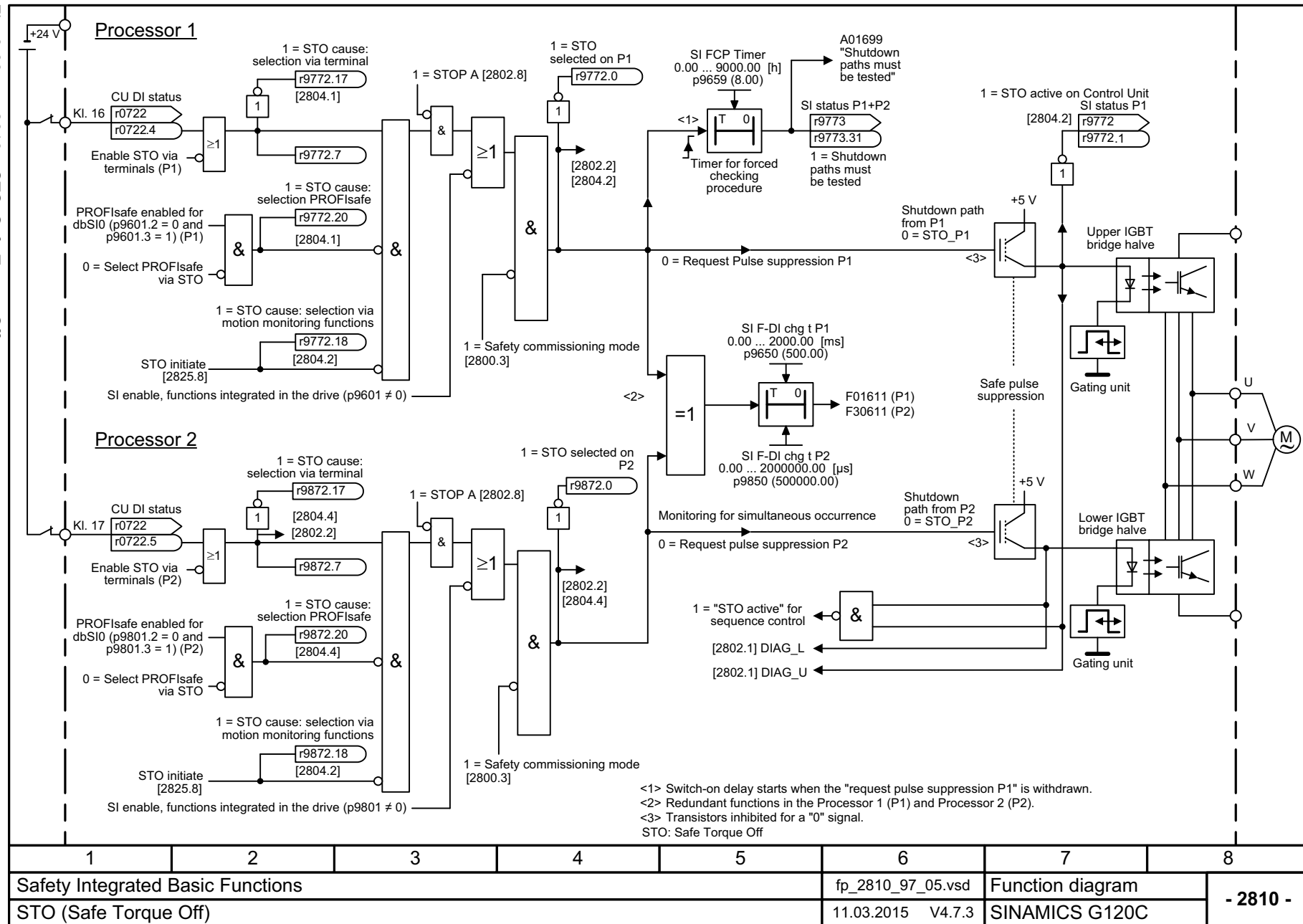


Fig. 3-57 2800 – Parameter manager







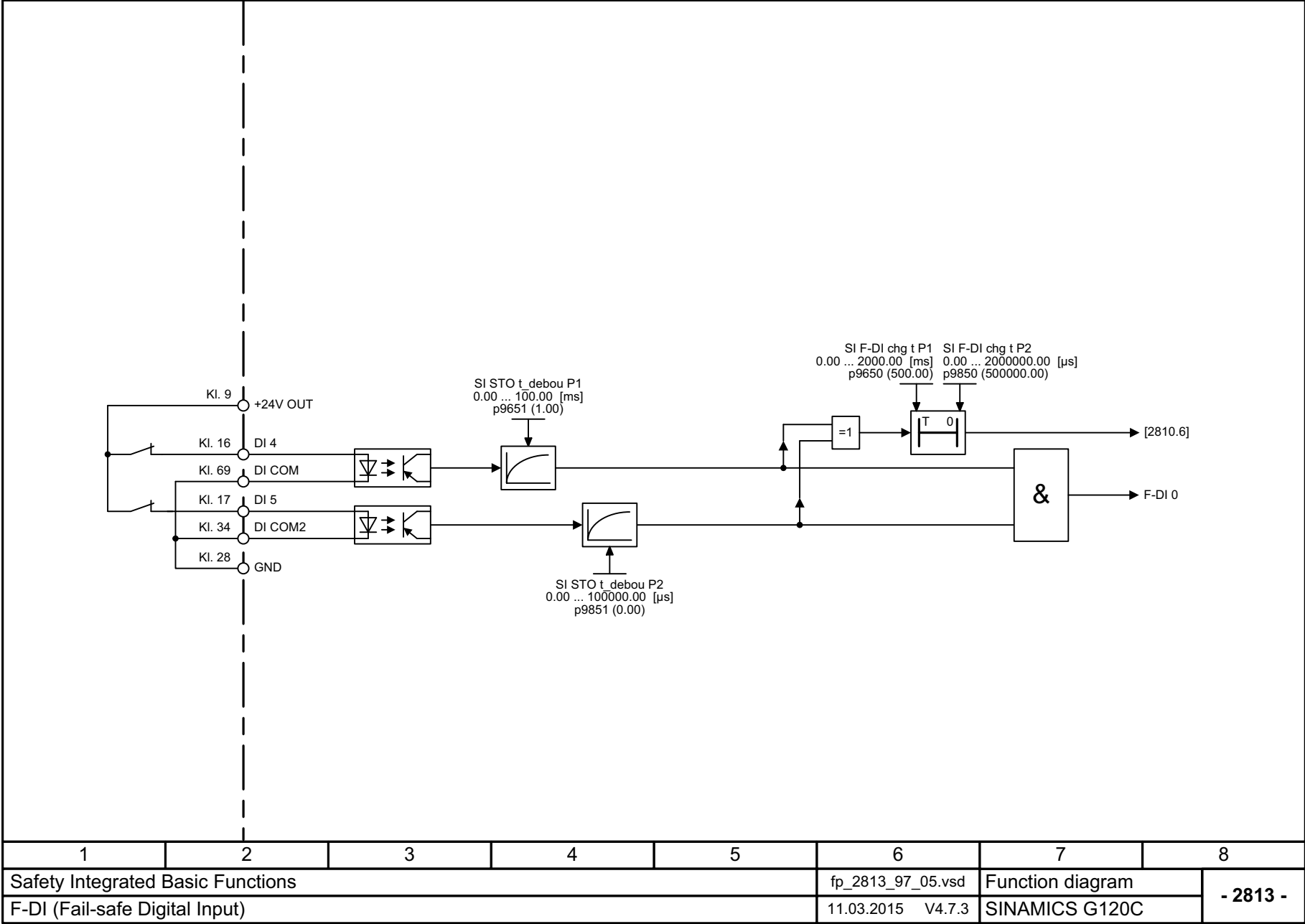


Fig. 3-61 2813 – F-DI: Fail-safe Digital Input

3.11 Safety Integrated PROFIsafe

Function block diagrams

2915 – Standard telegrams

432

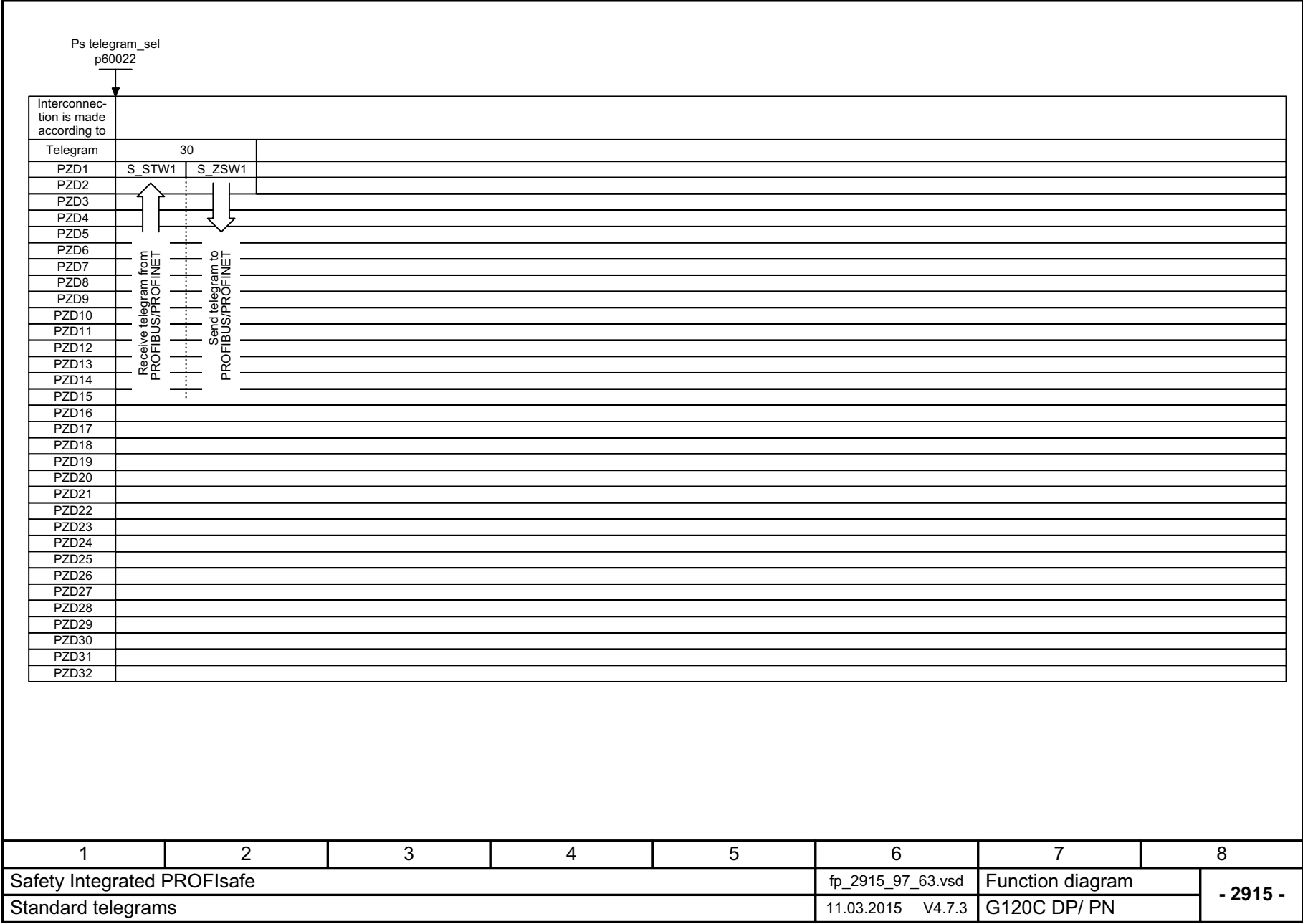


Fig. 3-62 2915 – Standard telegrams

3.12 Setpoint channel

Function block diagrams

3001 – Overview	434
3010 – Fixed speed setpoints, binary selection (p1016 = 2)	435
3011 – Fixed speed setpoints, direct selection (p1016 = 1)	436
3020 – Motorized potentiometer	437
3030 – Main/supplementary setpoint, setpoint scaling, jogging	438
3040 – Direction limitation and direction reversal	439
3050 – Skip frequency bands and speed limitations	440
3070 – Extended ramp-function generator	441

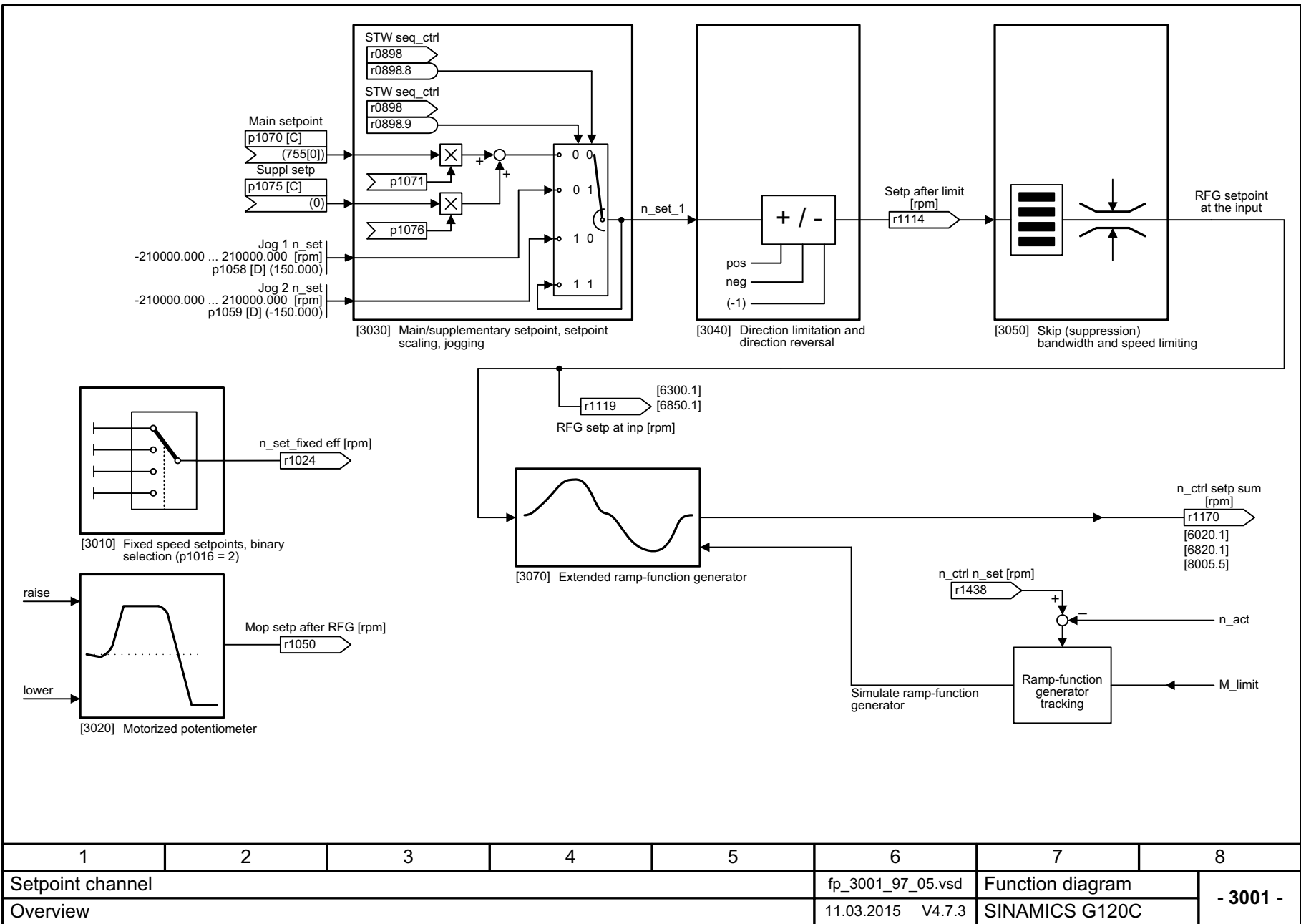


Fig. 3-63 3001 – Overview

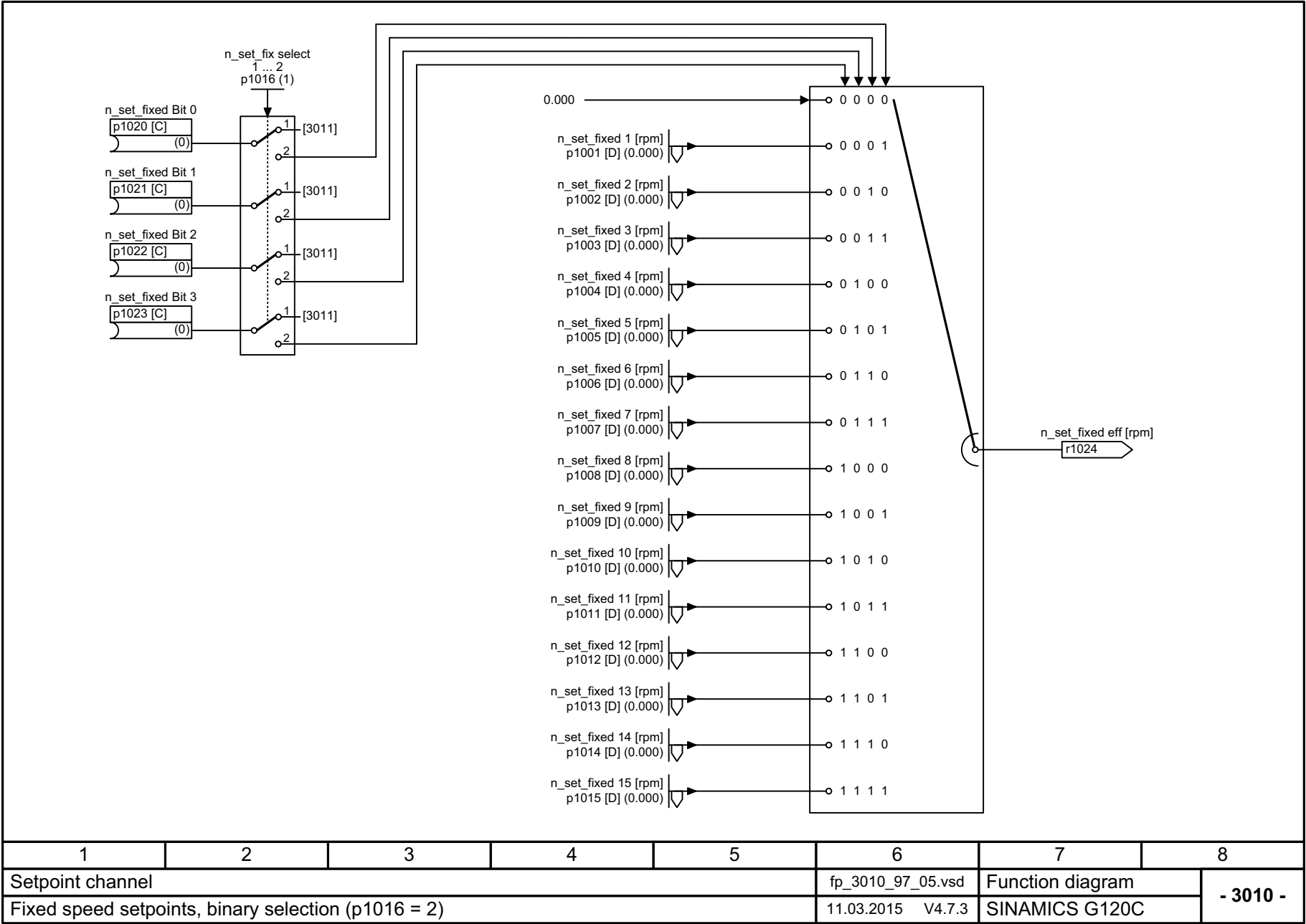
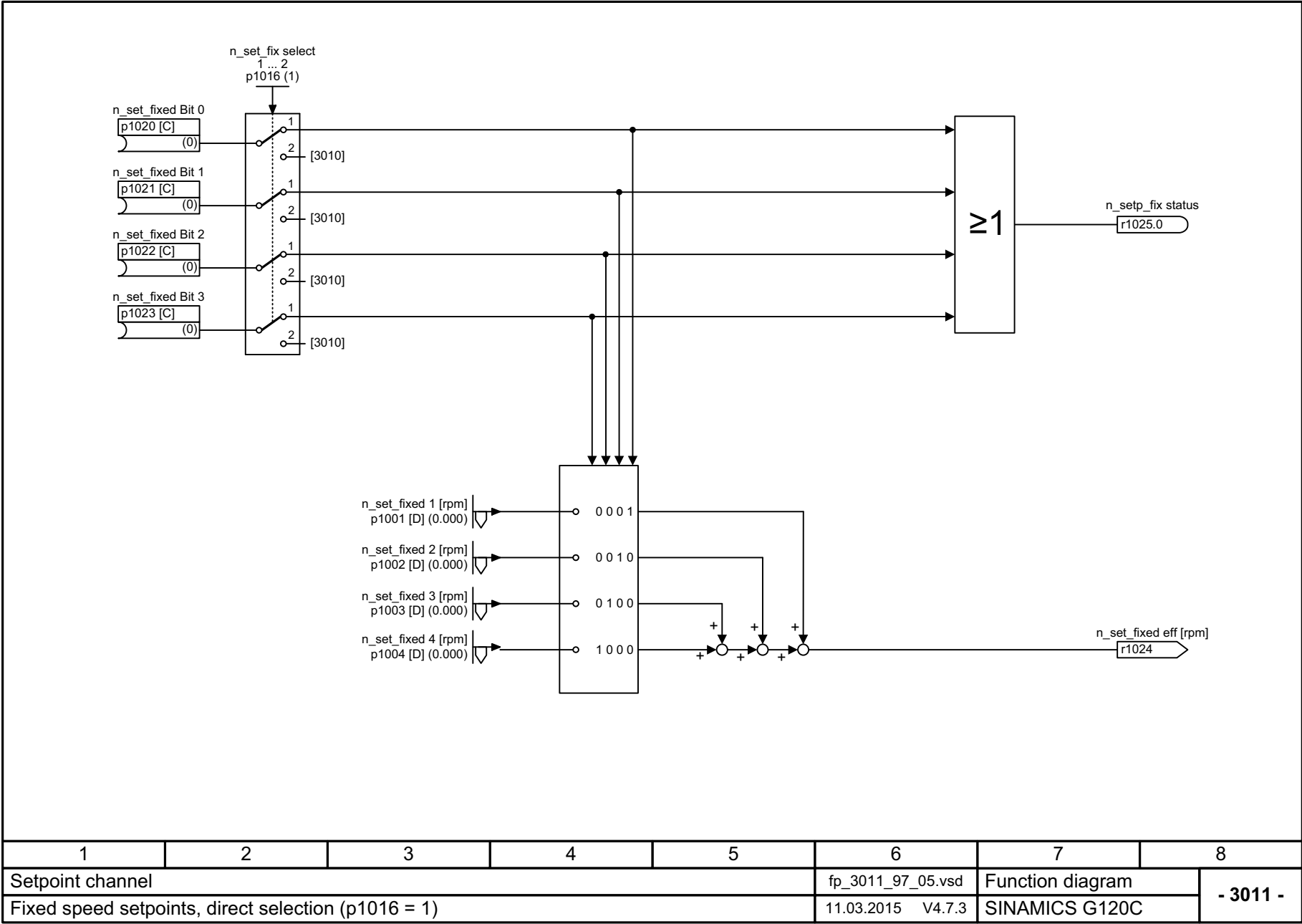
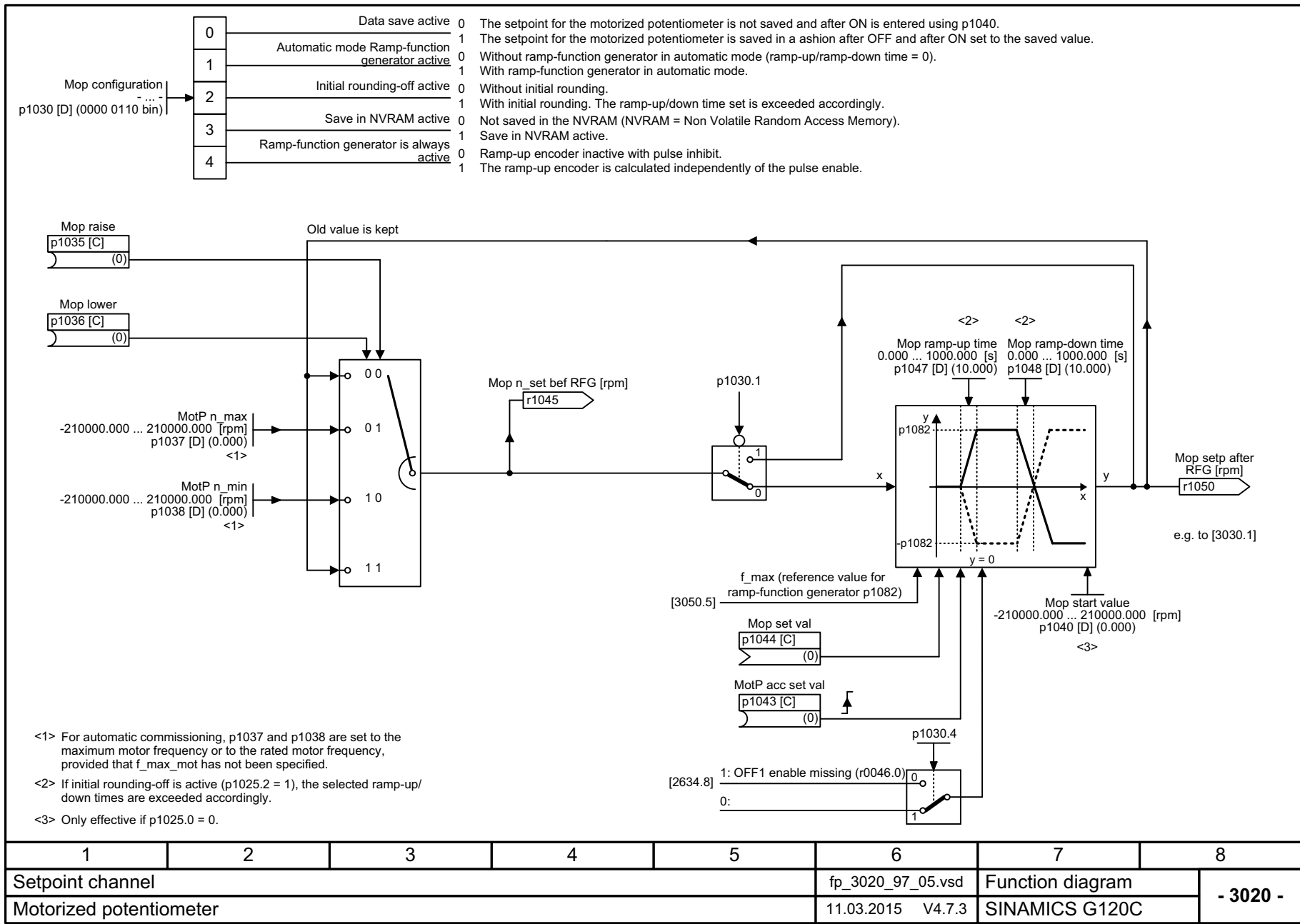
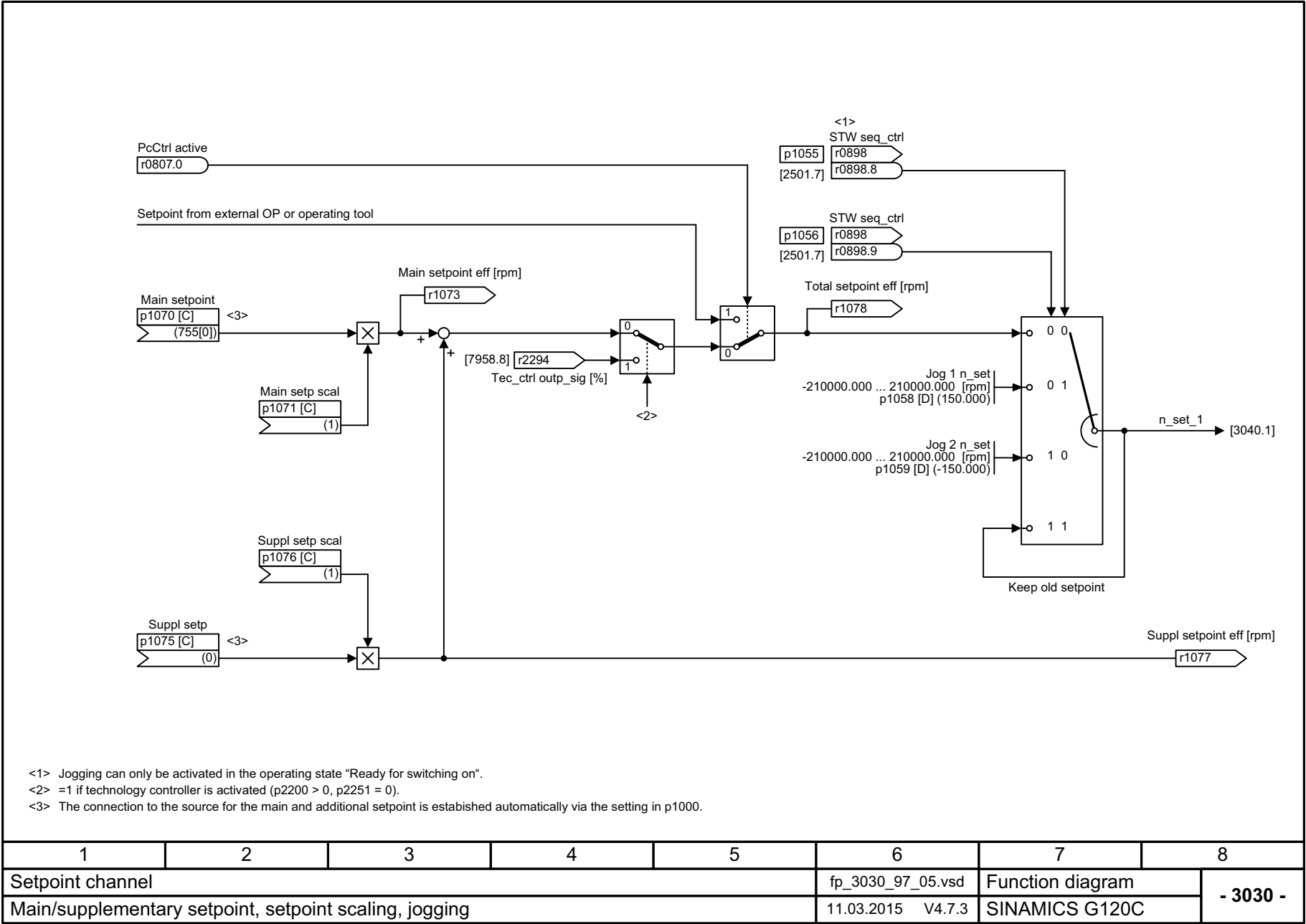
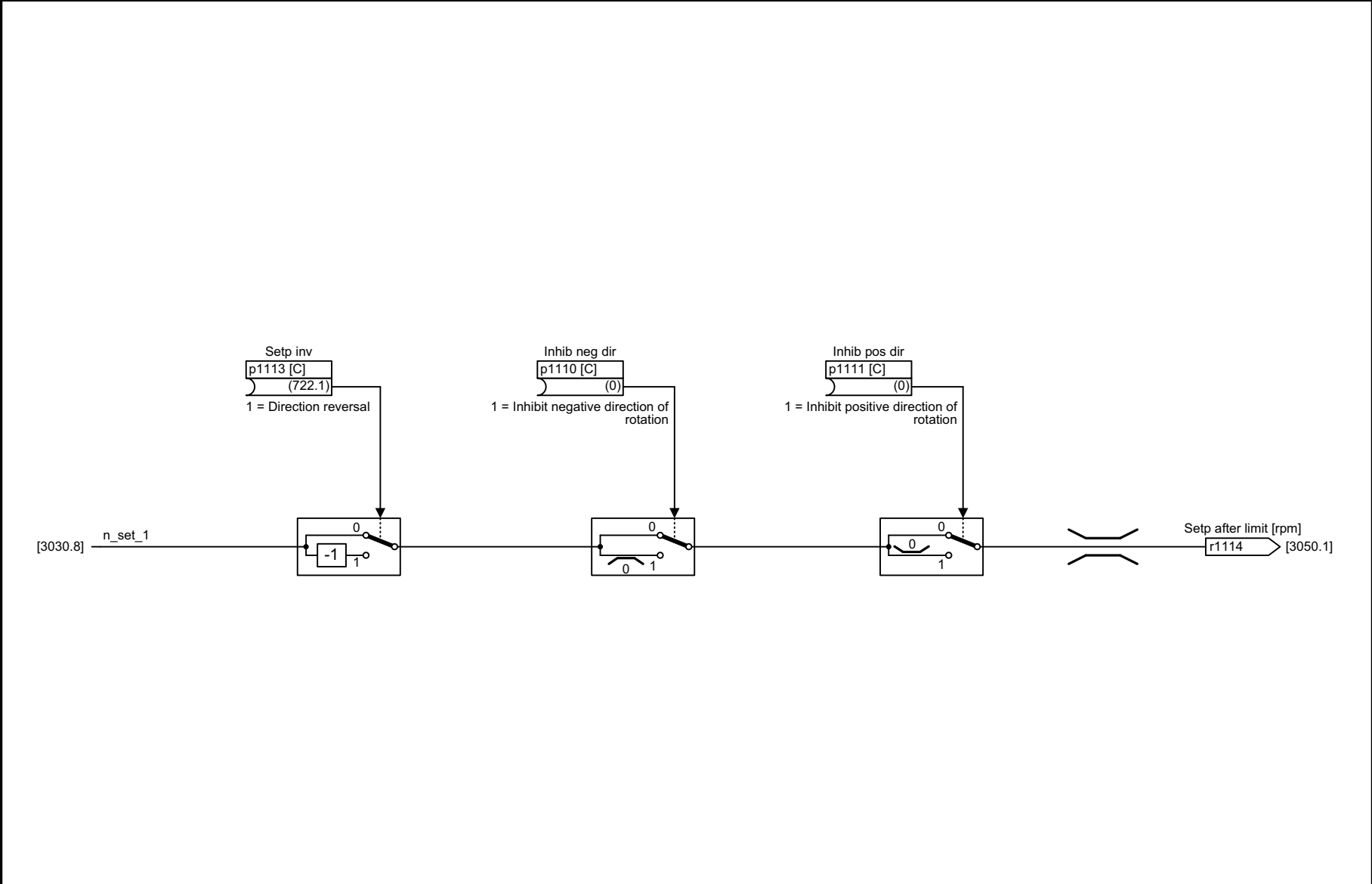


Fig. 3-64 3010 – Fixed speed setpoints, binary selection (p1016 = 2)





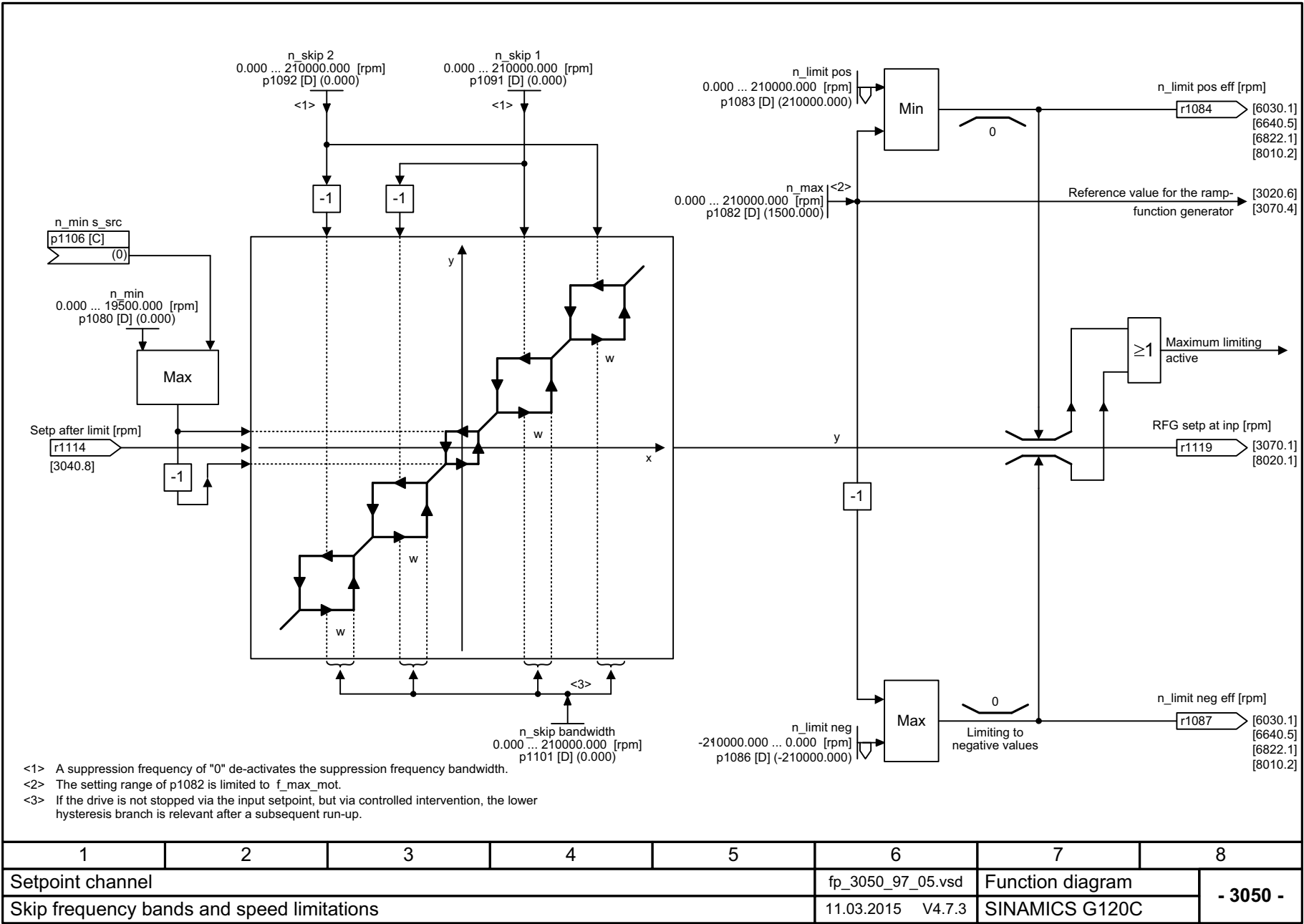


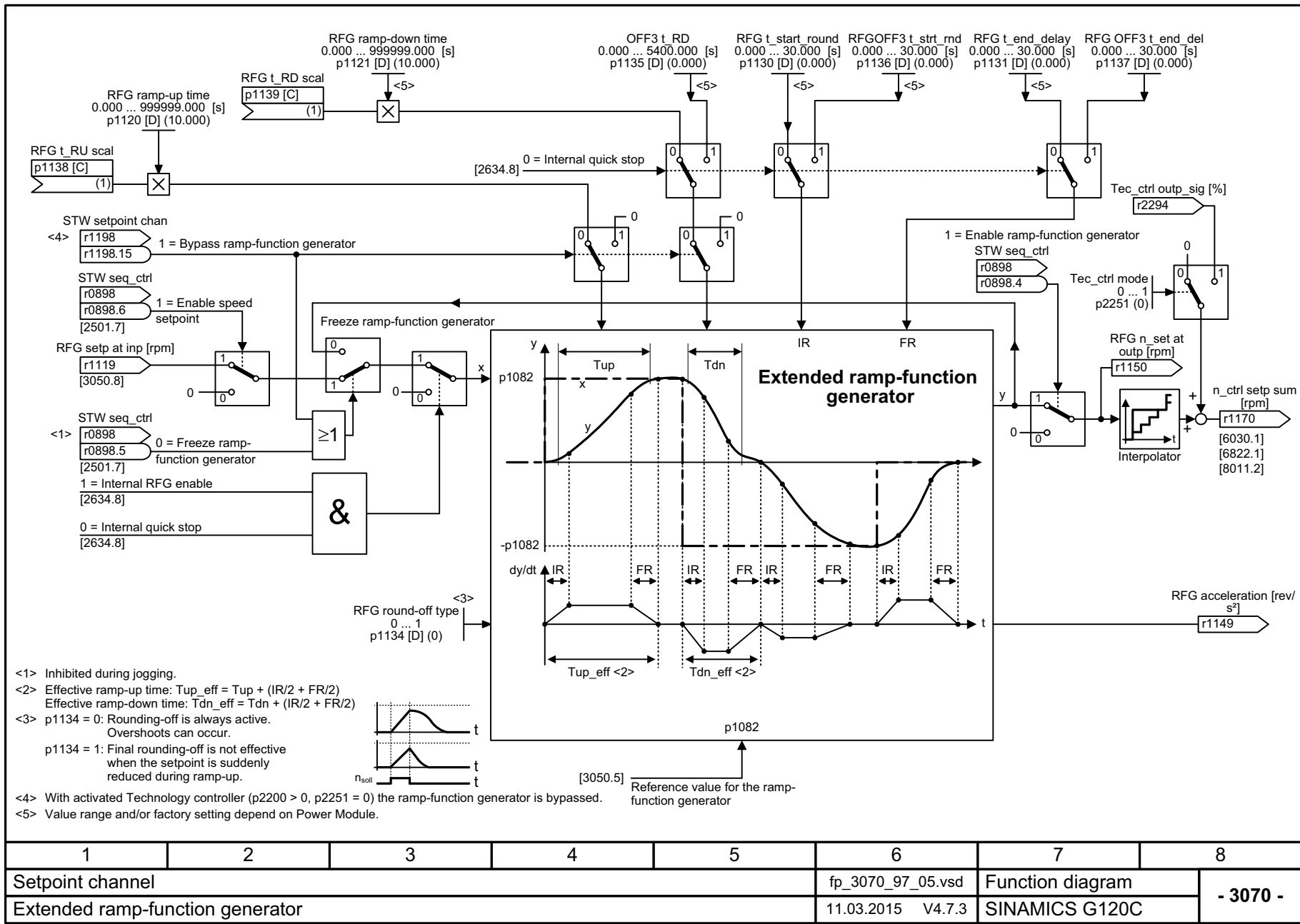


1	2	3	4	5	6	7	8
Setpoint channel					fp_3040_97_05.vsd	Function diagram	
Direction limitation and direction reversal					11.03.2015 V4.7.3		

- 3040 -

Fig. 3-68 3040 – Direction limitation and direction reversal





3.13 Vector control

Function block diagrams

6019 – Application classes (p0096), overview	443
6020 – Speed control and generation of the torque limits, overview	444
6030 – Speed setpoint, acceleration model	445
6035 – Moment of inertia estimator	446
6040 – Speed controller	447
6060 – Torque setpoint	448
6220 – Vdc_max controller and Vdc_min controller	449
6300 – U/f control, overview	450
6301 – U/f characteristic and voltage boost	451
6310 – Resonance damping and slip compensation (U/f)	452
6320 – Vdc_max controller	453
6490 – Speed control configuration	454
6630 – Upper/lower torque limit	455
6640 – Current/power/torque limits	456
6700 – Current control, overview	457
6710 – Current setpoint filter	458
6714 – Iq and Id controllers	459
6721 – Id setpoint (PMSM, p0300 = 2)	460
6722 – Field weakening characteristic, flux setpoint (ASM, p0300 = 1)	461
6723 – Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1)	462
6724 – Field weakening controller (PMSM, p0300 = 2)	463
6730 – Interface to the Power Module (ASM, p0300 = 1)	464
6731 – Interface to the Power Module (PMSM, p0300 = 2)	465
6799 – Display signals	466

Fig. 3-71

(p0096), overview

	Possible application classes (p0096) <1>			
	For induction motors (p0300 = 1xx)	For synchronous motors (p0300 = 2xx)	For reluctance motors (p0300 = 6xx)	Applicable function diagrams:
PM240	p0096 = 0	p0096 = 0	p0096 = 0	Chapter "Vector control"
	p0096 = 1	✗	✗	Chapter "Vector control, Standard Drive Control (p0096 = 1)" + [6799]
	p0096 = 2	p0096 = 2	p0096 = 2	Chapter "Vector control, Dynamic Drive Control (p0096 = 2)" + [6490], [6491], [6799]

```
<1> p0096 = 0: Expert
      p0096 = 1: Standard Drive Control
      p0096 = 2: Dynamic Drive Control
```

1	2	3	4	5	6	7	8
Vector control					fp_6019_97_05.vsd	Function diagram	- 6019 -
Application classes (p0096), overview					11.03.2015 V4.7.3	SINAMICS G120C	

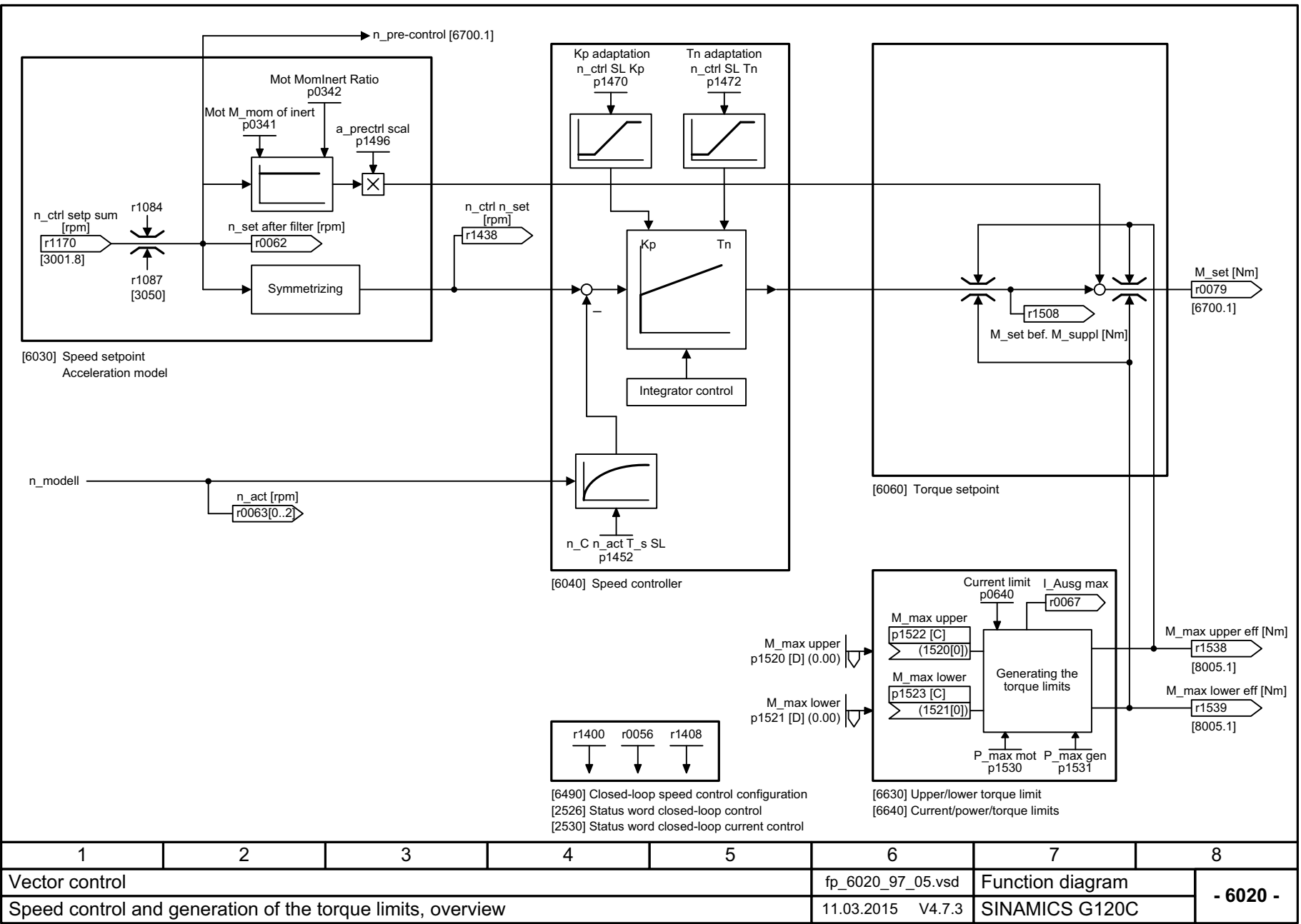


Fig. 3-72 6020 – Speed control and generation of the torque limits, overview

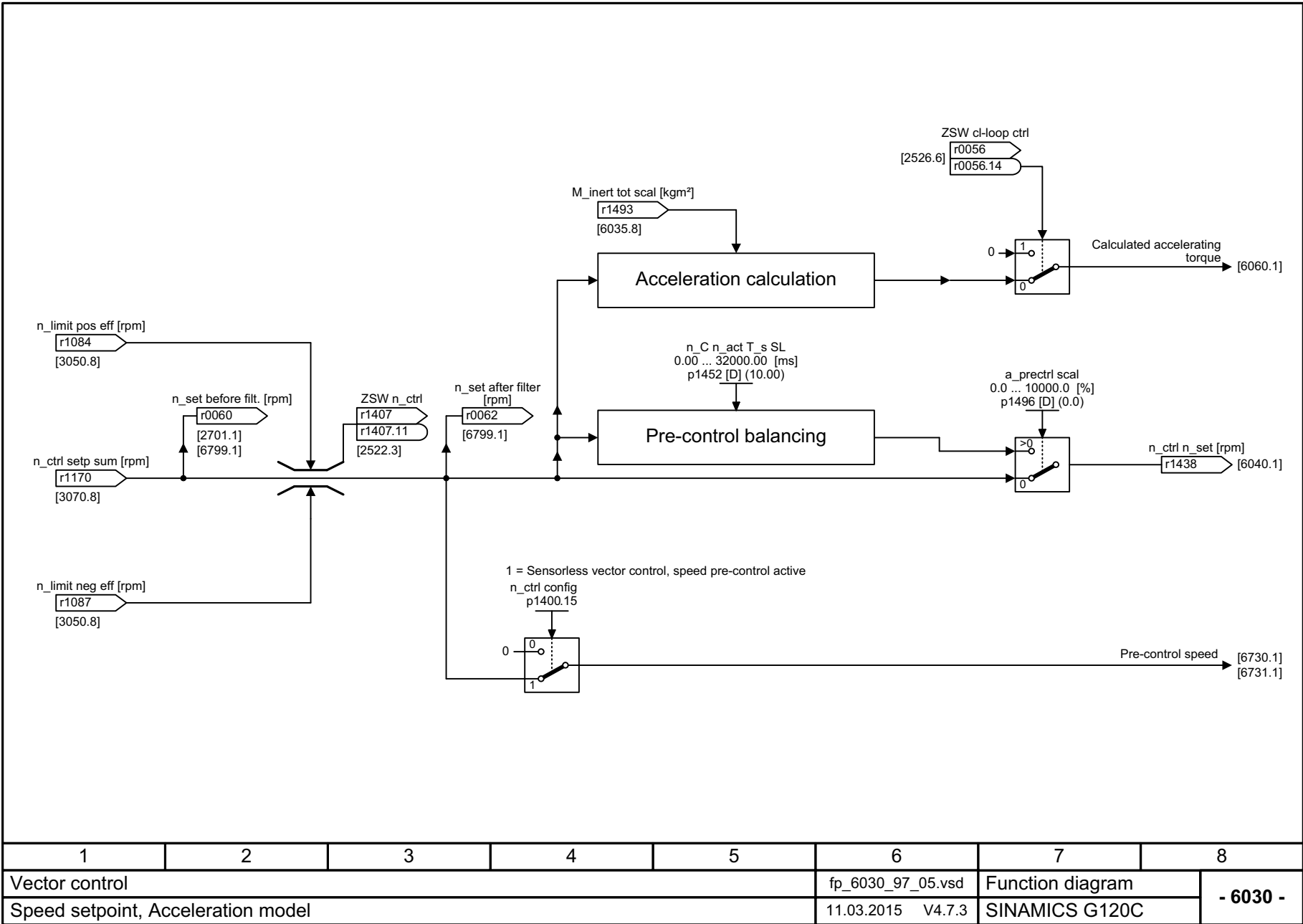
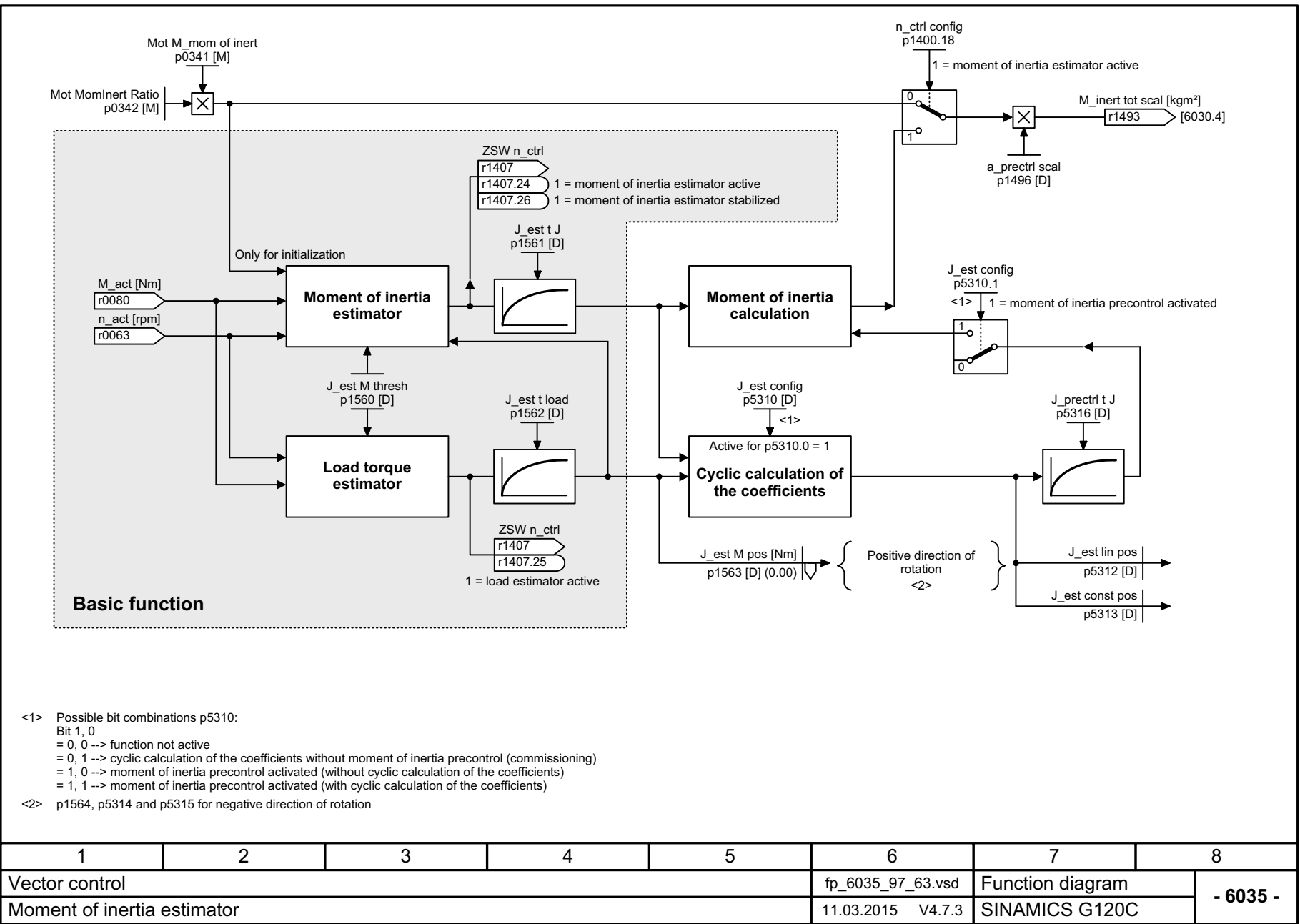
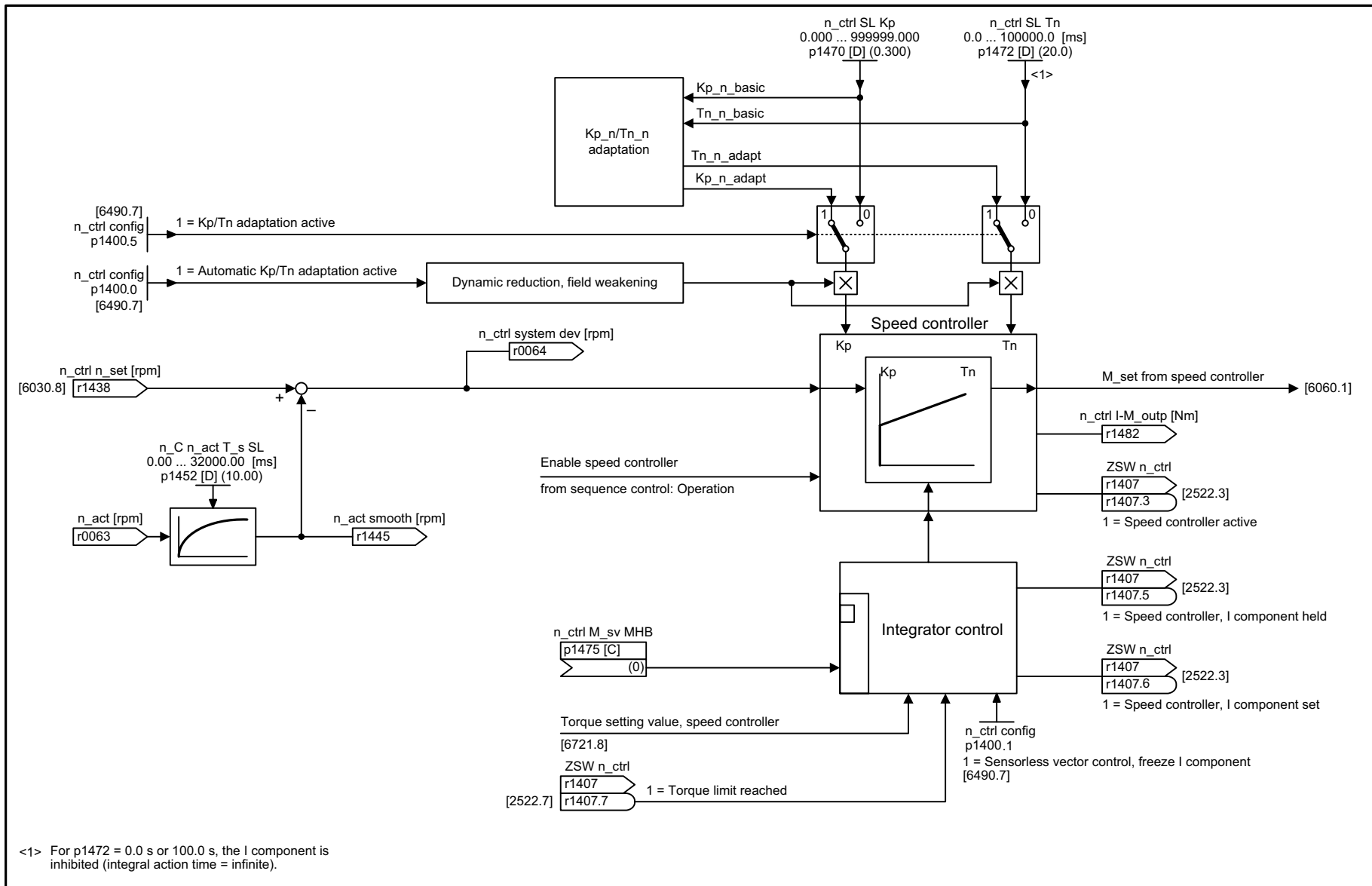


Fig. 3-73 6030 – Speed setpoint, acceleration model





1	2	3	4	5	6	7	8
Vector control					fp_6040_97_05.vsd	Function diagram	
Speed controller with Kp_n/Tn_n adaptation					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6040 -

Fig. 3-75 6040 – Speed controller

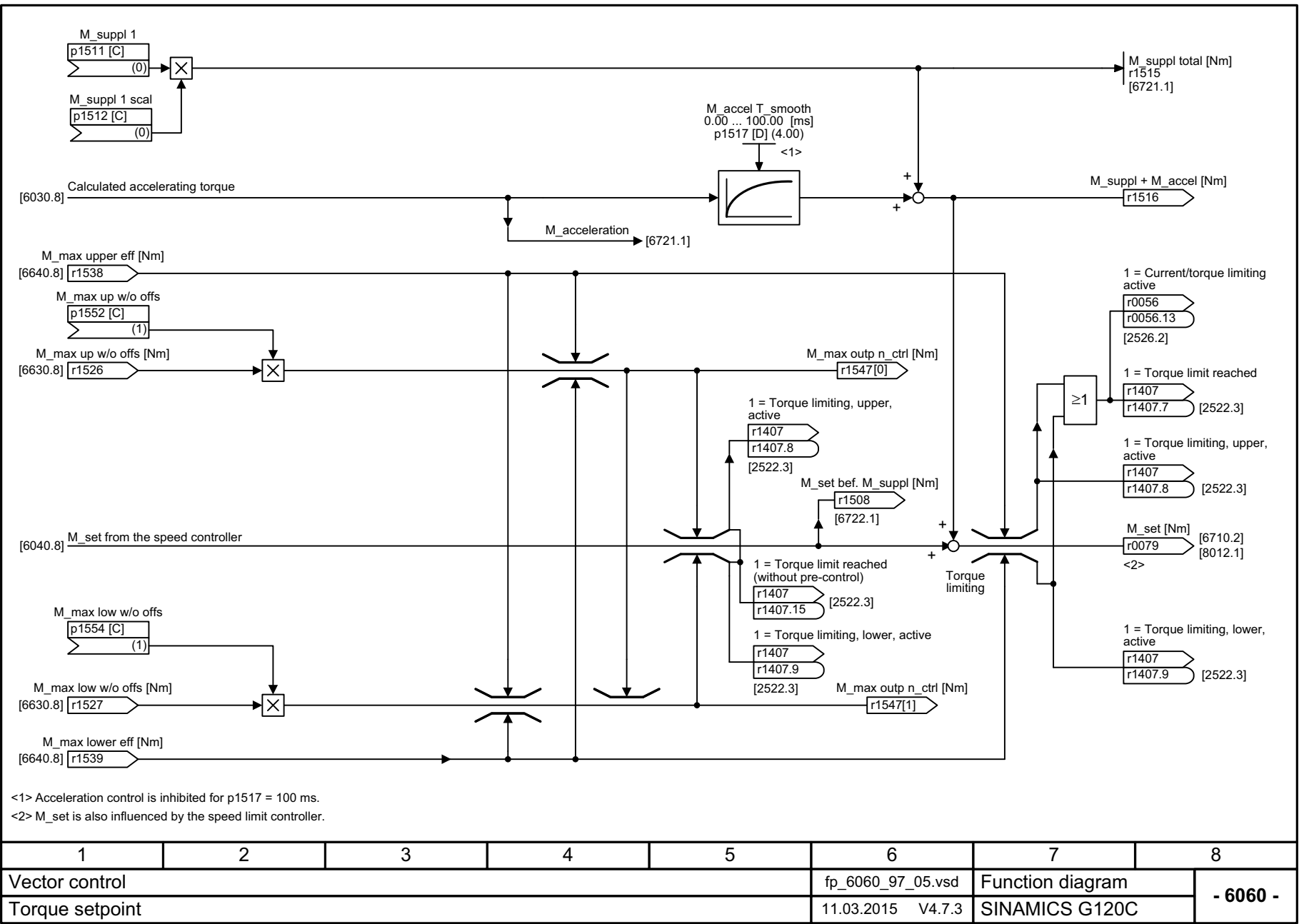
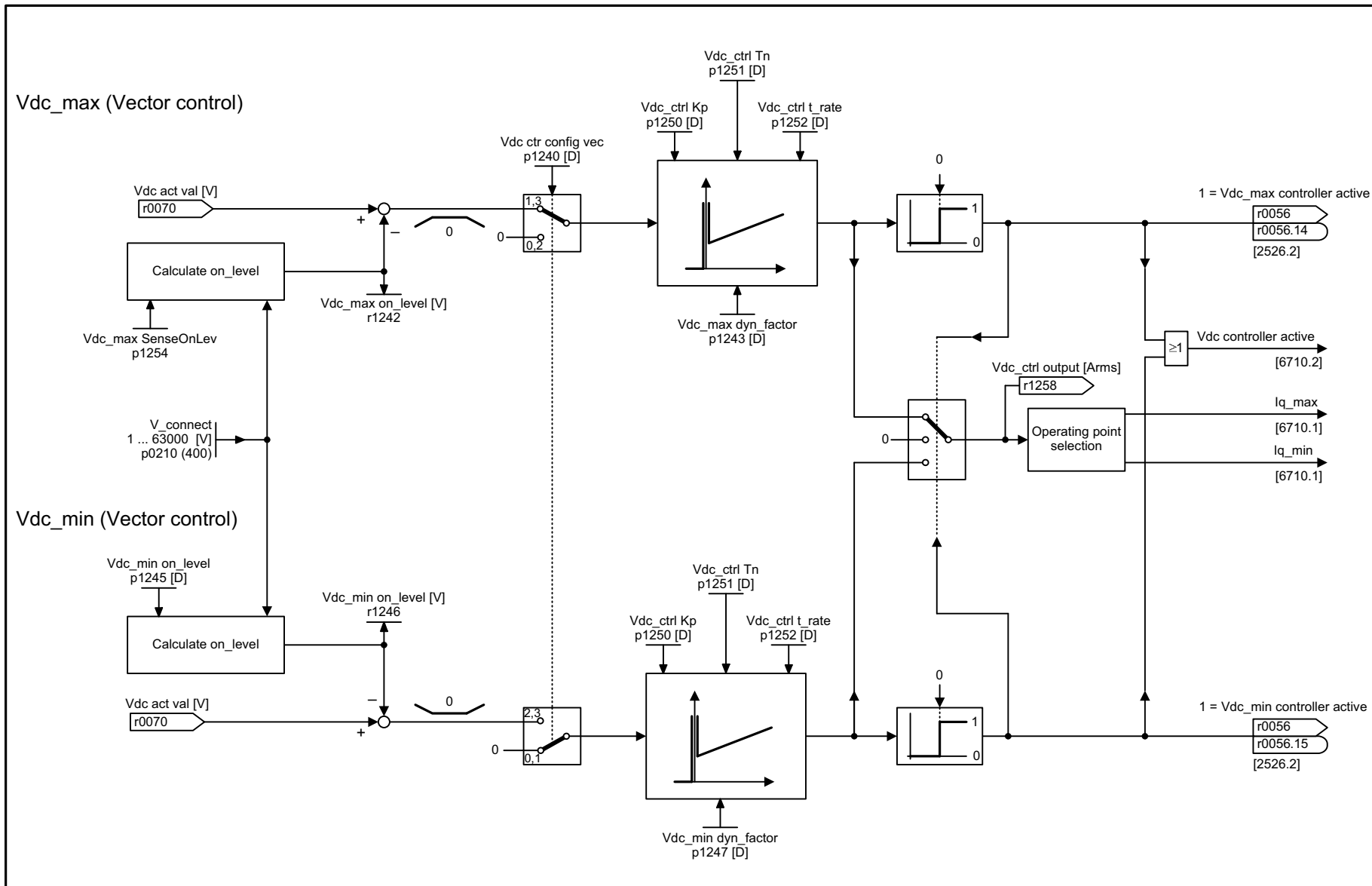
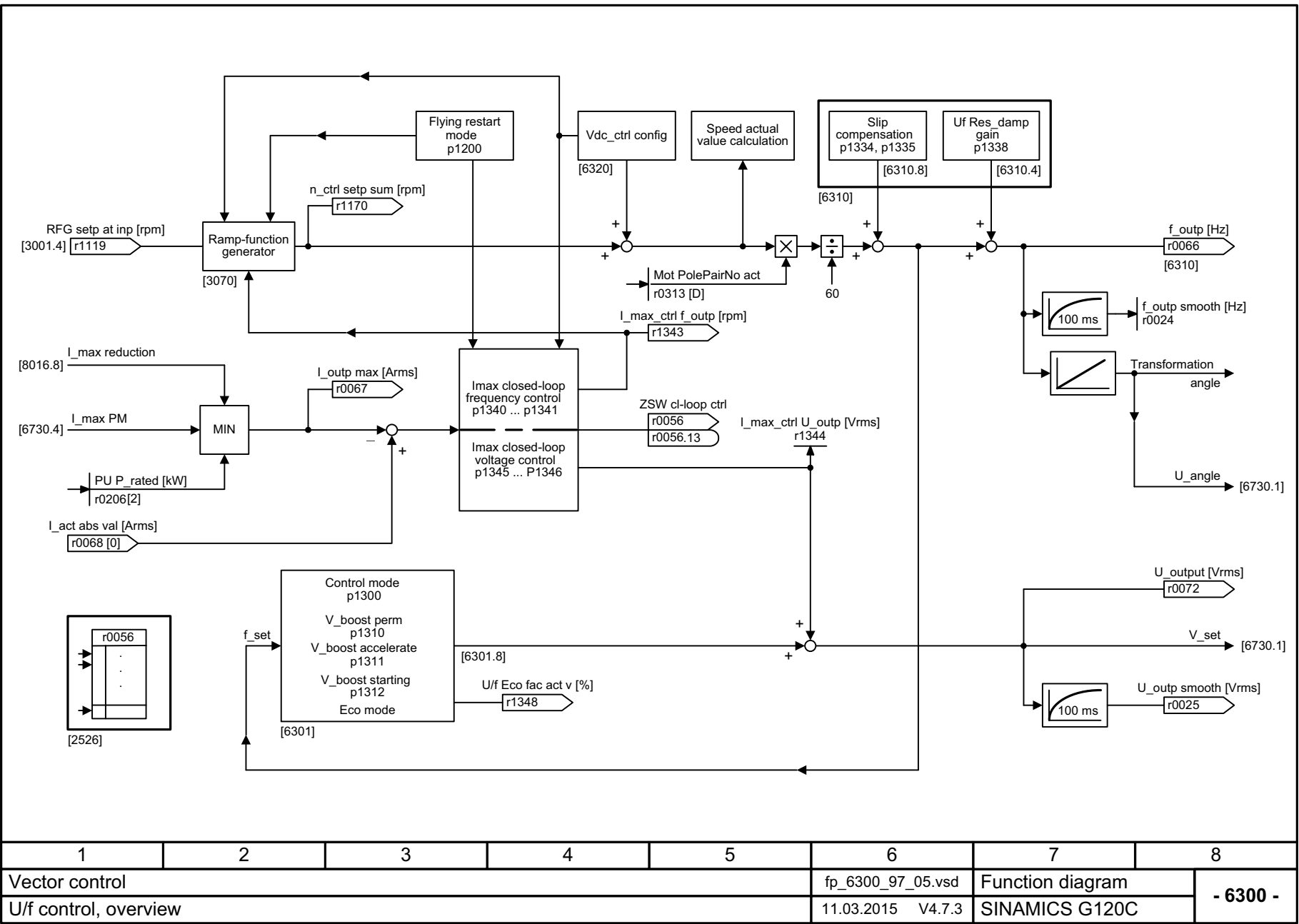


Fig. 3-76 6060 – Torque setpoint



1	2	3	4	5	6	7	8
Vector control					fp_6220_97_62.vsd	Function diagram	
Vdc_max controller and Vdc_min controller (Vector)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6220 -

Fig. 3-77 6220 – Vdc_max controller and Vdc_min controller



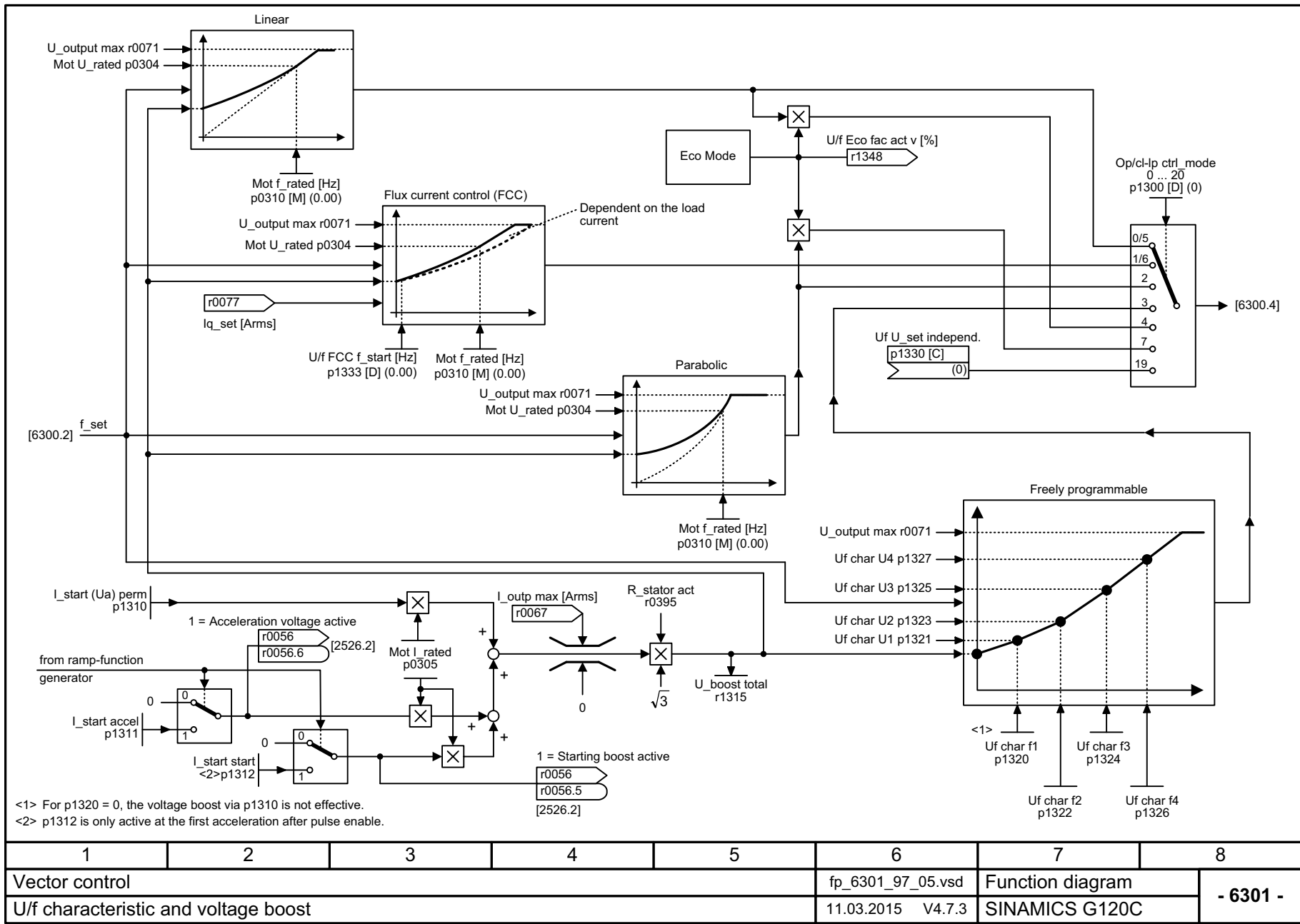


Fig. 3-79 6301 – U/f characteristic and voltage boost

1	2	3	4	5	6	7	8
Vector control					fp_6301_97_05.vsd	Function diagram	
U/f characteristic and voltage boost					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6301 -

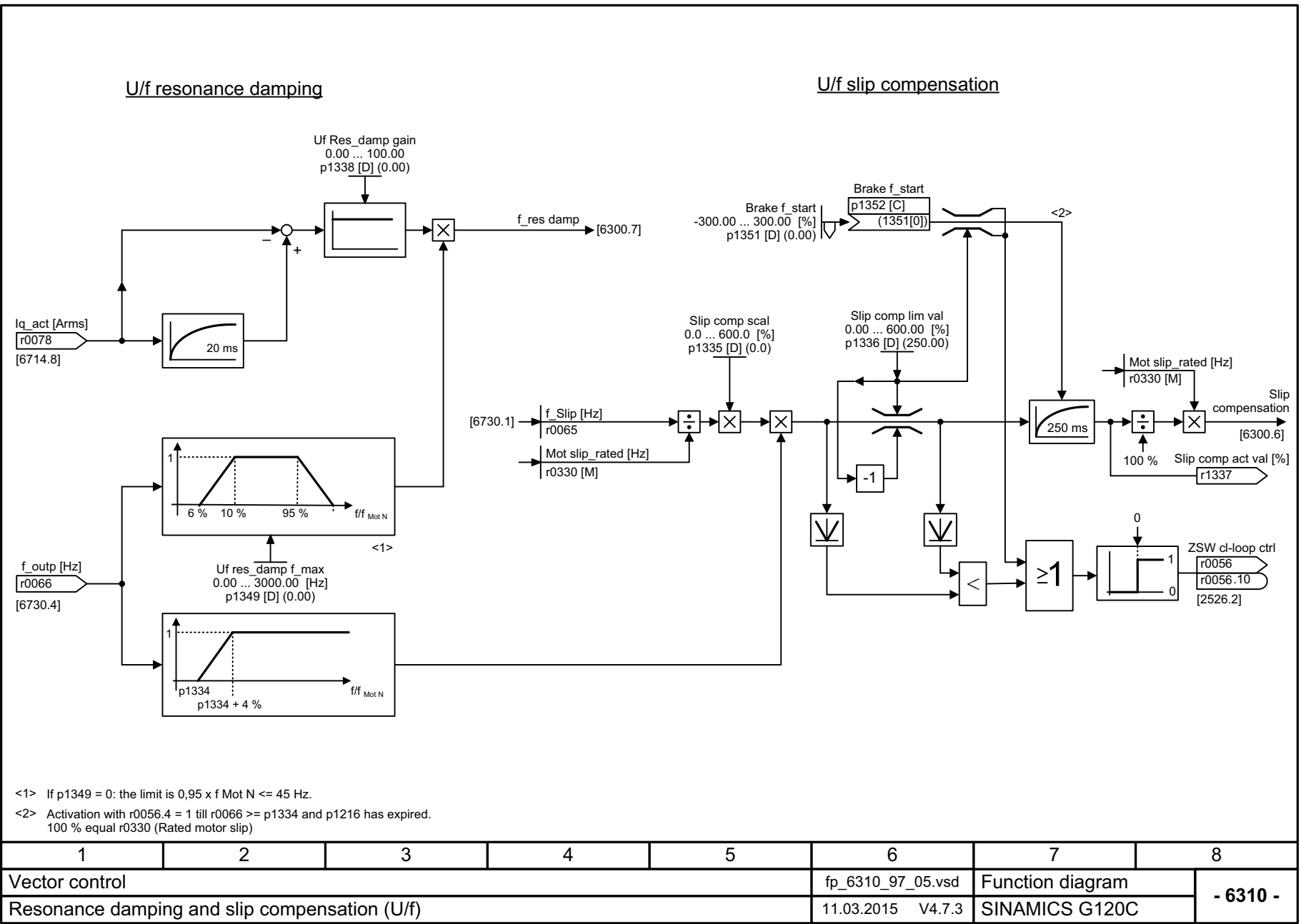


Fig. 3-80 6310 – Resonance damping and slip compensation (U/f)

1	2	3	4	5	6	7	8
Vector control					fp_6310_97_05.vsd	Function diagram	
Resonance damping and slip compensation (U/f)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6310 -

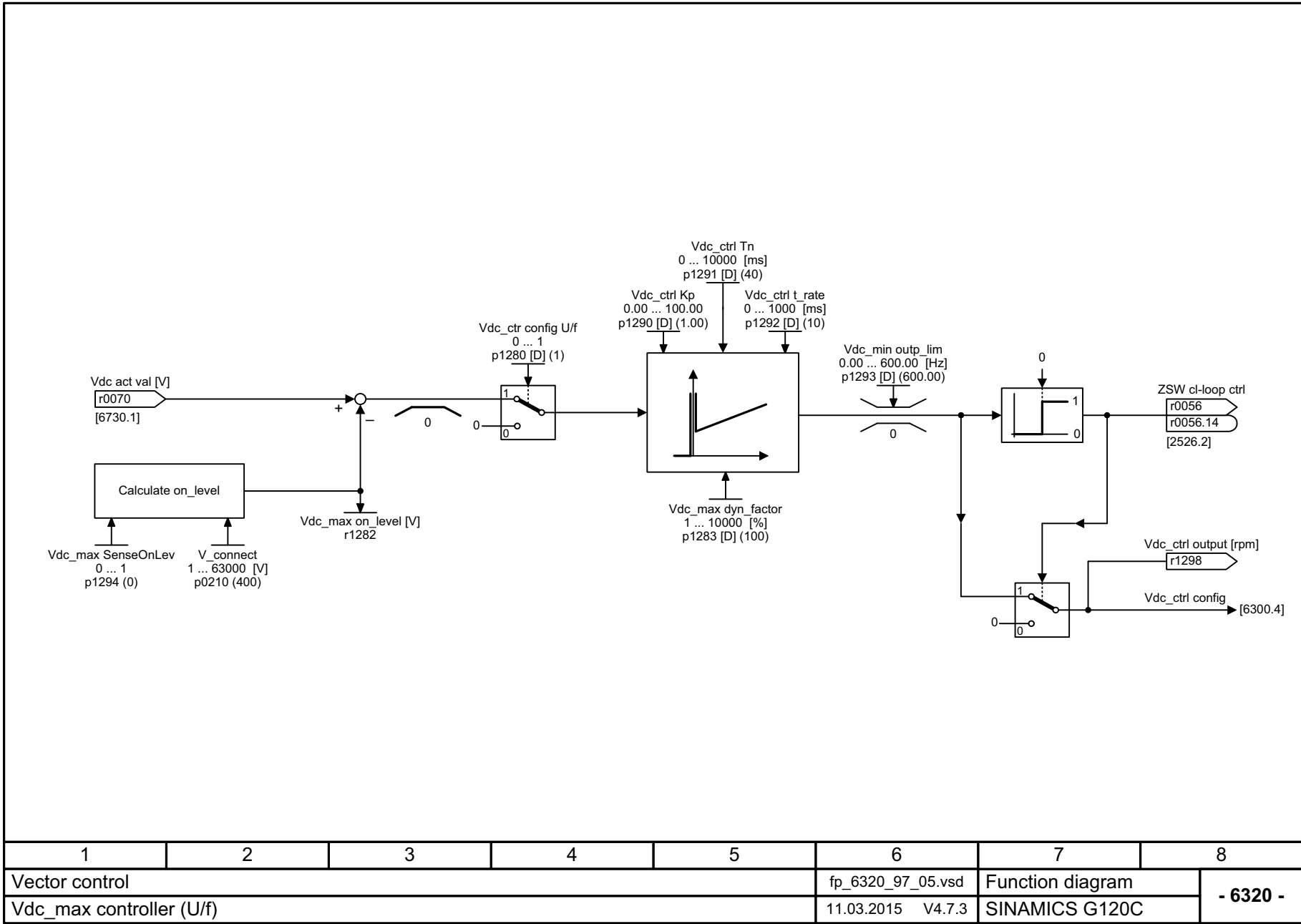
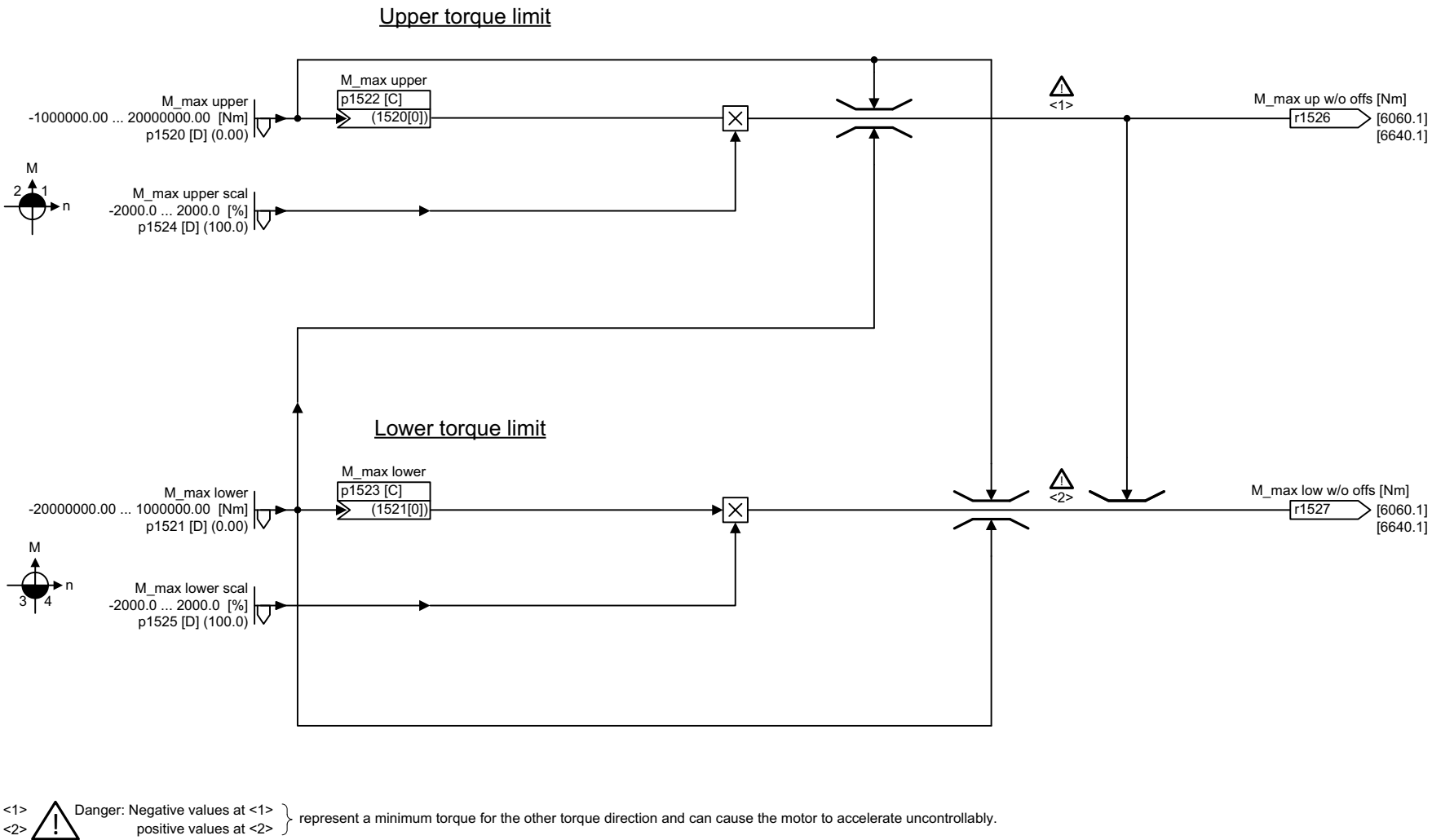


Fig. 3-81 6320 – Vdc_max controller

Speed control configuration							
n_ctrl config p1400 [D]				Factory setting			
Bit No.	Meaning						
00	1 = Automatic Kp/Tn adaptation active	1				[6040.2] [6824.4]	
01	1 = Sensorless vector control, freeze I component	0				[6040.6] [6824.6]	
...	Reserved						
05	1 = Kp/Tn adaptation active	0				[6040.2] [6824.4]	
06	1 = Free Tn adaptation active	1				[6050.6]	
...	Reserved						
14	1 = Torque pre-control always active 0 = Torque pre-control for n_ctrl enabled	0				[6060.4] [6826.4]	
15	1 = Sensorless vector control, speed pre-control active	0				[6030.6] [6822.4]	
16	1 = I component for limiting enabled	1					
...	Reserved						
18	1 = Moment of inertia estimator active	0					
19	Reserved						
20	1 = Acceleration model	0					
21	Reserved						
22	1 = Obtain moment of inertia estimator value for pulse inhibit	0					
23	Reserved	0					
24	1 = moment of inertia estimator is actively accelerating the motor	0					

1	2	3	4	5	6	7	8	
Vector control					fp_6490_97_63.vsd	Function diagram		- 6490 -
Speed control configuration					11.03.2015 V4.7.3	SINAMICS G120C		

Fig. 3-82 6490 – Speed control configuration



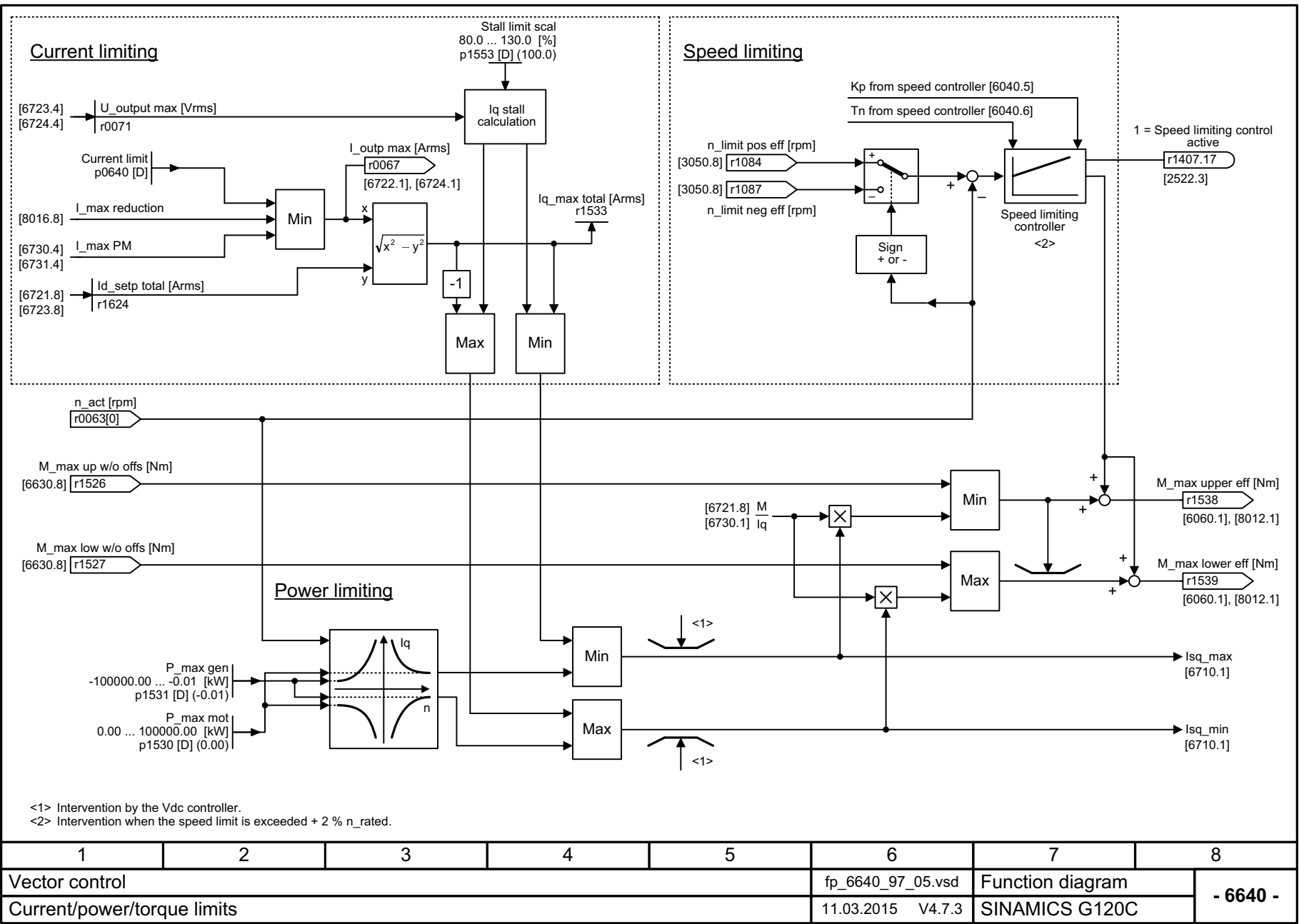
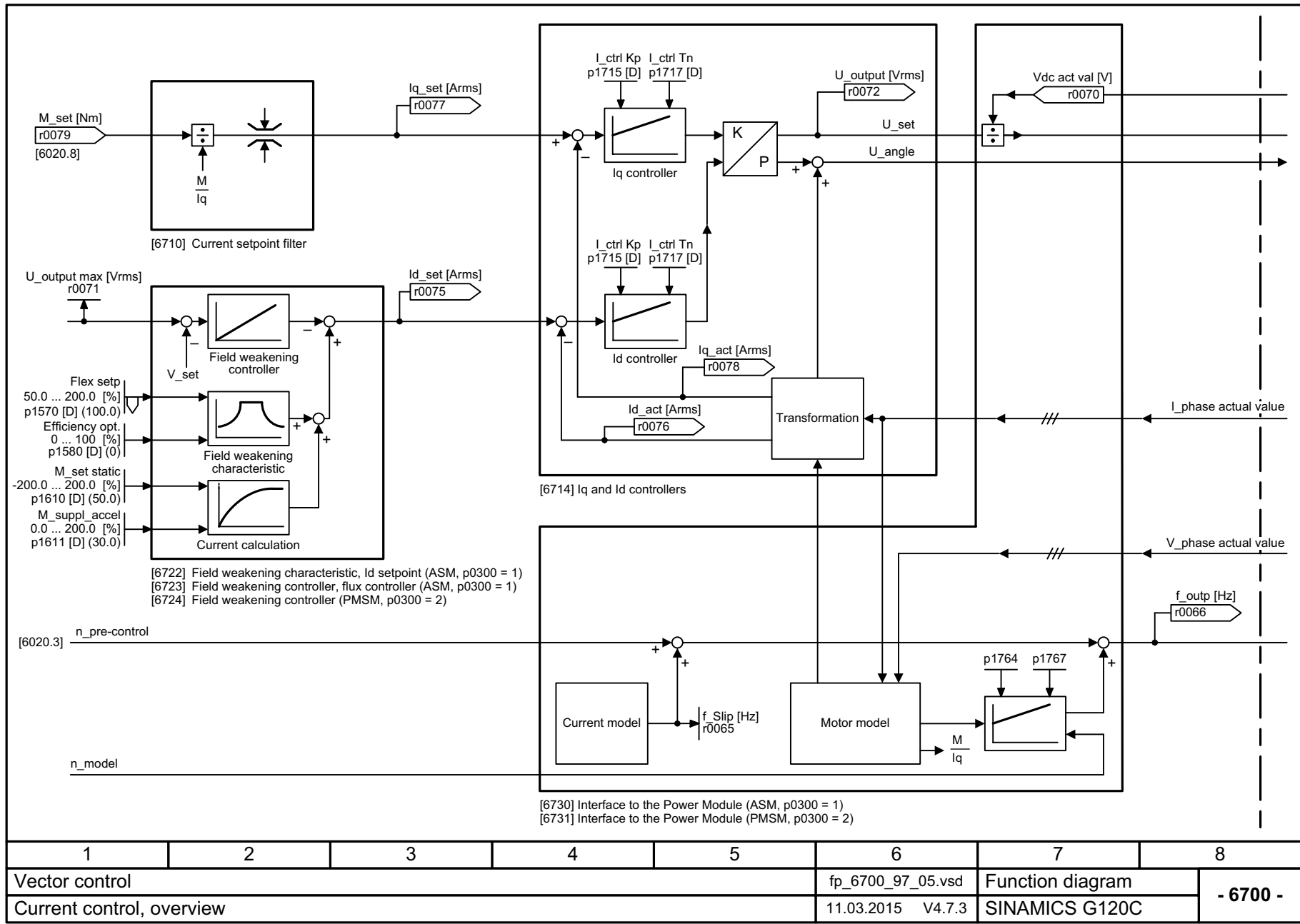
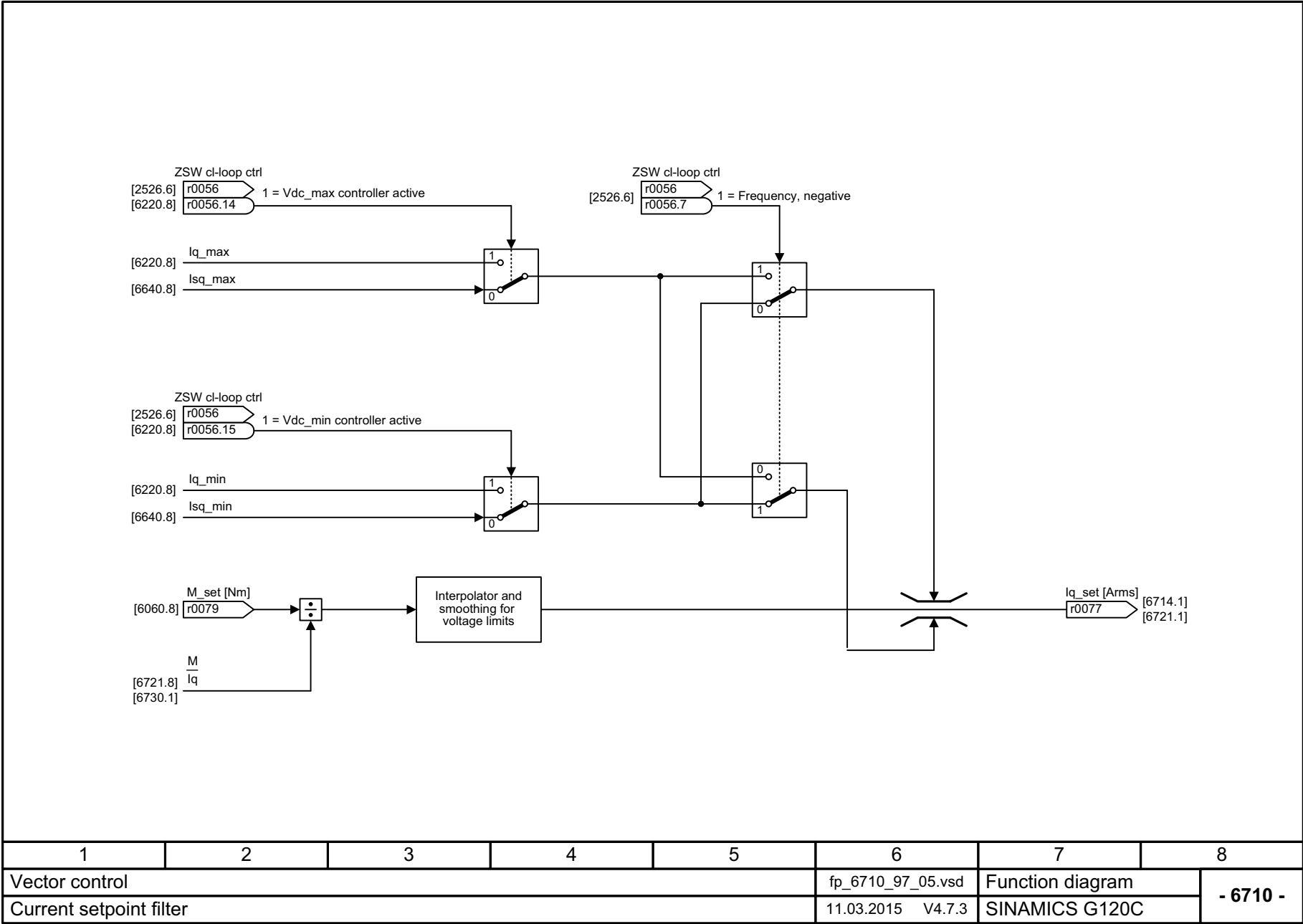
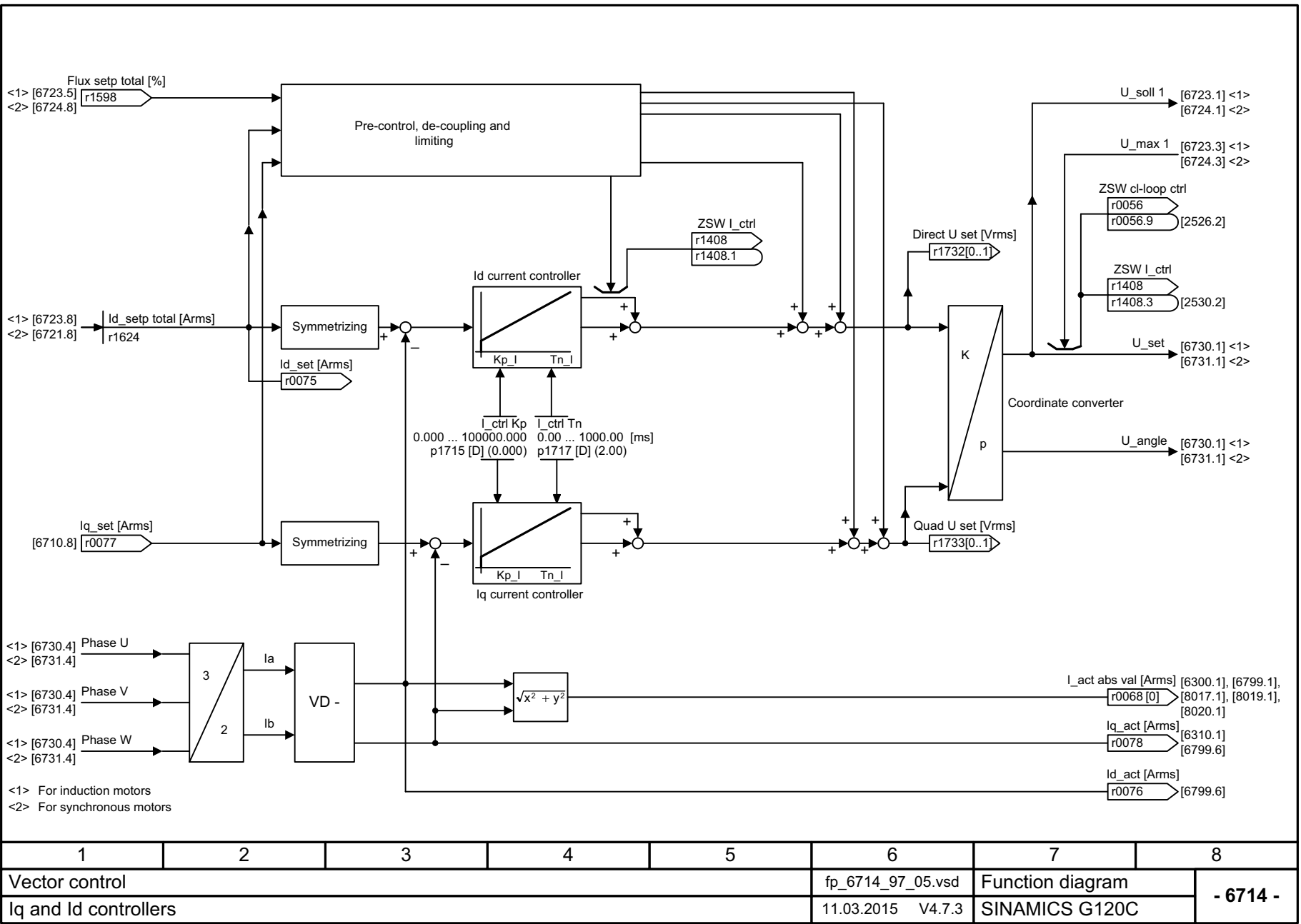


Fig. 3-84 6640 – Current/power/torque limits

1	2	3	4	5	6	7	8
Vector control					fp_6640_97_05.vsd	Function diagram	
Current/power/torque limits					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6640 -







1	2	3	4	5	6	7	8
Vector control					fp_6714_97_05.vsd	Function diagram	
Iq and Id controllers					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6714 -

Fig. 3-87 6714 – Iq and Id controllers

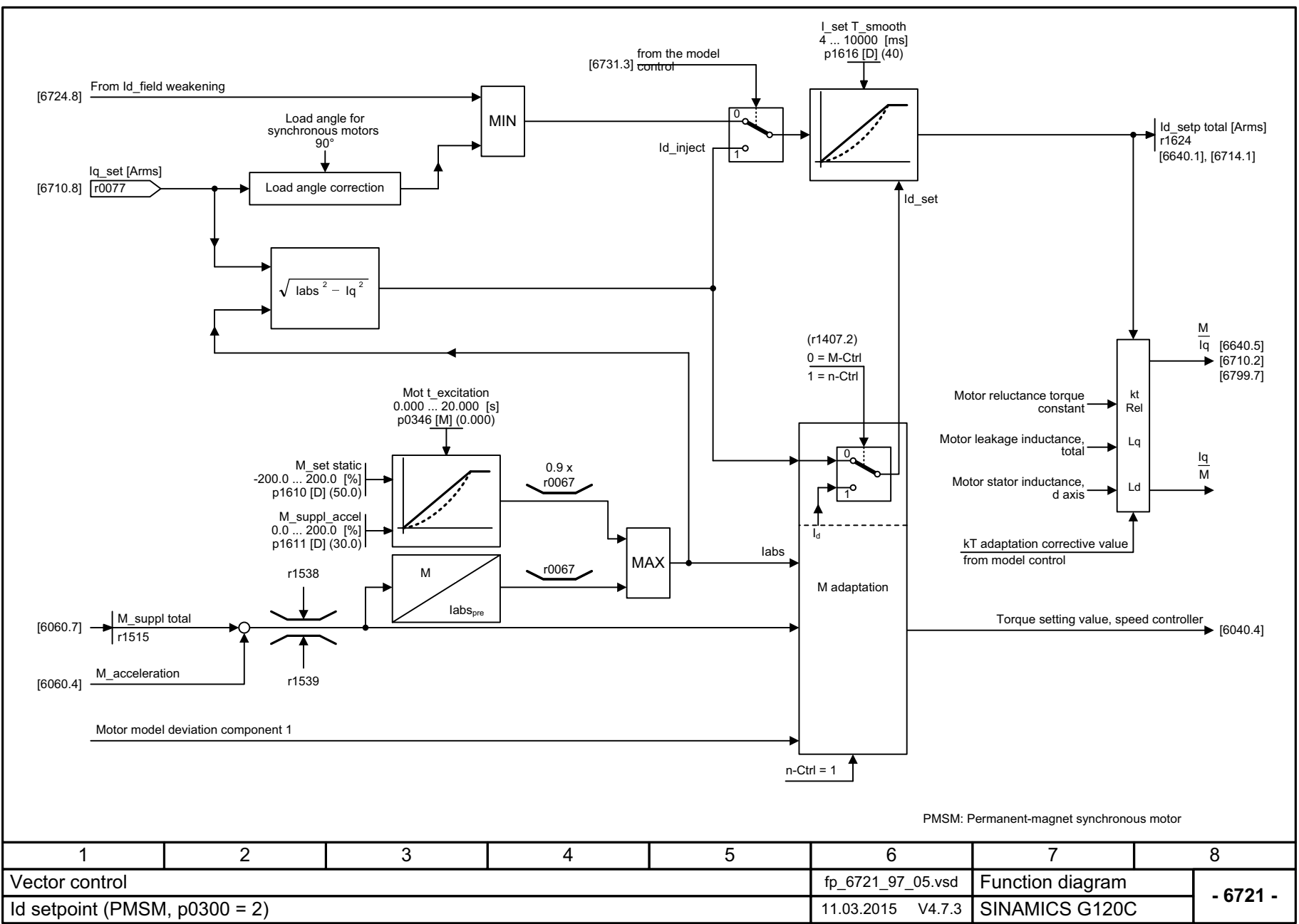
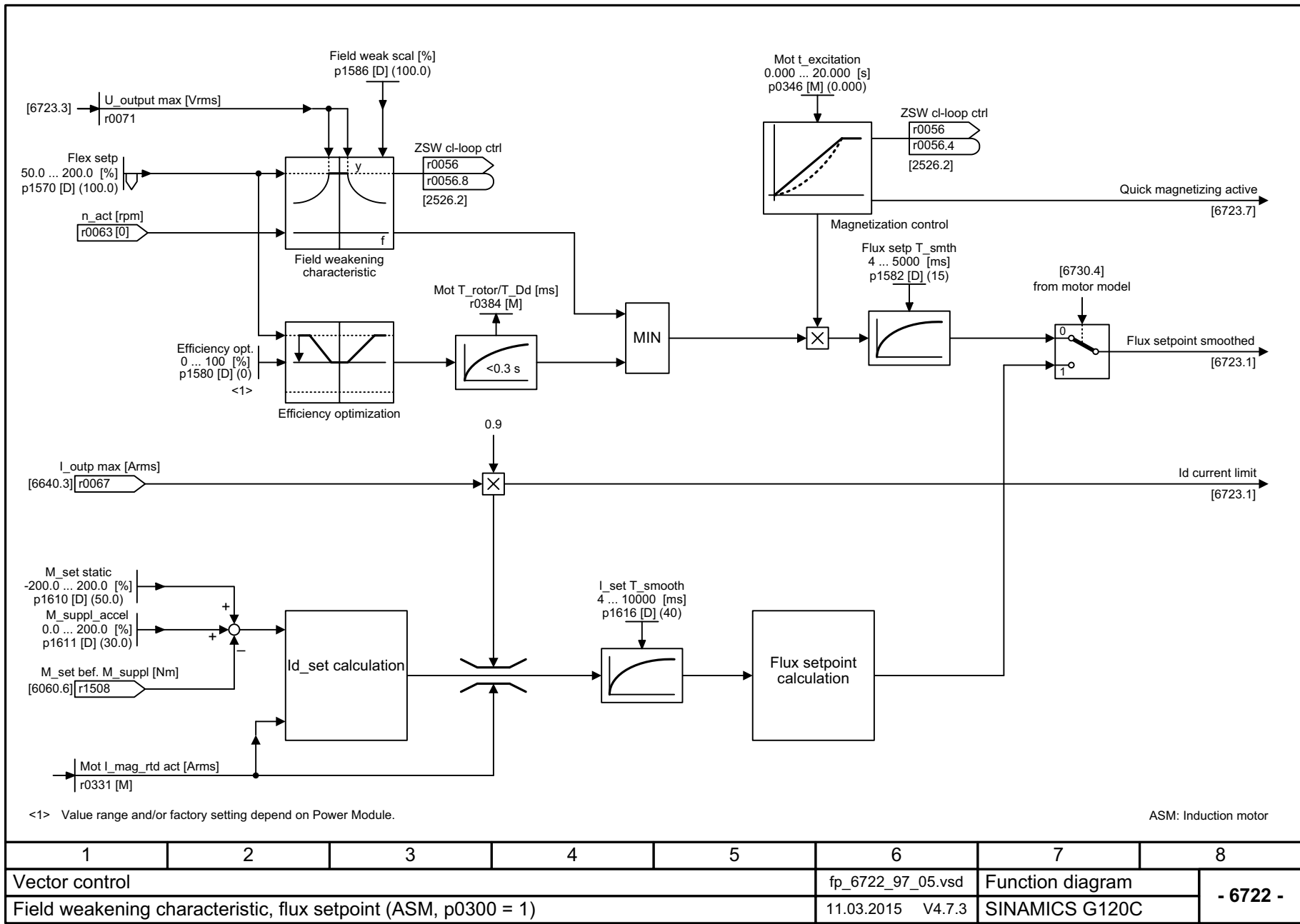
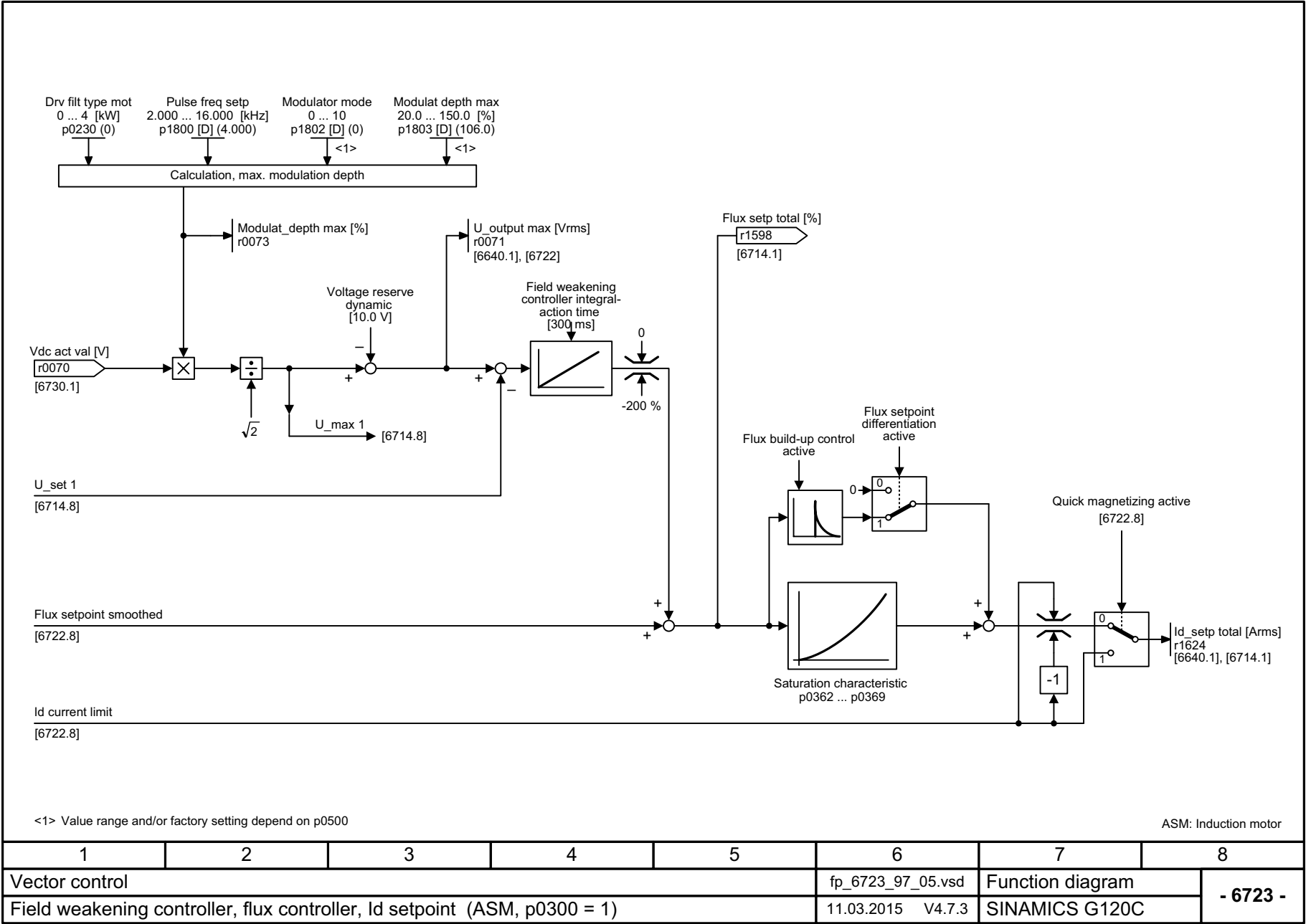
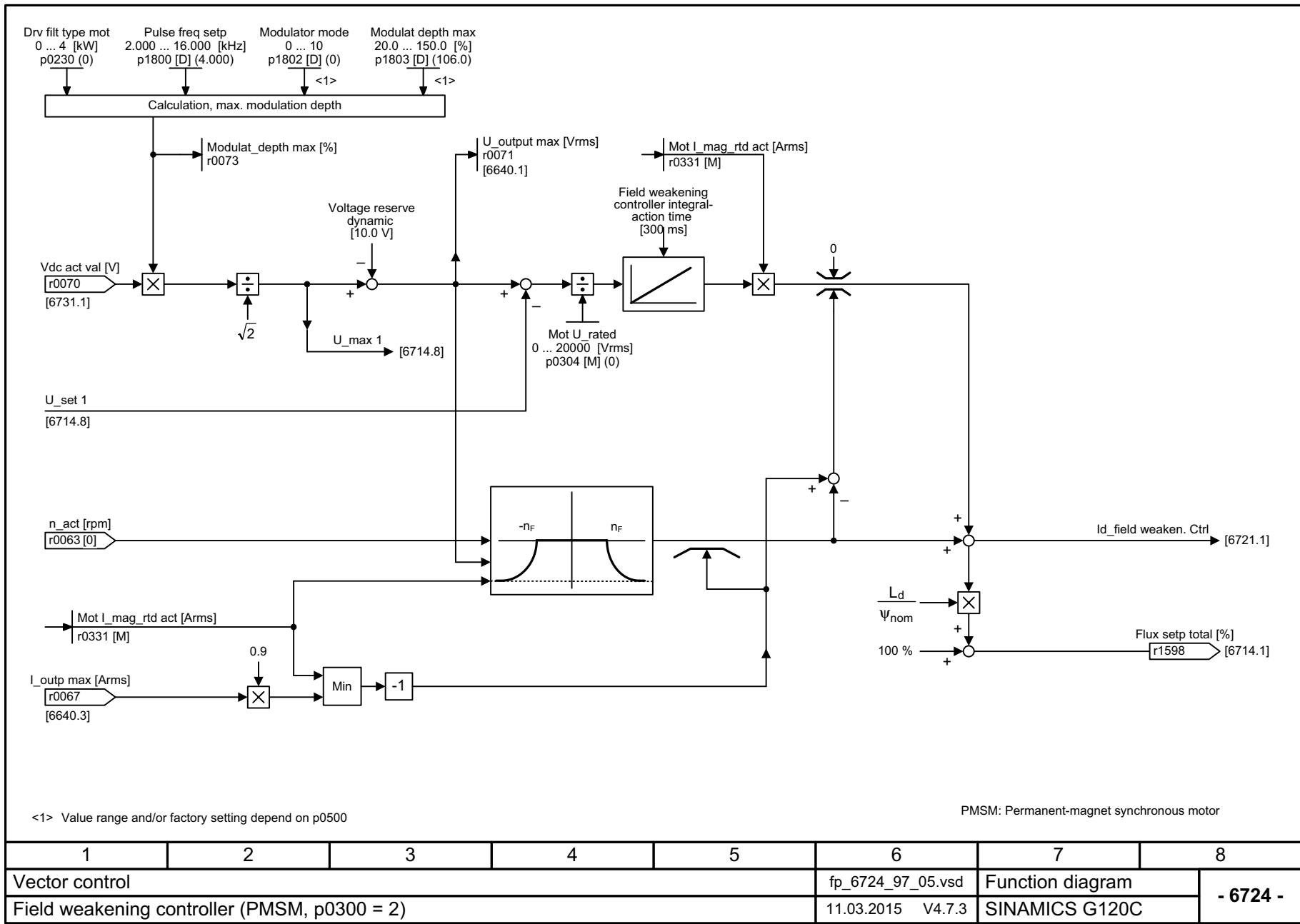


Fig. 3-88 6721 – Id setpoint (PMSM, p0300 = 2)



1	2	3	4	5	6	7	8
Vector control					fp_6722_97_05.vsd	Function diagram	
Field weakening characteristic, flux setpoint (ASM, p0300 = 1)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6722 -





1	2	3	4	5	6	7	8
Vector control					fp_6724_97_05.vsd	Function diagram	
Field weakening controller (PMSM, p0300 = 2)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6724 -

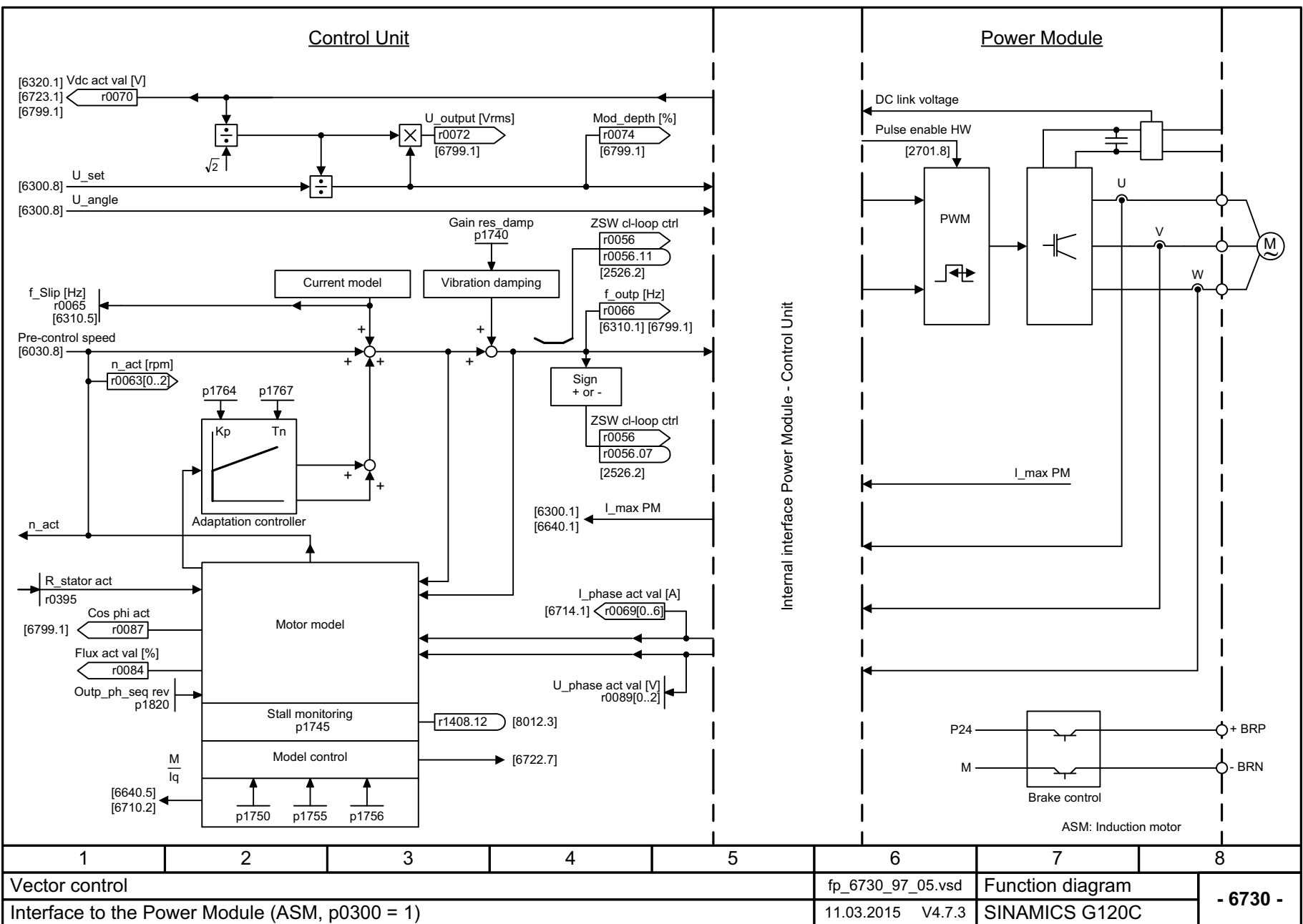
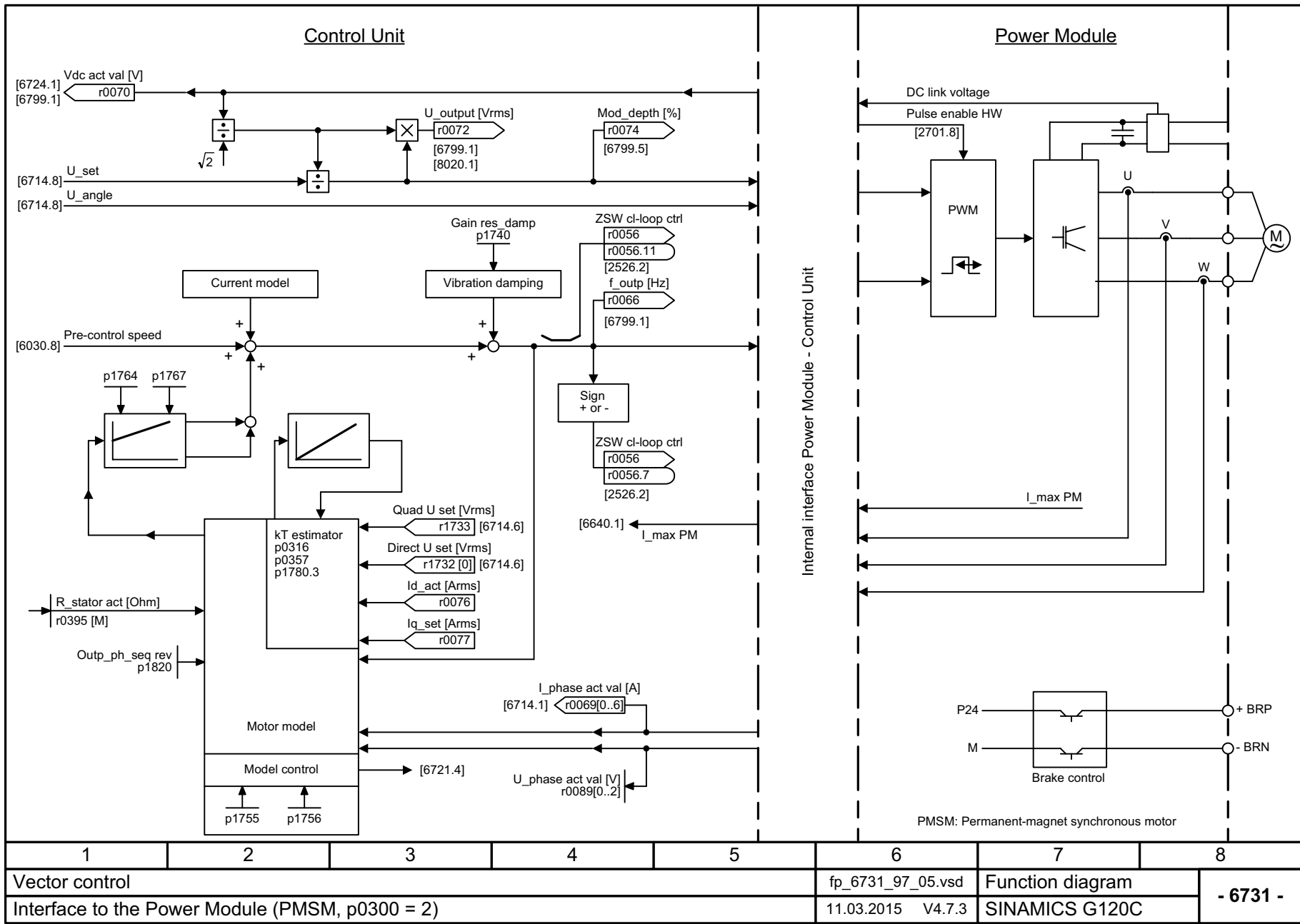
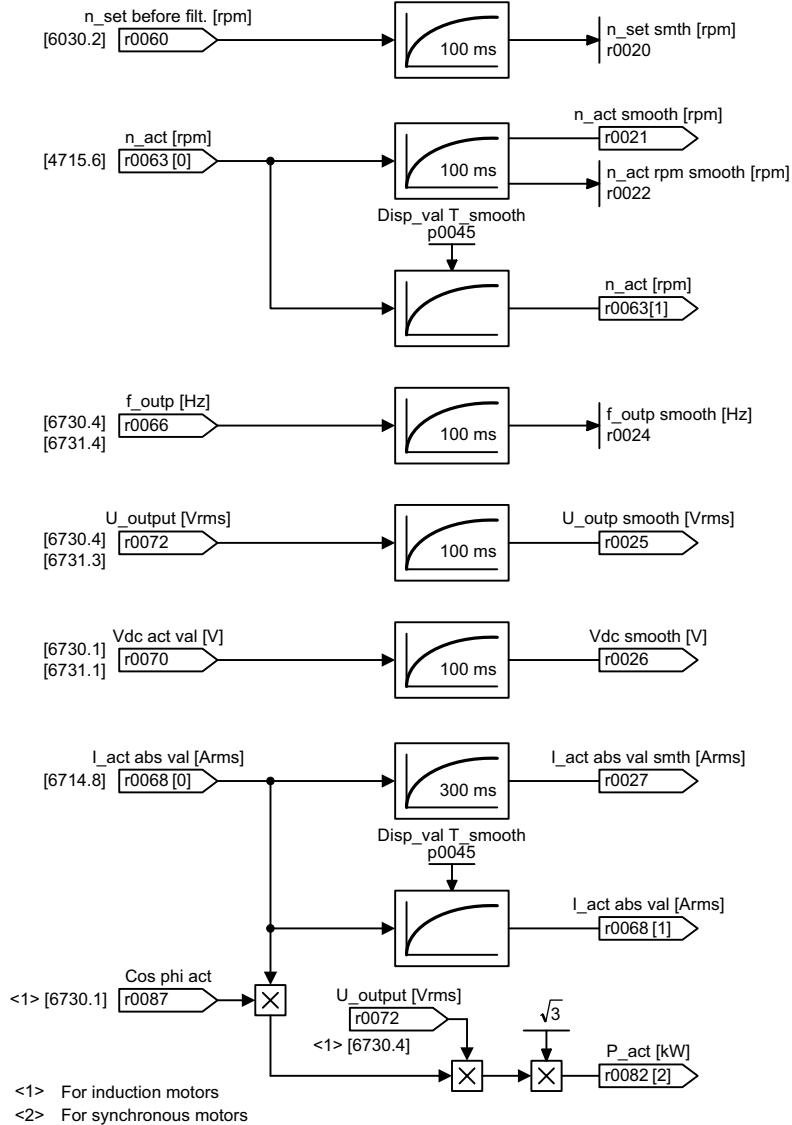
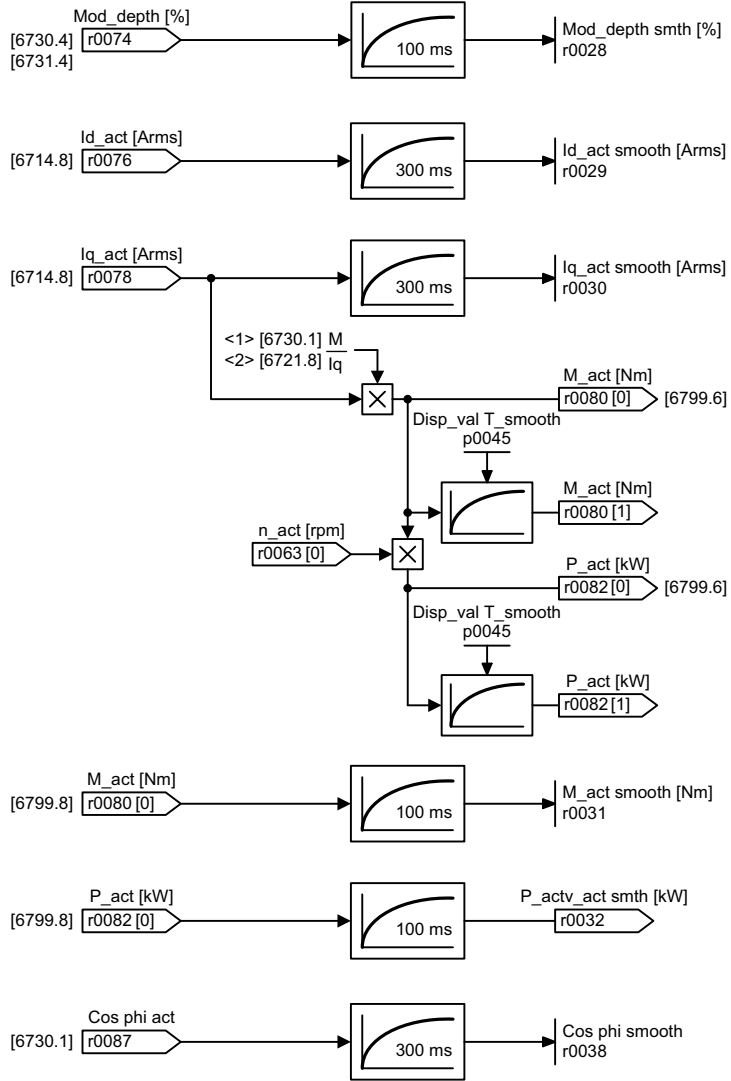


Fig. 3-92 6730 – Interface to the Power Module (ASM, p0300 = 1)





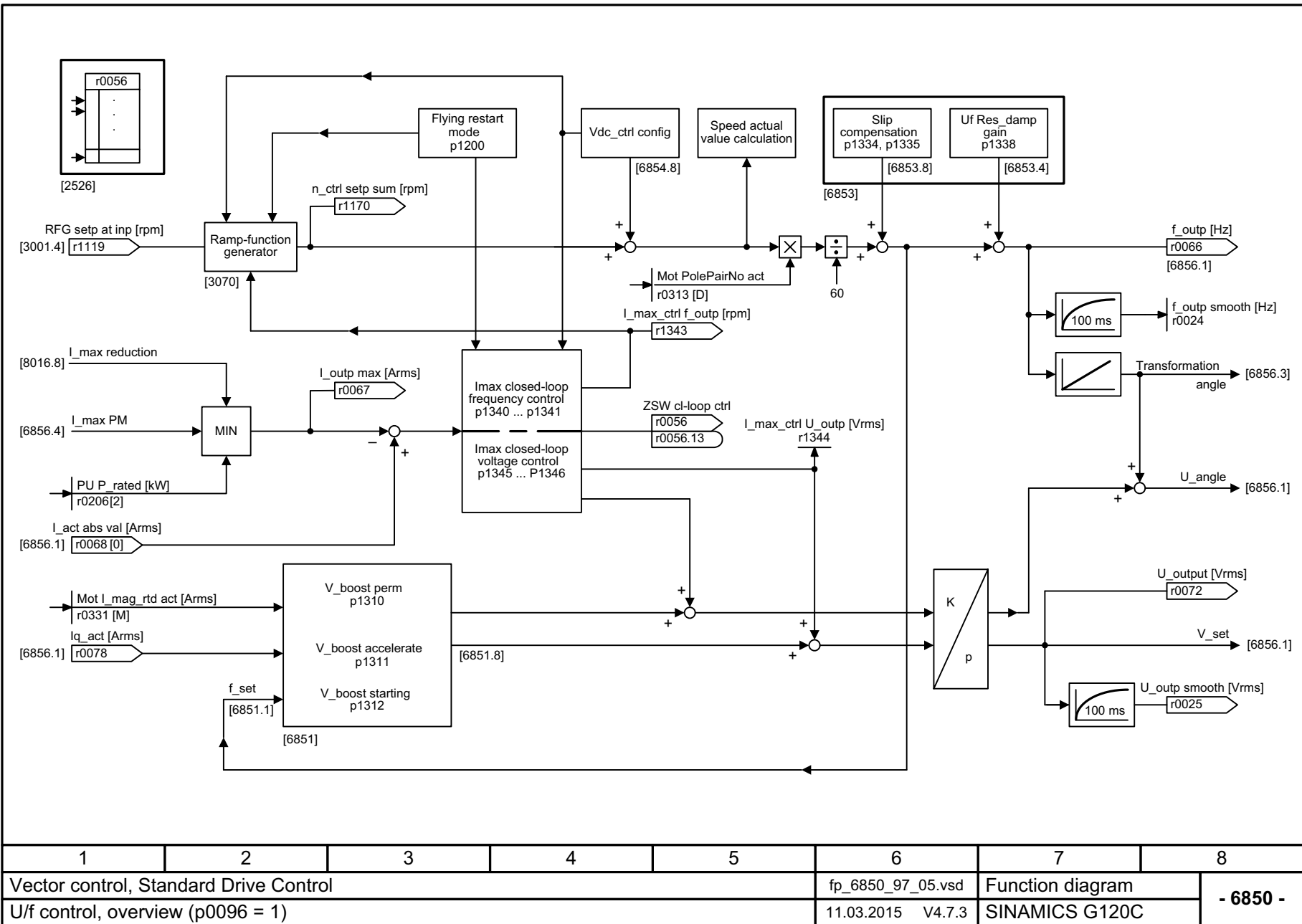
1	2	3	4	5	6	7	8
Vector control					fp_6799_97_66.vsd	Function diagram	
Display signals					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6799 -

Fig. 3-94 6799 – Display signals

3.14 Vector control, Standard Drive Control (p0096 = 1)

Function block diagrams

6850 – U/f control, overview (p0096 = 1)	468
6851 – U/f characteristic and voltage boost (p0096 = 1)	469
6853 – Resonance damping and slip compensation (U/f) (p0096 = 1)	470
6854 – Vdc_max controller (p0096 = 1)	471
6856 – Interface to the Power Module (p0096 = 1)	472



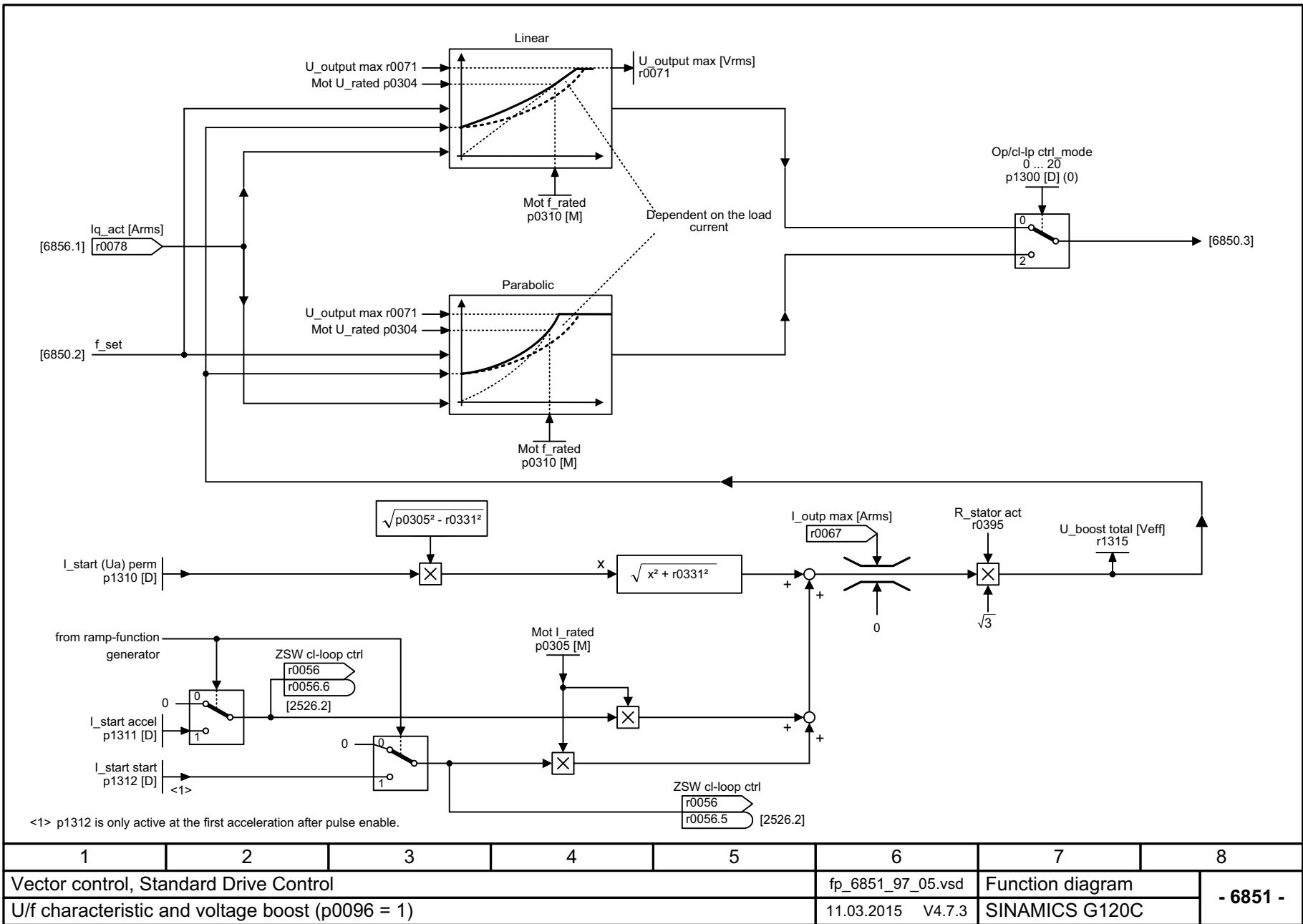


Fig. 3-96 6851 – U/f characteristic and voltage boost (p0096 = 1)

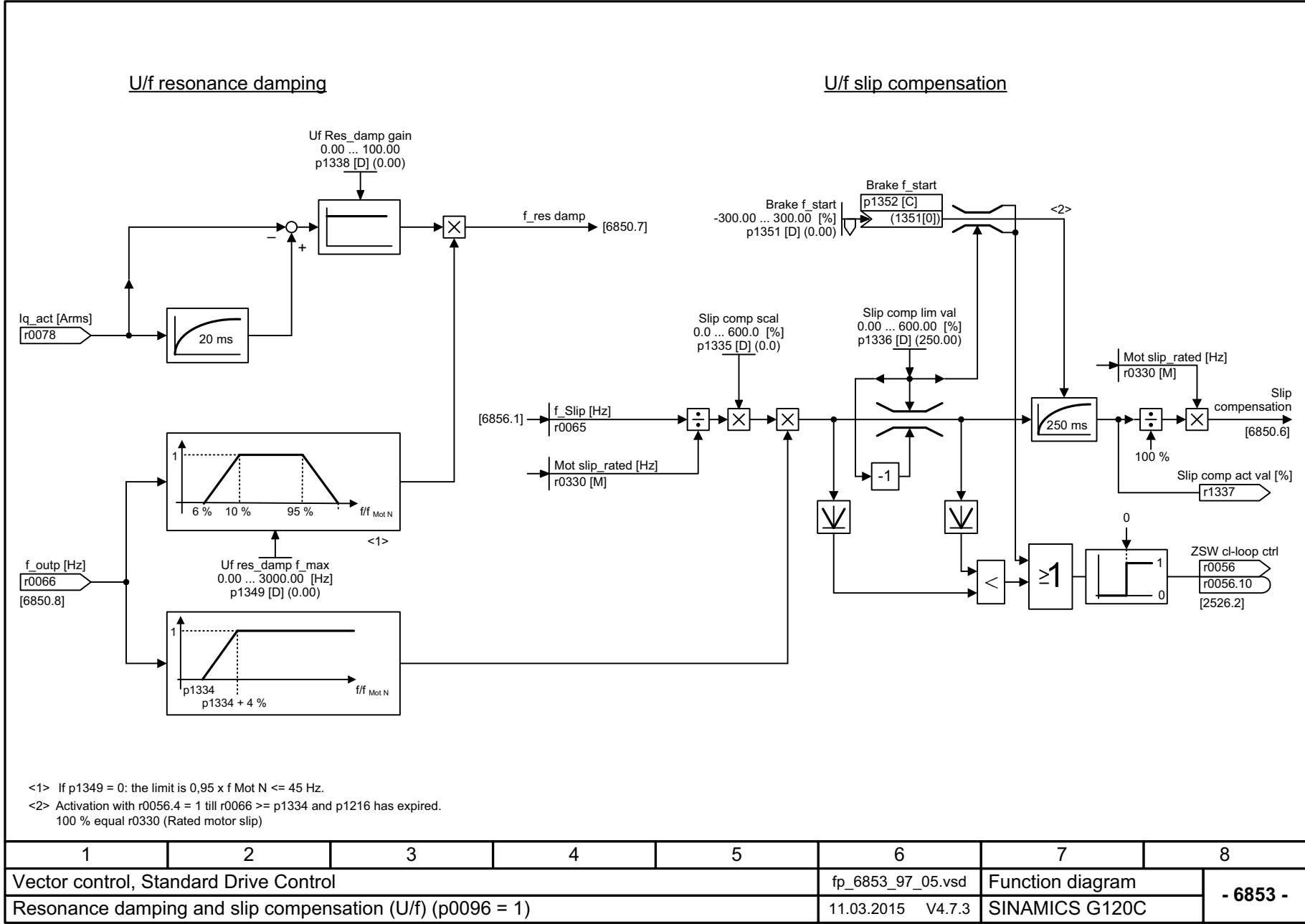


Fig. 3-97 6853 – Resonance damping and slip compensation (U/f) (p0096 = 1)

1	2	3	4	5	6	7	8
Vector control, Standard Drive Control					fp_6853_97_05.vsd	Function diagram	
Resonance damping and slip compensation (U/f) (p0096 = 1)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6853 -

3.14 Vector control, Standard Drive Control (p0096 = 1)

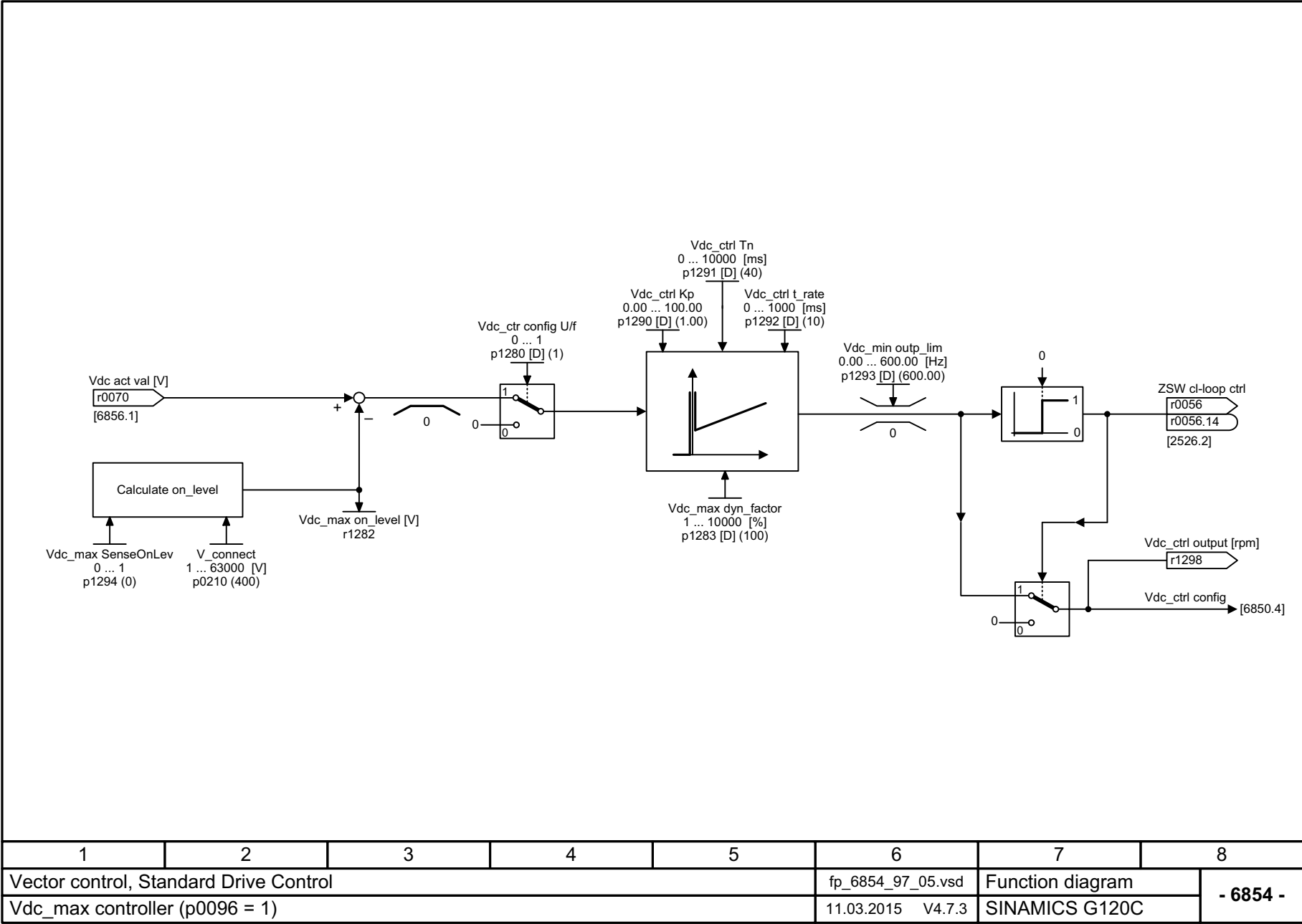
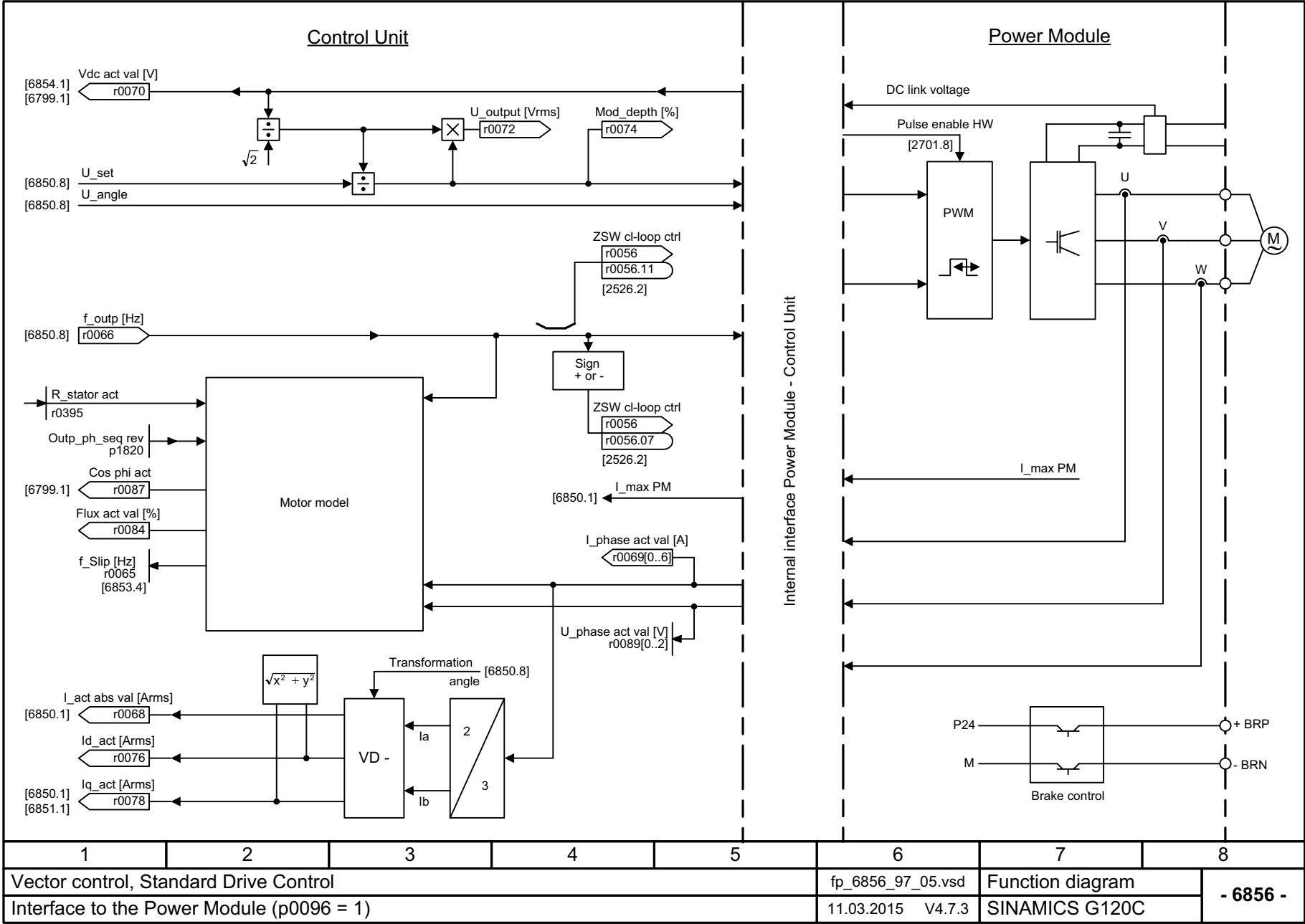


Fig. 3-98 6854 – Vdc_max controller (p0096 = 1)



3.15 Vector control, Dynamic Drive Control (p0096 = 2)

Function block diagrams

6820 – Speed control and generation of the torque limits, overview (p0096 = 2)	474
6821 – Current control, overview (p0096 = 2)	475
6822 – Speed setpoint, precontrol symmetrization, acceleration model (p0096 = 2)	476
6823 – Moment of inertia estimator (p0096 = 2)	477
6824 – Speed controller with Kp_n/Tn_n adaptation (p0096 = 2)	478
6826 – Torque setpoint (p0096 = 2)	479
6827 – Vdc_max controller and Vdc_min controller (p0096 = 2)	480
6828 – Current/power/torque limits (p0096 = 2)	481
6832 – Current setpoint filter (p0096 = 2)	482
6833 – Iq and Id controller (p0096 = 2)	483
6836 – Id setpoint (PMSM, p0300 = 2xx, p0096 = 2)	484
6837 – Field weakening characteristic, Id setpoint (ASM, p0300 = 1, p0096 = 2)	485
6838 – Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1, p0096 = 2)	486
6839 – Field weakening controller (PMSM, p0300 = 2xx, p0096 = 2)	487
6841 – Interface to the Power Module (ASM, p0300 = 1, p0096 = 2)	488
6842 – Interface to the Power Module (PMSM, p0300 = 2xx, p0096 = 2)	489

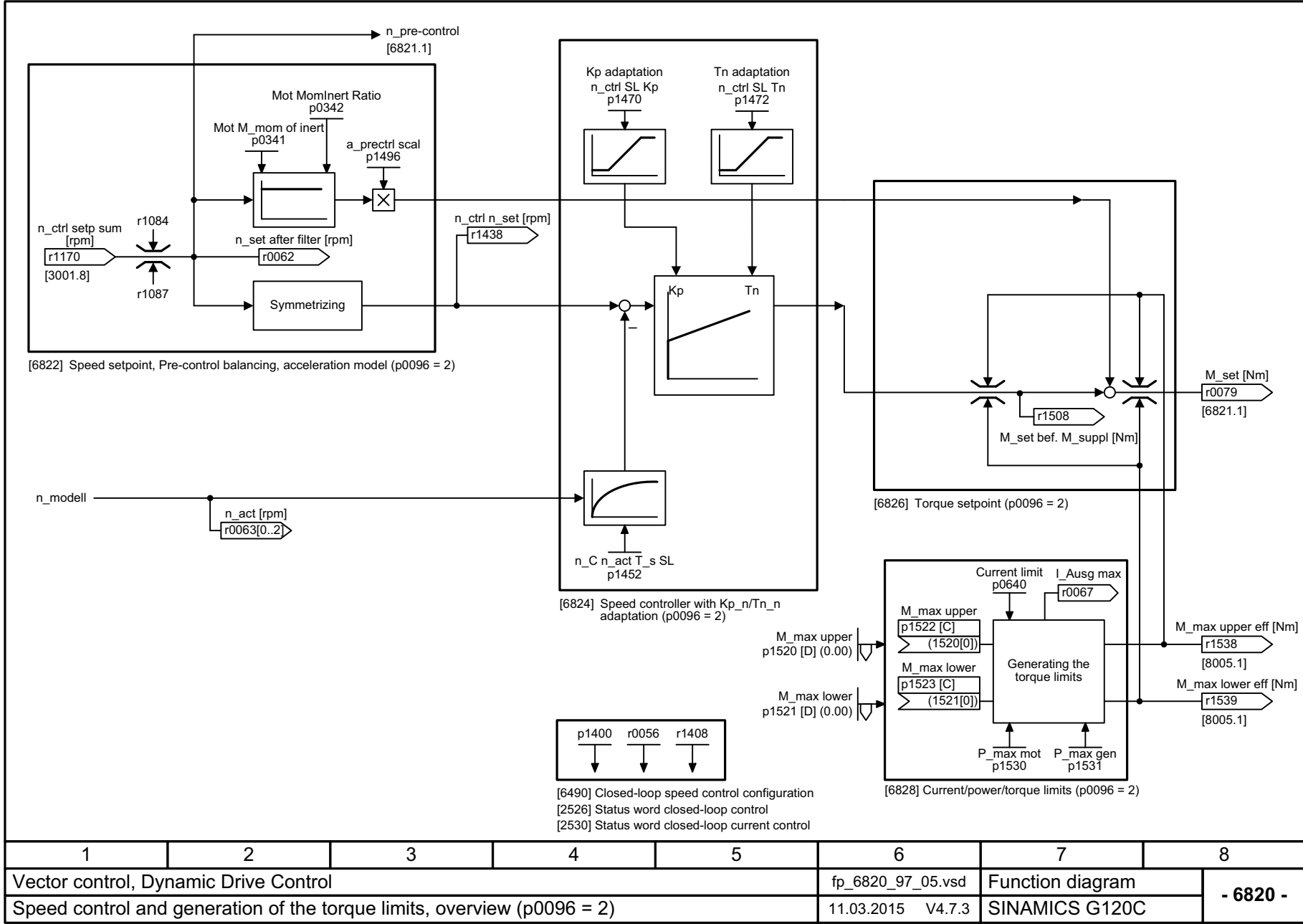
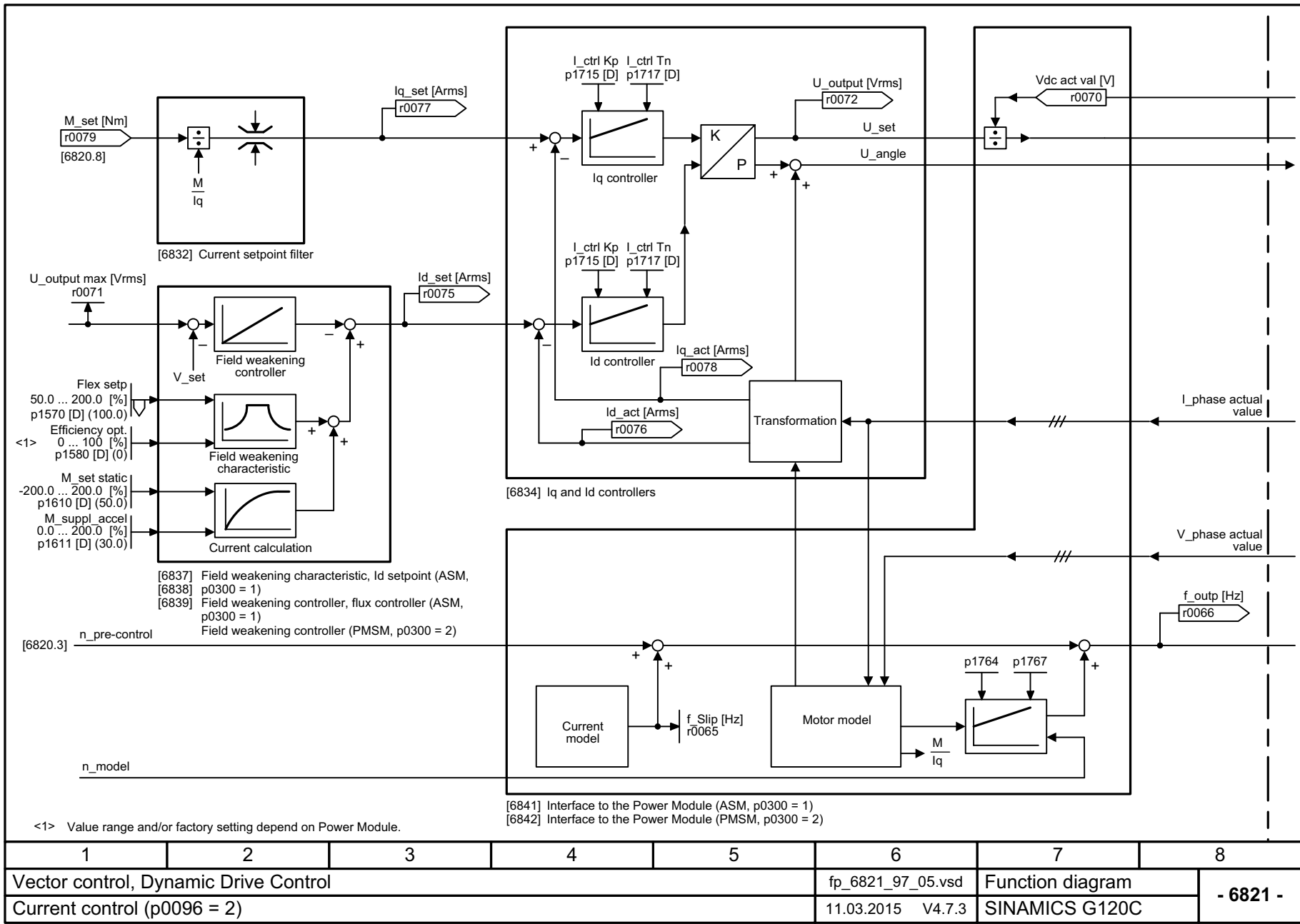


Fig. 3-100 6820 –Speed control and generation of the torque limits, overview (p0096 = 2)



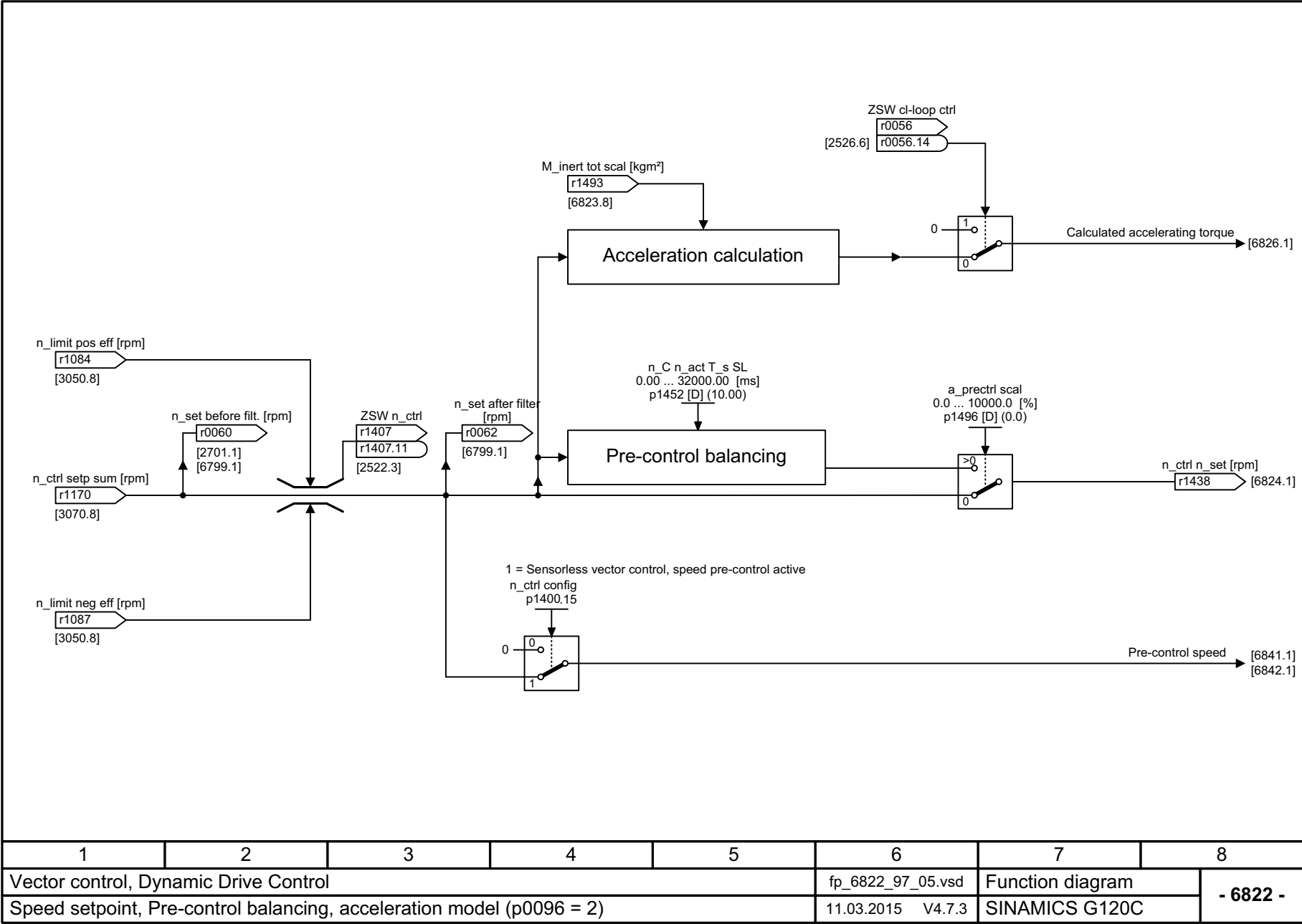
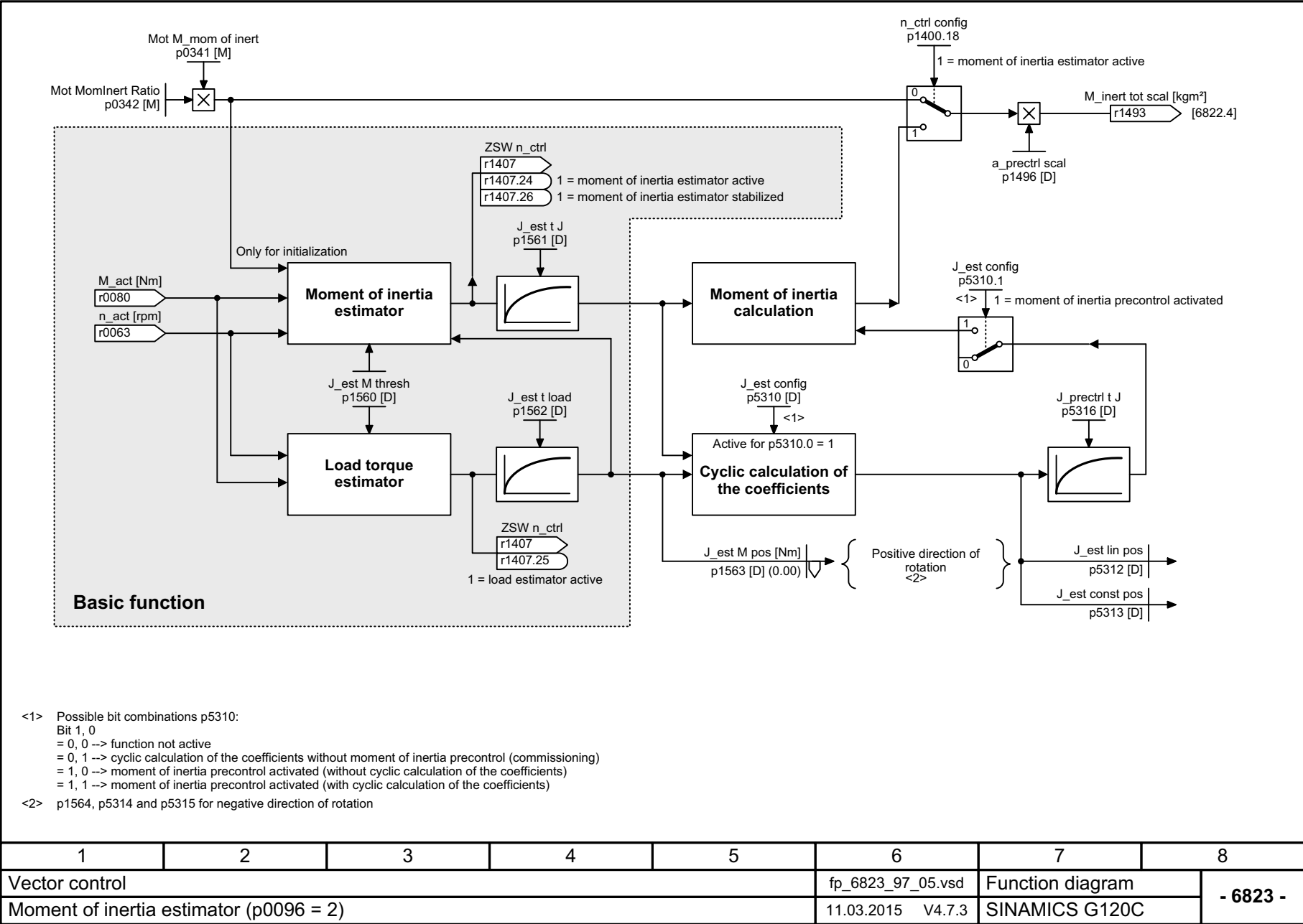
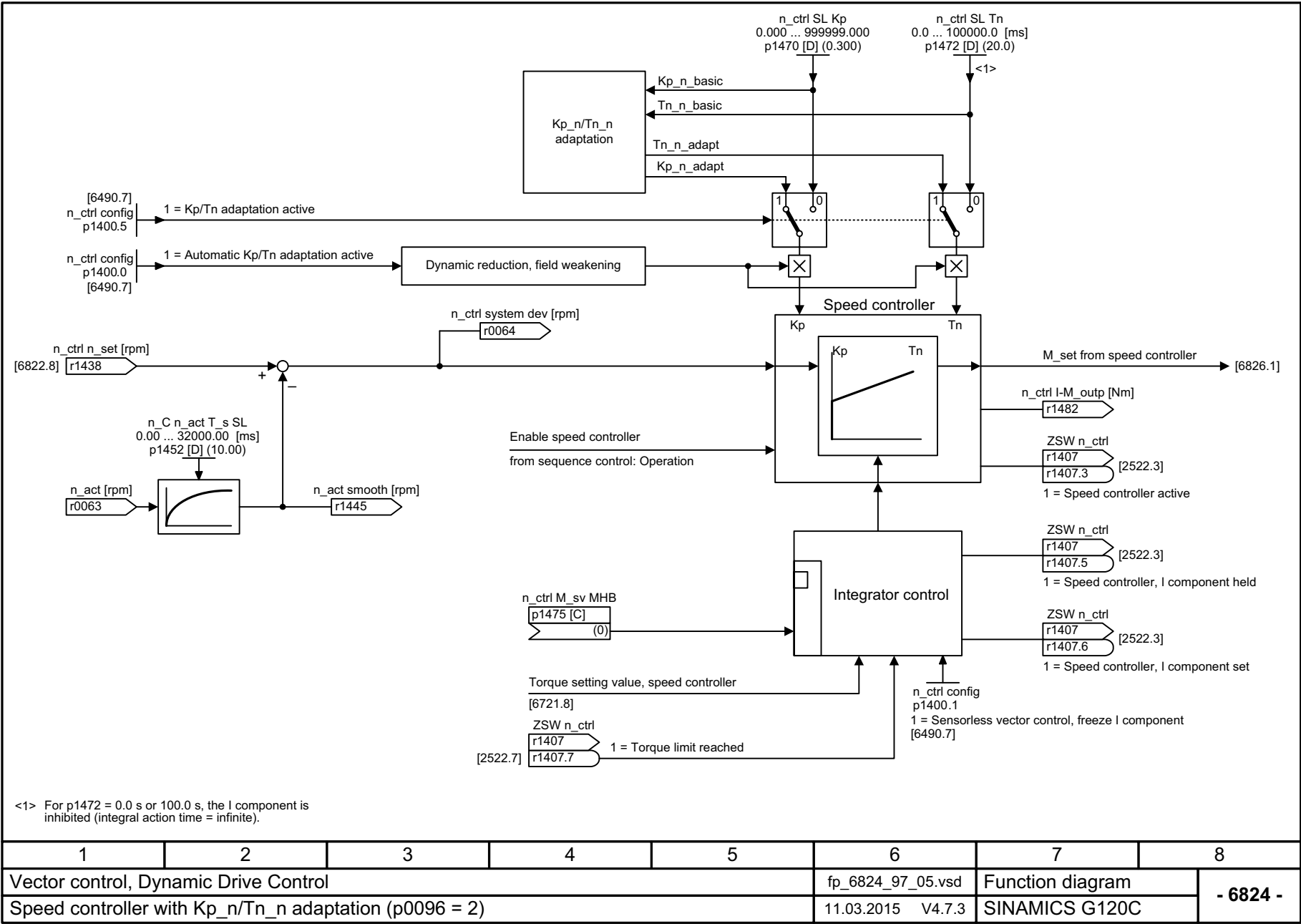
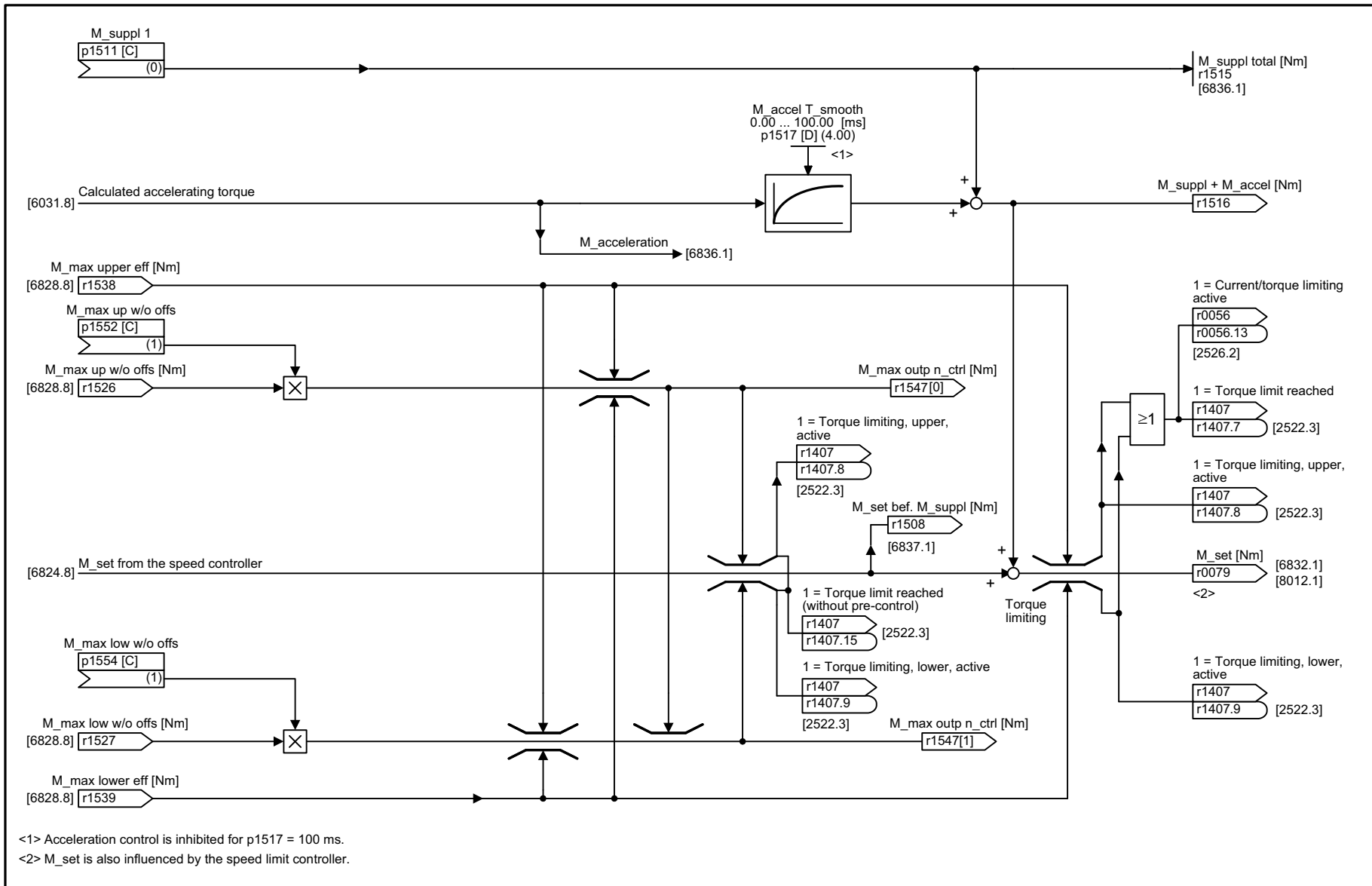


Fig. 3-102 6822 – Speed setpoint, precontrol symmetrization, acceleration model (p0096 = 2)



1	2	3	4	5	6	7	8
Vector control					fp_6823_97_05.vsd	Function diagram	
Moment of inertia estimator (p0096 = 2)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6823 -

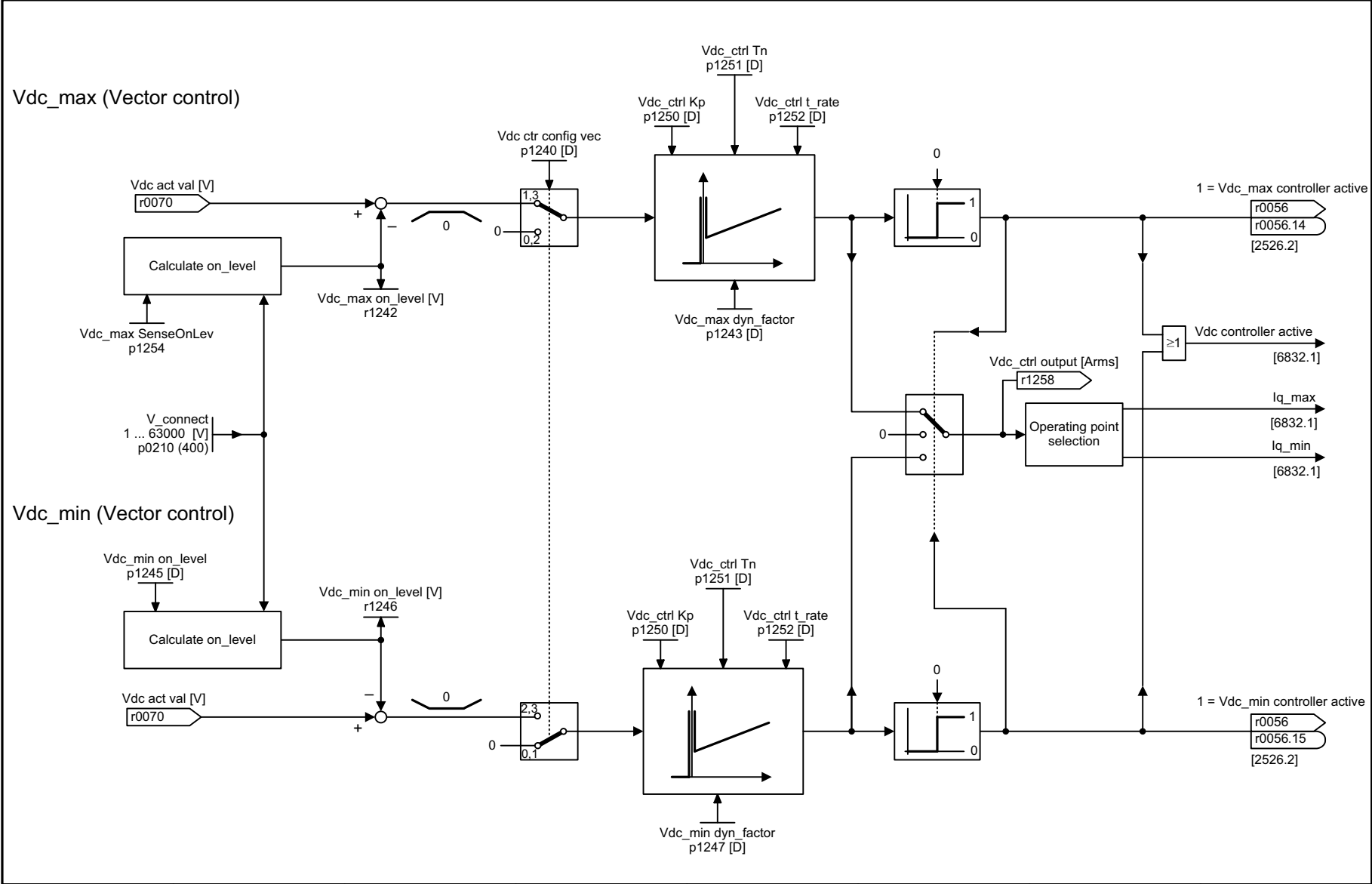




<1> Acceleration control is inhibited for p1517 = 100 ms.
<2> M_set is also influenced by the speed limit controller.

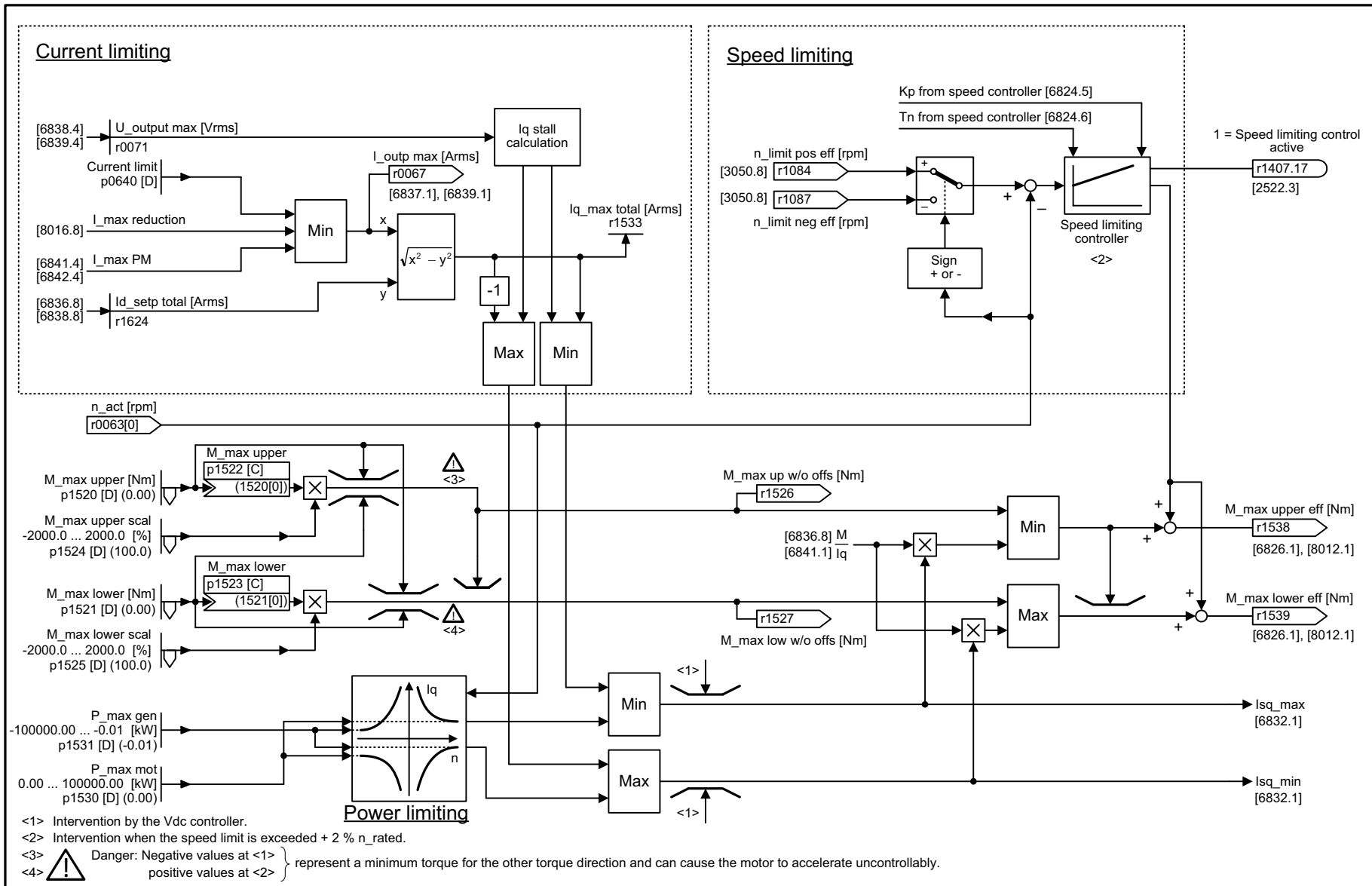
1	2	3	4	5	6	7	8
Vector control, Dynamic Drive Control					fp_6826_97_05.vsd	Function diagram	
Torque setpoint (p0096 = 2)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6826 -

Fig. 3-105 6826 – Torque setpoint (p0096 = 2)



1	2	3	4	5	6	7	8
Vector control, Dynamic Drive Control					fp_6827_97_05.vsd	Function diagram	
Vdc_max controller and Vdc_min controller (p0096 = 2)					11.03.2015 V4.7.3	SINAMICS G120C	
							- 6827 -

Fig. 3-106 6827 – Vdc_max controller and Vdc_min controller (p0096 = 2)



1	2	3	4	5	6	7	8
Vector control, Dynamic Drive Control					fp_6828_97_05.vsd	Function diagram	
Current/power/torque limits (p0096 = 2)					11.03.2015 V4.7.3	SINAMICS G120C	

- 6828 -

Fig. 3-107 6828 – Current/power/torque limits (p0096 = 2)

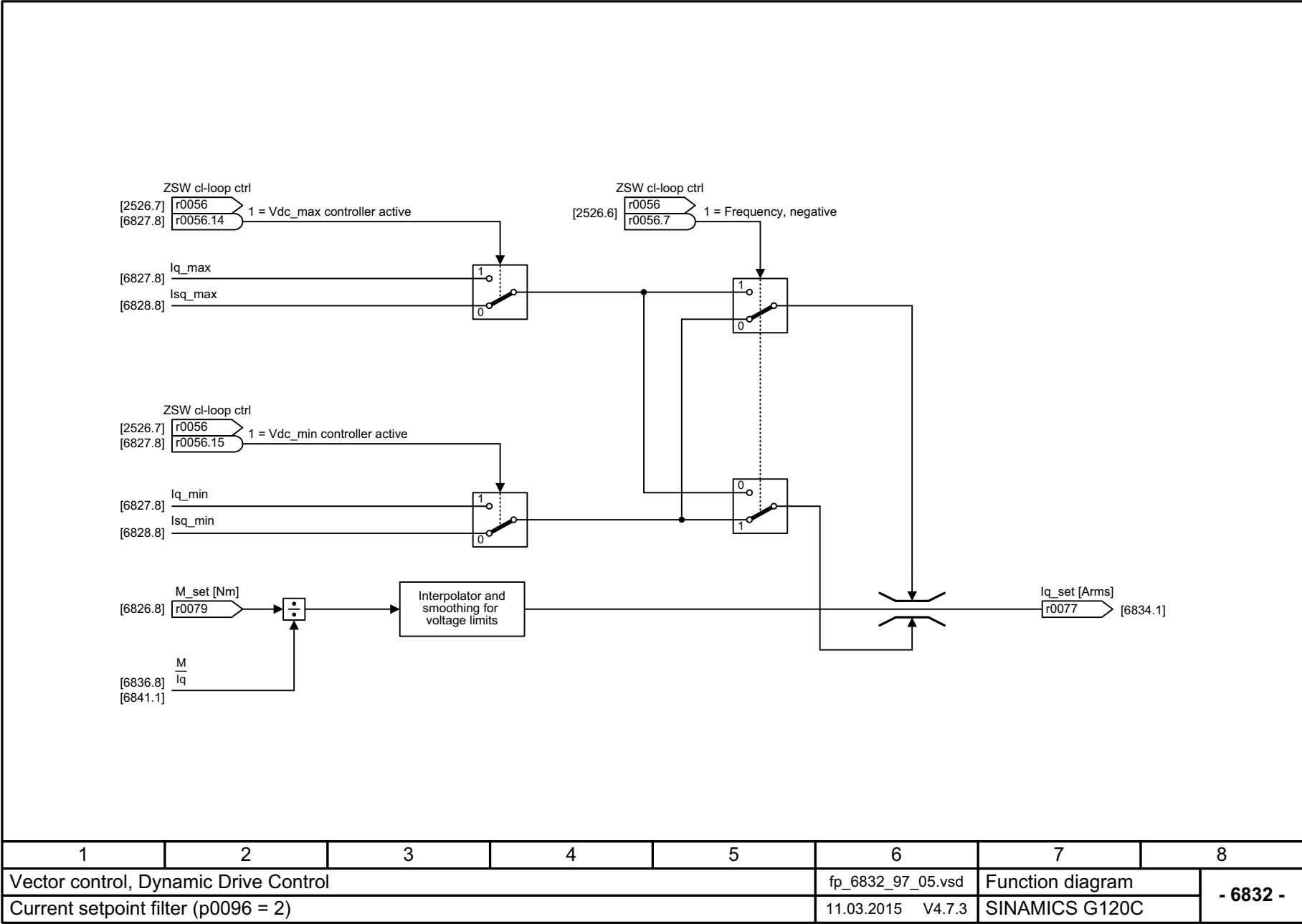


Fig. 3-108 6832 – Current setpoint filter (p0096 = 2)

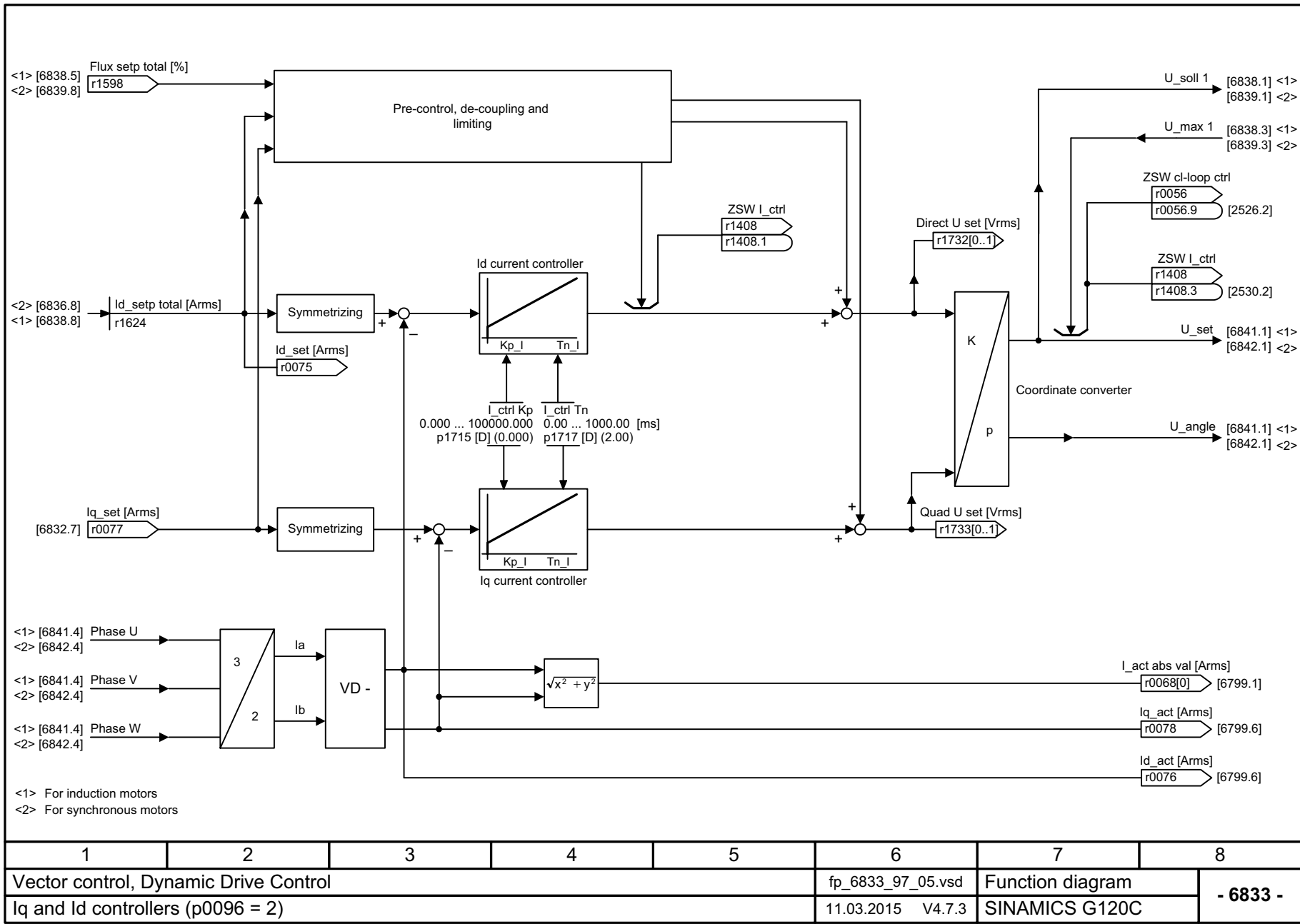


Fig. 3-109 6833 – Iq and Id controller (p0096 = 2)

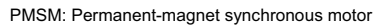
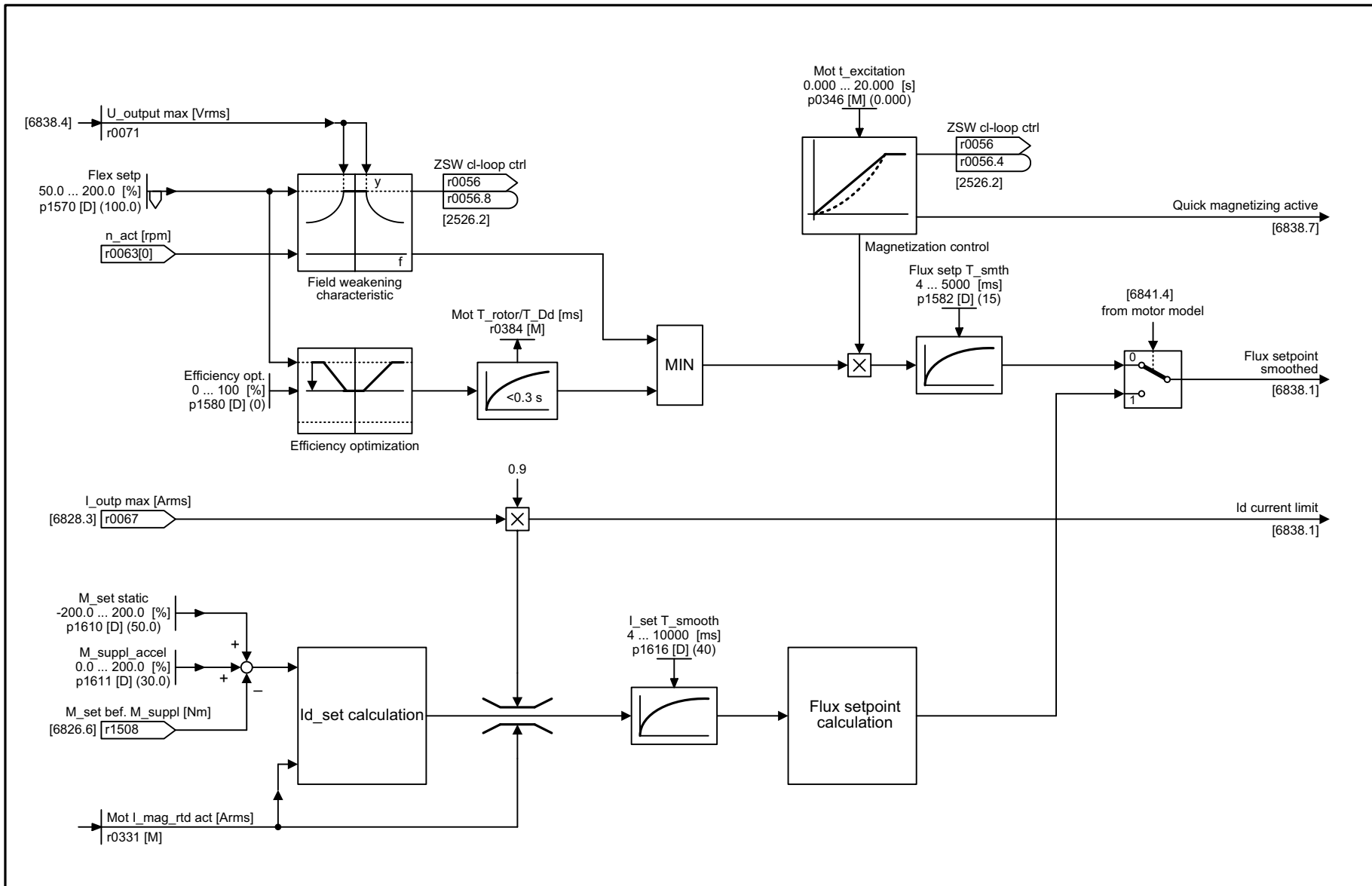


Fig. 3-110 6836 – Id setpoint (PMSM, p0300 = 2xx, p0096 = 2)



1	2	3	4	5	6	7	8
Vector control, Dynamic Drive Control					fp_6837_97_05.vsd	Function diagram	
Field weakening characteristic, flux setpoint (ASM, p0300 = 1, p0096 = 2)					11.03.2015 V4.7.3	SINAMICS G120C	

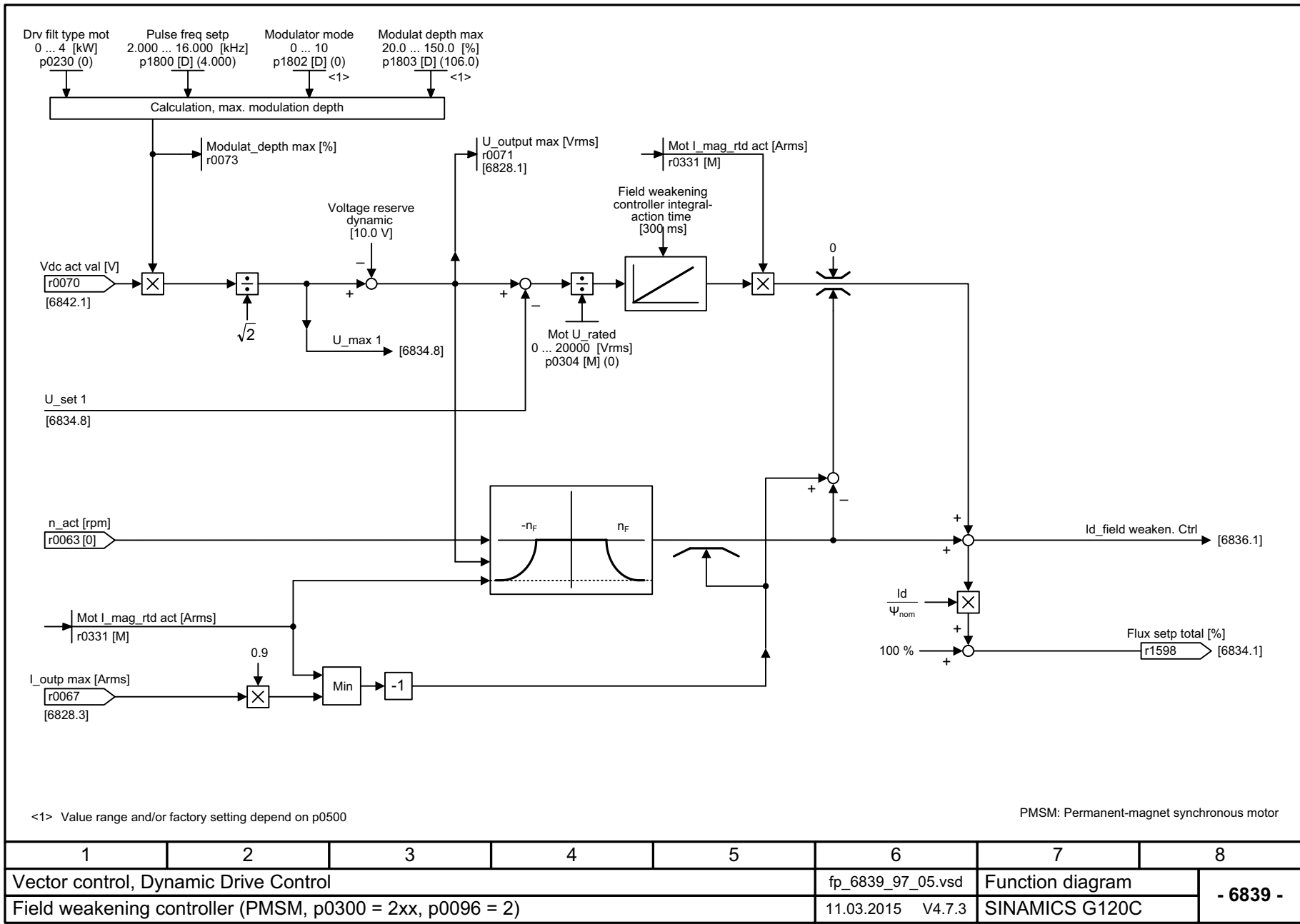
- 6837 -

Fig. 3-111 6837 – Field weakening characteristic, Id setpoint (ASM, p0300 = 1, p0096 = 2)



1	2	3	4	5	6	7	8	
Vector control, Dynamic Drive Control					fp_6838_97_05.vsd	Function diagram		- 6838 -
Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1, p0096 = 2)					11.03.2015 V4.7.3	SINAMICS G120C		

Fig. 3-112 6838 – Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1, p0096 = 2)



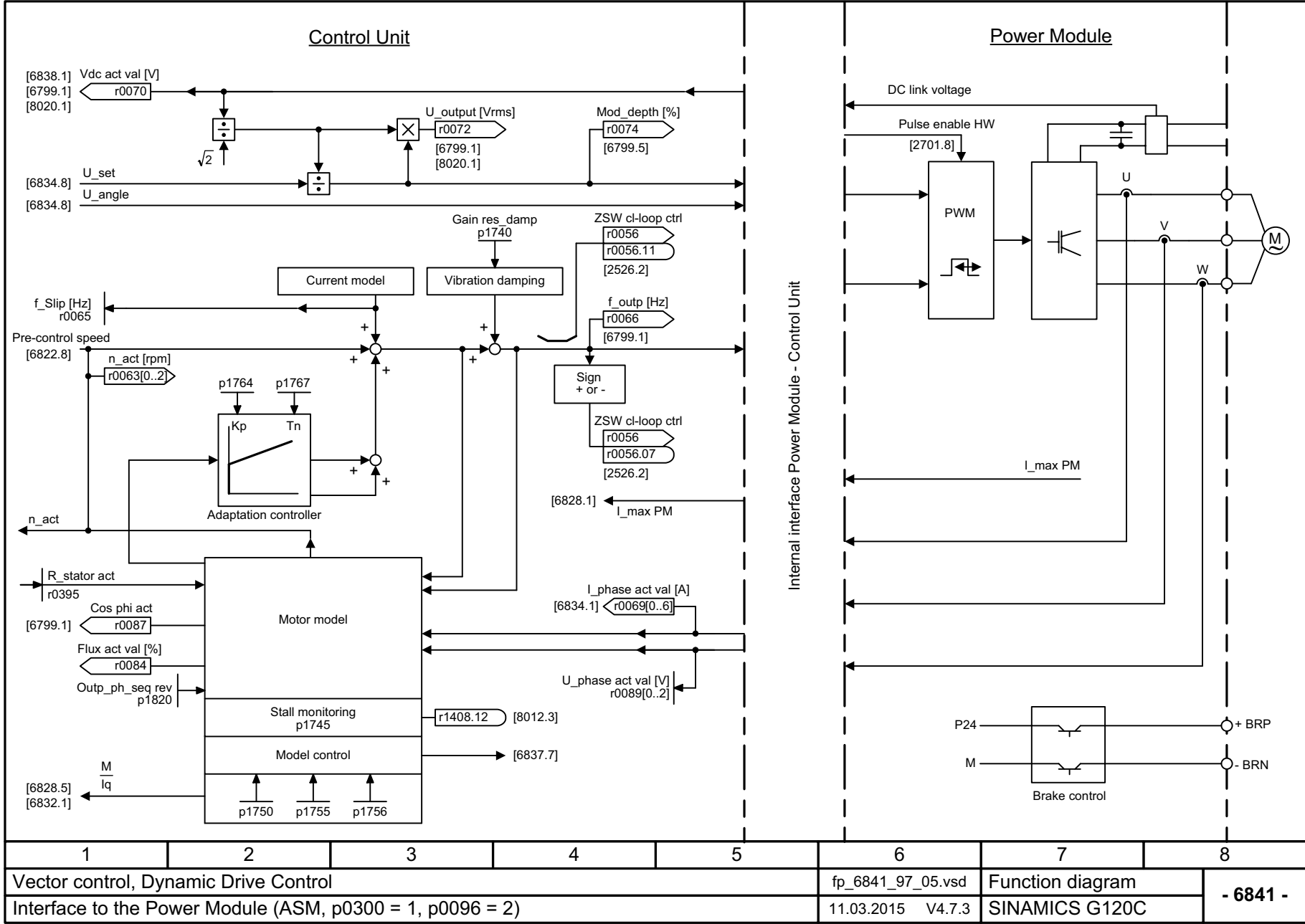
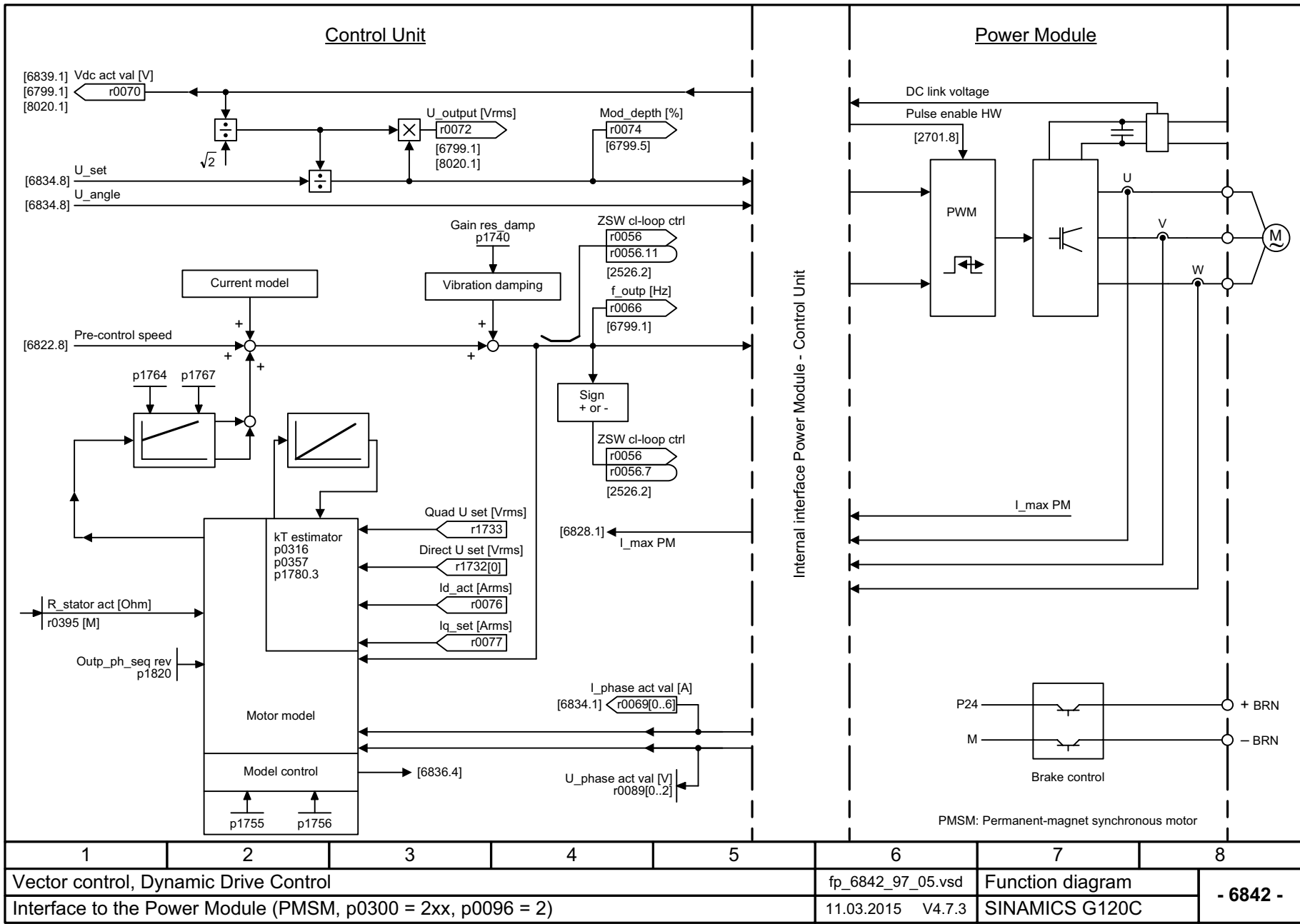


Fig. 3-114 6841 – Interface to the Power Module (ASM, p0300 = 1, p0096 = 2)

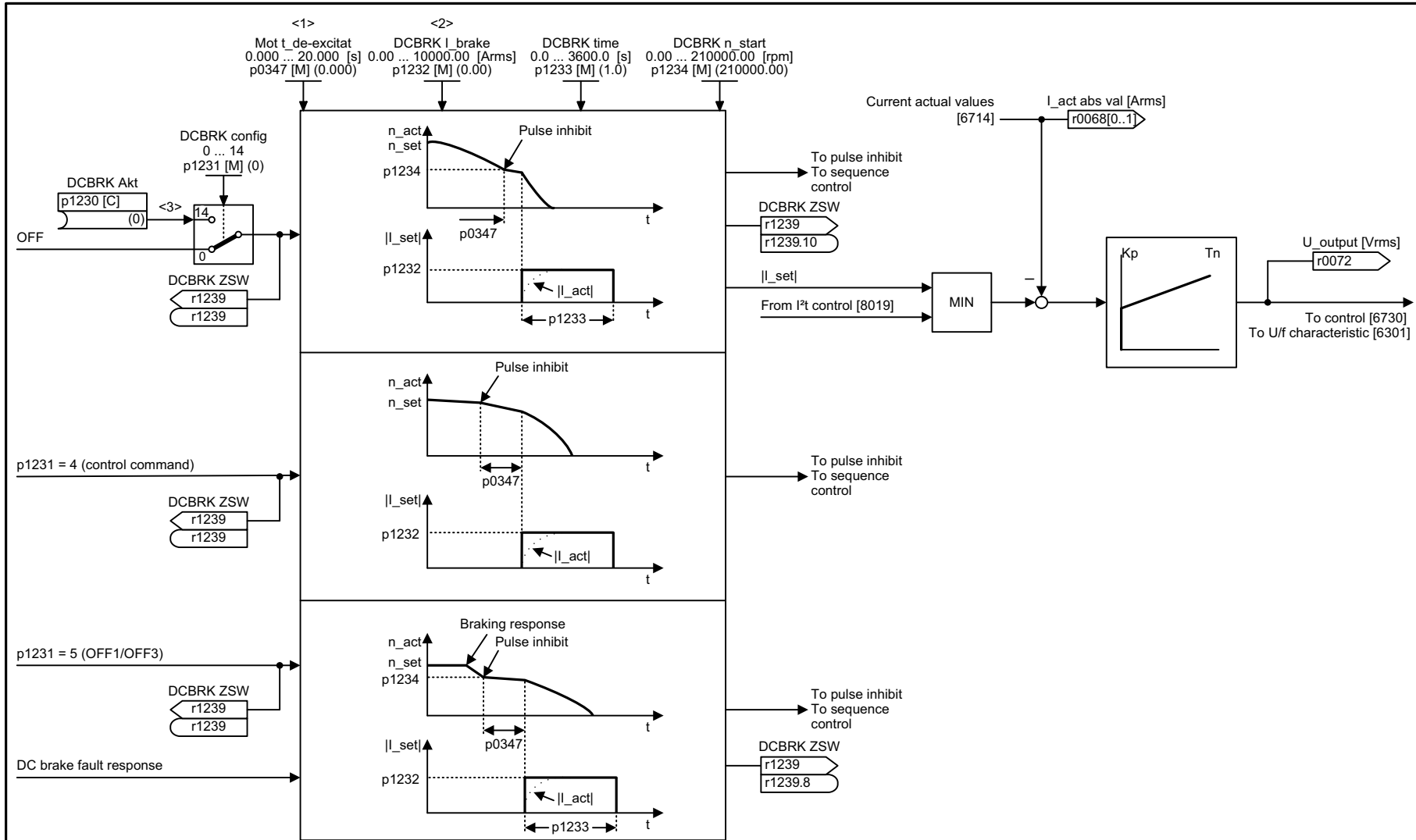


3.16 Technology functions

Function block diagrams

7017 – DC brake (p0300 = 1)

491



<1> The de-magnetization time is determined during automatic calculation (p0340 = 1, 3).
<2> The DC braking current is determined during automatic calculation (p0340 = 1).
<3> DC braking when starting speed for DC braking (p1234) is fallen below.

1	2	3	4	5	6	7	8
Technology functions					fp_7017_97_05.vsd	Function diagram	
DC brake (p0300 = 1)					11.03.2015 V4.7.3	SINAMICS G120C	
					- 7017 -		

3.17 Technology controller

Function block diagrams

7950 – Fixed value selection binary (p2216 = 2)	493
7951 – Fixed value selection direct (p2216 = 1)	494
7954 – Motorized potentiometer	495
7958 – Closed-loop control	496

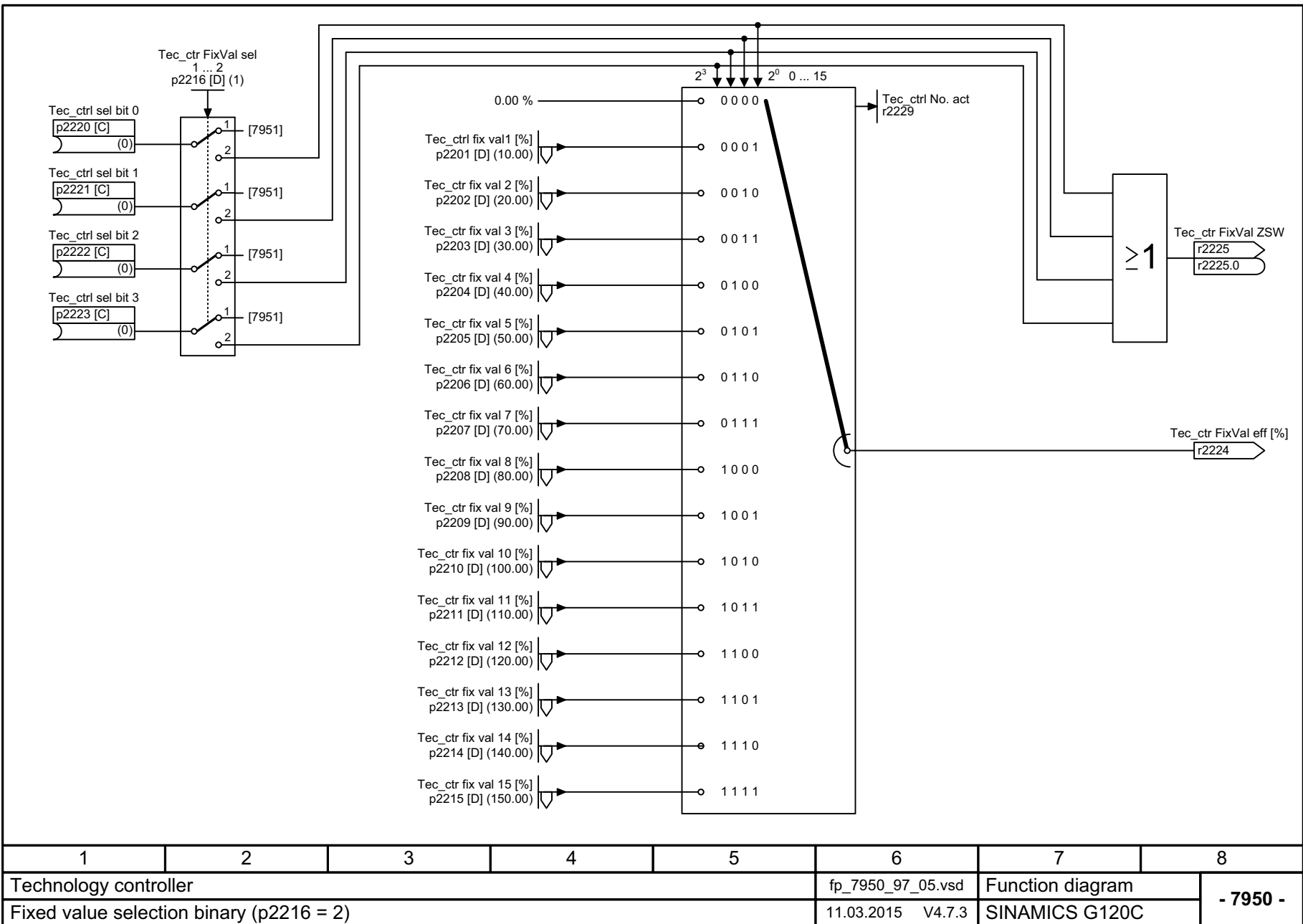


Fig. 3-117 7950 – Fixed value selection binary (p2216 = 2)

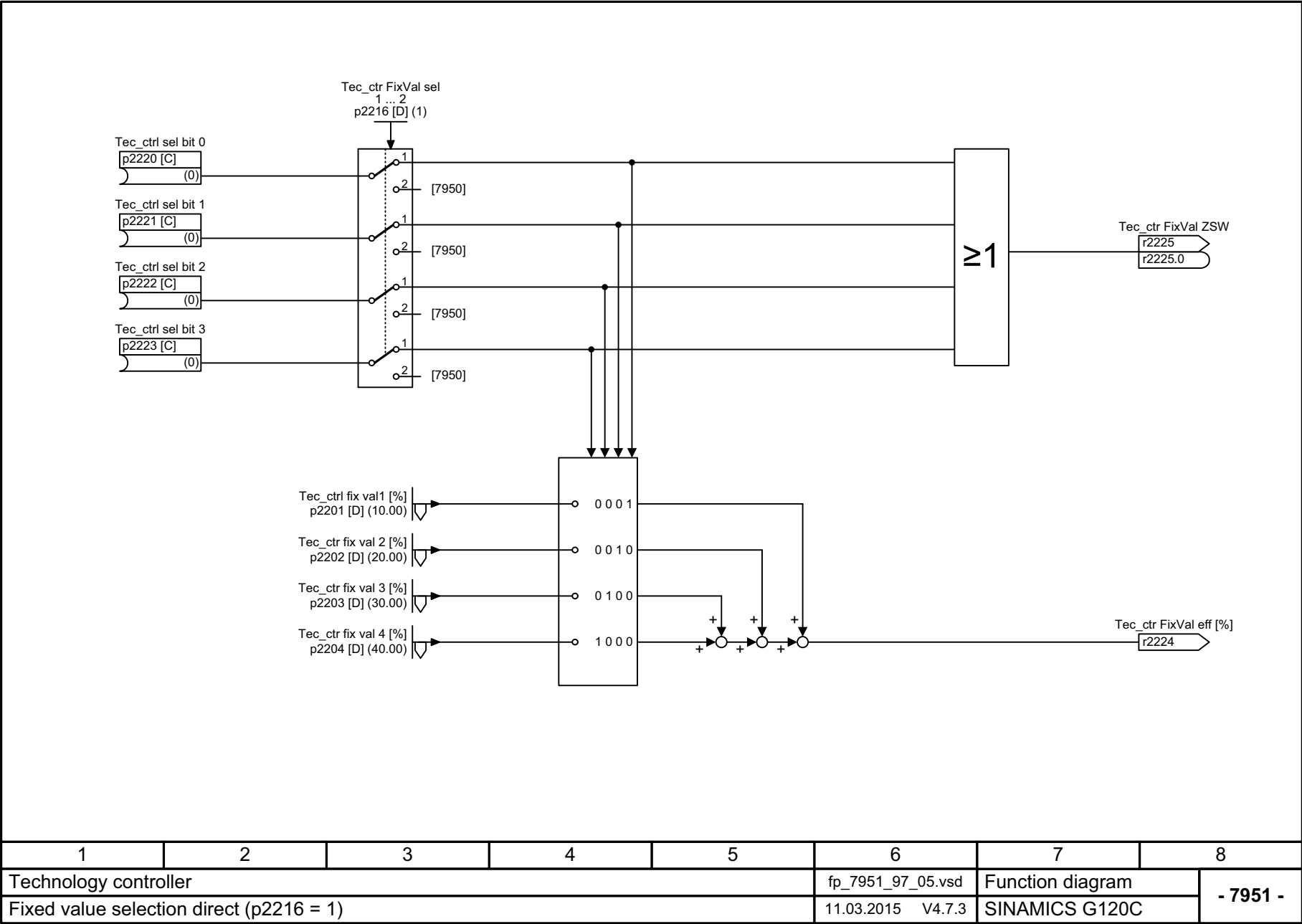
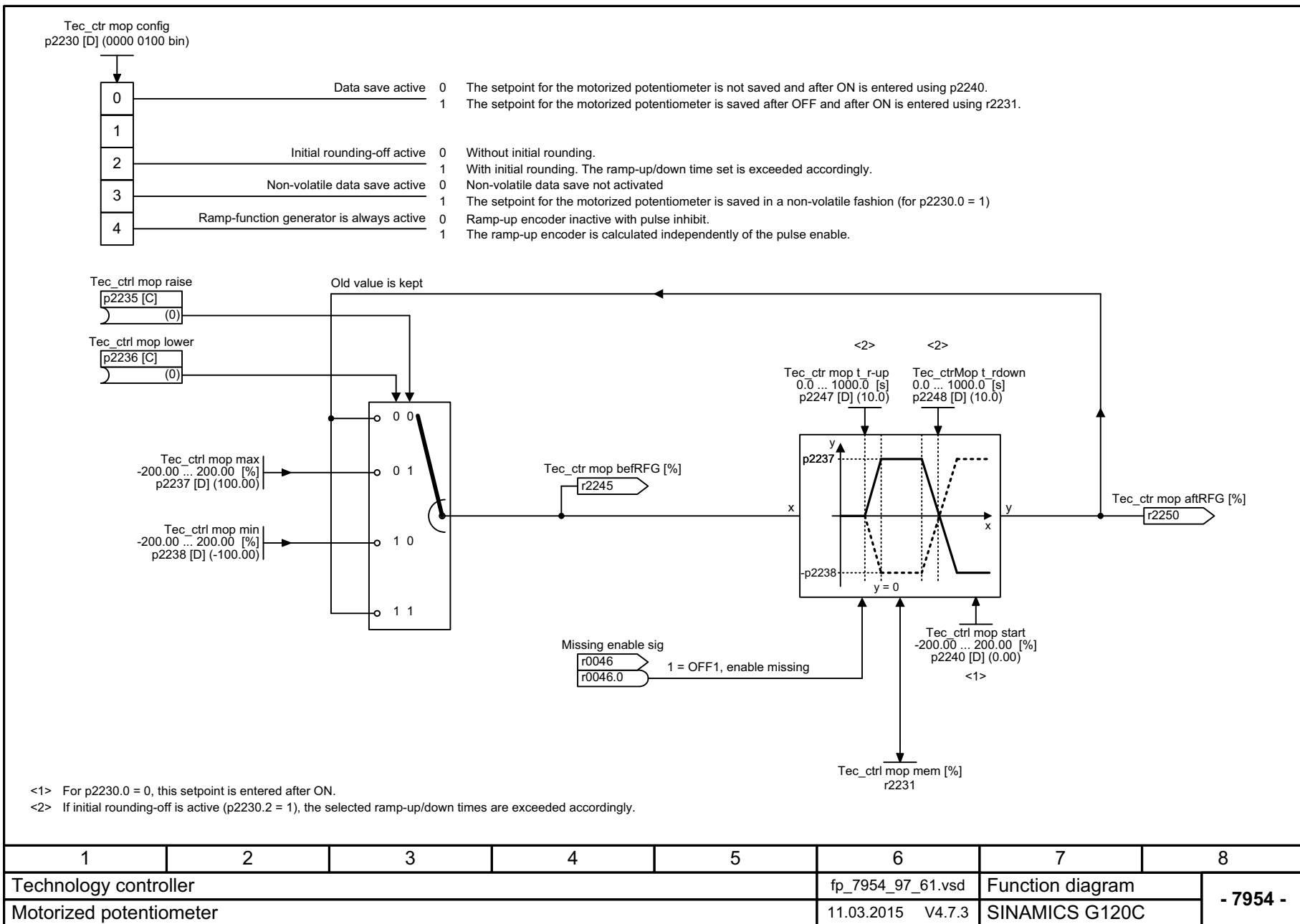


Fig. 3-118 7951 – Fixed value selection direct (p2216 = 1)



1	2	3	4	5	6	7	8
Technology controller					fp_7954_97_61.vsd	Function diagram	
Motorized potentiometer					11.03.2015 V4.7.3	SINAMICS G120C	
							- 7954 -

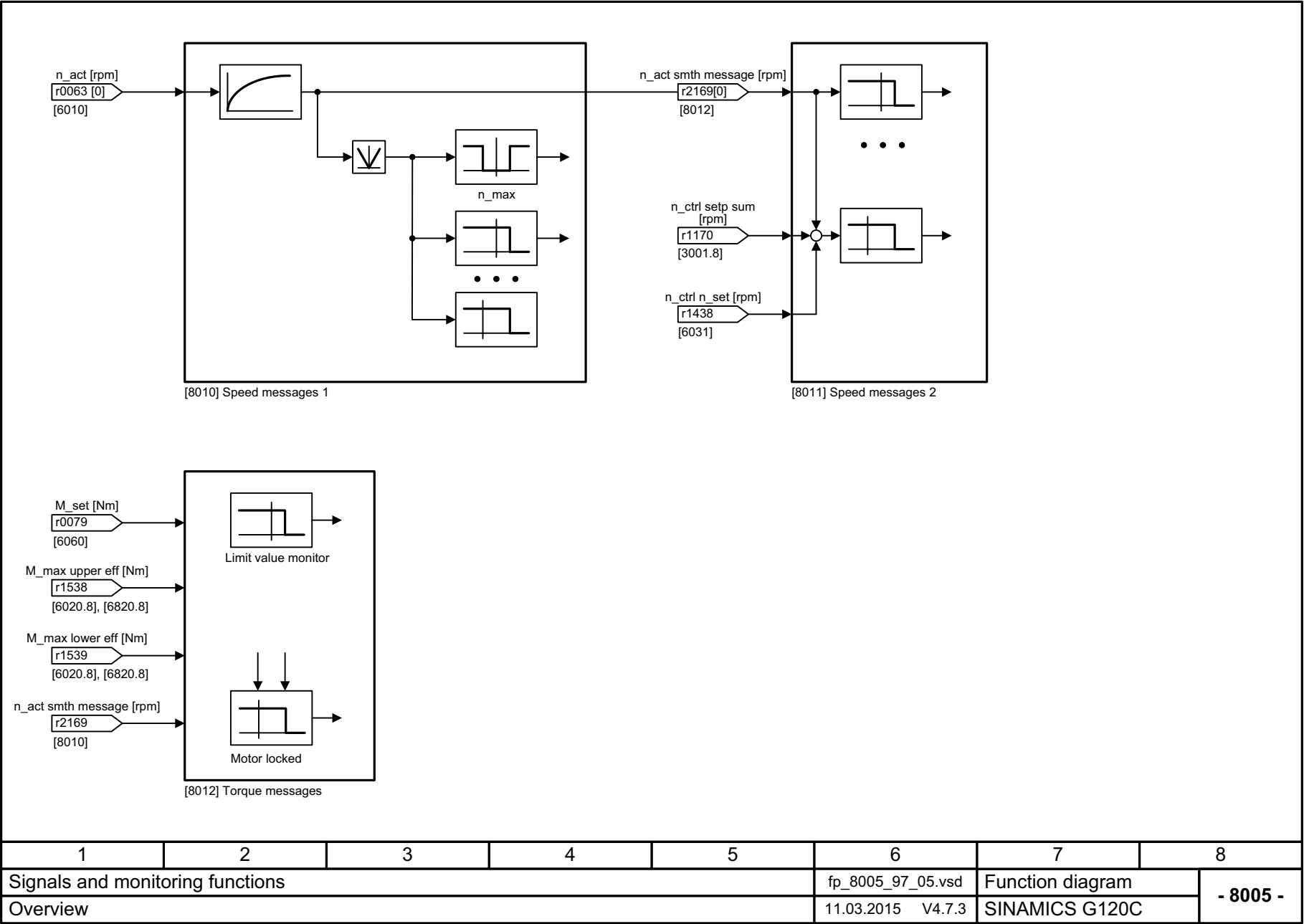
SINAMICS G120C
List Manual (LH13), 04/2015, A5E33840768



3.18 Signals and monitoring functions

Function block diagrams

8005 – Overview	498
8010 – Speed messages 1	499
8011 – Speed messages 2	500
8012 – Torque signals, motor blocked/stalled	501
8016 – Thermal monitoring, motor	502
8017 – Thermal motor models	503
8019 – Thermal monitoring, power unit	504
8020 – Monitoring functions 1	505
8021 – Monitoring functions 2	506



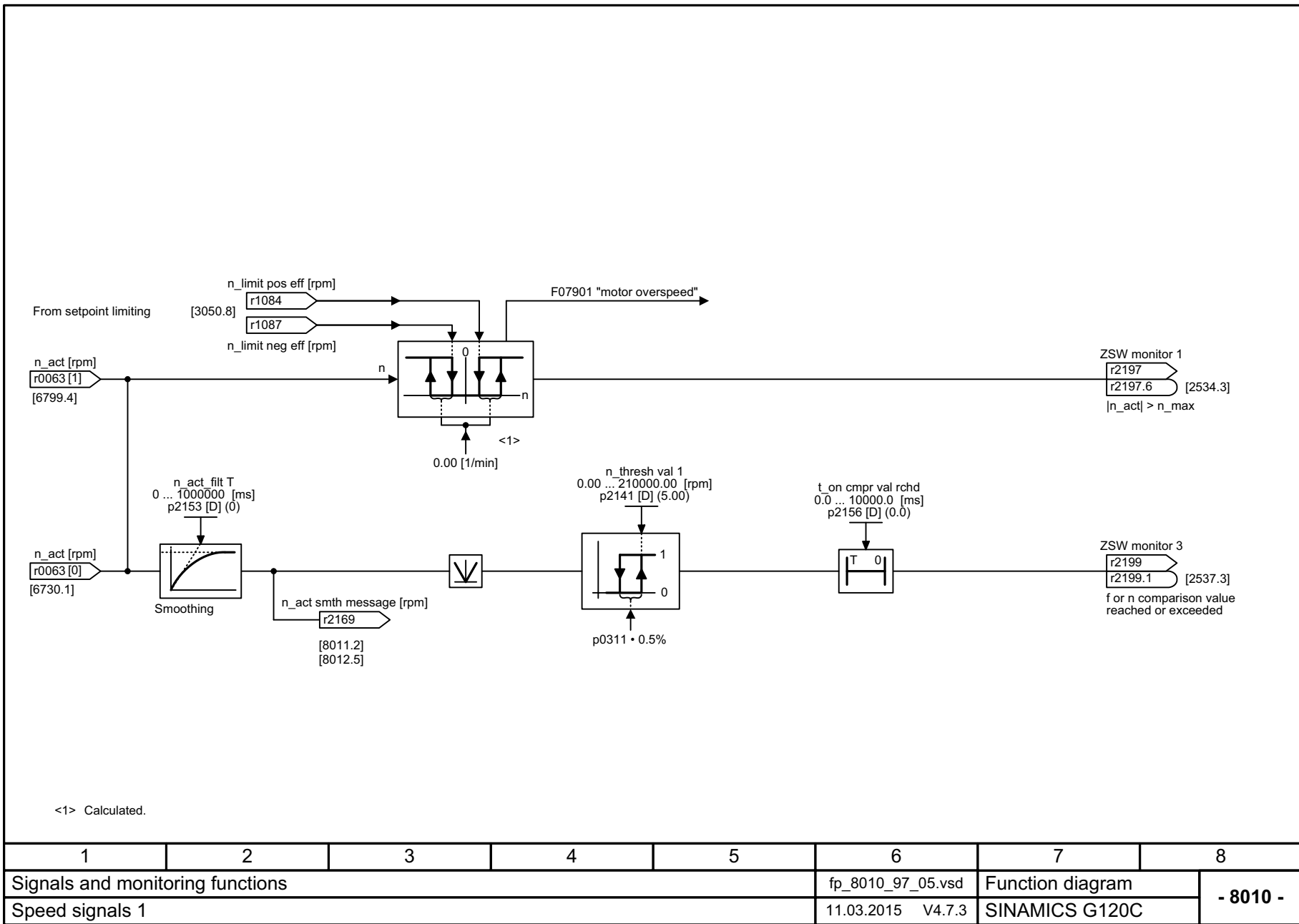
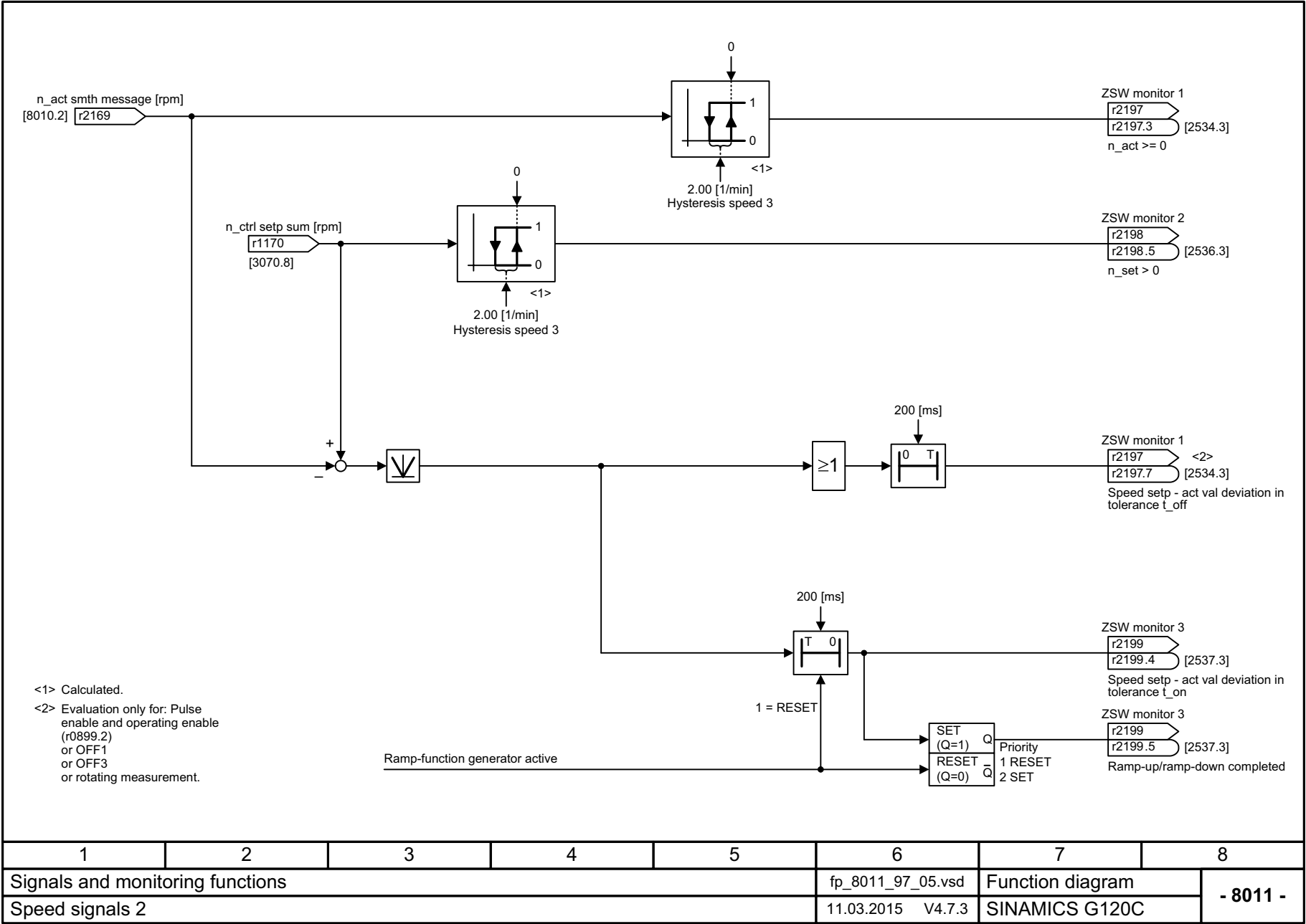


Fig. 3-122 8010 – Speed messages 1



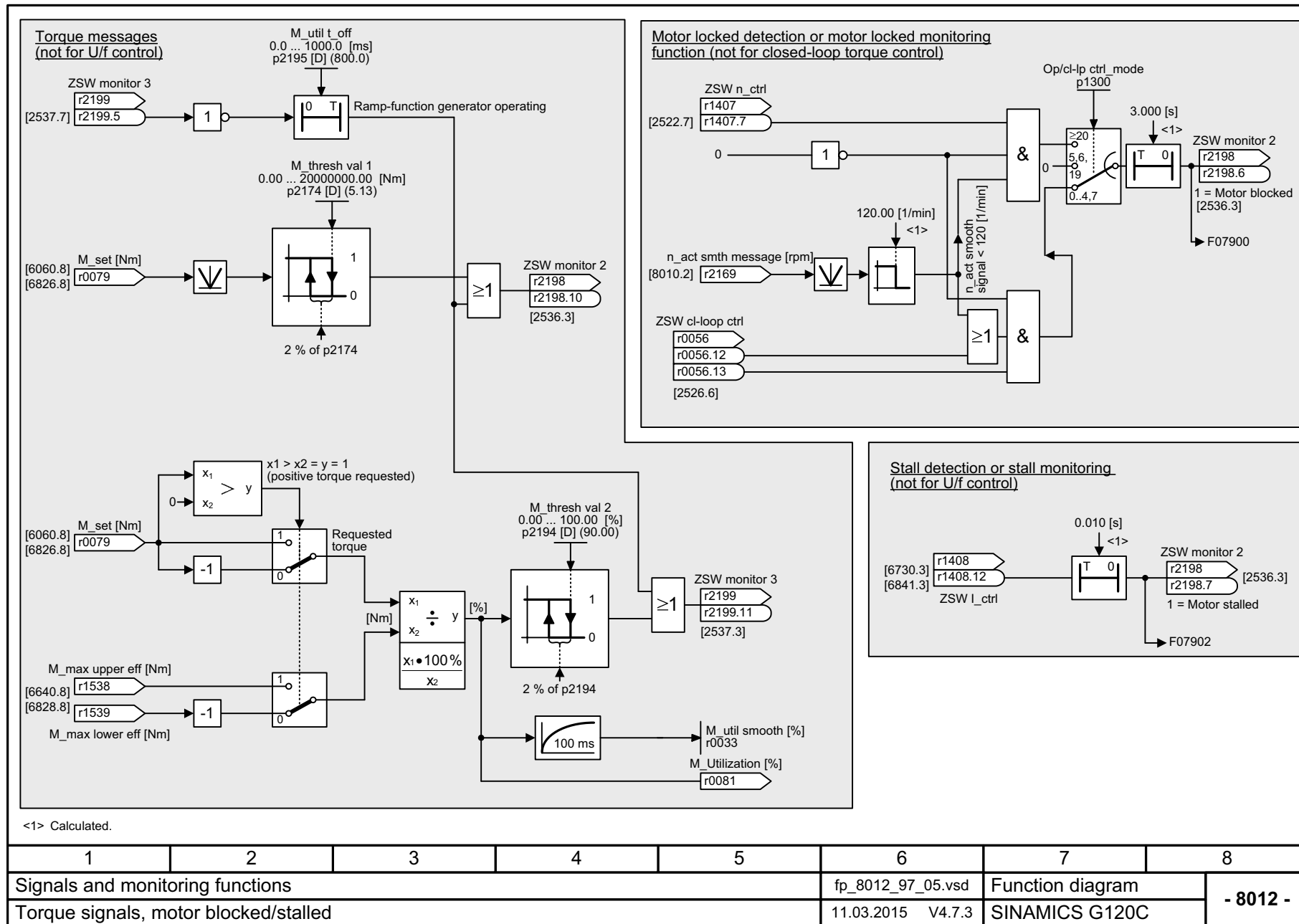
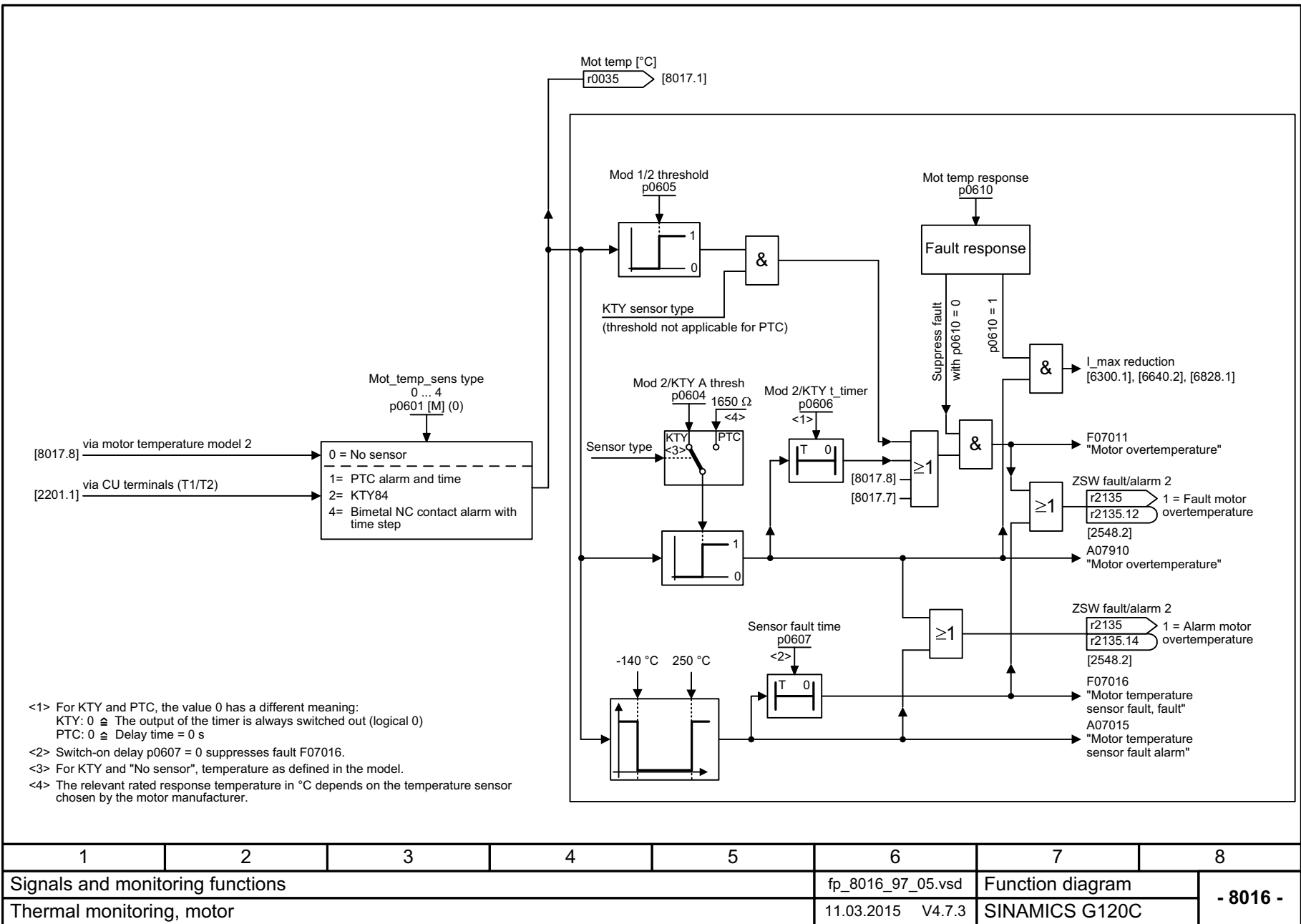
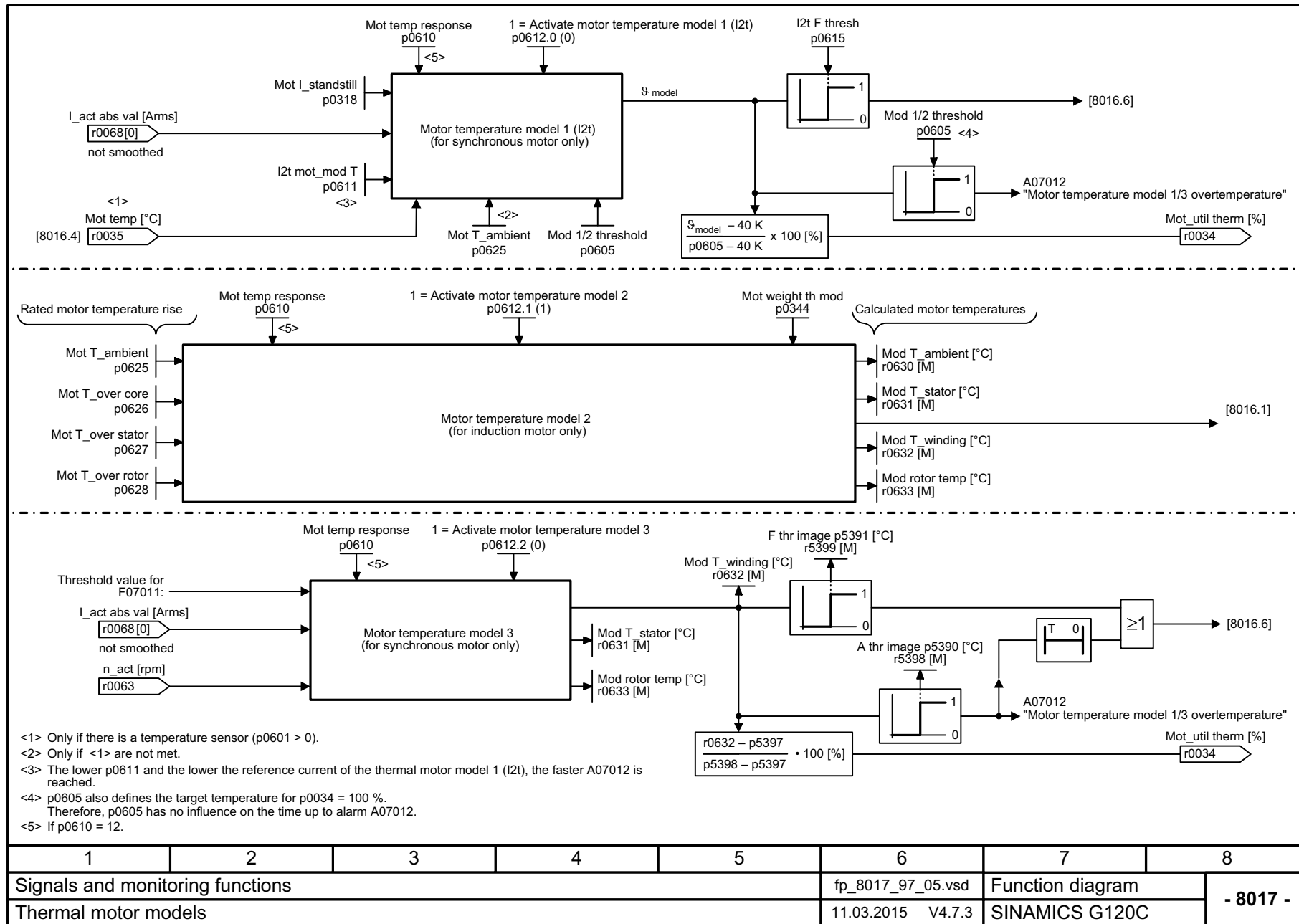


Fig. 3-124 8012 – Torque signals, motor blocked/stalled





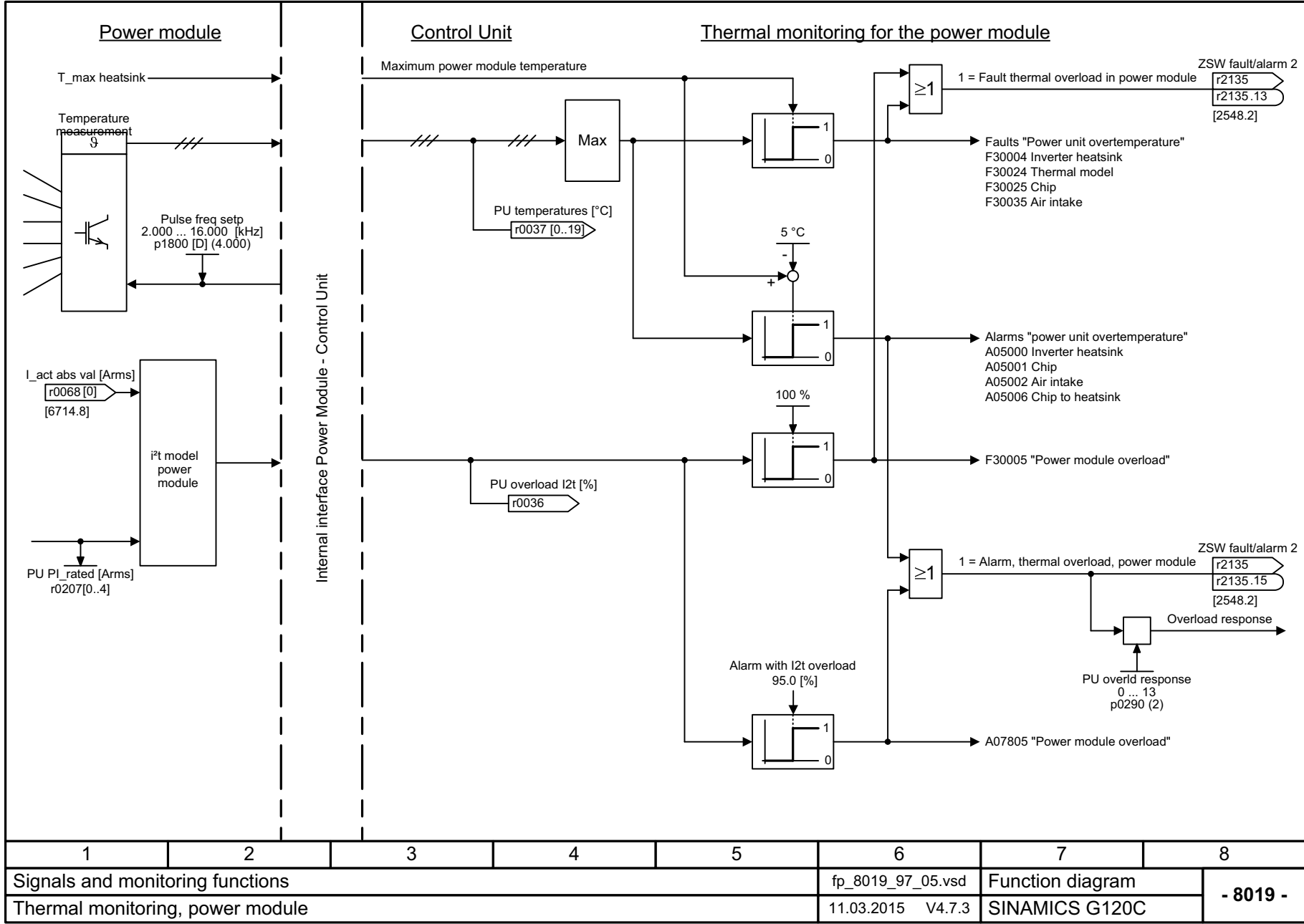
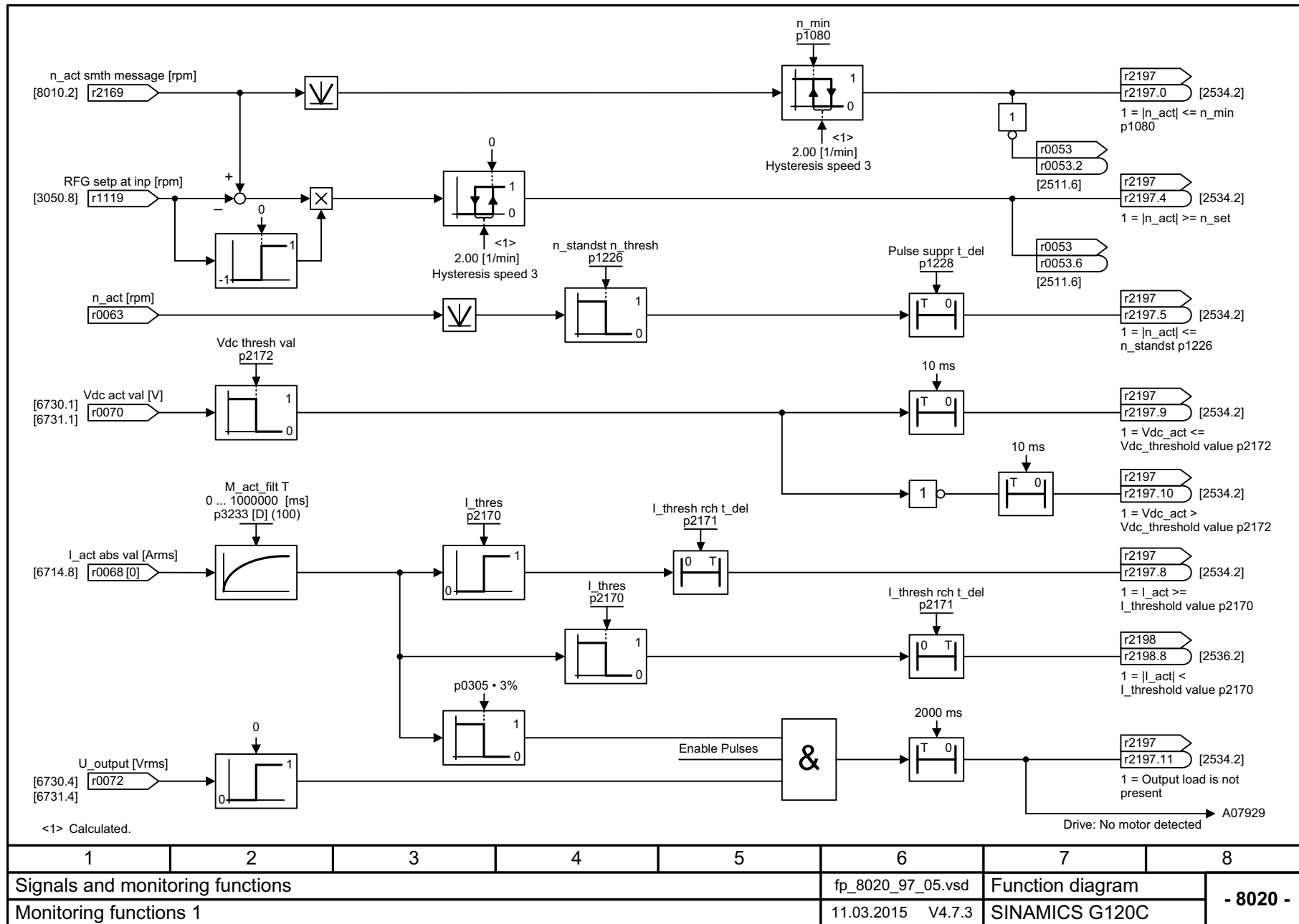
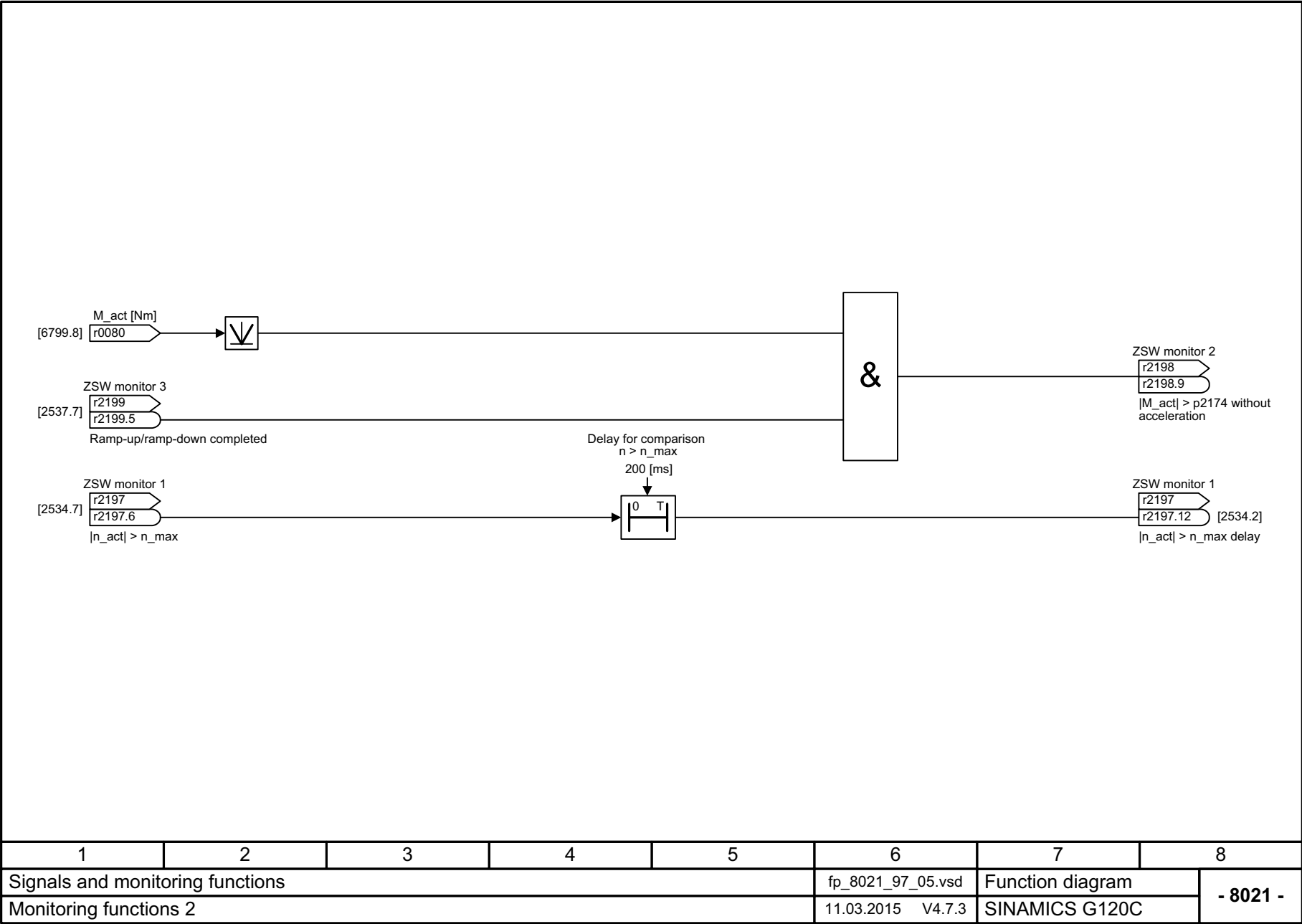


Fig. 3-127 8019 – Thermal monitoring, power unit





3.19 Diagnostics

Function block diagrams

8050 – Overview	508
8060 – Fault buffer	509
8065 – Alarm buffer	510
8070 – Faults/alarms trigger word (r2129)	511
8075 – Faults/alarms configuration	512

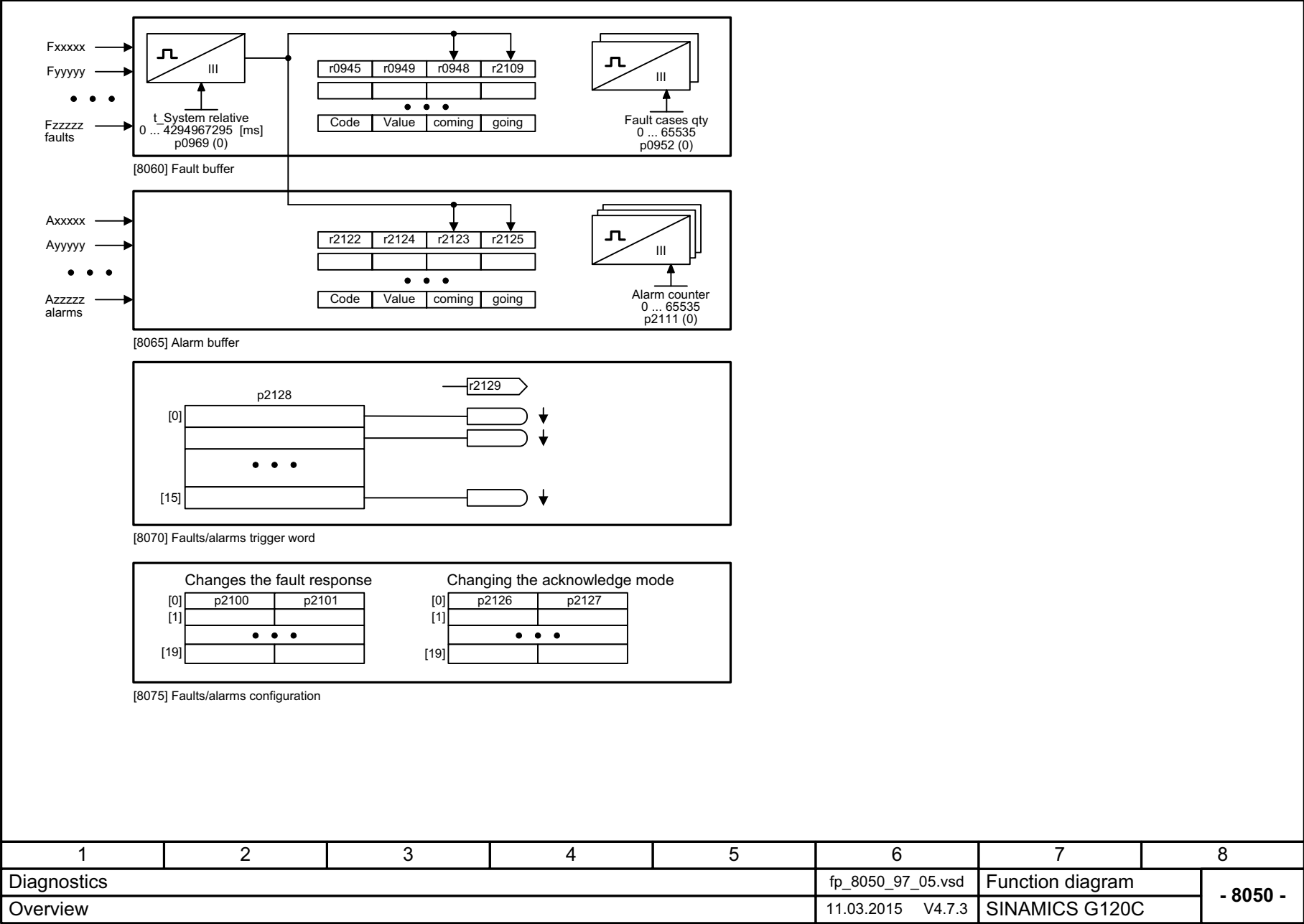
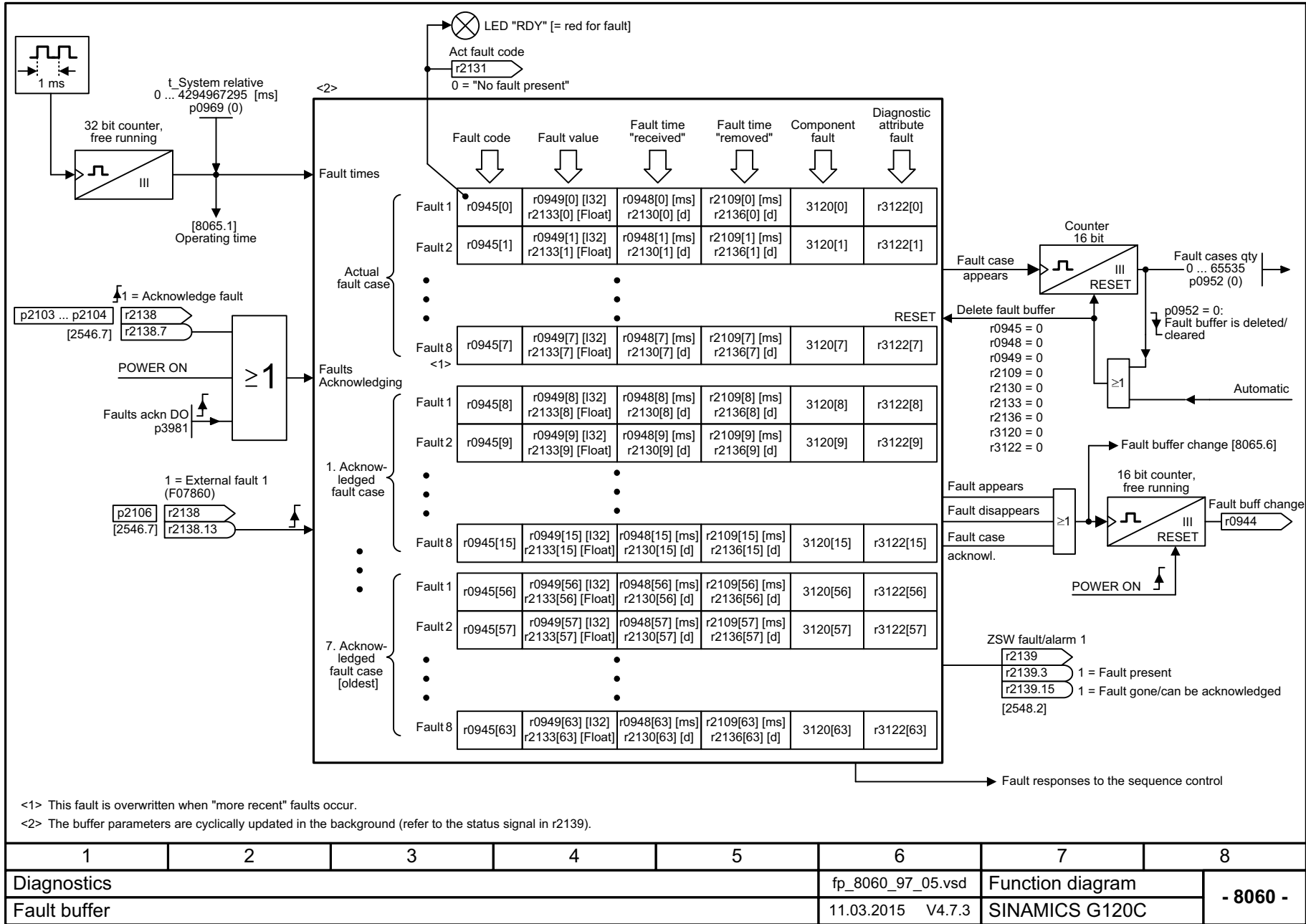


Fig. 3-130 8050 – Overview



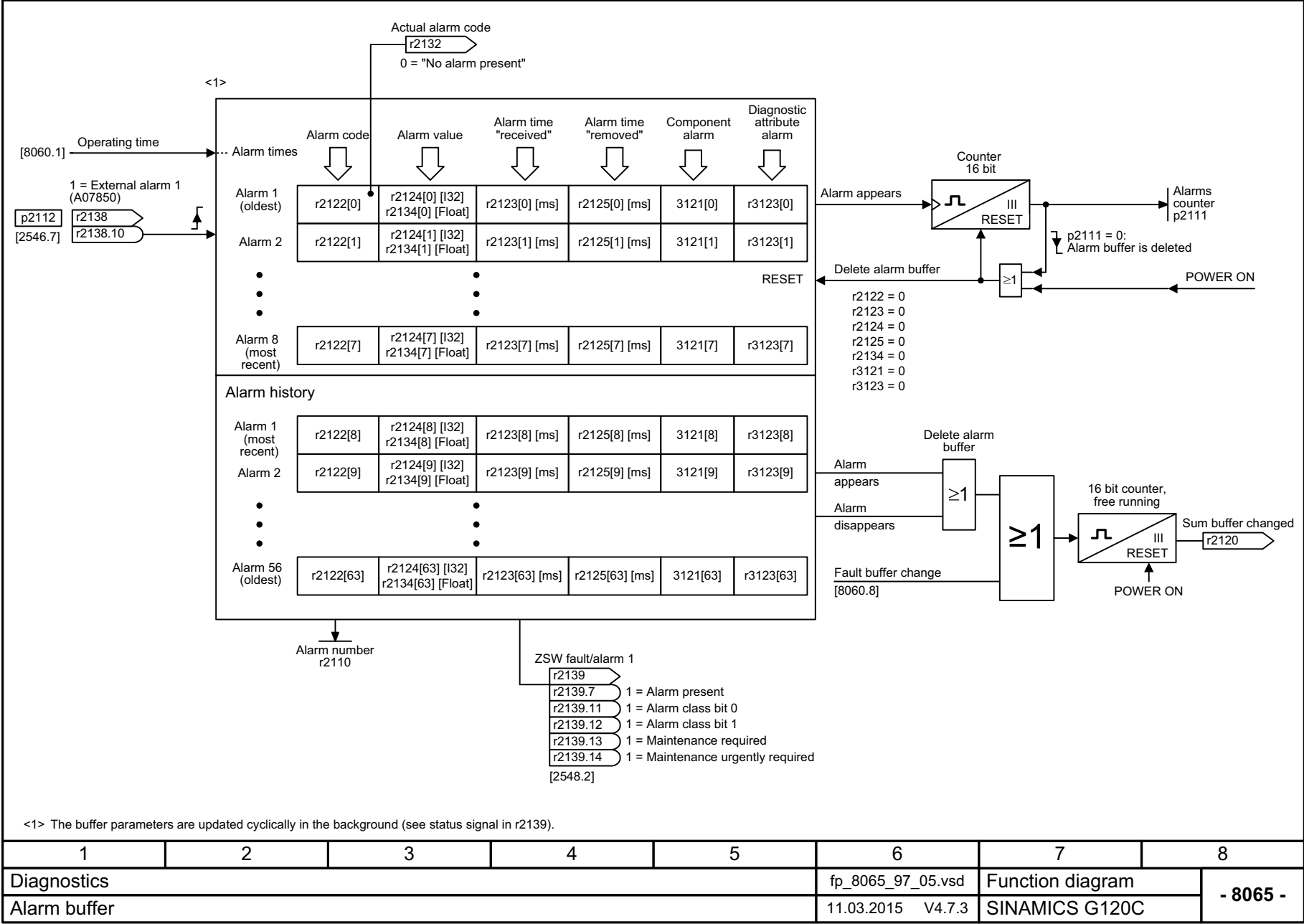


Fig. 3-132 8065 – Alarm buffer

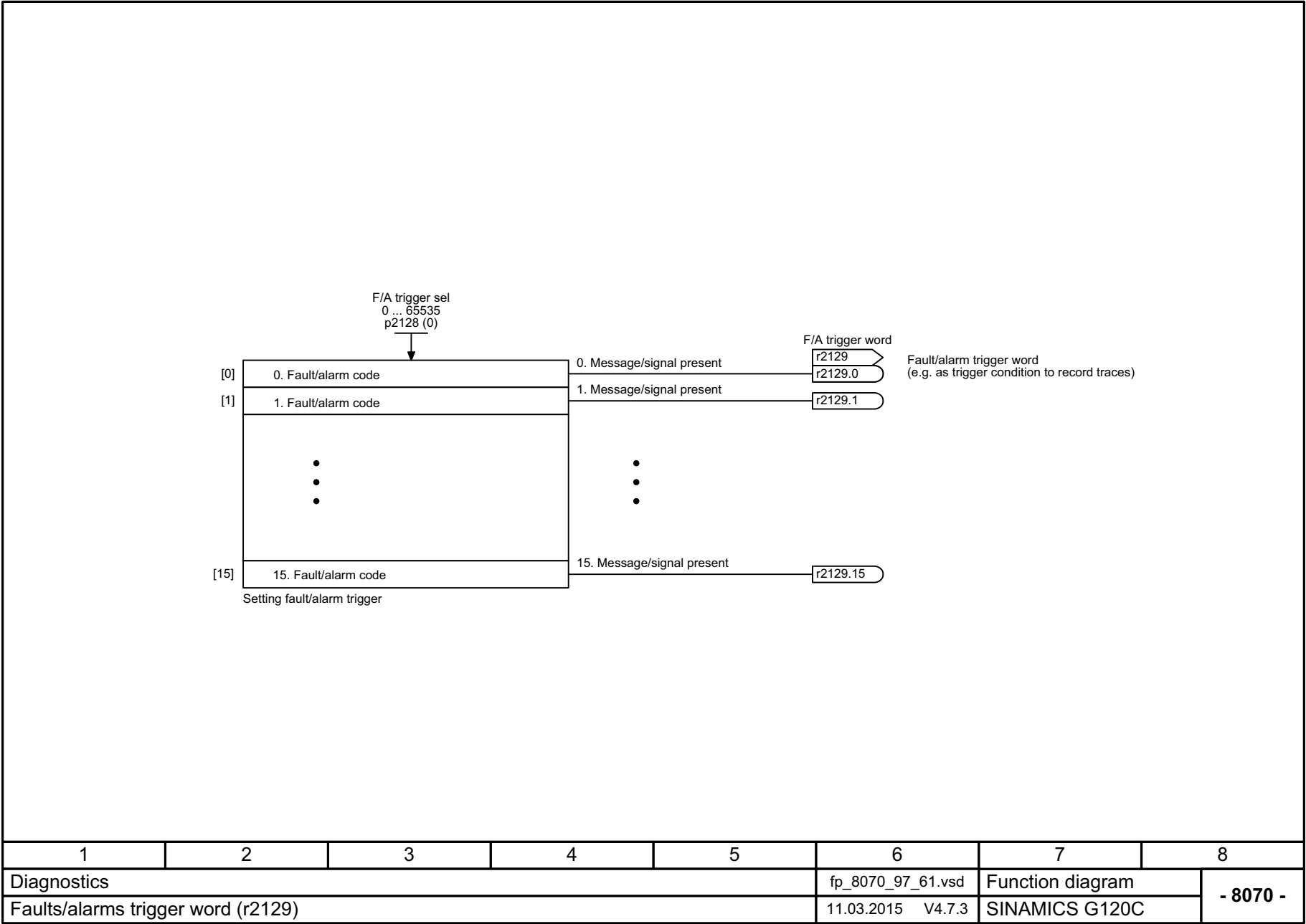
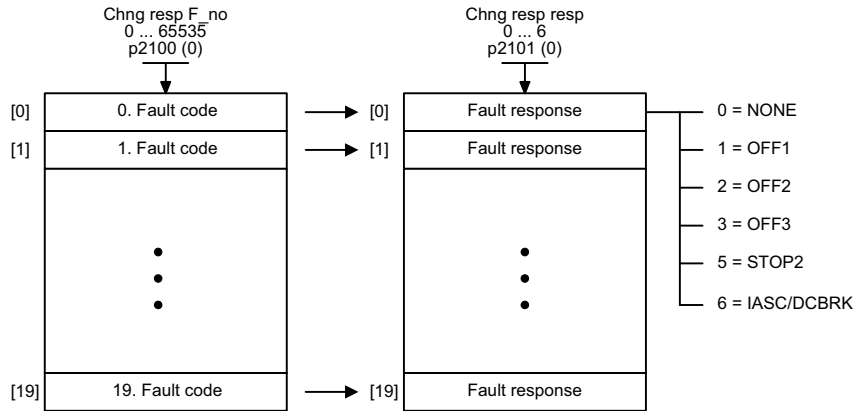
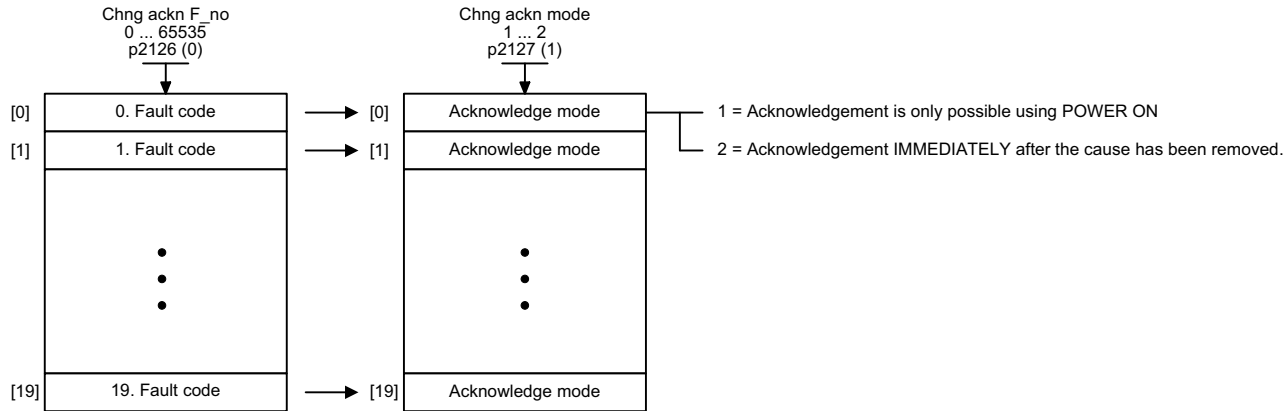


Fig. 3-133 8070 – Faults/alarms trigger word (r2129)

Changing the fault response for maximum 20 faults <1>



Changing the acknowledge mode for maximum 20 faults <1>



<1> The fault response, acknowledge mode and message type for all faults and alarms are set to meaningful default values in the factory setting.
Changes are only possible in specific value ranges specified by SIEMENS.
When the message type is changed, the supplementary information is transferred from fault value r0949 to alarm value r2124 and vice versa.

1	2	3	4	5	6	7	8
Diagnostics					fp_8075_97_05.vsd	Function diagram	- 8075 -
Faults/alarms configuration					11.03.2015 V4.7.3	SINAMICS G120C	

Fig. 3-134 8075 – Faults/alarms configuration

3.20 Data sets

Function block diagrams

8560 – Command Data Sets (CDS)	514
8565 – Drive Data Sets (DDS)	515

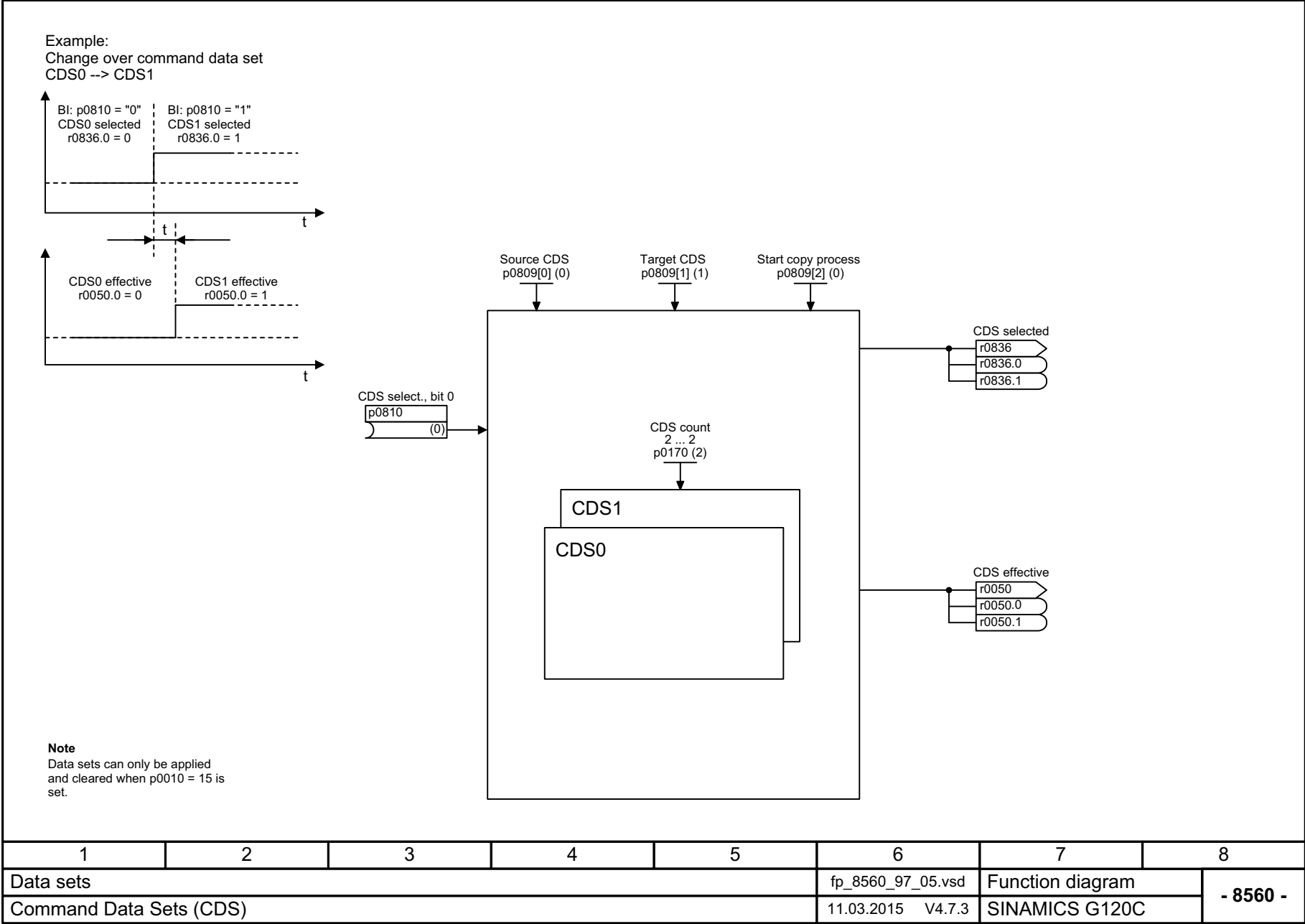
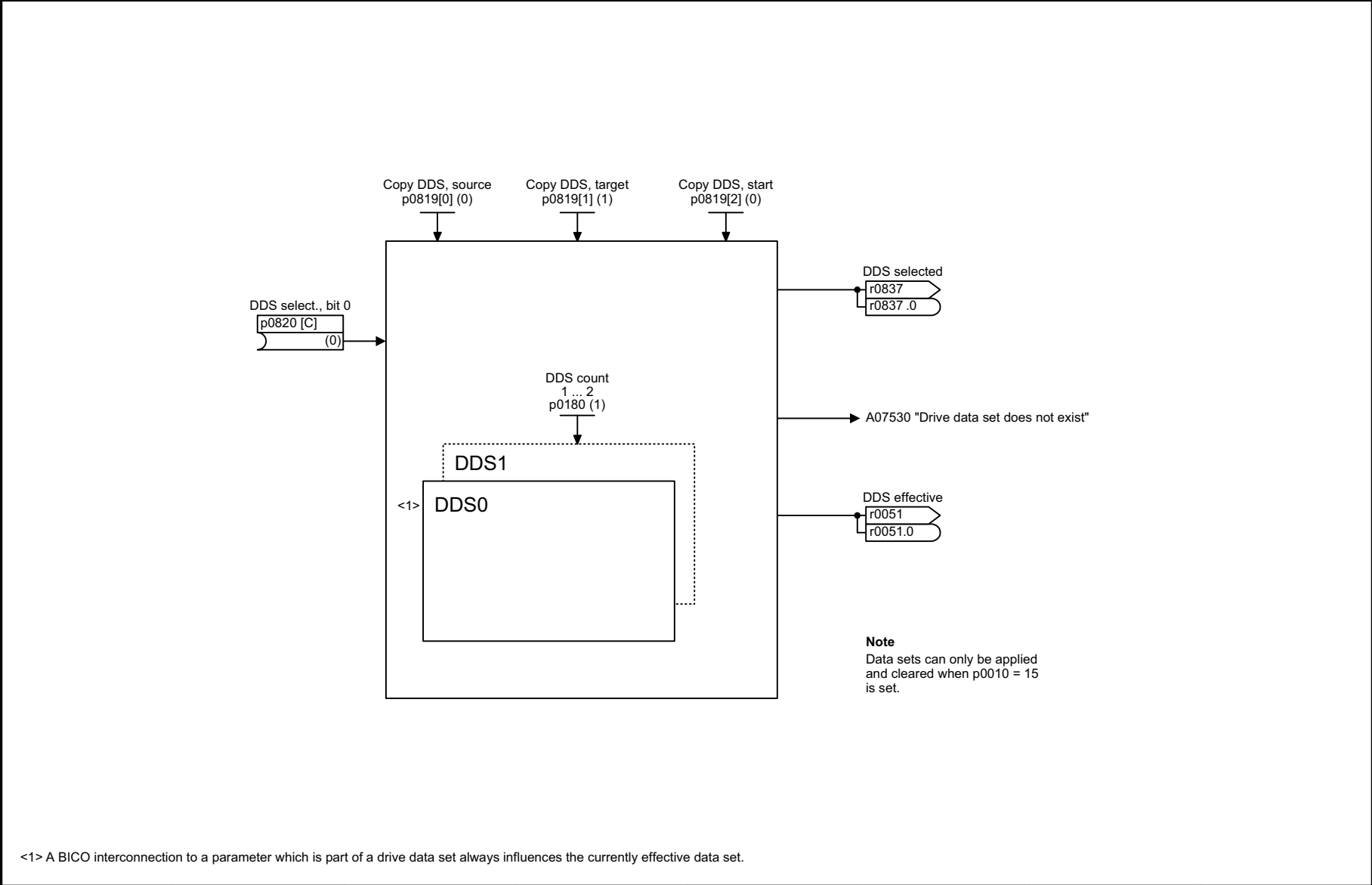


Fig. 3-135 8560 – Command Data Sets (CDS)



1	2	3	4	5	6	7	8
Data sets					fp_8565_97_05.vsd	Function diagram	
Drive Data Sets (DDS)					11.03.2015 V4.7.3	SINAMICS G120C	

Fig. 3-136 8565 – Drive Data Sets (DDS)

Faults and alarms

Content

4.1	Overview of faults and alarms	518
4.2	List of faults and alarms	529

4.1 Overview of faults and alarms

4.1.1 General

Display of faults/alarms (messages)

In the case of a fault, the drive signals the corresponding fault(s) and/or alarm(s).

For example, the following methods for displaying faults and alarms are available:

- Display via the fault and alarm buffer with PROFIBUS/PROFINET
- Display online via the commissioning software
- Display and operating unit (e.g. BOP, AOP)

Differences between faults and alarms

The differences between faults and alarms are as follows:

Table 4-1 Differences between faults and alarms

Type	Description
Faults	<p>What happens when a fault occurs?</p> <ul style="list-style-type: none"> • The appropriate fault response is triggered. • Status signal ZSW1.3 is set. • The fault is entered in the fault buffer. <p>How are faults eliminated?</p> <ul style="list-style-type: none"> • Remove the original cause of the fault. • Acknowledge the fault.
Alarms	<p>What happens when an alarm occurs?</p> <ul style="list-style-type: none"> • Status signal ZSW1.7 is set. • The alarm is entered into the alarm buffer. <p>How are alarms eliminated?</p> <ul style="list-style-type: none"> • Alarms acknowledge themselves. If the cause of the alarm is no longer present, they automatically reset themselves.

Fault reactions

The following fault reactions are defined:

Table 4-2 Fault reactions

List	PROFIdrive	Reaction	Description
NONE	-	None	<p>No response when a fault occurs.</p> <p>Note</p> <p>With "Basic positioner" (r0108.4 = 1), the following applies: When a fault occurs with fault reaction "NONE", an active traversing task is interrupted and the system switches to tracking mode until the fault has been rectified and acknowledged.</p>
OFF1	ON/ OFF	Brake along the ramp-function generator down ramp followed by pulse inhibit	<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 ramp-function generator ramp down (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>Torque control (p1300 = 22, 23)</p> <ul style="list-style-type: none"> The following applies for closed-loop torque control: Reaction as for OFF2. When the system switches to closed-loop torque control with p1501, the following applies: No separate braking reaction. <p>If the actual speed value drops below the speed threshold (p1226) or the timer stage (p1227) has expired, the motor holding brake (if one is being used) is closed. The pulses are suppressed when the brake application time (p1217) expires.</p>
OFF1_ DELAYED	-	As for OFF1, however delayed	<p>Faults with this fault response only become effective after the delay time in p3136 has expired.</p> <p>The remaining time up to OFF1 is displayed in r3137.</p>
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. Switching on inhibited is activated.

Table 4-2 Fault reactions, continued

List	PROFIdrive	Reaction	Description
OFF3	QUICK STOP	Brake along the OFF3 down 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 ramp down (p1135). When zero speed is detected, the motor holding brake (if parameterized) is closed. The pulses are suppressed when the holding brake's closing 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> <ul style="list-style-type: none"> Switching on inhibited is activated. <p>Torque control (p1300 = 22, 23)</p> <ul style="list-style-type: none"> Changeover to speed-controlled operation and other reactions as described for speed-controlled operation.
STOP2	-	n_set = 0	<ul style="list-style-type: none"> n_set = 0 is input immediately to brake the drive along the OFF3 ramp down (p1135). The drive remains in closed-loop speed control.
IASC/ DCBRAKE	-	-	<ul style="list-style-type: none"> For synchronous motors, the following applies: If a fault occurs with this fault reaction, an internal armature short-circuit is triggered. The conditions for p1231 = 4 must be observed. For induction motors, the following applies: If a fault occurs with this fault reaction, DC braking is triggered. DC braking must have been commissioned (p1230 to p1239).
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> <p>Notice</p> <p>When changing p0491, it is imperative that the information in the description of this parameter is carefully observed.</p>

Acknowledging faults

The list of faults and alarms specifies how to acknowledge each fault after the cause has been eliminated.

Table 4-3 Acknowledging faults

Acknowledgment	Description						
POWER ON	<p>The fault is acknowledged by a POWER ON (switch drive unit off and on again).</p> <p>Note If this action has not removed the fault cause, the fault is displayed again immediately after power up.</p>						
IMMEDIATELY	<p>Faults can be acknowledged on one drive object (Points 1 to 3) or on all drive objects (Point 4) as follows:</p> <p>1 Set acknowledgment by parameter: p3981 = 0 --> 1</p> <p>2 Acknowledging via binector inputs:</p> <table border="0"> <tr> <td>p2103</td> <td>BI: 1. Acknowledge faults</td> </tr> <tr> <td>p2104</td> <td>BI: 2. Acknowledge faults</td> </tr> <tr> <td>p2105</td> <td>BI: 3. Acknowledge faults</td> </tr> </table> <p>3 Acknowledging using a PROFIBUS control signal: STW1.7 = 0 --> 1 (edge)</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 will continue to be displayed after acknowledgement. • Safety Integrated faults The "Safe Torque Off" (STO) function must be deselected before these faults are acknowledged. 	p2103	BI: 1. Acknowledge faults	p2104	BI: 2. Acknowledge faults	p2105	BI: 3. Acknowledge faults
p2103	BI: 1. Acknowledge faults						
p2104	BI: 2. Acknowledge faults						
p2105	BI: 3. Acknowledge faults						
PULSE SUPPRESSION	<p>The fault can only be acknowledged when the pulses are inhibited (r0899.11 = 0).</p> <p>The same options are available for acknowledging as described under IMMEDIATE acknowledgement.</p>						

4.1.2 Explanation of the list of faults and alarms

The data in the following example have been chosen at random. The information listed below is the maximum amount of information that a description can contain. Some of the information is optional.

The "List of faults and alarms" (Page 529) has the following layout:

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

Axxxxx (F, N)	Fault location (optional): Name
Message class:	Text of the message class (number according to PROFIdrive)
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.

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

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 message 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 message" or "Internal message"
- C means "Safety message"

The optional brackets indicate whether the type specified for this message can be changed and which message types can be adjusted via parameters (p2118, p2119).

Information on reaction and acknowledgment is specified independently for a message with an adjustable message type (e.g. reaction to F, acknowledgment for F).

Note

You can change the default properties of a fault or alarm by setting parameters.

References: /BA7/ SINAMICS G120 Operating Instructions
 SINAMICS G120C Frequency Converter,
 Section "Alarms, faults, and system messages"

The "List of faults and alarms" (Page 529) supplies information referred to the properties of a message set as default. If the properties of a specific message are changed, the corresponding 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 message number are all used to identify the message (e.g. with the commissioning software).

Message class:

For each message, specifies the associated message class with the following structure:

Text of the message class (number according to PROFIdrive)

The message classes are transferred at different interfaces to higher-level control systems and their associated display and operating units.

The message classes that are available are shown in Table "Message classes and coding of various diagnostic interfaces" (Page 524). In addition to the text of the message class and their number according to PROFIdrive – as well as a brief help text regarding the cause and remedy – they also include information about the various diagnostic interfaces:

- PN (hex)
Specifies the "Channel error type" of the PROFINET channel diagnostics.
When activating the channel diagnostics, using the GSDML file, the texts listed in the table can be displayed.
- DS1 (dec)
Specifies the bit number in data set DS1 of the diagnostic alarm for SIMATIC S7.
When the diagnostic alarms are activated, the texts listed in the table can be displayed.
- DP (dec)
Specifies the "Error type" of the channel-related diagnostics for PROFIBUS.
When the channel diagnostics are activated, the texts listed in the standard and the GSD file can be displayed.
- ET 200 (dec)
Specifies the "Error type" of the channel-related diagnostics for the SIMATIC ET 200pro FC-2 device.
When the channel diagnostics are activated, the texts listed in the standard and the GSD file of the ET 200pro can be displayed.
- NAMUR (r3113.x)
Specifies the bit number in parameter r3113.

For the interfaces DP, ET 200, NAMUR, in some instances, the message classes are combined.

4 Faults and alarms

4.1 Overview of faults and alarms

Table 4-4 Message classes and coding of various diagnostic interfaces

Text of the message class (number according to PROFIdrive) Cause and remedy.	Diagnostics interface				
	PN (hex)	DS1 (dec)	DP (dec)	ET 200 (dec)	NAMUR (r3113.x)
Hardware/software errors (1) A hardware or software malfunction was detected. Carry out a POWER ON for the relevant component. If it occurs again, contact the hotline.	9000	0	16	9	0
Line fault (2) A line supply fault has occurred (phase failure, voltage level ...). Check the line supply and fuses. Check the supply voltage. Check the wiring.	9001	1	17	24	1
Supply voltage fault (3) An electronics supply voltage fault (48 V, 24 V, 5 V ...) was detected. Check the wiring. Check the voltage level.	9002	2	2 ¹ 3 ²	2 ¹ 3 ²	15
DC-link overvoltage (4) The DC-link voltage has assumed an inadmissibly high value. Check the dimensioning of the system (line supply, reactor, voltages). Check the infeed settings.	9003	3	18	24	2
Power electronics fault (5) An impermissible operating state of the power electronics was detected (overcurrent, overtemperature, IGBT failure ...). Check compliance with the permissible load cycles. Check the ambient temperatures (fan).	9004	4	19	24	3
Overtemperature of the electronic component (6) The temperature in the component has exceeded the highest permissible limit. Check the ambient temperature / control cabinet ventilation.	9005	5	20	5	4
Ground fault / inter-phase short-circuit detected (7) A ground fault / inter-phase short-circuit was detected in the power cables or in the motor windings. Check the power cables (connection). Check the motor.	9006	6	21	20	5
Motor overload (8) The motor was operated outside the permissible limits (temperature, current, torque ...). Check the load cycles and set limits. Check the ambient temperature / motor cooling.	9007	7	22	24	6
Communication to the higher-level controller faulted (9) The communication to the higher-level controller (internal coupling, PROFIBUS, PROFINET ...) is faulted or interrupted. Check the state of the higher-level controller. Check the communication connection/-wiring. Check the bus configuration/cycles.	9008	8	23	19	7
Safety monitoring channel has detected an error (10) A safe operation monitoring function has detected an error.	9009	9	24	25	8
Actual position/speed value incorrect or not available (11) An illegal signal state was detected while evaluating the encoder signals (track signals, zero marks, absolute values ...). Check the encoder / state of the encoder signals. Observe the maximum permissible frequencies.	900A	10	25	29	9

Table 4-4 Message classes and coding of various diagnostic interfaces, continued

Text of the message class (number according to PROFIdrive) Cause and remedy.	Diagnostics interface				
	PN (hex)	DS1 (dec)	DP (dec)	ET 200 (dec)	NAMUR (r3113.x)
Internal (DRIVE-CLiQ) communication faulted (12) The internal communication between the SINAMICS components is faulted or interrupted. Check the DRIVE-CLiQ wiring. Ensure an EMC-compliant installation. Observe the maximum permissible quantity structures / cycles.	900B	11	26	31	10
Infeed fault (13) The infeed is faulty or has failed. Check the infeed and its environment (line supply, filters, reactors, fuses ...). Check the infeed control.	900C	12	27	24	11
Braking controller / Braking Module faulted (14) The internal or external Braking Module is faulted or overloaded (temperature). Check the connection/state of the Braking Module. Comply with the permissible number of braking operations and their duration.	900D	13	28	24	15
Line filter fault (15) The line filter monitoring has detected an excessively high temperature or another impermissible state. Check the temperature / temperature monitoring. Check the configuration to ensure that it is permissible (filter type, infeed, thresholds).	900E	14	17	24	15
External measured value / signal state outside of the permissible range (16) A measured value / signal state read in via the input area (digital/analog/temperature) has assumed an impermissible value/state. Identify and check the relevant signal. Check the set thresholds.	900F	15	29	26	15
Application / technological function faulty (17) The application / technological function has exceeded a (set) limit (position, velocity, torque ...). Identify and check the relevant limit. Check the setpoint specification of the higher-level controller.	9010	16	30	9	15
Error in the parameterization/configuration/commissioning procedure (18) An error was identified in the parameterization or in a commissioning procedure, or the parameterization does not match the actual device configuration. Determine the precise cause of the fault using the commissioning tool. Adapt the parameterization or device configuration.	9011	17	31	16	15
General drive fault (19) Group fault. Determine the precise cause of the fault using the commissioning tool.	9012	18	9	9	15
Auxiliary unit fault (20) The monitoring of an auxiliary unit (incoming transformer, cooling unit ...) has detected an illegal state. Determine the exact cause of the fault and check the relevant device.	9013	19	29	26	15

1. Undervoltage condition of the electronics power supply
2. Overvoltage condition of the electronics power supply

Reaction: Default fault reaction (adjustable fault reaction)

Specifies the default reaction in the event of a fault.

The optional parentheses indicate whether the default fault reactions can be changed and which fault reactions can be adjusted via parameters (p2100, p2101).

Note

See Table "Fault reactions" (Page 519)

Acknowledgment: Default acknowledgment (adjustable acknowledgment)

Specifies the default method of acknowledging faults after the cause has been eliminated.

The optional parentheses indicate whether the default acknowledgment can be changed and which acknowledgment can be adjusted via parameters (p2126, p2127).

Note

See Table "Acknowledging faults" (Page 521)

Cause:

Describes the possible causes of the fault or alarm. A fault or alarm value can also be specified (optional).

Fault value (r0949, format):

The fault value is entered in the fault buffer in r0949[0...63] and specifies additional, more precise information about a fault.

Alarm value (r2124, format):

The alarm value specifies additional, more precise information about an alarm.

The alarm value is entered in the alarm buffer in r2124[0...7] and specifies additional, more precise information about an alarm.

Remedy:

Describes the methods available for eliminating the cause of the active fault or alarm.



WARNING

In certain cases, service and maintenance personnel are responsible for choosing a suitable method for eliminating the cause of faults.

4.1.3 Number ranges of faults and alarms

Note

The following number ranges represent an overview of all faults and alarms used in the SINAMICS drive family.

The faults and alarms for the product described in this List Manual are described in detail in "List of faults and alarms" (Page 529).

Faults and alarms are organized into the following number ranges:

Table 4-5 Number ranges of faults and alarms

of	To	Area
1000	3999	Control Unit
4000	4999	Reserved
5000	5999	Power section
6000	6899	Infeed
6900	6999	Braking Module
7000	7999	Drive
8000	8999	Option Board
9000	12999	Reserved
13000	13020	Licensing
13021	13099	Reserved
13100	13102	Know-how protection
13103	19999	Reserved
20000	29999	OEM
30000	30999	DRIVE-CLiQ component power unit
31000	31999	DRIVE-CLiQ component encoder 1
32000	32999	DRIVE-CLiQ component encoder 2 Note Faults that occur are automatically output as an alarm if the encoder is parameterized as a direct measuring system and does not intervene in the motor control.
33000	33999	DRIVE-CLiQ component encoder 3 Note Faults that occur are automatically output as an alarm if the encoder is parameterized as a direct measuring system and does not intervene in the motor control.
34000	34999	Voltage Sensing Module (VSM)
35000	35199	Terminal Module 54F (TM54F)
35200	35999	Terminal Module 31 (TM31)
36000	36999	DRIVE-CLiQ Hub Module
37000	37999	HF Damping Module

Table 4-5 Number ranges of faults and alarms, continued

of	To	Area
40000	40999	Controller Extension 32 (CX32)
41000	48999	Reserved
49000	49999	SINAMICS GM/SM/GL
50000	50499	Communication Board (COMM BOARD)
50500	59999	OEM Siemens
60000	65535	SINAMICS DC MASTER (closed-loop DC current control)

4.2 List of faults and alarms

Product: SINAMICS G120C, Version: 4705500, Language: eng
Objects: G120C_CAN, G120C_DP, G120C_PN, G120C_USS

F01000	Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	An internal software error has occurred. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	<ul style="list-style-type: none">- evaluate fault buffer (r0945).- Carry out a POWER ON (power off/on) for all components.- if required, check the data on the non-volatile memory (e.g. memory card).- upgrade firmware to later version.- contact the Hotline.- replace the Control Unit.
F01001	FloatingPoint exception
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	An exception occurred during an operation with the FloatingPoint data type. The error may be caused by the basic system or an OA application (e.g., FBLOCKS, DCC). Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting. Note: Refer to r9999 for further information about this fault. r9999[0]: Fault number. r9999[1]: Program counter at the time when the exception occurred. r9999[2]: Cause of the FloatingPoint exception. Bit 0 = 1: Operation invalid Bit 1 = 1: Division by zero Bit 2 = 1: Overflow Bit 3 = 1: Underflow Bit 4 = 1: Inaccurate result
Remedy:	<ul style="list-style-type: none">- Carry out a POWER ON (power off/on) for all components.- check configuration and signals of the blocks in FBLOCKS.- check configuration and signals of DCC charts.- upgrade firmware to later version.- contact the Hotline.
F01002	Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	An internal software error has occurred. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	<ul style="list-style-type: none">- Carry out a POWER ON (power off/on) for all components.- upgrade firmware to later version.- contact the Hotline.

F01003	Acknowledgement delay when accessing the memory
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
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.
N01004 (F, A)	Internal software error
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	An internal software error has occurred. Fault value (r0949, hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	- read out diagnostics parameter (r9999). - contact the Hotline.
F01005	File upload/download error
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The upload or download of EEPROM data was unsuccessful. Fault value (r0949, interpret hexadecimal): yyxxxx hex: yy = component number, xxxx = fault cause xxxx = 000B hex = 11 dec: Power unit component has detected a checksum error. xxxx = 000F hex = 15 dec: The selected power unit will not accept the content of the EEPROM file. xxxx = 0011 hex = 17 dec: Power unit component has detected an internal access error. xxxx = 0012 hex = 18 dec: After several communication attempts, no response from the power unit component. xxxx = 008B hex = 140 dec: EEPROM file for the power unit component not available on the memory card. xxxx = 008D hex = 141 dec: An inconsistent length of the firmware file was signaled. It is possible that the download/upload has been interrupted. xxxx = 0090 hex = 144 dec: When checking the file that was loaded, the component detected a fault (checksum). It is possible that the file on the memory card is defective. xxxx = 0092 hex = 146 dec: This SW or HW does not support the selected function. xxxx = 009C hex = 156 dec: Component with the specified component number is not available (p7828). xxxx = Additional values: Only for internal Siemens troubleshooting.
Remedy:	Save a suitable firmware file or EEPROM file for upload or download in folder "/ee_sac/" on the memory card.

A01009 (N)	CU: Control module overtemperature
Message class:	Overtemperature of the electronic components (6)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The temperature (r0037[0]) of the control module (Control Unit) has exceeded the specified limit value.
Remedy:	<ul style="list-style-type: none"> - check the air intake for the Control Unit. - check the Control Unit fan. <p>Note:</p> <p>The alarm is automatically withdrawn once the limit value has been fallen below.</p>
F01010	Drive type unknown
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	An unknown drive type was found.
Remedy:	<ul style="list-style-type: none"> - replace Power Module. - carry out a POWER ON (power off/on). - upgrade firmware to later version. - contact the Hotline.
F01015	Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	<p>An internal software error has occurred.</p> <p>Fault value (r0949, interpret decimal):</p> <p>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 firmware to later version. - contact the Hotline.
A01016 (F)	Firmware changed
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>At least one firmware file in the directory was illegally changed on the non-volatile memory (memory card/device memory) with respect to the version when shipped from the factory.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>0: Checksum of one file is incorrect.</p> <p>1: File missing.</p> <p>2: Too many files.</p> <p>3: Incorrect firmware version.</p> <p>4: Incorrect checksum of the back-up file.</p>
Remedy:	<p>For the non-volatile memory for the firmware (memory card/device memory), restore the delivery condition.</p> <p>Note:</p> <p>The file involved can be read out using parameter r9925.</p> <p>The status of the firmware check is displayed using r9926.</p>
A01017	Component lists changed
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	On the memory 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, interpret decimal):

zyx dec: x = Problem, y = Directory, z = File name

x = 1: File does not exist.

x = 2: Firmware version of the file does not match the software version.

x = 3: File checksum is incorrect.

y = 0: Directory /SIEMENS/SINAMICS/DATA/

y = 1: Directory /ADDON/SINAMICS/DATA/

z = 0: File MOTARM.ACX

z = 1: File MOTSRM.ACX

z = 2: File MOTSLM.ACX

z = 3: File ENCDATA.ACX

z = 4: File FILTDATA.ACX

z = 5: File BRKDATA.ACX

z = 6: File DAT_BEAR.ACX

z = 7: File CFG_BEAR.ACX

Remedy: For the file on the memory card involved, restore the status originally supplied from the factory.

F01018 Booting has been interrupted several times

Message class: Hardware/software error (1)

Reaction: NONE

Acknowledge: POWER ON

Cause: Module booting was interrupted several times. As a consequence, the module boots with the factory setting.

Possible reasons for booting being interrupted:

- power supply interrupted.
- CPU crashed.
- parameterization invalid.

Remedy: - carry out a POWER ON (power off/on). After switching on, the module reboots from the valid parameterization (if available).

- restore the valid parameterization.

Examples:

a) Carry out a first commissioning, save, carry out a POWER ON (switch-off/switch-on).

b) Load another valid parameter backup (e.g. from the memory card), save, carry out a POWER ON (switch-off/switch-on).

Note:

If the fault situation is repeated, then this fault is again output after several interrupted boots.

A01019 Writing to the removable data medium unsuccessful

Message class: Hardware/software error (1)

Reaction: NONE

Acknowledge: NONE

Cause: The write access to the removable data medium was unsuccessful.

Remedy: Remove and check the removable data medium. Then run the data backup again.

A01020 Writing to RAM disk unsuccessful

Message class: Hardware/software error (1)

Reaction: NONE

Acknowledge: NONE

Cause: A write access to the internal RAM disk was unsuccessful.

Remedy: Adapt the file size for the system logbook to the internal RAM disk (p9930).

A01021	Removable data medium as USB data storage medium from the PC used
Message class:	General drive fault (19)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The removable data medium is used as USB data storage medium from a PC</p> <p>As a consequence, the drive cannot access the removable data medium. When backing up, the configuration data cannot be saved on the removable data medium.</p> <p>Fault value (r0949, interpret decimal):</p> <p>1: The know-how protection as well as the copy protection for the removable data medium is active. Backup is inhibited.</p> <p>2: The configuration data are only backed up in the Control Unit.</p> <p>See also: r7760 (Write protection/know-how protection status), r9401 (Safely remove memory card status)</p>
Remedy:	<p>Deactivate the USB connection to the PC and back up the configuration data.</p> <p>Note:</p> <p>The alarm is automatically canceled when disconnecting the USB connection or when removing the removable data medium.</p> <p>See also: r9401 (Safely remove memory card status)</p>
F01023	Software timeout (internal)
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>An internal software timeout has occurred.</p> <p>Fault value (r0949, interpret decimal):</p> <p>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 firmware to later version. - contact the Hotline.
A01028 (F)	Configuration error
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The parameterization that was downloaded was generated with a different module type (Order No., MLFB).
Remedy:	Save parameters in a non-volatile fashion (p0971 = 1).
F01030	Sign-of-life failure for master control
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF3 (IASC/DCBRK, NONE, OFF1, OFF2, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	<p>For active PC master control, no sign-of-life was received within the monitoring time.</p> <p>The master control was returned to the active BICO interconnection.</p>
Remedy:	<p>Set the monitoring time higher at the PC or, if required, completely disable the monitoring function.</p> <p>For the commissioning software, the monitoring time is set as follows:</p> <p><Drive> -> Commissioning -> Control panel -> Button "Fetch master control" -> A window is displayed to set the monitoring time in milliseconds.</p> <p>Notice:</p> <p>The monitoring time should be set as short as possible. A long monitoring time means a late response when the communication fails!</p>

F01033	Units changeover: Reference parameter value invalid
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>When changing over the units to the referred representation type, it is not permissible for any of the required reference parameters to be equal to 0.0</p> <p>Fault value (r0949, parameter):</p> <p>Reference parameter whose value is 0.0.</p> <p>See also: p0505 (Selecting the system of units), p0595 (Technological unit selection)</p>
Remedy:	<p>Set the value of the reference parameter to a number different than 0.0.</p> <p>See also: p0304, p0305, p0310, p0596, p2000, p2001, p2002, p2003, r2004</p>
F01034	Units changeover: Calculation parameter values after reference value change unsuccessful
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>The change of a reference parameter meant that for an involved parameter the selected value was not able to be re-calculated in the per unit representation. The change was rejected and the original parameter value restored.</p> <p>Fault value (r0949, parameter):</p> <p>Parameter whose value was not able to be re-calculated.</p> <p>See also: p0304, p0305, p0310, p0596, p2000, p2001, p2002, p2003, r2004</p>
Remedy:	<p>- Select the value of the reference parameter such that the parameter involved can be calculated in the per unit representation.</p> <p>- Technology unit selection (p0595) before changing the reference parameter p0596, set p0595 = 1.</p>
A01035 (F)	ACX: Parameter back-up file corrupted
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>When the Control Unit is 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.</p> <p>It is possible that the backup was interrupted by switching off or withdrawing the memory card.</p> <p>Alarm value (r2124, interpret hexadecimal):</p> <p>ddccbbaa hex:</p> <p>aa = 01 hex:</p> <p>Power up was realized without data backup. The drive is in the factory setting.</p> <p>aa = 02 hex:</p> <p>The last available internal backup data record was loaded. The parameterization must be checked. It is recommended that the parameterization is downloaded again.</p> <p>aa = 03 hex:</p> <p>The last available data record from the memory card was loaded. The parameterization must be checked.</p> <p>aa = 04 hex:</p> <p>An invalid data backup was loaded from the memory card into the drive. The drive is in the factory setting.</p> <p>dd, cc, bb:</p> <p>Only for internal Siemens troubleshooting.</p> <p>See also: p0971 (Save parameters)</p>
Remedy:	<p>- Download the project again with the commissioning software.</p> <p>- save all parameters (p0971 = 1 or "copy RAM to ROM").</p>

F01036 (A)	ACX: Parameter back-up file missing
Message class:	Hardware/software error (1)
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	<p>When downloading the device parameterization, a parameter back-up file PSxxxxxyy.ACX associated with a drive object cannot be found.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>Byte 1: yyy in the file name PSxxxxxyy.ACX</p> <p>yyy = 000 --> consistency back-up file</p> <p>yyy = 001 ... 062 --> drive object number</p> <p>yyy = 099 --> PROFIBUS parameter back-up file</p> <p>Byte 2, 3, 4:</p> <p>Only for internal Siemens troubleshooting.</p>
Remedy:	<p>If you have saved the project data using the commissioning software, carry out a new download for your project.</p> <p>Save using the function "Copy RAM to ROM" or with p0971 = 1</p> <p>This means that the parameter files are again completely written into the non-volatile memory.</p> <p>Note:</p> <p>If the project data have not been backed up, then a new first commissioning is required.</p>
F01038 (A)	ACX: Loading the parameter back-up file unsuccessful
Message class:	Hardware/software error (1)
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	<p>An error has occurred when downloading PSxxxxxyy.ACX or PTxxxxxyy.ACX files from the non-volatile memory.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>Byte 1: yyy in the file name PSxxxxxyy.ACX</p> <p>yyy = 000 --> consistency back-up file</p> <p>yyy = 001 ... 062 --> drive object number</p> <p>yyy = 099 --> PROFIBUS parameter back-up file</p> <p>Byte 2:</p> <p>255: Incorrect drive object type.</p> <p>254: Topology comparison unsuccessful -> drive object type was not able to be identified.</p> <p>Reasons could be:</p> <ul style="list-style-type: none"> - Incorrect component type in the actual topology - Component does not exist in the actual topology. - Component not active. <p>Additional values:</p> <p>Only for internal Siemens troubleshooting.</p> <p>Byte 4, 3:</p> <p>Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - If you have saved the project data using the commissioning software, download the project again. Save using the function "Copy RAM to ROM" or with p0971 = 1 so that all of the parameter files are again completely written to the non-volatile memory. - replace the memory card or Control Unit.
F01039 (A)	ACX: Writing to the parameter back-up file was unsuccessful
Message class:	Hardware/software error (1)
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	<p>Writing to at least one parameter back-up file PSxxxxxyy.*** in the non-volatile memory was unsuccessful.</p> <ul style="list-style-type: none"> - In the directory /USER/SINAMICS/DATA/ at least one parameter back-up file PSxxxxxyy.*** has the "read only" file attribute and cannot be overwritten. - There is not sufficient free memory space available. - The non-volatile memory is defective and cannot be written to.

Fault value (r0949, interpret hexadecimal):
 dcba hex
 a = yyy in the file names PSxxxxyy.***
 a = 000 --> consistency back-up file
 a = 001 ... 062 --> drive object number
 a = 099 --> PROFIBUS parameter back-up file
 b = xxx in the file names PSxxxxyy.***
 b = 000 --> data save started with p0971 = 1
 b = 010 --> data save started with p0971 = 10
 b = 011 --> data save started with p0971 = 11
 b = 012 --> data save started with p0971 = 12
 d, c:

Only for internal Siemens troubleshooting.

Remedy:

- check the file attribute of the files (PSxxxxyy.***, CAxxxxyy.***, CCxxxxyy.***) and, if required, change from "read only" to "writeable".
- check the free memory space in the non-volatile memory. Approx. 80 kbyte of free memory space is required for every drive object in the system.
- replace the memory card or Control Unit.

F01040 Save parameter settings and carry out a POWER ON

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF2
Acknowledge: POWER ON
Cause: A parameter has been changed that requires the parameters to be backed up and the Control Unit to be switched OFF and ON again.
Remedy:

- Save parameters (p0971).
- carry out a POWER ON (power off/on) for the Control Unit.

F01042 Parameter error during project download

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF2 (NONE, OFF1, OFF3)
Acknowledge: IMMEDIATELY
Cause: An error was detected when downloading a project using the commissioning software (e.g. incorrect parameter value).
 For the specified parameter, it was detected that dynamic limits were exceeded that may possibly depend on other parameters.
 Fault value (r0949, interpret hexadecimal):
 ccbbaaaa hex
 aaaa = Parameter
 bb = Index
 cc = fault cause
 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 available.
 17: Task cannot be executed due to operating state.
 20: Illegal value.
 21: Response too long.
 22: Parameter address illegal.

23: Format illegal.
24: Number of values not consistent.
108: Unit unknown.
Additional values:
Only for internal Siemens troubleshooting.

Remedy:

- enter the correct value in the specified parameter.
- identify the parameter that restricts the limits of the specified parameter.

F01043

Fatal error at project download

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF2 (OFF1, OFF3)
Acknowledge: IMMEDIATELY
Cause: A fatal error was detected when downloading a project using the commissioning software.
Fault value (r0949, interpret decimal):
1: Device status cannot be changed to Device Download (drive object ON?).
2: Incorrect drive object number.
8: Maximum number of drive objects that can be generated exceeded.
11: Error while generating a drive object (global component).
12: Error while generating a drive object (drive component).
13: Unknown drive object type.
14: Drive status cannot be changed to "ready for operation" (r0947 and r0949).
15: Drive status cannot be changed to drive download.
16: Device status cannot be changed to "ready for operation".
18: A new download is only possible if the factory settings are restored for the drive unit.
20: The configuration is inconsistent.
21: Error when accepting the download parameters.
22: SW-internal download error.
100: The download was canceled, because no write requests were received from the commissioning client (e.g. for communication error).
Additional values:
Only for internal Siemens troubleshooting.

Remedy:

- use the current version of the commissioning software.
- modify the offline project and download again (e.g. compare the motor and Power Module in the offline project and on the drive).
- change the drive state (is a drive rotating or is there a message/signal?).
- carefully note any other messages/signals and remove their cause.
- boot from previously saved files (switch-off/switch-on or p0970).

F01044

CU: Descriptive data error

Message class: Hardware/software error (1)
Reaction: OFF2
Acknowledge: POWER ON
Cause: An error was detected when loading the descriptive data saved in the non-volatile memory.
Remedy: Replace the memory card or Control Unit.

A01045

Configuring data invalid

Message class: Hardware/software error (1)
Reaction: NONE
Acknowledge: NONE
Cause: An error was detected when evaluating the parameter files PSxxxxxyy.ACX, PTxxxxxyy.ACX, CAxxxxxyy.ACX, or CCxxxxxyy.ACX saved in the non-volatile memory. Because of this, under certain circumstances, several of the saved parameter values were not able to be accepted. Also see r9406 up to r9408.
Alarm value (r2124, interpret hexadecimal):
Only for internal Siemens troubleshooting.

Remedy:

- Check the parameters displayed in r9406 up to r9408, and correct these if required.
- Restore the factory setting using (p0970 = 1) and re-load the project into the drive unit.

Then save the parameterization in STARTER using the "Copy RAM to ROM" function or with p0971 = 1. This overwrites the incorrect parameter files in the non-volatile memory – and the alarm is withdrawn.

See also: r9406 (PS file parameter number parameter not transferred), r9407 (PS file parameter index parameter not transferred), r9408 (PS file fault code parameter not transferred)

A01049	It is not possible to write to file
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	It is not possible to write into a write-protected file (PSxxxxx.acx). The write request was interrupted. Alarm value (r2124, interpret decimal): Drive object number.
Remedy:	Check whether the "write protected" attribute has been set for the files in the non-volatile memory under .../USER/SINAMICS/DATA/... When required, remove write protection and save again (e.g. set p0971 to 1).
F01054	CU: System limit exceeded
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	At least one system overload has been identified. Fault value (r0949, interpret decimal): 1: Computing time load too high (r9976[1]). 5: Peak load too high (r9976[5]). Note: As long as this fault is present, it is not possible to save the parameters (p0971). See also: r9976 (System utilization)
Remedy:	Re fault value = 1, 5: - reduce the computing time load of the drive unit (r9976[1] and r9976[5]) to under 100 %. - check the sampling times and adjust if necessary (p0115, p0799, p4099). - de-activate function modules. - de-activate drive objects. - remove drive objects from the target topology. - note the DRIVE-CLiQ topology rules and if required, change the DRIVE-CLiQ topology. When using the Drive Control Chart (DCC) or free function blocks (FBLOCKS), the following applies: - the computing time load of the individual run-time groups on a drive object can be read out in r21005 (DCC) or r20005 (FBLOCKS). - if necessary, the assignment of the run-time group (p21000, p20000) can be changed in order to increase the sampling time (r21001, r20001). - if necessary, reduce the number of cyclically calculated blocks (DCC) and/or function blocks (FBLOCKS).
A01064 (F)	CU: Internal error (CRC)
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	CRC error in the Control Unit program memory
Remedy:	- Carry out a POWER ON (power off/on) for all components. - upgrade firmware to later version. - contact the Hotline.
A01066	Buffer memory: 70% fill level reached or exceeded
Message class:	General drive fault (19)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The non-volatile buffer memory for parameter changes is filled to at least 70%. This can also occur if the buffer memory is active (p0014 = 1) and parameters are continually changed via a fieldbus system.

Remedy: If required, de-activate and clear the buffer memory (p0014 = 0).
If required, clear the buffer memory (p0014 = 2).
In the following cases, the entries in the buffer memory are transferred into the ROM and then the buffer memory is cleared:
- p0971 = 1
- power down/power up the Control Unit

A01067 Buffer memory: 100 % fill level reached
Message class: General drive fault (19)
Reaction: NONE
Acknowledge: NONE
Cause: The non-volatile buffer memory for parameter changes is filled to 100%.
All additional parameter changes will no longer be taken into account in the non-volatile buffer memory. However, parameter changes can still be made in the volatile memory (RAM).
This can also occur if the buffer memory is active (p0014 = 1) and parameters are continually changed via a fieldbus system.
Remedy: If required, de-activate and clear the buffer memory (p0014 = 0).
If required, clear the buffer memory (p0014 = 2).
In the following cases, the entries in the buffer memory are transferred into the ROM and then the buffer memory is cleared:
- p0971 = 1
- power down/power up the Control Unit

F01068 CU: Data memory memory overflow
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The utilization for a data memory area is too large.
Fault value (r0949, interpret binary):
Bit 0 = 1: High-speed data memory 1 overloaded
Bit 1 = 1: High-speed data memory 2 overloaded
Bit 2 = 1: High-speed data memory 3 overloaded
Bit 3 = 1: High-speed data memory 4 overloaded
Remedy: - de-activate the function module.
- de-activate drive object.
- remove the drive object from the target topology.

A01069 Parameter backup and device incompatible
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The parameter backup on the memory card and the drive unit do not match.
The module boots with the factory settings.
Example:
Devices A and B. are not compatible and a memory card with the parameter backup for device A is inserted in device B.
Remedy: - insert a memory card with compatible parameter backup and carry out a POWER ON.
- insert a memory card without parameter backup and carry out a POWER ON.
- If required, withdraw the memory card and carry out POWER ON.
- save the parameters (p0971 = 1).

F01072	Memory card restored from the backup copy
Message class:	General drive fault (19)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The Control Unit was switched-off while writing to the memory card. This is why the visible partition became defective. After switching on, the data from the non-visible partition (backup copy) were written to the visible partition.
Remedy:	Check that the firmware and parameterization is up-to-date.
A01073 (N)	POWER ON required for backup copy on memory card
Message class:	General drive fault (19)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The parameter assignment on the visible partition of the memory card has changed. In order that the backup copy on the memory card is updated on the non-visible partition, it is necessary to carry out a POWER ON or hardware reset (p0972) of the Control Unit. Note: It is possible that a new POWER ON is requested via this alarm (e.g. after saving with p0971 = 1).
Remedy:	- carry out a POWER ON (power off/on) for the Control Unit. - carry out a hardware reset (RESET button, p0972).
F01105 (A)	CU: Insufficient memory
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF1
Acknowledge:	POWER ON
Cause:	Too many data sets are configured on this Control Unit. Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	- reduce the number of data sets.
F01107	Save to memory card unsuccessful
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A data save to the memory card was not able to be successfully carried out. - Memory card is defective. - Insufficient space on memory card. Fault value (r0949, interpret 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 could not be created on the memory card. 4: A new file could not be created on the memory card. 5: A new file could not be written on the memory card.
Remedy:	- try to save again. - replace the memory card or Control Unit.
F01112	CU: Power unit not permissible
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The connected power unit cannot be used together with this Control Unit. Fault value (r0949, interpret decimal): 1: Power unit is not supported (e.g. PM340).
Remedy:	Replace the power unit that is not permissible by a component that is permissible.

F01120 (A) Terminal initialization has failed

Message class: Hardware/software error (1)
Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: An internal software error occurred while the terminal functions were being initialized.
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.
Remedy:
- Carry out a POWER ON (power off/on) for all components.
- upgrade firmware to later version.
- contact the Hotline.
- replace the Control Unit.

F01122 (A) Frequency at the measuring probe input too high

Message class: Application/technological function faulted (17)
Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: The frequency of the pulses at the measuring probe input is too high.
Fault value (r0949, interpret decimal):
1: DI 1 (term. 6)
2: DI 3 (term. 8)
Remedy: Reduce the frequency of the pulses at the measuring probe input.

F01152 CU: Invalid constellation of drive object types

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: POWER ON
Cause: It is not possible to simultaneously operate drive object types SERVO, VECTOR and HLA.
A maximum of 2 of these drive object types can be operated on a Control Unit.
Remedy:
- power down the unit.
- restrict the use of drive object types SERVO, VECTOR, HLA to a maximum of 2.
- re-commission the unit.

F01205 CU: Time slice overflow

Message class: Hardware/software error (1)
Reaction: OFF2
Acknowledge: POWER ON
Cause: Insufficient computation time.
Fault value (r0949, interpret hexadecimal):
Only for internal Siemens troubleshooting.
Remedy: Contact the Hotline.

F01250 CU: CU-EEPROM incorrect read-only data

Message class: Hardware/software error (1)
Reaction: NONE (OFF2)
Acknowledge: POWER ON
Cause: Error when reading the read-only data of the EEPROM in the Control Unit.
Fault value (r0949, interpret decimal):
Only for internal Siemens troubleshooting.
Remedy:
- carry out a POWER ON.
- replace the Control Unit.

A01251	CU: CU-EEPROM incorrect read-write data
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	Error when reading the read-write data of the EEPROM in the Control Unit. Alarm value (r2124, interpret 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: - clear the fault memory (p0952 = 0). - replace the Control Unit.
F01257	CU: Firmware version out of date
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	The Control Unit firmware is too old. Fault value (r0949, interpret hexadecimal): bbbbbbaa hex: aa = unsupported component aa = 01 hex = 1 dec: The firmware being used does not support the Control Unit. aa = 02 hex = 2 dec: The firmware being used does not support the Control Unit. aa = 03 hex = 3 dec: The firmware being used does not support the Power Module. aa = 04 hex = 4 dec: The firmware being used does not support the Control Unit.
Remedy:	For fault value = 1, 2, 4: - Upgrade the firmware of the Control Unit. For fault value = 3: - Upgrade the firmware of the Control Unit. - Replace the Power Module by a component that is supported.
F01340	Topology: Too many components on one line
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
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 Control Unit is not sufficient for all read transfers. 2yy: The communications clock cycle of the DRIVE-CLiQ connection on the Control Unit is not sufficient for all write transfers. 3yy: Cyclic communication is fully utilized. 4yy: The DRIVE-CLiQ cycle starts before the earliest end of the application. An additional dead time must be added to the control. Sign-of-life errors can be expected. The conditions of operation with a current controller sampling time of 31.25 µs have not been maintained.

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.

8yy:
The component clock cycles cannot be combined with one another

900:
The lowest common multiple of the clock cycles in the system is too high to be determined.

901:
The lowest common multiple of the clock cycles in the system cannot be generated with the hardware.

Remedy:

- check the DRIVE-CLiQ wiring.
- Reduce the number of components on the DRIVE-CLiQ line involved and distribute these to other DRIVE-CLiQ sockets of the Control Unit. This means that communication is uniformly distributed over several lines.

Re fault value = 1yy - 4yy in addition:

- increase the sampling times (p0112, p0115, p4099). If necessary, for DCC or FBLOCKS, change the assignment of the run-time group (p21000, p20000) so that the sampling time (r21001, r20001) is increased.
- if necessary, reduce the number of cyclically calculated blocks (DCC) and/or function blocks (FBLOCKS).
- reduce the function modules (r0108).
- establish the conditions for operation with a current controller sampling time of 31.25 µs (at the DRIVE-CLiQ line, only operate Motor Modules and Sensor Modules with this sampling time and only use a permitted Sensor Module (e.g. SMC20, this means a 3 at the last position of the order number)).
- For an NX, the corresponding Sensor Module for a possibly existing second measuring system should be connected to a free DRIVE-CLiQ socket of the NX.

Re fault value = 8yy in addition:

- check the clock cycles settings (p0112, p0115, p4099). Clock cycles on a DRIVE-CLiQ line must be perfect integer multiples of one another. As clock cycle on a line, all clock cycles of all drive objects in the previously mentioned parameters apply, which have components on the line involved.

Re fault value = 9yy in addition:

- check the clock cycles settings (p0112, p0115, p4099). The lower the numerical value difference between two clock cycles, the higher the lowest common multiple. This behavior has a significantly stronger influence, the higher the numerical values of the clock cycles.

F01505 (A)

BICO: Interconnection cannot be established

Message class: Error in the parameterization / configuration / commissioning procedure (18)

Reaction: NONE

Acknowledge: IMMEDIATELY

Cause: A PROFIdrive telegram has been set (p0922).
An interconnection contained in the telegram was not able to be established.
Fault value (r0949, interpret decimal):
Parameter receiver that should be changed.

Remedy: Establish another interconnection.

F01510

BICO: Signal source is not float type

Message class: Error in the parameterization / configuration / commissioning procedure (18)

Reaction: NONE

Acknowledge: IMMEDIATELY

Cause: The requested connector output does not have the correct data type. This interconnection is not established.
Fault value (r0949, interpret 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 with different scalings
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>The requested BICO interconnection was established. However, a conversion is made between the BICO output and BICO input using the reference values.</p> <ul style="list-style-type: none">- the BICO output has different normalized units than the BICO input.- message only for interconnections within a drive object. <p>Example:</p> <p>The BICO output has, as normalized unit, voltage and the BICO input has current.</p> <p>This means that the factor p2002/p2001 is calculated between the BICO output and the BICO input.</p> <p>p2002: contains the reference value for current</p> <p>p2001: contains the reference value for voltage</p> <p>Fault value (r0949, interpret decimal):</p> <p>Parameter number of the BICO input (signal sink).</p>
Remedy:	Not necessary.
F01512	BICO: No scaling available
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	<p>An attempt was made to determine a conversion factor for a scaling that does not exist.</p> <p>Fault value (r0949, interpret decimal):</p> <p>Unit (e.g. corresponding to SPEED) for which an attempt was made to determine a factor.</p>
Remedy:	Apply scaling or check the transfer value.
F01513 (N, A)	BICO: Interconnection cross DO with different scalings
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>The requested BICO interconnection was established. However, a conversion is made between the BICO output and BICO input using the reference values.</p> <p>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.</p> <p>Example 1:</p> <p>BICO output with voltage normalized unit, BICO input with current normalized unit, BICO output and BICO input lie in different drive objects. This means that the factor p2002/p2001 is calculated between the BICO output and the BICO input.</p> <p>p2002: contains the reference value for current</p> <p>p2001: contains the reference value for voltage</p> <p>Example 2:</p> <p>BICO output with voltage normalized unit in drive object 1 (DO1), BICO input with voltage normalized unit in drive object 2 (DO2). The reference values for voltage (p2001) of the two drive objects have different values. This means that the factor p2001(DO1)/p2001(DO2) is calculated between the BICO output and the BICO input.</p> <p>p2001: contains the reference value for voltage, drive objects 1, 2</p> <p>Fault value (r0949, interpret decimal):</p> <p>Parameter number of the BICO input (signal sink).</p>
Remedy:	Not necessary.
A01514 (F)	BICO: Error when writing during a reconnect
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	During a reconnect operation (e.g. while booting or downloading - but can also occur in normal operation) a parameter was not able to be written to.

Example:

When writing to BICO input with double word format (DWORD), in the second index, the memory areas overlap (e.g. p8861). The parameter is then reset to the factory setting.

Alarm value (r2124, interpret decimal):

Parameter number of the BICO input (signal sink).

Remedy: Not necessary.

F01515 (A) BICO: Writing to parameter not permitted as the master control is active

Message class: Error in the parameterization / configuration / commissioning procedure (18)

Reaction: NONE

Acknowledge: IMMEDIATELY

Cause: When changing the number of CDS or when copying from CDS, the master control is active.

Remedy: If required, return the master control and repeat the operation.

A01590 (F) Drive: Motor maintenance interval expired

Message class: General drive fault (19)

Reaction: NONE

Acknowledge: NONE

Cause: The selected service/maintenance interval for this motor was reached.

Alarm value (r2124, interpret 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.

F01600 SI P1 (CU): STOP A initiated

Message class: Safety monitoring channel has identified an error (10)

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive-integrated "Safety Integrated" function on processor 1 has detected an error and initiated a STOP A.

- forced checking procedure (test stop) of the safety shutdown path on processor 1 unsuccessful.

- subsequent response to fault F01611 (defect in a monitoring channel).

Fault value (r0949, interpret decimal):

0: Stop request from processor 2.

1005: Pulses suppressed although STO not selected and there is no internal STOP A present.

1010: Pulses enabled although STO is selected or an internal STOP A is present.

1011: Internal fault for the pulse enable in the Power Module.

9999: Subsequent response to fault F01611.

Remedy: - select Safe Torque Off and de-select again.

- Carry out a POWER ON (power off/on) for all components.

- replace Power Module involved.

For fault value = 9999:

- carry out diagnostics for fault F01611.

Note:

PM: Power Module

STO: Safe Torque Off

F01611 (A) SI P1 (CU): Defect in a monitoring channel

Message class: Safety monitoring channel has identified an error (10)

Reaction: NONE (OFF1, OFF2, OFF3)

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The drive-integrated "Safety Integrated" function on processor 1 has detected a fault in the crosswise data comparison between the two monitoring channels and has initiated a STOP F.

Fault F01600 (SI P1: STOP A initiated) is output as a consequence of this fault.

Fault value (r0949, interpret decimal):

0: Stop request from processor 2.

1 ... 999:

Number of the cross-compared data that resulted in this fault. This number is also displayed in r9795.

2: SI enable safety functions (p9601, p9801). Crosswise data comparison is only carried out for the supported bits.

3: SI F-DI changeover discrepancy time (p9650, p9850).

8: SI PROFIsafe address (p9610, p9810).

9: SI debounce time for STO (p9651, p9851).

1000: Watchdog timer has expired.

Within the time of approx. 5 x p9650, alternatively, the following was defined:

- The signal at F-DI continually changed with time intervals less than or equal to the discrepancy time (p9650/p9850).

- Via PROFIsafe, STO (also as subsequent response) was continually selected and deselected with time intervals less than or equal to the discrepancy time (p9650/p9850).

1001, 1002: Initialization error, change timer / check timer.

1950: Module temperature outside the permissible temperature range.

1951: Module temperature not plausible.

2000: Status of the STO selection for both monitoring channels are different.

2001: Feedback signals of safe pulse suppression on the two monitoring channels are different.

2002: Statuses of the delay timer SS1 on both monitoring channels are different (status of the timer in p9650/p9850).

2003: Status of the STO terminal for both monitoring channels are different.

6000 ... 6166:

PROFIsafe fault values (PROFIsafe driver for PROFIBUS DP V1/V2 and PROFINET).

For these fault values, the failsafe control signals (failsafe values) are transferred to the safety functions.

6000: An internal software error has occurred (only for internal Siemens troubleshooting).

6064 ... 6071: Error when evaluating the F parameters. The values of the transferred F parameters do not match the expected values in the PROFIsafe driver.

6064: Destination address and PROFIsafe address are different (F_Dest_Add).

6065: Destination address not valid (F_Dest_Add).

6066: Source address not valid (F_Source_Add).

6067: Watchdog time not valid (F_WD_Time).

6068: Incorrect SIL level (F_SIL).

6069: Incorrect F-CRC length (F_CRC_Length).

6070: Incorrect F parameter version (F_Par_Version).

6071: CRC error for the F parameters (CRC1). The transferred CRC value of the F parameters does not match the value calculated in the PROFIsafe driver.

6072: F parameterization is inconsistent.

6165: A communications error was identified when receiving the PROFIsafe telegram. The fault may also occur if an inconsistent or out-of-date PROFIsafe telegram has been received after switching the Control Unit off and on or after plugging in the PROFIBUS/PROFINET cable.

6166: A time monitoring error (timeout) was identified when receiving the PROFIsafe telegram.

Remedy:

Re fault values 1 ... 999 described in "Cause":

- check the cross data comparison that resulted in a STOP F.

- carry out a POWER ON (power off/on).

For fault value = 1000:

- check the wiring of the F-DI (contact problems).

- PROFIsafe: Remove contact problems/faults at the PROFIBUS master/PROFINET controller.

- check the discrepancy time, and if required, increase the value (p9650/p9850).

Re fault value = 1001, 1002:

- carry out a POWER ON (power off/on).

Re fault value = 1950, 1951:

- Operate the Control Unit in the permissible temperature range.

- replace Control Unit.

For fault value = 2000, 2001, 2002, 2003:

- check the discrepancy time F-DI changeover and if required, increase the value (p9650/p9850).

- check the wiring of the F-DI (contact problems).

- check the causes of the STO selection in r9772.

For fault value = 6000:

- carry out a POWER ON (power off/on).
- upgrade firmware to later version.
- contact the Hotline.
- replace Control Unit.

For fault value = 6064:

- check the setting of the value in the F parameter F_Dest_Add at the PROFIsafe slave.
- check the setting of the PROFIsafe address on processor 1 (p9610) and on processor 2 (p9810).

For fault value = 6065:

- check the setting of the value in the F parameter F_Dest_Add at the PROFIsafe slave. It is not permissible for the destination address to be either 0 or FFFF!

For fault value = 6066:

- check the setting of the value in the F parameter F_Source_Add at the PROFIsafe slave. It is not permissible for the source address to be either 0 or FFFF!

For fault value = 6067:

- check the setting of the value in the F parameter F_WD_Time at the PROFIsafe slave. It is not permissible for the watch time to be 0!

For fault value = 6068:

- check the setting of the value in the F parameter F_SIL at the PROFIsafe slave. The SIL level must correspond to SIL2!

For fault value = 6069:

- check the setting of the value in the F parameter F_CRC_Length at the PROFIsafe slave. The setting of the CRC2 length is 2-byte CRC in the V1 mode and 3-byte CRC in the V2 mode!

For fault value = 6070:

- check the setting of the value in the F parameter F_Par_Version at the PROFIsafe slave. The value for the F parameter version is 0 in the V1 mode and 1 in the V2 mode!

For fault value = 6071:

- check the settings of the values of the F parameters and the F parameter CRC (CRC1) calculated from these at the PROFIsafe slave and, if required, update.

For fault value = 6072:

- check the settings of the values for the F parameters and, if required, correct.

The following combinations are permissible for F parameters F_CRC_Length and F_Par_Version:

F_CRC_Length = 2-byte CRC and F_Par_Version = 0

F_CRC_Length = 3-byte CRC and F_Par_Version = 1

For fault value = 6165:

- if the fault occurs after powering up or after inserting the PROFIBUS/PROFINET cable, acknowledge the fault.
- check the configuration and communication at the PROFIsafe slave.
- check the setting of the value for F parameter F_WD_Time on the PROFIsafe slave and increase if necessary.
- check whether all F parameters of the drive match the F parameters of the F host.

For fault value = 6166:

- check the configuration and communication at the PROFIsafe slave.
- check the setting of the value for F parameter F_WD_Time on the PROFIsafe slave and increase if necessary.
- evaluate diagnostic information in the F host.
- check PROFIsafe connection.
- check whether all F parameters of the drive match the F parameters of the F host.

Re fault values that are described in "Cause":

- carry out a POWER ON (power off/on).
- contact the Hotline.
- replace Control Unit.

Note:

F-DI: Failsafe Digital Input

STO: Safe Torque Off

N01620 (F, A)	SI P1 (CU): Safe Torque Off active
Message class:	Safety monitoring channel has identified an error (10)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The "Safe Torque Off" (STO) function has been selected on processor 1 using the input terminal and is active. Note: This message does not result in a safety stop response.
Remedy:	Not necessary. Note: STO: Safe Torque Off
F01625	SI P1 (CU): Sign-of-life error in safety data
Message class:	Internal (DRIVE-CLiQ) communication error (12)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-integrated "Safety Integrated" function on processor 1 has detected an error in the sign-of-life of the safety data and initiated a STOP A. - there is a communication error between processor 1 and processor 2 or communication has failed. - a time slice overflow of the safety software has occurred. Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	- select Safe Torque Off and de-select again. - carry out a POWER ON (power off/on). - check whether additional faults are present and if required, perform diagnostics. - check the electrical cabinet design and cable routing for EMC compliance
F01640	SI P1 (CU): component replacement identified and acknowledgment/save required
Message class:	General drive fault (19)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The "Safety Integrated" function integrated in the drive has identified that a component has been replaced. It is no longer possible to operate the drive. When safety functions are active, after a component has been replaced it is necessary to carry out a partial acceptance test. Fault value (r0949, interpret binary): Bit 0 = 1: It has been identified that the Control Unit has been replaced. Bit 1 = 1: It has been identified that the Motor Module/Hydraulic Module has been replaced. Bit 2 = 1: It has been identified that the Power Module has been replaced. Bit 3 = 1: It has been identified that the Sensor Module channel 1 has been replaced. Bit 4 = 1: It has been identified that the Sensor Module channel 2 has been replaced. Bit 5 = 1: It has been identified that the sensor channel 1 has been replaced. Bit 6 = 1: It has been identified that the sensor channel 2 has been replaced.
Remedy:	- acknowledge component replacement (p9702 = 29). - save all parameters (p0977 = 1 or p0971 = 1 or "copy RAM to ROM"). - acknowledge fault (e.g. BI: p2103). Note: In addition to the fault, diagnostics bits r9776.2 and r9776.3 are set. See also: r9776 (SI diagnostics)

F01641	SI P1 (CU): component replacement identified and save required
Message class:	General drive fault (19)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>The "Safety Integrated" function integrated in the drive has identified that a component has been replaced. No additional fault response is initiated, therefore operation of the particular drive is not restricted. When safety functions are active, after a component has been replaced it is necessary to carry out a partial acceptance test.</p> <p>Fault value (r0949, interpret binary):</p> <p>Bit 0 = 1: It has been identified that the Control Unit has been replaced.</p> <p>Bit 1 = 1: It has been identified that the Motor Module/Hydraulic Module has been replaced.</p> <p>Bit 2 = 1: It has been identified that the Power Module has been replaced.</p> <p>Bit 3 = 1: It has been identified that the Sensor Module channel 1 has been replaced.</p> <p>Bit 4 = 1: It has been identified that the Sensor Module channel 2 has been replaced.</p> <p>Bit 5 = 1: It has been identified that the sensor channel 1 has been replaced.</p> <p>Bit 6 = 1: It has been identified that the sensor channel 2 has been replaced.</p>
Remedy:	<ul style="list-style-type: none"> - save all parameters (p0977 = 1 or p0971 = 1 or "copy RAM to ROM"). - acknowledge fault (e.g. BI: p2103). <p>See also: r9776 (SI diagnostics)</p>
F01649	SI P1 (CU): Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>An internal error in the Safety Integrated software on processor 1 has occurred.</p> <p>Note:</p> <p>This fault results in a STOP A that cannot be acknowledged.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - carry out a POWER ON (power off/on). - re-commission the "Safety Integrated" function and carry out a POWER ON. - contact the Hotline. - replace Control Unit.
F01650	SI P1 (CU): Acceptance test required
Message class:	Safety monitoring channel has identified an error (10)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>The drive-integrated "Safety Integrated" function on processor 1 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, interpret decimal):</p> <p>130: Safety parameters for processor 2 not available.</p> <p>Note:</p> <p>This fault value is always output when Safety Integrated is commissioned for the first time.</p> <p>1000: Reference and actual checksum on processor 1 are not identical (booting).</p> <ul style="list-style-type: none"> - at least one checksum-checked piece of data is defective.

2000: Reference and actual checksum on processor 1 are not identical (commissioning mode).
- reference checksum incorrectly entered on processor 1 (p9799 not equal to r9798).
2001: Reference and actual checksum on processor 2 are not identical (commissioning mode).
- reference checksum incorrectly entered on processor 2 (p9899 not equal to r9898).
2002: Enable of safety-related functions between the processor 1 and processor 2 differ (p9601 not equal to p9801).
2003: Acceptance test is required as a safety parameter has been changed.
2004: An acceptance test is required because a project with enabled safety-functions has been downloaded.
2005: The Safety logbook has identified that a functional safety checksum has changed. An acceptance test is required.
2020: Error when saving the safety parameters for the processor 2.
9999: Subsequent response of another safety-related fault that occurred when booting that requires an acceptance test.

Remedy:

For fault value = 130:
- carry out safety commissioning routine.
For fault value = 1000:
- again carry out safety commissioning routine.
- replace the memory card or Control Unit.
- Using STARTER, activate the safety parameters for the drive involved (change settings, copy parameters, activate settings).
For fault value = 2000:
- check the safety parameters on processor 1 and adapt the reference checksum (p9799).
For fault value = 2001:
- check the safety parameters on processor 2 and adapt the reference checksum (p9899).
For fault value = 2002:
- enable the safety-related functions on processor 1 and check processor 2 (p9601 = p9801).
For fault value = 2003, 2004, 2005:
- Carry out an acceptance test and generate an acceptance report.
The fault with fault value 2005 can only be acknowledged when the "STO" function is de-selected.
For fault value = 2010:
- check the enable the safety-related brake control on both monitoring channels (p9602 = p9802).
For fault value = 2020:
- again carry out safety commissioning routine.
- replace the memory card or Control Unit.
For fault value = 9999:
- carry out diagnostics for the other safety-related fault that is present.
Note:
STO: Safe Torque Off
See also: p9799 (SI setpoint checksum SI parameters (processor 1)), p9899 (SI setpoint checksum SI parameters (processor 2))

F01651**SI P1 (CU): Synchronization safety time slices unsuccessful**

Message class: Hardware/software error (1)

Reaction: OFF2

Acknowledge: IMMEDIATELY (POWER ON)

Cause: The "Safety Integrated" function requires synchronization of the safety time slices between processor 1 and processor 2. This synchronization was unsuccessful.

Note:

This fault results in a STOP A that cannot be acknowledged.

Fault value (r0949, interpret decimal):

Only for internal Siemens troubleshooting.

Remedy:

Carry out a POWER ON (power off/on).

F01653	SI P1 (CU): PROFIBUS/PROFINET configuration error
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE (OFF1, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>There is a PROFIBUS/PROFINET configuration error for using Safety Integrated monitoring functions with a higher-level control.</p> <p>Note:</p> <p>For safety functions that have been enabled, this fault results in a STOP A that cannot be acknowledged.</p> <p>Fault value (r0949, interpret decimal):</p> <p>200: A safety slot for receive data from the control has not been configured.</p> <p>210, 220: The configured safety slot for the receive data from the control has an unknown format.</p> <p>230: The configured safety slot for the receive data from the F-PLC has the incorrect length.</p> <p>231: The configured safety slot for the receive data from the F-PLC has the incorrect length.</p> <p>250: A PROFIsafe slot is configured in the higher-level F control, however PROFIsafe is not enabled in the drive.</p> <p>300: A safety slot for the send data to the control has not been configured.</p> <p>310, 320: The configured safety slot for the send data to the control has an unknown format.</p> <p>330: The configured safety slot for the send data to the F-PLC has the incorrect length.</p> <p>331: The configured safety slot for the send data to the F-PLC has the incorrect length.</p>
Remedy:	<p>The following generally applies:</p> <ul style="list-style-type: none"> - check and, if necessary, correct the PROFIBUS/PROFINET configuration of the safety slot on the master side. - upgrade the Control Unit software. <p>For fault value = 250:</p> <ul style="list-style-type: none"> - remove the PROFIsafe configuring in the higher-level F control or enable PROFIsafe in the drive. <p>Re fault value = 231, 331:</p> <ul style="list-style-type: none"> - configure PROFIsafe telegram 30 in the F-PLC.
A01654 (F)	SI P1 (CU): Deviating PROFIsafe configuration
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The configuration of a PROFIsafe telegram in the higher-level control (F-PLC) does not match the parameterization in the drive.</p> <p>Note:</p> <p>This message does not result in a safety stop response.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>1:</p> <p>A PROFIsafe telegram is configured in the higher-level control, however PROFIsafe is not enabled in the drive (p9601.3).</p> <p>2:</p> <p>PROFIsafe is parameterized in the drive; however, a PROFIsafe telegram has not been configured in the higher-level control.</p>
Remedy:	<p>The following generally applies:</p> <ul style="list-style-type: none"> - check and, if necessary, correct the PROFIsafe configuration in the higher-level control. <p>Re alarm value = 1:</p> <ul style="list-style-type: none"> - remove the PROFIsafe configuring in the higher-level F control or enable PROFIsafe in the drive. <p>Re alarm value = 2:</p> <ul style="list-style-type: none"> - configure the PROFIsafe telegram to match the parameterization in the higher-level F-control.
F01655	SI P1 (CU): Align monitoring functions
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>An error has occurred when aligning the Safety Integrated monitoring functions on processor 1 and processor 2. No common set of supported SI monitoring functions was able to be determined.</p> <ul style="list-style-type: none"> - there is a communication error between processor 1 and processor 2 or communication has failed.

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).
- check the electrical cabinet design and cable routing for EMC compliance

F01656

SI P1 (CU): Parameter processor 2 error

Message class:

Hardware/software error (1)

Reaction:

OFF2

Acknowledge:

IMMEDIATELY (POWER ON)

Cause:

When accessing the Safety Integrated parameters for the processor 2 in the non-volatile memory, an error has occurred.

Note:

This fault results in a STOP A that can be acknowledged.

Fault value (r0949, interpret decimal):

129: Safety parameters for processor 2 corrupted.

131: Internal software error

132: Communication errors when uploading or downloading the safety parameters.

255: Internal software error on the Control Unit.

Remedy:

- re-commission the safety functions.
 - replace the memory card or Control Unit.
- For fault value = 129:
- activate the safety commissioning mode (p0010 = 95).
 - adapt the PROFIsafe address (p9610).
 - start the copy function for SI parameters (p9700 = D0 hex).
 - acknowledge data change (p9701 = DC hex).
 - exit the safety commissioning mode (p0010 = 0).
 - save all parameters (p0971 = 1 or "copy RAM to ROM").
 - carry out a POWER ON (power off/on) for the Control Unit.
- For fault value = 132:
- check the electrical cabinet design and cable routing for EMC compliance

F01658

SI P1 (CU): PROFIsafe telegram number not suitable

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF2

Acknowledge:

IMMEDIATELY (POWER ON)

Cause:

The PROFIsafe telegram number in p60022 is unsuitable for the enabled safety functions.

Possible causes:

- When PROFIsafe is not enabled (p9601.3 = 0), then it is not permissible to select a PROFIsafe telegram in p60022.
- When PROFIsafe is enabled (p9601.3 = 1), then a PROFIsafe telegram must be selected in p60022.

Note:

This fault does not result in a safety stop response.

See also: p9601 (SI enable functions integrated in the drive (processor 1)), p60022 (PROFIsafe telegram selection)

Remedy:

Select the telegram number that matches the Safety functions that have been enabled.

F01659

SI P1 (CU): Write request for parameter rejected

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF2

Acknowledge:

IMMEDIATELY (POWER ON)

Cause:

The write request for one or several Safety Integrated parameters on processor 1 was rejected.

Note:

This fault does not result in a safety stop response.

Fault value (r0949, interpret decimal):

- 1: The Safety Integrated password is not set.
- 2: A reset of the drive parameters was selected. However, the Safety Integrated parameters were not reset, as Safety Integrated is presently enabled.
- 3: The interconnected STO input is in the simulation mode.
- 10: An attempt was made to enable the STO 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.
- 18: An attempt was made to enable the PROFIsafe function for Basic Functions although this cannot be supported.
- 20: An attempt was made to simultaneously enable both the drive-integrated motion monitoring functions via integrated F-DI and STO via terminals, even though these cannot be supported at the same time.
- 21: An attempt was made to enable the Safety Integrated functions although these cannot be supported by the connected Power Module.
- 26: At a digital input of the Control Unit used by Safety Integrated, an attempt was made to activate the simulation mode.
- 28: An attempt was made to enable the "STO via terminals at the Power Module" function although this cannot be supported.

See also: p0970 (Reset drive parameters), p3900 (Completion of quick commissioning), r9771 (SI common functions (processor 1)), r9871 (SI common functions (processor 2))

Remedy:

For fault value = 1:

- set the Safety Integrated password (p9761).

For fault value = 2:

- Inhibit Safety Integrated (p9501, p9601) or reset safety parameters (p0970 = 5), then reset the drive parameters again.

For fault value = 3:

- end the simulation mode for the digital input (p0795).

For fault value = 10, 14, 15, 18:

- check whether there are faults in the safety function alignment (F01655, F30655) and if required, carry out diagnostics for the faults involved.
- use a Control Unit that supports the required function.

For fault value = 20:

- Correct the enable setting (p9601).

For fault value = 21:

- use a Power Module that supports the Safety Integrated functions.

For fault value = 26:

- Deactivate the simulation mode for the set signal source for STO (p9620) (p0795).
- Deactivate the simulation mode (p0795) for the F-DIs used by the Safety Integrated functions (r10049, p10006, p10009).
- For the set test stop of the F-DO with feedback signal input (p10046, p10047), check the simulation mode, and if required, deactivate (p0795).

For fault value = 28: use the power unit with the feature "STO via terminals at the Power Module".

Note:

F-DI: Failsafe Digital Input

STO: Safe Torque Off

See also: p9601 (SI enable functions integrated in the drive (processor 1)), p9761 (SI password input), p9801 (SI enable functions integrated in the drive (processor 2))

F01660

SI P1 (CU): Safety-related functions not supported

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF2

Acknowledge:

IMMEDIATELY (POWER ON)

Cause:

The Power Module does not support the safety-related functions. Safety Integrated cannot be commissioned.

Note:

This fault does not result in a safety stop response.

Remedy:

- use a Power Module that supports the safety-related functions.

F01662	Error internal communications
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	A module-internal communication error has occurred. Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.
Remedy:	- carry out a POWER ON (power off/on). - upgrade firmware to later version. - contact the Hotline.
F01663	SI P1 (CU): Copying the SI parameters rejected
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	In p9700, the value 208 is saved or was entered offline. This is the reason that when booting, an attempt is made to copy Safety Integrated parameters from processor 1 to processor 2. However, no safety-relevant function has been selected on processor 1 (p9601 = 0). This is the reason that copying is not possible. Note: This fault does not result in a safety stop response. SI: Safety Integrated See also: p9700 (SI copy function)
Remedy:	- Set p9700 to 0. - Check p9601 and if required, correct. - Restart the copying function by entering the corresponding value into p9700.
F01665	SI P1 (CU): System is defective
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A system defect was detected before the last boot or in the actual one. The system might have been rebooted (reset). Fault value (r0949, interpret hexadecimal): 200000 hex, 400000 hex, 8000yy hex (yy any): - Fault in the actual booting/operation. Additional values: - defect before the last time that the system booted.
Remedy:	- carry out a POWER ON (power off/on). - upgrade firmware to later version. - contact the Hotline. For fault value = 200000 hex, 400000 hex, 8000yy hex (yy any): - ensure that the Control Unit is connected to the Power Module.
A01678 (F)	SI: Test stop for STO via terminals required at the PM
Message class:	Safety monitoring channel has identified an error (10)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The time (p9661) set to monitor the forced checking procedure (test stop) for the "STO via the terminals at the Power Module" function has been exceeded. A new forced checking procedure is required. After the next time the "STO via terminals at the Power Module" function is deselected, the message is withdrawn and the monitoring time is reset.

Note:

- This message does not result in a safety stop response.
- The test must be performed within a defined, maximum time interval (p9661, maximum of 9000 hours) in order to comply with the requirements as laid down in the standards for timely fault detection and the conditions to calculate the failure rates of safety functions (PFH value). Operation beyond this maximum time period is permissible if it can be ensured that the forced checking procedure is performed before persons enter the hazardous area and who are depending on the safety functions correctly functioning.

Remedy:

Select the "STO via terminals at the Power Module" function and then deselect again.

Note:

PM: Power Module
SI: Safety Integrated
STO: Safe Torque Off

A01693 (F)

SI P1 (CU): Safety parameter setting changed, POWER ON required

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

NONE

Acknowledge:

NONE

Cause:

Safety parameters have been changed; these will only take effect following a POWER ON.

Notice:

All changed parameters of the safety motion monitoring functions will only take effect following a POWER ON.

Alarm value (r2124, interpret decimal):

Parameter number of the safety parameter which has changed, necessitating a POWER ON.

Remedy:

- execute the function "Copy RAM to ROM".
- carry out a POWER ON (power off/on).

A01698 (F)

SI P1 (CU): Commissioning mode active

Message class:

General drive fault (19)

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.
- In the safety commissioning mode, the "STO" function is internally selected.

See also: p0010 (Drive commissioning parameter filter)

Remedy:

Not necessary.

A01699 (F)

SI P1 (CU): Test stop for STO required

Message class:

Safety monitoring channel has identified an error (10)

Reaction:

NONE

Acknowledge:

NONE

Cause:

The time set in p9659 for the forced checking procedure (test stop) for the "STO" function has been exceeded. A new forced checking procedure is required.

After the next time the "STO" function is de-selected, the message is withdrawn and the monitoring time is reset.

Note:

- This message does not result in a safety stop response.
- The test must be performed within a defined, maximum time interval (p9659, maximum of 9000 hours) in order to comply with the requirements as laid down in the standards for timely fault detection and the conditions to calculate the failure rates of safety functions (PFH value). Operation beyond this maximum time period is permissible if it can be ensured that the forced checking procedure is performed before persons enter the hazardous area and who are depending on the safety functions correctly functioning.

See also: p9659 (SI forced checking procedure timer), r9660 (SI forced checking procedure remaining time)

Remedy:

Select STO and then de-select again.

Note:

SI: Safety Integrated
STO: Safe Torque Off

A01788	SI: Automatic test stop waits for STO deselection via motion monitoring functions
Message class:	Safety monitoring channel has identified an error (10)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The automatic test stop (forced checking procedure) was not able to be carried out after powering up.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - The STO function is selected via safe motion monitoring functions. - A safety message is present, that resulted in a STO. <p>Note:</p> <p>STO: Safe Torque Off</p>
Remedy:	<ul style="list-style-type: none"> - deselect STO via safe motion monitoring functions. - Remove the cause of the safety messages and acknowledge the messages. <p>Note:</p> <p>The automatic test stop is performed after removing the cause.</p>
A01790	SI: Power up stopped due to STO via terminals
Message class:	Safety monitoring channel has identified an error (10)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>When powering up, the automatic internal self test of the Control Unit was not able to be completed as the pulses were not enabled. It is possible that the "STO via terminals at the Power Module" function is being used, and STO is selected in at least one hardware shutdown path at the Power Module.</p>
Remedy:	<ul style="list-style-type: none"> - Deselect STO via the STO terminals at the Power Module (connect STO_A and STO_B to 24 V). - If required, deactivate the "STO via terminals at the Power Module" function via the DIP switch (both DIP switches set to "OFF"). <p>Note:</p> <ul style="list-style-type: none"> - After the cause has been removed, the Control Unit continues to power up. - While the alarm remains, a possibly existing brake is kept closed. <p>STO: Safe Torque Off</p>
A01796 (F, N)	SI P1 (CU): Wait for communication
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The drive waits for communication to be established to execute the safety-relevant motion monitoring functions.</p> <p>Note:</p> <p>In this state, the pulses are safely suppressed.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>3: Wait for communication to be established to PROFIsafe F-Host.</p>
Remedy:	<p>If, after a longer period of time, the message is not automatically withdrawn, the following checks have to be made:</p> <ul style="list-style-type: none"> - Check any other PROFIsafe communication messages/signals present and evaluate them. - check the operating state of the F-Host. - Check the communication connection to the F Host. <p>See also: p9601 (SI enable functions integrated in the drive (processor 1)), p9801 (SI enable functions integrated in the drive (processor 2))</p>
A01900 (F)	PROFIBUS: Configuration telegram error
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>A PROFIBUS master attempts to establish a connection using an incorrect configuring telegram.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>2: Too many PZD data words for input or output. The number of possible PZD is specified by the number of indices in r2050/p2051.</p> <p>3: Uneven number of bytes for input or output.</p>

	<p>211: Unknown parameterizing block. 501: PROFIsafe parameter error (e.g. F_dest). Additional values: Only for internal Siemens troubleshooting. Check the bus configuration on the master and the slave sides. Re alarm value = 2: Check the number of data words for input and output. Re alarm value = 211: Ensure offline version <= online version. Re alarm value = 501: Check the set PROFIsafe address (p9610).</p>
F01910 (N, A)	Fieldbus interface setpoint timeout
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF3 (IASC/DCBRK, NONE, OFF1, OFF2, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	<p>The reception of setpoints from the fieldbus interface has been interrupted.</p> <ul style="list-style-type: none"> - bus connection interrupted. - communication partner switched off. <p>For PROFIBUS:</p> <ul style="list-style-type: none"> - PROFIBUS master set into the STOP state. <p>See also: p2040 (Fieldbus interface monitoring time), p2047 (PROFIBUS additional monitoring time)</p>
Remedy:	<p>Ensure bus connection has been established and switch on communication peer.</p> <ul style="list-style-type: none"> - if required, adapt p2040. <p>For PROFIBUS:</p> <ul style="list-style-type: none"> - set the PROFIBUS master to the RUN state. - if the error is repeated, check the set response monitoring in the bus configuration (HW Config). - slave redundancy: For operation on a Y link, it must be ensured that "DP alarm mode = DPV1" is set in the slave parameterization.
A01920 (F)	PROFIBUS: Interruption cyclic connection
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The cyclic connection to the PROFIBUS master is interrupted.
Remedy:	<p>Establish the PROFIBUS connection and activate the PROFIBUS master in the cyclic mode.</p> <p>Note:</p> <p>If there is no communication to a higher-level control system, then p2030 should be set = 0 to suppress this message.</p> <p>See also: p2030 (Field bus int protocol selection)</p>
A01945	PROFIBUS: Connection to the Publisher failed
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>For PROFIBUS peer-to-peer data transfer, the connection to at least one Publisher has failed.</p> <p>Alarm value (r2124, interpret binary):</p> <p>Bit 0 = 1: Publisher with address in r2077[0], connection failed.</p> <p>...</p> <p>Bit 15 = 1: Publisher with address in r2077[15], connection failed.</p>
Remedy:	<p>Check the PROFIBUS cables.</p> <p>See also: r2077 (PROFIBUS diagnostics peer-to-peer data transfer addresses)</p>

F01946 (A)	PROFIBUS: Connection to the Publisher aborted
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF1 (NONE, OFF2, OFF3)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The connection to at least one Publisher for PROFIBUS peer-to-peer data transfer in cyclic operation has been aborted. Fault value (r0949, interpret binary): Bit 0 = 1: Publisher with address in r2077[0], connection aborted. ... Bit 15 = 1: Publisher with address in r2077[15], connection aborted.
Remedy:	- check the PROFIBUS cables. - check the state of the Publisher that has the aborted connection. See also: r2077 (PROFIBUS diagnostics peer-to-peer data transfer addresses)
F01951	CU SYNC: Synchronization application clock cycle missing
Message class:	Internal (DRIVE-CLiQ) communication error (12)
Reaction:	OFF2 (NONE)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	Internal synchronization of the application cycles unsuccessful. Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	- Carry out a POWER ON (power off/on) for all components. - upgrade the Control Unit software.
A01953	CU SYNC: Synchronization not completed
Message class:	Internal (DRIVE-CLiQ) communication error (12)
Reaction:	NONE
Acknowledge:	NONE
Cause:	After the drive system was powered up, synchronization between the basic clock cycle and application clock cycle was started but was not completed within the selected time tolerance. Alarm value (r2124, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	Carry out a POWER ON (power off/on).
A02050	Trace: Start not possible
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The trace has already been started.
Remedy:	Stop the trace and, if necessary, start again.
A02051	Trace: recording not possible as a result of know-how protection
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	TRACE recording is not possible as at least one signal or trigger signal being used is under know-how protection. Alarm value (r2124, interpret decimal): 1: Recorder 0 2: Recorder 1 3: Recorders 0 and 1
Remedy:	- Temporarily activate or deactivate know-how protection (p7766). - Include the signal in the OEM exception list (p7763, p7764). - Where relevant do not record the signal. See also: p7763 (KHP OEM exception list number of indices for p7764), p7764 (KHP OEM exception list)

A02055	Trace: Recording time too short
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The trace duration is too short. The minimum is twice the value of the trace clock cycle.
Remedy:	Check the selected recording time and, if necessary, adjust.
A02056	Trace: Recording cycle too short
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected recording clock cycle is lower than the basic clock cycle 500µs.
Remedy:	Increase the value for the trace cycle.
A02057	Trace: Time slice clock cycle invalid
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The time slice clock cycle selected does not match any of the existing time slices.
Remedy:	Enter an existing time slice clock cycle. The existing time slices can be read out via p7901.
A02058	Trace: Time slice clock cycle for endless trace not valid
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected time slice clock cycle cannot be used for the endless trace
Remedy:	Enter the clock cycle of an existing time slice with a cycle time ≥ 2 ms for up to 4 recording channels or ≥ 4 ms from 5 recording channels per trace. The existing time slices can be read out via p7901.
A02059	Trace: Time slice clock cycle for 2 x 8 recording channels not valid
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The selected time slice clock cycle cannot be used for more than 4 recording channels.
Remedy:	Enter the clock cycle of an existing time slice with a cycle time ≥ 4 ms or reduce the number of recording channels to 4 per trace. The existing time slices can be read out via p7901.
A02060	Trace: Signal to be traced missing
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	- a signal to be traced was not specified. - the specified signals are not valid.
Remedy:	- specify the signal to be traced. - check whether the relevant signal can be traced.
A02061	Trace: Invalid signal
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	- the specified signal does not exist. - the specified signal can no longer be traced (recorded).

Remedy:

- specify the signal to be traced.
- check whether the relevant signal can be traced.

A02062 **Trace: Invalid trigger signal**
Message class: Error in the parameterization / configuration / commissioning procedure (18)
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 a trigger signal for the trace.

Remedy: Specify a valid trigger signal.

A02063 **Trace: Invalid data type**
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The specified data type to select a signal using a physical address is invalid.
Remedy: Use a valid data type.

A02070 **Trace: Parameter cannot be changed**
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The trace parameter settings cannot be changed when the trace is active.
Remedy:

- stop the trace before parameterization.
- if required, start the trace.

A02075 **Trace: Pretrigger time too long**
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The selected pretrigger time must be shorter than the trace time.
Remedy: Check the pretrigger time setting and change if necessary.

F02080 **Trace: Parameterization deleted due to unit changeover**
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: The trace parameterization in the drive unit was deleted due to a unit changeover or a change in the reference parameters.
Remedy: Restart trace.

A02095 **MTrace 0: multiple trace cannot be activated**
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The following functions or settings are not permissible in conjunction with a multiple trace (trace recorder 0):

- measuring function
- long-time trace
- trigger condition "immediate recording start" (IMMEDIATE)
- trigger condition "start with function generator" (FG_START)

Remedy:

- if required, deactivate the multiple trace (p4840[0] = 0).
- deactivate function or setting that is not permissible

A02096	MTrace 0: cannot be saved
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>It is not possible to save the measurement results of a multiple trace on the memory card (trace recorder 0).</p> <p>A multiple trace is not started or is canceled.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>1: Memory card cannot be accessed.</p> <ul style="list-style-type: none"> - card is not inserted or is blocked by a mounted USB drive. <p>3: data save operation too slow.</p> <ul style="list-style-type: none"> - a second trace has been completed before the measurement results of the first trace were able to be saved. - writing the measurement result files to the card is blocked by the parameter save. <p>4: Data save operation canceled.</p> <ul style="list-style-type: none"> - for instance, the file required for the data save operation was not able to be found.
Remedy:	<ul style="list-style-type: none"> - insert or remove the memory card. - use a larger memory card. - configure a longer trace time or use an endless trace. - avoid saving parameters while a multiple trace is running. - check whether other functions are presently accessing measurement result files.
A02097	MTrace 1: multiple trace cannot be activated
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The following functions or settings are not permissible in conjunction with a multiple trace (trace recorder 1):</p> <ul style="list-style-type: none"> - measuring function - long-time trace - trigger condition "immediate recording start" (IMMEDIATE) - trigger condition "start with function generator" (FG_START)
Remedy:	<ul style="list-style-type: none"> - if required, deactivate the multiple trace (p4840[1] = 0). - deactivate function or setting that is not permissible
A02098	MTrace 1: cannot be saved
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>It is not possible to save the measurement results of a multiple trace on the memory card (trace recorder 1).</p> <p>A multiple trace is not started or is canceled.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>1: Memory card cannot be accessed.</p> <ul style="list-style-type: none"> - card is not inserted or is blocked by a mounted USB drive. <p>3: data save operation too slow.</p> <ul style="list-style-type: none"> - a second trace has been completed before the measurement results of the first trace were able to be saved. - writing the measurement result files to the card is blocked by the parameter save. <p>4: Data save operation canceled.</p> <ul style="list-style-type: none"> - for instance, the file required for the data save operation was not able to be found.
Remedy:	<ul style="list-style-type: none"> - insert or remove the memory card. - use a larger memory card. - configure a longer trace time or use an endless trace. - avoid saving parameters while a multiple trace is running. - check whether other functions are presently accessing measurement result files.

A02099 Trace: Insufficient Control Unit memory

Message class: Error in the parameterization / configuration / commissioning procedure (18)
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 time.
- increase the trace clock cycle.
- reduce the number of signals to be traced.

A02150 OA: Application cannot be loaded

Message class: Hardware/software error (1)
Reaction: NONE
Acknowledge: NONE
Cause: The system was not able to load an OA application.
Alarm value (r2124, interpret hexadecimal):
16:
The interface version in the DCB user library is not compatible to the DCC standard library that has been loaded.
Only for internal Siemens troubleshooting.
Remedy:
- Carry out a POWER ON (power off/on) for all components.
- upgrade firmware to later version.
- contact the Hotline.
Re alarm value = 16:
Load a compatible DCB user library (compatible to the interface of the DCC standard library).
Note:
OA: Open Architecture

F02151 (A) OA: Internal software error

Message class: Hardware/software error (1)
Reaction: 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 firmware to later version.
- contact the Hotline.
- replace the Control Unit.
Note:
OA: Open Architecture

F02152 (A) OA: Insufficient memory

Message class: Hardware/software error (1)
Reaction: OFF1
Acknowledge: IMMEDIATELY (POWER ON)
Cause: Too many functions have been configured on this Control Unit (e.g. too many drives, function modules, data sets, OA applications, blocks, etc).
Fault value (r0949, interpret decimal):
Only for internal Siemens troubleshooting.
Remedy:
- change the configuration on this Control Unit (e.g. fewer drives, function modules, data sets, OA applications, blocks, etc).
- use an additional Control Unit.
Note:
OA: Open Architecture

F03000 NVRAM fault on action

Message class: Hardware/software error (1)
Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A fault occurred during execution of action p7770 = 1 or 2 for the NVRAM data.
 Fault value (r0949, interpret hexadecimal):
 yyxx hex: yy = fault cause, xx = application ID
 yy = 1:
 The action p7770 = 1 is not supported by this version if Drive Control Chart (DCC) is activated for the drive object concerned.
 yy = 2:
 The data length of the specified application is not the same in the NVRAM and the backup.
 yy = 3:
 The data checksum in p7774 is not correct.
 yy = 4:
 No data available to load.
Remedy:
 - Perform the remedy according to the results of the troubleshooting.
 - If necessary, start the action again.

F03001 NVRAM checksum incorrect

Message class: Hardware/software error (1)
Reaction: NONE
Acknowledge: IMMEDIATELY
Cause: A checksum error occurred when evaluating the non-volatile data (NVRAM) on the Control Unit.
 The NVRAM data affected was deleted.
Remedy: Carry out a POWER ON (power off/on) for all components.

F03505 (N, A) Analog input wire breakage

Message class: External measured value / signal state outside the permissible range (16)
Reaction: OFF1 (NONE, OFF2)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The wire-break monitoring for an analog input has responded.
 The input value of the analog input has undershot the threshold value parameterized in p0761[0...3].
 p0756[0]: analog input 0 (only CU240D-2)
 p0756[1]: analog input 1 (only CU240D-2)
 Fault value (r0949, interpret decimal):
 yxxx dec
 y = analog input (0 = analog input 0 (AI 0), 1 = analog input 1 (AI 1))
 xxx = component number (p0151)
 Note:
 For the following analog input type, the wire breakage monitoring is active:
 p0756[0...1] = 1 (2 ... 10 V with monitoring)
Remedy:
 - Check the connection to the signal source for interruptions.
 - Check the magnitude of the injected current - it is possible that the infed signal is too low.
 Note:
 The input current measured by the analog input can be read in r0752[x].

A03510 (F, N) Calibration data not plausible

Message class: Hardware/software error (1)
Reaction: NONE
Acknowledge: NONE
Cause: During booting, the calibration data for the analog inputs is read and checked with respect to plausibility.
 At least one calibration data point was determined to be invalid.

4 Faults and alarms

4.2 List of faults and alarms

Remedy: - power down/power up the power supply for the Control Unit.
Note:
If it reoccurs, then replace the module.
In principle, operation could continue.
The analog channel involved possibly does not achieve the specified accuracy.

A05000 (N) Power unit: Overtemperature heat sink AC inverter
Message class: Power electronics faulted (5)
Reaction: NONE
Acknowledge: NONE
Cause: The alarm threshold for overtemperature at the inverter heat sink has been reached. The response is set using p0290.
If the temperature of the heat sink 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?

A05001 (N) Power unit: Overtemperature depletion layer chip
Message class: Power electronics faulted (5)
Reaction: NONE
Acknowledge: NONE
Cause: Alarm threshold for overtemperature of the power semiconductor in the AC converter has been reached.
Note:
- The response is set using p0290.
- If the depletion layer temperature increases by an additional 15 K, then fault F30025 is triggered.
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)

A05002 (N) Power unit: Air intake overtemperature
Message class: Power electronics faulted (5)
Reaction: NONE
Acknowledge: NONE
Cause: For chassis power units, the following applies:
The alarm threshold for the air intake overtemperature has been reached. For air-cooled power units, the threshold is 42 °C (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.

A05004 (N) Power unit: Rectifier overtemperature
Message class: Power electronics faulted (5)
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 triggered.
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?

A05006 (N)	Power unit: Overtemperature thermal model
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The temperature difference between the chip and heat sink has exceeded the permissible limit value (blocksize power units only). Depending on p0290, an appropriate overload response is initiated. See also: r0037 (Power unit temperatures)
Remedy:	Not necessary. The alarm disappears automatically once the limit value is undershot. Note: If the alarm does not disappear automatically and the temperature continues to rise, this can result in fault F30024. See also: p0290 (Power unit overload response)
A05065 (F, N)	Voltage measured values not plausible
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The voltage measurement does not supply any plausible values and is not used. Alarm value (r2124, interpret bitwise binary): Bit 1: Phase U Bit 2: Phase V Bit 3: Phase W
Remedy:	The following parameterization must be made in order to deactivate the alarm: - Deactivate voltage measurement (p0247.0 = 0). - Deactivate flying restart with voltage measurement (p0247.5 = 0) and deactivate fast flying restart (p1780.11 = 0).
F06310 (A)	Supply voltage (p0210) incorrectly parameterized
Message class:	Network fault (2)
Reaction:	NONE (OFF1, OFF2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The measured DC voltage lies outside the tolerance range after pre-charging has been completed. Permissible range: $1.16 * p0210 < r0070 < 1.6 * p0210$ Note: The fault can only be acknowledged when the drive is powered down. 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)
A06921 (N)	Braking resistor phase unsymmetry
Message class:	Braking Module faulted (14)
Reaction:	NONE
Acknowledge:	NONE
Cause:	- the three resistors of the braking chopper are not symmetrical. - DC link voltage oscillations caused by fluctuating loads of the connected drives.
Remedy:	- check the feeder cables to the braking resistors. - If required, increase the value for detecting dissymmetry (p1364).

F06922	Braking resistor phase failure
Message class:	Braking Module faulted (14)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A phase failure for the brake resistor was detected. Fault value (r0949, interpret decimal): 11: Phase U 12: Phase V 13: Phase W
Remedy:	Check the feeder cables to the braking resistors.
F07011	Drive: Motor overtemperature
Message class:	Motor overload (8)
Reaction:	OFF2 (NONE, OFF1, OFF3, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	KTY: The motor temperature has exceeded the fault threshold (p0605) or the timer (p0606) after the alarm threshold was exceeded (p0604) has expired. The response parameterized in p0610 becomes active. The alarm is withdrawn if the response threshold for wire breakage or sensor not connected is exceeded ($R > 2120 \text{ Ohm}$). PTC or bimetallic NC contact: The response threshold of 1650 Ohm was exceeded or the NC contact opened and the timer (p0606) has expired. The response parameterized in p0610 becomes active. Possible causes: - Motor is overloaded - motor ambient temperature too high. - Wire break or sensor not connected Fault value (r0949, interpret decimal): 200: The motor temperature model 1 (I2t) signals an overtemperature ($p0612.0 = 1$, $p0611 > 0$, p0615 reached). See also: p0604, p0605, p0606, p0612, p0625, p0626, p0627, p0628
Remedy:	- Reduce the motor load. - check the ambient temperature and the motor ventilation. - check the wiring and the connection of the PTC or bimetallic NC contact. See also: p0604, p0605, p0606, p0612, p0625, p0626, p0627, p0628
A07012 (N)	Drive: Motor temperature model 1/3 overtemperature
Message class:	Motor overload (8)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The motor temperature model 1/3 identified that the alarm threshold was exceeded. Hysteresis:2K. Alarm value (r2124, interpret decimal): 200: Motor temperature model 1 (I2t): Temperature too high (p0605). 300: Motor temperature model 3: Temperature too high (p5398). See also: r0034 (Motor utilization thermal), p0605 (Mot_temp_mod 1/2 threshold), p0611 (I2t motor model thermal time constant), p0612 (Mot_temp_mod activation)
Remedy:	- check the motor load and if required, reduce. - check the motor ambient temperature. - check activation of the motor temperature model (p0612). Motor temperature model 1 (I2t): - check the thermal time constant (p0611). - check the alarm threshold (p0605).

Motor temperature model 3:

- check the motor type.
- check the alarm threshold (p5398).
- check the model parameters.

See also: r0034 (Motor utilization thermal), p0605 (Mot_temp_mod 1/2 threshold), p0611 (I2t motor model thermal time constant), p0612 (Mot_temp_mod activation), r5397 (Mot_temp_mod 3 ambient temperature image p0613)

A07014 (N)	Drive: Motor temperature model configuration alarm
Message class:	Motor overload (8)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>A fault has occurred in the configuration of the motor temperature model.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>1:</p> <p>All motor temperature models: It is not possible to save the model temperature</p> <p>See also: p0610 (Motor overtemperature response)</p>
Remedy:	<p>- set the response for motor overtemperature to "Alarm and fault, no reduction of I_max" (p0610 = 2).</p> <p>See also: p0610 (Motor overtemperature response)</p>
A07015	Drive: Motor temperature sensor alarm
Message class:	External measured value / signal state outside the permissible range (16)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>An error was detected when evaluating the temperature sensor set in 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, 50 ms after alarm A07015.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - wire breakage or sensor not connected (KTY: R > 2120 Ohm). - measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).
Remedy:	<ul style="list-style-type: none"> - make sure that the sensor is connected correctly. - check the parameterization (p0601). <p>See also: r0035 (Motor temperature), p0601 (Motor temperature sensor type), p0607 (Temperature sensor fault timer)</p>
F07016	Drive: Motor temperature sensor fault
Message class:	External measured value / signal state outside the permissible range (16)
Reaction:	OFF1 (NONE, OFF2, OFF3, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	<p>An error was detected when evaluating the temperature sensor set in p0601.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - wire breakage or sensor not connected (KTY: R > 2120 Ohm). - measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm). <p>Note:</p> <p>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, 50 ms after alarm A07015.</p> <p>See also: p0607 (Temperature sensor fault timer)</p>
Remedy:	<ul style="list-style-type: none"> - make sure that the sensor is connected correctly. - check the parameterization (p0601). - induction motors: De-activate temperature sensor fault (p0607 = 0). <p>See also: r0035 (Motor temperature), p0601 (Motor temperature sensor type), p0607 (Temperature sensor fault timer)</p>

F07080	Drive: Incorrect control parameter
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The closed-loop control parameters have been parameterized incorrectly (e.g. p0356 = L_spread = 0). Fault value (r0949, interpret decimal): The fault value includes the parameter number involved. See also: p0310, p0311, p0341, p0344, p0350, p0354, p0356, p0357, p0358, p0360, p0640, p1082, p1300
Remedy:	Modify the parameter indicated in the fault value (r0949) (e.g. p0640 = current limit > 0). See also: p0311, p0341, p0344, p0350, p0354, p0356, p0358, p0360, p0640, p1082
F07082	Macro: Execution not possible
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The macro cannot be executed. Fault value (r0949, interpret hexadecimal): ccccbbaa hex: cccc = preliminary parameter number, bb = supplementary information, aa = fault cause Fault causes for the trigger parameter itself: 19: Called file is not valid for the trigger parameter. 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). Fault causes 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 (or CDS-dependent) 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.
Remedy:	- check the parameter involved. - check the macro file and BICO interconnection. See also: p0015 (Macro drive unit), p1000 (Speed setpoint selection)

F07083	Macro: ACX file not found
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
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, interpret decimal): Parameter number with which the execution was started. See also: p0015 (Macro drive unit), p1000 (Speed setpoint selection)
Remedy:	- check whether the file is saved in the appropriate directory on the memory card.
F07084	Macro: Condition for WaitUntil not fulfilled
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The WaitUntil condition set in the macro was not fulfilled in a certain number of attempts. Fault value (r0949, interpret decimal): Parameter number for which the condition was set.
Remedy:	Check and correct the conditions for the WaitUntil loop.
F07086	Units changeover: Parameter limit violation due to reference value change
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A reference parameter was changed in the system. This resulted in the fact that for the parameters involved, the selected value was not able to be written in the per unit notation. The values of the parameters were set to the corresponding violated minimum limit/maximum limit or to the factory setting. Possible causes: - the steady-state minimum limit/maximum limit or that defined in the application was violated. Fault value (r0949, parameter): Diagnostics parameter to display the parameters that were not able to be re-calculated. See also: p0304, p0305, p0310, p0596, p2000, p2001, p2002, p2003, r2004
Remedy:	Check the adapted parameter value and if required correct.
F07088	Units changeover: Parameter limit violation due to units changeover
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	A changeover of units was initiated. This resulted in a violation of a parameter limit Possible causes for the violation of a parameter limit: - When rounding off a parameter corresponding to its decimal places, the steady-state minimum limit or maximum limit was violated. - inaccuracies for the data type "FloatingPoint". In these cases, when the minimum limit is violated then the parameter value is rounded up and when the maximum limited is violated the parameter value is rounded down. Fault value (r0949, interpret decimal): Diagnostics parameter to display all parameters whose value had to be adapted. See also: p0100 (IEC/NEMA mot stds), p0505 (Selecting the system of units), p0595 (Technological unit selection)
Remedy:	Check the adapted parameter values and if required correct.

A07089	Changing over units: Function module activation is blocked because the units have been changed over
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	An attempt was made to activate a function module. This is not permissible if the units have already been changed over. See also: p0100 (IEC/NEMA mot stds), p0505 (Selecting the system of units)
Remedy:	Restore units that have been changed over to the factory setting.
A07092	Drive: moment of inertia estimator still not ready
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The moment of inertia estimator still has no valid values. The acceleration cannot be calculated. The moment of inertia estimator is ready, if the frictional values (p1563, p1564) as well as the moment of inertia value (p1493) have been determined (r1407.26 = 1).
Remedy:	Repeat the operation when the moment of inertia estimator is ready (r1407.26 = 1).
A07094	General parameter limit violation
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	As a result of the violation of a parameter limit, the parameter value was automatically corrected. Minimum limit violated --> parameter is set to the minimum value. Maximum limit violated --> parameter is set to the maximum value. Fault value (r0949, interpret decimal): Parameter number, whose value had to be adapted.
Remedy:	Check the adapted parameter values and if required correct.
A07200	Drive: Master control ON command present
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The ON/OFF1 command is present (no 0 signal). The command is either influenced via binector input p0840 (current CDS) or control word bit 0 via the master control.
Remedy:	Switch the signal via binector input p0840 (current CDS) or control word bit 0 via the master control to 0.
F07220 (N, A)	Drive: Master control by PLC missing
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF1 (NONE, OFF2, OFF3, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	The "master control by PLC" signal was missing in operation. - interconnection of the binector input for "master control by PLC" is incorrect (p0854). - the higher-level control has withdrawn the "master control by PLC" signal. - data transfer via the fieldbus (master/drive) was interrupted.
Remedy:	- check the interconnection of the binector input for "master control by PLC" (p0854). - check the "master 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 "master control by PLC" then fault response must be parameterized to NONE or the message type should be parameterized as alarm.

F07320	Drive: Automatic restart interrupted
Message class:	Application/technological function faulted (17)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<ul style="list-style-type: none"> - The specified number of restart attempts (p1211) has been completely used up because within the monitoring time (p1213) the faults were not able to be acknowledged. The number of restart attempts (p1211) is decremented at each new start attempt. - the monitoring time for the power unit 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. <p>Fault value (r0949, interpret hexadecimal): Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - increase the number of restart attempts (p1211). - increase the delay time in p1212 and/or the monitoring time in p1213. - Reduce the delay time for resetting the start counter p1213[1] so that fewer faults are registered in the time interval.
A07321	Drive: Automatic restart active
Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>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.</p> <p>For p1210 = 26, restarting is realized with the delayed setting of the ON command.</p>
Remedy:	<ul style="list-style-type: none"> - 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). - for p1210 = 26: by withdrawing the OFF2- / OFF3 command.
F07330	Flying restart: Measured search current too low
Message class:	Application/technological function faulted (17)
Reaction:	OFF2 (NONE, OFF1)
Acknowledge:	IMMEDIATELY
Cause:	<p>During a flying restart, it was identified that the search current reached is too low.</p> <p>It is possible that the motor is not connected.</p>
Remedy:	Check the motor feeder cables.
F07331	Flying restart: Function not supported
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2 (NONE, OFF1)
Acknowledge:	IMMEDIATELY
Cause:	<p>It is not possible to power up with the motor rotating (no flying restart).</p> <p>In the following cases, the "flying restart" function is not supported:</p> <p>Permanent magnet synchronous motor (PEM): operation with U/f characteristic and sensorless vector control.</p>
Remedy:	De-activate the "flying restart" function (p1200 = 0).
A07400 (N)	Drive: DC link voltage maximum controller active
Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The DC link voltage controller has been activated because the upper switch-in threshold has been exceeded (r1242, r1282).</p> <p>The ramp-down times are automatically increased in order to maintain the DC link voltage (r0070) within the permissible limits. There is a system deviation between the setpoint and actual speeds.</p> <p>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.</p> <p>See also: r0056 (Status word, closed-loop control), p1240 (Vdc controller configuration (vector control)), p1280 (Vdc controller configuration (U/f))</p>

Remedy:

If the controller is not to intervene:

- increase the ramp-down times.
- switch-off the Vdc_max controller (p1240 = 0 for vector control, p1280 = 0 for U/f control).

If the ramp-down times are not to be changed:

- use a chopper or regenerative feedback unit.

A07401 (N) Drive: DC link voltage maximum controller de-activated

Message class: Application/technological function faulted (17)
Reaction: NONE
Acknowledge: NONE
Cause: The Vdc_max controller can no longer maintain the DC link voltage (r0070) below the limit value (r1242, r1282) and was therefore switched out (disabled).

- 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:

- check whether the input voltage is within the permissible range (if required, increase the value in p0210).
- check whether the load duty cycle and load limits are within the permissible limits.

A07402 (N) Drive: DC link voltage minimum controller active

Message class: Application/technological function faulted (17)
Reaction: NONE
Acknowledge: NONE
Cause: The DC link voltage controller has been activated as the lower switch-in threshold has been undershot (r1246, r1286).
The kinetic energy of the motor is used to buffer the DC link. The drive is therefore braked.
See also: r0056 (Status word, closed-loop control), p1240 (Vdc controller configuration (vector control)), p1280 (Vdc controller configuration (U/f))
Remedy: The alarm disappears when power supply returns.

F07404 Drive: DC link voltage monitoring Vdc_max

Message class: DC-link overvoltage (4)
Reaction: OFF2 (NONE, OFF1, OFF3)
Acknowledge: IMMEDIATELY
Cause: The monitoring of the DC link voltage p1284 has responded (only U/f control).
Remedy:

- check the line supply voltage.
- check the braking module.
- adapt the device supply voltage (p0210).
- adapt the DC link voltage monitoring (p1284).

F07405 (N, A) Drive: Kinetic buffering minimum speed not reached

Message class: Application/technological function faulted (17)
Reaction: OFF2 (IASC/DCBRK, NONE, OFF1, OFF3, STOP2)
Acknowledge: IMMEDIATELY
Cause: During kinetic buffering the speed fell below minimum speed (p1257 or p1297 for vector drives with U/f control) and the line supply did not return.
Remedy: Check the speed threshold for the Vdc_min controller (kinetic buffering) (p1257, p1297).
See also: p1257 (Vdc_min controller speed threshold), p1297 (Vdc_min controller speed threshold (U/f))

F07406 (N, A) Drive: Kinetic buffering maximum time exceeded

Message class: Application/technological function faulted (17)
Reaction: OFF3 (IASC/DCBRK, NONE, OFF1, OFF2, STOP2)
Acknowledge: IMMEDIATELY
Cause: The maximum buffer time (p1255 and p1295 for vector drives with U/f control) has been exceeded without the line supply having returned.
Remedy: Check the time threshold for Vdc-min controller (kinetic buffering) (p1255, p1295).
See also: p1255 (Vdc_min controller time threshold), p1295 (Vdc_min controller time threshold (U/f))

A07409 (N)	Drive: U/f control, current limiting controller active
Message class:	Application/technological function faulted (17)
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 after one of the following measures: - increase current limit (p0640). - reduce the load. - slow down the ramp up to the setpoint speed.
F07410	Drive: Current controller output limited
Message class:	Application/technological function faulted (17)
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. - motor data and motor configuration (star-delta) do not match. - no DC link voltage present. - power unit defective. - the "flying restart" function is not activated.
Remedy:	- connect the motor or check the motor contactor. - check the motor parameterization and the connection type (star-delta). - check the DC link voltage (r0070). - check the power unit. - activate the "flying restart" function (p1200).
F07426 (A)	Technology controller actual value limited
Message class:	Application/technological function faulted (17)
Reaction:	OFF1 (IASC/DCBRK, NONE, OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	The actual value for the technology controller, interconnected via connector input p2264, has reached a limit. Fault value (r0949, interpret decimal): 1: upper limit reached. 2: lower limit reached.
Remedy:	- adapt the limits to the signal level (p2267, p2268). - Check the actual value normalization (p0595, p0596). See also: p0595 (Technological unit selection), p0596 (Technological unit reference quantity), p2264 (Technology controller actual value), p2267 (Technology controller upper limit actual value), p2268 (Technology controller lower limit actual value)
A07428 (N)	Technology controller parameterizing error
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The technology controller has a parameterizing error. Alarm value (r2124, interpret decimal): 1: The upper output limit in p2291 is set lower than the lower output limit in p2292.
Remedy:	Re alarm value = 1: Set the output limit in p2291 higher than in p2292. See also: p2291 (Technology controller maximum limiting), p2292 (Technology controller minimum limiting)

F07435 (N)	Drive: Setting the ramp-function generator for sensorless vector control
Message class:	Application/technological function faulted (17)
Reaction:	OFF2 (IASC/DCBRK, NONE, OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	During operation with sensorless vector control (r1407.1) the ramp-function generator was stopped (p1141). An internal setting command of the ramp-function generator output caused the set setpoint speed to be frozen.
Remedy:	<ul style="list-style-type: none">- de-activate the holding command for the ramp-function generator (p1141).- suppress the fault (p2101, p2119). This is necessary if the ramp-function generator is held using jogging and the speed setpoint is simultaneously inhibited (r0898.6).
A07444	PID autotuning running
Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	PID autotuning running.
Remedy:	<p>Not necessary.</p> <p>The alarm is automatically withdrawn once the autotuning has been completed.</p>
F07445	PID autotuning canceled
Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The PID autotuning was canceled as a result of an error.
Remedy:	<ul style="list-style-type: none">- increase the offset.- check system configuration.
A07530	Drive: Drive Data Set DDS not present
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The selected drive data set is not available. The drive data set was not changed over.</p> <p>See also: p0180 (Number of Drive Data Sets (DDS)), p0820 (Drive Data Set selection DDS bit 0), r0837 (Drive Data Set DDS selected)</p>
Remedy:	<ul style="list-style-type: none">- select the existing drive data set.- set up additional drive data sets.
A07531	Drive: Command Data Set CDS not present
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The selected command data set is not available (p0836 > p0170). The command data set was not changed over.</p> <p>See also: p0810 (Command data set selection CDS bit 0), r0836 (Command Data Set CDS selected)</p>
Remedy:	<ul style="list-style-type: none">- select the existing command data set.- set up additional command data sets.
F07754	Drive: Incorrect shutoff valve configuration
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>An incorrect shutoff valve configuration was detected.</p> <p>Fault value (r0949, interpret decimal):</p> <p>100:</p> <p>Enable Safety Integrated (p9601/p9801), but p0218.0 = 0 (shutoff valve not available).</p> <p>101:</p> <p>The manipulated variable inhibit time is set less than the wait time to evaluate the feedback signal contacts when switching on the shutoff valve (p0230 < p9625[0]/p9825[0]).</p>

102:

The manipulated variable inhibit time is set less than the wait time to evaluate the feedback signal contacts when switching off the shutoff valve (p0230 < p9625[1]/p9825[1]).

Remedy:

For fault value = 100:

Check the enable of Safety Integrated and the shutoff valve (p9601/p9801, p0218.0).

For fault value = 101:

Set the manipulated variable inhibit time higher than the wait time to evaluate the feedback signal contacts when switching on the shutoff valve (p0230 > p9625[0]/p9825[0]).

For fault value = 102:

Set the manipulated variable inhibit time higher than the wait time to evaluate the feedback signal contacts when switching off the shutoff valve (p0230 > p9625[1]/p9825[1]).

See also: p0230 (Drive filter type motor side)

F07800

Drive: No power unit present

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

NONE

Acknowledge:

IMMEDIATELY

Cause:

The power unit parameters cannot be read or no parameters are stored in the power unit.

Note:

This fault also occurs if an incorrect topology was selected in the commissioning software and this parameterization is then downloaded to the Control Unit.

Remedy:

- Carry out a POWER ON (power off/on) for all components.
- Check the power unit and replace if necessary.
- check the Control Unit, and if required replace it.
- after correcting the topology, the parameters must be again downloaded using the commissioning software.

F07801

Drive: Motor overcurrent

Message class:

Motor overload (8)

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.
- 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 current of power unit.
- Switch to rotating motor without flying restart function (p1200).

Note:

Limit current = 2 x minimum (p0640, 4 x p0305 x p0306) >= 2 x p0305 x p0306

Remedy:

- check the current limits (p0640).
- U/f control: Check the current limiting controller (p1340 ... p1346).
- increase the up ramp (p1120) or reduce the load.
- check the motor and motor cables for short-circuit and ground fault.
- check the motor for the star-delta configuration and rating plate parameterization.
- check the power unit and motor combination.
- Choose "flying restart" function (p1200) if switched to rotating motor.

F07802

Drive: Infeed or power unit not ready

Message class:

Infeed faulted (13)

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.

4 Faults and alarms

4.2 List of faults and alarms

Remedy:

- 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 overload I2t

Message class: Power electronics faulted (5)
Reaction: NONE
Acknowledge: NONE
Cause: Alarm threshold for I2t overload 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 motor and power unit rated currents.

F07807 Drive: Short-circuit/ground fault detected

Message class: Ground fault / inter-phase short-circuit detected (7)
Reaction: OFF2 (NONE)
Acknowledge: IMMEDIATELY
Cause: A phase-phase short-circuit or ground fault was detected at the motor-side output terminals of the converter.
Fault value (r0949, interpret decimal):
1: Short-circuit, phase UV.
2: Short-circuit, phase UW.
3: Short-circuit, phase VW.
4: Ground fault with overcurrent.
1yxxx: Ground fault with current in phase U detected (y = pulse number, xxxx = component of the current in phase V in per mille).
2yxxx: Ground fault with current in phase V detected (y = pulse number, xxxx = component of the current in phase U in per mille).
Note:

Also when interchanging the line and motor cables is identified as a motor-side short circuit.
The ground fault test only functions when the motor is stationary.
Connecting to a motor that is either not de-energized or partially de-energized is possibly detected as ground fault.

Remedy:

- check the motor-side converter connection for a phase-phase short-circuit.
- rule-out interchanged line and motor cables.
- check for a ground fault.

For a ground fault the following applies:

- do not enable the pulses when connecting to a rotating motor without the "Flying restart" function activated (p1200).
- increase the de-energization time (p0347).
- increase pulse suppression delay time (p1228) to ensure standstill.
- If required, deactivate the monitoring (p1901).

F07810 Drive: Power unit EEPROM without rated data

Message class: Hardware/software error (1)
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.

A07850 (F)	External alarm 1
Message class:	External measured value / signal state outside the permissible range (16)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The condition for "External alarm 1" is satisfied. Note: The "External alarm 1" is initiated by a 1/0 edge via binector input p2112. See also: p2112 (External alarm 1)
Remedy:	Eliminate the causes of this alarm.
F07860 (A)	External fault 1
Message class:	External measured value / signal state outside the permissible range (16)
Reaction:	OFF2 (IASC/DCBRK, NONE, OFF1, OFF3, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The condition for "External fault 1" is satisfied. Note: The "External fault 1" is initiated by a 1/0 edge via binector input p2106. See also: p2106 (External fault 1)
Remedy:	- eliminate the causes of this fault. - acknowledge fault.
A07891	Drive: Load monitoring pump/fan blocked
Message class:	Motor overload (8)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The load monitoring is configured for a pump or fan (p2193 = 4, 5). The monitoring function detects when the pump/fan is blocked. It is possible that the blocking torque threshold (p2168) is set too low (e.g. heavy duty starting). See also: p2165 (Load monitoring stall monitoring upper threshold), p2168 (Load monitoring stall monitoring torque threshold)
Remedy:	- check whether the pump/fan is blocked, and if blocked, then resolve the problem. - check that the fan can freely move, and if necessary, resolve the problem. - adapt the parameterization corresponding to the load (p2165, p2168)..
A07892	Drive: Load monitoring pump/fan no load condition
Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The load monitoring is configured for a pump or fan (p2193 = 4, 5). The monitoring function detects when the pump/fan is operating under no load conditions. The pump is running in the dry state (no medium to be pumped) – or the fan has a broken belt. It is possible that the detection torque threshold is too low (p2191). See also: p2191 (Load monitoring torque threshold no load)
Remedy:	- for a pump, check the medium being pumped, and if required, provide the medium. - for a fan, check the belt, and if required, replace. - If necessary, increase the detection torque threshold (p2191).
A07893	Drive: Load monitoring pump leakage
Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The load monitoring is configured for a pump (p2193 = 4). The monitoring function detects a leak in the pump circuit. In this case, the pump requires a torque that is lower than in normal operation to pump the reduced quantity.

- Remedy:**
- remove the leak in the pump circuit.
 - for a nuisance trip, reduce the torque thresholds of the leakage characteristic (p2186, p2188, p2190).

F07894 Drive: Load monitoring pump/fan blocked

Message class: Motor overload (8)

Reaction: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The load monitoring is configured for a pump or fan (p2193 = 4, 5).
The monitoring function detects when the pump/fan is blocked.
It is possible that the blocking torque threshold (p2168) is set too low (e.g. heavy duty starting).
See also: p2165 (Load monitoring stall monitoring upper threshold), p2168 (Load monitoring stall monitoring torque threshold)

- Remedy:**
- check whether the pump/fan is blocked, and if blocked, then resolve the problem.
 - check that the fan can freely move, and if necessary, resolve the problem.
 - adapt the parameterization corresponding to the load (p2165, p2168)..

F07895 Drive: Load monitoring pump/fan no load condition

Message class: Application/technological function faulted (17)

Reaction: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The load monitoring is configured for a pump or fan (p2193 = 4, 5).
The monitoring function detects when the pump/fan is operating under no load conditions.
The pump is running in the dry state (no medium to be pumped) – or the fan has a broken belt.
It is possible that the detection torque threshold is too low (p2191).
See also: p2191 (Load monitoring torque threshold no load)

- Remedy:**
- for a pump, check the medium being pumped, and if required, provide the medium.
 - for a fan, check the belt, and if required, replace.
 - If necessary, increase the detection torque threshold (p2191).

F07896 Drive: Load monitoring pump leakage

Message class: Application/technological function faulted (17)

Reaction: OFF1 (NONE, OFF2, OFF3)

Acknowledge: IMMEDIATELY

Cause: The load monitoring is configured for a pump (p2193 = 4).
The monitoring function detects a leak in the pump circuit.
In this case, the pump requires a torque that is lower than in normal operation to pump the reduced quantity.

- Remedy:**
- remove the leak in the pump circuit.
 - for a nuisance trip, reduce the torque thresholds of the leakage characteristic (p2186, p2188, p2190).

F07900 (N, A) Drive: Motor blocked

Message class: Application/technological function faulted (17)

Reaction: OFF2 (NONE, OFF1, OFF3, STOP2)

Acknowledge: IMMEDIATELY

Cause: Motor has been operating at the torque limit at a low speed for a longer period of time and below the set speed threshold.
This signal can also be triggered if the speed is oscillating and the speed controller output repeatedly goes to its limit.
It may also be the case that thermal monitoring of the power unit reduces the current limit (see p0290), thereby causing the motor to decelerate.

- Remedy:**
- check that the motor can freely move.
 - check the effective torque limit (r1538, r1539).
 - check the direction of rotation enable signals for a flying restart of the motor (p1110, p1111).
 - for U/f control: check the current limits and acceleration times (p0640, p1120).

F07901	Drive: Motor overspeed
Message class:	Application/technological function faulted (17)
Reaction:	OFF2 (IASC/DCBRK)
Acknowledge:	IMMEDIATELY
Cause:	The maximum permissible speed was either positively or negatively exceeded. The maximum permissible positive speed is formed as follows: Minimum (p1082) The maximum permissible negative speed is formed as follows: Maximum (-p1082)
Remedy:	The following applies for a positive direction of rotation: - check r1084 and if required, correct p1082. The following applies for a negative direction of rotation: - check r1087 and if required, correct p1082. Activate pre-control of the speed limiting controller (bit 7 = 1). Increase the hysteresis for the overspeed signal. This upper limit is dependent upon the maximum motor speed p0322 and the maximum speed p1082 of the setpoint channel.
F07902 (N, A)	Drive: Motor stalled
Message class:	Application/technological function faulted (17)
Reaction:	OFF2 (IASC/DCBRK, NONE, OFF1, OFF3, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	The system has identified that the motor has stalled for a time longer than is set. Fault value (r0949, interpret decimal): 1: Reserved. 2: Stall detection using r1408.12 (p1745) or via (r0084 ... r0083).
Remedy:	Steps should always be taken to ensure that both motor data identification and the rotating measurement were carried out (see p1900, r3925). - check whether the drive stalls solely due to the load in controlled mode or when the speed setpoint is still zero. If yes, then increase the current setpoint using p1610. - if the motor excitation time (p0346) was significantly reduced and the drive stalls when it is switched on and run immediately, p0346 should be increased again. - check whether the motor cables are disconnected (see A07929). If there is no fault, then the fault tolerance can be increased (p1745). - check the current limits (p0640, r0067, r0289). If the current limits are too low, then the drive cannot be magnetized. - If the fault occurs with fault value 2 when the motor accelerates very quickly to the field weakening range, the deviation between the flux setpoint and flux actual value can be reduced and, in turn, the message prevented, by reducing p1553.
A07910 (N)	Drive: Motor overtemperature
Message class:	Motor overload (8)
Reaction:	NONE
Acknowledge:	NONE
Cause:	KTY or no sensor: The measured motor temperature or the temperature of the motor temperature model 2 has exceeded the alarm threshold (p0604). The response parameterized in p0610 becomes active. PTC or bimetallic NC contact: The response threshold of 1650 Ohm was exceeded or the NC contact opened. Alarm value (r2124, interpret decimal): 11: No output current reduction. 12: Output current reduction active. See also: p0604 (Mot_temp_mod 2/KTY alarm threshold), p0610 (Motor overtemperature response)
Remedy:	- check the motor load. - check the motor ambient temperature. - check KTY84. - check overtemperatures of the motor temperature model 2 (p0626 ... p0628). See also: p0612 (Mot_temp_mod activation), p0625 (Motor ambient temperature during commissioning), p0626 (Motor overtemperature, stator core), p0627 (Motor overtemperature, stator winding), p0628 (Motor overtemperature rotor)

A07927 DC braking active

Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The motor is braked with DC current. DC braking is active. 1) A message with response DCBRK is active. The motor is braked with the braking current set in p1232 for the duration set in p1233. If the standstill threshold is fallen below, then braking is prematurely canceled. 2) DC braking has been activated at binector input p1230 with the DC braking set (p1230 = 4). Braking current p1232 is injected until this binector input becomes inactive.
Remedy:	Not necessary. The alarm automatically disappears once DC braking has been executed.

A07929 (F) Drive: No motor detected

Message class:	Application/technological function faulted (17)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The absolute current value is so small after enabling the inverter pulses that no motor is detected. Note: In the case of vector control and an induction motor, this alarm is followed by the fault F07902.
Remedy:	- check the motor feeder cables. - check the voltage boost of the U/f control (p1310). - carry out a standstill measurement to set the stator resistance (p0350).

F07950 (A) Motor parameter incorrect

Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	The motor parameters were incorrectly entered while commissioning (e.g. p0300 = 0, no motor) Fault value (r0949, interpret decimal): Parameter number involved. See also: p0300, p0301, p0304, p0305, p0307, p0310, p0311, p0314, p0316, p0320, p0322, p0323
Remedy:	Compare the motor data with the rating plate data and if required, correct.

A07960 Drive: Incorrect friction characteristic

Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The friction characteristic is incorrect. Alarm value (r2124, interpret 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. 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. 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.

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)

Remedy:

Fulfill the conditions for the friction characteristic.

Re alarm value = 1538:

Check the upper effective torque limit (e.g. in the field weakening range).

Re alarm value = 1539:

Check the lower effective torque limit (e.g. in the field weakening range).

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).

A07961

Drive: Friction characteristic record activated

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

NONE

Acknowledge:

NONE

Cause:

The automatic friction characteristic record is activated.

The friction characteristic is recorded at the next power-on command.

When plotting the friction characteristic, it is not possible to save the parameters (p0971, p0977).

Remedy:

Not necessary.

The alarm disappears automatically after the friction characteristic record has been successfully completed or the record is de-activated (p3845 = 0).

F07963

Drive: Friction characteristic record interrupted

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF1

Acknowledge:

IMMEDIATELY

Cause:

The conditions to record the friction characteristic are not fulfilled.

Fault value (r0949, interpret decimal):

0046: Missing enable signals (r0046).

1082: The highest speed value to be approached (p3829) is greater than the maximum speed (p1082).

1084: The highest speed value to be approached (p3829) is greater than the maximum speed (r1084, p1083, p1085).

1087: The highest speed value to be approached (p3829) is greater than the maximum speed (r1087, p1086, p1088).

1110: Friction characteristic record, negative direction selected (p3845) and negative direction inhibited (p1110).

1111: Friction characteristic record, positive direction selected (p3845) and positive direction inhibited (p1111).

1198: Friction characteristic record selected (p3845 > 0) and negative (p1110) and positive directions (p1111) inhibited (r1198).

1300: The control mode (p1300) has not been set to closed-loop speed control.

1755: For encoderless 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).

1910: Motor data identification activated.

1960: Speed controller optimization activated.

3820 ... 3829: Speed (p382x) cannot be approached.

3840: Friction characteristic incorrect.

3845: Friction characteristic record de-selected.

Remedy:

Fulfill the conditions to record the friction characteristic.

Re fault value = 0046:

- establish missing enable signals.

For fault value = 1082, 1084, 1087:

- Select the highest speed value to be approached (p3829) less than or equal to the maximum speed (p1082, r1084, r1087).

- Re-calculate the speed points along the friction characteristic (p0340 = 5).

- For fault value = 1110:
 - Select the friction characteristic record, positive direction (p3845).
- For fault value = 1111:
 - Select the friction characteristic record, negative direction (p3845).
- For fault value = 1198:
 - Enable the permitted direction (p1110, p1111, r1198).
- For fault value = 1300:
 - Set the control mode (p1300) on the closed-loop speed control (p1300 = 20, 21).
- For fault value = 1755:
 - For encoderless 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).
 - Re-calculate the speed points along the friction characteristic (p0340 = 5).
- For fault value = 1910:
 - Exit the motor data identification routine (p1910).
- For fault value = 1960:
 - Exit the speed controller optimization routine (p1960).
- Re fault value 3820 ... 3829:
 - check the load at speed p382x.
 - check the speed signal (r0063) for oscillation at speed p382x. Check the settings of the speed controller if applicable.
- For fault value = 3840:
 - Make the friction characteristic error-free (p3820 ... p3829, p3830 ... p3839, p3840).
- For fault value = 3845:
 - Activate the friction characteristic record (p3845).

F07967	Drive: Incorrect pole position identification
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2 (NONE, OFF1)
Acknowledge:	IMMEDIATELY
Cause:	A fault has occurred during the pole position identification routine. Only for internal Siemens troubleshooting.
Remedy:	Carry out a POWER ON.

F07968	Drive: Lq-Ld measurement incorrect
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A fault has occurred during the Lq-Ld measurement. Fault value (r0949, interpret 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:	For fault value = 10: Check whether the motor is correctly connected. Replace the power unit involved. De-activate technique (p1909). For fault value = 12: Check whether motor data have been correctly entered. De-activate technique (p1909). For fault value = 16: De-activate technique (p1909). For fault value = 17: Repeat technique.

F07969 Drive: Incorrect pole position identification

Message class: Error in the parameterization / configuration / commissioning procedure (18)

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: A fault has occurred during the pole position identification routine.

Fault value (r0949, interpret decimal):

1: Current controller limited

2: Motor shaft locked.

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: For fault value = 1:

Check whether the motor is correctly connected.

Check whether motor data have been correctly entered.

Replace the power unit involved.

For fault value = 2:

Bring the motor into a no-load condition.

For 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 power unit involved.

For fault value = 11:

Increase the value for p0329.

Check whether the motor is correctly connected.

Replace the power unit involved.

For 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.

For fault value = 13:

Reduce the value for p0329.

Check whether motor data have been correctly entered.

For fault value = 14:

Increase the value for p0329.

For fault value = 15:

Increase the value for p0325.

Motor not sufficiently anisotropic, change the technique (p1980 = 1, 10).

For fault value = 16:

Change the technique (p1980).

For fault value = 17:

Repeat technique.

For fault value = 18:

Increase the value for p0329 (if required, first set p0323).

Saturation not sufficient, change the technique (p1980 = 10).

For fault value = 20:

Before carrying out a pole position identification routine ensure that the motor shaft is absolutely stationary (zero speed).

A07976 Drive: Fine encoder calibration activated

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The alarm indicates the phases of the fine encoder calibration using the alarm value.
Alarm value (interpret decimal):
1: Fine encoder calibration active.
2: Rotating measurement started (set the setpoint speed > 40 % rated motor speed).
3: Rotating measurement lies within the speed and torque range.
4: Rotating measurement successful: pulse inhibit can be initiated to accept the values.
5: Fine encoder calibration is calculated.
10: Speed too low, rotating measurement interrupted.
12: Torque too high, rotating measurement interrupted.
Remedy: Re alarm value = 10:
Increase the speed.
Re alarm value = 12:
Bring the drive into a no-load condition.

A07980 Drive: Rotating measurement activated

Message class: Error in the parameterization / configuration / commissioning procedure (18)
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.
Note:
During the rotating measurement it is not possible to save the parameters (p0971).
See also: p1960 (Rotating measurement selection)
Remedy: Not 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

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: NONE
Acknowledge: NONE
Cause: The rotating measurement cannot be started due to missing enable signals.
For p1959.13 = 1, the following applies:
- enable signals for the ramp-function generator missing (see p1140 ... p1142).
Remedy: - acknowledge faults that are present.
- establish missing enable signals.
See also: r0002 (Drive operating display), r0046 (Missing enable sig)

F07983 Drive: Rotating measurement saturation characteristic

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF1 (NONE, OFF2)
Acknowledge: IMMEDIATELY
Cause: A fault has occurred while determining the saturation characteristic.
Fault value (r0949, interpret 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 high.

Remedy:

For fault value = 1:

- the total drive moment of inertia is far higher than that of the motor (p0341, p0342).

De-select rotating measurement (p1960), enter the moment of inertia p0342, re-calculate the speed controller p0340 = 4 and repeat the measurement.

Re fault value = 1 ... 2:

- increase the measuring speed (p1961) and repeat the measurement.

Re fault value = 1 ... 4:

- check the motor parameters (rating plate data). After the change: Calculate p0340 = 3.
- check the moment of inertia (p0341, p0342). After the change: Calculate p0340 = 3.
- carry out a motor data identification routine (p1910).
- if required, reduce the dynamic factor (p1967 < 25 %).

For fault value = 5:

- the speed setpoint (p1961) is too high. Reduce the speed.

For fault value = 6:

- adapt the speed setpoint (p1961) or minimum limiting (p1080).

For fault value = 7:

- adapt the speed setpoint (p1961) or suppression (skip) bandwidths (p1091 ... p1092, p1101).

For fault value = 8:

- adapt the speed setpoint (p1961) or maximum limit (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

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF1 (NONE, OFF2)

Acknowledge:

IMMEDIATELY

Cause:

A fault has occurred while identifying the moment of inertia.

Fault value (r0949, interpret 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. The measured moment of inertia is less than the 0.1x or greater than 500x the preset moment of inertia of the motor p0341.

Remedy:

For fault value = 1:

- check the motor parameters (rating plate data). After the change: Calculate p0340 = 3.
- check the moment of inertia (p0341, p0342). After the change: Calculate p0340 = 3.
- 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 adapt the minimum limit (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 limit (p1082, p1083 and p1086).

For fault value = 8:

- 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 p0342, re-calculate the speed controller p0340 = 4 and repeat the measurement.

For fault value = 9:

- check the moment of inertia (p0341, p0342). After the change, re-calculate (p0340 = 3 or 4).

For fault value = 10:

- check the moment of inertia (p0341, p0342). After the change: Calculate p0340 = 3.

For fault value = 11:

- reduce the moment of inertia of the motor p0341 (e.g., factor of 0.2) or increase (e.g. factor of 5) and repeat the measurement.

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)

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF1 (NONE, OFF2)

Acknowledge:

IMMEDIATELY

Cause:

A fault has occurred during the vibration test.

Fault value (r0949, interpret 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:

For fault value = 1:

- check the motor parameters (rating plate data). After the change: Calculate p0340 = 3.

- check the moment of inertia (p0341, p0342). After the change: Calculate p0340 = 3.

- carry out a motor data identification routine (p1910).

- if required, reduce the dynamic factor (p1967 < 25 %).

For fault value = 2:

- adapt the speed setpoint (p1965) or adapt the minimum limit (p1080).

For fault value = 3:

- adapt the speed setpoint (p1965) or suppression (skip) bandwidths (p1091 ... p1092, p1101).

For fault value = 4:

- adapt the speed setpoint (p1965) or maximum limit (p1082, p1083 and p1086).

For fault value = 5:

- increase the torque limits (e.g. p1520, p1521).

For fault value = 6:

- reduce the dynamic factor (p1967).

- disable the vibration test (p1959.4 = 0) and repeat the rotating measurement.

See also: p1959 (Rotating measurement configuration)

F07986

Drive: Rotating measurement ramp-function generator

Message class:

Error in the parameterization / configuration / commissioning procedure (18)

Reaction:

OFF1 (NONE, OFF2)

Acknowledge:

IMMEDIATELY

Cause:

During the rotating measurements, problems with the ramp-function generator occurred.

Fault value (r0949, interpret decimal):

1: The positive and negative directions are inhibited.

Remedy: For fault value = 1:
Enable the direction (p1110 or p1111).

F07988 Drive: Rotating measurement, no configuration selected
Message class: Error in the parameterization / configuration / commissioning procedure (18)
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
Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF2 (NONE, OFF1)
Acknowledge: IMMEDIATELY
Cause: A fault has occurred during the identification routine.
 Fault value (r0949, interpret decimal):
 1: Current limit value reached.
 2: Identified stator resistance lies outside the expected range 0.1 ... 100% of Zn.
 3: Identified rotor resistance lies outside the expected range 0.1 ... 100% of Zn.
 4: Identified stator reactance lies outside the expected range 50 ... 500 % of Zn.
 5: Identified magnetizing reactance lies outside the expected range 50 ... 500 % of Zn.
 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 Zn.
 8: Identified stator leakage reactance lies outside the expected range 2 ... 50% of Zn.
 9: Identified rotor leakage reactance lies outside the expected range 2 ... 50% of Zn.
 10: Motor has been incorrectly connected.
 11: Motor shaft rotates.
 12: Ground fault detected.
 15: Pulse inhibit occurred during motor data identification
 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.
Note:
 Percentage values are referred to the rated motor impedance:

$$Z_n = V_{mot,nom} / \sqrt{3} / I_{mot,nom}$$

Remedy: Re fault value = 1 ... 40:
 - check whether motor data have been correctly entered in p0300, p0304 ... p0311.
 - is there an appropriate relationship between the motor power rating and that of the power unit? The ratio of the power unit to the rated motor current should not be less than 0.5 and not be greater than 4.
 - check connection type (star-delta).
 Re fault value = 4, 7:
 - check whether the inductance in p0233 is correctly set.
 - check whether motor has been correctly connected (star-delta).
 For fault value = 11 in addition:
 - Deactivate oscillation monitoring (p1909.7 = 1).
 For fault value = 12:
 - check the power cable connections.
 - check the motor.
 - check the CT.

A07991 (N)	Drive: Motor data identification activated
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The motor data identification routine is activated.</p> <p>The motor data identification routine is carried out at the next power-on command.</p> <p>If rotating measurement is selected (see p1900, p1960), it will not be possible to save the parameter assignment. Once motor data identification has been completed or de-activated, the option to save the parameter assignment will be made available again.</p> <p>See also: p1910 (Motor data identification selection)</p>
Remedy:	<p>Not necessary.</p> <p>The alarm automatically disappears after the motor data identification routine has been successfully completed or for the setting p1900 = 0.</p>
A07994 (F, N)	Drive: motor data identification not performed
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The "vector control" mode has been selected and a motor data identification has still not been performed.</p> <p>The alarm is initiated when changing the drive data set (see r0051) in the following cases:</p> <ul style="list-style-type: none"> - vector control is parameterized in the actual drive data set (p1300 >= 20). <p>and</p> <ul style="list-style-type: none"> - motor data identification has still not been performed in the actual drive data set (see r3925). <p>Note:</p> <p>For SINAMICS G120, a check is made and an alarm is output also when exiting commissioning and when the system powers up.</p>
Remedy:	<ul style="list-style-type: none"> - Perform motor data identification (see p1900). - If required, parameterize "U/f control" (p1300 < 20). - switch over to a drive data set, in which the conditions do not apply.
F08010 (N, A)	CU: Analog-to-digital converter
Message class:	Hardware/software error (1)
Reaction:	OFF1 (IASC/DCBRK, NONE, OFF2, OFF3, STOP2)
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The analog-to-digital converter on the Control Unit has not supplied any converted data.
Remedy:	<ul style="list-style-type: none"> - check the power supply. - replace Control Unit.
F08501 (N, A)	PROFINET: Setpoint timeout
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF3 (IASC/DCBRK, NONE, OFF1, OFF2, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	<p>The reception of setpoints from PROFINET has been interrupted.</p> <ul style="list-style-type: none"> - bus connection interrupted. - controller switched off. - controller set into the STOP state.
Remedy:	<ul style="list-style-type: none"> - Restore the bus connection and set the controller to RUN. - if the error is repeated, check the update time set in the bus configuration (HW Config).
F08502 (A)	PROFINET: Monitoring time sign-of-life expired
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF1 (OFF2, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	<p>The monitoring time for the sign-of-life counter has expired.</p> <p>The connection to the PROFINET interface was interrupted.</p>

Remedy:

- carry out a POWER ON (power off/on).
- contact the Hotline.

A08511 (F)	PROFINET: Receive configuration data invalid
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The drive unit did not accept the receive configuration data. Alarm value (r2124, interpret decimal): Return value of the receive configuration data check. 2: Too many PZD data words for output or input to a drive object. Maximum of 12 words are possible. 3: Uneven number of bytes for input or output. 501: PROFIsafe parameter error (e.g. F_dest).
Remedy:	Check the receive configuration data. Re alarm value = 2: - Check the number of data words for output and input to a drive object. Re alarm value = 501: - Check the set PROFIsafe address (p9610).

A08526 (F)	PROFINET: No cyclic connection
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	There is no connection to a PROFINET controller.
Remedy:	Establish the cyclic connection and activate the controller with cyclic operation. Check the parameters "Name of Station" and "IP of Station" (r61000, r61001).

A08564	PN/COMM BOARD: syntax error in the configuration file
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	A syntax error has been detected in the ASCII configuration file for the Communication Board Ethernet. The saved configuration file has not been loaded.
Remedy:	- correct the PROFINET interface configuration (p8920 and following) and activate (p8925 = 2). Note: The configuration is not applied until the next POWER ON! - reinitialize the station (e.g. using the STARTER commissioning software) See also: p8925 (PN interface configuration)

A08565	PROFINET: Consistency error affecting adjustable parameters
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	A consistency error was detected when activating the configuration (p8925) for the PROFINET interface. The currently set configuration has not been activated. Alarm value (r2124, interpret decimal): 0: general consistency error 1: error in the IP configuration (IP address, subnet mask or standard gateway) 2: Error in the station names. 3: DHCP was not able to be activated, as a cyclic PROFINET connection already exists. 4: a cyclic PROFINET connection is not possible as DHCP is activated. See also: p8920 (PN Name of Station), p8921 (PN IP address), p8922 (PN Def Gateway), p8923 (PN Subnet Mask)
Remedy:	- Check the required interface configuration (p8920 and following), correct if necessary, and activate (p8925). or - Reconfigure the station via the "Edit Ethernet node" screen form (e.g. with STARTER commissioning software). See also: p8925 (PN interface configuration)

F08700 (A)	CAN: Communications error
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF3 (NONE, OFF1, OFF2)
Acknowledge:	IMMEDIATELY
Cause:	<p>A CAN communications error has occurred.</p> <p>Fault value (r0949, interpret decimal):</p> <p>1: The error counter for the send telegrams has exceeded the BUS OFF value 255. The bus disables the CAN controller.</p> <ul style="list-style-type: none">- bus cable short circuit.- incorrect baud rate.- incorrect bit timing. <p>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]).</p> <ul style="list-style-type: none">- bus cable interrupted.- bus cable not connected.- incorrect baud rate.- incorrect bit timing.- master fault. <p>Note:</p> <p>The fault response can be set as required using p8641.</p> <p>See also: p8604 (CAN life guarding), p8641 (CAN Abort Connection Option Code)</p>
Remedy:	<ul style="list-style-type: none">- check the bus cable- check the baud rate (p8622).- check the bit timing (p8623).- check the master. <p>The CAN controller must be manually restarted with p8608 = 1 after the cause of the fault has been resolved!</p> <p>See also: p8608 (CAN Clear Bus Off Error), p8622 (CAN bit rate), p8623 (CAN Bit Timing selection)</p>
F08701	CAN: NMT state change
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF3
Acknowledge:	IMMEDIATELY
Cause:	<p>A CANopen NMT state transition from "operational" to "pre-operational" or after "stopped".</p> <p>Fault value (r0949, interpret decimal):</p> <p>1: CANopen NMT state transition from "operational" to "pre-operational".</p> <p>2: CANopen NMT state transition from "operational" to "stopped".</p> <p>Note:</p> <p>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.</p>
Remedy:	<p>Not necessary.</p> <p>Acknowledge the fault and continue operation.</p>
F08702 (A)	CAN: RPDO Timeout
Message class:	Communication error to the higher-level control system (9)
Reaction:	OFF3 (NONE, OFF1, OFF2)
Acknowledge:	IMMEDIATELY
Cause:	<p>The monitoring time of the CANopen RPDO telegram has expired because the bus connection was either interrupted or the CANopen Master was switched-off.</p> <p>See also: p8699 (CAN: RPDO monitoring time)</p>
Remedy:	<ul style="list-style-type: none">- check the bus cable- check the master.- If required, increase the monitoring time (p8699).

A08751 (N)	CAN: Telegram loss
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The CAN controller has lost a receive message (telegram).
Remedy:	Reduce the cycle times of the receive messages.
A08752	CAN: Error counter for error passive exceeded
Message class:	Communication error to the higher-level control system (9)
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 (CAN bit rate), p8623 (CAN Bit Timing selection)
A08753	CAN: Message buffer overflow
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	A message buffer overflow. Alarm value (r2124, interpret 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:	<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). Re alarm value = 2: <ul style="list-style-type: none"> - reduce the cycle times of the SDO receive messages. - SDO request from master only after SDO feedback for previous SDO request. See also: p8622 (CAN bit rate), p8623 (CAN Bit Timing selection)
A08754	CAN: Incorrect communications mode
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	In the "operational" mode, an attempt was made to change parameters p8700 ... p8737.
Remedy:	Change to the "pre-operational" or "stopped" mode.
A08755	CAN: Obj cannot be mapped
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
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): <ul style="list-style-type: none"> - RPDO: 6040 hex, 6060 hex, 60FF hex, 6071 hex; 5800 hex - 580F hex; 5820 hex - 5827 hex - TPDO: 6041 hex, 6061 hex, 6063 hex, 6069 hex, 606B hex, 606C hex, 6074 hex; 5810 hex - 581F hex; 5830 hex - 5837 hex Only sub-index 0 of the specified objects can be mapped. Note: As long as A08755 is present, the COB-ID cannot be set to valid.

A08756	CAN: Number of mapped bytes exceeded
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The number of bytes of the mapped objects exceeds the telegram size for net data. A max. of 8 bytes is permissible.
Remedy:	Map fewer objects or objects with a smaller data type. See also: p8710, p8711, p8712, p8713, p8714, p8715, p8716, p8717, p8730, p8731, p8732, p8733, p8734, p8735, p8736, p8737
A08757	CAN: Set COB-ID invalid
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
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.
A08759	CAN: PDO COB-ID already available
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	An existing PDO COB-ID was allocated.
Remedy:	Select another PDO COB-ID.
A08760	CAN: maximum size of the IF PZD exceeded
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The maximum size of the IF PZD was exceeded. Alarm value (r2124, interpret decimal): 1: error for IF PZD receive. 2: error for IF PZD send. Note: IF: interface
Remedy:	Map fewer process data in PDO. Apply one of the following options to delete the alarm: - POWER ON (off/on). - carry out a warm restart (p0009 = 30, p0976 = 2). - execute CANopen NMT command reset node. - change CANopen NMT state. - delete alarm buffer [0...7] (p2111 = 0).
A08800	PROFenergy energy-saving mode active
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The PROFenergy energy-saving mode is active Alarm value (r2124, interpret decimal): Mode ID of the active PROFenergy energy-saving mode. See also: r5600 (Pe energy-saving mode ID)

Remedy: The alarm is automatically withdrawn when the energy-saving mode is exited.
Note:
The energy-saving mode is exited after the following events:
- the PROFlenergy command end_pause is received from the higher-level control.
- the higher-level control has changed into the STOP operating state.
- the PROFINET connection to the higher-level control has been disconnected.

A08802 PROFlenergy not possible to switch off incremental encoder supply

Message class: Communication error to the higher-level control system (9)
Reaction: NONE
Acknowledge: NONE
Cause: The incremental encoder is used for the closed-loop position control. This means that its power supply cannot be switched off during the PROFlenergy energy-saving mode, otherwise it would lose its position actual value.
Alarm value (r2124, interpret decimal):
Encoder number
Remedy: The alarm is automatically withdrawn when the energy-saving mode is exited.
Note:
The energy-saving mode is exited after the following events:
- the PROFlenergy command end_pause is received from the higher-level control.
- the higher-level control has changed into the STOP operating state.
- the PROFINET connection to the higher-level control has been disconnected.

F13009 Licensing OA application not licensed

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF1
Acknowledge: IMMEDIATELY
Cause: At least one OA application which is under license does not have a license.
Note:
Refer to r4955 and p4955 for information about the installed OA applications.
Remedy:
- enter and activate the license key for OA applications under license (p9920, p9921).
- if necessary, de-activate unlicensed OA applications (p4956).

F13100 Know-how protection: Copy protection error

Message class: Error in the parameterization / configuration / commissioning procedure (18)
Reaction: OFF1
Acknowledge: IMMEDIATELY
Cause: The know-how protection with copy protection for the memory card is active.
An error has occurred when checking the memory card.
Fault value (r0949, interpret decimal):
0: A memory card is not inserted.
1: An invalid memory card is inserted (not SIEMENS).
2: An invalid memory card is inserted.
3: The memory card is being used in another Control Unit.
12: An invalid memory card is inserted (OEM input incorrect, p7769).
13: The memory card is being used in another Control Unit (OEM input incorrect, p7759).
See also: p7765 (KHP configuration)
Remedy:
Re fault value = 0, 1:
- Insert the correct memory card and carry out POWER ON.
For fault value = 2, 3, 12, 13:
- contact the responsible OEM.
- Deactivate copy protection (p7765) and acknowledge the fault (p3981).
- Deactivate know-how protection (p7766 ... p7768) and acknowledge the fault (p3981).
Note:
In general, the copy protection can only be changed when know-how protection is deactivated.
KHP: Know-How Protection
See also: p3981 (Faults acknowledge drive object), p7765 (KHP configuration)

F13101	Know-how protection: Copy protection cannot be activated
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>An error occurred when attempting to activate the copy protection for the memory card.</p> <p>Fault value (r0949, interpret decimal):</p> <p>0: A memory card is not inserted.</p> <p>1: An invalid memory card is inserted (not SIEMENS).</p> <p>Note:</p> <p>KHP: Know-How Protection</p>
Remedy:	<ul style="list-style-type: none"> - Insert a valid memory card. - Try to activate copy protection again (p7765). <p>See also: p7765 (KHP configuration)</p>
F13102	Know-how protection: Consistency error of the protected data
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF1
Acknowledge:	IMMEDIATELY
Cause:	<p>An error was identified when checking the consistency of the protected files. As a consequence, the project on the memory card cannot be run.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>yyyyxxxx hex: yyyy = object number, xxxx = fault cause</p> <p>xxxx = 1:</p> <p>A file has a checksum error.</p> <p>xxxx = 2:</p> <p>The files are not consistent with one another.</p> <p>xxxx = 3:</p> <p>The project files, which were loaded into the file system via load (download from the memory card), are inconsistent.</p> <p>Note:</p> <p>KHP: Know-How Protection</p>
Remedy:	<ul style="list-style-type: none"> - Replace the project on the memory card or replace project files for download from the memory card. - Restore the factory setting and download again.
F30001	Power unit: Overcurrent
Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The power unit has detected an overcurrent condition.</p> <ul style="list-style-type: none"> - 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 current of motor much greater than that of power unit. - High discharge and post-charging current for line supply voltage interruptions. - High post-charging currents for overload when motoring and DC link voltage dip. - Short-circuit currents at power-on due to the missing line reactor. - power cables are not correctly connected. - power cables exceed the maximum permissible length. - power unit defective. - line phase interrupted. <p>Fault value (r0949, interpret bitwise binary):</p> <p>Bit 0: Phase U.</p> <p>Bit 1: Phase V.</p> <p>Bit 2: Phase W.</p> <p>Bit 3: Overcurrent in the DC link.</p>

Note:

Fault value = 0 means that the phase with overcurrent is not recognized.

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 assignment of rated currents of motor and power unit.
- check the line supply quality.
- Reduce motor load.
- Correct connection of line 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.
- check the line supply phases.

F30002 Power unit: DC link voltage overvoltage

Message class: DC-link overvoltage (4)

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.
- line phase interrupted.
- DC-link voltage control switched off.
- dynamic response of DC-link voltage controller excessive or insufficient.

Fault value (r0949, interpret decimal):

DC link voltage at the time of trip [0.1 V].

Remedy:

- increase the ramp-down time (p1121).
 - set the rounding times (p1130, p1136). This is particularly recommended in U/f operation to relieve the DC link voltage controller with rapid ramp-down times of the ramp-function generator.
 - Activate the DC link voltage controller (p1240, p1280).
 - adapt the dynamic response of the DC-link voltage controller (p1243, p1247, p1283, p1287).
 - check the line supply voltage and setting in p0210.
 - check and correct the phase assignment at the power unit.
 - check the line supply phases.
- See also: p0210 (Drive unit line supply voltage), p1240 (Vdc controller configuration (vector control))

F30003 Power unit: DC link voltage undervoltage

Message class: Infeed faulted (13)

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 phase interrupted.

Note:

The monitoring threshold for the DC link undervoltage is the minimum of the following values:

- for a calculation, refer to p0210.

Remedy:

- check the line supply voltage
 - check the line supply phases.
- See also: p0210 (Drive unit line supply voltage)

F30004 Power unit: Overtemperature heat sink AC inverter

Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The temperature of the power unit heat sink has exceeded the permissible limit value.</p> <ul style="list-style-type: none">- insufficient cooling, fan failure.- overload.- ambient temperature too high.- pulse frequency too high. <p>Fault value (r0949): Temperature [1 bit = 0.01 °C].</p>
Remedy:	<ul style="list-style-type: none">- 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. <p>Notice: This fault can only be acknowledged after the alarm threshold for alarm A05000 has been undershot. See also: p1800 (Pulse frequency setpoint)</p>

F30005 Power unit: Overload I2t

Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The power unit was overloaded (r0036 = 100 %).</p> <ul style="list-style-type: none">- the permissible rated power unit current was exceeded for an inadmissibly long time.- the permissible load duty cycle was not maintained. <p>Fault value (r0949, interpret decimal): I2t [100 % = 16384].</p>
Remedy:	<ul style="list-style-type: none">- reduce the continuous load.- adapt the load duty cycle.- check the motor and power unit rated currents.- reduce the current limit (p0640).- during operation with U/f characteristic: reduce the integral time of the current limiting controller (p1341). <p>See also: r0036 (Power unit overload I2t), r0206 (Rated power unit power), p0307 (Rated motor power)</p>

F30011 Power unit: Line phase failure in main circuit

Message class:	Network fault (2)
Reaction:	OFF2 (OFF1)
Acknowledge:	IMMEDIATELY
Cause:	<p>At the power unit, the DC link voltage ripple has exceeded the permissible limit value.</p> <p>Possible causes:</p> <ul style="list-style-type: none">- A line phase has failed.- The 3 line phases are inadmissibly unsymmetrical.- The capacitance of the DC link capacitor forms a resonance frequency with the line inductance and the reactor integrated in the power unit.- the fuse of a phase of a main circuit has ruptured.- A motor phase has failed. <p>Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none">- check the main circuit fuses.- Check whether a single-phase load is distorting the line voltages.- Detune the resonant frequency with the line inductance by using an upstream line reactor.

- Dampen the resonant frequency with the line inductance by switching over the DC link voltage compensation in the software (see p1810) – or increase the smoothing (see p1806). However, this can have a negative impact on the torque ripple at the motor output.
- check the motor feeder cables.

F30012 Power unit: Temperature sensor heat sink wire breakage

Message class: Power electronics faulted (5)
Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: The connection to a heat sink temperature sensor 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
Remedy: Contact the manufacturer.

F30013 Power unit: Temperature sensor heat sink short-circuit

Message class: Power electronics faulted (5)
Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: The heat sink temperature sensor in the power unit 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.

F30015 (N, A) Power unit: Phase failure motor cable

Message class: Application/technological function faulted (17)
Reaction: OFF2 (NONE, OFF1, OFF3)
Acknowledge: IMMEDIATELY
Cause: A phase failure in the motor feeder cable was detected.
 The signal can also be output in the following cases:
 - The motor is correctly connected, but the drive has stalled in U/f control. In this case, a current of 0 A is possibly measured in one phase due to asymmetry of the currents.
 - the motor is correctly connected, however the closed-speed control is instable and therefore an oscillating torque is generated.
 Note:
 Chassis power units do not feature phase failure monitoring.
Remedy:

- check the motor feeder cables.
- increase the ramp-up or ramp-down time (p1120) if the drive has stalled in U/f control.
- check the speed controller settings.

A30016 (N)	Power unit: Load supply switched out
Message class:	Network fault (2)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The DC link voltage is too low. Alarm value (r2124, interpret decimal): DC link voltage at the time of trip [0.1 V].
Remedy:	Under certain circumstances, the AC line supply is not switched on.
F30017	Power unit: Hardware current limit has responded too often
Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	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. - 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. Fault value (r0949, interpret binary): Bit 0: Phase U Bit 1: Phase V Bit 2: Phase W
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. - replace power unit.
F30021	Power unit: Ground fault
Message class:	Ground fault / inter-phase short-circuit detected (7)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The power has detected a ground fault. Possible causes: - ground fault in the power cables. - Ground fault at the motor. - CT defective. - when the brake closes, this causes the hardware DC current monitoring to respond. - short-circuit at the braking resistor. Fault value (r0949, interpret decimal): 0: - the hardware DC current monitoring has responded. - short-circuit at the braking resistor. > 0: Absolute value, summation current [32767 = 271 % rated current].
Remedy:	- check the power cable connections. - check the motor. - check the CT. - check the cables and contacts of the brake connection (a wire is possibly broken). - check the braking resistor. See also: p0287 (Ground fault monitoring thresholds)

F30022	Power unit: Monitoring U_{ce}
Message class:	Ground fault / inter-phase short-circuit detected (7)
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: - fiber-optic cable interrupted. - power supply of the IGBT gating module missing. - short-circuit at the power unit 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 fiber-optic cable and if required, replace. - check the power supply of the IGBT gating module (24 V). - check the power cable connections. - select the defective semiconductor and replace.

F30024	Power unit: Overtemperature thermal model
Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The temperature difference between the heat sink and chip 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. See also: r0037 (Power unit temperatures)
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. - if DC braking is active: reduce braking current (p1232).

F30025	Power unit: Chip overtemperature
Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	The 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, interpret decimal): Temperature difference between the heat sink and chip [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 the alarm threshold for alarm A05001 has been undershot.

See also: r0037 (Power unit temperatures)

F30027

Power unit: Precharging DC link time monitoring

Message class: Infeed faulted (13)

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The power unit DC link was not able to be pre-charged within the expected time.

- 1) There is no line supply voltage connected.
- 2) The line contactor/line side switch has not been closed.
- 3) The line supply voltage is too low.
- 4) Line supply voltage incorrectly set (p0210).
- 5) The pre-charging resistors are overheated as there were too many pre-charging operations per time unit.
- 6) The pre-charging resistors are overheated as the DC link capacitance is too high.
- 7) The DC link has either a ground fault or a short-circuit.
- 8) Pre-charging circuit may be defective.

Fault value (r0949, interpret binary):

yyyyxxxx hex:

yyyy = power unit state

0: Fault status (wait for OFF and fault acknowledgement).

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 bridging contactor to open -> change into the fault state.

5: Wait for bridging contactor to open -> change into restart inhibit.

6: Commissioning.

7: Ready for pre-charging.

8: Pre-charging started, DC link voltage less 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: Reserved.

xxxx = Missing internal enable signals, power unit (inverted bit-coded, FFFF hex -> all internal enable signals available)

Bit 0: Power supply of the IGBT gating shut down.

Bit 1: Ground fault detected.

Bit 2: Peak current intervention.

Bit 3: I2t exceeded.

Bit 4: Thermal model overtemperature calculated.

Bit 5: (heat sink, gating module, power unit) overtemperature measured.

Bit 6: Reserved.

Bit 7: Overvoltage detected.

Bit 8: Power unit has completed pre-charging, ready for pulse enable.

Bit 9: Reserved.

Bit 10: Overcurrent detected.

Bit 11: Reserved.

Bit 12: Reserved.

Bit 13: Vce fault detected, transistor de-saturated due to overcurrent/short-circuit.

Bit 14: Undervoltage detected.

See also: p0210 (Drive unit line supply voltage)

Remedy:

In general:

- check the line supply voltage at the input terminals.
- check the line supply voltage setting (p0210).
- wait until the pre-charging resistors have cooled down. For this purpose, preferably disconnect the infeed unit from the line supply.

Re 5):

- carefully observe the permissible pre-charging frequency (refer to the appropriate Equipment Manual).

Re 6):

- check the capacitance of the DC link and, if necessary, reduce it in accordance with the maximum permissible DC link capacitance (see relevant Equipment Manual).

Re 7):

- check the DC link for a ground fault or short circuit.

See also: p0210 (Drive unit line supply voltage)

A30030 Power unit: Internal overtemperature alarm

Message class: Power electronics faulted (5)

Reaction: NONE

Acknowledge: NONE

Cause: The temperature inside the drive converter has exceeded the permissible temperature limit.

- insufficient cooling, fan failure.

- overload.

- ambient temperature too high.

Alarm value (r2124, interpret decimal):

Only for internal Siemens troubleshooting.

Remedy:

- possibly use an additional fan.
- check whether the ambient temperature is in the permissible range.

Notice:

This fault can only be acknowledged once the permissible temperature limit minus 5 K has been fallen below.

A30031 Power unit: Hardware current limiting in phase U

Message class: Power electronics faulted (5)

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.

Note:

Alarm A30031 is always output if, for a Power Module, the hardware current limiting of phase U, V or W responds.

Remedy:

- check the motor data and if required, recalculate the control parameters (p0340 = 3). As an alternative, run a motor data identification (p1910 = 1, p1960 = 1).

- 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 in phase V
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	Hardware current limit for phase V responded. The pulsing in this phase is inhibited for one pulse period. <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. Note: Alarm A30031 is always output if, for a Power Module, the hardware current limiting of phase U, V or W responds.
Remedy:	Check the motor data and if required, recalculate the control parameters (p0340 = 3). As an alternative, run a motor data identification (p1910 = 1, p1960 = 1). <ul style="list-style-type: none">- 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 in phase W
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	Hardware current limit for phase W responded. The pulsing in this phase is inhibited for one pulse period. <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. Note: Alarm A30031 is always output if, for a Power Module, the hardware current limiting of phase U, V or W responds.
Remedy:	<ul style="list-style-type: none">- check the motor data and if required, recalculate the control parameters (p0340 = 3). As an alternative, run a motor data identification (p1910 = 1, p1960 = 1).- 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.
A30034	Power unit: Internal overtemperature
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The alarm threshold for internal overtemperature has been reached. If the temperature inside the unit continues to increase, fault F30036 may be triggered. <ul style="list-style-type: none">- ambient temperature might be too high.- insufficient cooling, fan failure. Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	<ul style="list-style-type: none">- check the ambient temperature.- check the fan for the inside of the unit.

F30035 Power unit: Air intake overtemperature

Message class: Power electronics faulted (5)
Reaction: OFF1 (OFF2)
Acknowledge: IMMEDIATELY
Cause: The air intake in the power unit has exceeded the permissible temperature limit.
For air-cooled power units, the temperature limit is at 55 °C.
- ambient temperature too high.
- insufficient cooling, fan failure.
Fault value (r0949, interpret decimal):
Temperature [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 the alarm threshold for alarm A05002 has been undershot.

F30036 Power unit: Internal overtemperature

Message class: Power electronics faulted (5)
Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The temperature inside the drive converter has exceeded the permissible temperature limit.
- insufficient cooling, fan failure.
- overload.
- ambient temperature too high.
Fault value (r0949, interpret decimal):
Only for internal Siemens troubleshooting.
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 once the permissible temperature limit minus 5 K has been fallen below.

F30037 Power unit: Rectifier overtemperature

Message class: Power electronics faulted (5)
Reaction: OFF2
Acknowledge: IMMEDIATELY
Cause: The temperature in the rectifier of the power unit has exceeded the permissible temperature limit.
- insufficient cooling, fan failure.
- overload.
- ambient temperature too high.
- line supply phase failure.
Fault value (r0949, interpret decimal):
Temperature [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 the alarm threshold for alarm A05004 has been undershot.

A30042	Power unit: Fan has reached the maximum operating hours
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>The maximum operating time of at least one fan will soon be reached, or has already been exceeded.</p> <p>Fault value (r0949, interpret binary):</p> <p>Bit 0: heat sink fan will reach the maximum operating time in 500 hours.</p> <p>Bit 1: heat sink fan has exceeded the maximum operating time.</p> <p>Bit 8: internal device fan will reach the maximum operating time in 500 hours.</p> <p>Bit 9: internal device fan has exceeded the maximum operating time.</p> <p>Note:</p> <p>The maximum operating time of the heat sink fan in the power unit is displayed in p0252.</p> <p>The maximum operating time of the internal device fan in the power unit is internally specified and is fixed.</p>
Remedy:	<p>For the fan involved, carry out the following:</p> <ul style="list-style-type: none"> - replace the fan. - reset the operating hours counter (p0251, p0254).
A30049	Power unit: Internal fan faulty
Message class:	Auxiliary unit faulted (20)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The internal fan has failed.
Remedy:	Check the internal fan and replace if necessary.
F30051	Power unit: Motor holding brake short circuit detected
Message class:	External measured value / signal state outside the permissible range (16)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>A short-circuit at the motor holding brake terminals has been detected.</p> <p>Fault value (r0949, interpret decimal):</p> <p>Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - check the motor holding brake for a short-circuit. - check the connection and cable for the motor holding brake.
F30052	EEPROM data error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	<p>EEPROM data error of the power unit module.</p> <p>Fault value (r0949, interpret decimal):</p> <p>0, 2, 3, 4:</p> <p>The EEPROM data read in from the power unit module is inconsistent.</p> <p>1:</p> <p>EEPROM data is not compatible to the firmware of the Control Unit.</p>
Remedy:	Replace power unit module.
A30054 (F, N)	Power unit: Undervoltage when opening the brake
Message class:	Supply voltage fault (undervoltage) (3)
Reaction:	NONE
Acknowledge:	NONE
Cause:	<p>When the brake is being opened, it is detected that the power supply voltage is less than 21.4 V</p> <p>Alarm value (r2124, interpret decimal):</p> <p>Supply voltage fault [0.1 V].</p> <p>Example:</p> <p>Alarm value = 195 --> voltage = 19.5 V</p>

Remedy: Check the 24 V voltage for stability and value.

F30055 Power unit: Braking chopper overcurrent

Message class: Braking Module faulted (14)

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: An overcurrent condition has occurred in the braking chopper.

Remedy: - check whether the braking resistor has a short circuit.
- for an external braking resistor, check whether the resistor may have been dimensioned too small.

Note:

The braking chopper is only enabled again at pulse enable after the fault has been acknowledged.

A30057 Power unit: Line asymmetry

Message class: Network fault (2)

Reaction: NONE

Acknowledge: NONE

Cause: Frequencies have been detected on the DC link voltage that would suggest line asymmetry or failure of a line phase. It is also possible that a motor phase has failed.

Fault F30011 is output if the alarm is present and at the latest after 5 minutes.

The precise duration depends on the power unit type and the particular frequencies. For booksize and chassis power units, the duration also depends on how long the alarm has been active.

Alarm value (r2124, interpret decimal):

Only for internal Siemens troubleshooting.

Remedy: - check the line phase connection.
- check the motor feeder cable connections.
If there is no phase failure of the line or motor, then line asymmetry is involved.
- reduce the power in order to avoid fault F30011.

F30059 Power unit: Internal fan faulty

Message class: Auxiliary unit faulted (20)

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: The internal power unit fan has failed and is possibly defective.

Remedy: Check the internal fan and replace if necessary.

A30065 (F, N) Voltage measured values not plausible

Message class: Power electronics faulted (5)

Reaction: NONE

Acknowledge: NONE

Cause: The voltage measurement is not supplying any plausible values

Alarm value (r2124, interpret bitwise binary):

Bit 1: Phase U.

Bit 2: Phase V.

Bit 3: Phase W.

Remedy: - Deactivate voltage measurement (p0247.0 = 0).
- Deactivate flying restart with voltage measurement (p0247.5 = 0) and deactivate fast flying restart (p1780.11 = 0).

F30071 No new actual values received from the Power Module

Message class: Internal (DRIVE-CLiQ) communication error (12)

Reaction: OFF2

Acknowledge: IMMEDIATELY

Cause: More than one actual value telegram from the power unit module has failed.

Remedy: Check the interface (adjustment and locking) to the power unit module.

F30072	Setpoints can no longer be transferred to the Power Module
Message class:	Internal (DRIVE-CLiQ) communication error (12)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	More than one setpoint telegram was not able to be transferred to the power unit module.
Remedy:	Check the interface (adjustment and locking) to the power unit module.
F30074 (A)	Communication error between the Control Unit and Power Module
Message class:	Internal (DRIVE-CLiQ) communication error (12)
Reaction:	NONE
Acknowledge:	IMMEDIATELY
Cause:	<p>Communications between the Control Unit (CU) and Power Module (PM) via the interface no longer possible. The CU may have been withdrawn or is incorrectly inserted.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>0 hex:</p> <ul style="list-style-type: none">- a Control Unit with external 24 V supply was withdrawn from the Power Module during operation.- with the Power Module switched off, the external 24 V supply for the Control Unit was interrupted for some time. <p>1 hex:</p> <p>The Control Unit was withdrawn from the Power Module during operation, although the encoderless safe motion monitoring functions are enabled. This is not supported. After re-inserting the Control Unit in operation, communications to the Power Module no longer possible.</p> <p>20A hex:</p> <p>The Control Unit was inserted on a Power Module, which has another code number.</p> <p>20B hex:</p> <p>The Control Unit was inserted on a Power Module, which although it has the same code number, has a different serial number. The Control Unit executes an automatic warm restart to accept the new calibration data.</p>
Remedy:	<p>For fault value = 0 and 20A hex:</p> <p>Insert the Control Unit on an appropriate Power Module and continue operation. If required, carry out a POWER ON of the Control Unit.</p> <p>For fault value = 1 hex:</p> <p>Carry out a POWER ON of the Control Unit.</p>
F30075	Configuration of the power unit unsuccessful
Message class:	Internal (DRIVE-CLiQ) communication error (12)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>A communication error has occurred while configuring the power unit using the Control Unit. The cause is not clear.</p> <p>Fault value (r0949, interpret decimal):</p> <p>0:</p> <p>The output filter initialization was unsuccessful.</p> <p>1:</p> <p>Activation/deactivation of the regenerative feedback functionality was unsuccessful.</p>
Remedy:	<ul style="list-style-type: none">- acknowledge the fault and continue operation.- if the fault reoccurs, carry out a POWER ON (switch off/on).- if required, replace the power unit.
F30080	Power unit: Current increasing too quickly
Message class:	Power electronics faulted (5)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	<p>The power unit has detected an excessive rate of rise in the overvoltage range.</p> <ul style="list-style-type: none">- 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 current of motor much greater than that of power unit.- power cables are not correctly connected.

- power cables exceed the maximum permissible length.
- power unit defective.

Fault value (r0949, interpret bitwise binary):

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 assignment of rated currents of motor and power unit.
- 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.

F30081

Power unit: Switching operations too frequent

Message class:

Power electronics faulted (5)

Reaction:

OFF2

Acknowledge:

IMMEDIATELY

Cause:

The power unit has executed too many switching operations for current limitation.

- 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 current of motor much greater than that of power unit.
- power cables are not correctly connected.
- power cables exceed the maximum permissible length.
- power unit defective.

Fault value (r0949, interpret bitwise binary):

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 assignment of rated currents of motor and power unit.
- 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.

F30105

PU: Actual value sensing fault

Message class:

Power electronics faulted (5)

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.

A30502 Power unit: DC link overvoltage

Message class: DC-link overvoltage (4)
Reaction: NONE
Acknowledge: NONE
Cause: The power unit has detected overvoltage in the DC link on a pulse inhibit.
- device connection voltage too high.
- line reactor incorrectly dimensioned.
Alarm value (r0949, interpret decimal):
DC link voltage [1 bit = 100 mV].
See also: r0070 (Actual DC link voltage)
Remedy: - check the device supply voltage (p0210).
- check the dimensioning of the line reactor.
See also: p0210 (Drive unit line supply voltage)

F30600 SI P2: STOP A initiated

Message class: Safety monitoring channel has identified an error (10)
Reaction: OFF2
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The drive-integrated "Safety Integrated" function on processor 2 has detected an error and initiated a STOP A.
- forced checking procedure (test stop) of the safety shutdown path on processor 2 unsuccessful.
- subsequent response to fault F30611 (defect in a monitoring channel).
Fault value (r0949, interpret decimal):
0: Stop request from processor 1.
1005: Pulses suppressed although STO not selected and there is no internal STOP A present.
1010: Pulses enabled although STO is selected or an internal STOP A is present.
1011: Internal fault for the pulse enable in the Power Module.
9999: Subsequent response to fault F30611.
Remedy: - select Safe Torque Off and de-select again.
- Carry out a POWER ON (power off/on) for all components.
- replace Power Module involved.
For fault value = 9999:
- carry out diagnostics for fault F30611.
Note:
PM: Power Module
STO: Safe Torque Off

F30611 (A) SI P2: Defect in a monitoring channel

Message class: Safety monitoring channel has identified an error (10)
Reaction: NONE (OFF1, OFF2, OFF3)
Acknowledge: IMMEDIATELY (POWER ON)
Cause: The drive-integrated "Safety Integrated" function on processor 2 has detected a fault in the crosswise data comparison between the two monitoring channels and has initiated a STOP F.
As a consequence of this fault, fault F30600 (SI P2: STOP A initiated) is output.
Fault value (r0949, interpret decimal):
0: Stop request from processor 1.
1 ... 999:
Number of the cross-compared data that resulted in this fault. This number is also displayed in r9795.
2: SI enable safety functions (p9601, p9801). Crosswise data comparison is only carried out for the supported bits.
3: SI F-DI changeover discrepancy time (p9650, p9850).
8: SI PROFIsafe address (p9610, p9810).
9: SI debounce time for STO (p9651, p9851).

1000: Watchdog timer has expired.
Within the time of approx. 5 x p9650, alternatively, the following was defined:

- The signal at F-DI continually changed with time intervals less than or equal to the discrepancy time (p9650/p9850).
- Via PROFIsafe, STO (also as subsequent response) was continually selected and deselected with time intervals less than or equal to the discrepancy time (p9650/p9850).

1001, 1002: Initialization error, change timer / check timer.
2000: Status of the STO selection for both monitoring channels are different.
2001: Feedback of the safe pulse suppression on the two monitoring channels are different.
2002: Statuses of the delay timer SS1 on both monitoring channels are different (status of the timer in p9650/p9850).
2003: Status of the STO terminal on the processor 1 and processor 2 are different.
6000 ... 6999:
Error in the PROFIsafe control.
For these fault values, the failsafe control signals (failsafe values) are transferred to the safety functions.
The significance of the individual message values is described in safety fault F01611.

Remedy:
Re fault values 1 ... 999 described in "Cause":

- check the cross data comparison that resulted in a STOP F.
- carry out a POWER ON (power off/on).

For fault value = 1000:

- check the wiring of the F-DI (contact problems).
- PROFIsafe: Remove contact problems/faults at the PROFIBUS master/PROFINET controller.
- check the discrepancy time, and if required, increase the value (p9650/p9850).

Re fault value = 1001, 1002:

- carry out a POWER ON (power off/on).

For fault value = 2000, 2001, 2002, 2003:

- check the discrepancy time, and if required, increase the value (p9650/p9850).
- check the wiring of the F-DI (contact problems).
- check the causes of the STO selection in r9772.

Re fault value = 6000 ... 6999:
Refer to the description of the message values in safety fault F01611.
Re fault values that are described in "Cause":

- carry out a POWER ON (power off/on).
- contact the Hotline.
- replace Control Unit.

Note:
F-DI: Failsafe Digital Input
STO: Safe Torque Off

N30620 (F, A)	SI P2: Safe Torque Off active
Message class:	Safety monitoring channel has identified an error (10)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The "Safe Torque Off" (STO) function has been selected on processor 2 using the input terminal and is active. Note: This message does not result in a safety stop response.
Remedy:	Not necessary. Note: STO: Safe Torque Off
F30625	SI P2: Sign-of-life error in safety data
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-integrated "Safety Integrated" function on processor 2 has detected an error in the sign-of-life of the safety data and initiated a STOP A. - there is a communication error between processor 1 and processor 2 or communication has failed. - a time slice overflow of the safety software has occurred.

	Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	<ul style="list-style-type: none">- select Safe Torque Off and de-select again.- carry out a POWER ON (power off/on).- check whether additional faults are present and if required, perform diagnostics.- check the electrical cabinet design and cable routing for EMC compliance

F30649 SI P2: Internal software error

Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	An internal error in the Safety Integrated software on processor 2 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:	<ul style="list-style-type: none">- carry out a POWER ON (power off/on).- re-commission the "Safety Integrated" function and carry out a POWER ON.- contact the Hotline.- replace Control Unit.

F30650 SI P2: Acceptance test required

Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-integrated "Safety Integrated" function on processor 2 requires an acceptance test. Note: This fault results in a STOP A that can be acknowledged. Fault value (r0949, interpret decimal): 130: Safety parameters for processor 2 not available. Note: This fault value is always output when Safety Integrated is commissioned for the first time. 1000: Reference and actual checksum on processor 2 are not identical (booting). - at least one checksum-checked piece of data is defective. - Safety parameters set offline and loaded into the Control Unit. 2000: Reference and actual checksum on processor 2 are not identical (commissioning mode). - reference checksum incorrectly entered on processor 2 (p9899 not equal to r9898). 2003: Acceptance test is required as a safety parameter has been changed. 2010: Enable of safety-related brake control between the two monitoring channels differ (p9602 not equal to p9802). 9999: Subsequent response of another safety-related fault that occurred when booting that requires an acceptance test.
Remedy:	For fault value = 130: - carry out safety commissioning routine. For fault value = 1000: - again carry out safety commissioning routine. - replace the memory card or Control Unit. - Using STARTER, activate the safety parameters for the drive involved (change settings, copy parameters, activate settings). For fault value = 2000: - check the safety parameters on processor 2 and adapt the reference checksum (p9899). For fault value = 2003: - Carry out an acceptance test and generate an acceptance report. For fault value = 2010: - check the enable the safety-related brake control on both monitoring channels (p9602 = p9802).

For fault value = 9999:

- carry out diagnostics for the other safety-related fault that is present.

See also: p9799 (SI setpoint checksum SI parameters (processor 1)), p9899 (SI setpoint checksum SI parameters (processor 2))

F30651	SI P2: Synchronization with Control Unit unsuccessful
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	The drive-integrated "Safety Integrated" function requires synchronization of the safety time slices on processor 1 and processor 2. This synchronization was unsuccessful. Note: This fault results in a STOP A that cannot be acknowledged. Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	Carry out a POWER ON (power off/on).
F30655	SI P2: Align monitoring functions
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	An error has occurred when aligning the Safety Integrated monitoring functions on processor 1 and processor 2. No common set of supported SI monitoring functions was able to be determined. - there is a communication error between processor 1 and processor 2 or communication has failed. 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). - check the electrical cabinet design and cable routing for EMC compliance
F30656	SI P2: Parameter processor 2 parameter error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	When accessing the Safety Integrated parameters for the processor 2 in the non-volatile memory, an error has occurred. Note: This fault results in a STOP A that can be acknowledged. Fault value (r0949, interpret decimal): 129: Safety parameters for processor 2 corrupted. 131: Internal software error on processor 1. 255: Internal software error on processor 2.
Remedy:	- re-commission the safety functions. - replace the memory card or Control Unit. For fault value = 129: - activate the safety commissioning mode (p0010 = 95). - start the copy function for SI parameters (p9700 = D0 hex). - acknowledge data change (p9701 = DC hex). - exit the safety commissioning mode (p0010 = 0). - save all parameters (p0971 = 1 or "copy RAM to ROM"). - carry out a POWER ON (power off/on) for the Control Unit.

F30659	SI P2: Write request for parameter rejected
Message class:	Error in the parameterization / configuration / commissioning procedure (18)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY (POWER ON)
Cause:	<p>The write request for one or several Safety Integrated parameters on processor 2 was rejected.</p> <p>Note:</p> <p>This fault does not result in a safety stop response.</p> <p>Fault value (r0949, interpret decimal):</p> <p>10: An attempt was made to enable the STO function although this cannot be supported.</p> <p>15: An attempt was made to enable the motion monitoring functions integrated in the drive although these cannot be supported.</p> <p>16: An attempt was made to enable the PROFIsafe communications although this cannot be supported.</p> <p>18: An attempt was made to enable the PROFIsafe function for Basic Functions although this cannot be supported.</p> <p>20: An attempt was made to simultaneously enable both the drive-integrated motion monitoring functions via integrated F-DI and STO via terminals, even though these cannot be supported at the same time.</p> <p>28: An attempt was made to enable the "STO via terminals at the Power Module" function although this cannot be supported.</p> <p>See also: r9771 (SI common functions (processor 1)), r9871 (SI common functions (processor 2))</p>
Remedy:	<p>For fault value = 10, 15, 16, 18:</p> <ul style="list-style-type: none"> - check whether there are faults in the safety function alignment (F01655, F30655) and if required, carry out diagnostics for the faults involved. - use a Control Unit that supports the required function. <p>For fault value = 28:</p> <ul style="list-style-type: none"> - Use the power unit with the feature "STO via terminals at the Power Module". <p>Note:</p> <p>F-DI: Failsafe Digital Input</p> <p>STO: Safe Torque Off</p>
F30662	Error in internal communications
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	<p>A module-internal communication error has occurred.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - carry out a POWER ON (power off/on). - upgrade firmware to later version. - contact the Hotline.
F30664	Error while booting
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	<p>An error has occurred during booting.</p> <p>Fault value (r0949, interpret hexadecimal):</p> <p>Only for internal Siemens troubleshooting.</p>
Remedy:	<ul style="list-style-type: none"> - carry out a POWER ON (power off/on). - upgrade firmware to later version. - contact the Hotline.
F30665	SI P2: System is defective
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	A system defect was detected before the last boot or in the actual one. The system might have been rebooted (reset).

	<p>Fault value (r0949, interpret hexadecimal): 200000 hex, 400000 hex:</p> <ul style="list-style-type: none"> - Fault in the actual booting/operation. <p>Additional values:</p> <ul style="list-style-type: none"> - defect before the last time that the system booted. <p>Remedy:</p> <ul style="list-style-type: none"> - carry out a POWER ON (power off/on). - upgrade firmware to later version. - contact the Hotline. <p>Re fault value = 400000 hex:</p> <ul style="list-style-type: none"> - ensure that the Control Unit is connected to the Power Module.
A30693 (F)	<p>SI P2: Safety parameter settings changed, POWER ON required</p> <p>Message class: Error in the parameterization / configuration / commissioning procedure (18)</p> <p>Reaction: NONE</p> <p>Acknowledge: NONE</p> <p>Cause: Safety parameters have been changed; these will only take effect following a POWER ON.</p> <p>Notice:</p> <p>All changed parameters of the safety motion monitoring functions will only take effect following a POWER ON.</p> <p>Alarm value (r2124, interpret decimal):</p> <p>Parameter number of the safety parameter which has changed, necessitating a POWER ON.</p> <p>Remedy:</p> <ul style="list-style-type: none"> - execute the function "Copy RAM to ROM". - carry out a POWER ON (power off/on).
A30788	<p>Automatic test stop: wait for STO deselection via SMM</p> <p>Message class: Safety monitoring channel has identified an error (10)</p> <p>Reaction: NONE</p> <p>Acknowledge: NONE</p> <p>Cause: The automatic test stop was not able to be carried out after powering up.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> - The STO function is selected via Safety Extended Functions. - A safety message is present, that resulted in a STO. <p>Remedy:</p> <ul style="list-style-type: none"> - Deselect STO via Safety Extended Functions. - Remove the cause of the safety messages and acknowledge the messages. <p>The automatic test stop is performed after removing the cause.</p>
N30800 (F)	<p>Power unit: Group signal</p> <p>Message class: Power electronics faulted (5)</p> <p>Reaction: OFF2</p> <p>Acknowledge: NONE</p> <p>Cause: The power unit has detected at least one fault.</p> <p>Remedy: Evaluate the other messages that are presently available.</p>
F30802	<p>Power unit: Time slice overflow</p> <p>Message class: Hardware/software error (1)</p> <p>Reaction: OFF2</p> <p>Acknowledge: IMMEDIATELY</p> <p>Cause: A time slice overflow has occurred.</p> <p>Fault value (r0949, interpret decimal):</p> <p>xx: Time slice number xx</p> <p>Remedy:</p> <ul style="list-style-type: none"> - Carry out a POWER ON (power off/on) for all components. - upgrade firmware to later version. - contact the Hotline.

F30804 (N, A)	Power unit: CRC
Message class:	Hardware/software error (1)
Reaction:	OFF2 (OFF1, OFF3)
Acknowledge:	IMMEDIATELY
Cause:	A CRC error has occurred for the power unit.
Remedy:	<ul style="list-style-type: none">- Carry out a POWER ON (power off/on) for all components.- upgrade firmware to later version.- contact the Hotline.

F30805	Power unit: EEPROM checksum error
Message class:	Hardware/software error (1)
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
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	IMMEDIATELY
Cause:	For 3P gating unit, the following applies: The last switching status word in the setpoint telegram is identified by the end ID. Such an end ID was not found.
Remedy:	<ul style="list-style-type: none">- Carry out a POWER ON (power off/on) for all components.- upgrade firmware to later version.- contact the Hotline.

A30810 (F)	Power unit: Watchdog timer
Message class:	Hardware/software error (1)
Reaction:	NONE
Acknowledge:	NONE
Cause:	When booting it was detected that the cause of the previous reset was an SAC watchdog timer overflow.
Remedy:	<ul style="list-style-type: none">- Carry out a POWER ON (power off/on) for all components.- upgrade firmware to later version.- contact the Hotline.

F30850	Power unit: Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF1 (NONE, OFF2, OFF3)
Acknowledge:	POWER ON
Cause:	An internal software error has occurred in the power unit. Fault value (r0949, interpret decimal): Only for internal Siemens troubleshooting.
Remedy:	<ul style="list-style-type: none">- replace power unit.- if required, upgrade the firmware in the power unit.- contact the Hotline.

F30903	Power unit: I2C bus error occurred
Message class:	Hardware/software error (1)
Reaction:	OFF2 (IASC/DCBRK, NONE, OFF1, OFF3, STOP2)
Acknowledge:	IMMEDIATELY
Cause:	Communications error with an EEPROM or an analog/digital converter. Fault value (r0949, interpret hexadecimal): 80000000 hex: - internal software error. 00000001 hex ... 0000FFFF hex: - module fault.
Remedy:	Re fault value = 80000000 hex: - upgrade firmware to later version. Re fault value = 00000001 hex ... 0000FFFF hex: - replace the module.
A30920 (F)	Temperature sensor fault
Message class:	Power electronics faulted (5)
Reaction:	NONE
Acknowledge:	NONE
Cause:	When evaluating the temperature sensor, an error occurred. Alarm value (r2124, interpret decimal): 1: Wire breakage or sensor not connected (KTY: R > 2120 Ohm). 2: Measured resistance too low (PTC: R < 20 Ohm, KTY: R < 50 Ohm).
Remedy:	- make sure that the sensor is connected correctly. - replace the sensor.
F30950	Power unit: Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF2
Acknowledge:	POWER ON
Cause:	An internal software error has occurred. Fault value (r0949, interpret decimal): Information about the fault source. Only for internal Siemens troubleshooting.
Remedy:	- If necessary, upgrade the firmware in the power unit to a later version. - contact the Hotline.
A30999 (F, N)	Power unit: Unknown alarm
Message class:	Power electronics faulted (5)
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 this component is more recent than the firmware on the Control Unit. Alarm value (r2124, interpret decimal): Alarm number. Note: 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).

F35950	TM: Internal software error
Message class:	Hardware/software error (1)
Reaction:	OFF2 (NONE)
Acknowledge:	POWER ON
Cause:	An internal software error has occurred. Fault value (r0949, interpret decimal): Information about the fault source. Only for internal Siemens troubleshooting.
Remedy:	- If necessary, upgrade the firmware in the Terminal Module to a later version. - contact the Hotline.
A50001 (F)	PROFINET configuration error
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	A PROFINET controller attempts to establish a connection using an incorrect configuring telegram. The "Shared Device" function has been activated (p8929 = 2). Alarm value (r2124, interpret decimal): 10: A/F-CPU configures mixed PZD/PROFIsafe telegram. 13: F-CPU and PROFIsafe is not activated (p9601.3). 15: PROFIsafe telegram of the F-CPU does not match the setting in p9501.30. See also: p9601 (SI enable functions integrated in the drive (processor 1))
Remedy:	Check the configuration of the PROFINET controllers as well as the p8929 setting.
A50010 (F)	PROFINET: Consistency error affecting adjustable parameters
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	A consistency error was detected when activating the configuration (p8925) for the PROFINET interface. The currently set configuration has not been activated. Alarm value (r2124, interpret decimal): 0: general consistency error 1: error in the IP configuration (IP address, subnet mask or standard gateway). 2: Error in the station names. 3: DHCP was not able to be activated, as a cyclic PROFINET connection already exists. 4: a cyclic PROFINET connection is not possible as DHCP is activated. Note: DHCP: Dynamic Host Configuration Protocol See also: p8920 (PN Name of Station), p8921 (PN IP address), p8922 (PN Def Gateway), p8923 (PN Subnet Mask), p8924 (PN DHCP Mode)
Remedy:	- Check the required interface configuration (p8920 and following), correct if necessary, and activate (p8925). or - Reconfigure the station via the "Edit Ethernet node" screen form (e.g. with STARTER commissioning software). See also: p8925 (PN interface configuration)
A50020 (F)	PROFINET: Second controller missing
Message class:	Communication error to the higher-level control system (9)
Reaction:	NONE
Acknowledge:	NONE
Cause:	The PROFINET function "Shared Device" has been activated (p8929 = 2). However, only the connection to a PROFINET controller is present.
Remedy:	Check the configuration of the PROFINET controllers as well as the p8929 setting.

Appendix

Content

A.1	ASCII table (characters that can be displayed)	618
A.2	List of abbreviations	621

A.1 ASCII table (characters that can be displayed)

The following table includes the decimal and hexadecimal notation of ASCII characters that can be displayed (printable).

Table A-1 ASCII table (characters that can be displayed)

Character	Decimal	Hexadecimal	Meaning
	32	20	Space
!	33	21	Exclamation mark
"	34	22	Quotation mark
#	35	23	Number sign
\$	36	24	Dollar
%	37	25	Percent
&	38	26	Ampersand
'	39	27	Apostrophe, closing single quotation mark
(40	28	Opening parenthesis
)	41	29	Closing parenthesis
*	42	2A	Asterisk
+	43	2B	Plus
,	44	2C	Comma
-	45	2D	Hyphen, minus
.	46	2E	Period, decimal point
/	47	2F	Slash, slant
0	48	30	Digit 0
1	49	31	Digit 1
2	50	32	Digit 2
3	51	33	Digit 3
4	52	34	Digit 4
5	53	35	Digit 5
6	54	36	Digit 6
7	55	37	Digit 7
8	56	38	Digit 8
9	57	39	Digit 9
:	58	3A	Colon
;	59	3B	Semicolon
<	60	3C	Less than
=	61	3D	Equals
>	62	3E	Greater than
?	63	3F	Question mark
@	64	40	Commercial At

A.1 ASCII table (characters that can be displayed)

Table A-1 ASCII table (characters that can be displayed), continued

Character	Decimal	Hexadecimal	Meaning
A	65	41	Capital letter A
B	66	42	Capital letter B
C	67	43	Capital letter C
D	68	44	Capital letter D
E	69	45	Capital letter E
F	70	46	Capital letter F
G	71	47	Capital letter G
H	72	48	Capital letter H
I	73	49	Capital letter I
J	74	4A	Capital letter J
K	75	4B	Capital letter K
L	76	4C	Capital letter L
M	77	4D	Capital letter M
N	78	4E	Capital letter N
O	79	4F	Capital letter O
P	80	50	Capital letter P
Q	81	51	Capital letter Q
R	82	52	Capital letter R
S	83	53	Capital letter S
T	84	54	Capital letter T
U	85	55	Capital letter U
V	86	56	Capital letter V
W	87	57	Capital letter W
X	88	58	Capital letter X
Y	89	59	Capital letter Y
Z	90	5A	Capital letter Z
[91	5B	Opening bracket
\	92	5C	Backslash
]	93	5D	Closing bracket
^	94	5E	Circumflex
_	95	5F	Underline
`	96	60	Opening single quotation mark
a	97	61	Small letter a
b	98	62	Small letter b
c	99	63	Small letter c
d	100	64	Small letter d

Table A-1 ASCII table (characters that can be displayed), continued

Character	Decimal	Hexadecimal	Meaning
e	101	65	Small letter e
f	102	66	Small letter f
g	103	67	Small letter g
h	104	68	Small letter h
i	105	69	Small letter i
j	106	6A	Small letter j
k	107	6B	Small letter k
l	108	6C	Small letter l
m	109	6D	Small letter m
n	110	6E	Small letter n
o	111	6F	Small letter o
p	112	70	Small letter p
q	113	71	Small letter q
r	114	72	Small letter r
s	115	73	Small letter s
t	116	74	Small letter t
u	117	75	Small letter u
v	118	76	Small letter v
w	119	77	Small letter w
x	120	78	Small letter x
y	121	79	Small letter y
z	122	7A	Small letter z
{	123	7B	Opening brace
	124	7C	Vertical line
}	125	7D	Closing brace
~	126	7E	Tilde

A.2 List of abbreviations

Note

The following list of abbreviations includes all abbreviations and their meanings used in the entire SINAMICS family of drives.

Abbreviation	Source of abbreviation	Significance
A		
A...	Alarm	Warning
AC	Alternating Current	Alternating current
ADC	Analog Digital Converter	Analog-Digital converter
AI	Analog Input	Analog input
AIM	Active Interface Module	Active Interface Module
ALM	Active Line Module	Active Line Module
AO	Analog Output	Analog output
AOP	Advanced Operator Panel	Advanced Operator Panel
APC	Advanced Positioning Control	Advanced Positioning Control
AR	Automatic Restart	Automatic restart
ASC	Armature Short Circuit	Armature short-circuit
ASCII	American Standard Code for Information Interchange	American coding standard for the exchange of information
AS-i	AS-Interface (Actuator Sensor Interface)	AS interface (open bus system in automation technology)
ASM	Asynchronmotor	Induction motor
B		
BB	Betriebsbedingung	Operation condition
BERO	-	Contactless proximity switch
BI	Binector Input	Binector input
BIA	Berufsgenossenschaftliches Institut für Arbeitssicherheit	BG-Institute for Occupational Safety and Health
BICO	Binector Connector Technology	Binector connector technology
BLM	Basic Line Module	Basic Line Module
BO	Binector Output	Binector output
BOP	Basic Operator Panel	Basic operator panel
C		
C	Capacitance	Capacitance
C...	-	Safety message
CAN	Controller Area Network	Serial bus system
CBC	Communication Board CAN	Communication Board CAN
CBE	Communication Board Ethernet	PROFINET communication module (Ethernet)
CD	Compact Disc	Compact disk
CDS	Command Data Set	Command data set
CF Card	CompactFlash Card	CompactFlash card
CI	Connector Input	Connector input

Abbreviation	Source of abbreviation	Significance
CLC	Clearance Control	Clearance control
CNC	Computer Numerical Control	Computer-supported numerical control
CO	Connector Output	Connector output
CO/BO	Connector Output / Binector Output	Connector Output / Binector Output
COB ID	CAN Object-Identification	CAN Object-Identification
CoL	Certificate of License	Certificate of License
COM	Common contact of a changeover relay	Center contact of a changeover contact
COMM	Commissioning	Startup
CP	Communication Processor	Communications processor
CPU	Central Processing Unit	Central processing unit
CRC	Cyclic Redundancy Check	Cyclic redundancy check
CSM	Control Supply Module	Control Supply Module
CU	Control Unit	Control Unit
CUA	Control Unit Adapter	Control Unit Adapter
CUD	Control Unit DC	Control Unit DC
D		
DAC	Digital Analog Converter	Digital analog converter
DC	Direct Current	DC current
DCB	Drive Control Block	Drive Control Block
DCBRK	DC Brake	DC braking
DCC	Drive Control Chart	Drive Control Chart
DCN	Direct Current Negative	Direct current negative
DCP	Direct Current Positive	Direct current positive
DDS	Drive Data Set	Drive Data Set
DI	Digital Input	Digital input
DI/DO	Digital Input / Digital Output	Digital input/output, bidirectional
DMC	DRIVE-CLiQ Hub Module Cabinet	DRIVE-CLiQ Hub Module Cabinet
DME	DRIVE-CLiQ Hub Module External	DRIVE-CLiQ Hub Module External
DMM	Double Motor Module	Double Motor Module
DO	Digital Output	Digital output
DO	Drive Object	Drive object
DP	Decentralized Peripherals	Distributed I/O
DPRAM	Dual-Port Random Access Memory	Dual-Port Random Access Memory
DQ	DRIVE-CLiQ	DRIVE-CLiQ
DRAM	Dynamic Random Access Memory	Dynamic Random Access Memory
DRIVE-CLiQ	Drive Component Link with IQ	Drive Component Link with IQ
DSC	Dynamic Servo Control	Dynamic Servo Control
DTC	Digital Time Clock	Timer
E		
EASC	External Armature Short-Circuit	External armature short-circuit
EDS	Encoder Data Set	Encoder data set
EEPROM	Electrically Erasable Programmable Read-Only Memory	Electrically Erasable Programmable Read-Only-Memory

Abbreviation	Source of abbreviation	Significance
EGB	Elektrostatisch gefährdete Baugruppen	Electrostatic sensitive devices
ELCB	Earth Leakage Circuit-Breaker	Residual current operated circuit breaker
ELP	Earth Leakage Protection	Ground-fault monitoring
EMC	Electromagnetic Compatibility	Electromagnetic compatibility
EMF	Electromotive Force	Electromotive force
EMK	Elektromotorische Kraft	Electromotive force
EMV	Elektromagnetische Verträglichkeit	Electromagnetic compatibility
EN	Europäische Norm	European Standard
EnDat	Encoder-Data-Interface	Encoder interface
EP	Enable Pulses	Pulse enable
EPOS	Einfachpositionierer	Basic positioner
ES	Engineering System	Engineering system
ESB	Ersatzschaltbild	Equivalent circuit diagram
ESD	Electrostatic Sensitive Devices	Electrostatic sensitive devices
ESM	Essential Service Mode	Essential service mode
ESR	Extended Stop and Retract	Extended stop and retract
F		
F...	Fault	Fault
FAQ	Frequently Asked Questions	Frequently Asked Questions
FBLOCKS	Free Blocks	Free function blocks
FCC	Function Control Chart	Function control chart
FCC	Flux Current Control	Flux current control
FD	Function Diagram	Function diagram
F-DI	Failsafe Digital Input	Failsafe digital input
F-DO	Failsafe Digital Output	Fail-safe digital output
FEPROM	Flash-EPROM	Non-volatile write and read memory
FG	Function Generator	Function Generator
FI	-	Fault current
FOC	Fiber-Optic Cable	Fiber-optic cable
FP	Funktionsplan	Function diagram
FPGA	Field Programmable Gate Array	Field Programmable Gate Array
FW	Firmware	Firmware
G		
GB	Gigabyte	Gigabyte
GC	Global Control	Global control telegram (broadcast telegram)
GND	Ground	Reference potential for all signal and operating voltages, usually defined as 0 V (also referred to as M)
GSD	Gerätestammdatei	Generic Station Description: Describes the features of a PROFIBUS slave
GSV	Gate Supply Voltage	Gate supply voltage
GUID	Globally Unique Identifier	Globally Unique Identifier

Abbreviation	Source of abbreviation	Significance
H		
HF	High frequency	High frequency
HFD	Hochfrequenzdrossel	Radio frequency reactor
HLA	Hydraulic Linear Actuator	Hydraulic linear actuator
HLG	Hochlaufgeber	Ramp-function Generator
HM	Hydraulic Module	Hydraulic Module
HMI	Human Machine Interface	Human Machine Interface
HTL	High-Threshold Logic	Logic with high interference threshold
HW	Hardware	Hardware
I		
i. V.	In Vorbereitung	Under development: This property is currently not available
I/O	Input/Output	Input/output
I2C	Inter-Integrated Circuit	Internal serial data bus
IASC	Internal Armature Short-Circuit	Internal armature short-circuit
IBN	Inbetriebnahme	Startup
ID	Identifier	Identification
IE	Industrial Ethernet	Industrial Ethernet
IEC	International Electrotechnical Commission	International Electrotechnical Commission
IF	Interface	Interface
IGBT	Insulated Gate Bipolar Transistor	Insulated gate bipolar transistor
IGCT	Integrated Gate-Controlled Thyristor	Semiconductor power switch with integrated control electrode
IL	Impulslöschung	Pulse suppression
IP	Internet Protocol	Internet protocol
IPO	Interpolator	Interpolator
IT	Isolé Terre	Non-grounded three-phase line supply
IVP	Internal Voltage Protection	Internal voltage protection
J		
JOG	Jogging	Jogging
K		
KDV	Kreuzweiser Datenvergleich	Data cross-check
KHP	Know-how protection	Know-how protection
KIP	Kinetische Pufferung	Kinetic buffering
Kp	-	Proportional gain
KTY	-	Special temperature sensor
L		
L	-	Symbol for inductance
LED	Light Emitting Diode	Light emitting diode
LIN	Linearmotor	Linear motor
LR	Lageregler	Position controller
LSB	Least Significant Bit	Least Significant Bit
LSC	Line-Side Converter	Line-side converter

Abbreviation	Source of abbreviation	Significance
LSS	Line-Side Switch	Line-side switch
LU	Length Unit	Length unit
LWL	Lichtwellenleiter	Fiber-optic cable
M		
M	-	Symbol for torque
M	Masse	Reference potential for all signal and operating voltages, usually defined as 0 V (also referred to as GND)
MB	Megabyte	Megabyte
MCC	Motion Control Chart	Motion Control Chart
MDI	Manual Data Input	Manual data input
MDS	Motor Data Set	Motor data set
MLFB	Maschinenlesbare Fabrikatebezeichnung	Machine-readable product code
MM	Motor Module	Motor Module
MMC	Man-Machine Communication	Man-machine communication
MMC	Micro Memory Card	Micro memory card
MSB	Most Significant Bit	Most significant bit
MSC	Motor-Side Converter	Motor-side converter
MSCY_C1	Master Slave Cycle Class 1	Cyclic communication between master (class 1) and slave
MSR	Motorstromrichter	Motor-side converter
MT	Messtaster	Probe
N		
N. C.	Not Connected	Not connected
N...	No Report	No report or internal message
NAMUR	Normenarbeitsgemeinschaft für Mess- und Regeltechnik in der chemischen Industrie	Standardization association for measurement and control in chemical industries
NC	Normally Closed (contact)	NC contacts
NC	Numerical Control	Numerical control
NEMA	National Electrical Manufacturers Association	Standardization association in USA (United States of America)
NM	Nullmarke	Zero mark
NO	Normally Open (contact)	NO contacts
NSR	Netzstromrichter	Line-side converter
NVRAM	Non-Volatile Random Access Memory	Non-volatile read/write memory
O		
OA	Open Architecture	Software component (technology package) which provides additional functions for the SINAMICS drive system
OAIF	Open Architecture Interface	Version of the SINAMICS firmware as of which the OA-application can be used
OASP	Open Architecture Support Package	Expands the STARTER commissioning tool by the corresponding OA-application
OC	Operating Condition	Operation condition
OEM	Original Equipment Manufacturer	Original equipment manufacturer

Abbreviation	Source of abbreviation	Significance
OLP	Optical Link Plug	Bus connector for fiber-optic cable
OMI	Option Module Interface	Option Module Interface
P		
p...	-	Adjustable parameters
P1	Processor 1	CPU 1
P2	Processor 2	CPU 2
PB	PROFIBUS	PROFIBUS
PcCtrl	PC Control	Master control
PD	PROFIdrive	PROFIdrive
PDS	Power unit Data Set	Power unit data set
PE	Protective Earth	Protective ground
PELV	Protective Extra Low Voltage	Safety extra-low voltage
PFH	Probability of dangerous failure per hour	Probability of dangerous failure per hour
PG	Programmiergerät	Programming device
PI	Proportional Integral	Proportional integral
PID	Proportional Integral Differential	Proportional integral differential
PLC	Programmable Logical Controller	Programmable logic controller
PLL	Phase-Locked Loop	Phase-locked loop
PM	Power Module	Power Module
PMSM	Permanent-magnet synchronous motor	Permanent-magnet synchronous motor
PN	PROFINET	PROFINET
PNO	PROFIBUS Nutzerorganisation	PROFIBUS user organization
PPI	Point to Point Interface	Point-to-point interface
PRBS	Pseudo Random Binary Signal	White noise
PROFIBUS	Process Field Bus	Serial data bus
PS	Power Supply	Power supply
PSA	Power Stack Adapter	Power Stack Adapter
PTC	Positive Temperature Coefficient	Positive temperature coefficient
PTP	Point To Point	Point-to-point
PWM	Pulse Width Modulation	Pulse width modulation
PZD	Prozessdaten	Process data
Q		
R		
r...	-	Display parameters (read only)
RAM	Random Access Memory	Speicher zum Lesen und Schreiben
RCCB	Residual Current Circuit Breaker	Residual current operated circuit breaker
RCD	Residual Current Device	Residual current operated circuit breaker
RCM	Residual Current Monitor	Residual current monitor
REL	Reluctance motor textile	Reluctance motor textile
RESM	Reluctance synchronous motor	Synchronous reluctance motor
RFG	Ramp-Function Generator	Ramp-function Generator

Abbreviation	Source of abbreviation	Significance
RJ45	Registered Jack 45	Term for an 8-pin socket system for data transmission with shielded or non-shielded multi-wire copper cables
RKA	Rückkühlanlage	Cooling unit
RLM	Renewable Line Module	Renewable Line Module
RO	Read Only	Read only
ROM	Read-Only Memory	Read-only memory
RPDO	Receive Process Data Object	Receive Process Data Object
RS232	Recommended Standard 232	Interface standard for a cable-connected serial data transmission between a sender and receiver (also known as EIA232)
RS485	Recommended Standard 485	Interface standard for a cable-connected differential, parallel, and/or serial bus system (data transmission between a number of senders and receivers, also known as EIA485)
RTC	Real Time Clock	Real-time clock
RZA	Raumzeigerapproximation	Space-vector approximation
S		
S1	-	Continuous operation
S3	-	Intermittent duty
SAM	Safe Acceleration Monitor	Safe acceleration monitoring
SBC	Safe Brake Control	Safe brake control
SBH	Sicherer Betriebshalt	Safe operating stop
SBR	Safe Brake Ramp	Safe brake ramp monitoring
SBT	Safe Brake Test	Safe brake test
SCA	Safe Cam	Safe cam
SD Card	SecureDigital Card	Secure digital memory card
SDI	Safe Direction	Safe motion direction
SE	Sicherer Software-Endschalter	Safe software limit switch
SESM	Separately-excited synchronous motor	Separately excited synchronous motor
SG	Sicher reduzierte Geschwindigkeit	Safely-limited speed
SGA	Sicherheitsgerichteter Ausgang	Safety-related output
SGE	Sicherheitsgerichteter Eingang	Safety-related input
SH	Sicherer Halt	Safe stop
SI	Safety Integrated	Safety Integrated
SIL	Safety Integrity Level	Safety Integrity Level
SLM	Smart Line Module	Smart Line Module
SLP	Safely-Limited Position	Safely Limited Position
SLS	Safely-Limited Speed	Safely-limited speed
SLVC	Sensorless Vector Control	Sensorless vector control
SM	Sensor Module	Sensor Module
SMC	Sensor Module Cabinet	Sensor Module Cabinet
SME	Sensor Module External	Sensor Module External
SMI	SINAMICS Sensor Module Integrated	SINAMICS Sensor Module Integrated

Abbreviation	Source of abbreviation	Significance
SMM	Single Motor Module	Single Motor Module
SN	Sicherer Software-Nocken	Safe software cam
SOS	Safe Operating Stop	Safe operating stop
SP	Service Pack	Service pack
SP	Safe Position	Safe position
SPC	Setpoint Channel	Setpoint channel
SPI	Serial Peripheral Interface	Serial peripheral interface
SPS	Speicherprogrammierbare Steuerung	Programmable logic controller
SS1	Safe Stop 1	Safe Stop 1 (monitored for time and ramp)
SS2	Safe Stop 2	Safe Stop 2
SSI	Synchronous Serial Interface	Synchronous serial interface
SSM	Safe Speed Monitor	Safe feedback from speed monitor
SSP	SINAMICS Support Package	SINAMICS support package
STO	Safe Torque Off	Safe torque off
STW	Steuerwort	Control word
T		
TB	Terminal Board	Terminal Board
TIA	Totally Integrated Automation	Totally Integrated Automation
TM	Terminal Module	Terminal module
TN	Terre Neutre	Grounded three-phase line supply
Tn	-	Integral time
TPDO	Transmit Process Data Object	Transmit Process Data Object
TT	Terre Terre	Grounded three-phase line supply
TTL	Transistor-Transistor-Logik	Transistor-Transistor-Logik
Tv	-	Rate time
U		
UL	Underwriters Laboratories Inc.	Underwriters Laboratories Inc.
UPS	Uninterruptible Power Supply	Uninterruptible power supply
USV	Unterbrechungsfreie Stromversorgung	Uninterruptible power supply
UTC	Universal Time Coordinated	Universal time coordinated
V		
VC	Vector Control	Vector control
Vdc	-	DC-link voltage
VdcN	-	Partial DC-link voltage negative
VdcP	-	Partial DC-link voltage positive
VDE	Verband Deutscher Elektrotechniker	Verband Deutscher Elektrotechniker [Association of German Electrical Engineers]
VDI	Verein Deutscher Ingenieure	Verein Deutscher Ingenieure [Association of German Engineers]
VPM	Voltage Protection Module	Voltage Protection Module
Vpp	Volt peak to peak	Volt peak to peak
VSM	Voltage Sensing Module	Voltage Sensing Module

Abbreviation	Source of abbreviation	Significance
W		
WEA	Wiedereinschaltautomatik	Automatic restart
WZM	Werkzeugmaschine	Machine tool
X		
XML	Extensible Markup Language	Extensible markup language (standard language for Web publishing and document management)
Y		
Z		
ZK	Zwischenkreis	DC link
ZM	Zero Mark	Zero mark
ZSW	Zustandswort	Status Word

Index

Numbers

- 1020
 - Explanation of the symbols (part 1), 362
- 1021
 - Explanation of the symbols (part 2), 363
- 1022
 - Explanation of the symbols (part 3), 364
- 1030
 - Handling BICO technology, 365
- 2201
 - Connection overview, 367
- 2221
 - Digital inputs, electrically isolated (DI 0 ... DI 5), 368
- 2241
 - Digital outputs (DO 0 ... DO 1), 369
- 2250
 - Analog input 0 (AI 0), 370
- 2255
 - Analog inputs, digital inputs (DI 11), 371
- 2260
 - Analog output 0 (AO 0), 372
- 2272
 - Two-wire control, 373
- 2273
 - Three-wire control, 374
- 2381
 - Control commands and interrogation commands, 376
- 2382
 - States, 377
- 2401
 - PROFIdrive / PROFIBUS overview, 379
- 2410
 - PROFIBUS (PB) / PROFINET (PN), addresses and diagnostics, 380
- 2420
 - Telegrams and process data (PZD), 381
- 2440
 - PZD receive signals interconnection, 382
- 2441
 - STW1 control word interconnection (p2038 = 2), 383
- 2442
 - STW1 control word interconnection (p2038 = 0), 384
- 2446
 - STW3 control word interconnection, 385
- 2450
 - PZD send signals interconnection, 386
- 2451
 - ZSW1 status word interconnection (p2038 = 2), 387
- 2452
 - ZSW1 status word interconnection (p2038 = 0), 388
- 2456
 - ZSW3 status word interconnection, 389
- 2468
 - Receive telegram, free interconnection via BICO (p0922 = 999), 390
- 2470
 - Send telegram, free interconnection via BICO (p0922 = 999), 391
- 2501
 - Control word, sequence control, 406
- 2503
 - Status word, sequence control, 407
- 2505
 - Control word, setpoint channel, 408
- 2510
 - Status word 1 (r0052), 409
- 2511
 - Status word 2 (r0053), 410
- 2512
 - Control word 1 (r0054), 411
- 2513
 - Control word 2 (r0055), 412
- 2522
 - Status word, speed controller, 413
- 2526
 - Status word, closed-loop control, 414
- 2530
 - Status word, closed-loop current control, 415
- 2534
 - Status word monitoring functions 1, 416
- 2536
 - Status word monitoring functions 2, 417
- 2537
 - Status word monitoring functions 3, 418
- 2546
 - Control word, faults/alarms, 419
- 2548
 - Status word, faults/alarms 1 and 2, 420
- 2610
 - Sequence control - Sequencer, 421
- 2634
 - Sequence control - Missing enable signals, 422

- 2701
 - Simple brake control, 424
- 2800
 - Parameter manager, 426
- 2802
 - Monitoring functions and faults/alarms, 427
- 2804
 - Status words, 428
- 2810
 - STO, Safe Torque Off, 429
- 2813
 - F-DI, Fail-safe Digital Input, 430
- 2915
 - Standard telegrams, 432
- 3001
 - Overview of setpoint channel, 434
- 3010
 - Fixed speed setpoints, binary selection (p1016 = 2), 435
- 3011
 - Fixed speed setpoints, direct selection (p1016 = 1), 436
- 3020
 - Motorized potentiometer, 437
- 3030
 - Main/supplementary setpoint, setpointscaling, jogging, 438
- 3040
 - Direction limitation and direction reversal, 439
- 3050
 - Skip frequency bands and speedlimitations, 440
- 3070
 - Extended ramp-function generator, 441
- 6019
 - Application classes (p0096), overview, 443
- 6020
 - Speed control and generation of the torque limits, overview, 444
- 6030
 - Speed setpoint, accelerationmodel, 445
- 6035
 - Moment of inertia estimator, 446
- 6040
 - Speed controller, 447
- 6060
 - Torque setpoint, 448
- 6220
 - Vdc_max controller and Vdc_min controller (vector control), 449
- 6300
 - U/f control, overview, 450
- 6301
 - U/f characteristic and voltage boost, 451
- 6310
 - Resonance damping and slip compensation (U/f), 452
- 6320
 - Vdc_max controller (U/f), 453
- 6490
 - Speed control configuration, 454
- 6630
 - Upper/lower torque limit, 455
- 6640
 - Current/power/torque limits, 456
- 6700
 - Current control, overview, 457
- 6710
 - Current setpoint filter, 458
- 6714
 - Iq and Id controllers, 459
- 6721
 - Id setpoint (PMSM, p0300 = 2), 460
- 6722
 - Field weakening characteristic, flux setpoint (ASM, p0300 = 1), 461
- 6723
 - Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1), 462
- 6724
 - Field weakening controller (PMSM, p0300 = 2), 463
- 6730
 - Interface to the Power Module (ASM, p0300 = 1), 464
- 6731
 - Interface to the Power Module (PMSM, p0300 = 2), 465
- 6799
 - Display signals, 466
- 6820
 - Speed control and generation of the torque limits, overview (p0096 = 2), 474
- 6821
 - Current control, overview (p0096 = 2), 475
- 6822
 - Speed setpoint, precontrol symmetrization, acceleration model (p0096 = 2), 476
- 6823
 - Moment of inertia estimator (p0096 = 2), 477
- 6824
 - Speed controller with Kp_n/Tn_n adaptation) (p0096 = 2), 478
- 6826
 - Torque setpoint (p0096 = 2), 479
- 6827
 - Vdc_max controller and Vdc_min controller (p0096 = 2), 480
- 6828
 - Current/power/torque limits (p0096 = 2), 481

- 6832
 - Current setpoint (p0096 = 2), 482
 - 6833
 - Iq and Id controller (p0096 = 2), 483
 - 6836
 - Id setpoint (PMSM, p0300 = 2xx, p0096 = 2), 484
 - 6837
 - Field weakening characteristic, flux setpoint (ASM, p0300 = 1, p0096 = 2), 485
 - 6838
 - Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1, p0096 = 2), 486
 - 6839
 - Field weakening controller (PMSM, p0300 = 2xx, p0096 = 2), 487
 - 6841
 - Interface to the power module (ASM, p0300 = 1, p0096 = 2), 488
 - 6842
 - Interface to the power module (PMSM, p0300 = 2xx, p0096 = 2), 489
 - 6850
 - U/f control, overview (p0096 = 1), 468
 - 6851
 - U/f characteristic and voltage boost (p0096 = 1), 469
 - 6853
 - Resonance damping and slip compensation (U/f) (p0096 = 1), 470
 - 6854
 - Vdc_max controller (p0096 = 1), 471
 - 6856
 - Interface to the power module (ASM, p0300 = 1, p0096 = 1), 472
 - 7017
 - DC brake (p0300 = 1), 491
 - 7950
 - Fixed value selection binary (p2216 = 2), 493
 - 7951
 - Fixed value selection direct (p2216 = 1), 494
 - 7954
 - Motorized potentiometer, 495
 - 7958
 - Closed-loop control, 496
 - 8005
 - Overview, signals and monitoring functions, 498
 - 8010
 - Speed messages 1, 499
 - 8011
 - Speed messages 2, 500
 - 8012
 - Torque signals, motor blocked/stalled, 501
 - 8016
 - Thermal monitoring, motor, 502
 - 8017
 - Thermal motor models, 503
 - 8019
 - Thermal monitoring, power unit, 504
 - 8020
 - Monitoring functions 1, 505
 - 8021
 - Monitoring functions 2, 506
 - 8050
 - Diagnostics overview, 508
 - 8060
 - Fault buffer, 509
 - 8065
 - Alarm buffer, 510
 - 8070
 - Faults/alarms trigger word (r2129), 511
 - 8075
 - Faults/alarms configuration, 512
 - 8560
 - Command Data Sets (CDS), 514
 - 8565
 - Drive Data Sets (DDS), 515
 - 9204
 - Receive telegram, free PDO mapping (p8744 = 2), 393
 - 9206
 - Receive telegram, Predefined Connection Set (p8744 = 1), 394
 - 9208
 - Send telegram, free PDO mapping (p8744 = 2), 395
 - 9210
 - Send telegram, Predefined Connection Set (p8744 = 1), 396
 - 9220
 - Control word CANopen, 397
 - 9226
 - Status word, CANopen, 398
 - 9310
 - Configuration, addresses and diagnostics, 400
 - 9342
 - STW1 control word interconnection, 401
 - 9352
 - ZSW1 status word interconnection, 402
 - 9360
 - Receive telegram, free interconnection via BICO (p0922 = 999), 403
 - 9370
 - Send telegram, free interconnection via BICO (p0922 = 999), 404
- A**
- Acknowledgment
 - Adjustable, 526
 - Default, 526
 - IMMEDIATELY, 521
 - POWER ON, 521
 - PULSE SUPPRESSION, 521

Adjustable parameters, 13

Alarm

- Cause, 526
- Display, 518
- Explanation of list, 522
- Fault location, 523
- General, 518
- How to distinguish an alarm from a fault, 518
- List of all alarms, 529
- Message class, 523
- Name, 523
- Number, 522
- Number range, 22, 527
- Remedy, 526

Alarm buffer, 507

Alarm value, 526

Analog inputs, 366

Analog outputs, 366

ASCII table, 618

Axxxx, 522

B

BI, Binector Input, 14

BICO technology, 365

Binector

- Input (BI), 14
- Output (BO), 14

Bit field (parameter), 21

BO, Binector Output, 14

Brake control, 423

C

Calculated, 15

Can be changed (parameters), 17

CANopen, 392, 399

CDS, (Command Data Set), 18, 513, 514

CI, Connector Input, 14

Closed-loop control

- Technology controller, 496
- Vector, 442
- Vector (Dynamic Drive Control), 473
- Vector (Standard Drive Control), 467

CO, Connector Output, 14

CO/BO, Connector/Binector Output, 14

Command data sets, 513

Connector

- Input (CI), 14
- Output (CO), 14

Control words, 375, 378

Converter

- Connector-binector, 390

Cxxxxx, 522

D

Data Set, 513

- Command Data Set, CDS, 18
- Drive Data Set, DDS, 18
- Encoder Data Set, EDS, 18
- Motor Data Set, MDS, 18
- Power unit Data Set, PDS, 18

Data set, 513

- Command data set, 18
- Drive data set, 18
- Encoder data set, 18
- Motor data set, 18
- Power unit data set, 18

Data type (parameters), 16

DC braking, 491

DCBRAKE, 520

DDS, (Drive Data Set), 18, 513

DDS, (Drive Data Sets), 515

Dependency (parameter), 21

Description (parameter), 20

Digital inputs, 366

Digital outputs, 366

Direction of rotation limiting, 433

Direction reversal, 433

Directory

- ASCII table, 618
- Complete table of contents, 5
- Index, 631
- List of abbreviations, 621
- Table of contents, function diagrams, 356

Display

- Alarms, 518
- Faults, 518

Display parameters, 13

Drive data sets, 513

Dynamic index (parameters), 18

E

EDS, (Encoder Data Set), 18

ENCODER, 520

F

Factory setting, 20

Fault

- Acknowledgment, 521, 526
- Cause, 526
- Display, 518
- Explanation of list, 522
- Fault location, 523
- Fault reaction, 519, 526
- General, 518
- How to distinguish a fault from an alarm, 518
- List of all faults, 529
- Message class, 523
- Name, 523

- Number, 522
- Number range, 22, 527
- Remedy, 526
- Fault buffer, 507
 - Configuration, 509
- Fault value, 526
- Faults/alarms configuration, 507
- Faults/alarms triggering (r2129), 507
- Fixed speed setpoints, 433
- Fixed values, 493, 494
- Free interconnection via BICO, 375, 378
- Function block diagrams Dynamic Drive Control
 - Current control, overview (p0096 = 2), 475
 - Current setpoint (p0096 = 2), 482
 - Current/power/torque limits (p0096 = 2), 481
 - Field weakening characteristic, flux setpoint (ASM, p0300 = 1, p0096 = 2), 485
 - Field weakening controller (PMSM, p0300 = 2xx, p0096 = 2), 487
 - Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1, p0096 = 2), 486
 - Id setpoint (PMSM, p0300 = 2xx, p0096 = 2), 484
 - Interface to the power module (ASM, p0300 = 1, p0096 = 2), 488
 - Interface to the power module (PMSM, p0300 = 2xx, p0096 = 2), 489
 - Iq and Id controller (p0096 = 2), 483
 - Moment of inertia estimator (p0096 = 2), 477
 - Speed control and generation of the torque limits, overview (p0096 = 2), 474
 - Speed controller with Kp_n/Tn_n adaptation (p0096 = 2), 478
 - Speed setpoint, precontrol symmetrization, acceleration model (p0096 = 2), 476
 - Torque setpoint (p0096 = 2), 479
 - Vdc_max controller and Vdc_min controller (p0096 = 2), 480
- Function block diagrams, brake control
 - Simple brake control, 424
- Function block diagrams, input/output terminals
 - Analog input 0 (AI 0), 370
 - Analog inputs, digital inputs (DI 11), 371
 - Analog output 0 (AO 0), 372
 - Connection overview, 367
 - Digital inputs, electrically isolated (DI 0 ... DI 5), 368
 - Digital outputs (DO 0 ... DO 1), 369
 - Three-wire control, 374
 - Two-wire control, 373
- Function block diagrams, signals and monitoring functions
 - Monitoring functions 1, 505
 - Monitoring functions 2, 506
 - Speed messages 1, 499
 - Speed messages 2, 500
 - Thermal monitoring, motor, 502
 - Thermal monitoring, power unit, 504
 - Thermal motor models, 503
 - Torque signals, motor blocked/stalled, 501
- Function diagram (parameters), 19
- Function diagrams, CANopen
 - Control word CANopen, 397
 - Receive telegram, free PDO mapping (p8744 = 2), 393
 - Receive telegram, Predefined Connection Set (p8744 = 1), 394
 - Send telegram, free PDO mapping (p8744 = 2), 395
 - Send telegram, Predefined Connection Set (p8744 = 1), 396
 - Status word, CANopen, 398
- Function diagrams, data sets
 - Command Data Sets (CDS), 514
 - Drive Data Sets (DDS), 515
- Function diagrams, diagnostics
 - Alarm buffer, 510
 - Fault buffer, 509
 - Faults/alarms configuration, 512
 - Faults/alarms trigger word (r2129), 511
 - Overview, 508
- Function diagrams, fieldbus interface
 - Configuration, addresses and diagnostics, 400
 - Receive telegram, free interconnection via BICO (p0922 = 999), 403
 - Send telegram, free interconnection via BICO (p0922 = 999), 404
 - STW1 control word interconnection, 401
 - ZSW1 status word interconnection, 402
- Function diagrams, general information
 - Explanation of the symbols (part 1), 362
 - Explanation of the symbols (part 2), 363
 - Explanation of the symbols (part 3), 364
 - Handling BICO technology, 365
- Function diagrams, internal control/status words
 - Control word 1 (r0054), 411
 - Control word 2 (r0055), 412
 - Control word, faults/alarms, 419
 - Control word, sequence control, 406
 - Control word, setpoint channel, 408
 - Sequence control - Missing enable signals, 422
 - Sequence control - Sequencer, 421
 - Status word monitoring functions 1, 416
 - Status word monitoring functions 2, 417
 - Status word monitoring functions 3, 418
 - Status word 1 (r0052), 409
 - Status word 2 (r0053), 410
 - Status word, closed-loop control, 414
 - Status word, closed-loop current control, 415
 - Status word, faults/alarms 1 and 2, 420
 - Status word, sequence control, 407
 - Status word, speed controller, 413

- Function diagrams, PROFIdrive
 - Overview, 379
 - PROFIBUS (PB) / PROFINET (PN), addresses and diagnostics, 380
 - PZD receive signals interconnection, 382
 - PZD send signals interconnection, 386
 - Receive telegram, free interconnection via BICO (p0922 = 999), 390
 - Send telegram, free interconnection via BICO (p0922 = 999), 391
 - STW1 control word interconnection (p2038 = 0), 384
 - STW1 control word interconnection (p2038 = 2), 383
 - STW3 control word interconnection, 385
 - Telegrams and process data (PZD), 381
 - ZSW1 status word interconnection (p2038 = 0), 388
 - ZSW1 status word interconnection (p2038 = 2), 387
 - ZSW3 status word interconnection, 389
- Function diagrams, PROFInergy
 - Control commands and interrogation commands, 376
 - States, 377
- Function diagrams, Safety Integrated Basic Functions
 - F-DI, Fail-safe Digital Input, 430
 - Monitoring functions and faults/alarms, 427
 - Parameter manager, 426
 - Status words, 428
 - STO, Safe Torque Off, 429
- Function diagrams, Safety Integrated PROFIsafe
 - Standard telegrams, 432
- Function diagrams, setpoint channel
 - Direction limitation and direction reversal, 439
 - Fixed speed setpoints, binary selection (p1016 = 2), 435
 - Fixed speed setpoints, direct selection (p1016 = 1), 436
 - Main/supplementary setpoint, setpointscaling, jogging, 438
 - Motorized potentiometer, 437
 - Overview, 434
 - Ramp-function generator (extended), 441
 - Skip frequency bands and speedlimitations, 440
- Function diagrams, signals and monitoring functions
 - Overview, 498
- Function diagrams, Standard Drive Control
 - Interface to the power module (ASM, p0300 = 1, p0096 = 1), 472
 - Resonance damping and slip compensation (U/f) (p0096 = 1), 470
 - U/f characteristic and voltage boost (p0096 = 1), 469
 - U/f control, overview (p0096 = 1), 468
 - Vdc_max controller (p0096 = 1), 471
- Function diagrams, technology controller
 - Closed-loop control, 496
 - Fixed value selection binary (p2216 = 2), 493
 - Fixed value selection direct (p2216 = 1), 494
 - Motorized potentiometer, 495
- Function diagrams, technology functions
 - DC brake (p0300 = 1), 491
- Function diagrams, vector control
 - Application classes (p0096), overview, 443
 - Current control, overview, 457
 - Current setpoint filter, 458
 - Current/power/torque limits, 456
 - Display signals, 466
 - Field weakening characteristic, flux setpoint (ASM, p0300 = 1), 461
 - Field weakening controller (PMSM, p0300 = 2), 463
 - Field weakening controller, flux controller, Id setpoint (ASM, p0300 = 1), 462
 - Id setpoint (PMSM, p0300 = 2), 460
 - Interface to the Power Module (ASM, p0300 = 1), 464
 - Interface to the Power Module (PMSM, p0300 = 2), 465
 - Iq and Id controllers, 459
 - Moment of inertia estimator, 446
 - Resonance damping and slip compensation (U/f), 452
 - Speed control and generation of the torque limits, overview, 444
 - Speed control configuration, 454
 - Speed controller, 447
 - Speed setpoint, accelerationmodel, 445
 - Torque setpoint, 448
 - U/f characteristic and voltage boost, 451
 - U/f control, overview, 450
 - Upper/lower torque limit, 455
 - Vdc_max controller (U/f), 453
 - Vdc_max controller and Vdc_min controller, 449
- Fxxxx, 522
- G**
- General
 - About parameters, 12
 - on faults and alarms, 518
 - on function diagrams, 361
- I**
- IASC, 520
- Index
 - Parameters, 13
- Index (parameters), 20
- Industrial security, 9
- Input/output terminals, 366
 - Analog inputs, 366
 - Digital inputs, 366
- Internal control words, 405
- Internal control/status words, 405

J

Jogging, 433, 438

L

Linked parameters, 13

List

- Abbreviations, 621
- ASCII table, 618
- Binector inputs (BI parameters), 344
- Binector outputs (BO parameters), 345
- Command data sets, 336
- Connector inputs (CI parameters), 345
- Connector outputs (CO parameters), 346
- Connector/binector outputs (CO/BO parameters), 349
- Drive data sets, 337
- Encoder data sets, 343
- Faults and alarms, 529
- Message ranges, 22, 527
- Motor data sets, 341
- Parameters for quick commissioning, 352
- Parameters for write protection and know-how protection, 350
- Parameters, all, 24
- Power unit data sets, 343

List of abbreviations, 621

Load monitoring, 497

M

Manufacturer-specific telegrams, 381

MDS, Motor Data Set, 18

Message buffer, 507

Message class, 523

Monitoring functions, 497

Motorized potentiometer, 433, 495

N

Name

- Alarm, 523
- Fault, 523

Number

- Alarm, 522
- Fault, 522
- Parameters, 13

Number range

- Alarms, 22, 527
- Faults, 22, 527

O

OFF1, 519

OFF1_DELAYED, 519

OFF2, 519

OFF3, 520

P

Parameter

Scaling, 17

Parameters

- Access level, 15
- Bit field, 21
- Calculated, 15
- Can be changed, 17
- Command data sets, 336
- Data type, 16
- Dependency, 21
- Description, 20
- Drive data sets, 337
- Dynamic index, 18
- Encoder data sets, 343
- Full name, 14
- Function diagram, 19
- Index, 13, 20
- Linked parameters, 13
- List for quick commissioning, 352
- List of all parameters, 24
- List of the binector inputs, 344
- List of the binector outputs, 345
- List of the connector inputs, 345
- List of the connector outputs, 346
- List of the connector/binector outputs, 349
- Motor data sets, 341
- Number, 13
- Parameter values, 20
- Power unit data sets, 343
- Recommendation, 20
- Safety guidelines, 21
- Short name, 14
- Unit group, 18
- Unit selection, 18
- Values, 20

Password for access level 4, 15

PDS, (Power unit Data Set), 18

Process data, 375, 378

PROFIBUS, 375, 378

PROFIdrive, 375, 378

PROFINET, 375, 378

pxxxx, 13

Q

Quick commissioning (parameters), 352

R

Ramp-function generator, 433

Reaction to faults, 519

Resetting faults, 526

rxxxx, 13

S

- Safety instructions
 - Fundamental, 7
 - General, 8
 - Industrial security, 9
- Safety instructions (parameter), 21
- Safety Integrated
 - Basic Functions, 425, 431
 - Extended Functions, 425, 431
- Scaling, 17
- Setpoint channel, 433
- Signals, 497
- Skip frequency bands, 433
- Speed control
 - Vector, 442
 - Vector (Dynamic Drive Control), 473
 - Vector (Standard Drive Control), 467
- Speed messages, 497
- Standard telegrams, 381
- Status words, 375, 378
 - Internal, 405
- STOP2, 520

T

- Technology controller, 492
- Technology functions, 490
- Telegrams, 375, 378
- Temperature evaluation, 366
- Thermal monitoring, 497
- Torque signals, 497

U

- Unit (parameter), 18

V

- Values (parameter), 20
- Vector control
 - Table of contents, 442
- Vector control (Dynamic Drive Control)
 - Table of contents, 473
- Vector control (Standard Drive Control)
 - Table of contents, 467
- Version
 - List of all parameters, 24
 - List of faults and alarms, 529

Siemens AG
Digital Factory
Motion Control
P.O. Box 3180
91050 ERLANGEN
GERMANY

Subject to change
© Siemens AG 2014 - 2015

Find out more on
SINAMICS G120C
by scanning the
QR code.



www.siemens.com/sinamics-g120c